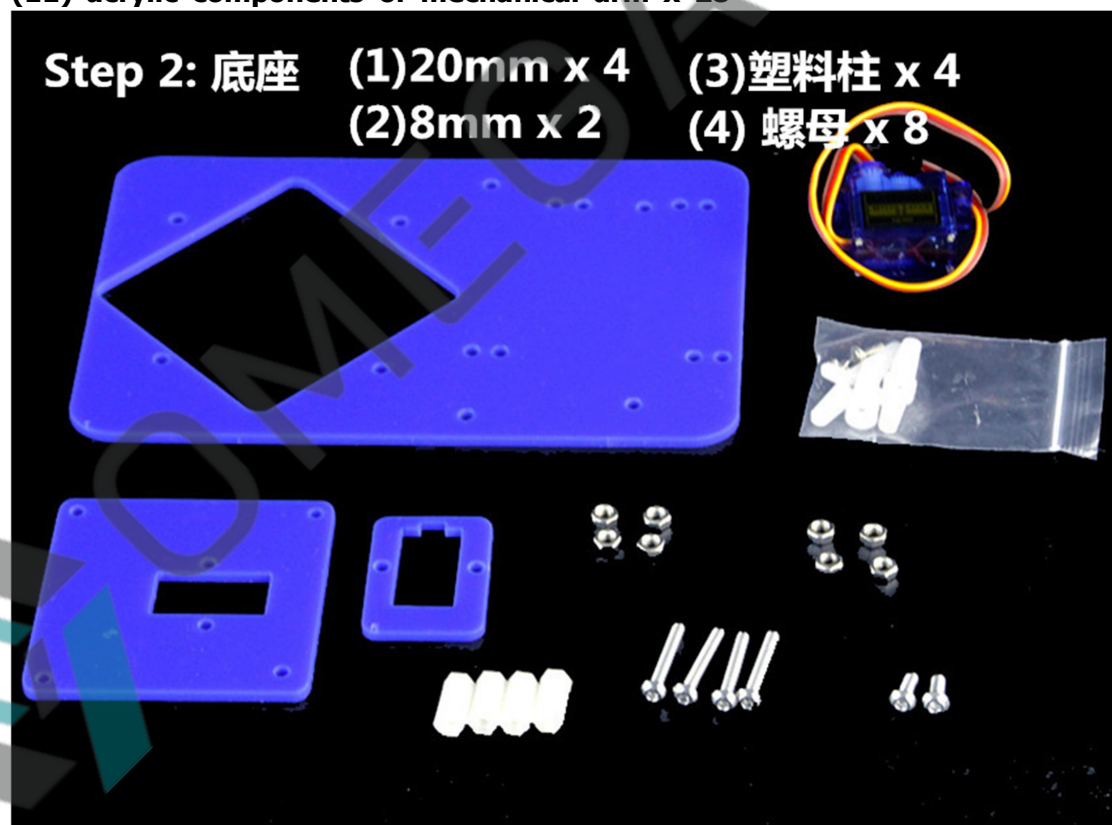


Assembly as a diagram

Clear Suites

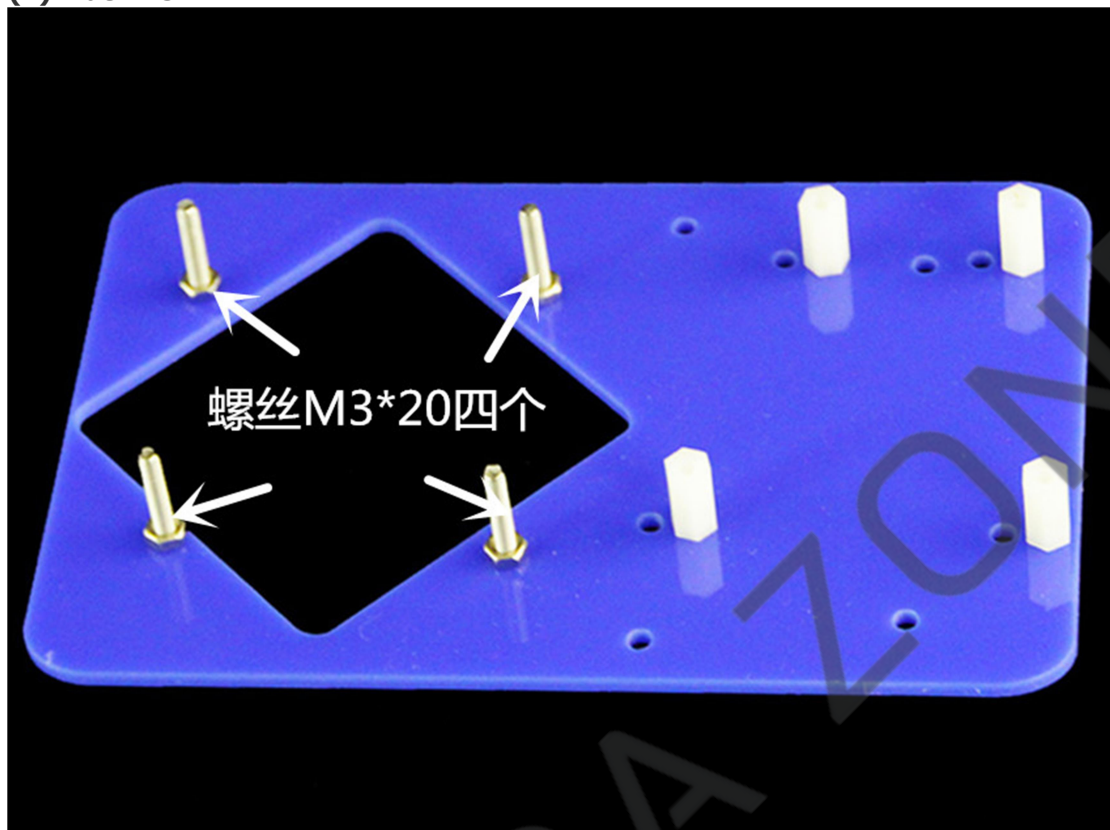
- (1) 20mm x 4
- (2) 12mm x 6
- (3) 8mm x 20
- (4) 6mm x 17
- (5) plastic column x 7
- (6) nut x 12
- (7) motor x 4
- (8) Arduino main board x 1
- (9) remote sensing expansion board x 1
- (10) silica gel gasket x 1
- (11) acrylic components of mechanical arm x 28



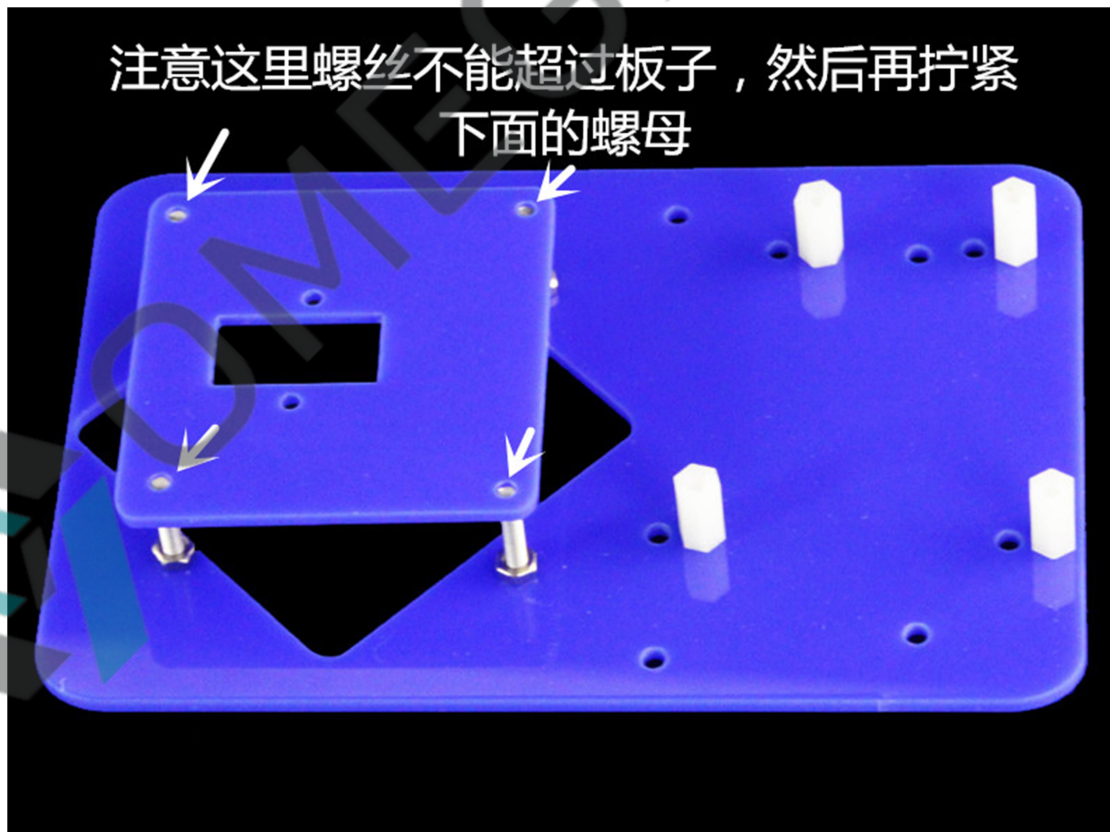
step 2 : base

- (1)20mm x 4
- (2)9mm x 2
- (3) plastic column x 4

(4) nut x 8



Screw M3*20 four



Be careful not to exceed the board, then tighten the nut below.

Step 3: 第一颗马达

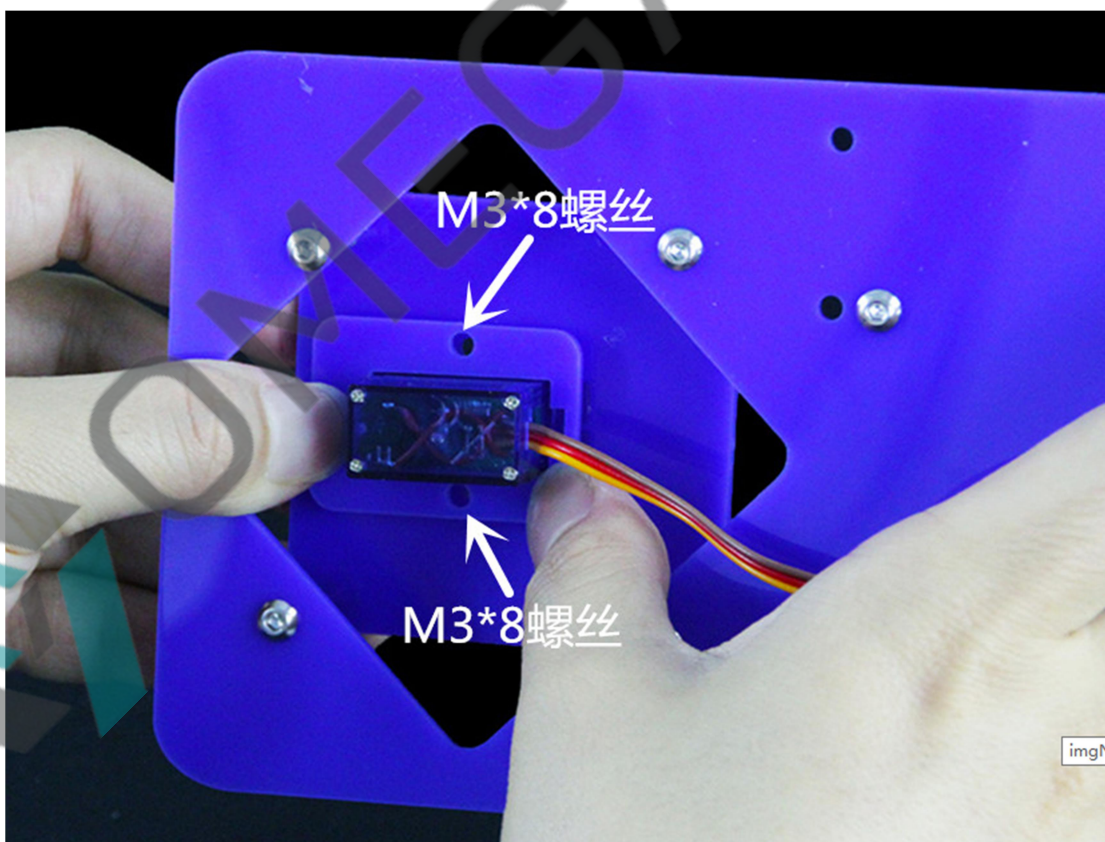
注意：马达尺寸和亚克力很密合，所以施力要慢
以免弄破亚克力，之后装马达时也要留意



step 3 : The first motor

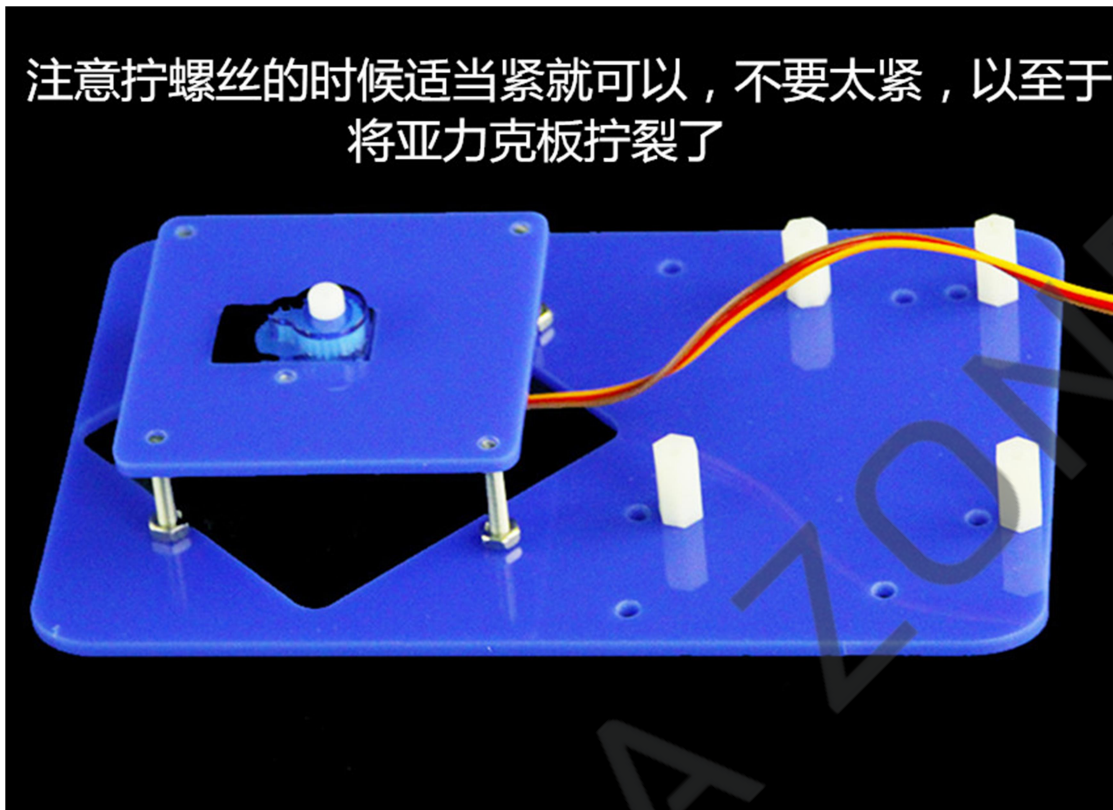
NOTE : The size of the motor is very close to that of the acrylic, so the force must be slow, so as not to break the acrylic.

NOTE : The gap is the location of the line.



M3*8 screw (double)

注意拧螺丝的时候适当紧就可以，不要太紧，以至于将亚克力板拧裂了

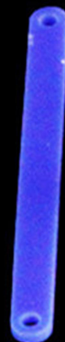
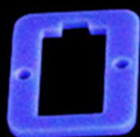


Be careful not to tighten the screws too tightly. It will crack the acrylic board too tightly.

Step 4: 左臂

(1) 12mm x 2

(2) 8mm x 3



(3) 螺母 x 2

(4) 舵机螺丝一长一短

Step 4 : Left arm

(1) 12mm x 2

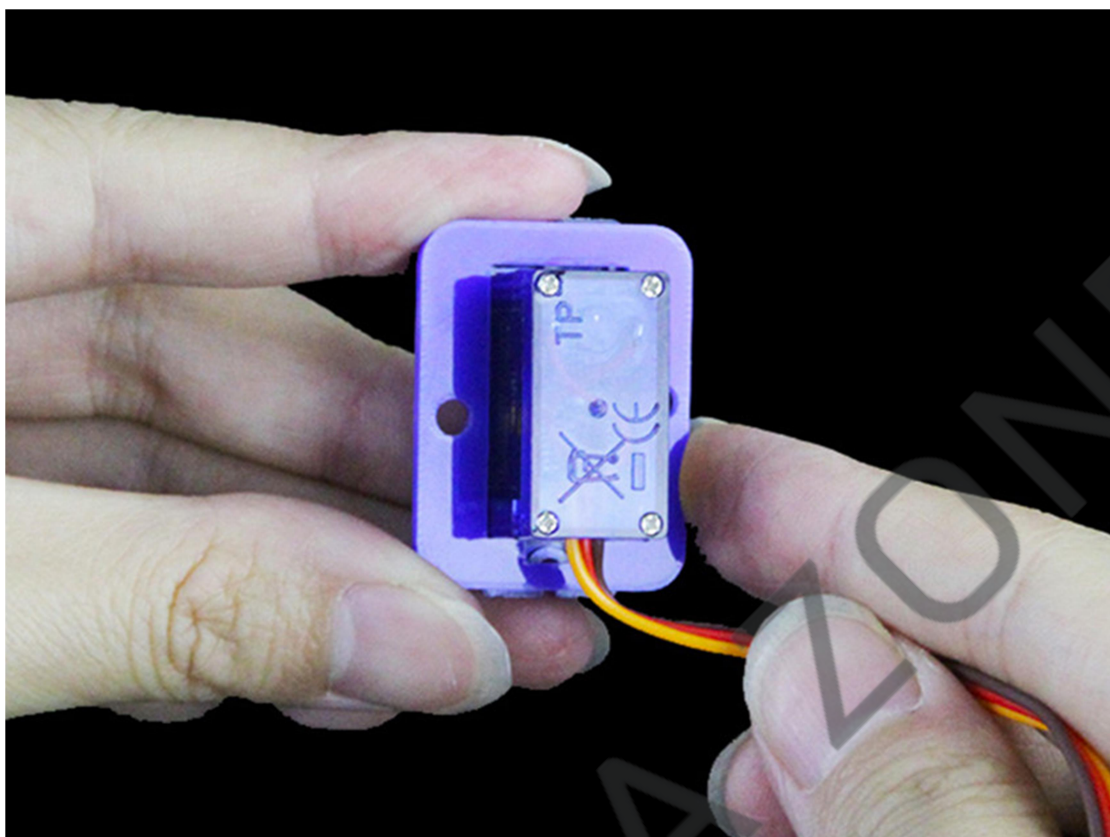
(2) 8mm x 3

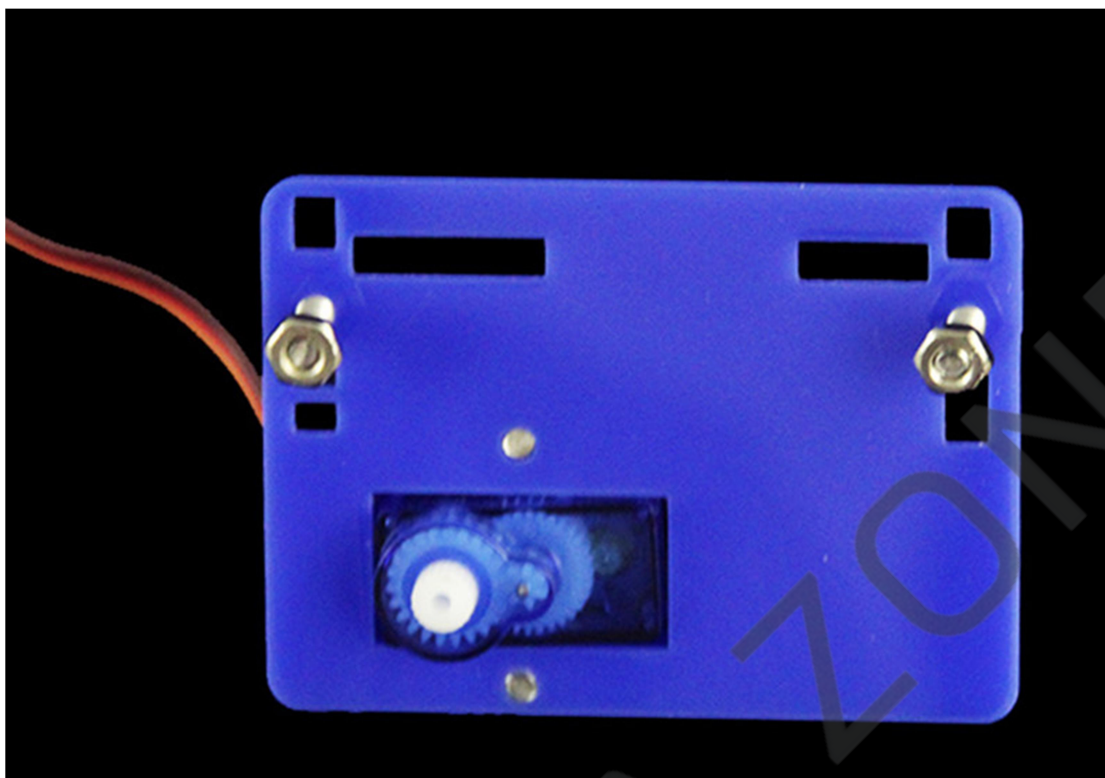
(3) nut x 2

(4) the screw of the steering gear is one length and one short

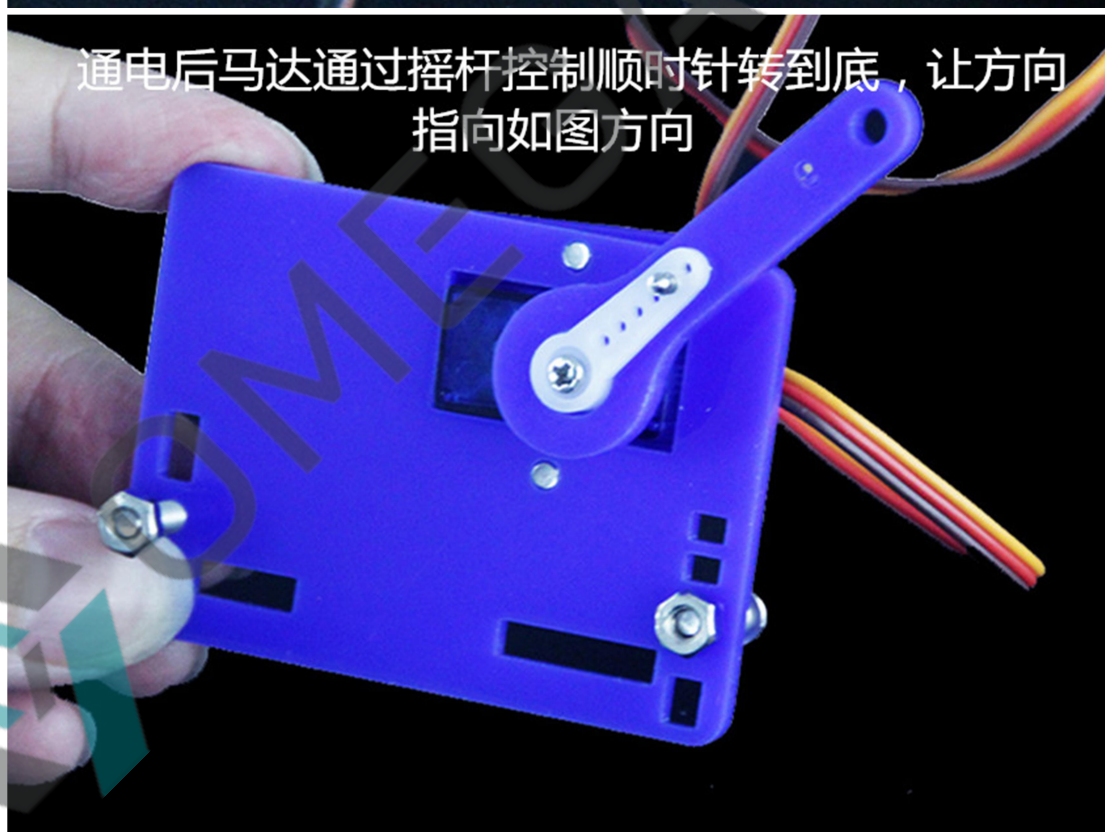


OMEGA ZONE



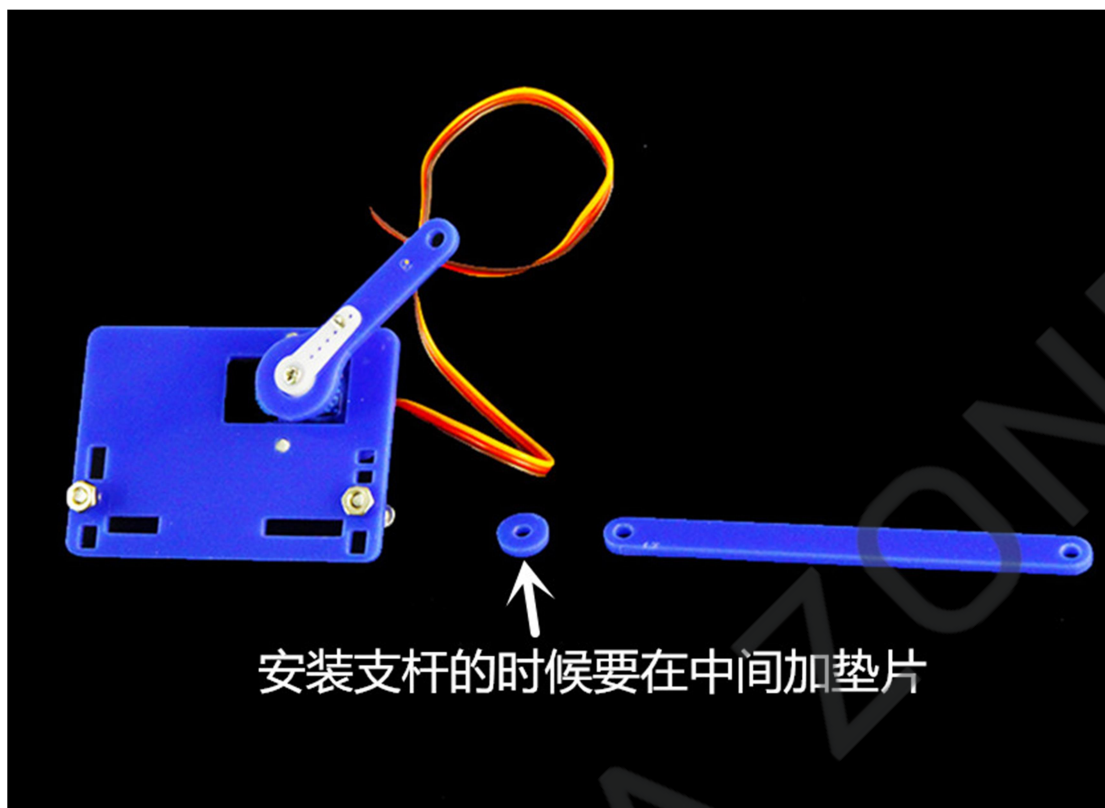


Screw M3*8



通电后马达通过摇杆控制顺时针转到底，让方向
指向如图方向

After power on, the motor is controlled by a rocker to turn clockwise to the end, so that the direction is consistent with the picture.

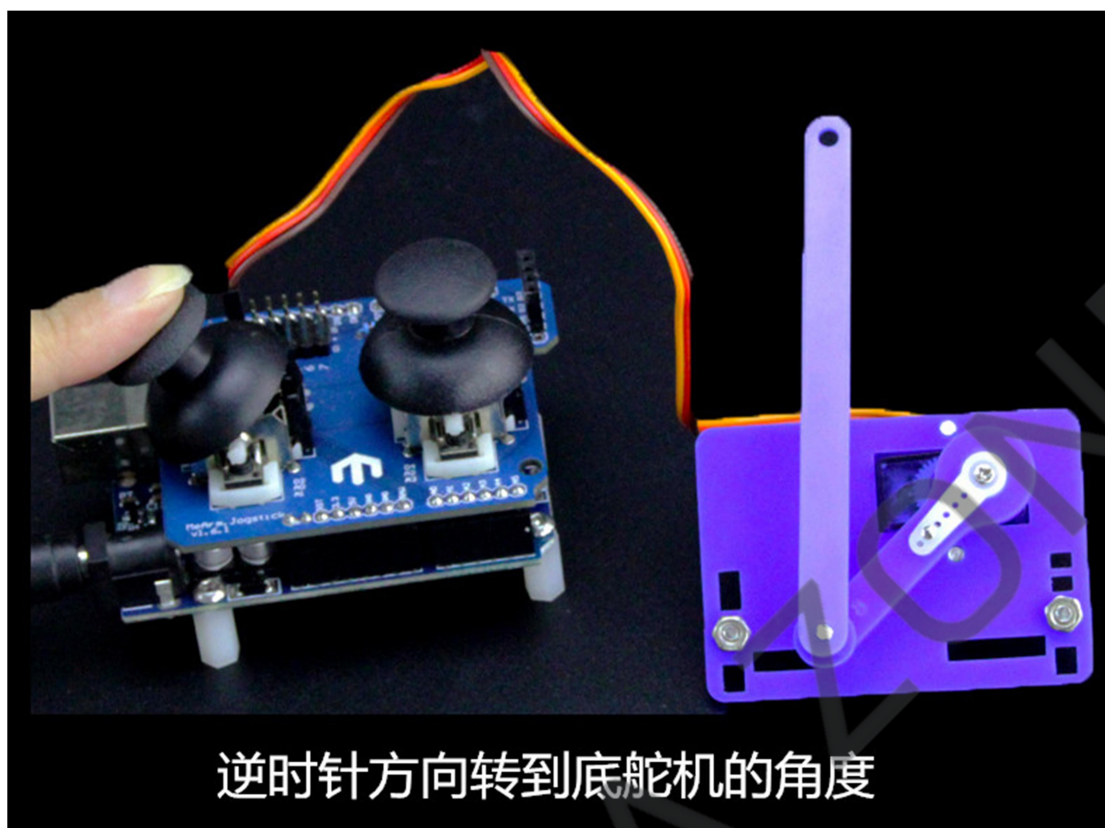


When installing a stick, add a gasket in the middle

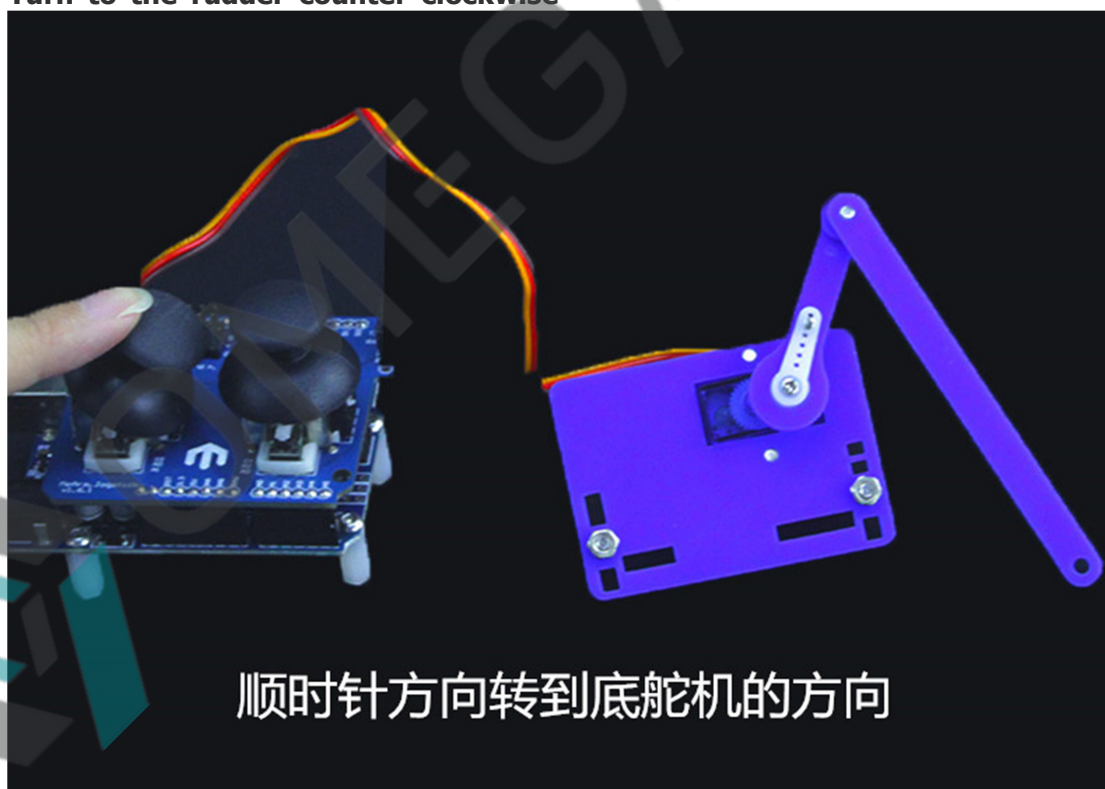


Yellow to the outside

Power supply 5V 2A charger



Turn to the rudder counter clockwise



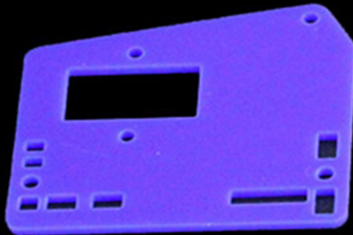
Clockwise steering wheel

Step 5: 右臂

12mm x 3

8mm x 2

6mm x 1

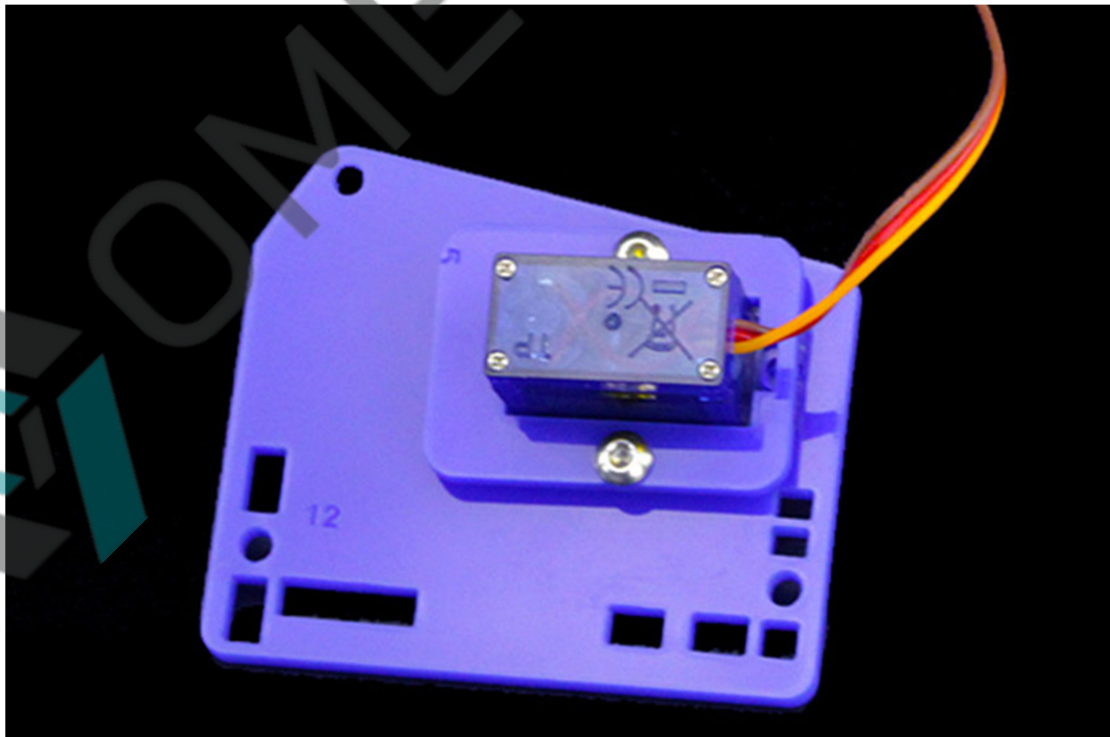


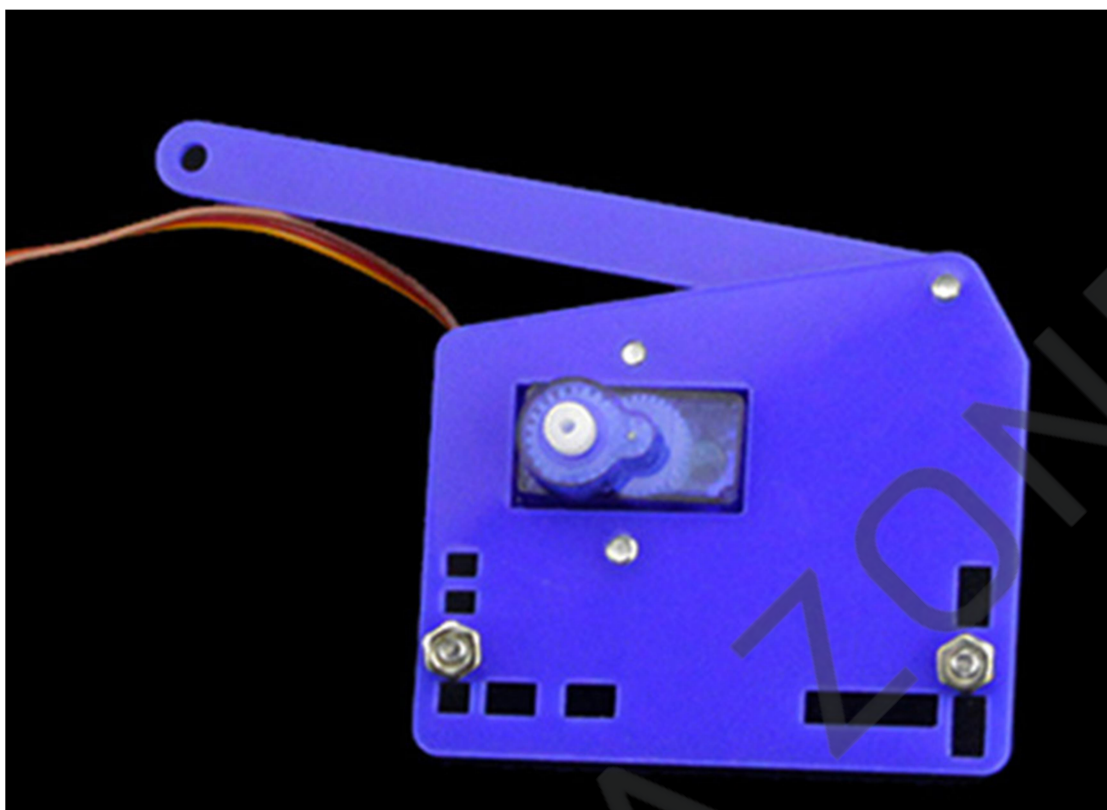
Step 5 : Right arm

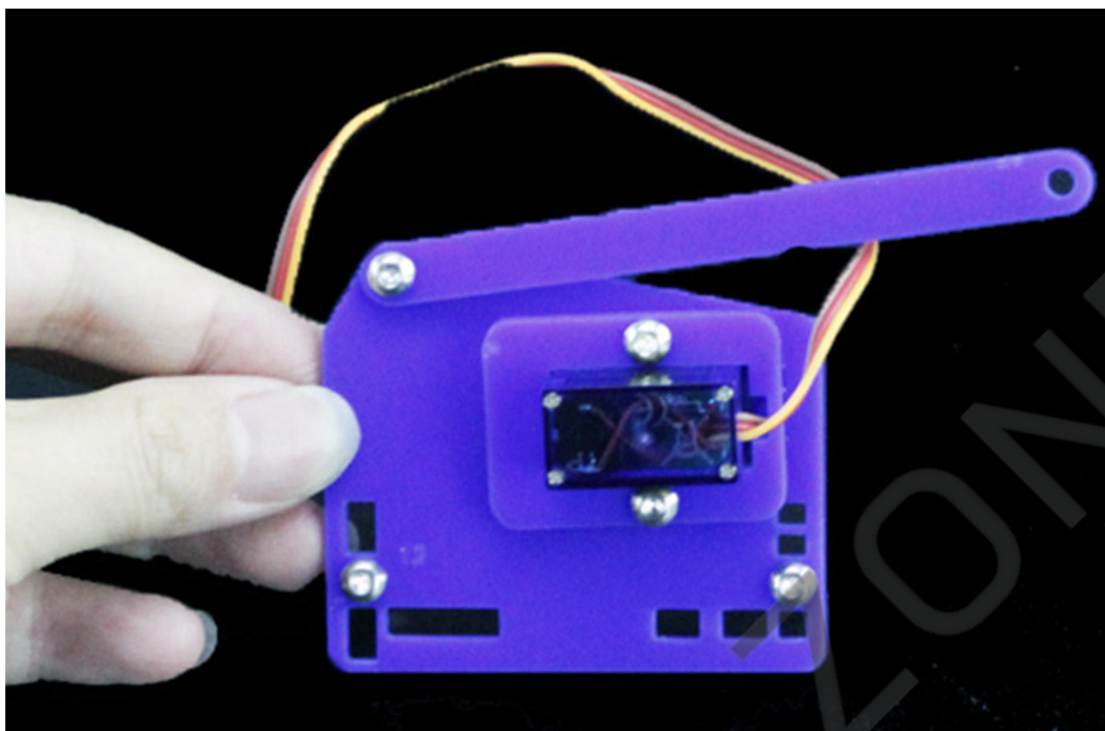
12mm X 3

8mm x 2

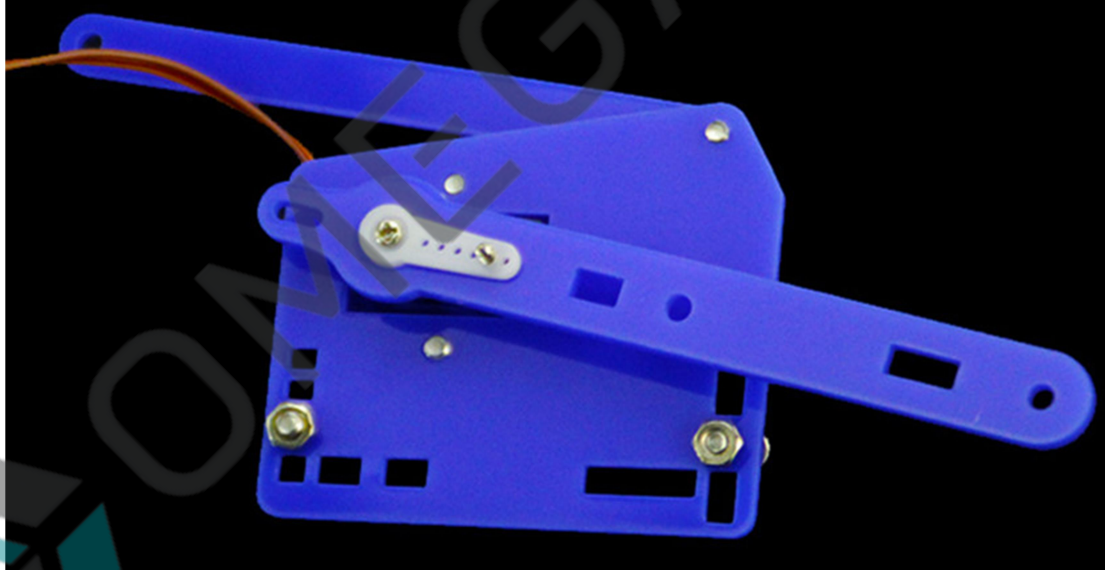
6mm x 1



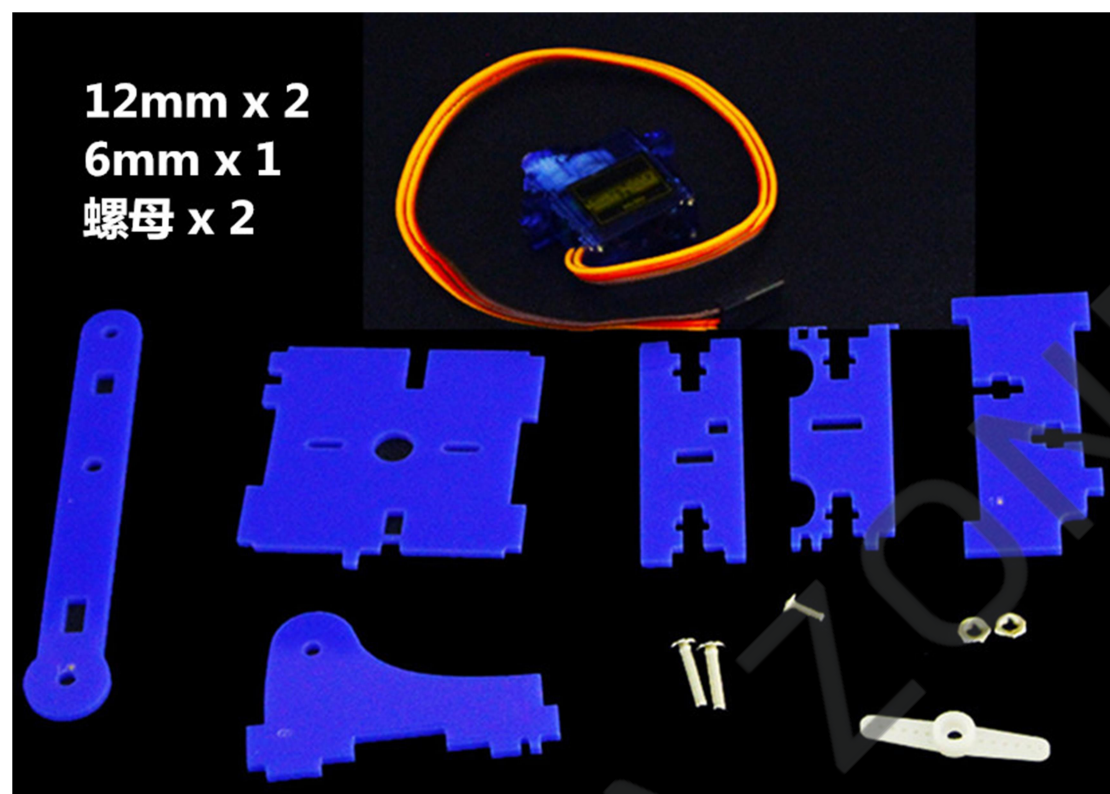




通电后舵机线插电路板顺时针旋转至如下图方向

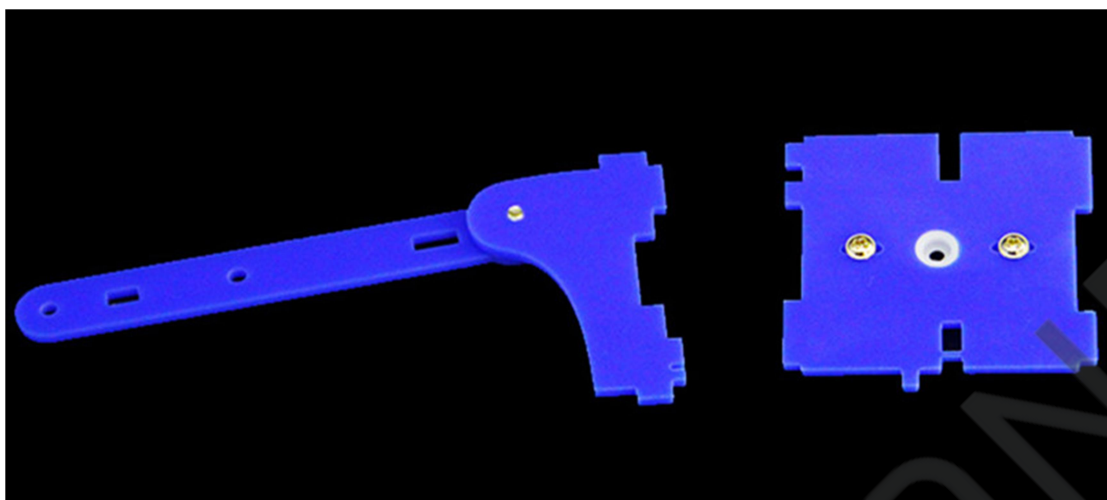


After power on, the steering wheel is inserted into the circuit board, turning clockwise to the same direction as the picture.



12mm x 2
6mm x 1
螺母 x 2

12mm x 2
6mm x 1
Nut x2

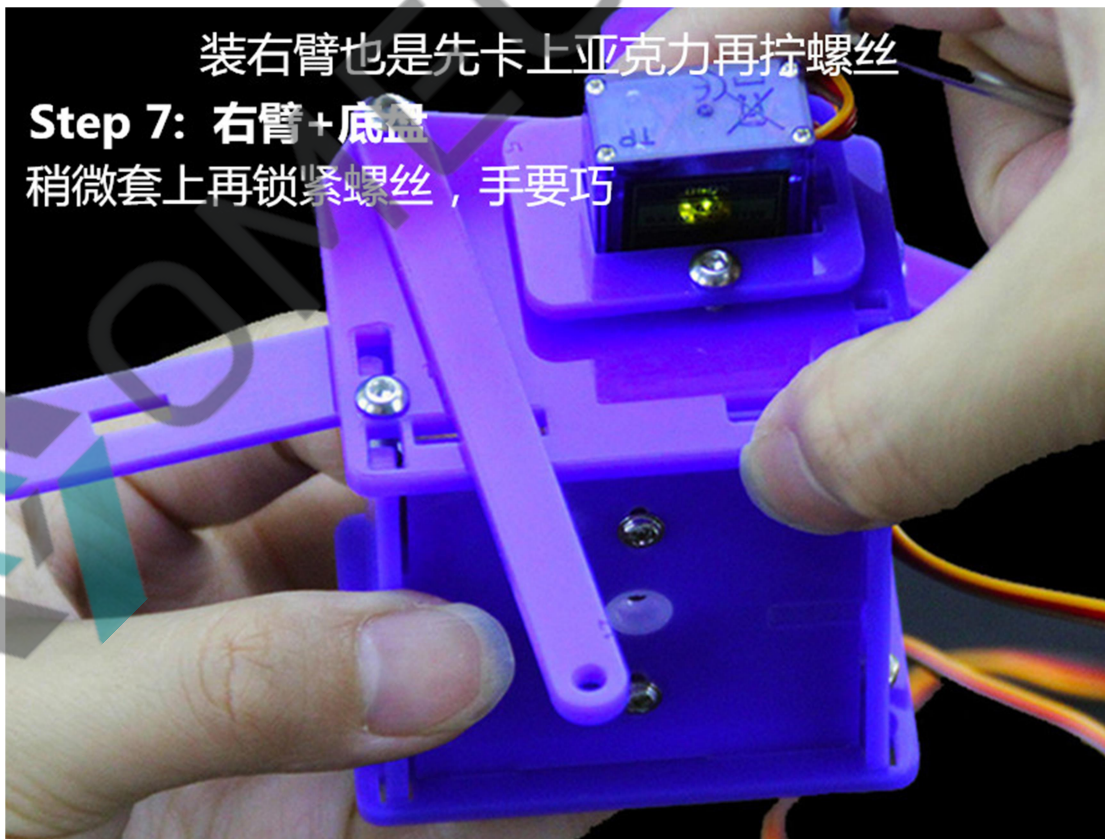


先卡上外壳，再装螺丝拧紧的时候不要太紧



First put on the shell and then install the screws. When tightening, do not tighten too tightly.

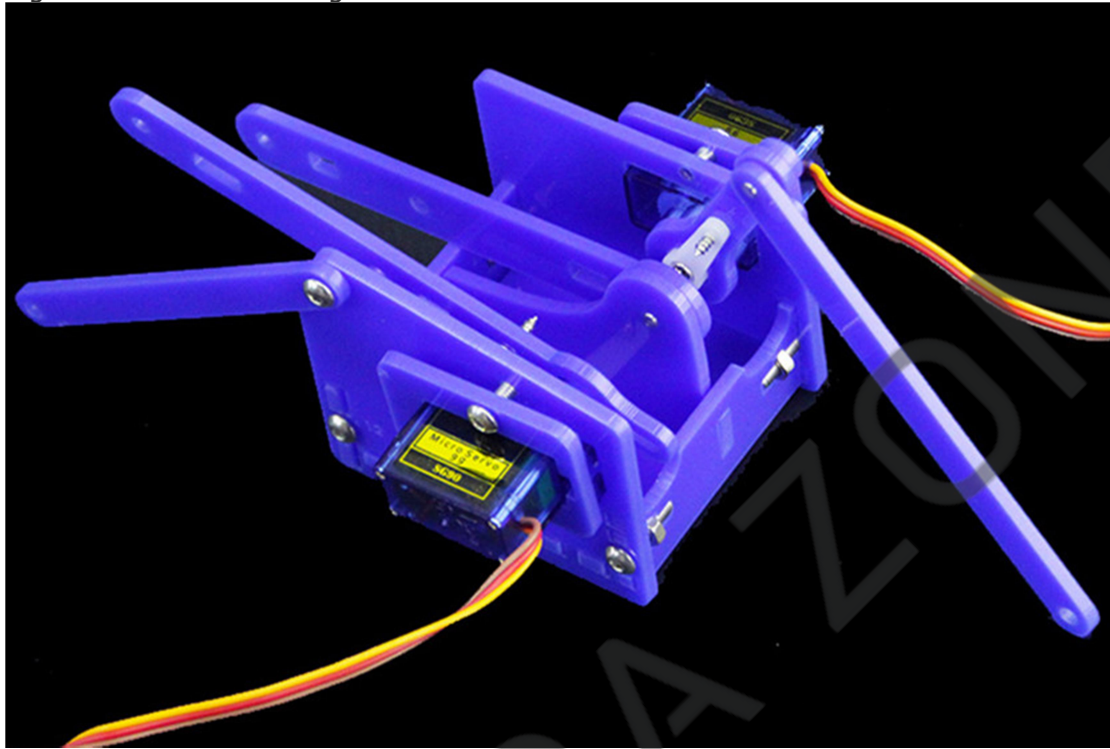
装右臂也是先卡上亚克力再拧螺丝
Step 7: 右臂+底盘
稍微套上再锁紧螺丝，手要巧



The right arm is put on the shell first and then tightened.

Step 7: right arm + chassis

Tighten the screw and tighten the screw

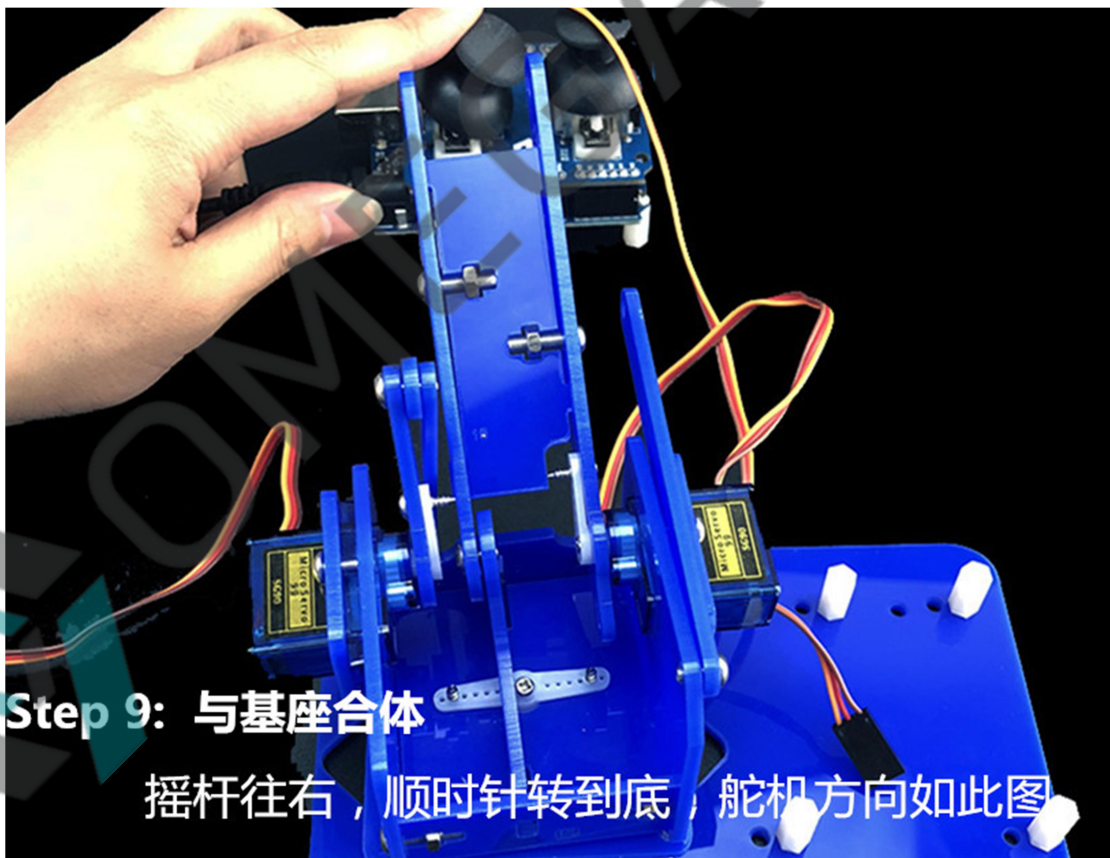
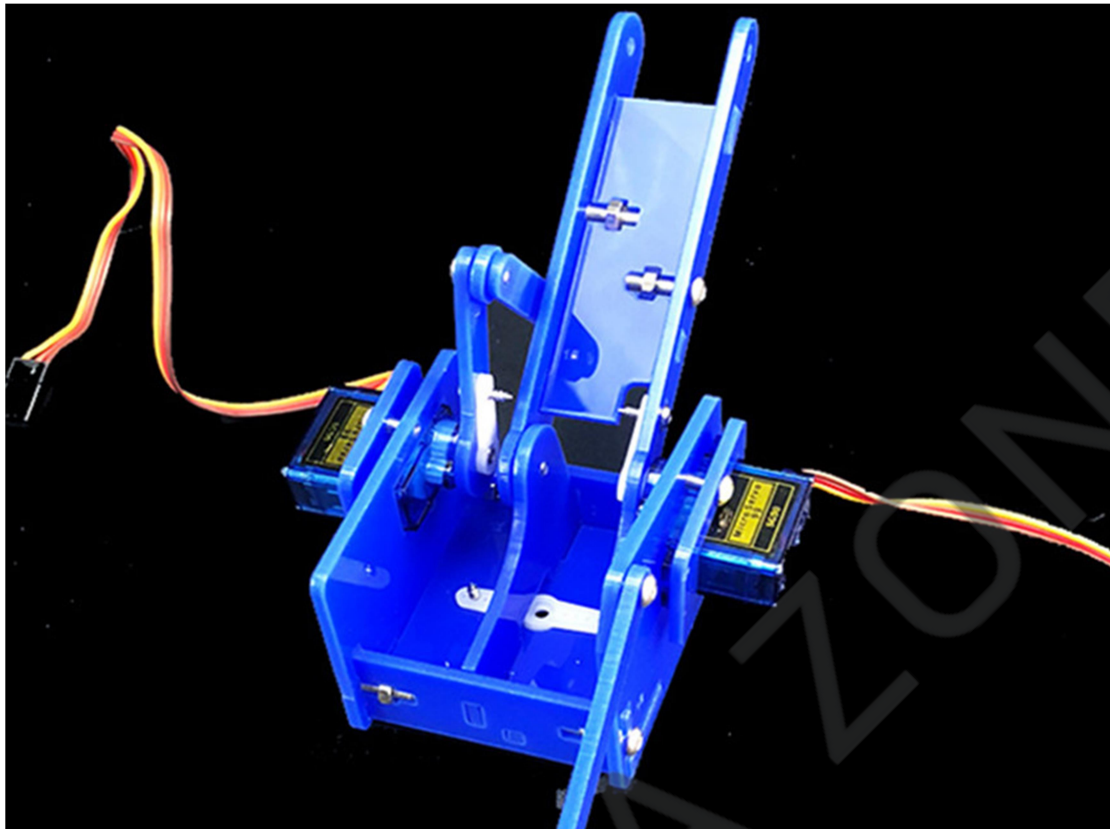


Step 8: 中间支架 先上螺母再装螺丝



Step 8: intermediate bracket

Screw the nut first

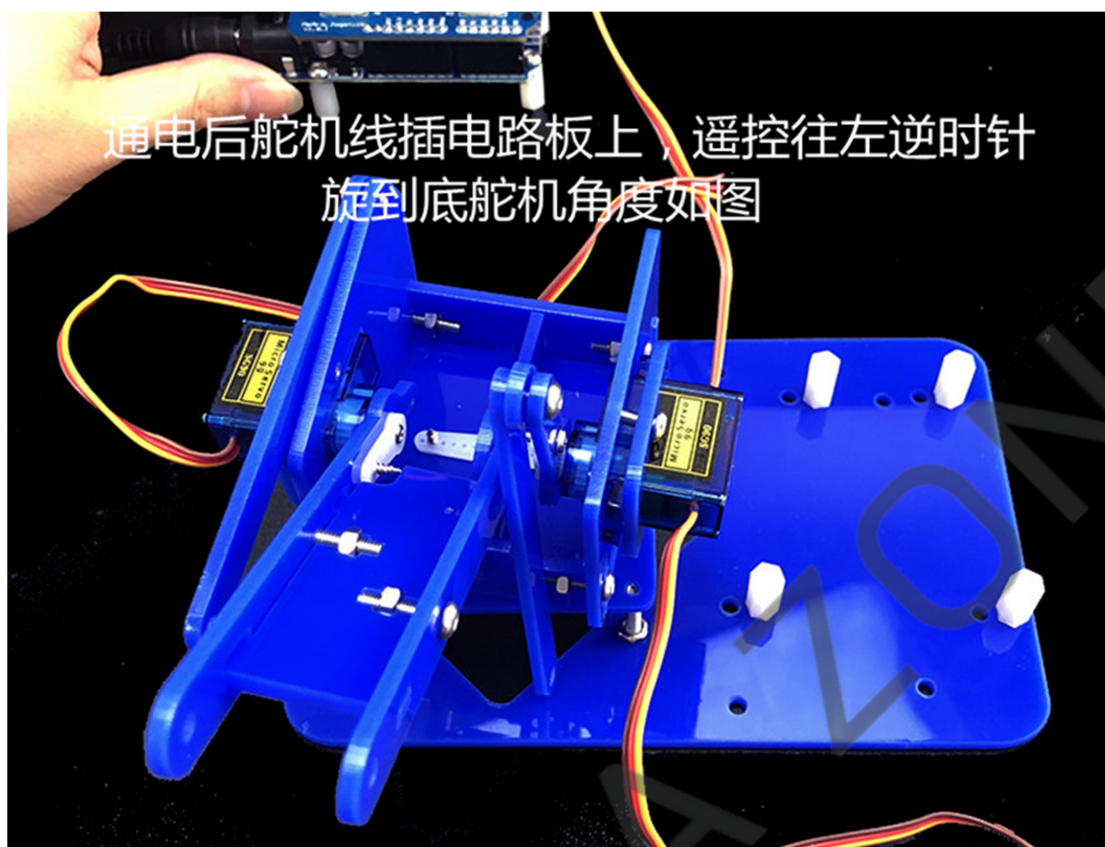


Step 9: 与基座合体

摇杆往右，顺时针转到底，舵机方向如此图

Step 9: complex with the base

The rocker moves to the right, clockwise to the end, and the steering gear is aligned with the picture

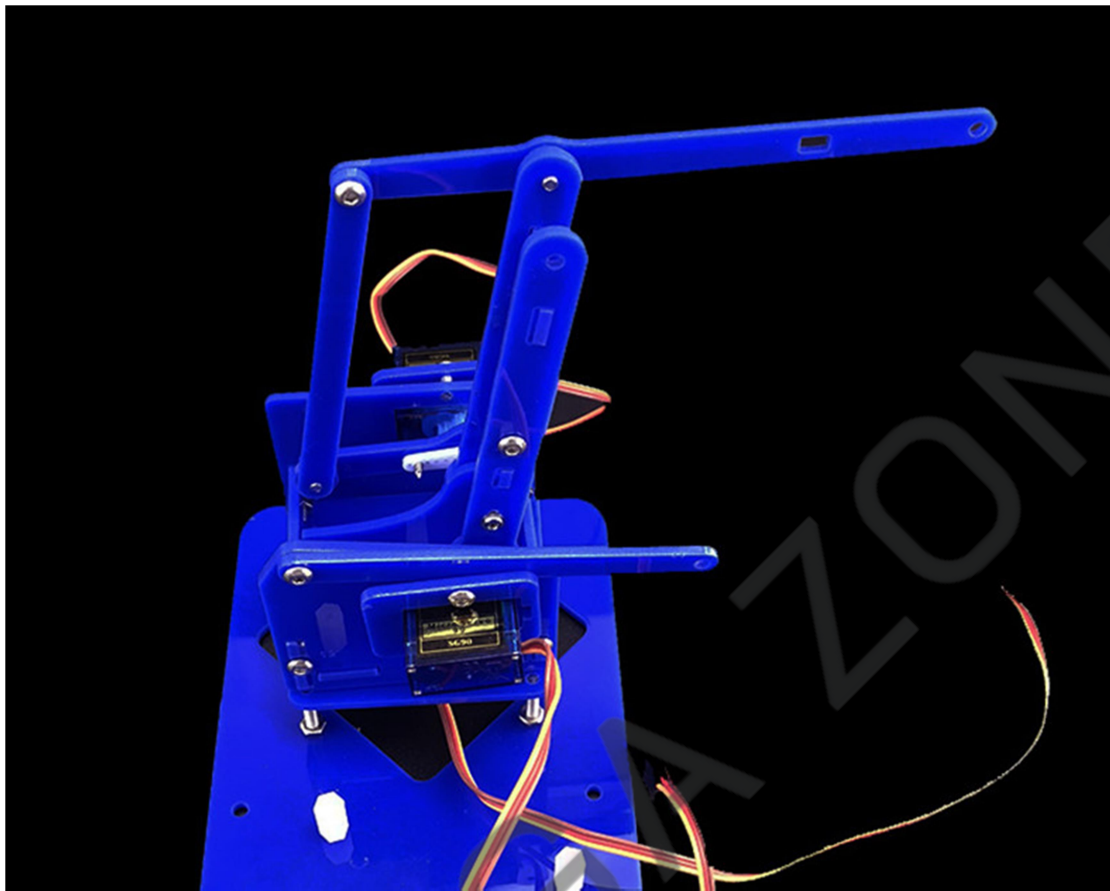


After power on, the rudder line is plugged into the circuit board, and the remote control counter-clockwise turns to the end of the steering gear angle and the picture is consistent.



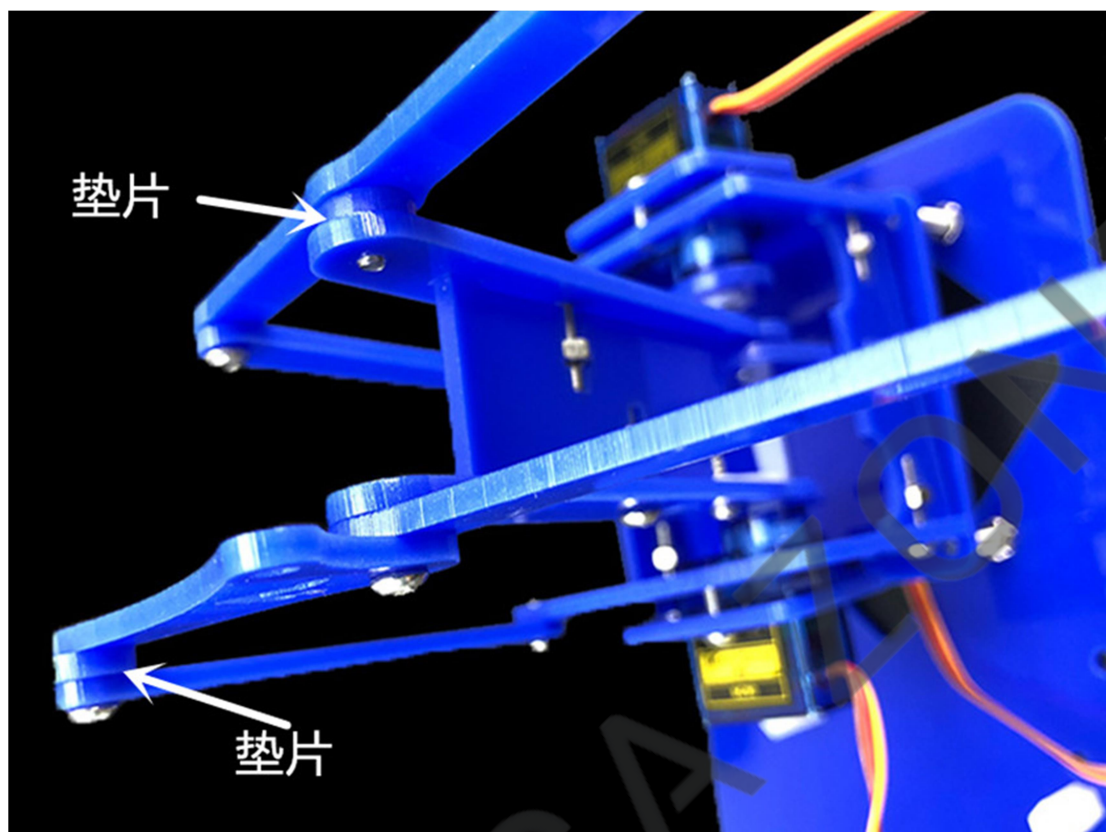
step 10 : Branched rod

Two screw M3*6

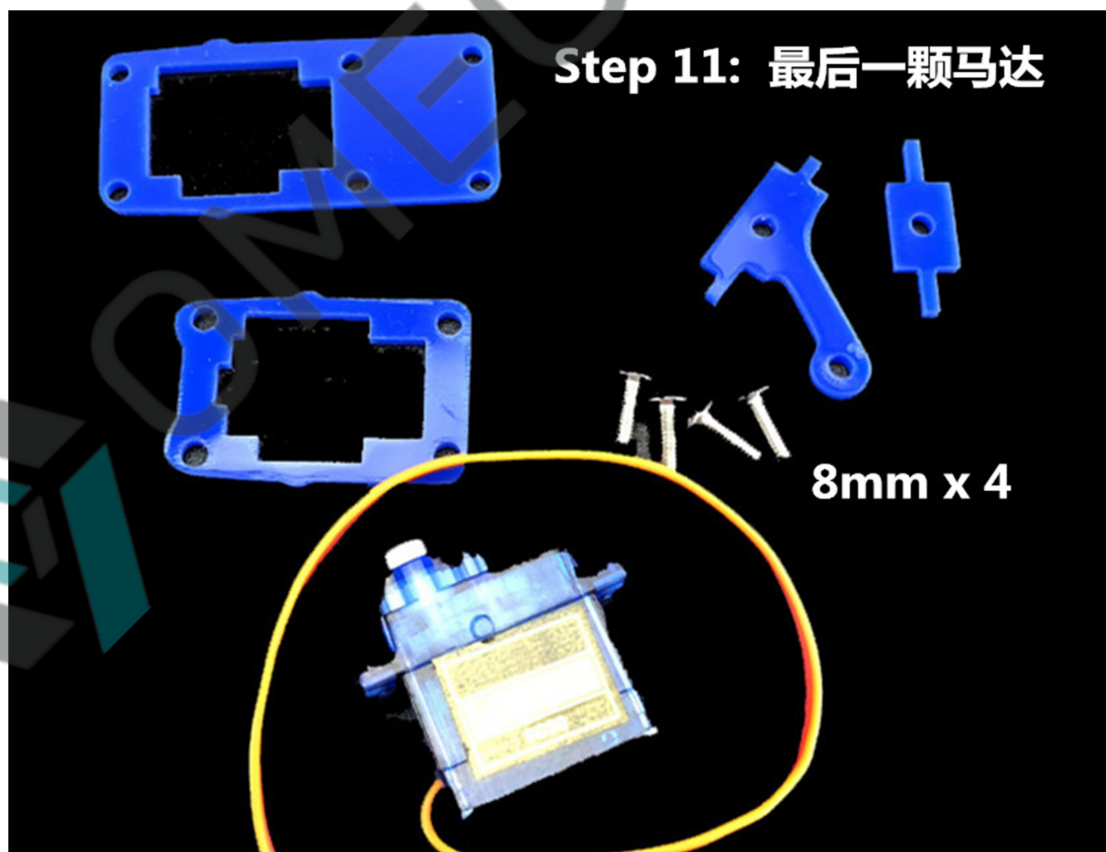


M3*6

M3*8



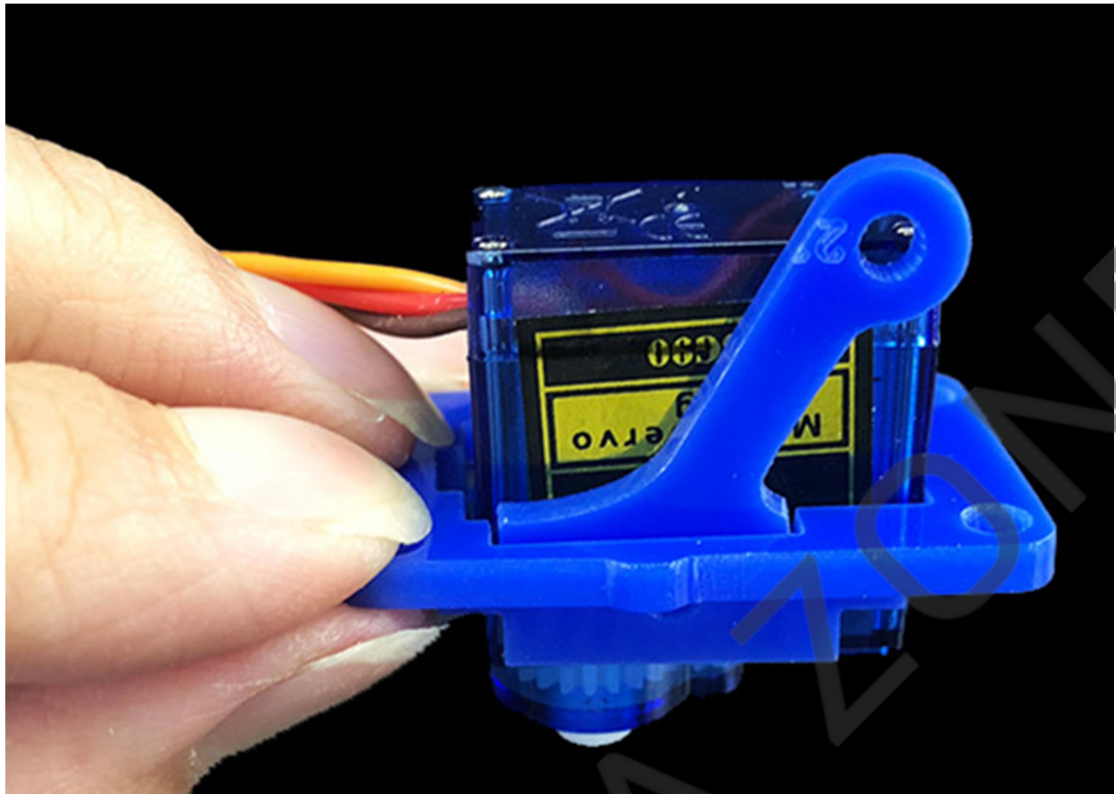
Shim(double)



step 11 : The last motor
8mm x4



The side of the mouth is large and the side is small.

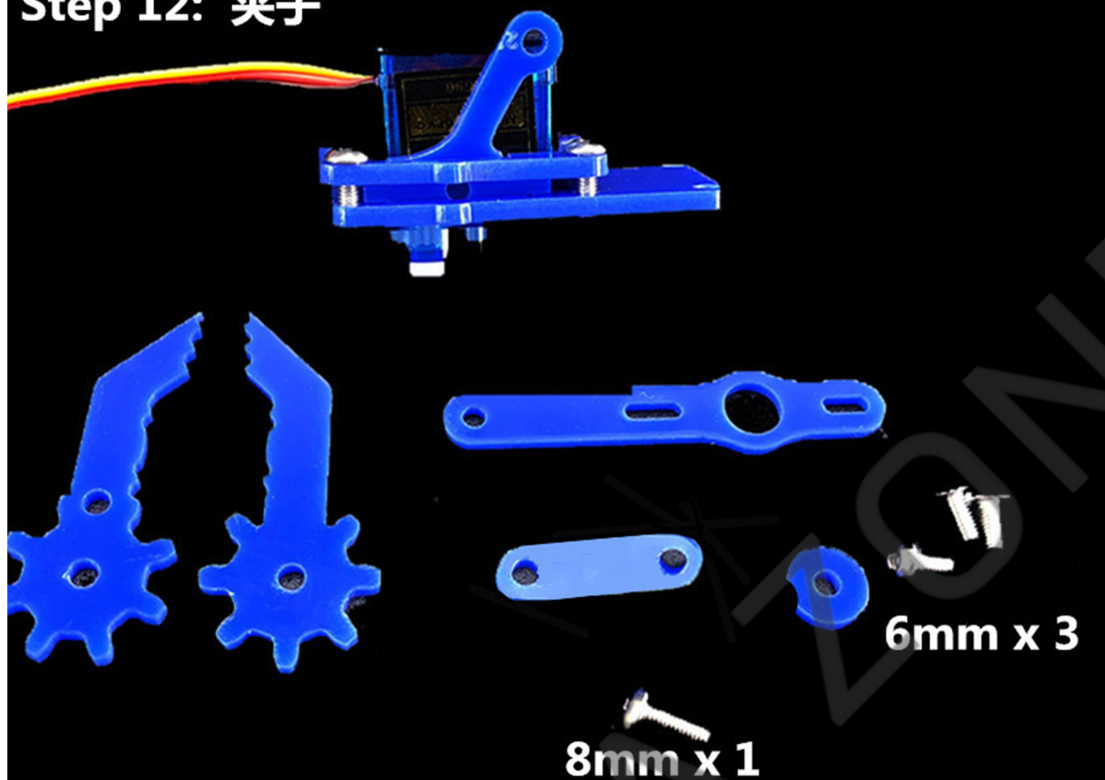




4 M3*8 screws fixed



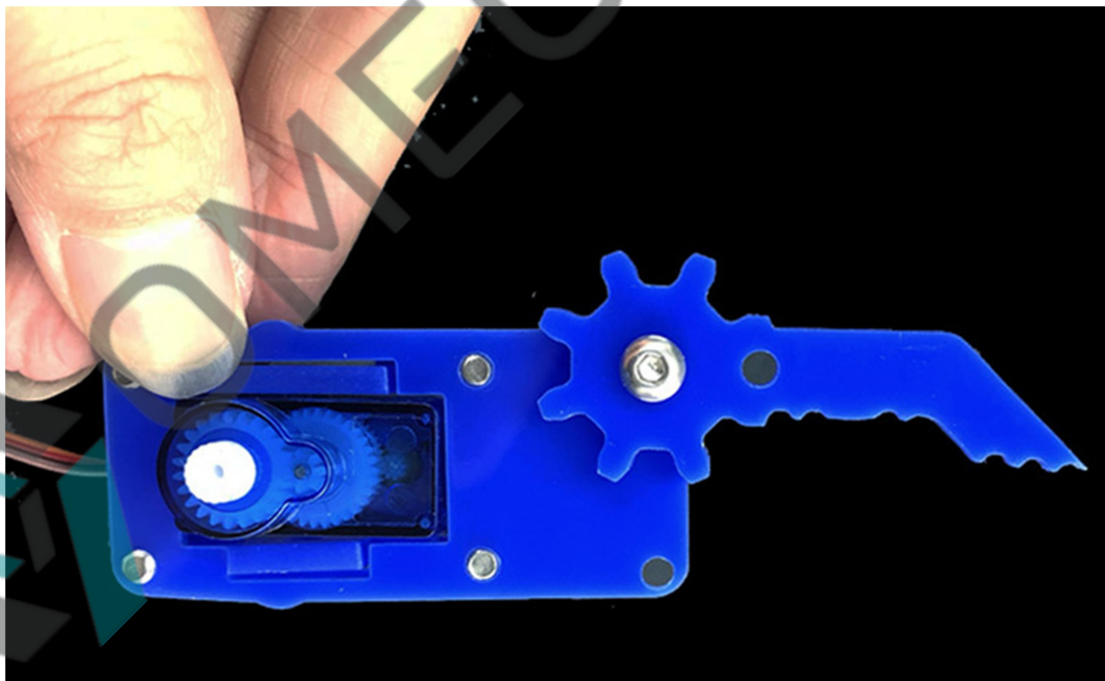
Step 12: 夹子

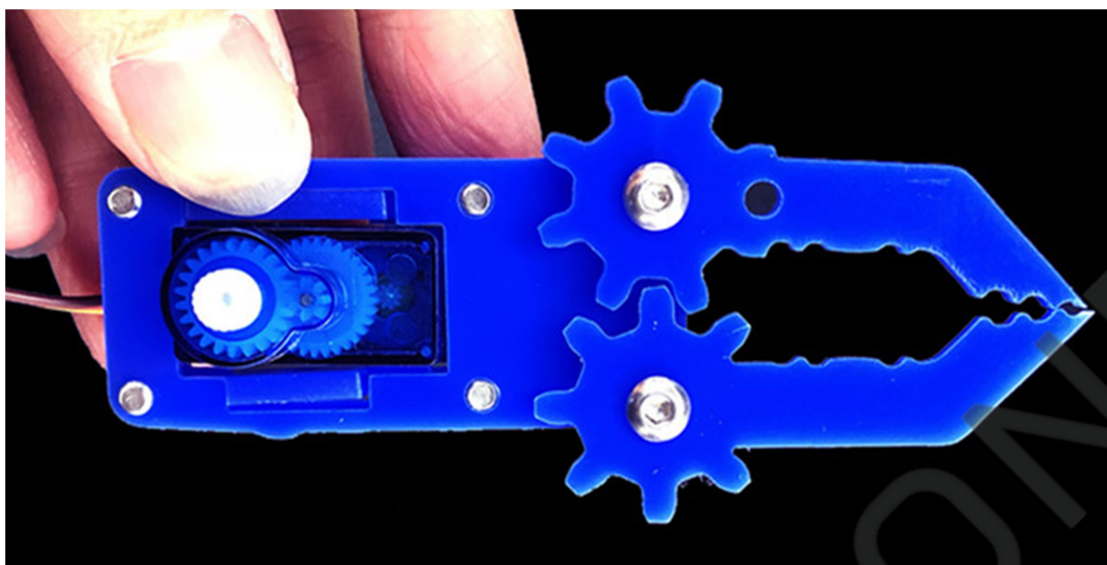


step 12 : clip

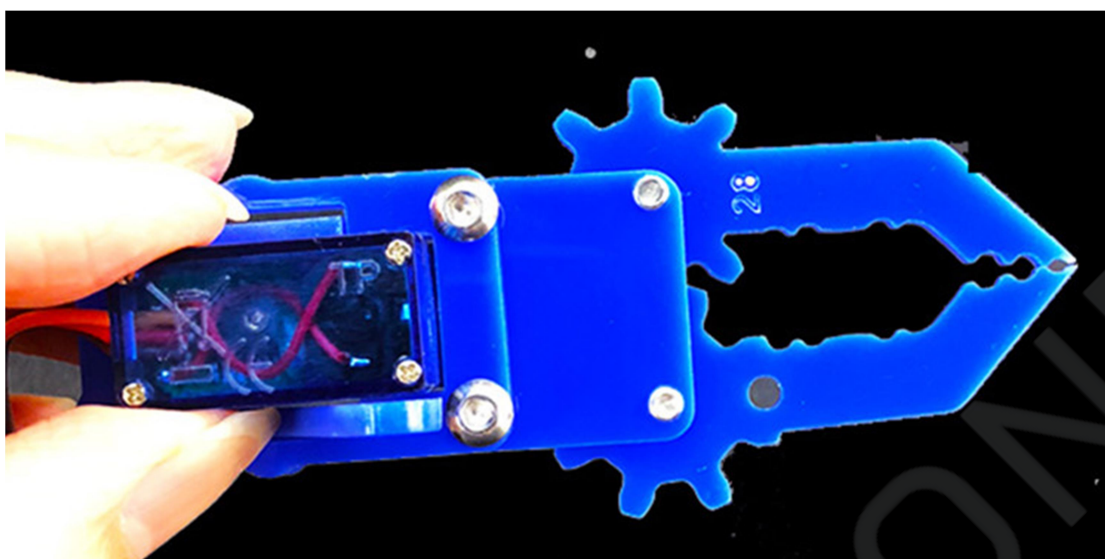
6mm x 3

8mm x 1

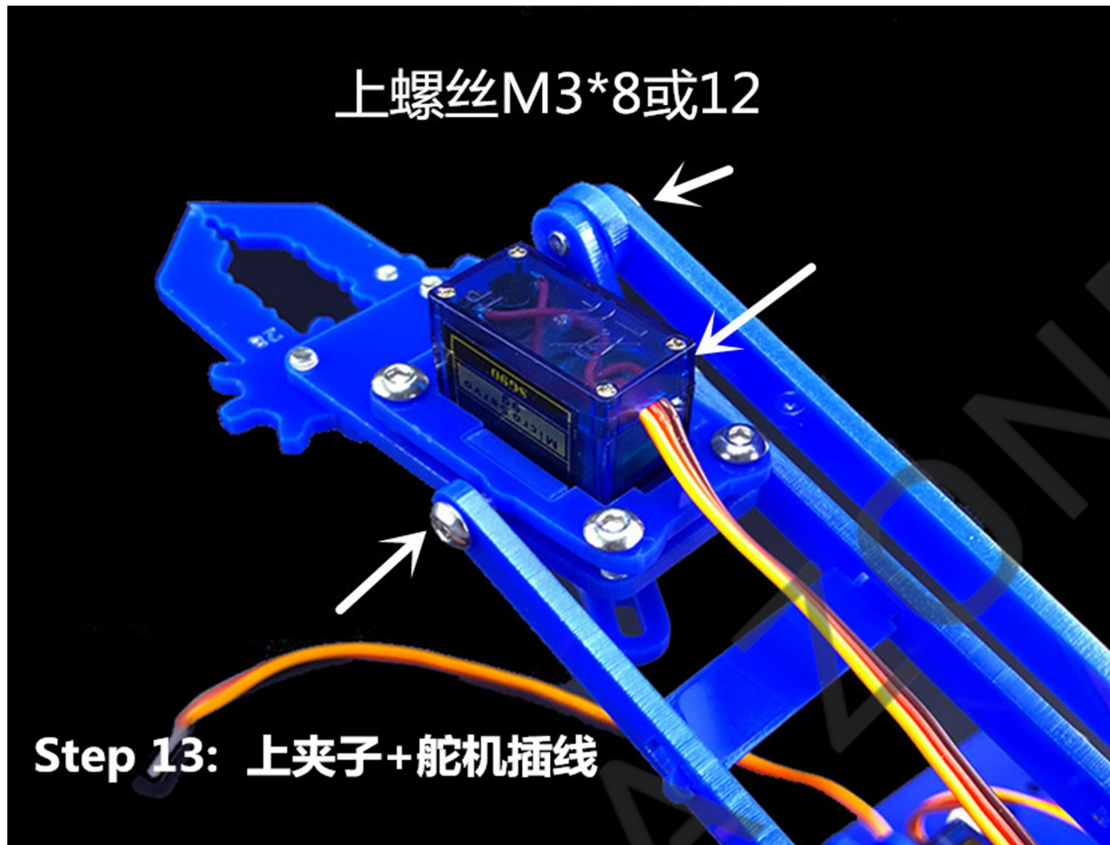




OMEGA ZONE



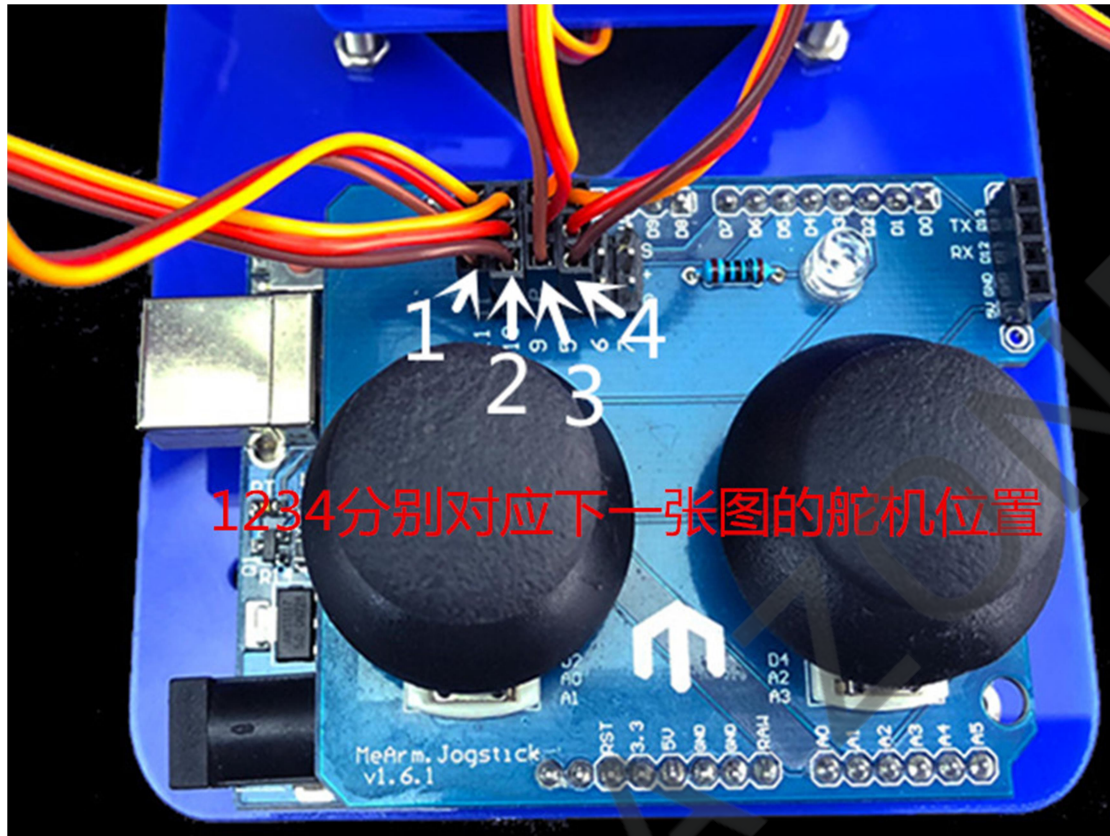
This step is focused on motors, the same way of operation as before. When the rocker turns left or right, the claw can be opened or closed. Finally, remember to lock the motor's screw.



Install screw M8*8 or 12

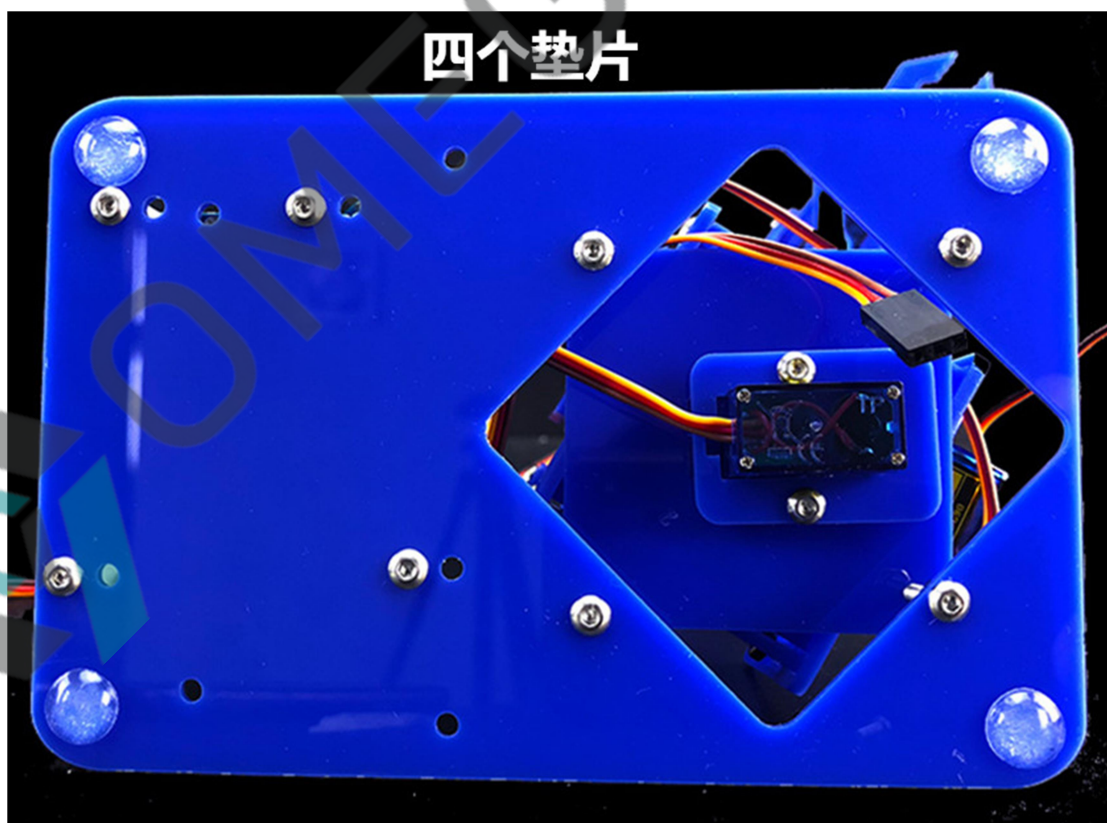
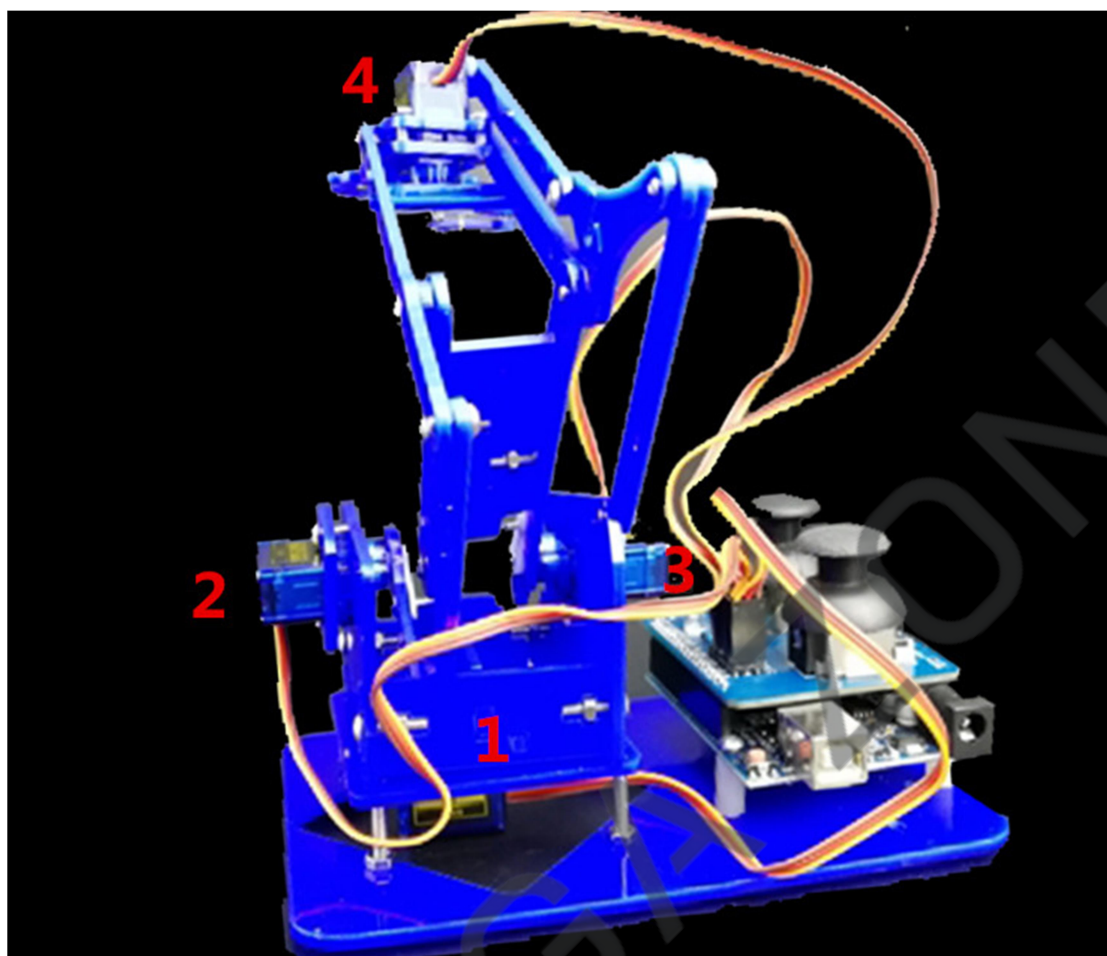
Step 13: install the clamp, the rudder is connected to the line





1234分别对应下一张图的舵机位置

1234 corresponding to the position of the rudder in the next picture.



Four gaskets