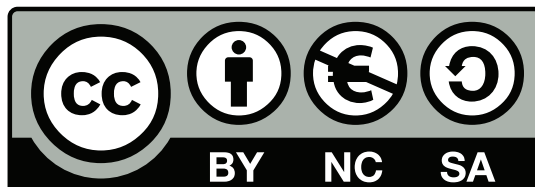


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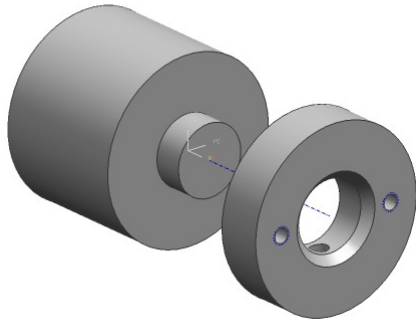
Assembly instruction of GECK3robot



Biel February 4, 2008 MicroLab Raphaël Loeffel

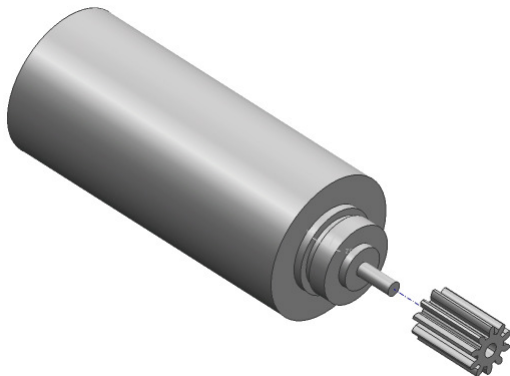


Step 1



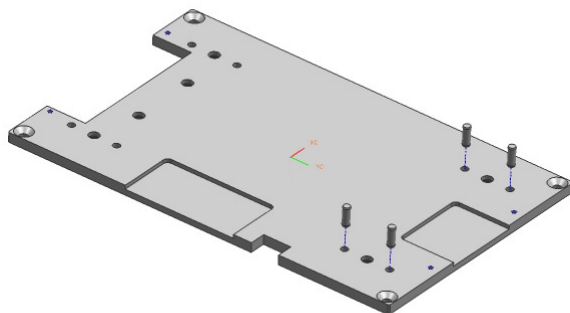
- Clean with acetone the surfaces for gluing.
- Expanding the gluing-activator (Loctite 770) on the gluing surfaces of Tenon
- Apply glue (Loctite 480) on the gluing surfaces of ball runner.
- Assemble the two pieces.

Step 2



- Clean with acetone the axale of the motor and the gears.
- Apply glue (Loctite 493) on the motor's axis.
- Assemble the two pieces.

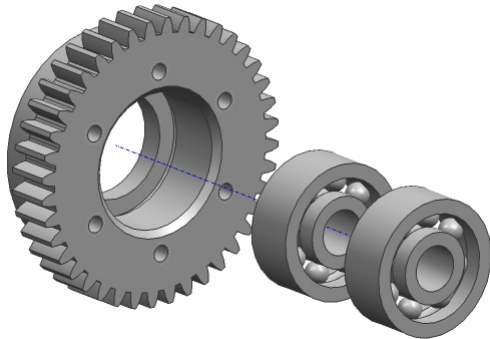
Step 3



- Clean the base and the pin $\text{\O}1.5\text{mm}$ with acetone.
- Apply glue (Loctite 493) into the holes.
- Assemble the pieces.

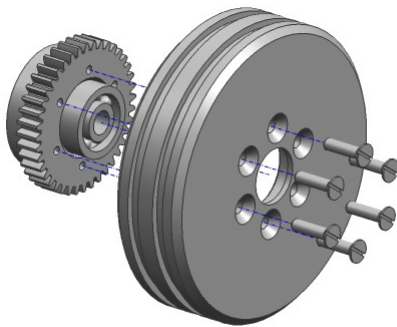


Step 4



- Place the two ball bearing into the gears.

Step 5



- Screw the rim on the gears with the conical screw M1 x 4.

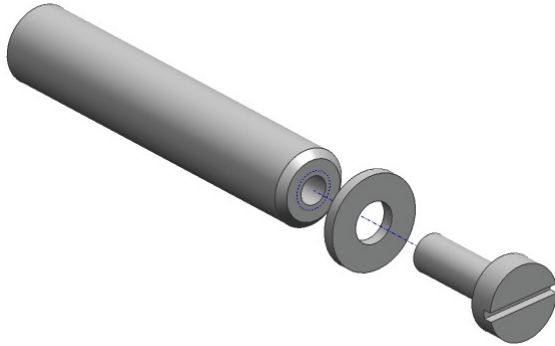
Step 6



- Mount the two O-Ring 23 x1 on the rim.

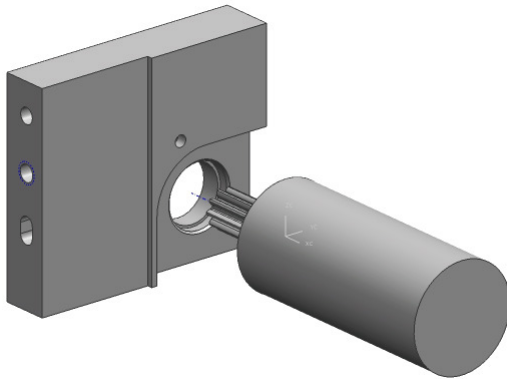


Step 7



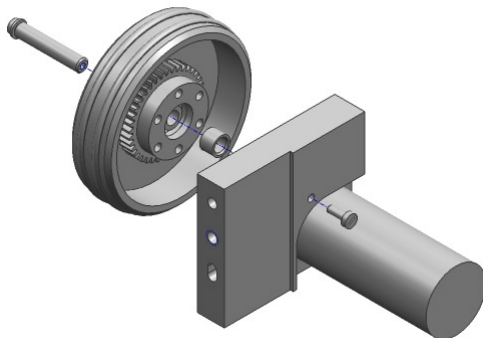
- Fix the spinner M1 with the M1 x 3 screw on the axale of the wheel.

Step 8



- Screw the motor on the support.

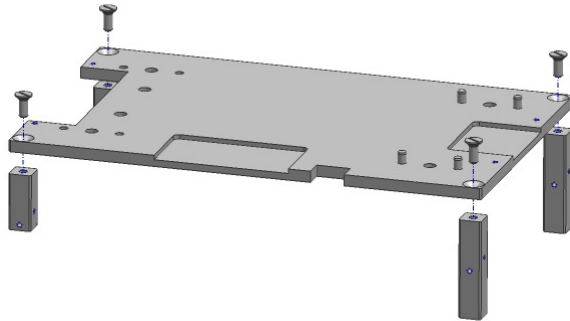
Step 9



- Place successively on the axale wheel, the wheel and the spacing tube.
- Place the axale in the motor-support.
- Fix the axale with the M1 x 3 screw.

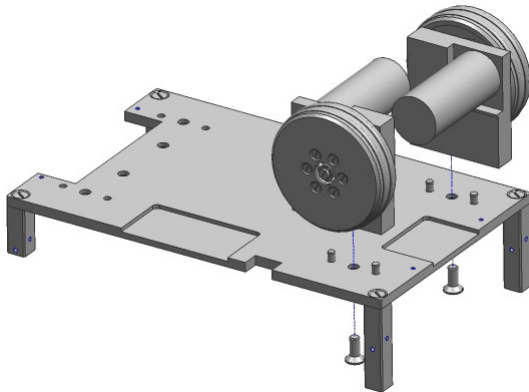


Step 10



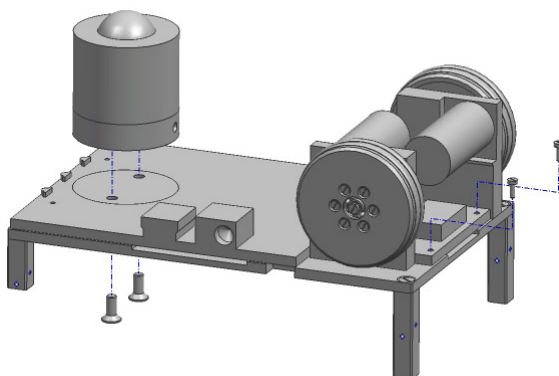
- Fix the support of body and the foot of the Geko on the base with the conical crews M1.6 x 4.

Step 11



- Fix the pre-assembly of step 9 on the base with the conical screws M2 x 5.

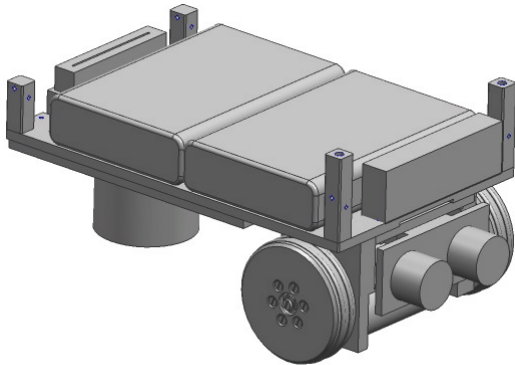
Step 12



- Place the power supply circuit on the chassis.
- Fix the board using M1 x 3 screws, and the ball runner using conical screws M2 x 5.

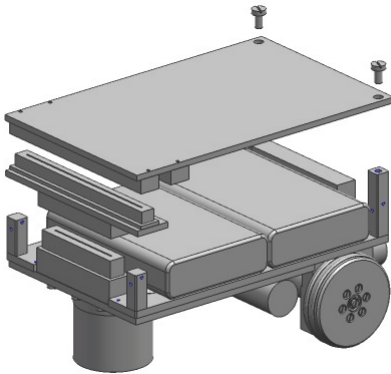


Step 13



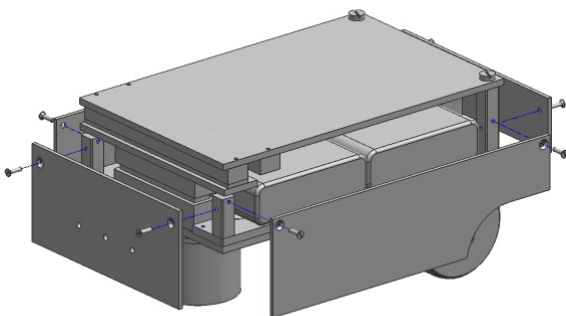
- Place the battery pack as shown.
- Plugged the ultra-sonic circuit

Step 14



- Plugged the circuits as shown.
- Fix the Geko card by M2 x 4 screws.

Step 15



- Fix the 4 body plate by conical screws M1 x 4.

