











ArmBot

ArmBot is a REX robot that can move items around it from one point to another, thanks to the 4-axis robot arm and wheels it has in its body.

What is Robot Arm? Where Is Robot Arm Used?

With advancements in technology, robotic arms are frequently used to reduce manpower in industrial $\frac{1}{2}$ production and prevent accidents that individuals might encounter in hazardous tasks. The capacity of the robot arm to reach various points is determined by the number of axes. The robot arm included in The REX 8 in 1 kit is a 4-axis robotic arm capable of reaching four different points by utilizing four servo motors.







Types of Robot Arm

Robot arms are divided into five according to their features.

Joint Robot Arm

A robot with joints that can rotate to at least three different points is referred to as a robotic arm with joints.

It is the robot arm that moves only spherically. The range of motion is restricted according to the length of the arms.

Cylindrical Robot Arm

This type of robot arms move in a cylindrical workspace.

■ Cartesian Robot Arm

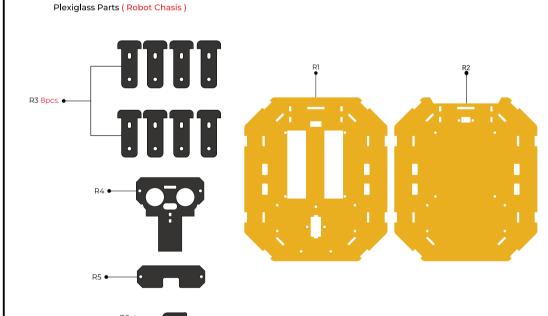
It is a robot arm that moves linearly in the X, Y and Z axes.

SCARA Robot Arm

The most fundamental characteristic that sets the SCARA Robot Arm apart from a joint robot arm is that its rotation axes are vertical. While it does not have vertical movement, it offers various options in the horizontal direction.



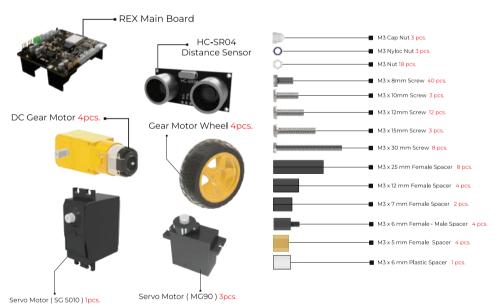


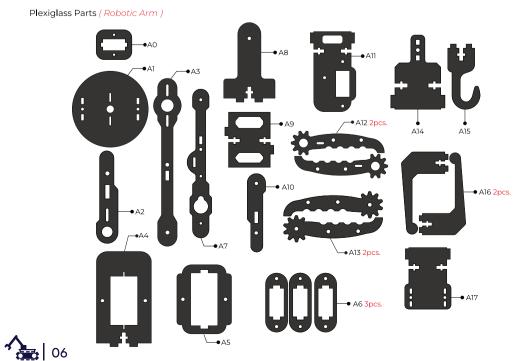




03

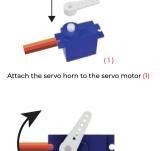
Components of ArmBot





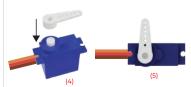
Servo Motor Calibration (Essential)

Before starting the assembly, you have to manually calibrate the angles of the servo motors. Otherwise, Servo Motors won't be working properly.



Then slowly turn the servo horn clockwise until it stops. It is not a problem if the servo horn is not the same as the angle shown in the image above. The important thing here is that you have hit the last angle of the servo. (2)





Reattach (4) and reposition the servo horn perpendicular to the servo motor as shown. (5)



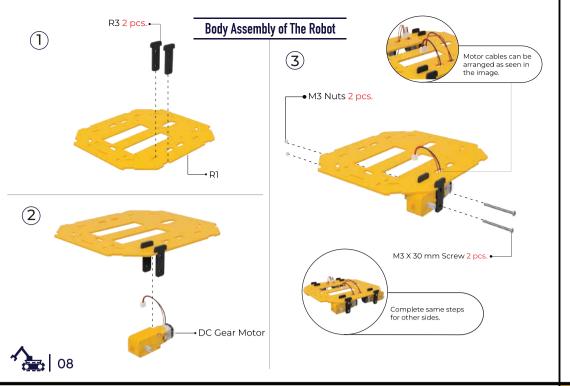
Slowly turn the servo horn counterclockwise (6) until it is parallel with the servo motor, as seen in the

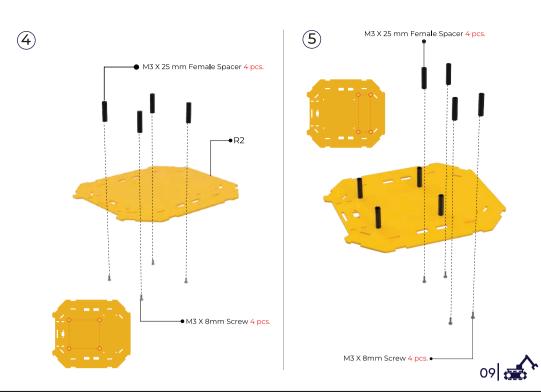


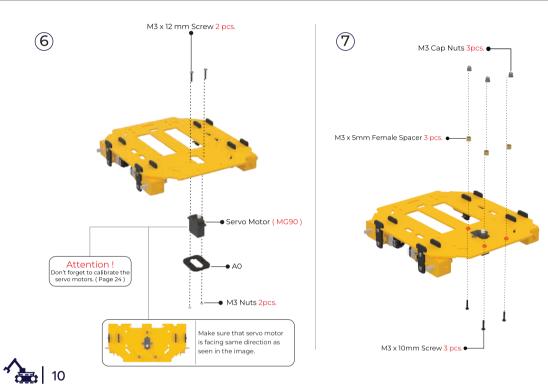
For more detailed information about servo motor calibration scan the QR code.

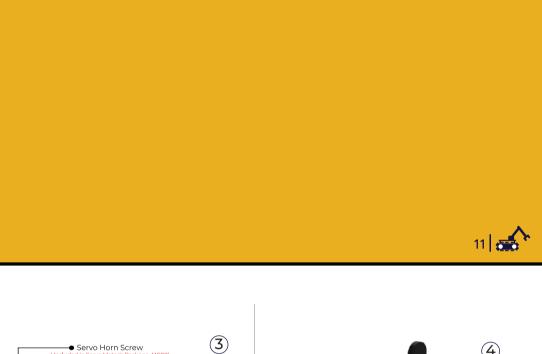


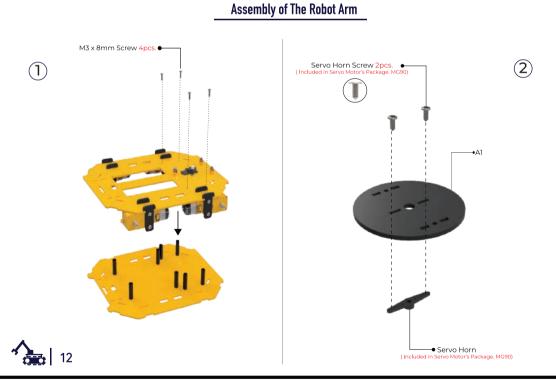


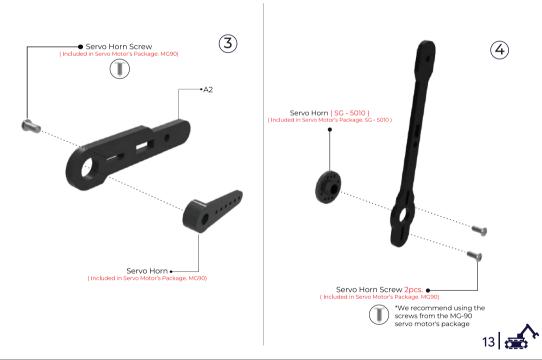


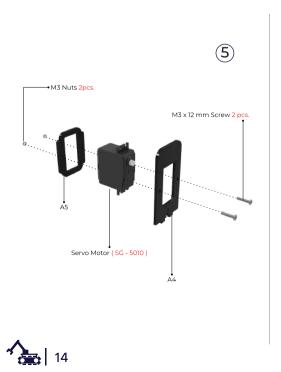


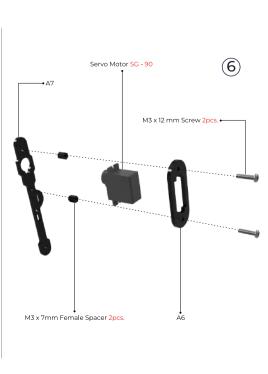




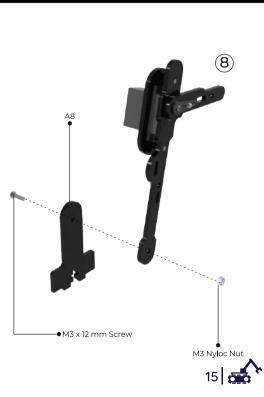




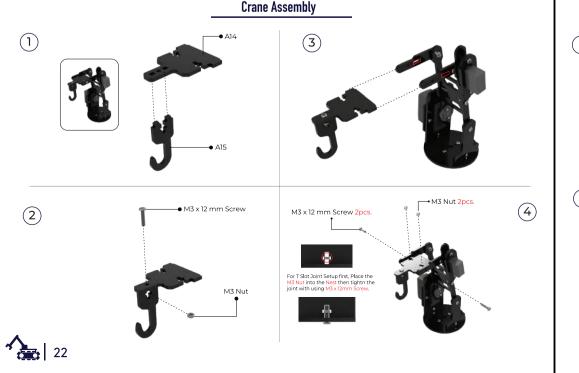


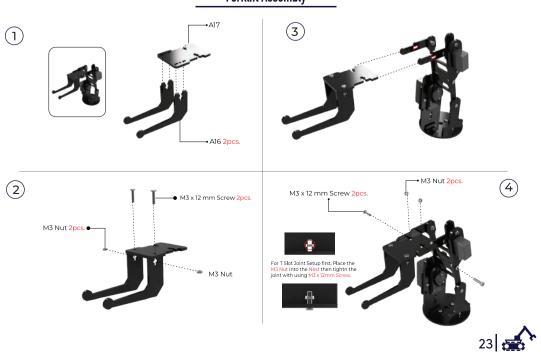


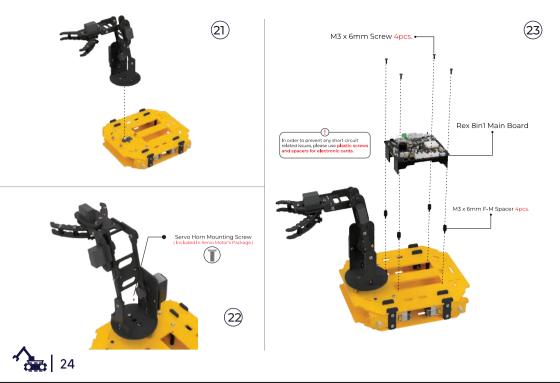


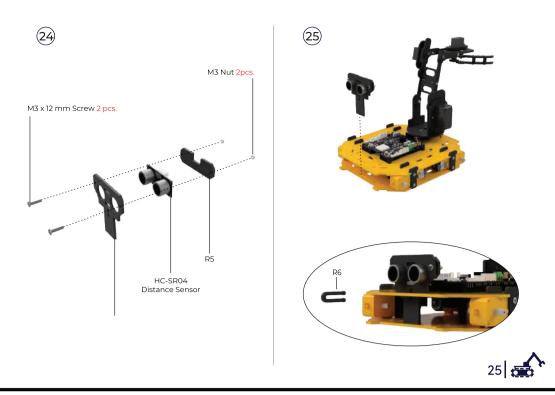














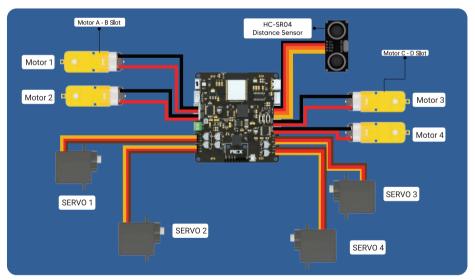






The Circuit Diagram

After assembling the acrylic pieces, you can proceed with circuit installation as shown in the diagram below.



	Ard	ino Code		
rmBat l	ins			
1 2	//REX BIRL Arm Bot" //Check the web site for Robots https://rwx-rdt.readthedocs.Id	on/latest/		
4 5	Wdefine CUSTOM_SETTINGS #define INCLUDE GAMEPAD MODULE			
6	#include <dabbleesp32.h></dabbleesp32.h>		V4	V5
7	winclude <arduino.h></arduino.h>		/armbotcode	rbt.ist/armbotv5
9	#Include <msspace.h> #Include <msspace.h></msspace.h></msspace.h>	rocisc	/ drimbotcode	rbt.ist/drmbotv5
18	TIN LOGE SEDESES VOTES			
11	enum HOTOR_TYPE (
12	DC_MOTOR,	<u> </u>	66.4	
13	SERVO_MOTOR	TW:		176 E.Z.
15);	C:574	95,462	1-2-C2-20-3
15	enum MOTOR_TYPE motorType = DC_MOTOR;	<u> </u>	1037H	
17	//define pins of motors	l m l r		III III
1.5	wdefine Motoral 15			
19	#define MotorA2 23			
20		Sca	in the QR	code to go to
2.1	#define Mator81 32			•
22	#define MotorB2 33	τη	e wnoie c	ode and the
23			necessar	y libraries.
2.4	#define MaterCi 17		necessar,	indianes.
25 26	Wdefine MotorC2 10			
27	#define MotorD1 27			
28	#define MotorD2 14			
29				
30	int positions - 0 j			
31	int position2 = 0 ;			
32	int position3 - 8;			
33	int position4 = 0 ;			
34	Conflict to the sales and a series areas			
35	//dofine bursdr pins which named "horn" Wdefine born 2			
37	THE THE LIMIT &			
38	//define pins of servo motors			
30	Servo Servol; // Forward-Bakcward			
40	Servo Servoz: // Right-Legt			
41	Servo Servo3; // Up-Ooun			
42	Servo Servo4; // Open-Close			
43				
				29

	•
·····	•
	.
	•
······	•
	•

28