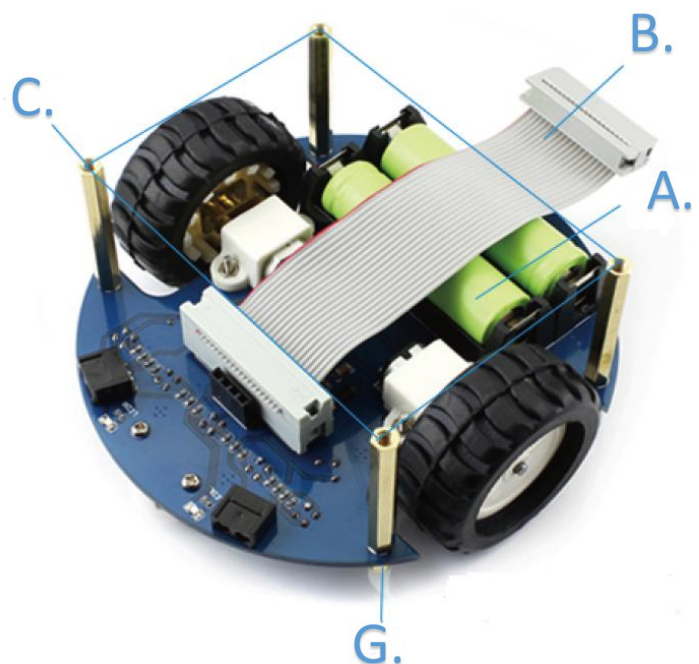
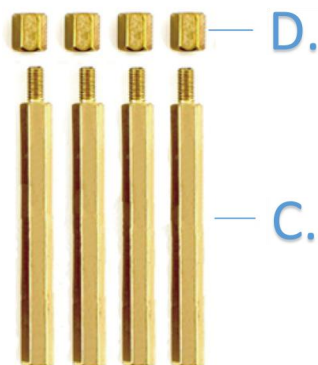
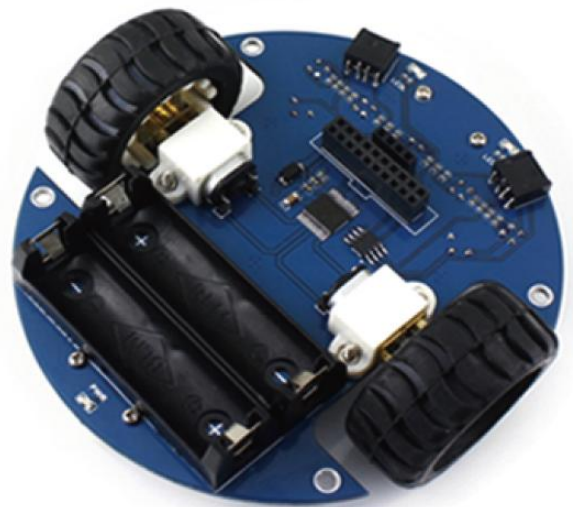


AlphaBot2-Pi Assembly Diagram

1. Base Chassis Assembly

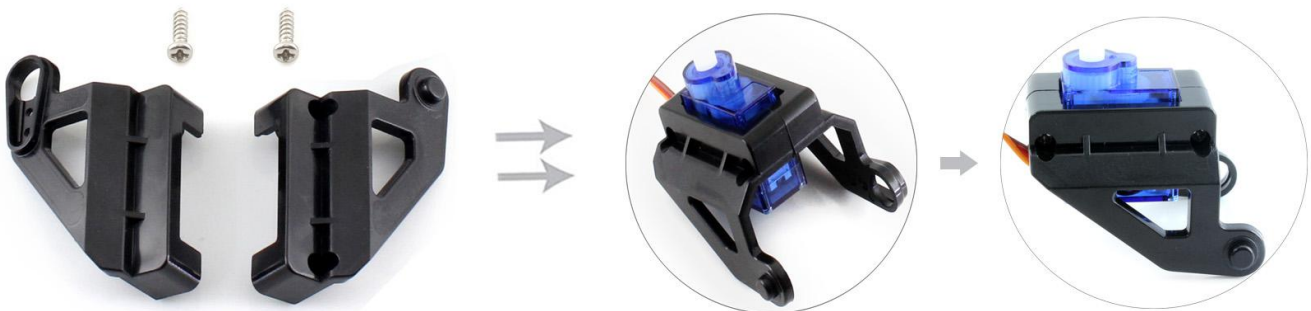
Install the 14500 batteries 2pcs (A), FC-20P cable 8cm (B) and screw pillars/caps (C & D) onto the AlphaBot2-Base (base chassis).



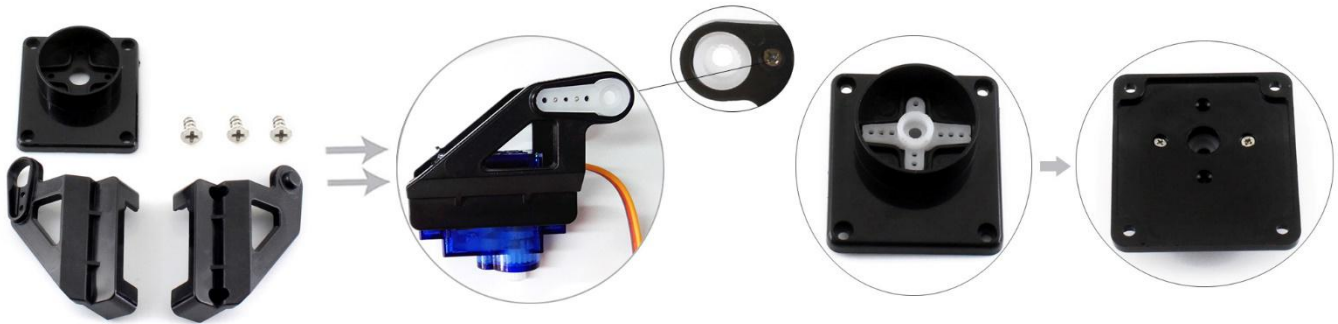
2. Camera Pan & Tilt Assembly



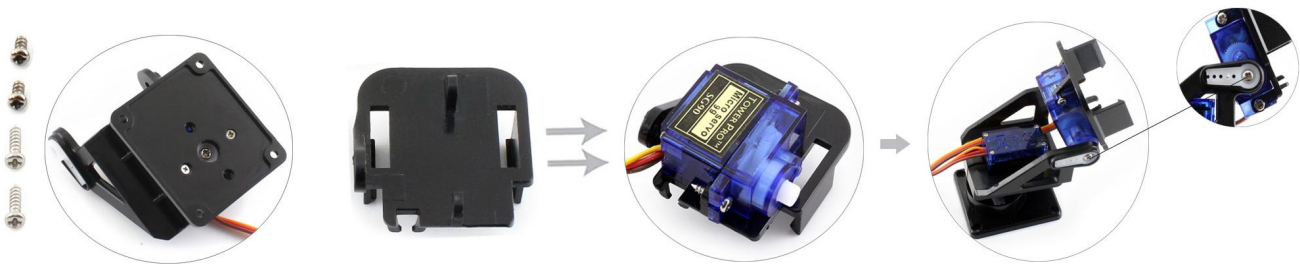
Place the steering gear in the middle of the stands **(f)** and **(g)** and fix it with the screw **(7)**. Please make sure the rotor on the steering gear is installed in a correct direction.



Cut out a little bit of the arm on the rocket arm **(c)**, place it into the stand **(g)**, and fix it with the screw **(5)**. Then, cut out a bit of each arm on the cross-shape rocket arm, and place it into the base, and fix it with the screw **(5)** on the back side of the base.



Insert the steering gear describe above to cross-shape rocket arm **(b)** in the stand **(d)** and fix the installation with a screw **(1)**. Fix another steering gear into the stand **(e)**, and fix it with two screws **(7)**. Install the stand **(e)** and steering gear to the stands **(f)** and **(g)**, and fix them with the screw **(1)**.

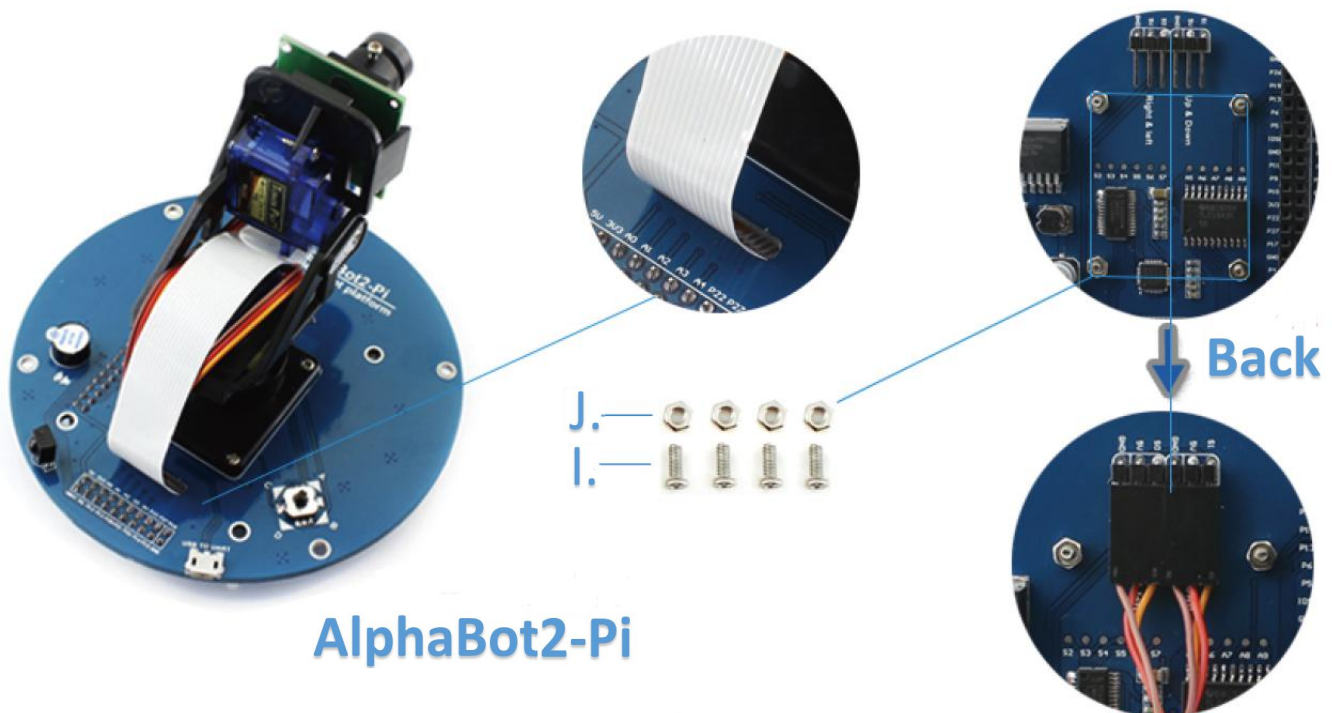


Connect a 25Pin FFC cable (opposite sides contact) to the Raspberry Pi camera, and clamp the camera on the top of the stand **(e)**

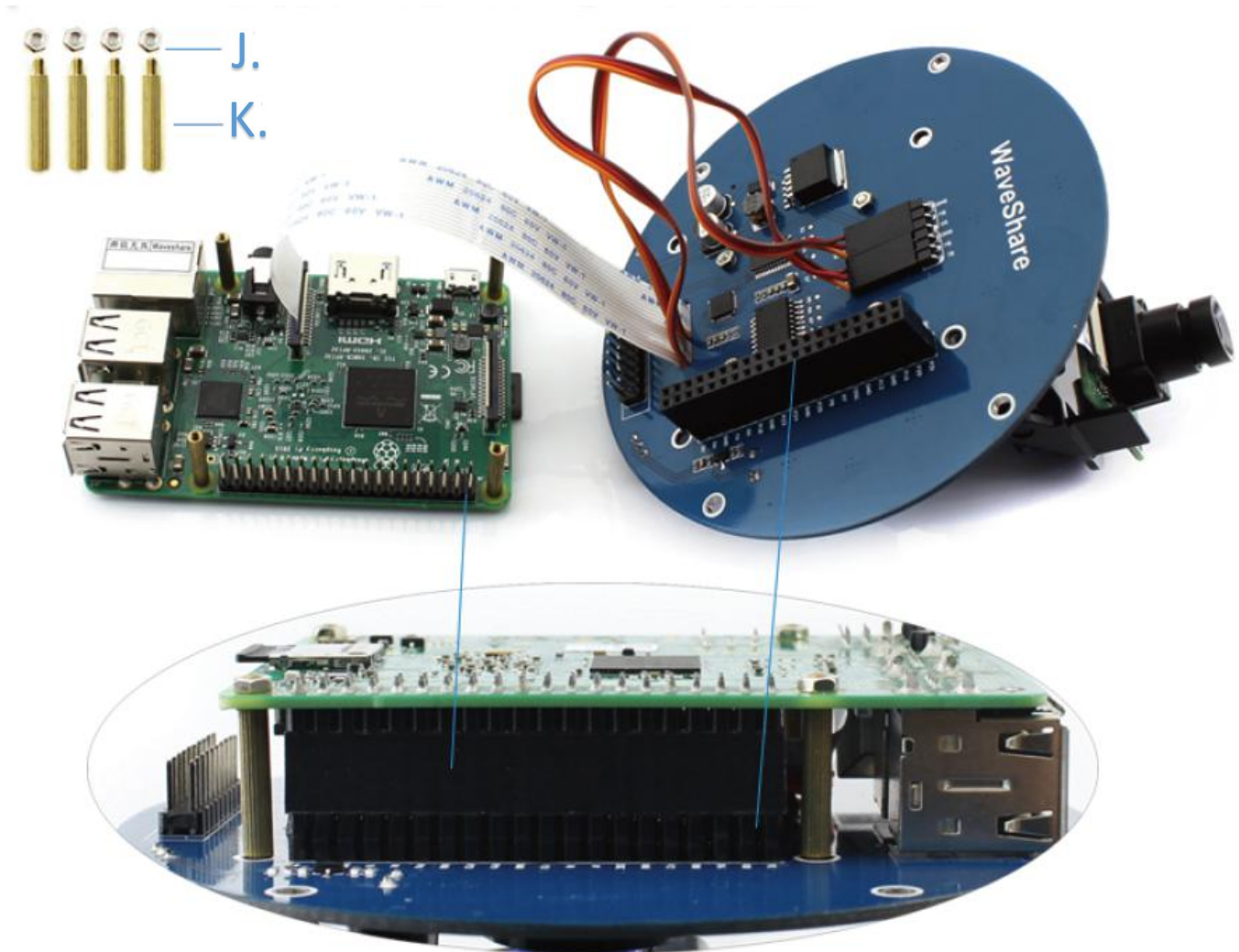


3. Integral Assembly

Fix the Camera Pan & Tilt unit to AlphaBot2-Pi (adapter board) with the screws/caps (**I & J**). Pass the motor cable through the flat cable hole and connect it to the pins on the other side of the adapter board. Also, pass the camera cable through the flat cable hole and connect it to the Raspberry Pi board.

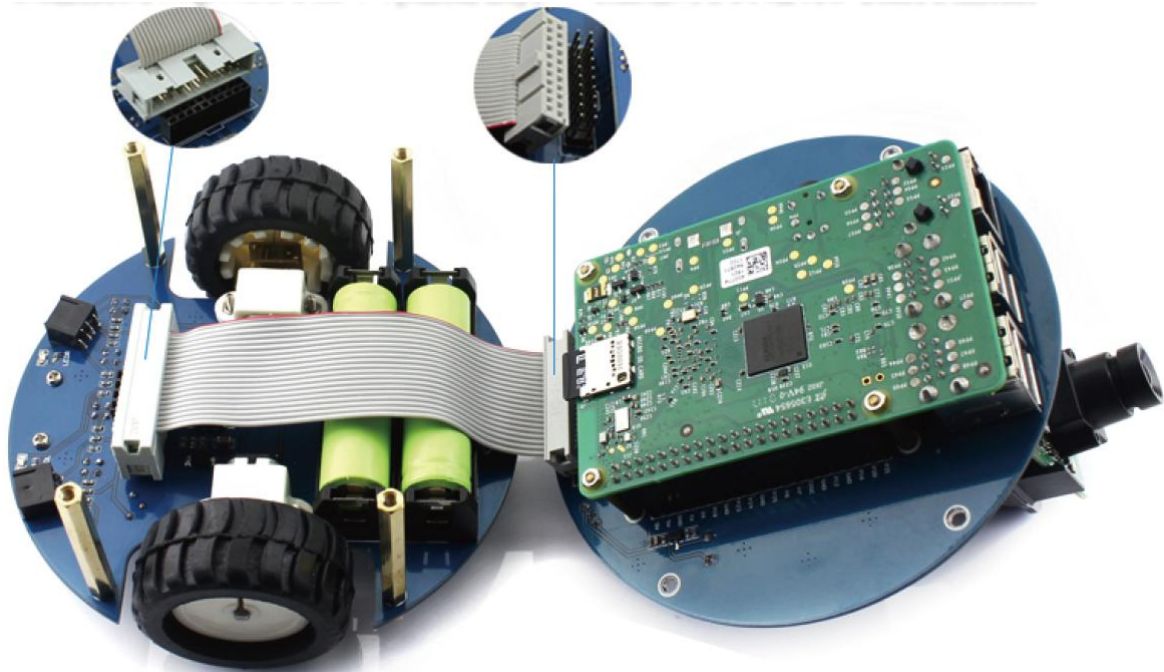


Fix your Pi to the adapter board with screw pillars/screw caps and then connect the camera cable to the Pi.



Plug the FC-20P cable to both the AlphaBot2-Pi (adapter board) and AlphaBot2-Base (base chassis). Note: the connector of the cable must be plugged following the marks on the PCB. Please make sure

the cable is connected correctly.



Fix your Pi to the AlphaBot2-Pi (adapter board) with the screws **(I)**.
Fix the AlphaBot2-Pi (adapter board) to the AlphaBot2-Base (base chassis) with the screws **(F)**.

