

[illegible]

1

2x 2x 1x

2

Utilizamos el servomotor para poder ajustar el ángulo de movimiento del brazo

3

4

2x

1x

5

2x


1x

6

1x


7

8




2x

9




4x 2x

10




2x

11



12

13




2x

14

1x

1x

15



16

Conectamos el servomotor a SI