

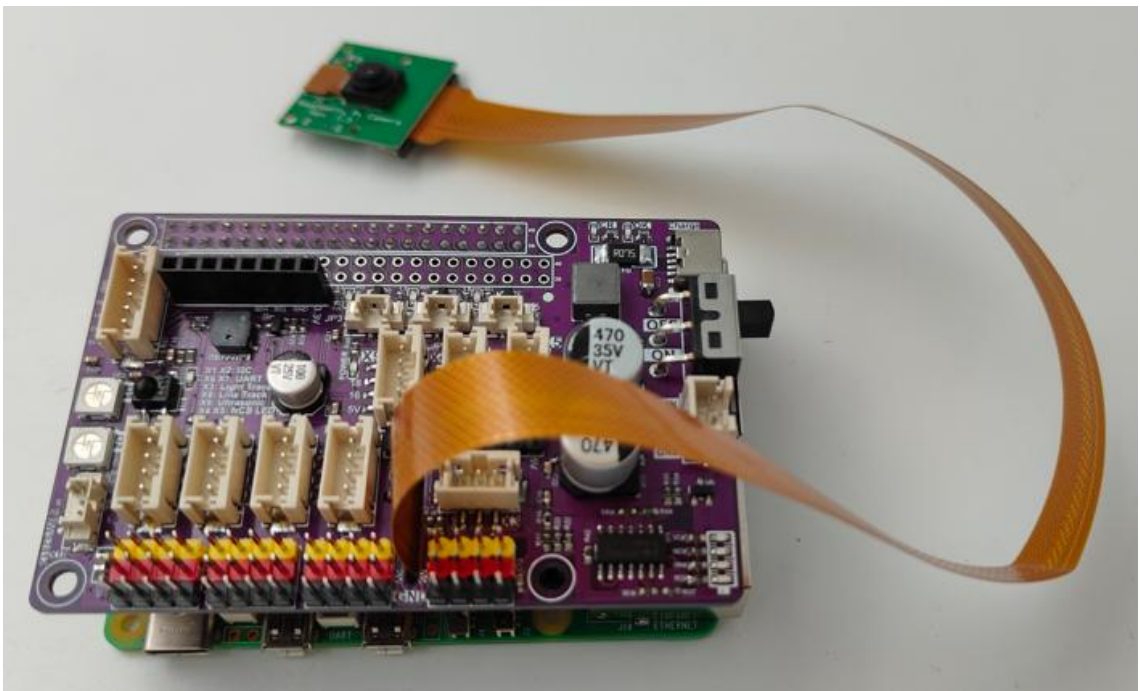
1 Precautions for Assembly

1. 1 Precautions for Assembly

- Many servos are used in this robot. Therefore, the assembly of servos has great impact on its performance. Before assembling the servo rocker arm, it's recommended to power on the servo and control the servo shaft to rotate to the central position, so then the rocker arm installed at a specific angle will be in the center position.

Operation steps of powering on the servo:

Boot up the Raspberry Pi.



Assemble the servo. Pay attention to the direction of the port when assembling. The yellow wire is connected to the yellow pin, the red wire to the red pin, and the brown wire to the black pin.

- After the Raspberry Pi boots, it will automatically run `webServer_HAT_V3.1.py`, and then control all the servo ports to send signals to move to the middle position. When assembling the servo rocker arm, you can connect the servo to any servo port and the servo shaft will rotate to the center position after connected. After the rocker arm is assembled at a specific angle, you can disconnect the servo from the port. Wire another servo without rocker arm and the servo will rotate to the center position.
- The Raspberry Pi will control the PCA9685 to set the signal for all servo ports as rotating to the center position a while after booting – it may take 30-50s to boot.
- The angle of all servo assembly in the document is the center position of the servo shaft rotating. Therefore, when the servo is connected to the port, it will rotate automatically to the center position; you can simply assemble the rocker arm to the shaft as instructed in the images of the document.
- Pay attention not to move the servo shaft during assembly. If you want to adjust the angle of the rocker arm, please remove it from the servo, find a proper angle and insert again.
- If `webServer_HAT_V3.1.py` does not run automatically, you can manually run `initPosServos.py` to rotate the servo to the position of 90° .

```
sudo python3 adeept_picar-b2/initPosServos.py
```

- Note: It's not recommended to tighten any lock nuts mentioned in this document.

1.2 Precautions for Power Supply

- Requirement on current may vary from Raspberry Pi models. For example, the Raspberry Pi 3B needs at least 2A to boot up, and the Raspberry Pi 4 normally needs 3A. You can check specifications on the side before powering the Raspberry Pi by adaptor.
- When Adeept Robot HAT V3.1 is connected to a load, such as a motor or a few servos, a high-current power supply is required to connect to Vin on the Adeept Robot HAT V3.1. You can use two high-current 18650 batteries for power supply. The Adeept robot provides

a dual 18650 battery box with a 2-pin interface for you to supply power to the Adeept Robot HAT V3.1.

- If your robot reboots automatically after booting, or disconnects and reboots at the moment it starts to move after normal booting, it is likely that your power supply does not provide enough current as the robot automatically runs the program to control all servos to rotate to the center position when booting – it then drops the voltage on the Raspberry Pi and causes a reboot.
- We've tested when powering with 7.4V, the peak current of the robot would be around 3.75A, which means you need to connect batteries with a 4A output.
- You may also power the Adeept Robot HAT V3.1 with high energy li-ion battery; Adeept Robot HAT V3.1 can be supplied by a power source under 15V.
- You may use a USB cable for program installation and debugging, yet it's not recommended to debug high power modules like servo and motor in case of under-voltage. Battery supply is recommended for them instead.

Q&A

- **Servo keeps on jittering.**

The gear reducer of the servo may be broken.