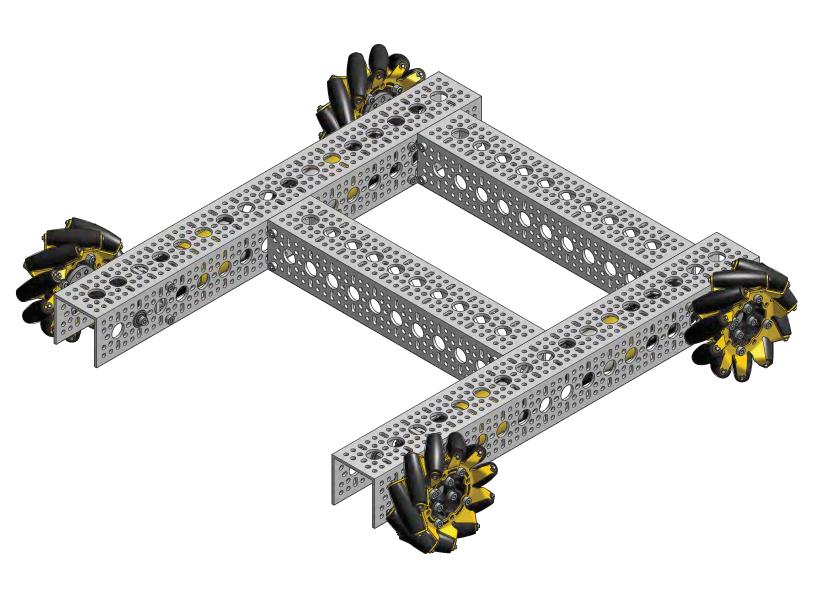
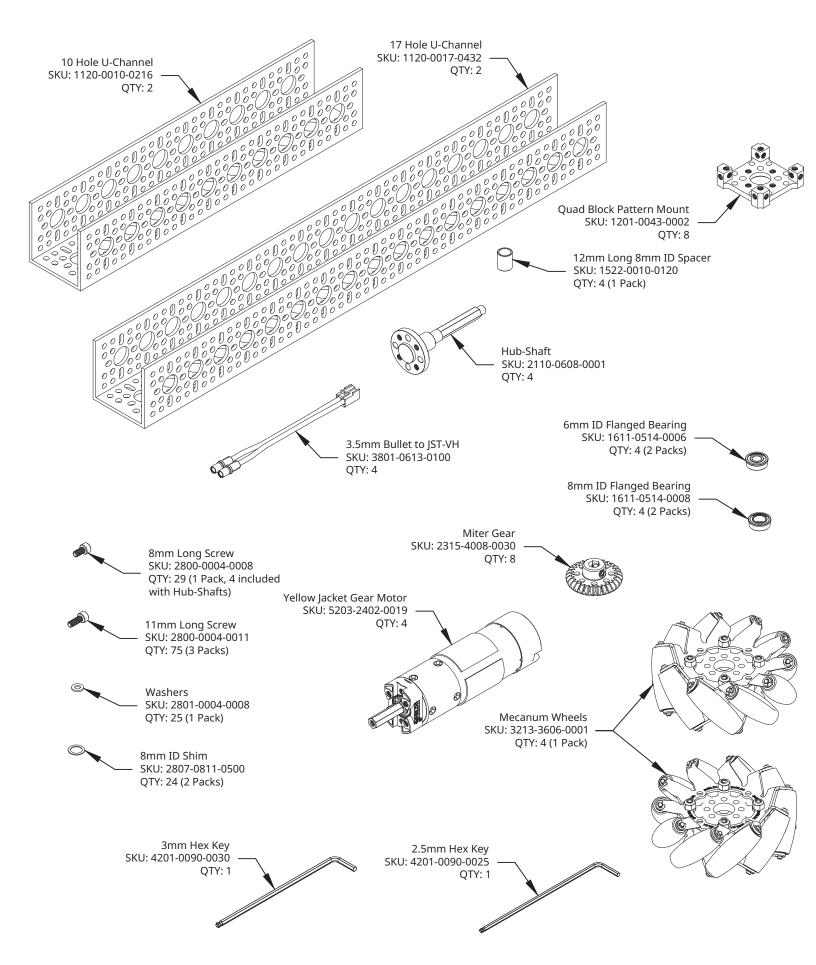
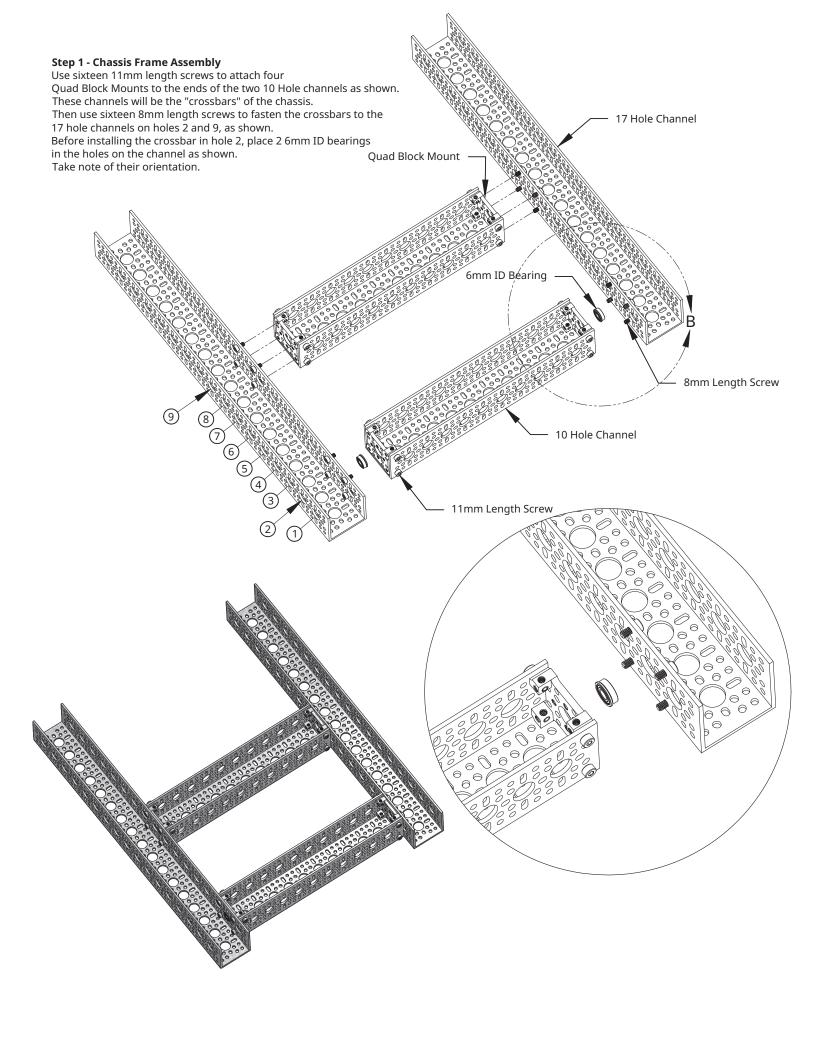
Assembly instructions for Strafer™ Chassis V5 SKU: 3209-0001-0005



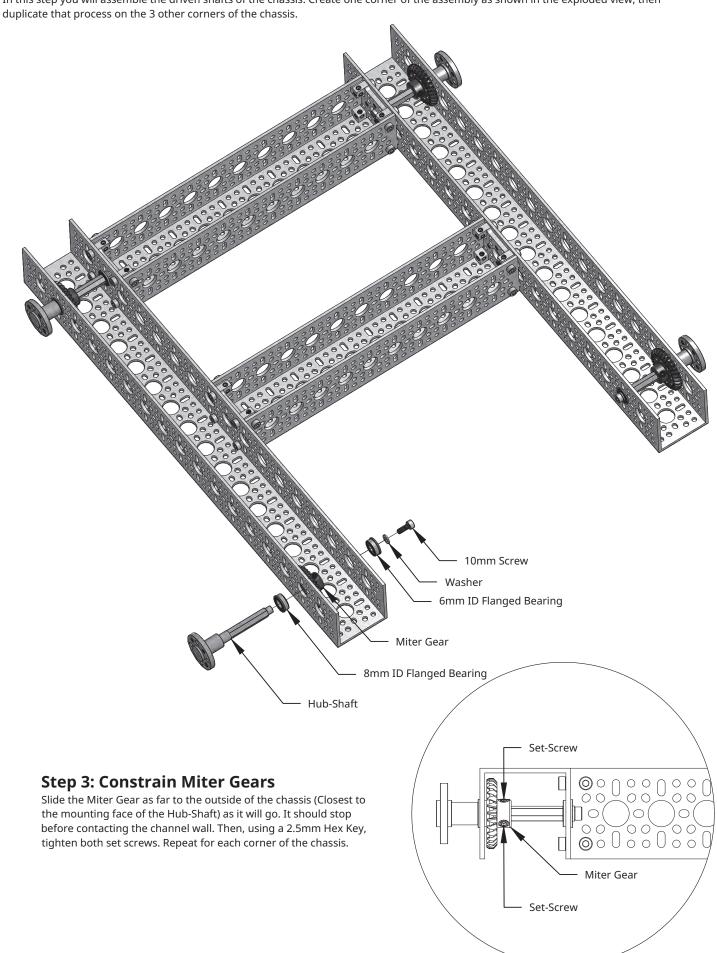
## **Kit Contains:**

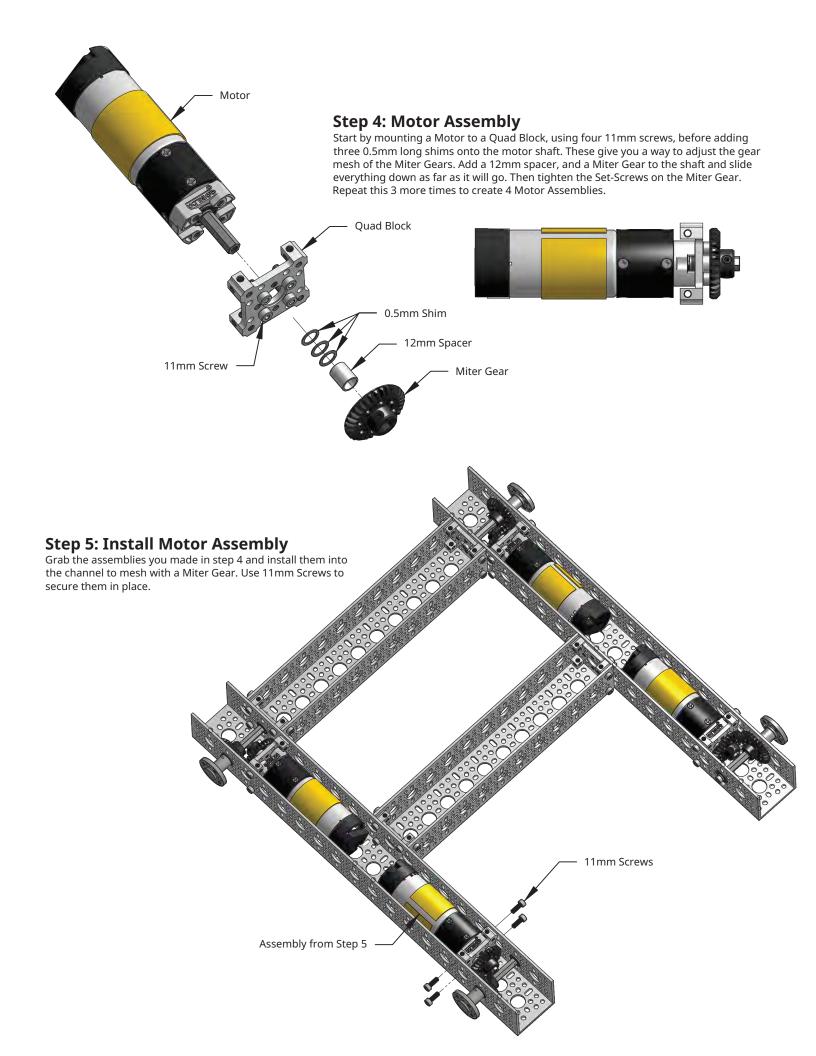




## **Step 2 - Output Shaft Assemblies**

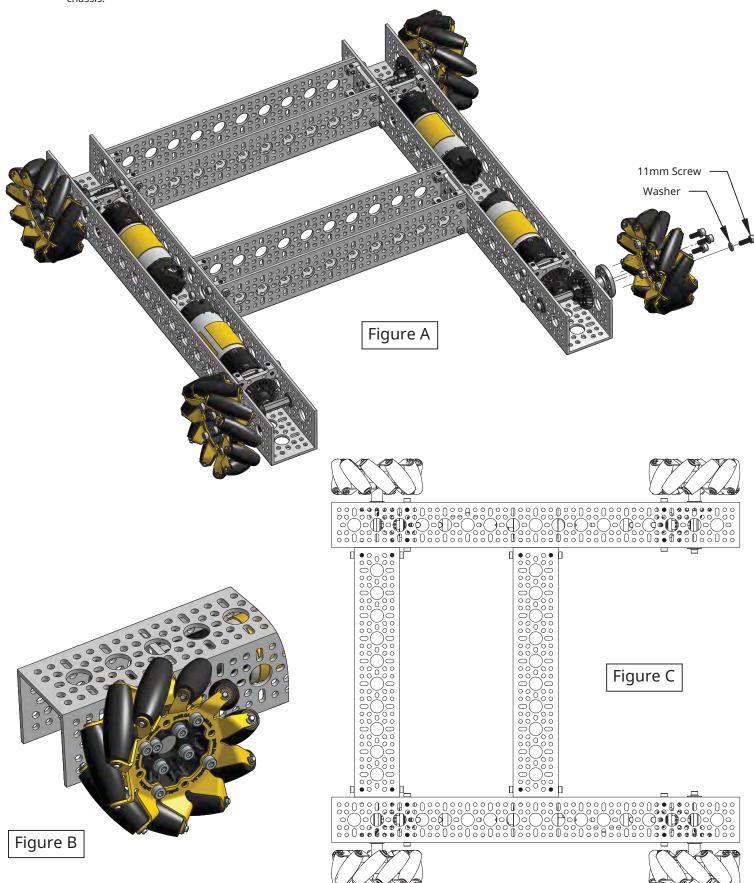
In this step you will assemble the driven shafts of the chassis. Create one corner of the assembly as shown in the exploded view, then





## Step 6: Wheels

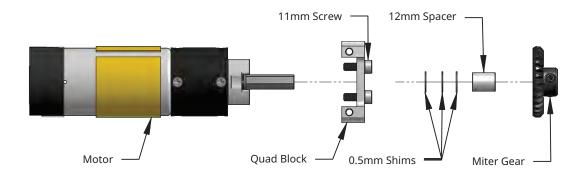
The final step is to use sixteen 11mm length screws (each with a washer) to fasten the wheels to the Hyper Hubs. (Figure A) Note that each side of the robot gets one left-slant wheel and one right-slant wheel. Also note that each wheel's core has a shallow side and a deep side - the deep side will be towards the outside of the chassis (see Figure B). For ease-of-assembly and visibility, we have been assembling the chassis upside-down. When you flip your chassis right-side-up and look down from above (Figure C), the rollers of the wheels should "point" towards the center of the chassis



## Congrats! Your chassis is now assembled.

We've incuded some parts that make running and fine-tuning your chassis easier.

- A. Your chassis comes with 4 Bullet to JST VH adaptor cables so you can control the chassis with a REV Robotics controller.
- B. Spin each wheel of the chassis by hand (with the battery disconnected). Make sure each shaft is able to rotate smoothly. A small amount of backlash between the miter gears is desirable. If the gear mesh is too tight (you'll feel excess friction when rotating the wheel), remove a shim from the motor assembly covered in step 4.



C. Included with each Hub-Shaft is a 6mm id 0.25mm thick shim. This can adjust the spacing between the bearings. If the Hub-Shaft can slide back and forth in the channel, and the screw is tight, install the shim under the washer while making sure to align the inside of the shim to the round portion of the hub shaft.

