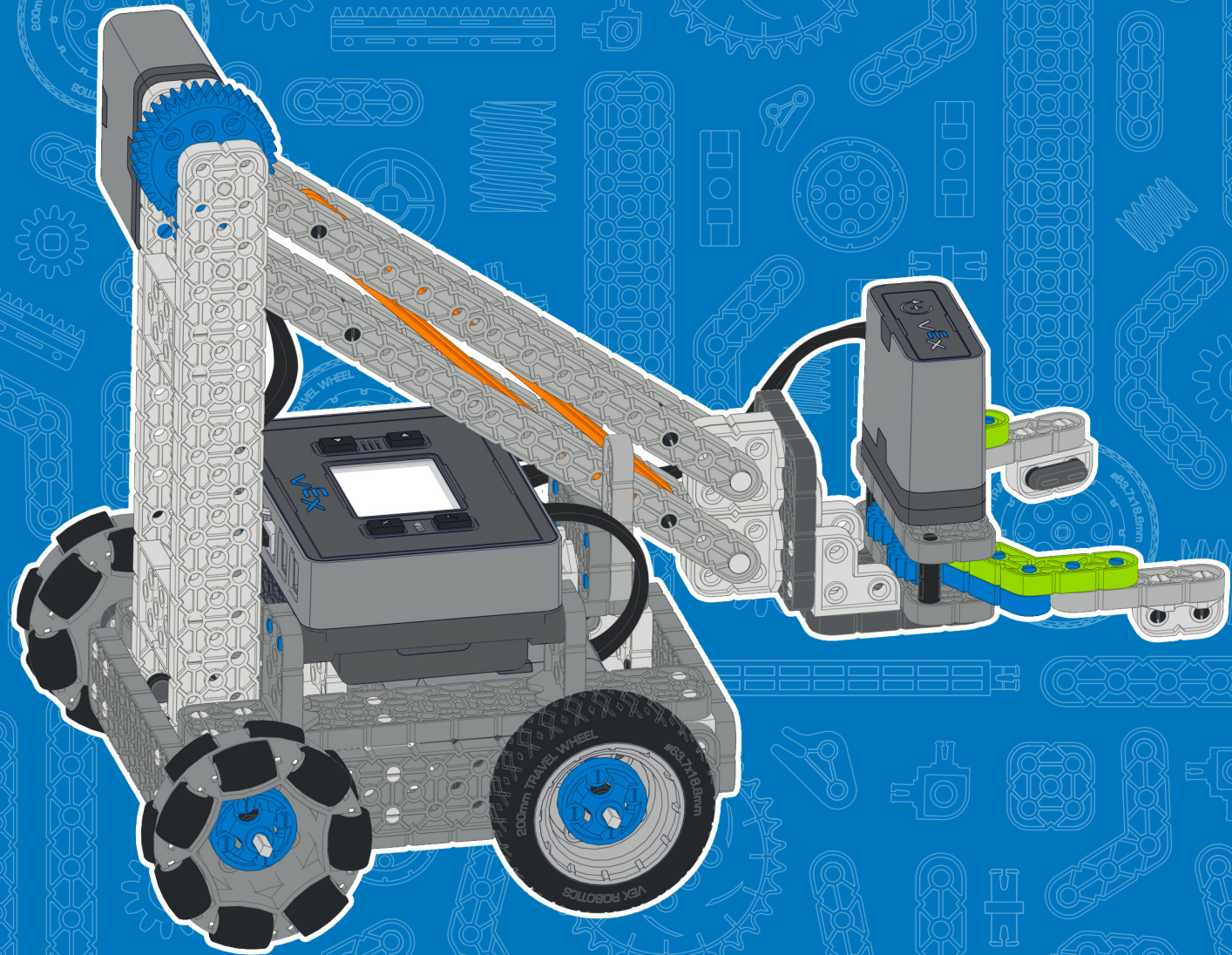
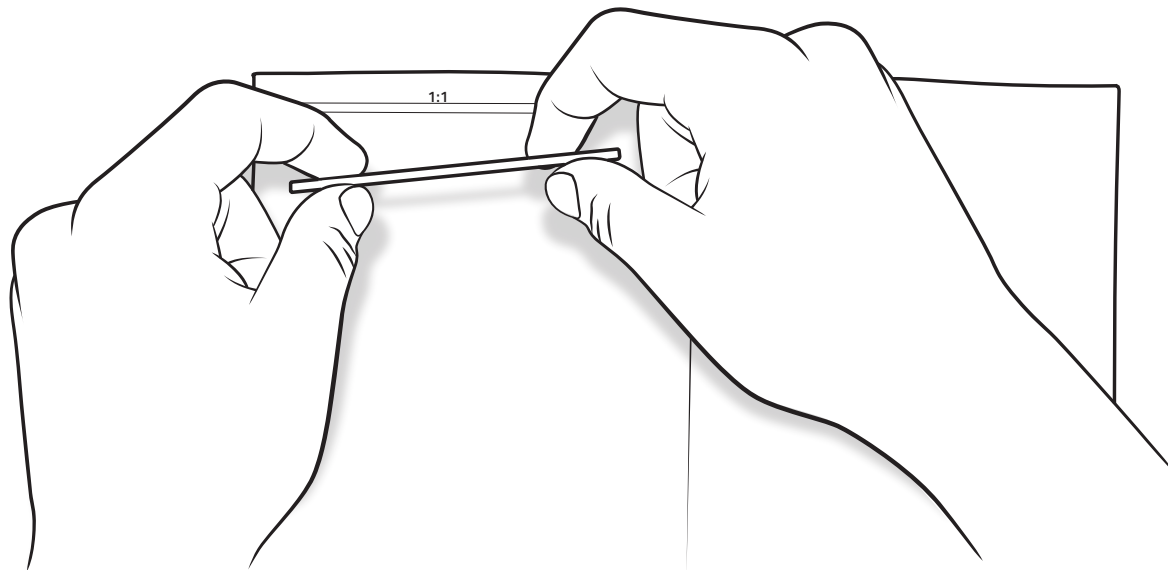


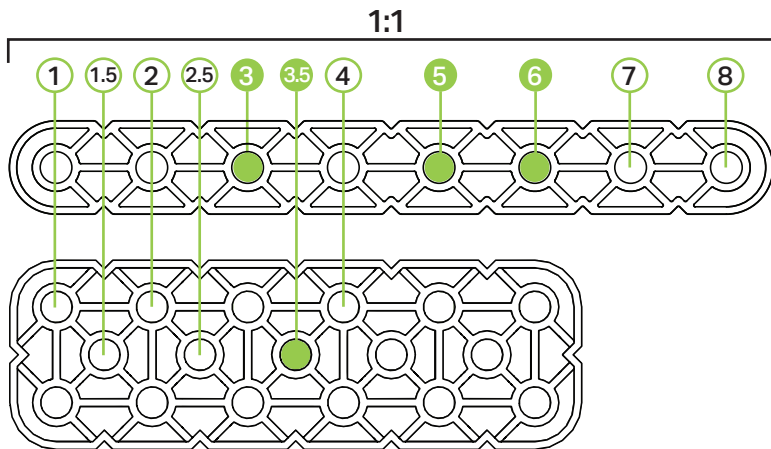
# VEX IQ

## Clawbot Build Instructions

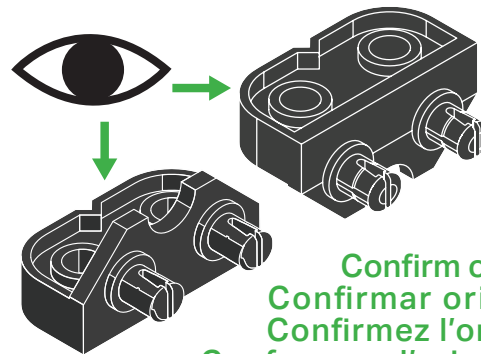




Check pieces against actual size in manual  
 Verificar partes contra tamaño real en el manual  
 Verifiez les pieces contre leurs tailles reelles dans le manuel  
 Controllare le dimensioni dei pezzi nel manuale rispetto alla grandezza naturale  
 Bauteile mit der originalgröße in der anleitung vergleichen  
 Sprawdź elementy względem rzeczywistego rozmiaru w instrukcji  
 Check stukken tegen de werkelijke grootte in de handmatige



Count before you connect • Contar antes de conectar • Compter avant de connecter •  
 Contare i pezzi prima di collegarli • Erst zählen, dann verbinden • Policz, zanim połączysz • Tell voordat u aansluit



Confirm orientation  
 Confirmar orientación  
 Confirmez l'orientation  
 Ausrichtung prüfen  
 Potwierdź orientację  
 Bevestig orientatie



Alert  
 Alerta  
 Alerte  
 Attenzione  
 Warnung  
 Ostrzeżenie  
 Waarschuwing



Correct  
 Correcto  
 Correcte  
 Corretto  
 Richtig  
 Prawidłowo  
 Correct



Pivot  
 Pivote  
 Pivot  
 Imperniare  
 Drehbar lagern  
 Obracać się na osi  
 Draaien



Incorrect  
 Incorrecto  
 Incorrecte  
 Non corretto  
 Falsch  
 Nieprawidłowo  
 Verkeerd



Alternate view  
 Vista alternativa  
 Autre vue  
 Vista alternativa  
 Andere ansicht  
 Widok alternatywny  
 Vitzicht



Size  
 Tamaño  
 Taille  
 Dimensione  
 Größe  
 Rozmiar  
 Grootte



Notice  
 Aviso  
 Avis  
 Fare attenzione  
 Hinweis  
 Zwróć uwagę  
 Opmerken

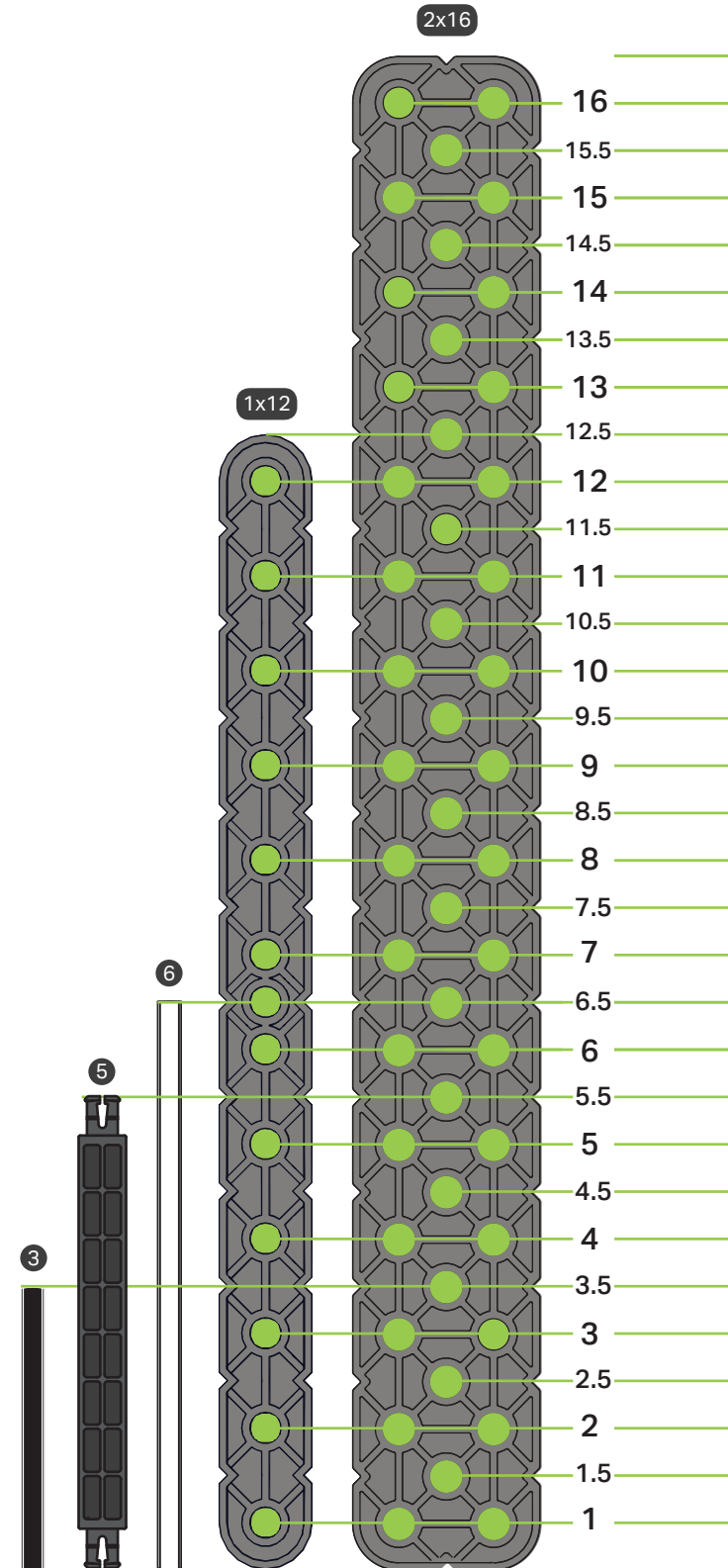
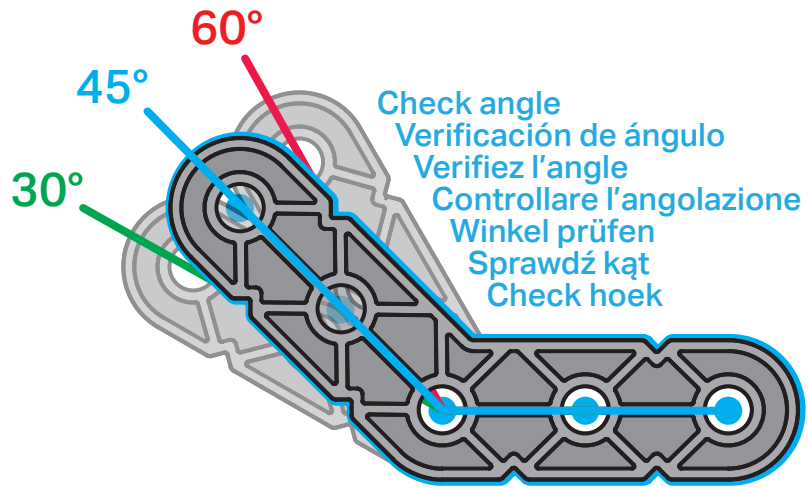
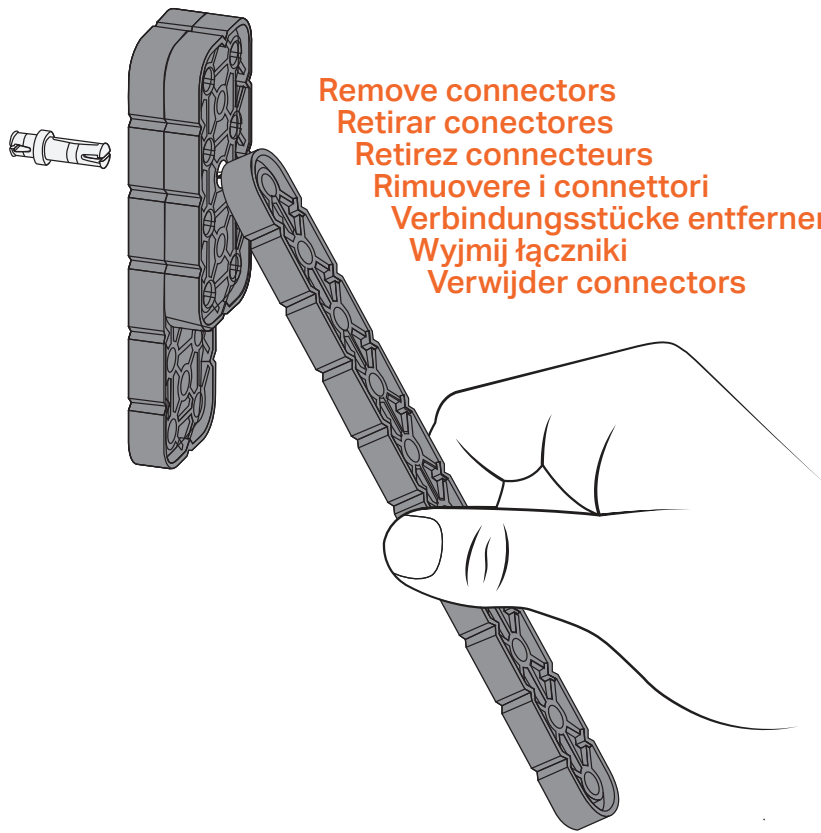


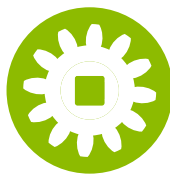
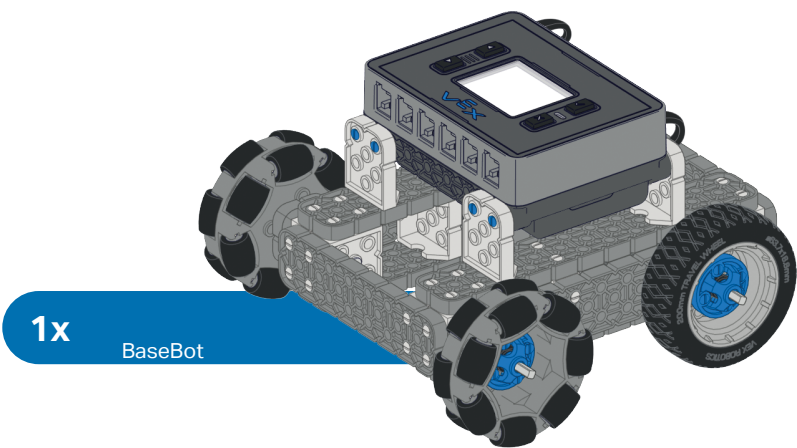
Wind up  
 Dar cuerda  
 Liquider  
 Arrotola  
 Aufziehen  
 Nawiń  
 Opwinden



Rotate  
 Girar  
 Faire tourner  
 Ruotare

Drehen  
 Obróć  
 Draaien





12x

0.25x

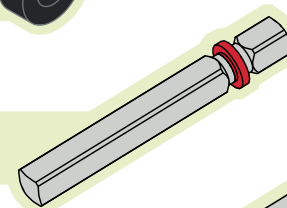
Pitch Shaft Spacer



2x

2

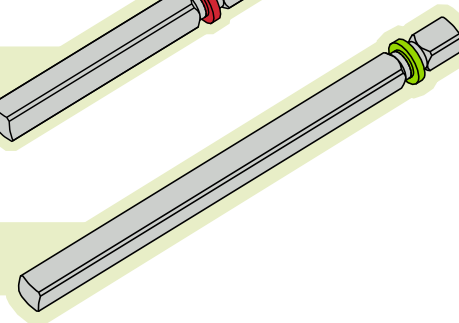
Pitch Motor Shaft



2x

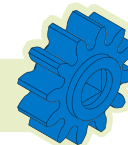
4

Pitch Motor Shaft



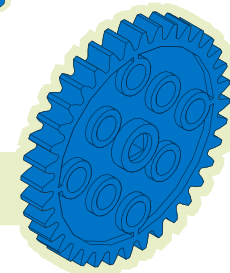
2x

12 Tooth Gear



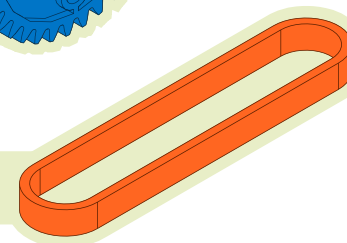
2x

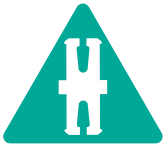
36 Tooth Gear



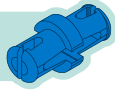
2x

Silicone Rubber Band

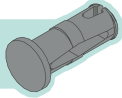




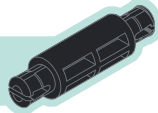
**36x** **1x1**  
Connector Pin



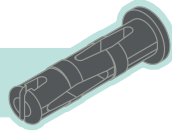
**8x** **0x2**  
Connector Pin



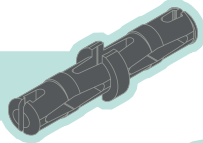
**6x** **1x**  
Pitch Standoff



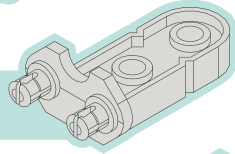
**8x** **0x3**  
Connector Pin



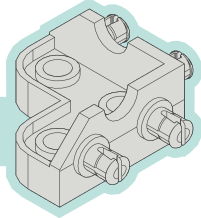
**1x** **2x2**  
Connector Pin



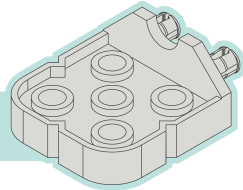
**1x** 2x Wide, 2x1 Offset  
Corner Connector



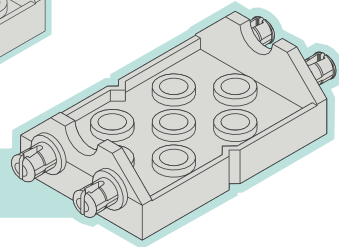
**2x** Large Chassis  
Corner Connector



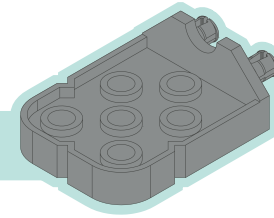
**4x** 2x Wide, 2x2  
Corner Connector



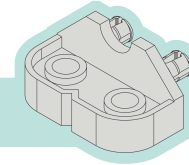
**2x** Double 2x Wide, 2x2 Double  
Offset Corner Connector



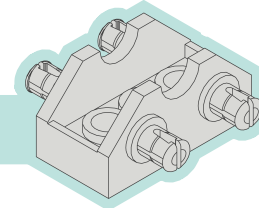
**4x** 2x Wide, 2x2 Offset  
Corner Connector

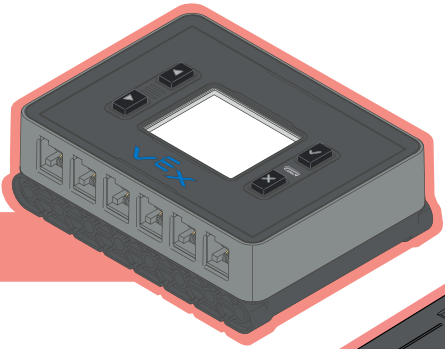


**2x** 2x Wide, 1x2  
Corner Connector

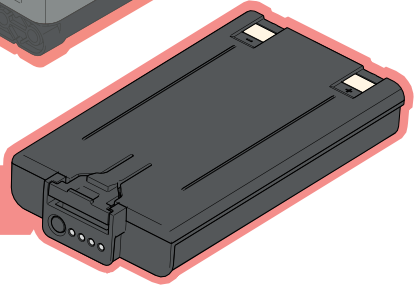


**1x** Double 2x Wide, 1x2  
Corner Connector

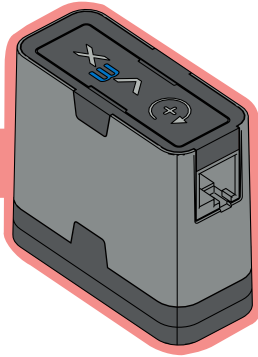




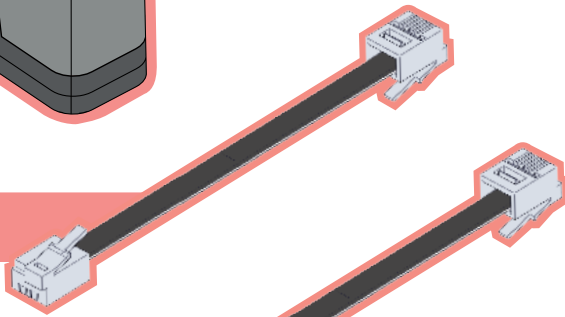
**1x** Robot Brain



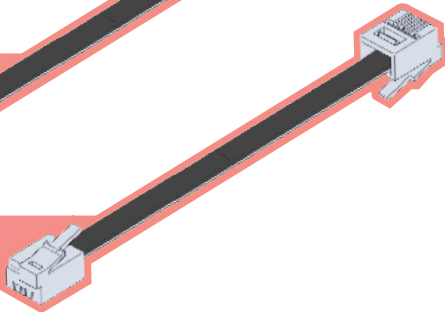
**1x** Robot Battery



**1x** Smart Motor



**3x** **200mm** Smart Cable



**1x** **600mm** Smart Cable



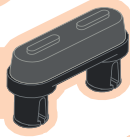
4x

1x1  
Beam



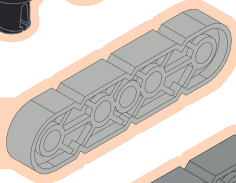
2x

Traction Link



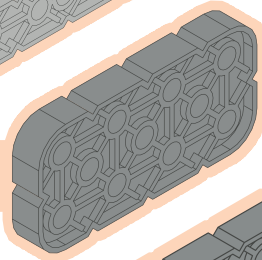
4x

1x4  
Beam



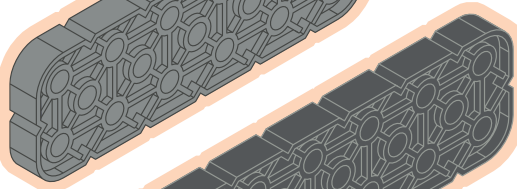
1x

2x4  
Beam



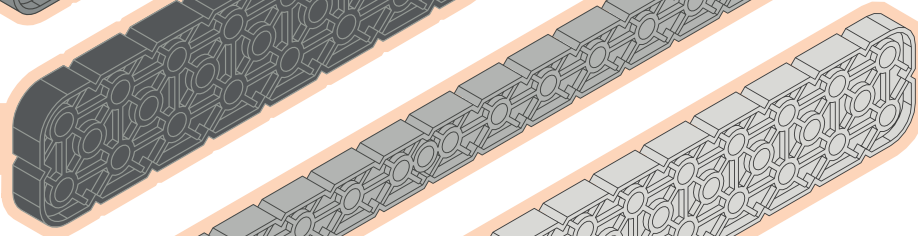
2x

2x6  
Beam



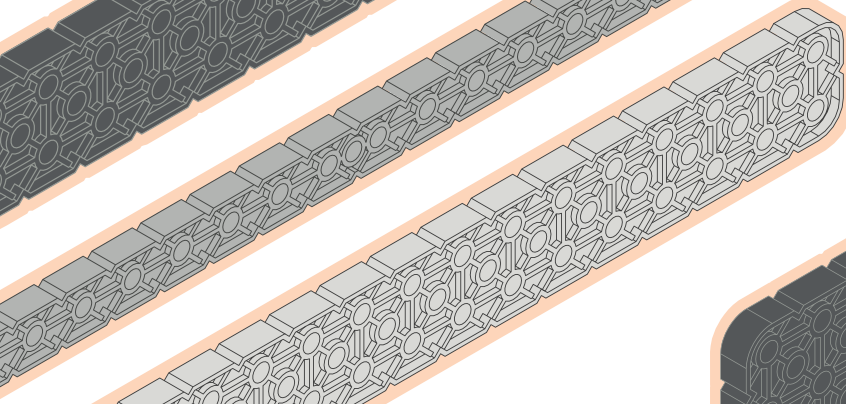
2x

2x8  
Beam



4x

1x16  
Beam



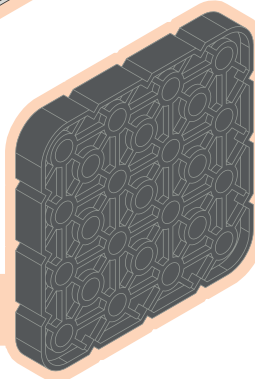
2x

2x16  
Beam



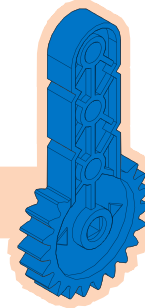
2x

4x4  
Plate



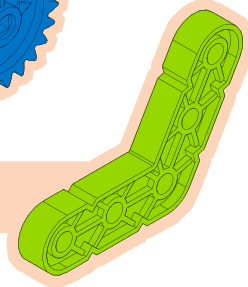
2x

1x4  
Crank Arm with 23 Tooth Gear

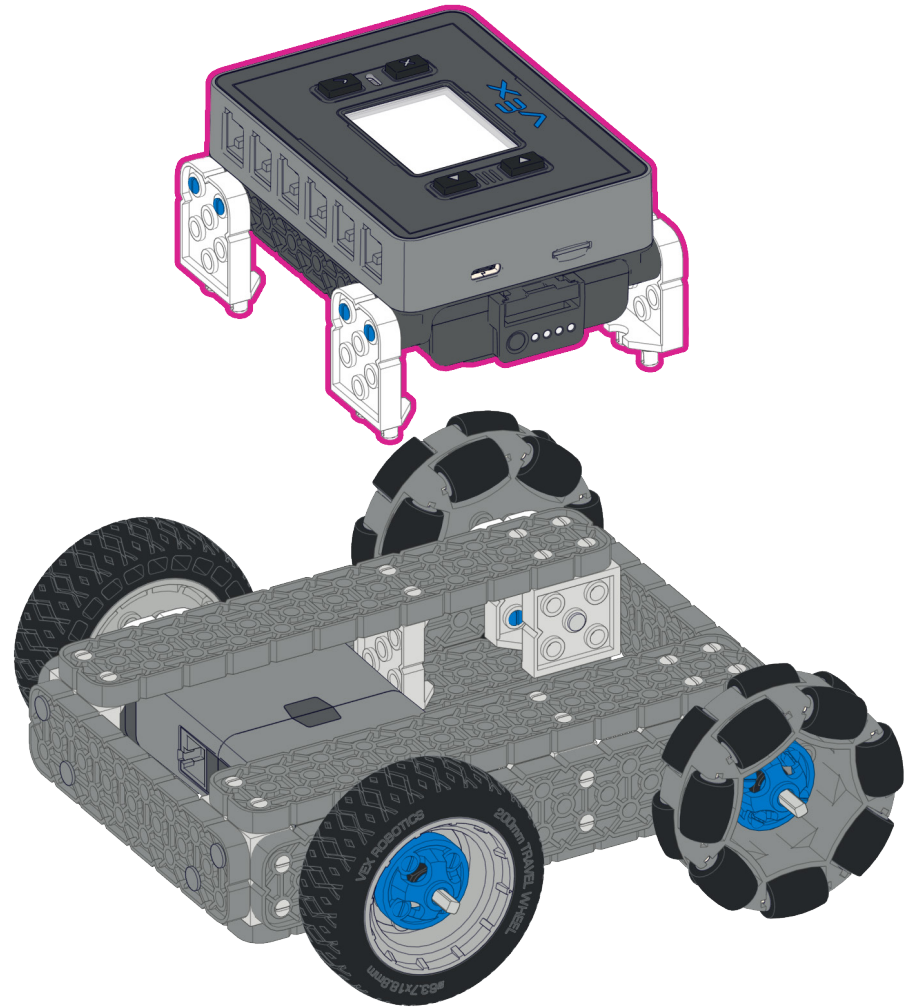
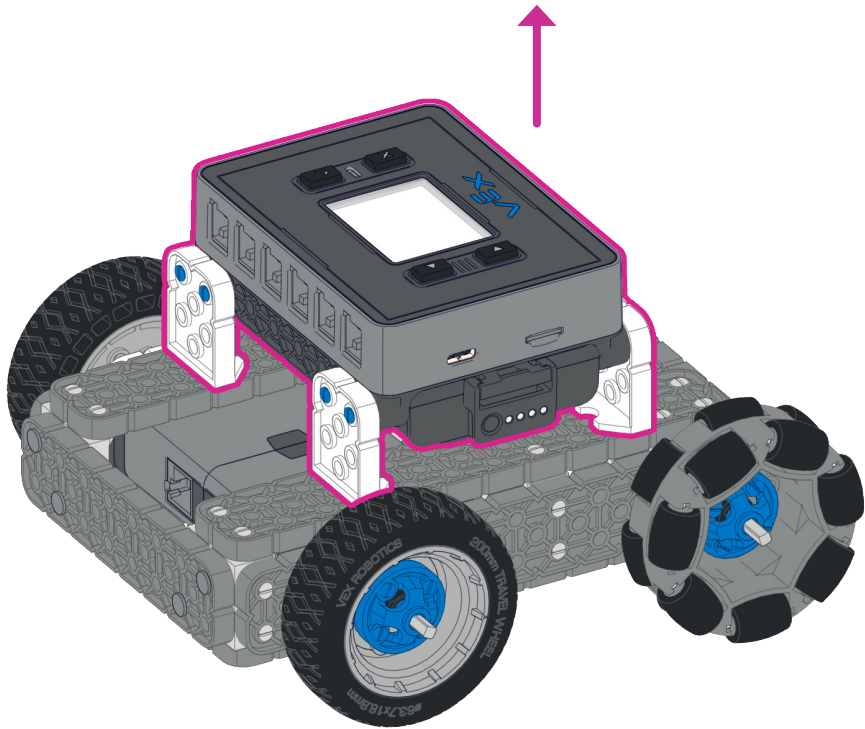


2x

3x3  
60° Angle Beam

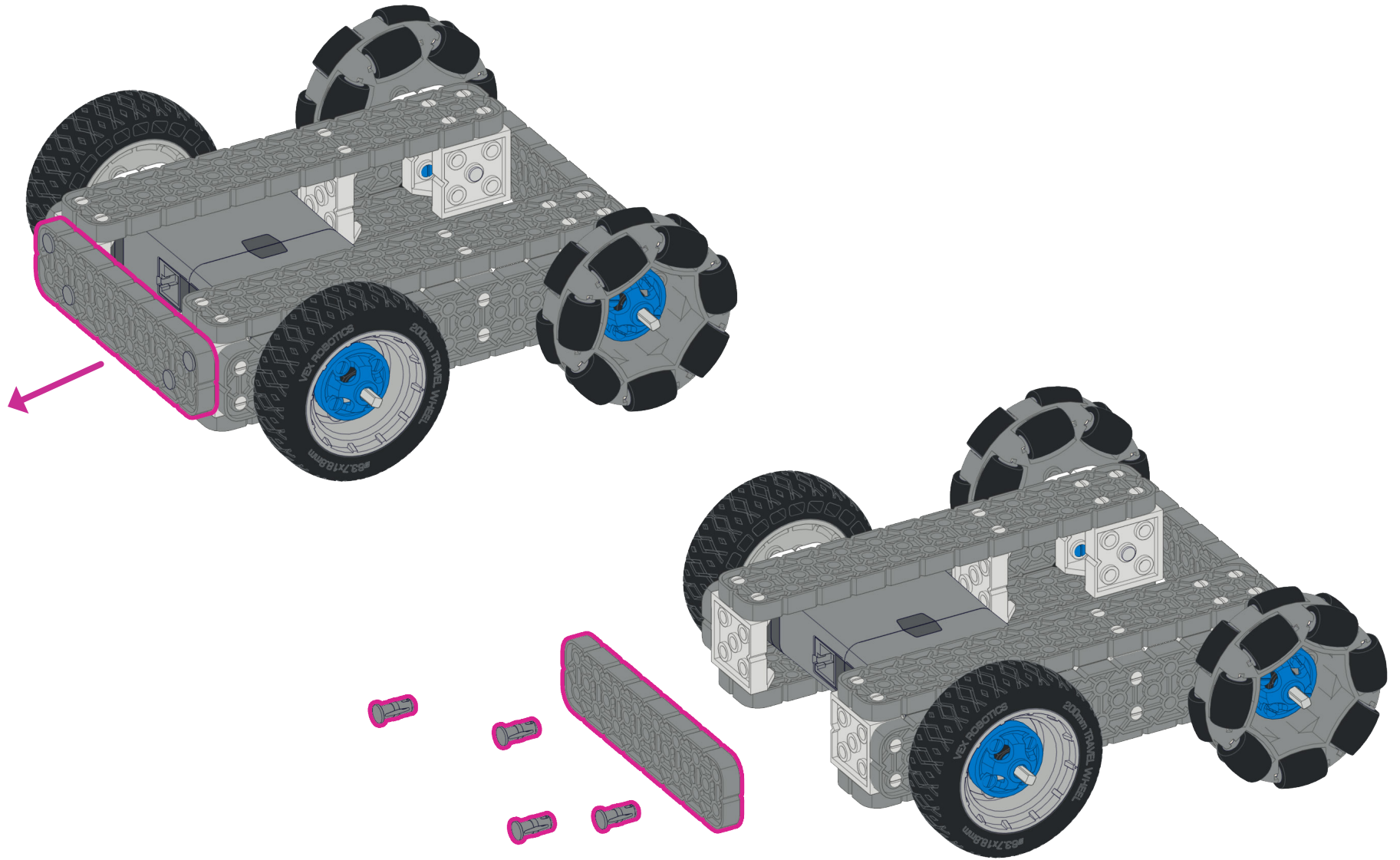


1

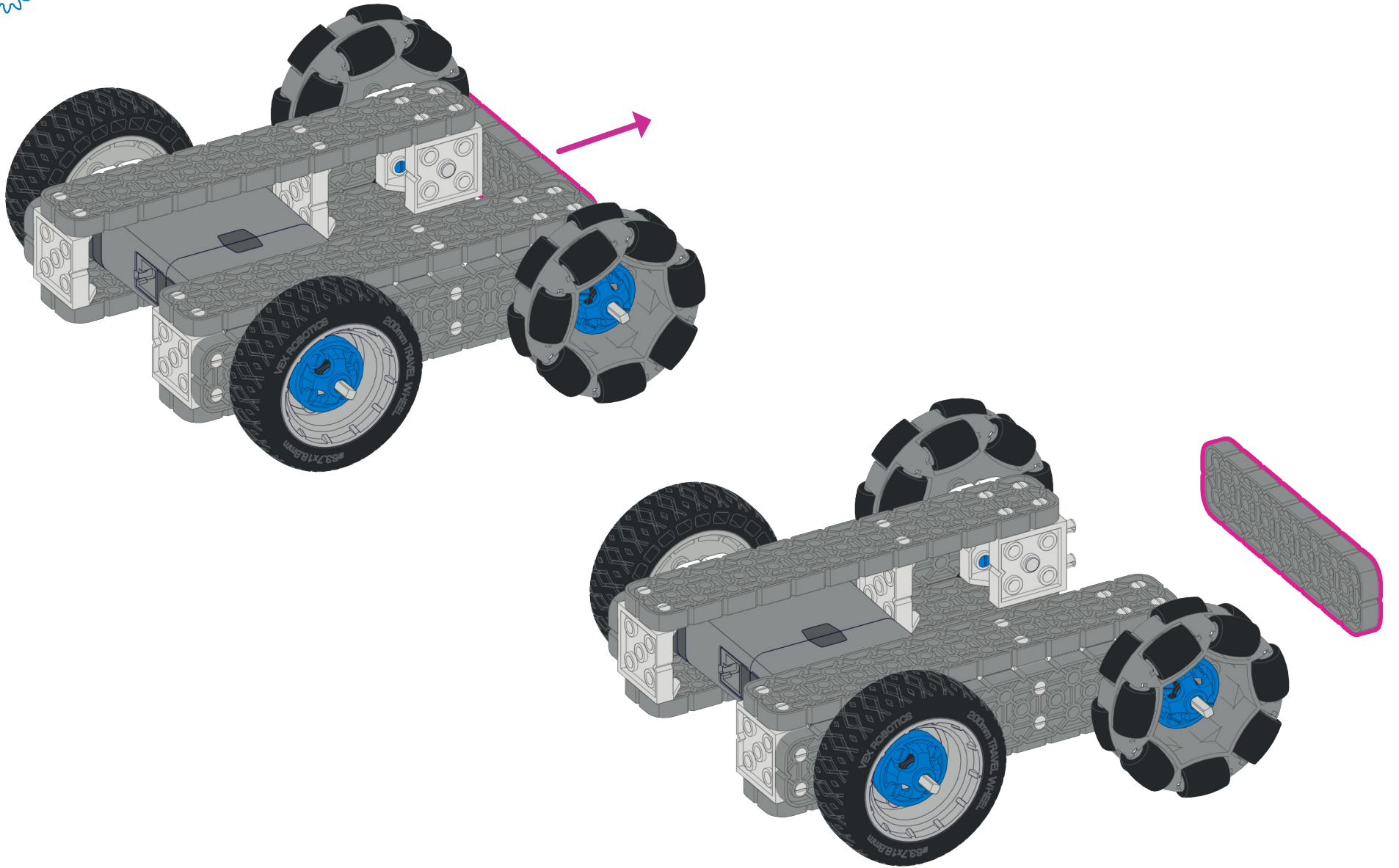




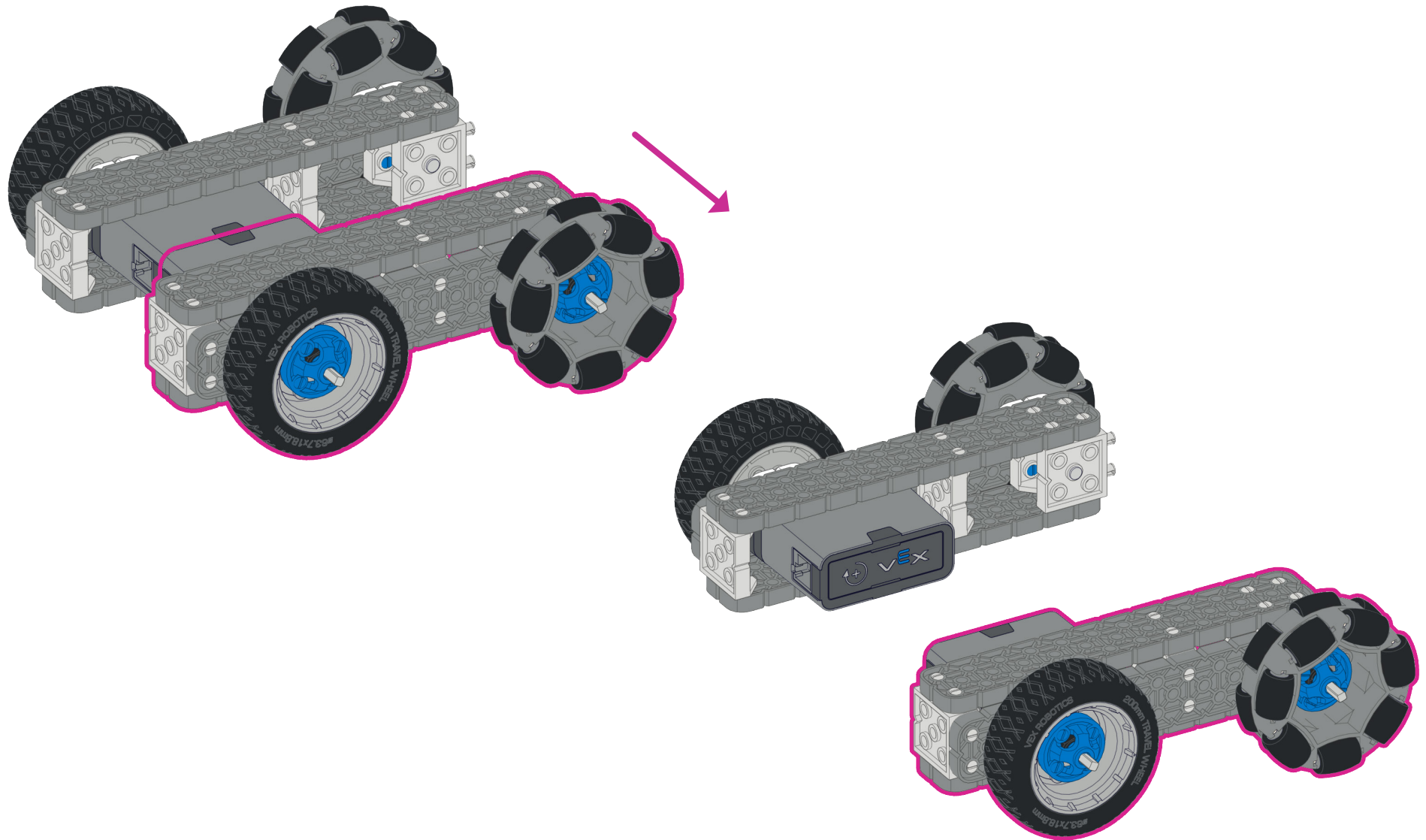
2



3

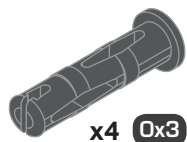


4



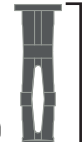
2x16

x1



x4

0x3

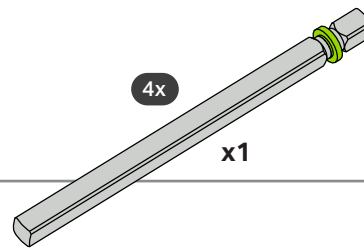


1:1



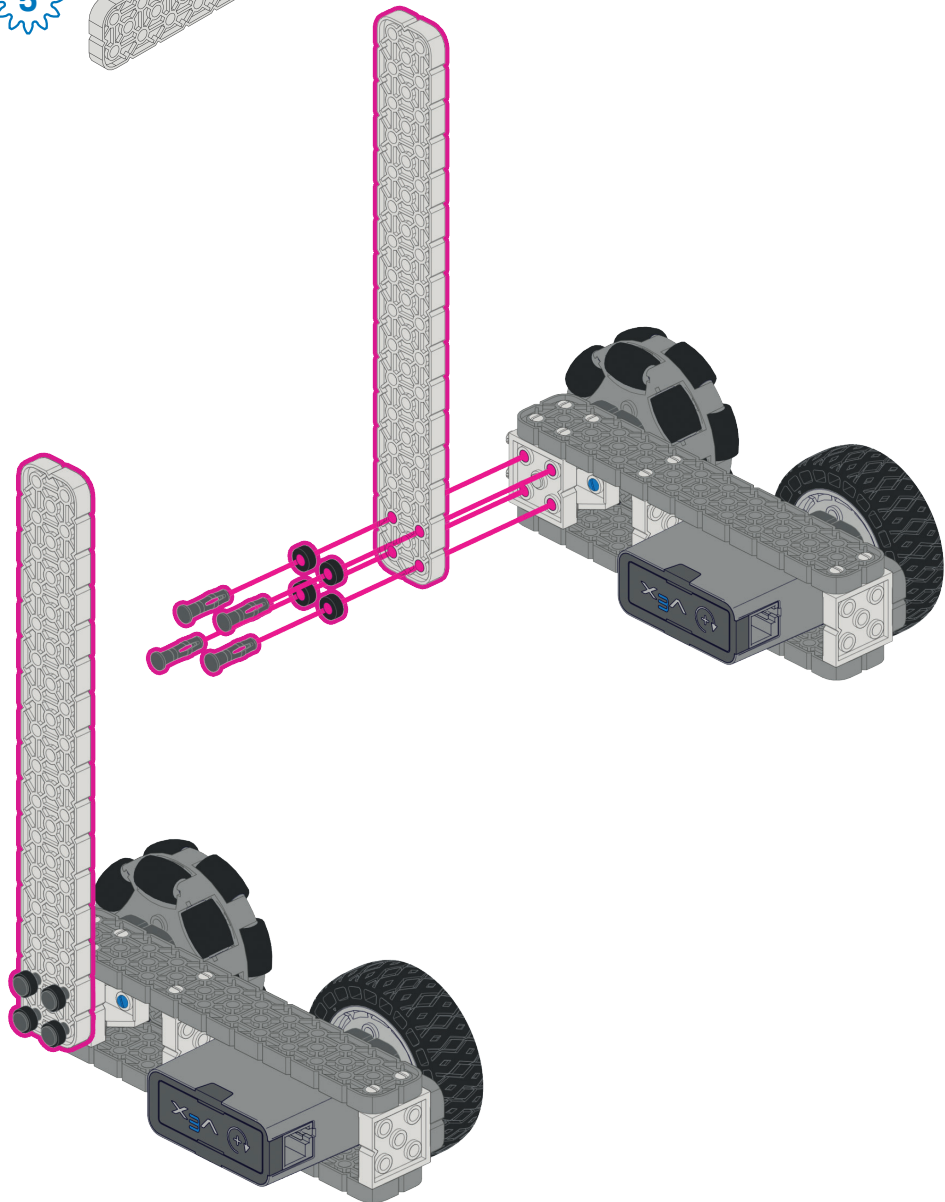
x4

4x

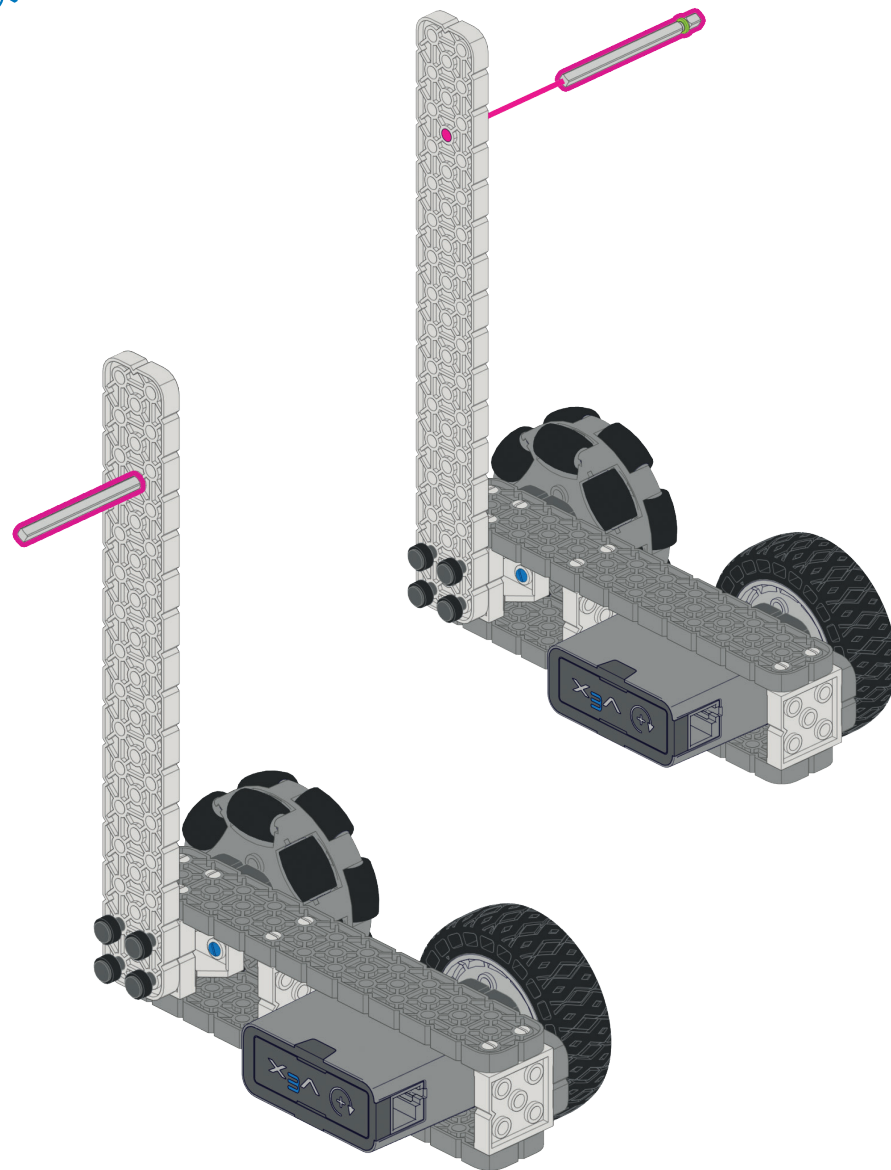


x1

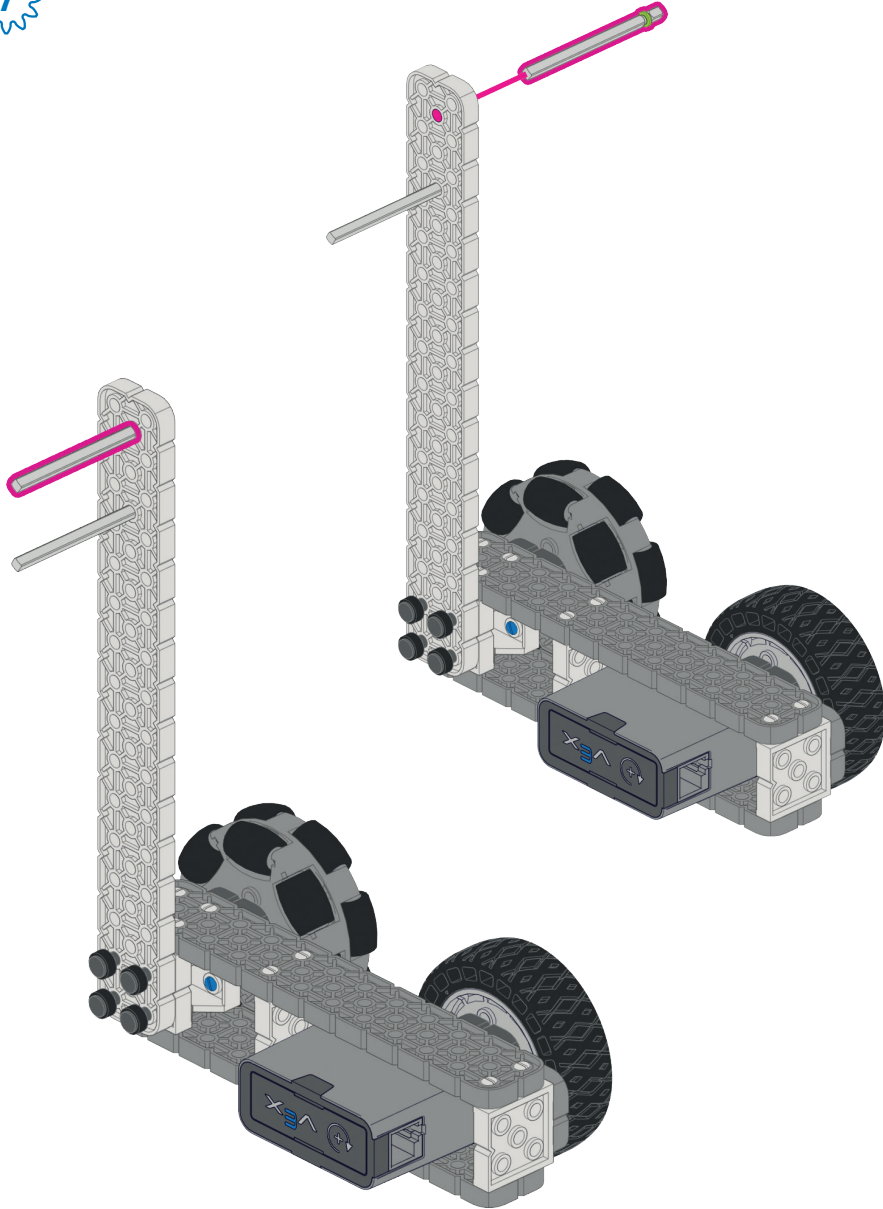
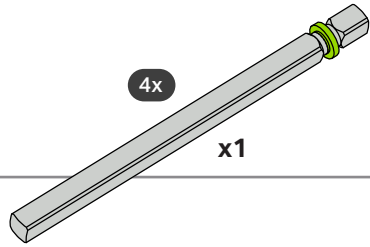
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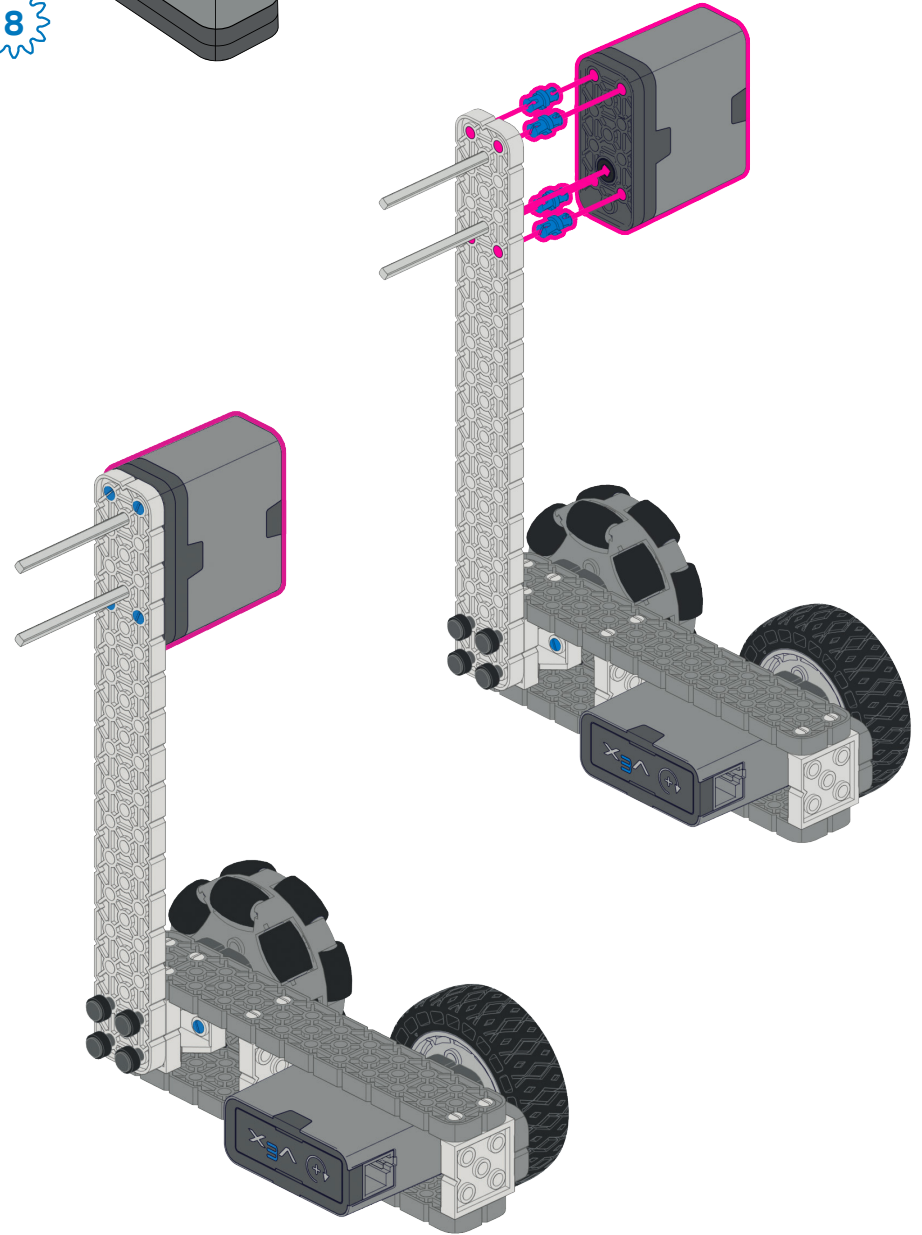
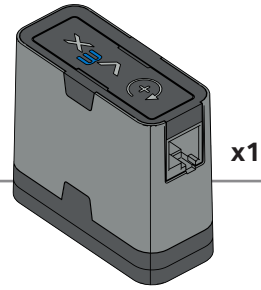
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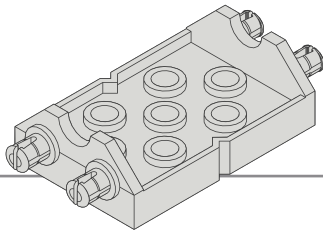


7



8



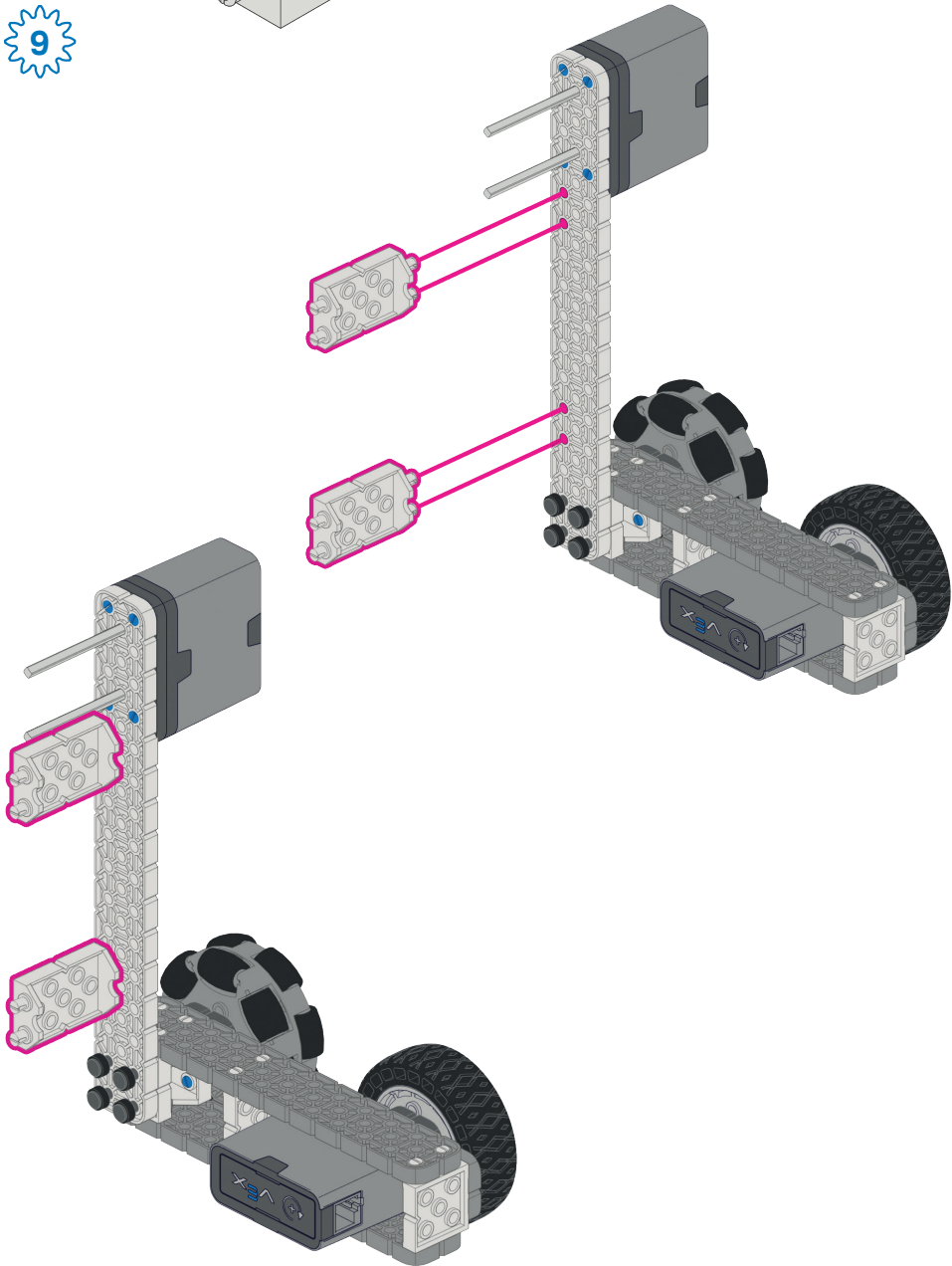


x2

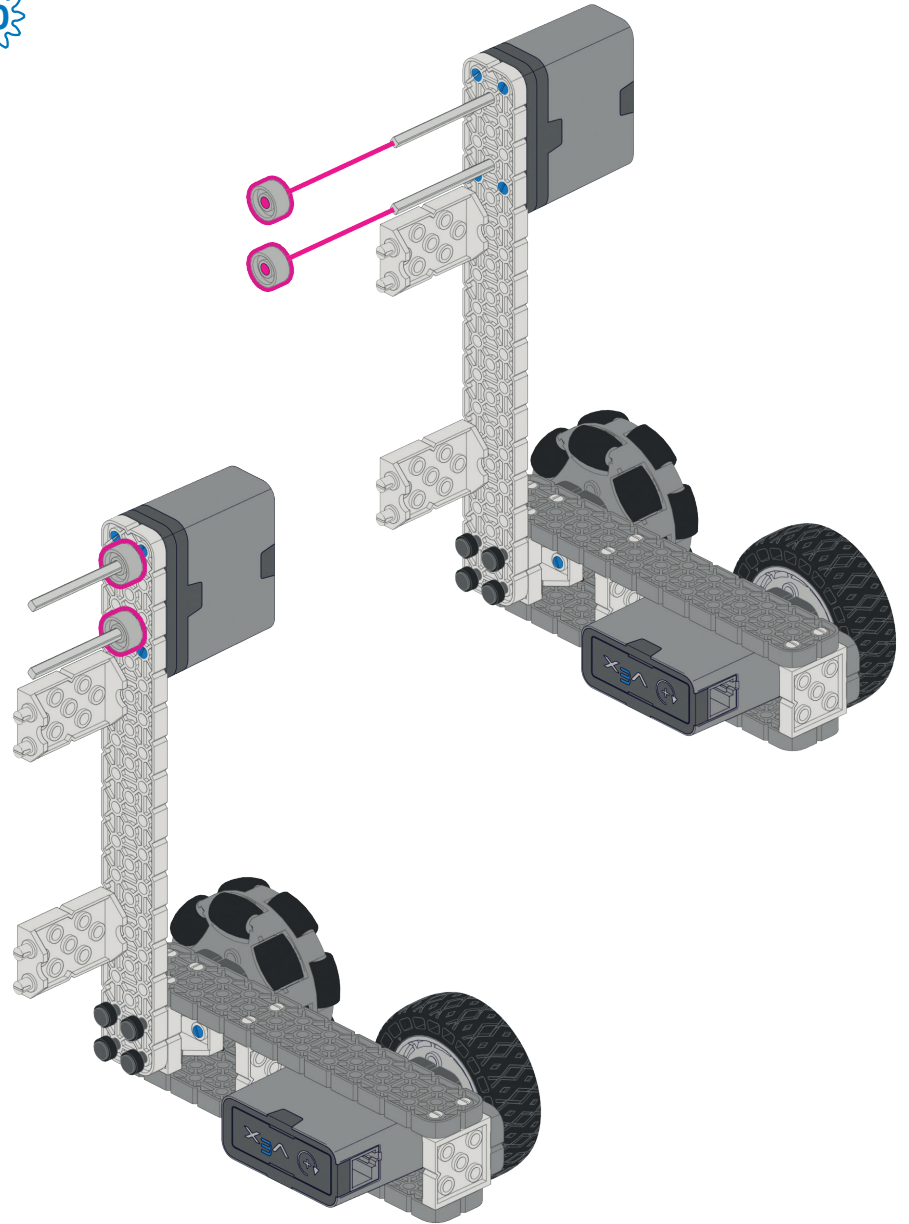


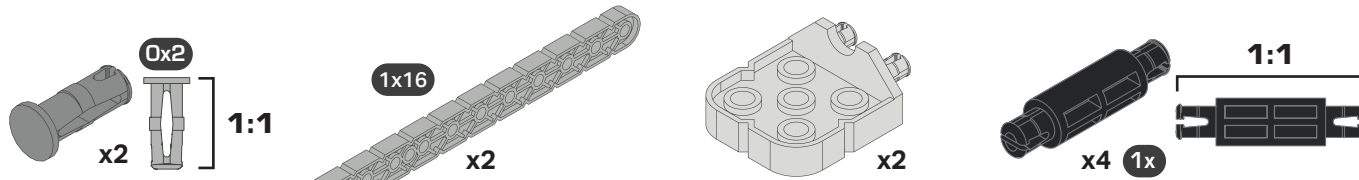
x2

9



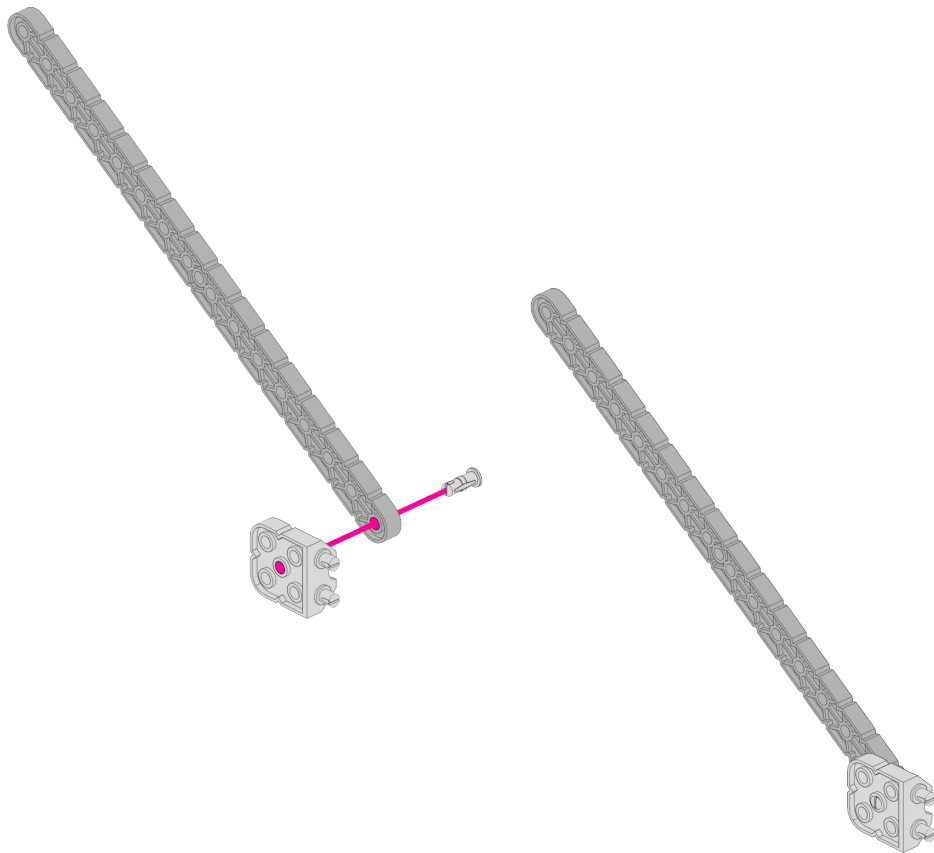
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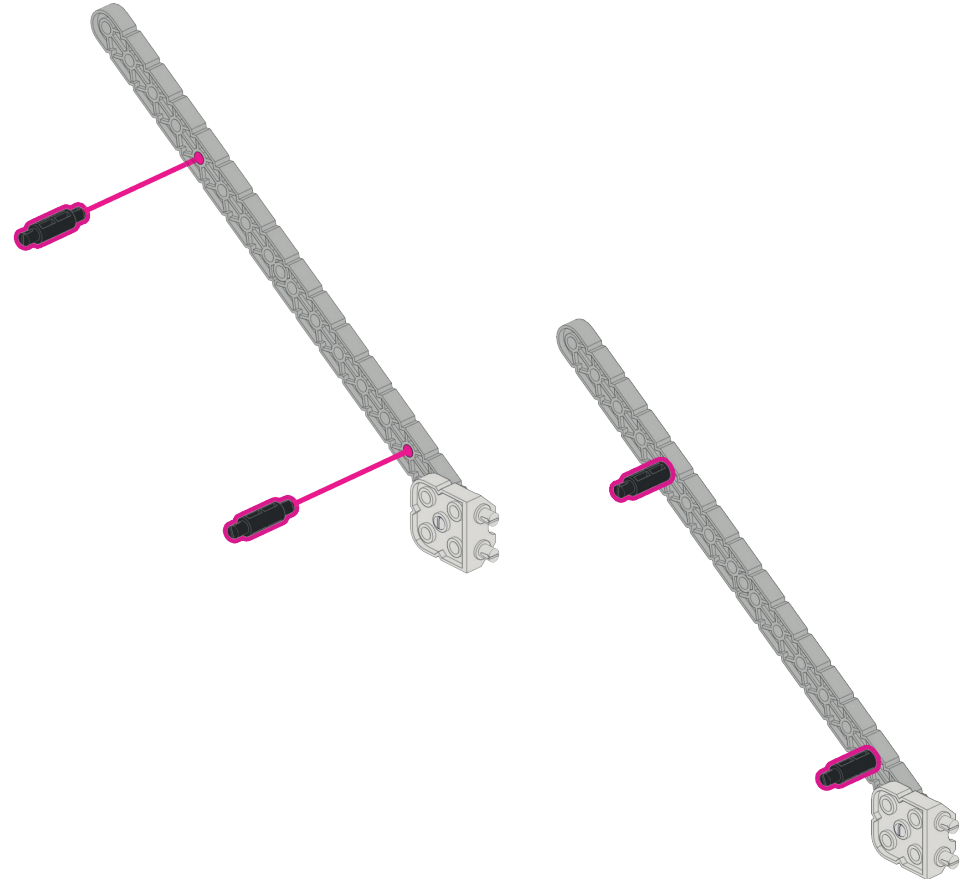
11

2X

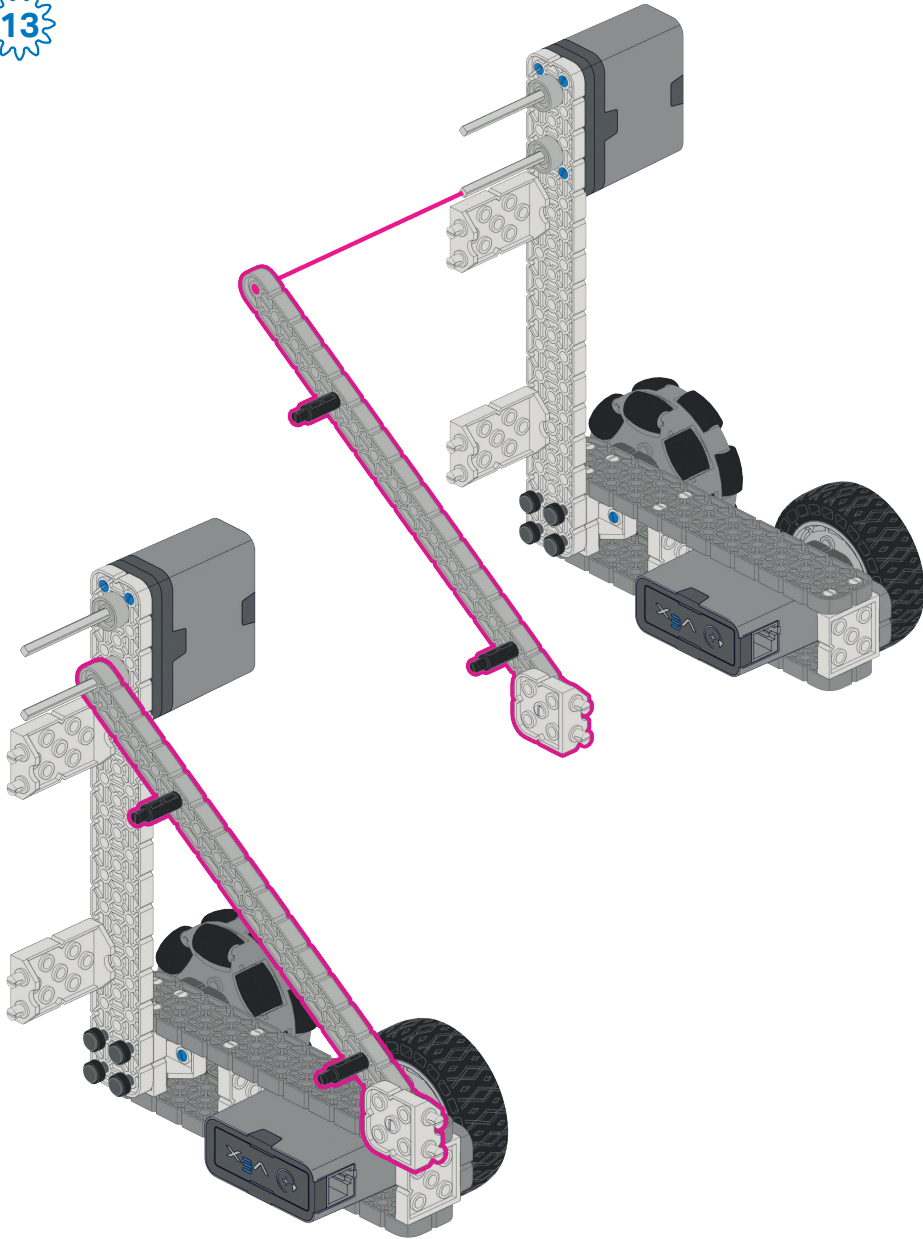


12

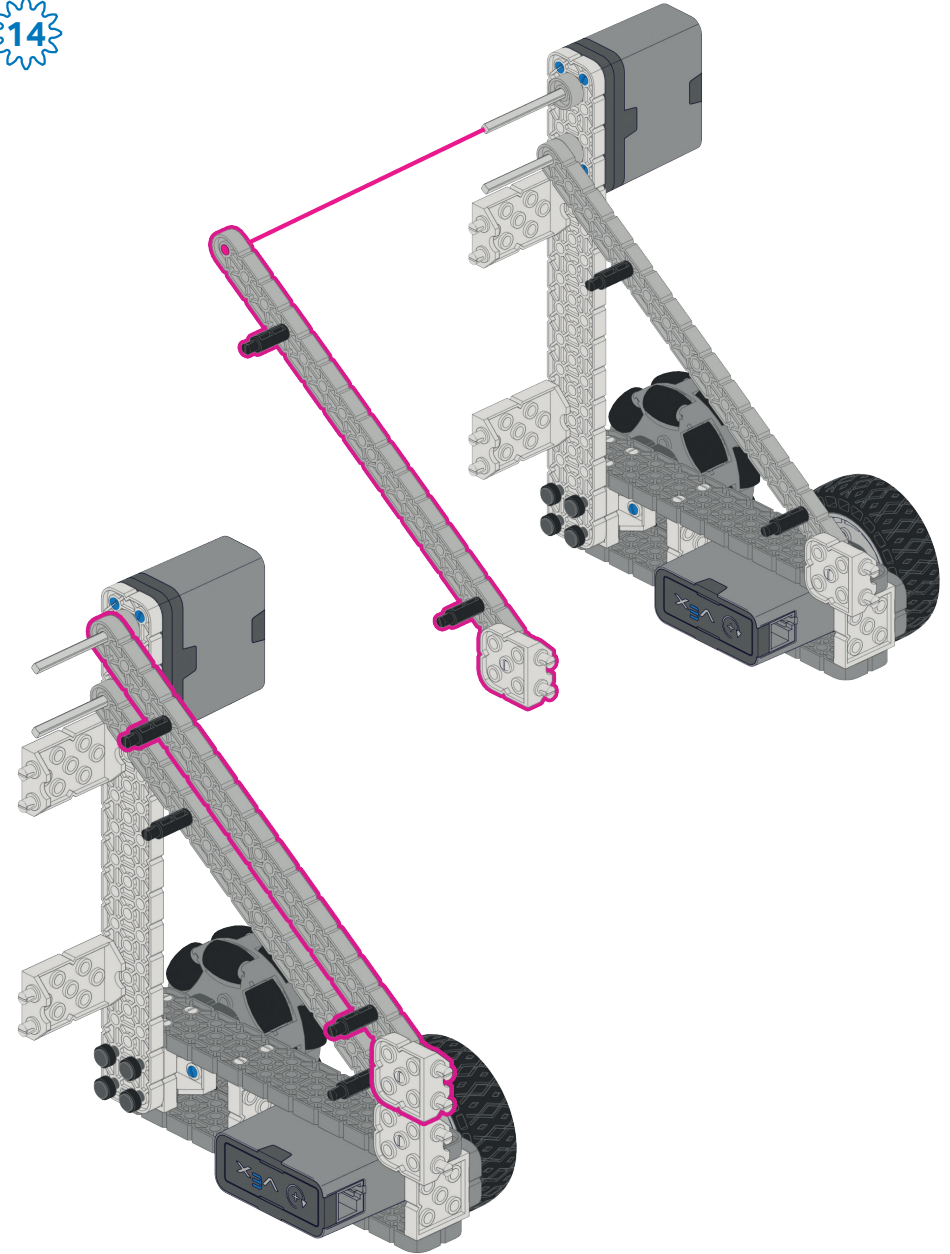
2X



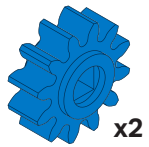
13



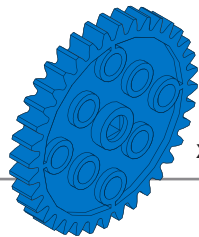
14



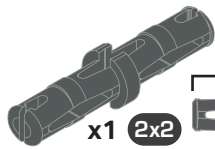




x2



x2



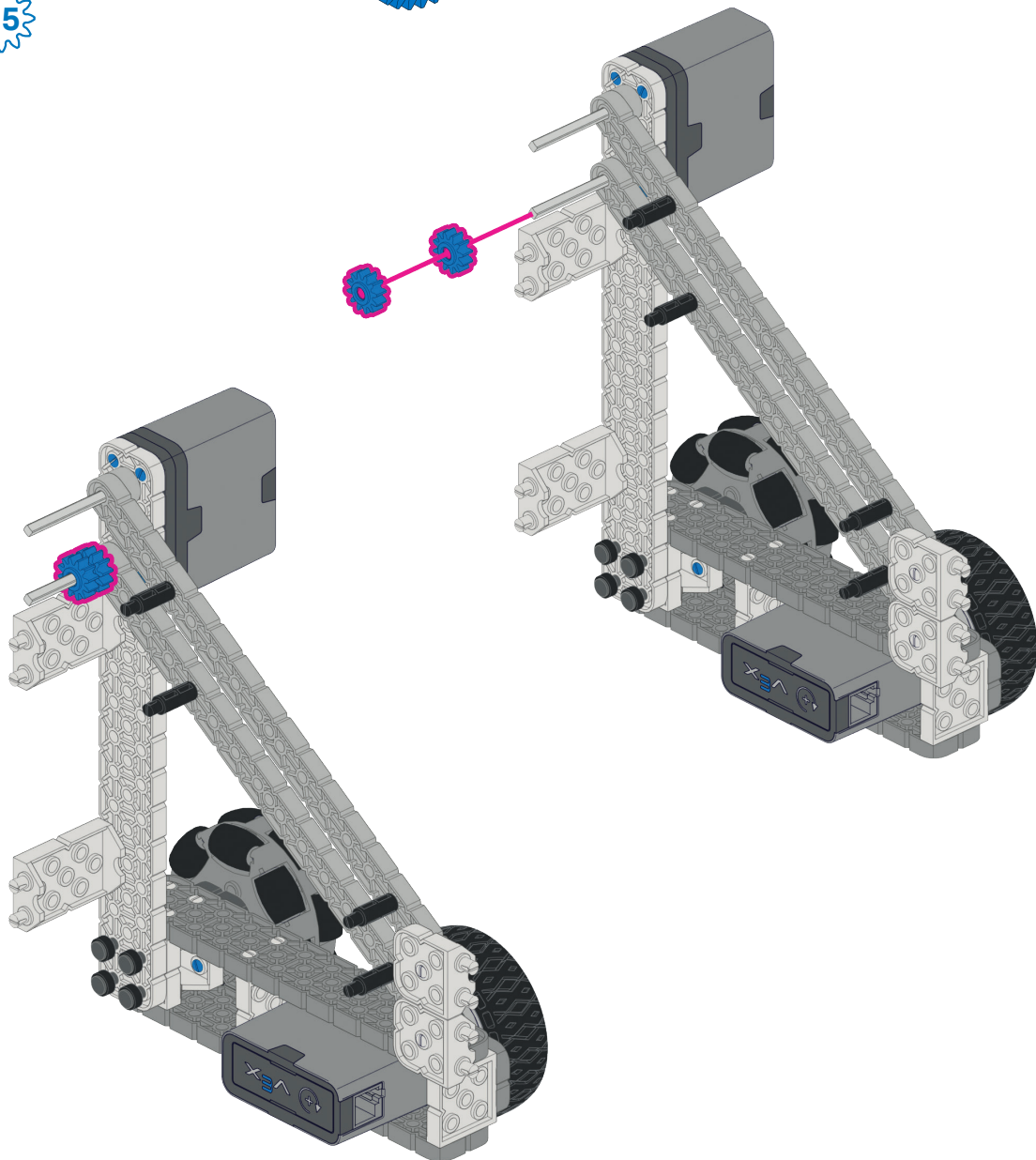
x1

2x2

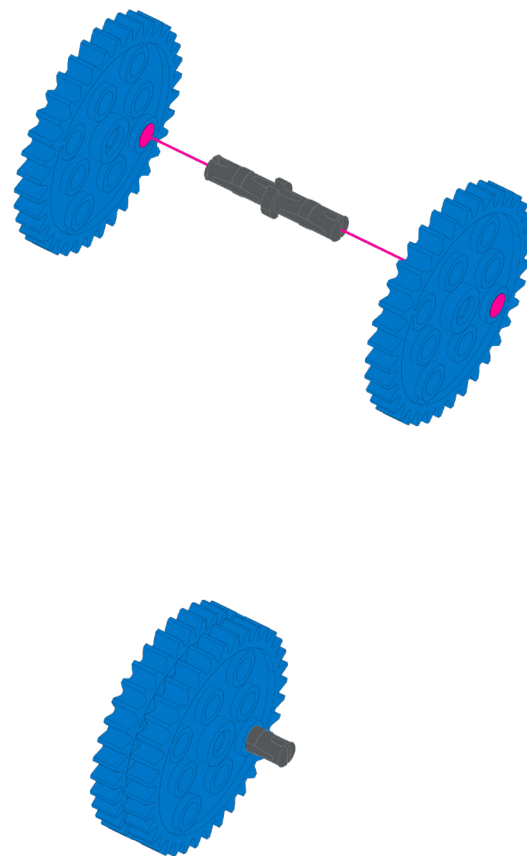


1:1

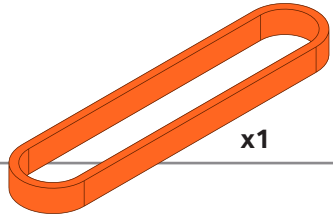
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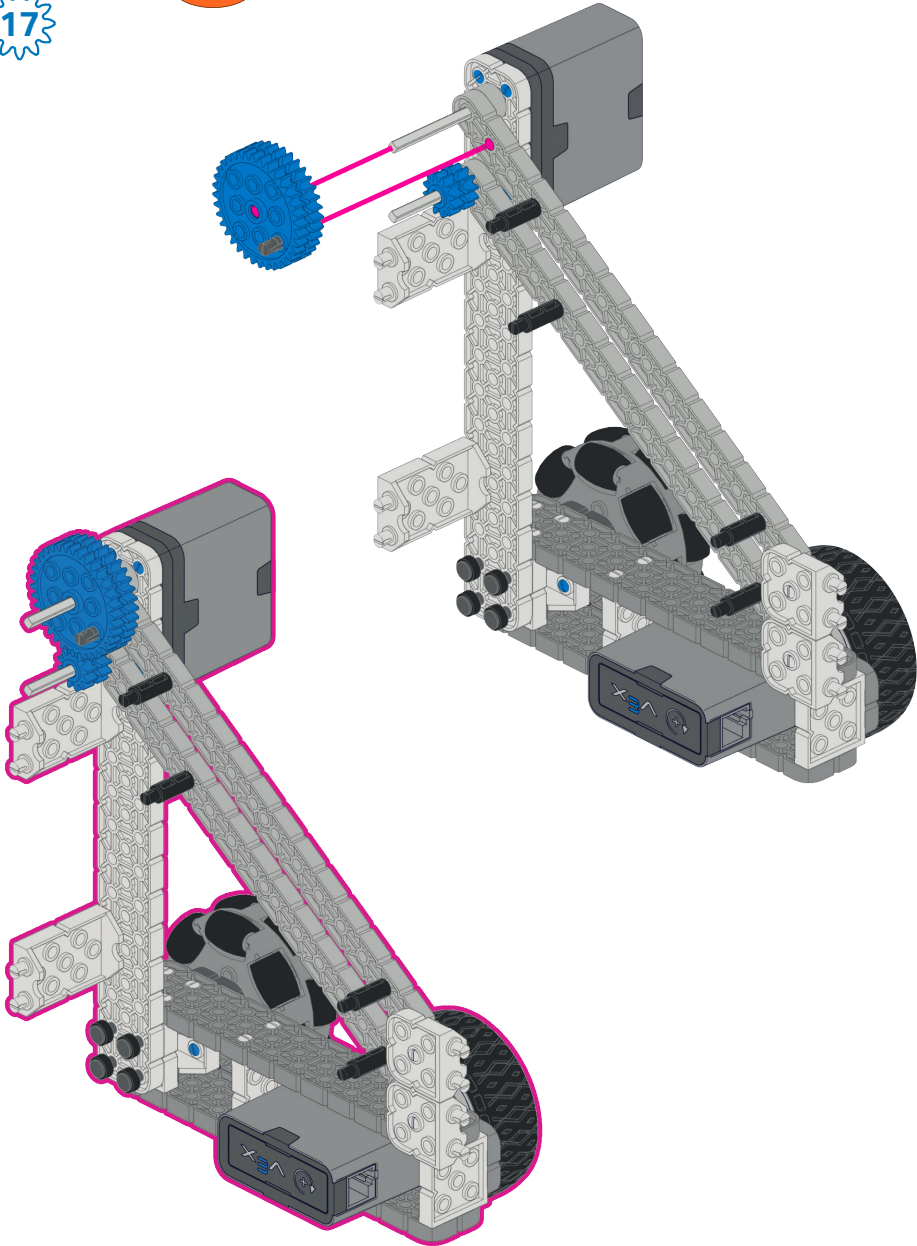
16



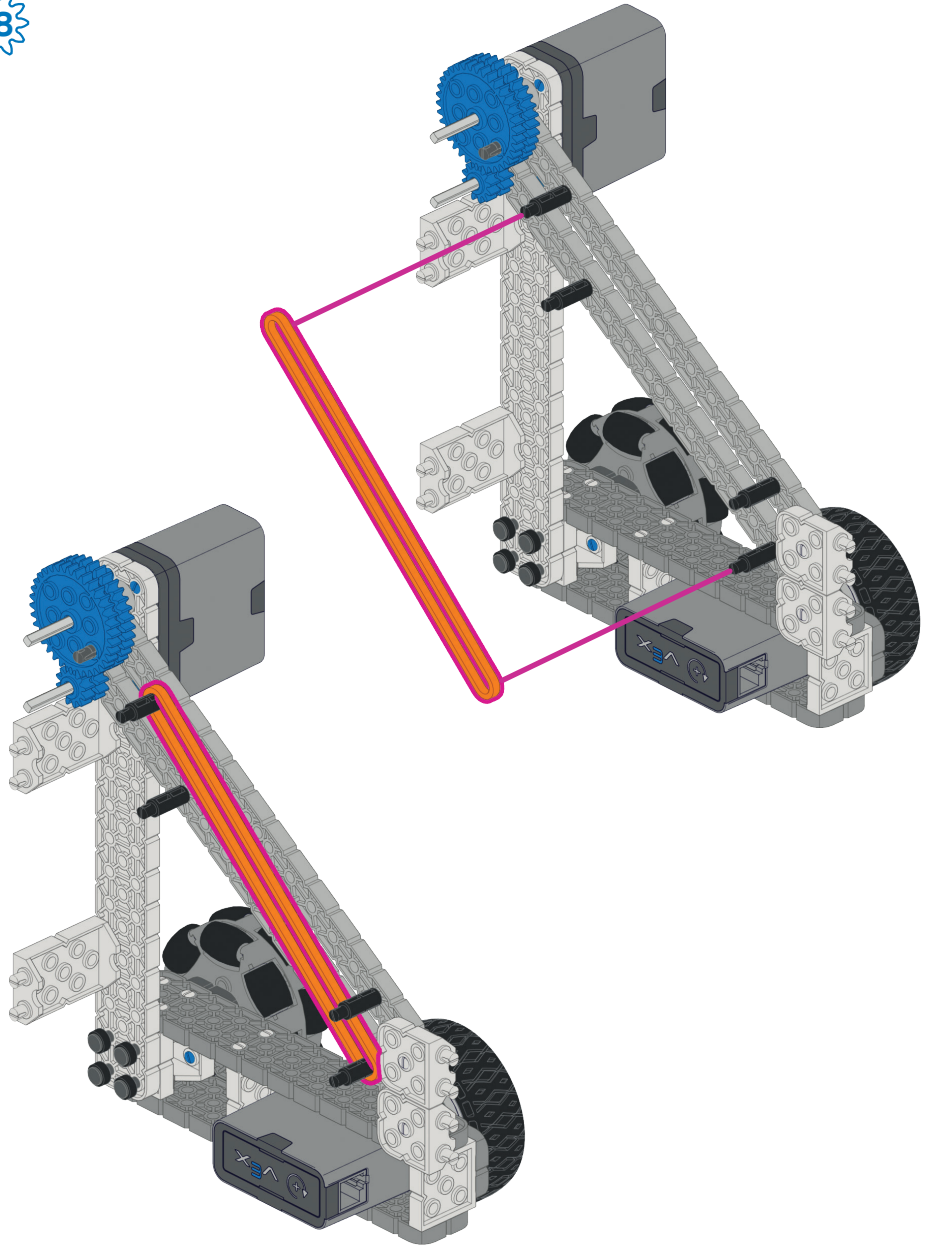
17



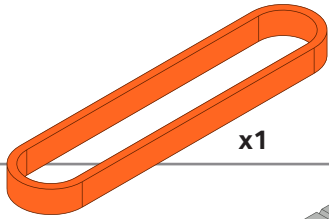
x1



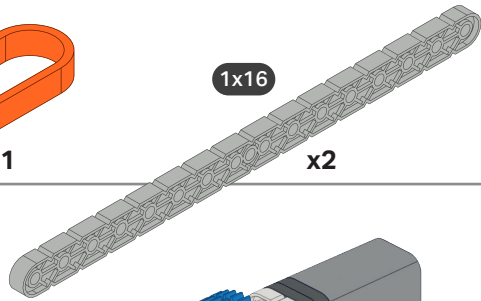
18



19

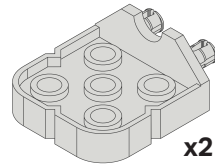


x1

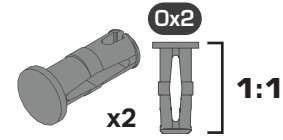


1x16

x2



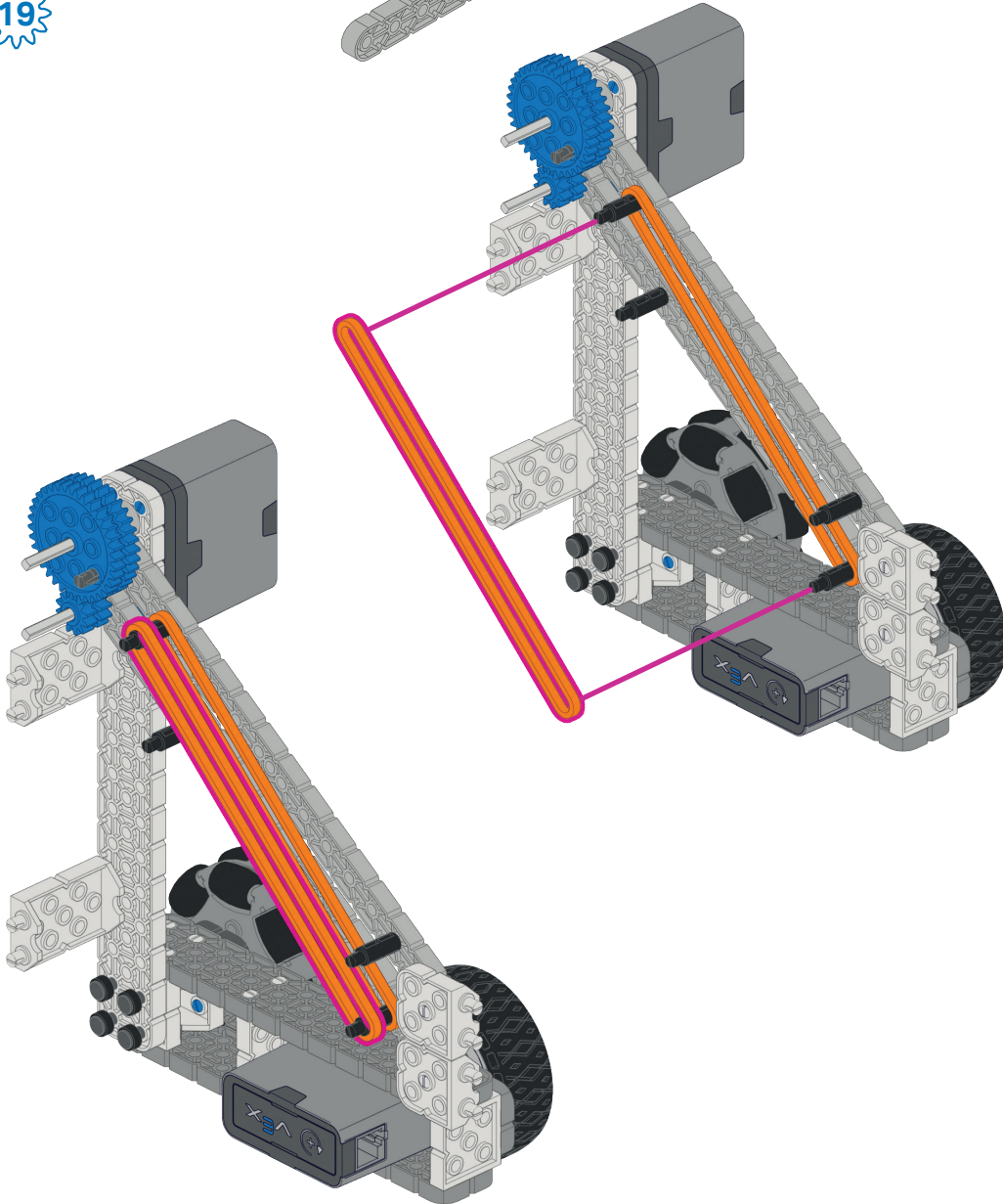
x2



x2

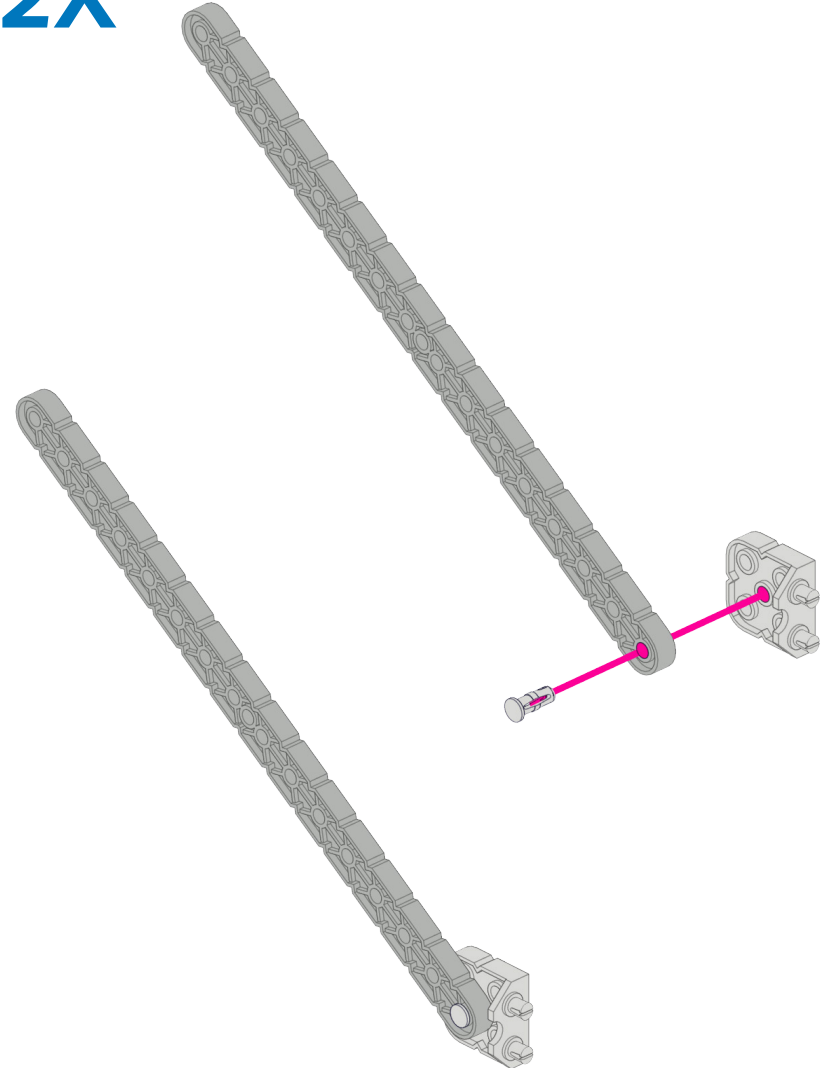
0x2

1:1

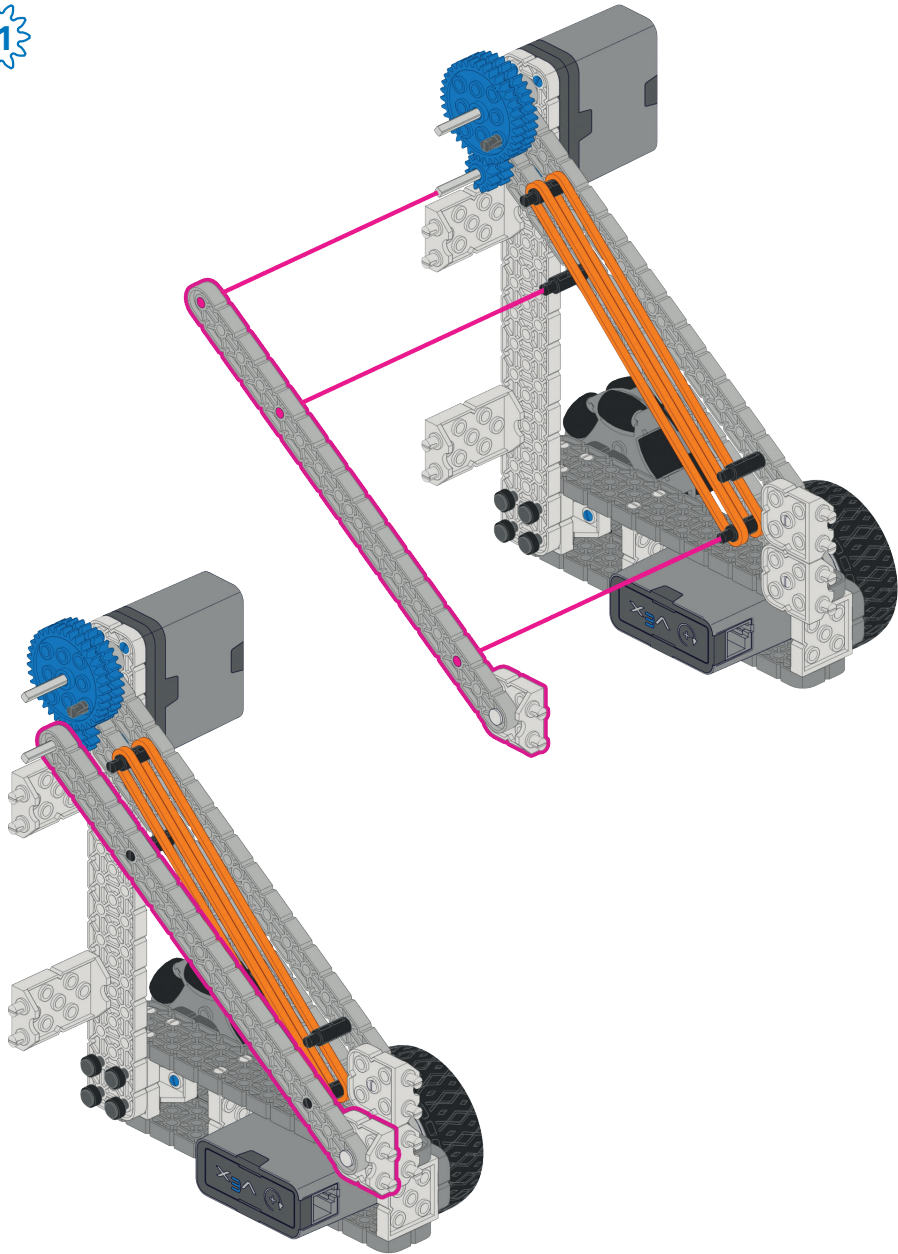


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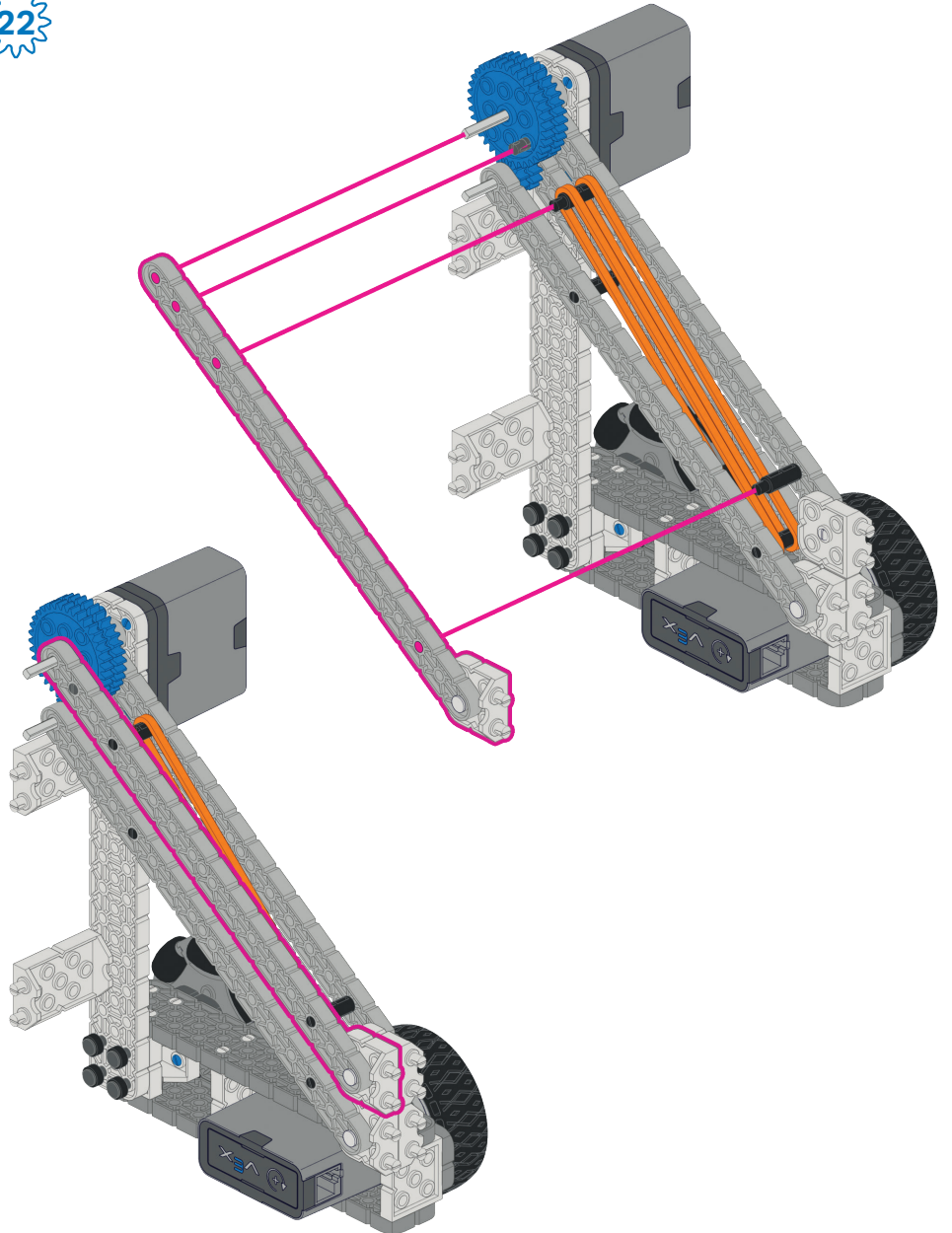
2X



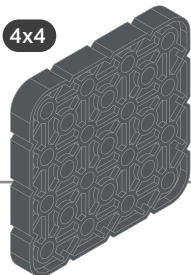
21



22

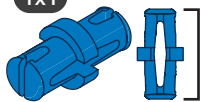


4x4

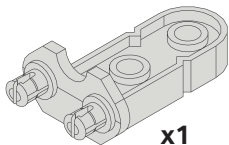


x1

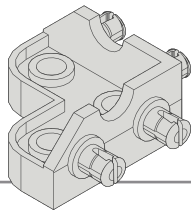
x2  
1x1



1:1

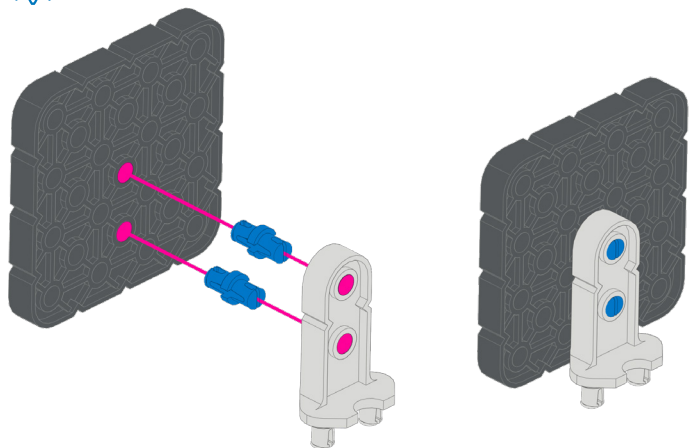


x1

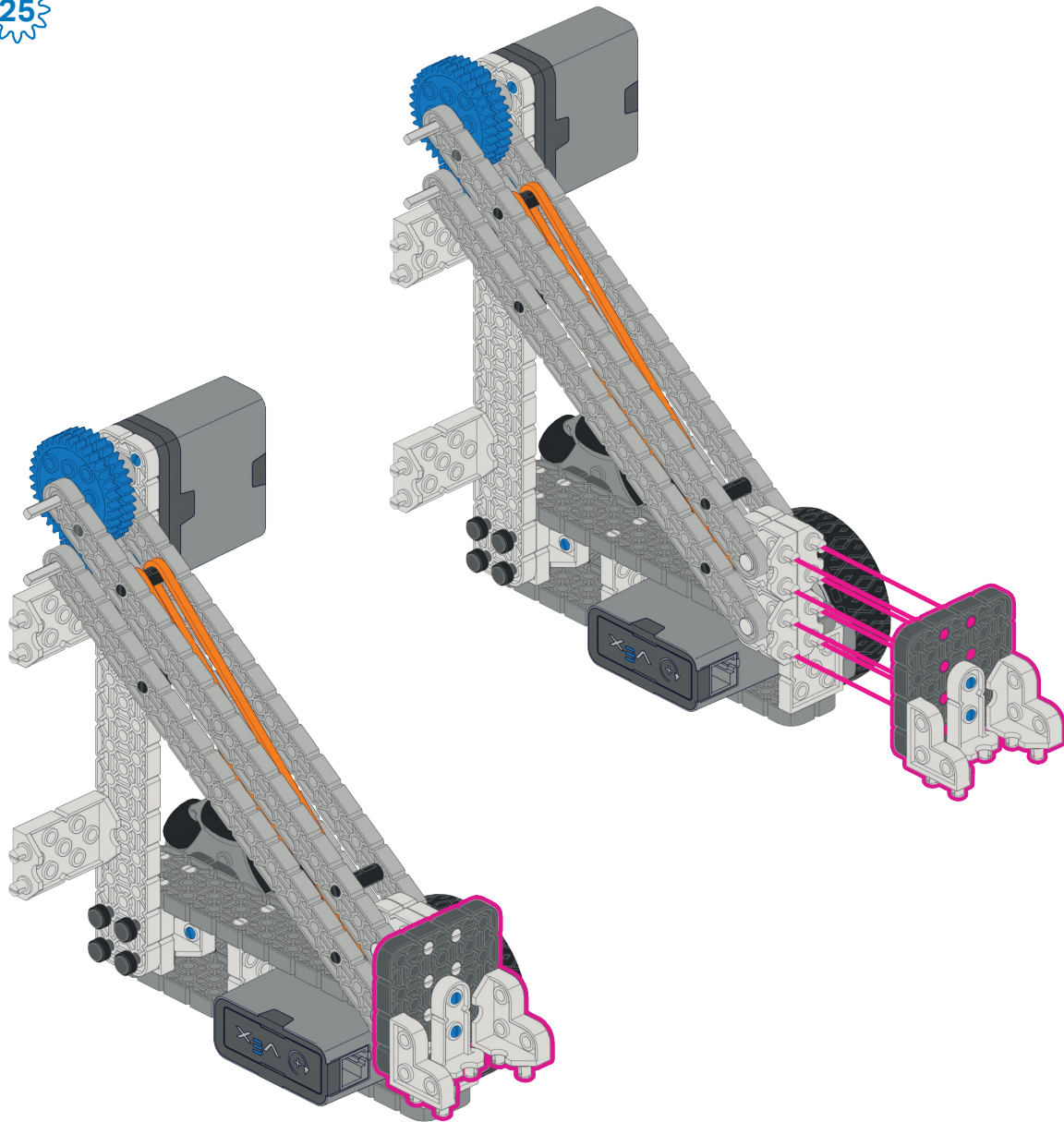


x2

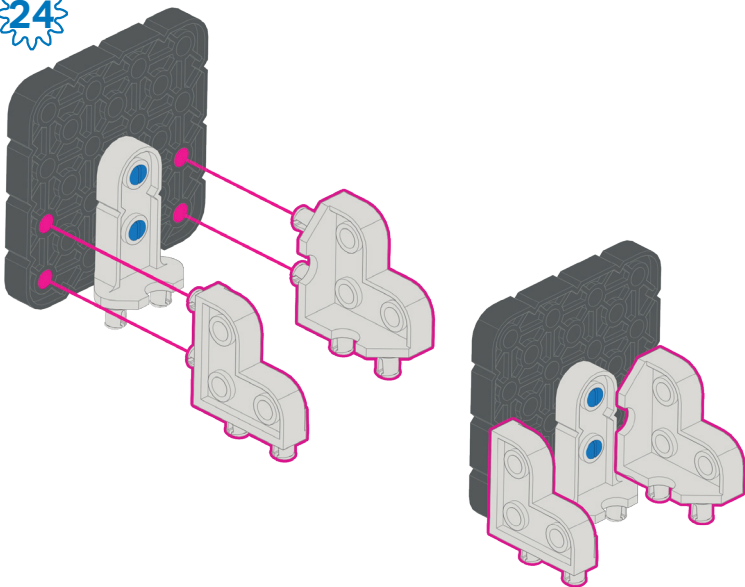
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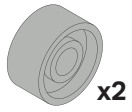


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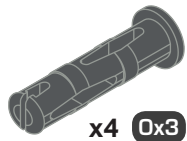


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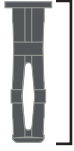


x2



x4

Øx3



1:1

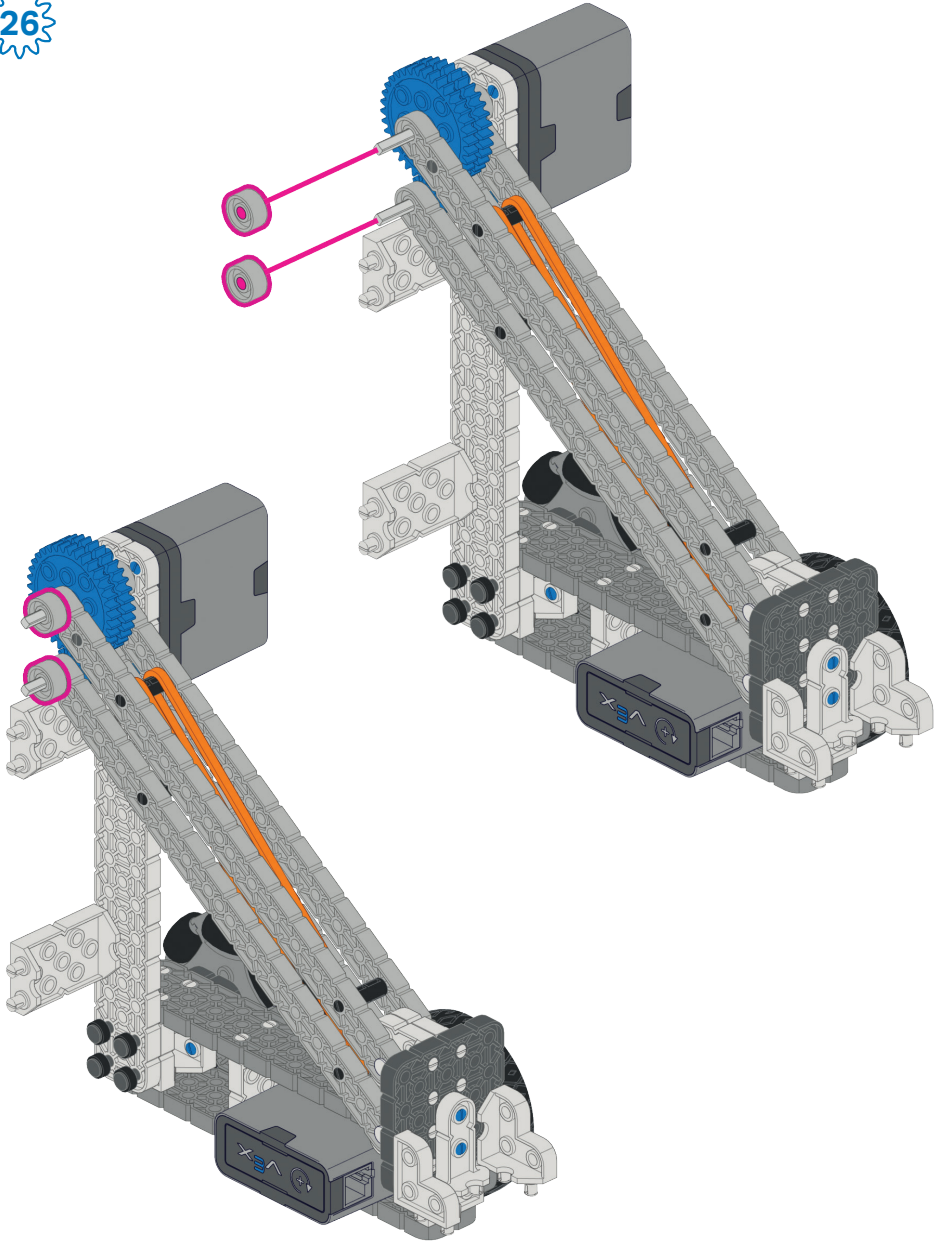


x4

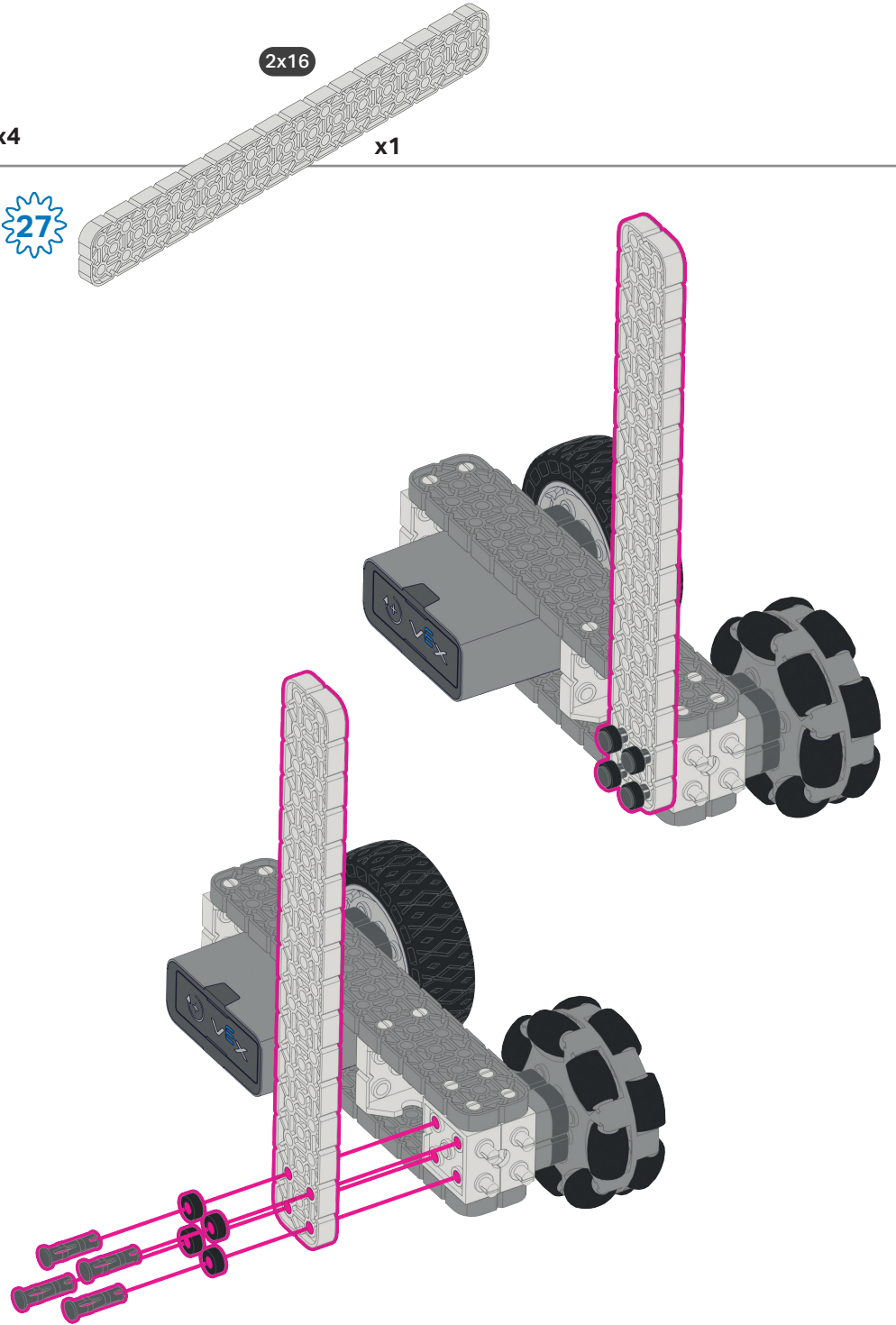
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x1

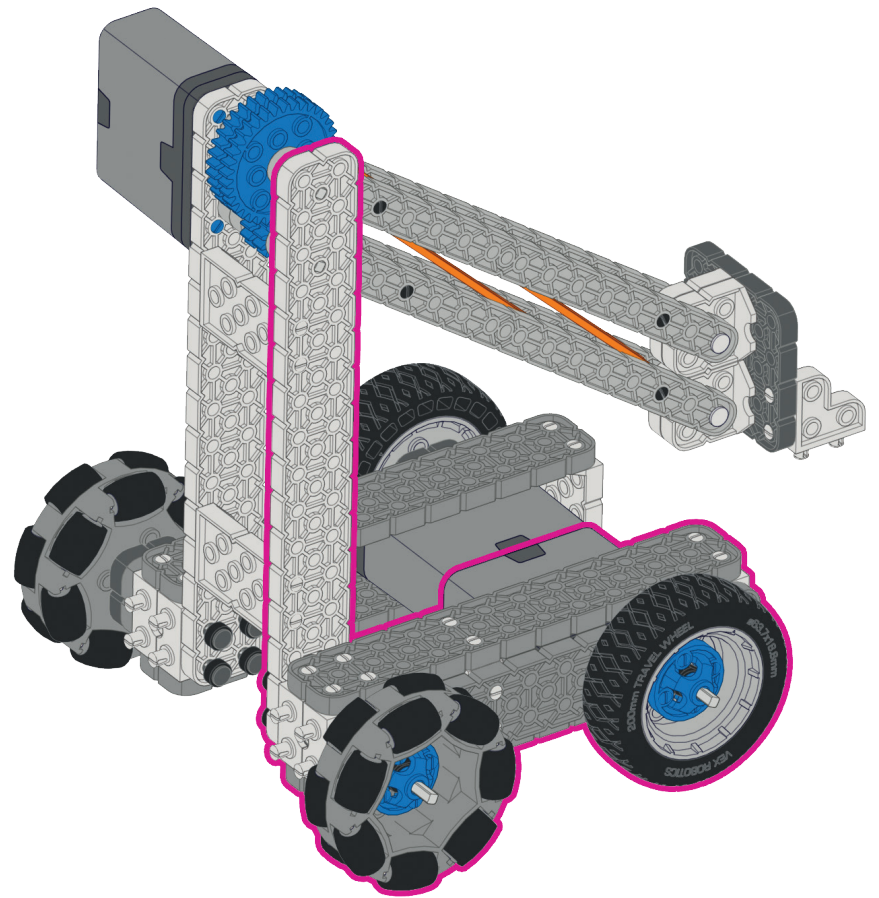
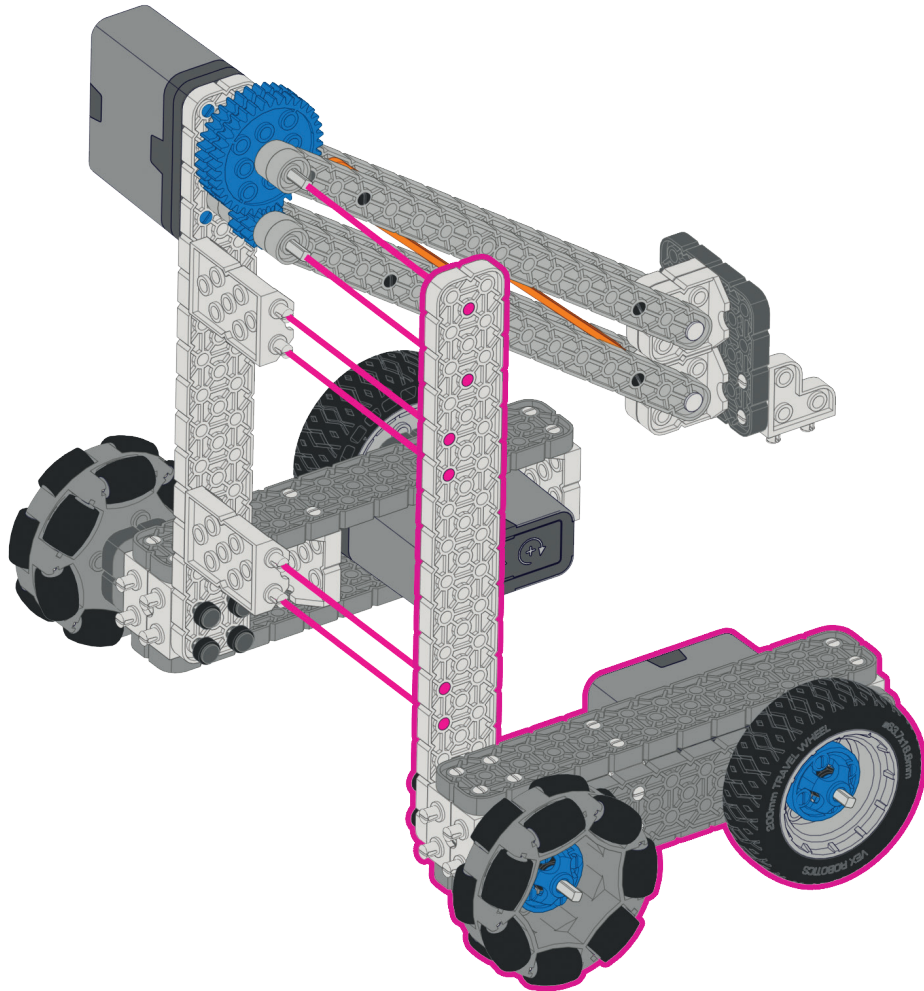
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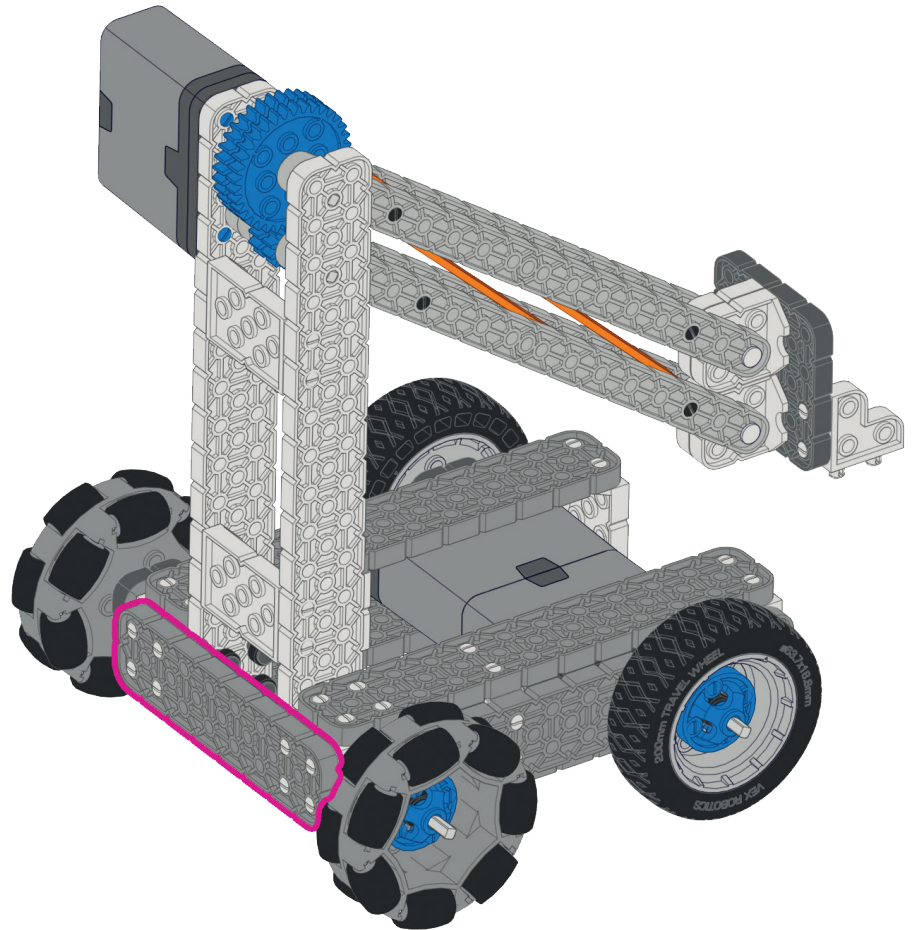
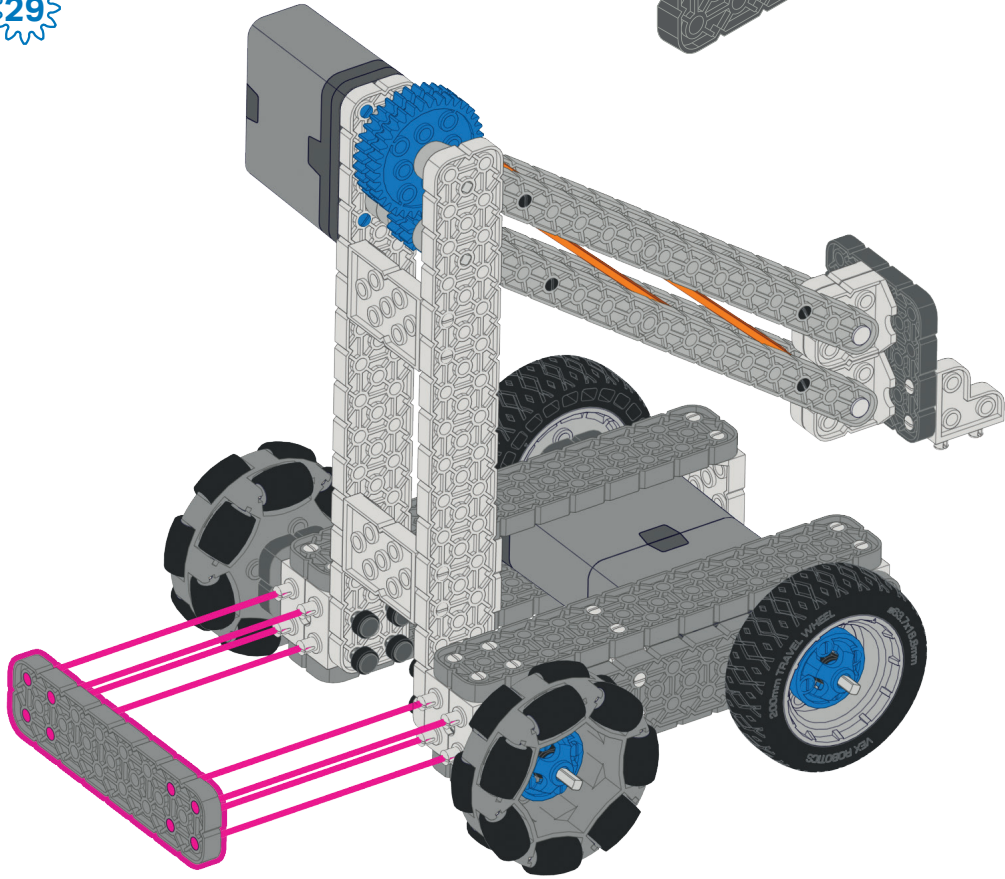
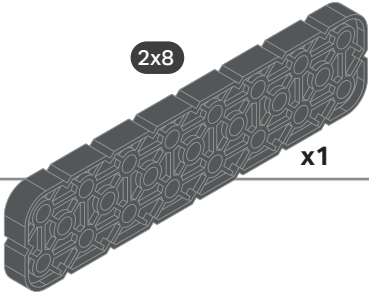


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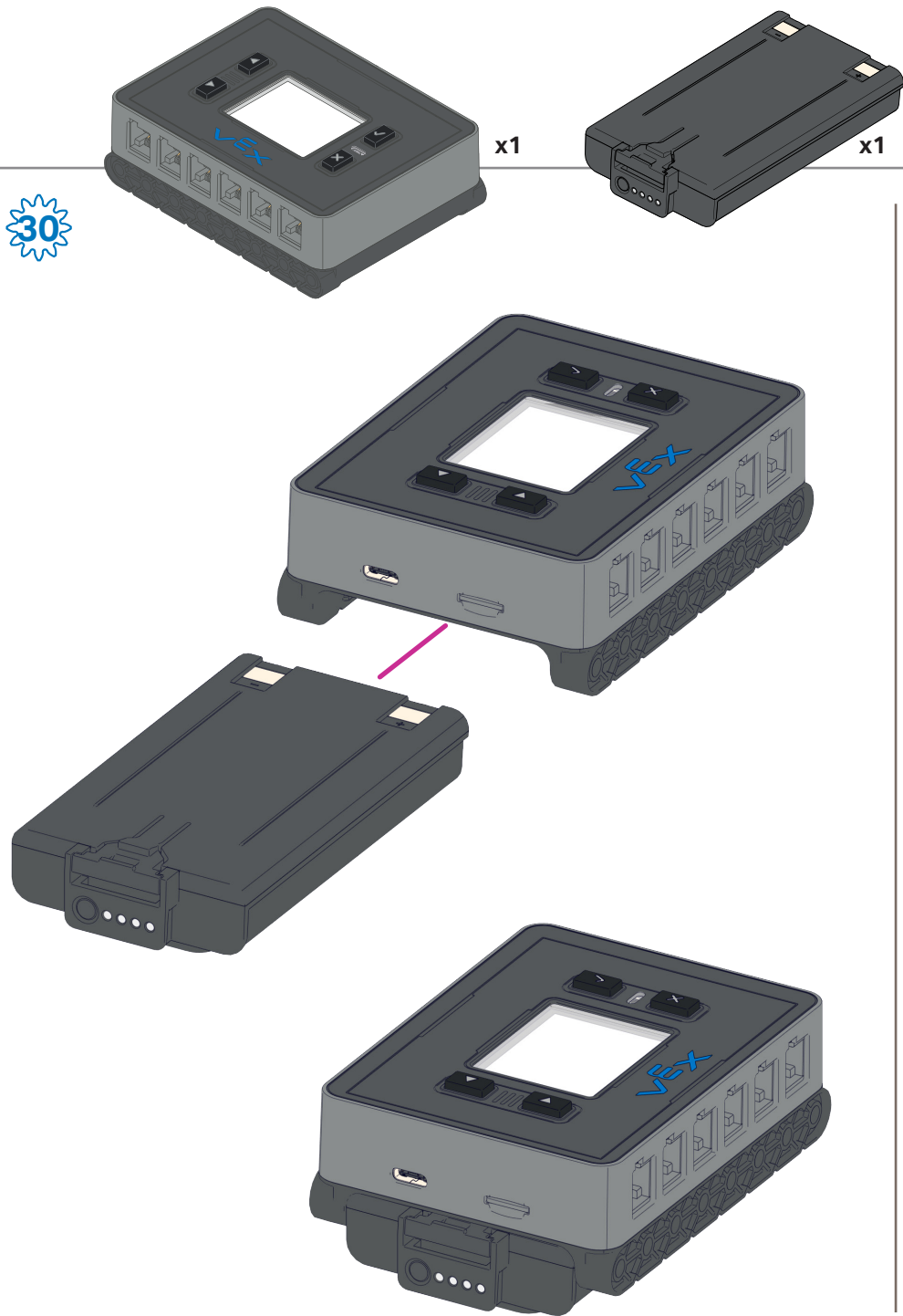
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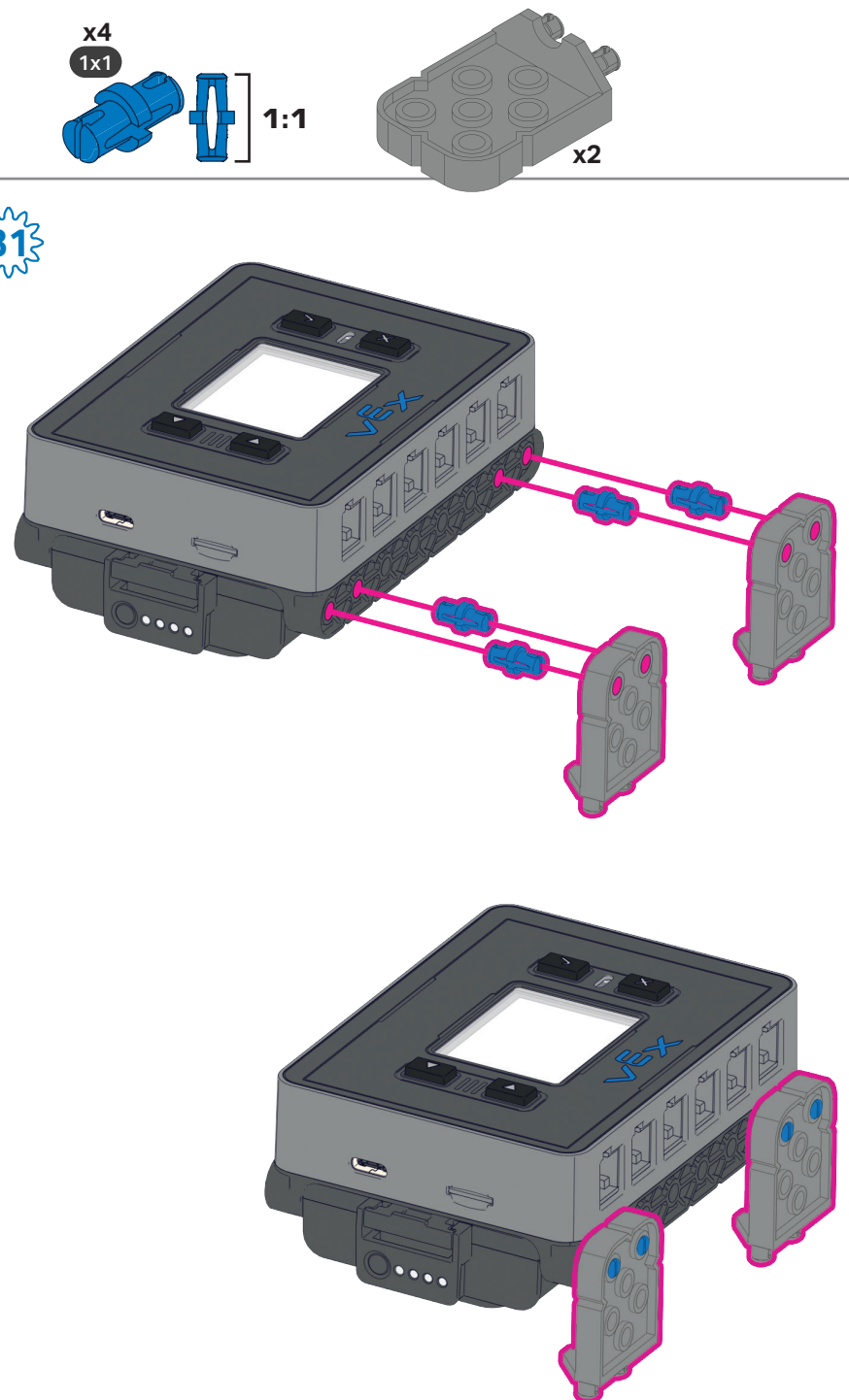




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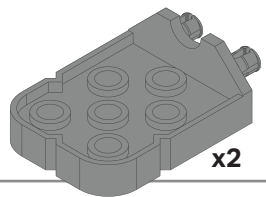
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x4  
1x1

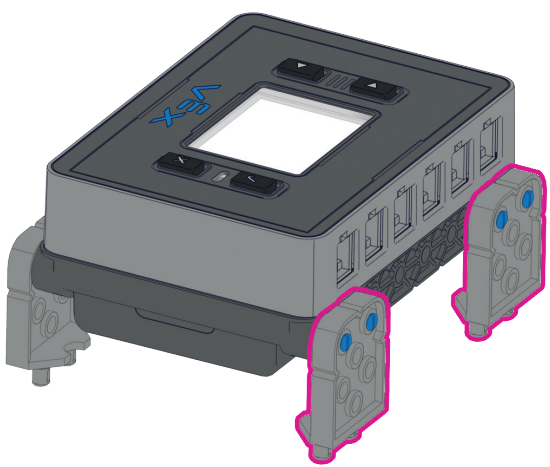
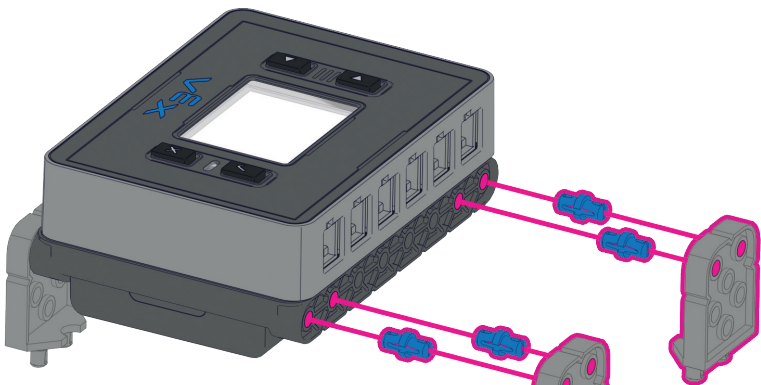


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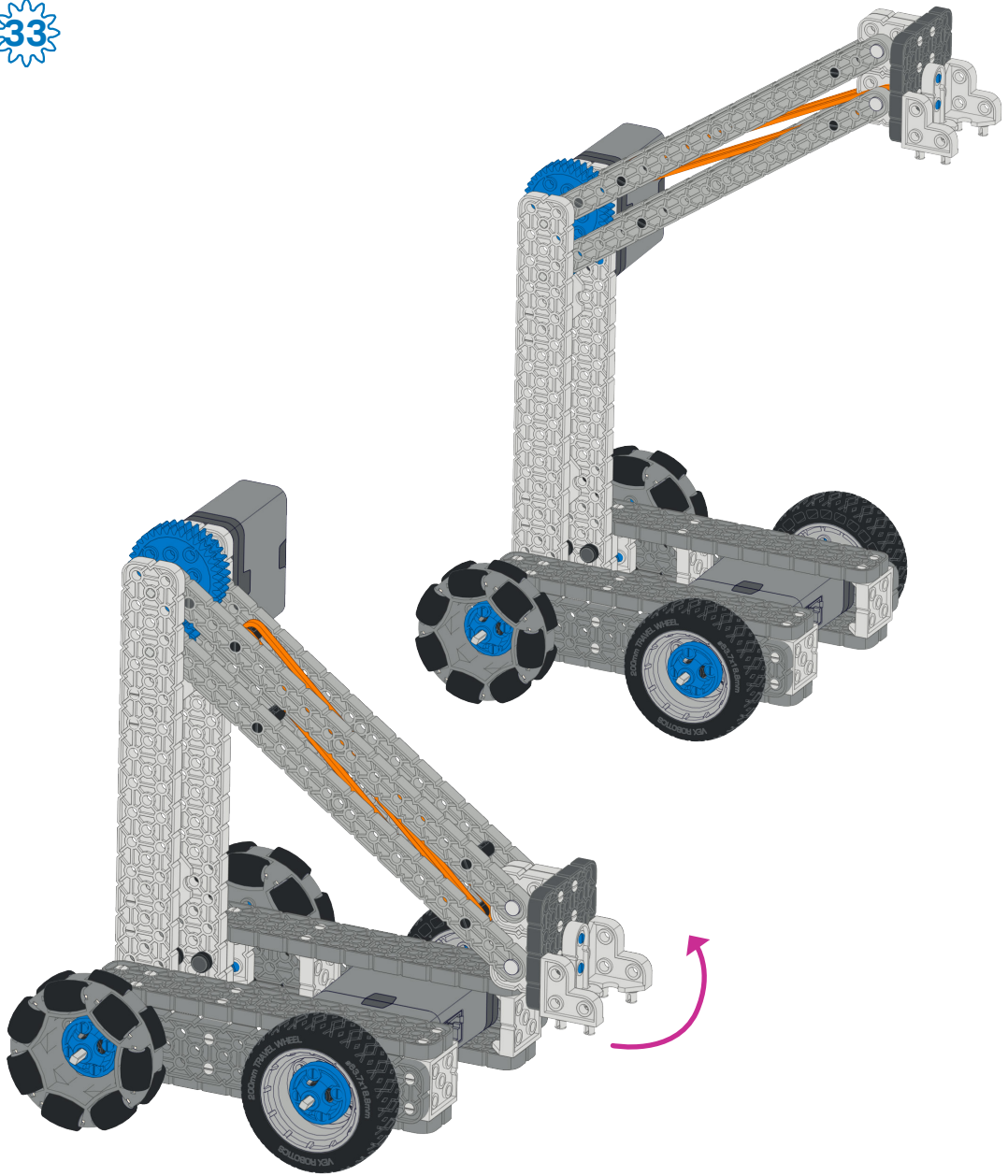


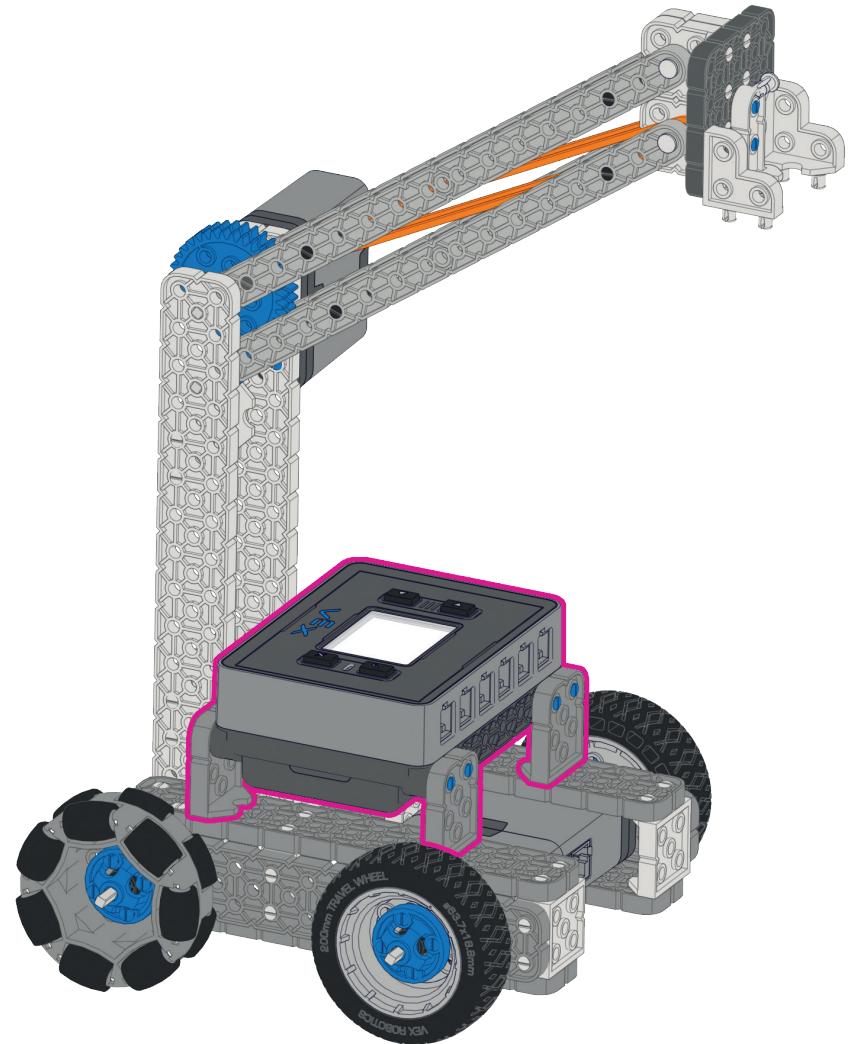
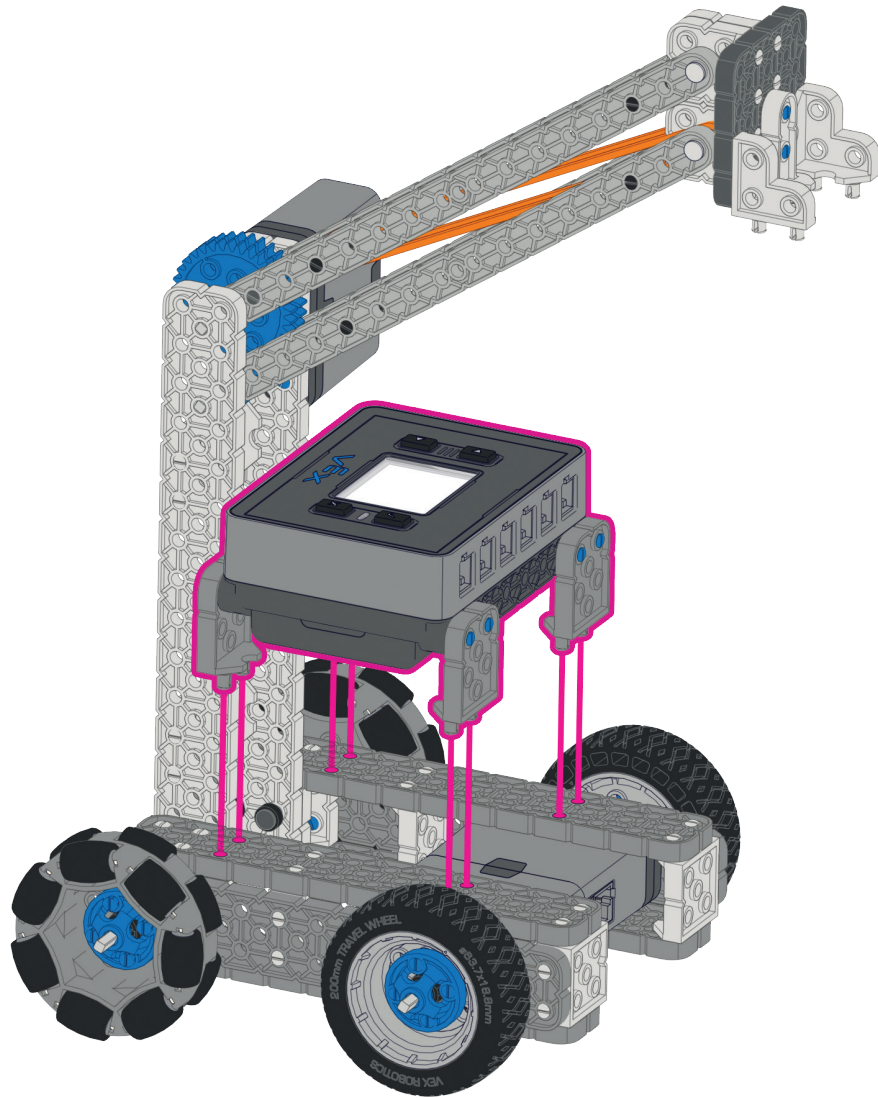
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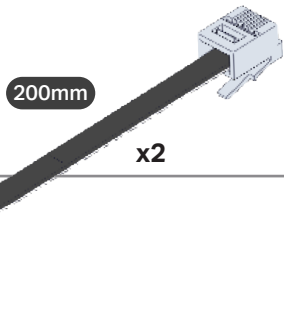
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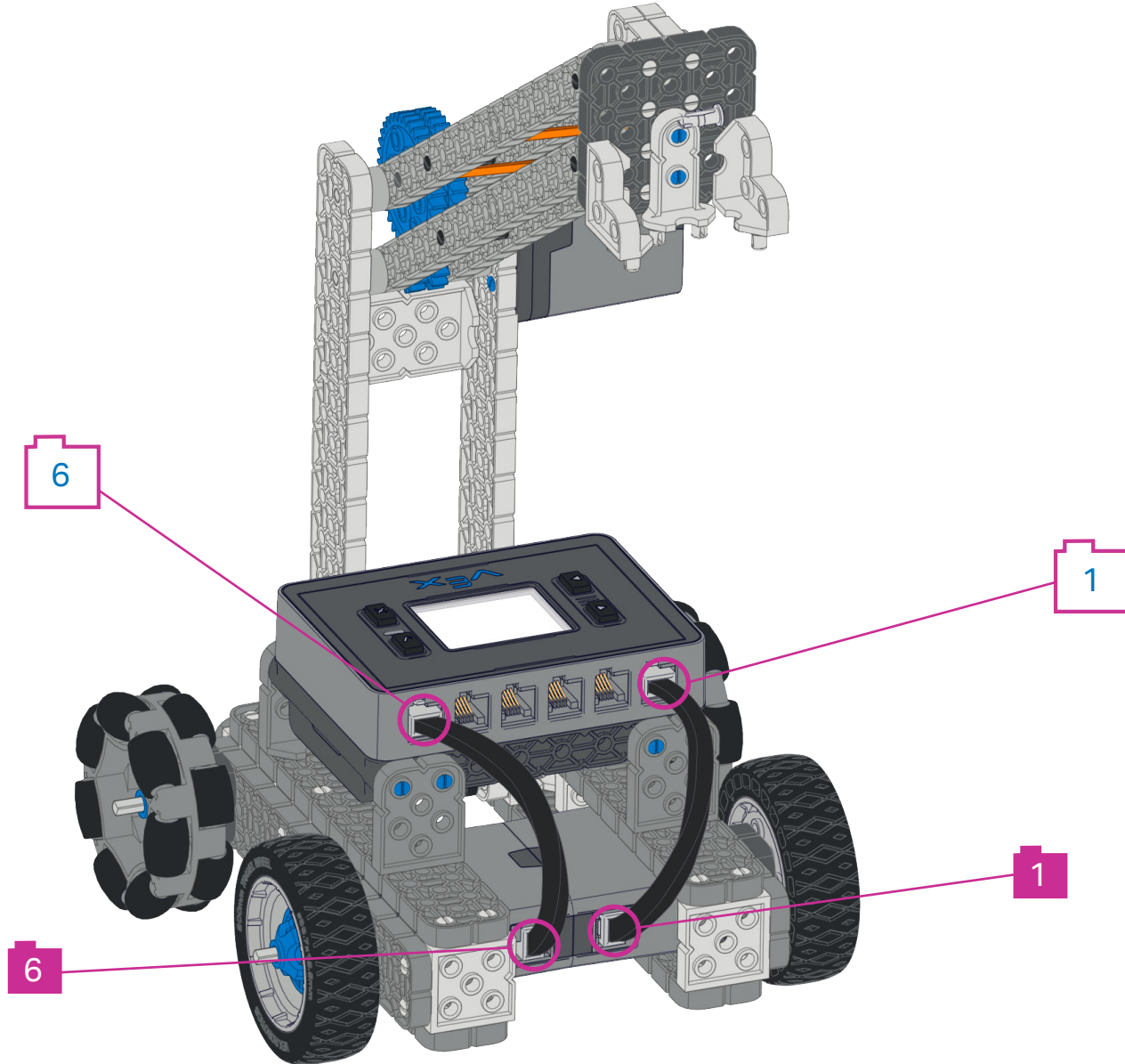
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35

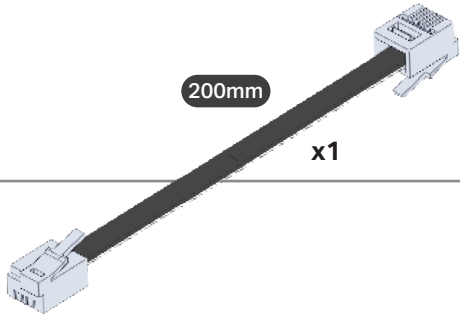


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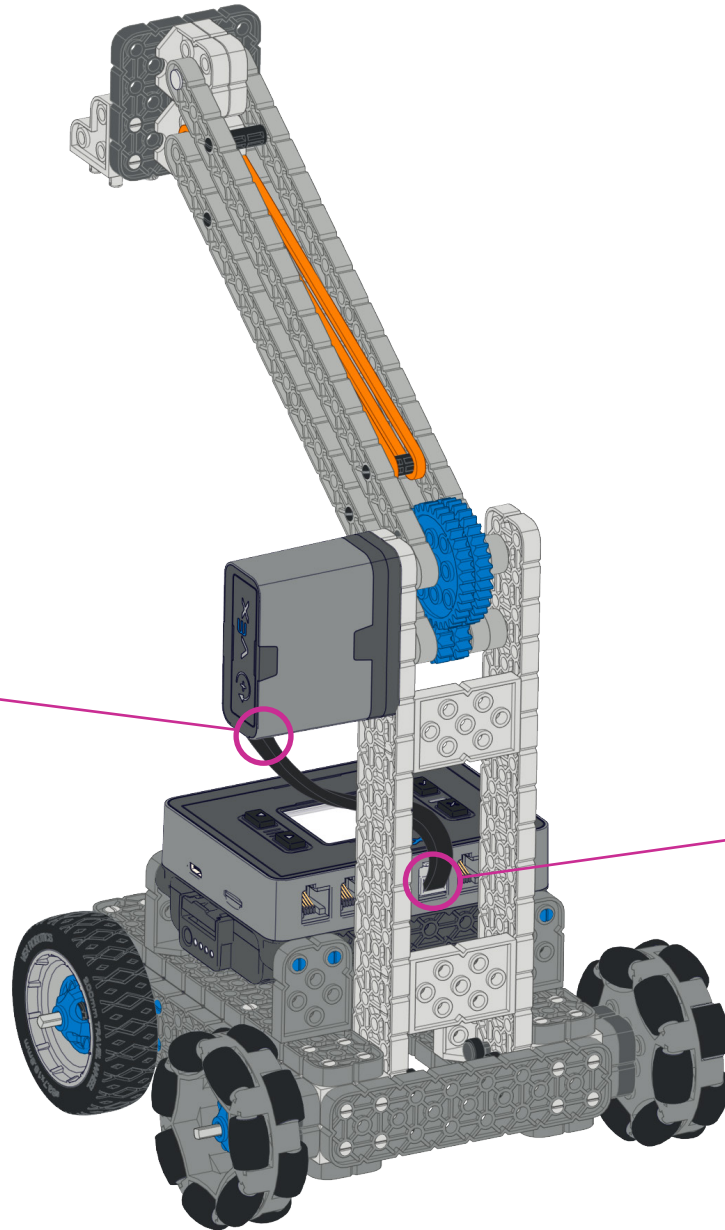
200mm

x1



10

10



2x8

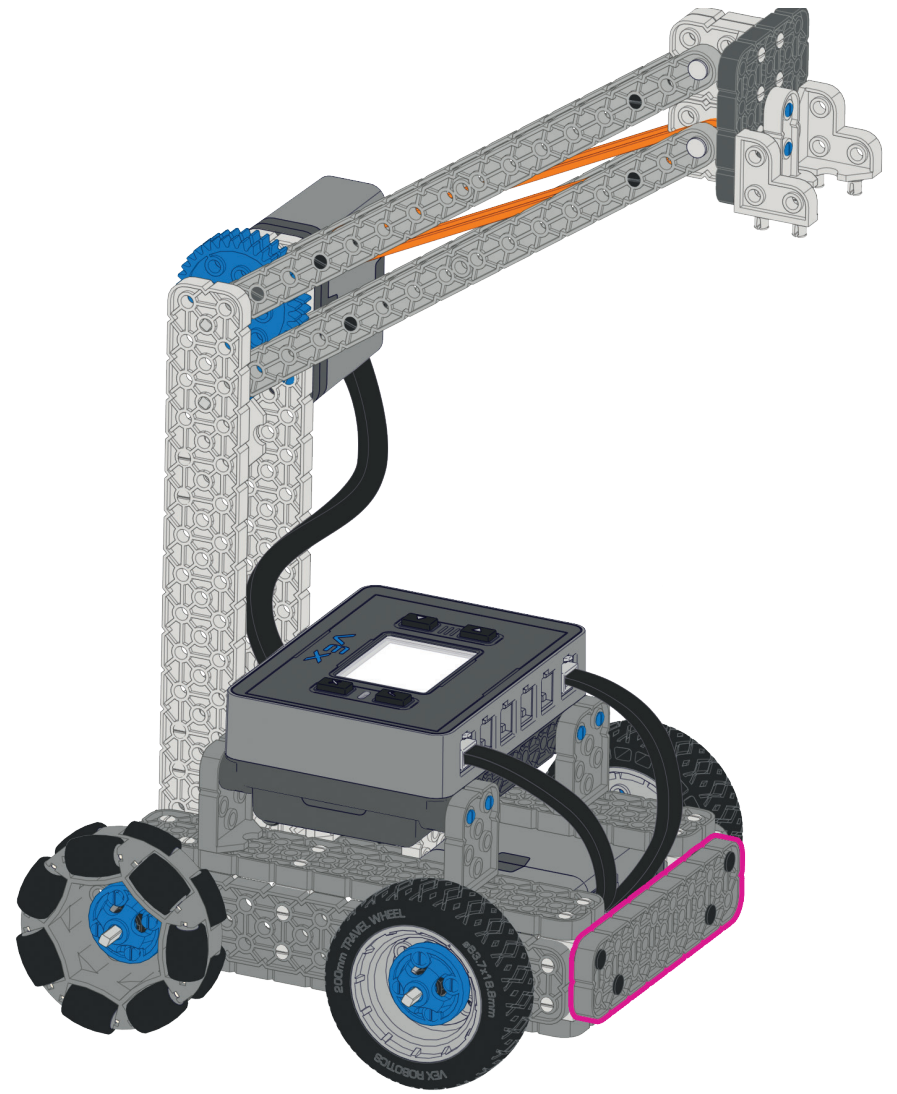
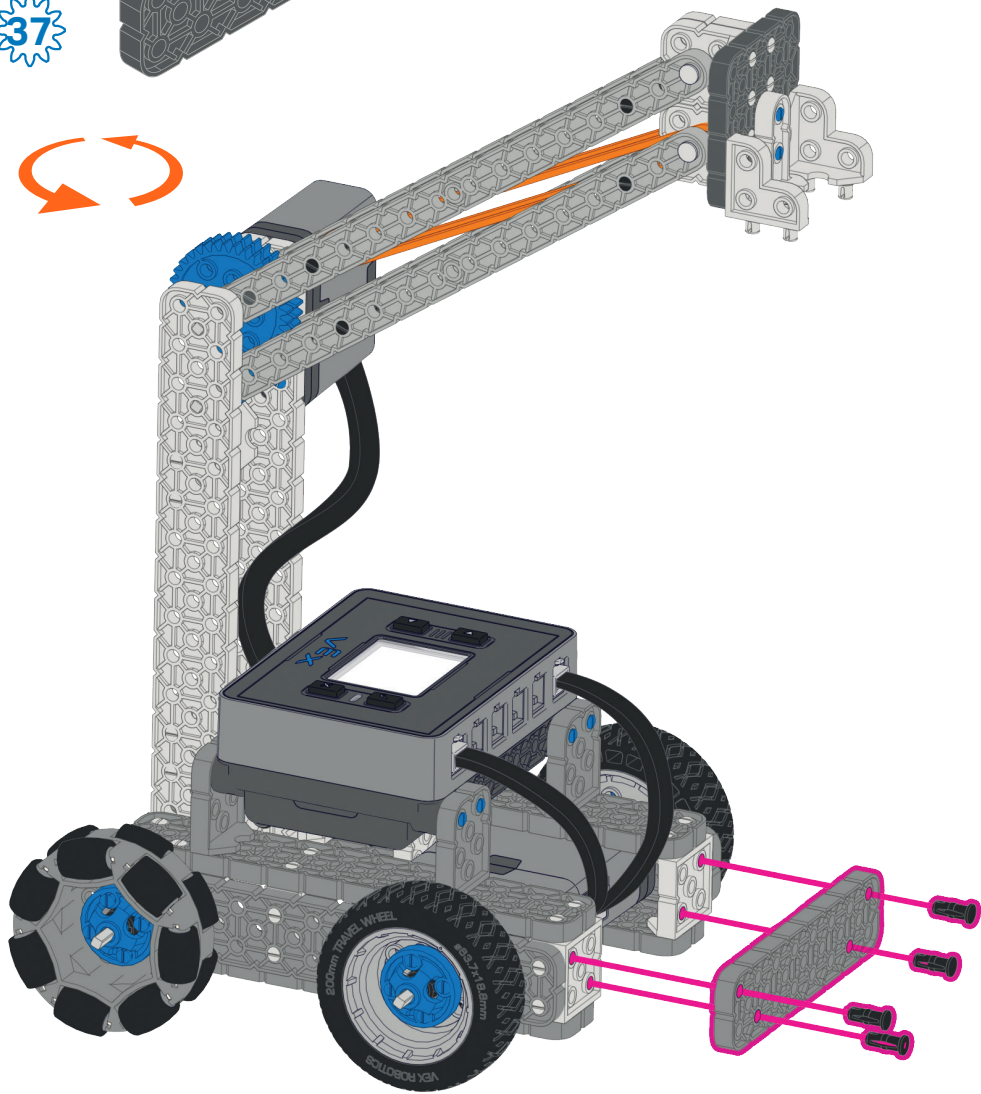
x1

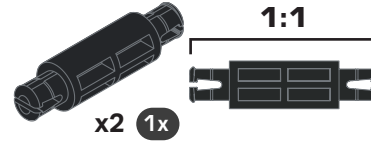
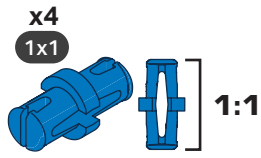
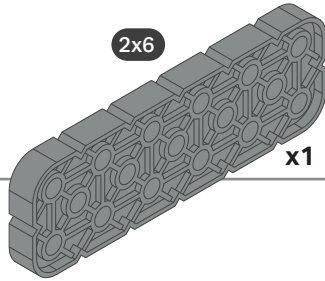
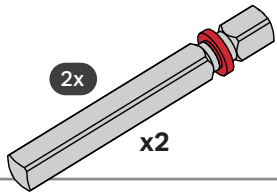
0x2

x4

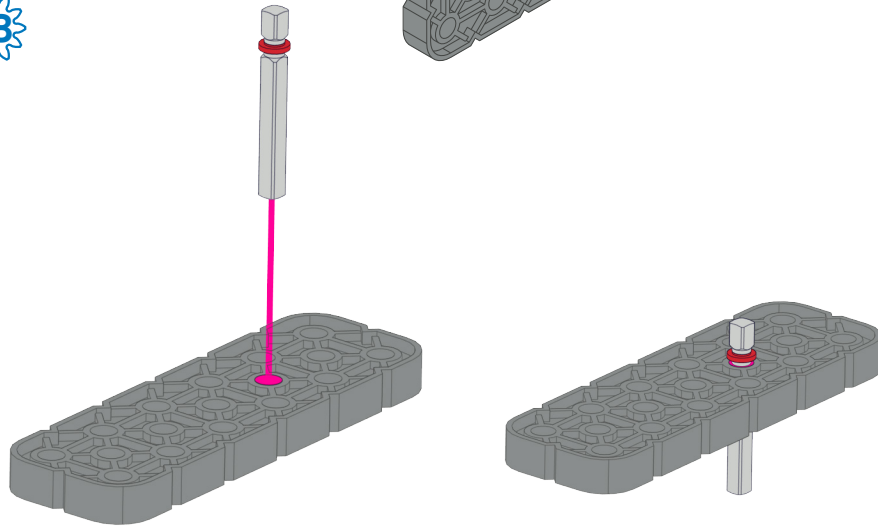
1:1

37

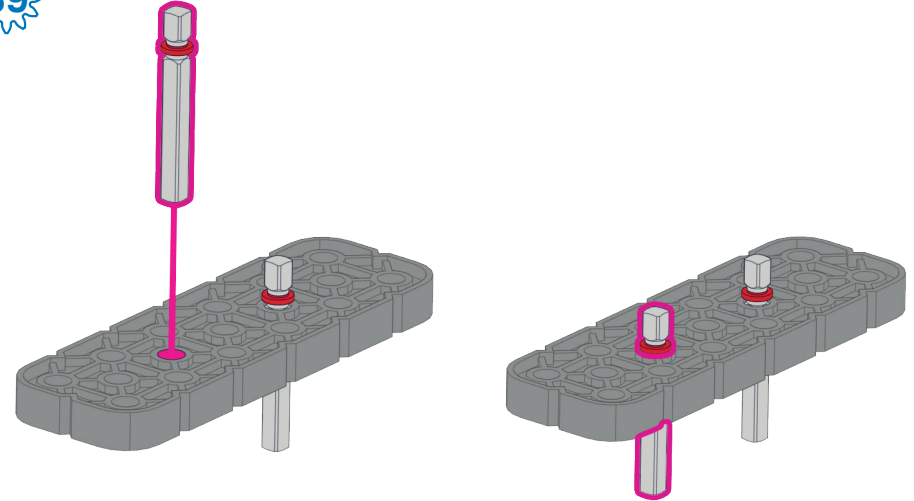




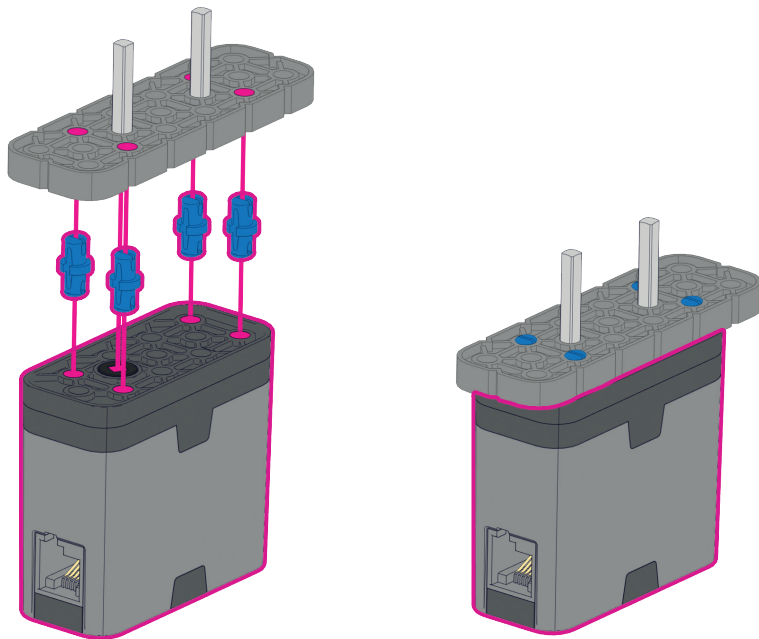
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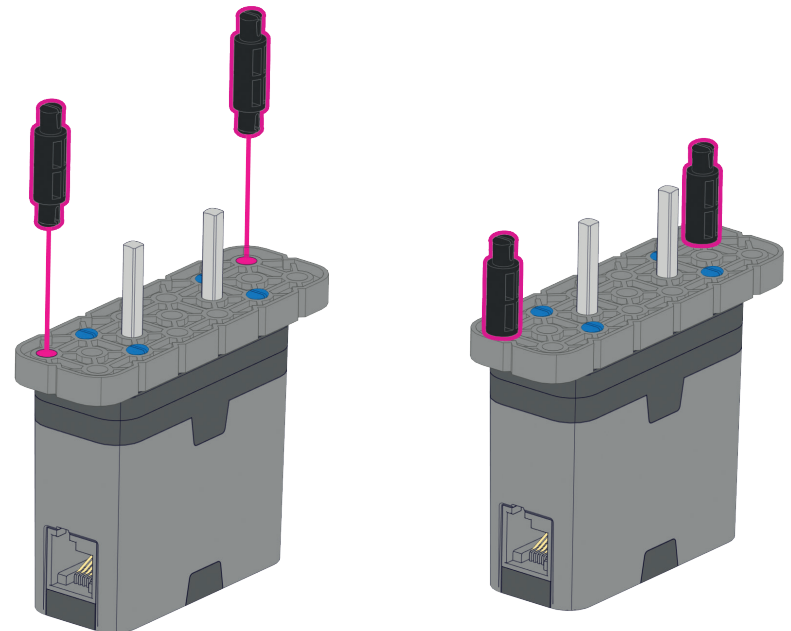
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40



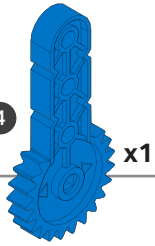
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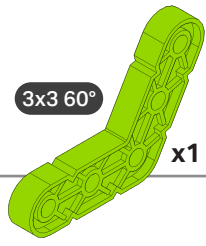
x4

1x4

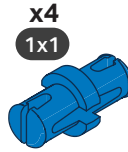


x1

3x3 60°



x1

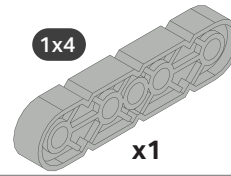


x4

1x1

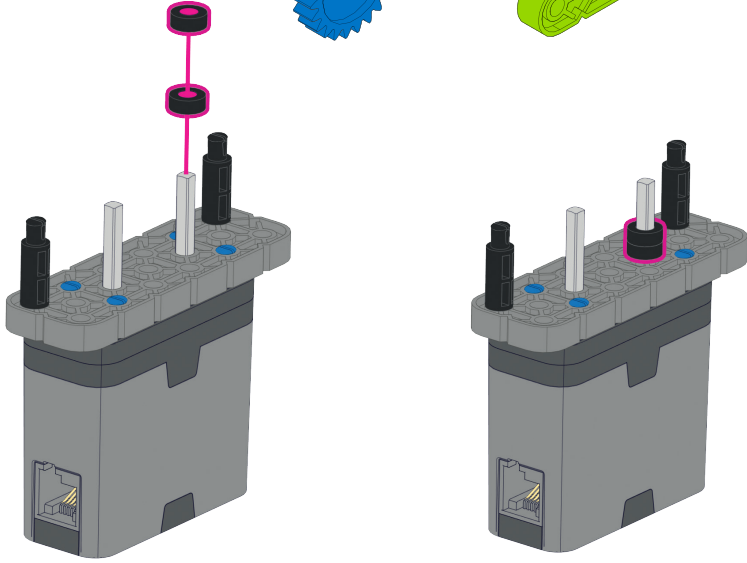
1:1

1x4

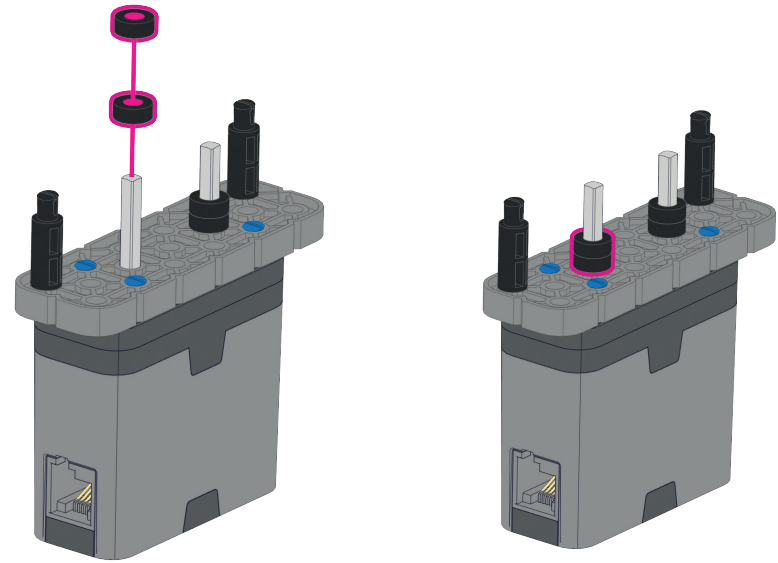


x1

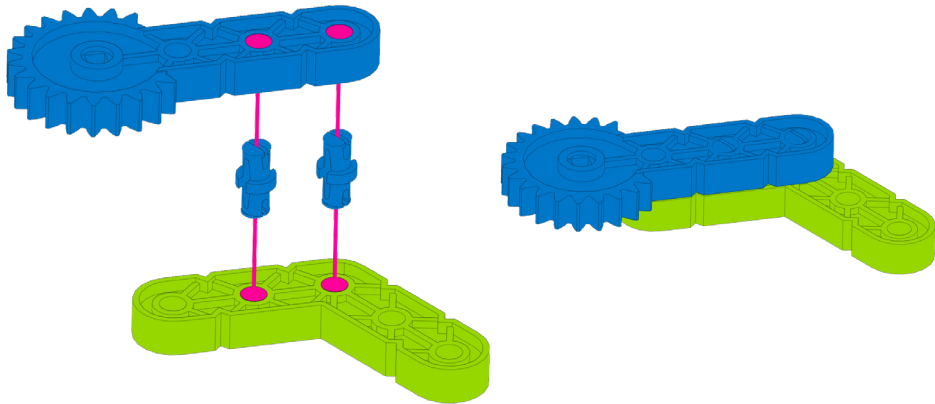
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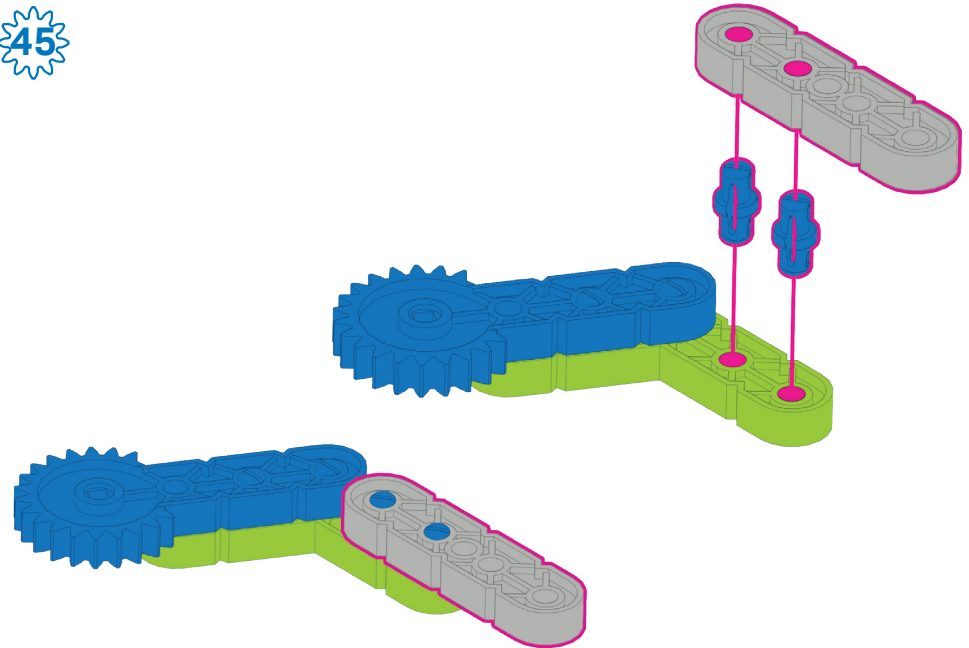
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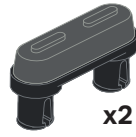
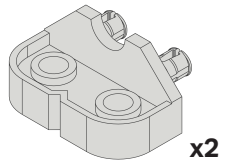
44



45

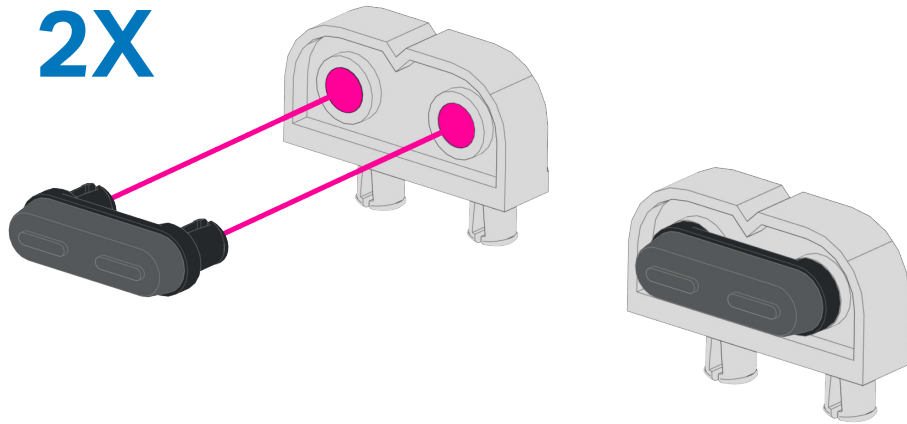




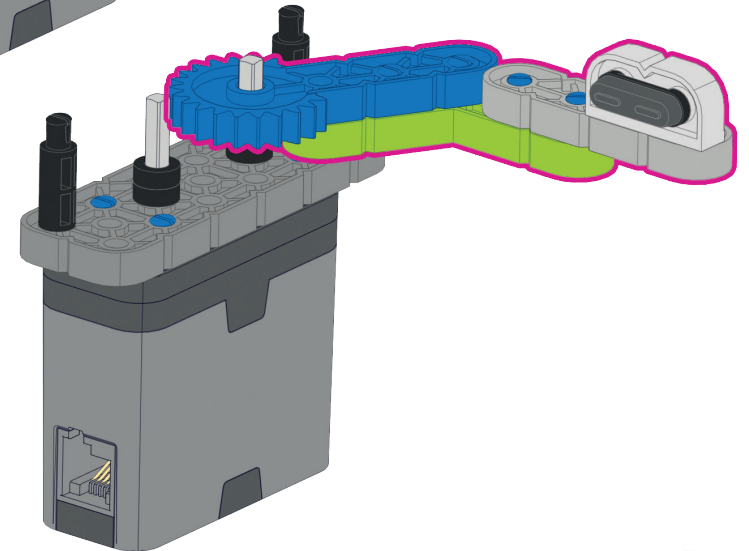
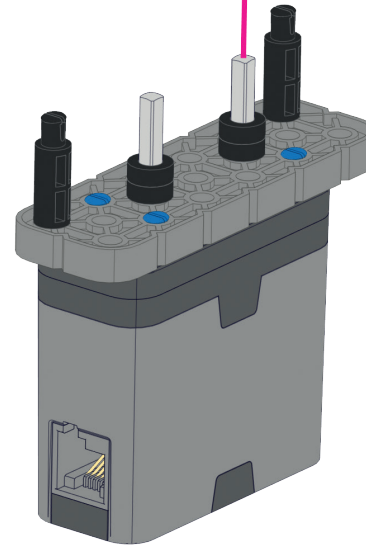
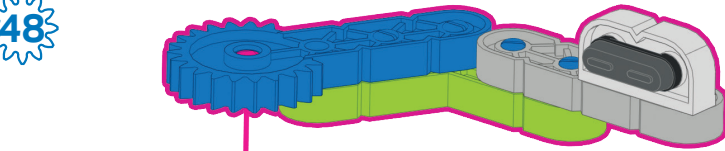


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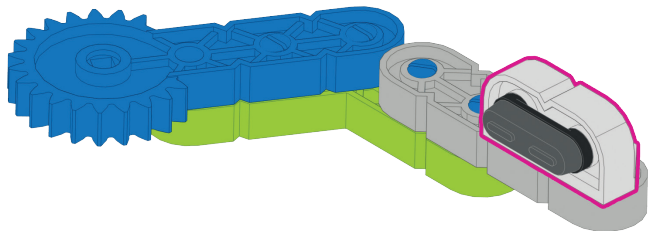
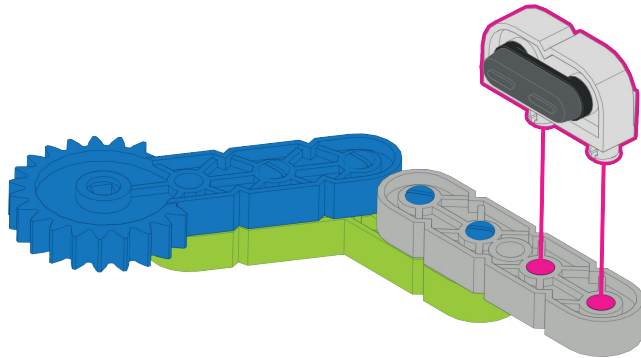
2X



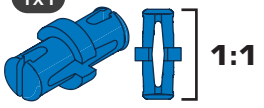
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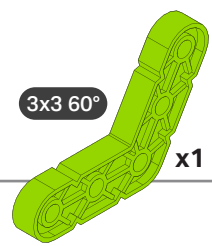
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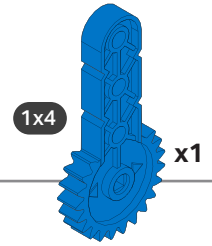
x4  
1x1



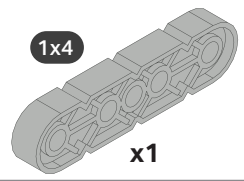
3x3 60°



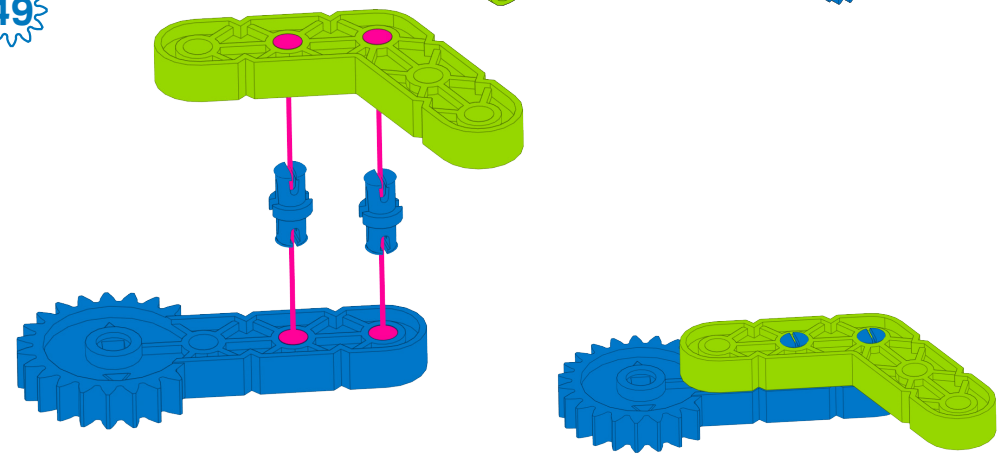
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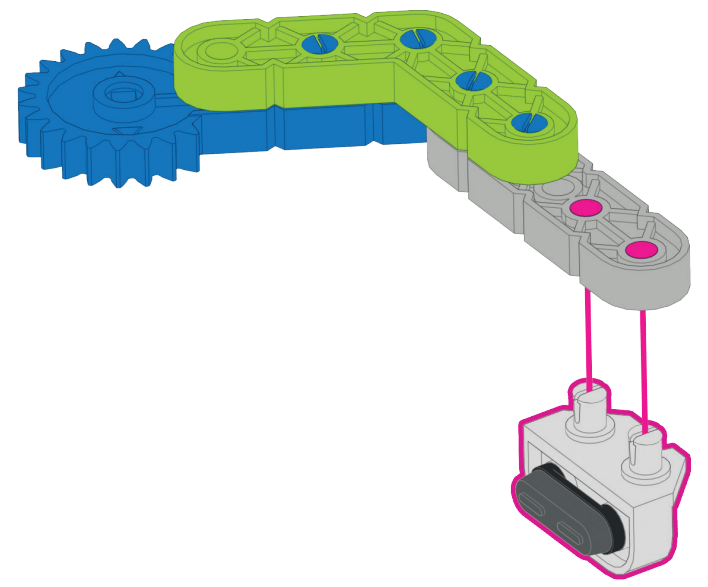
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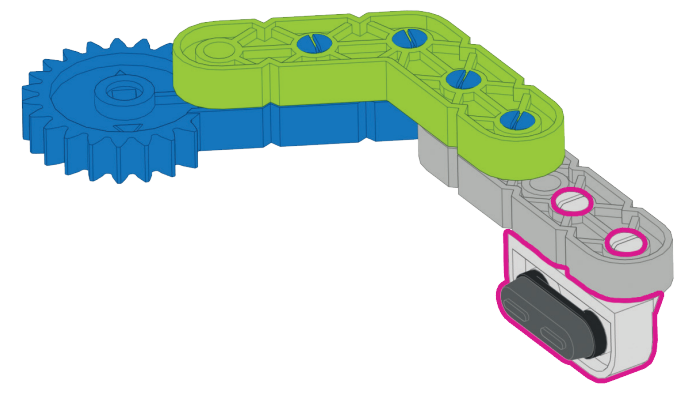
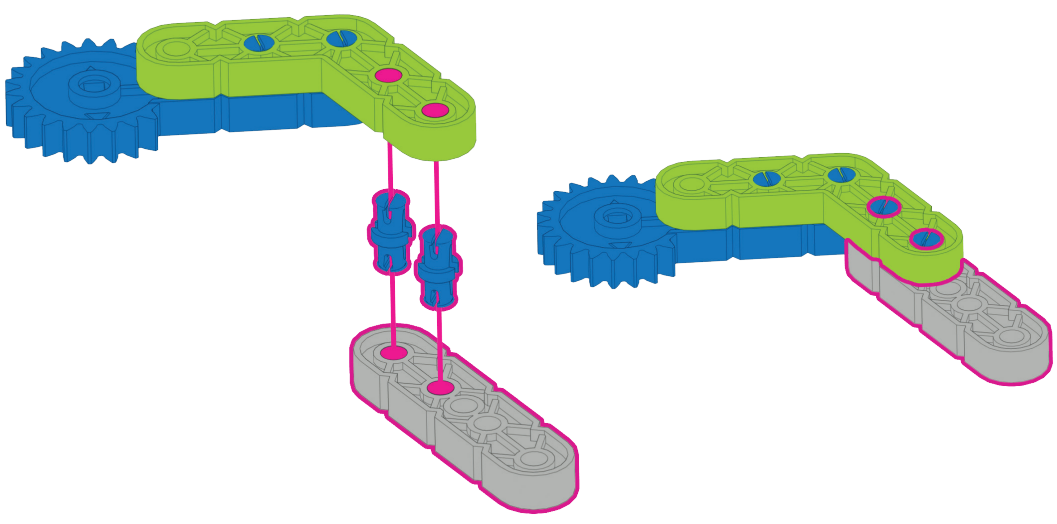
49



51



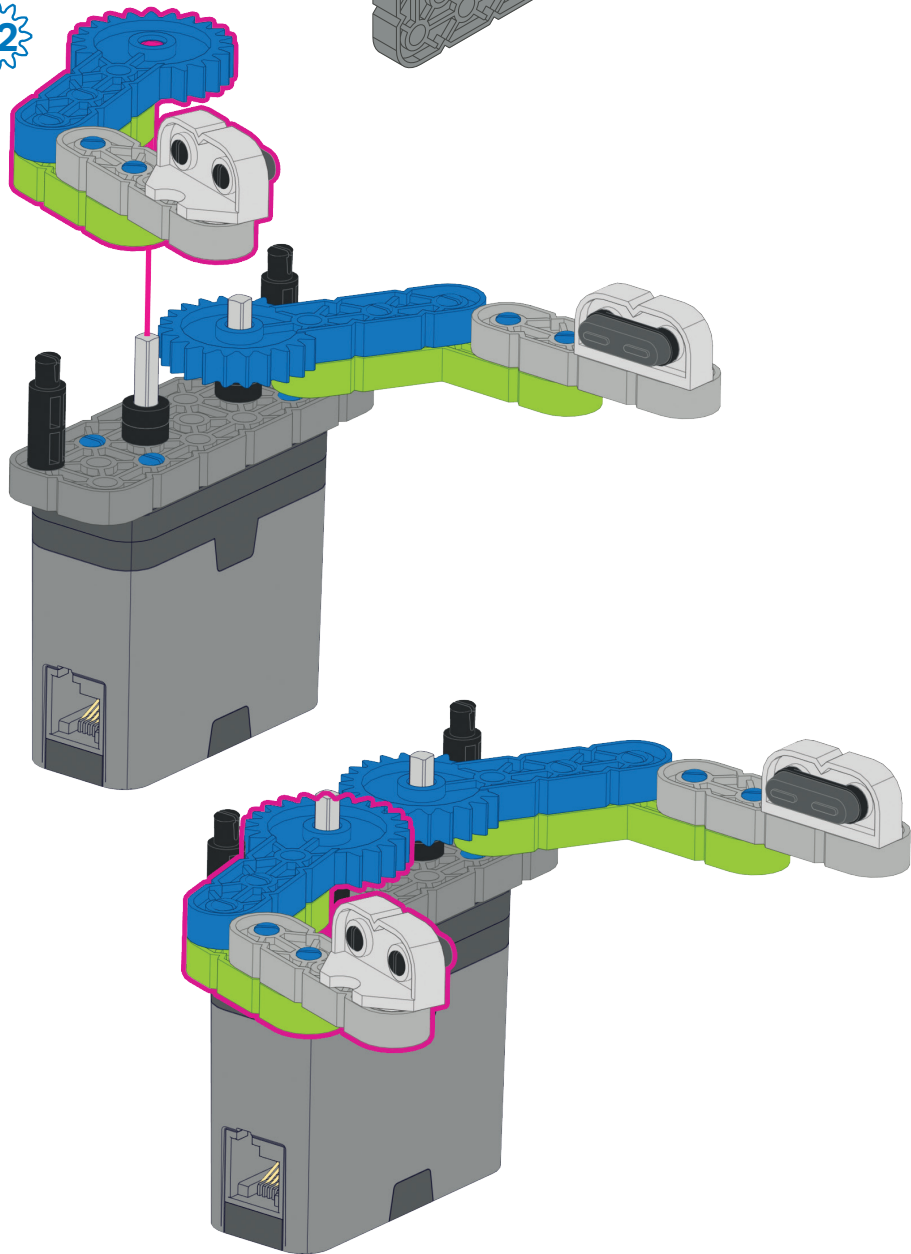
50



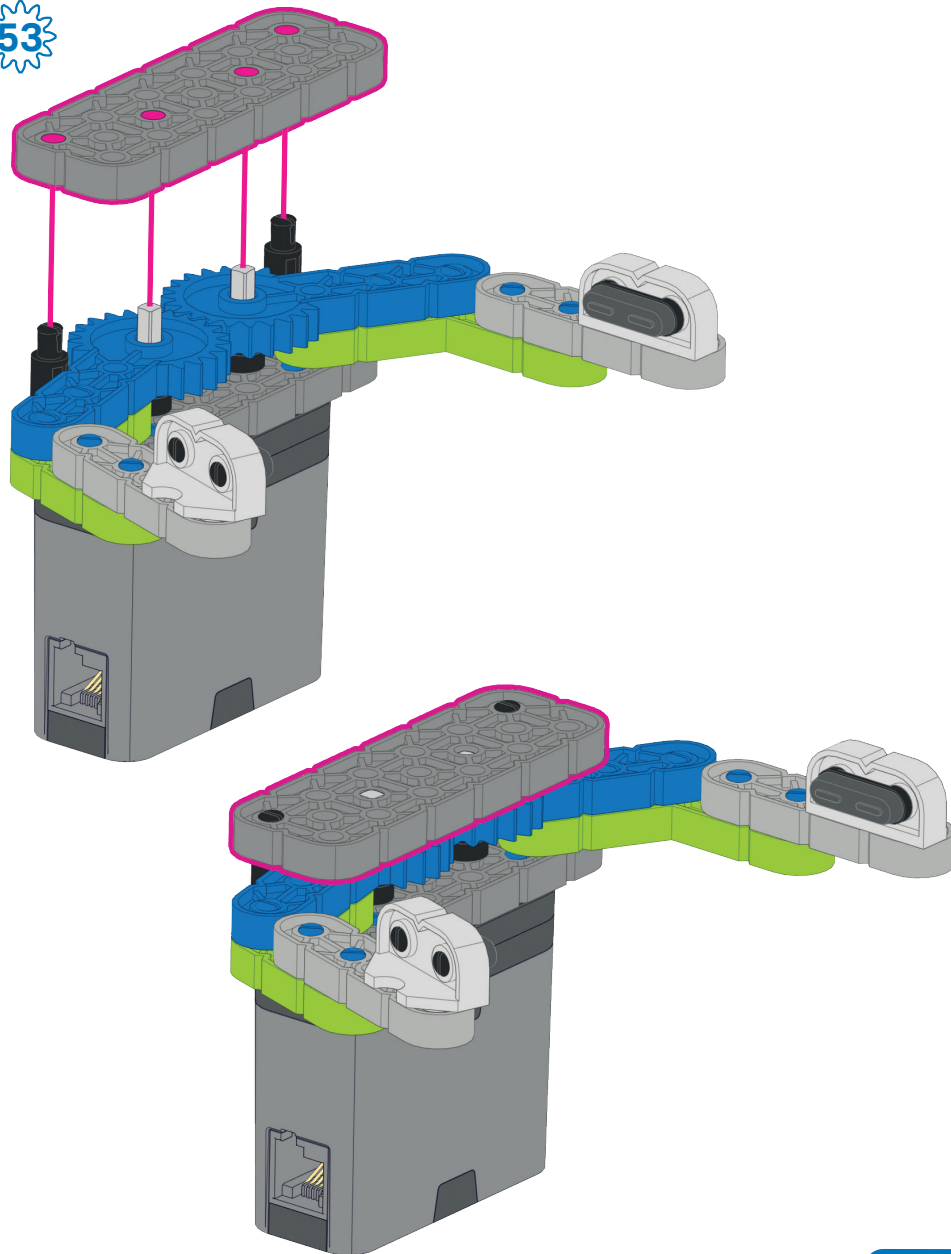
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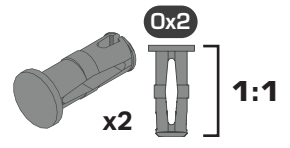
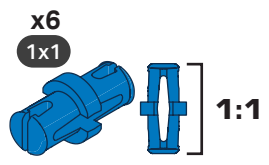
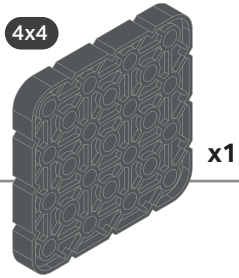
x1

52

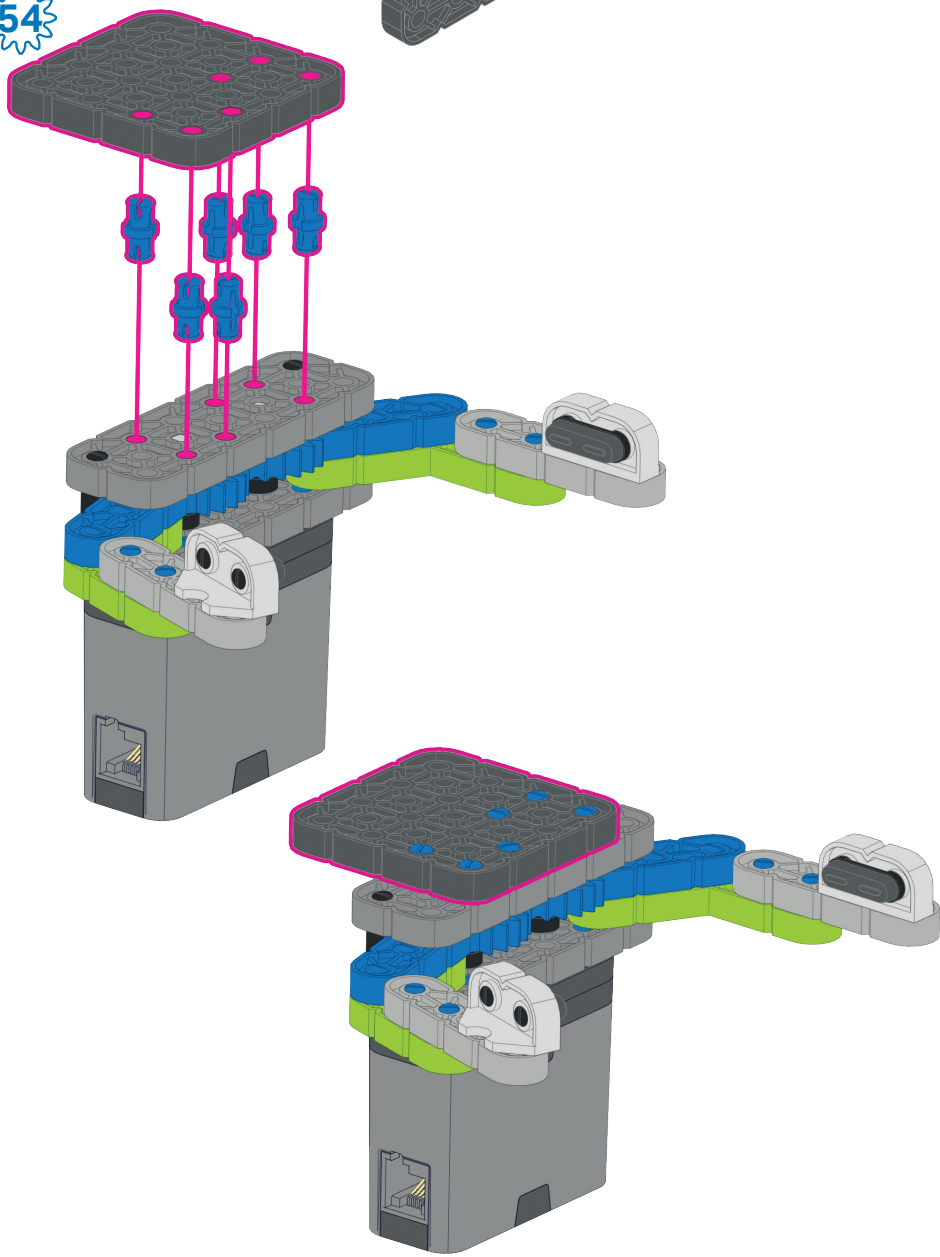


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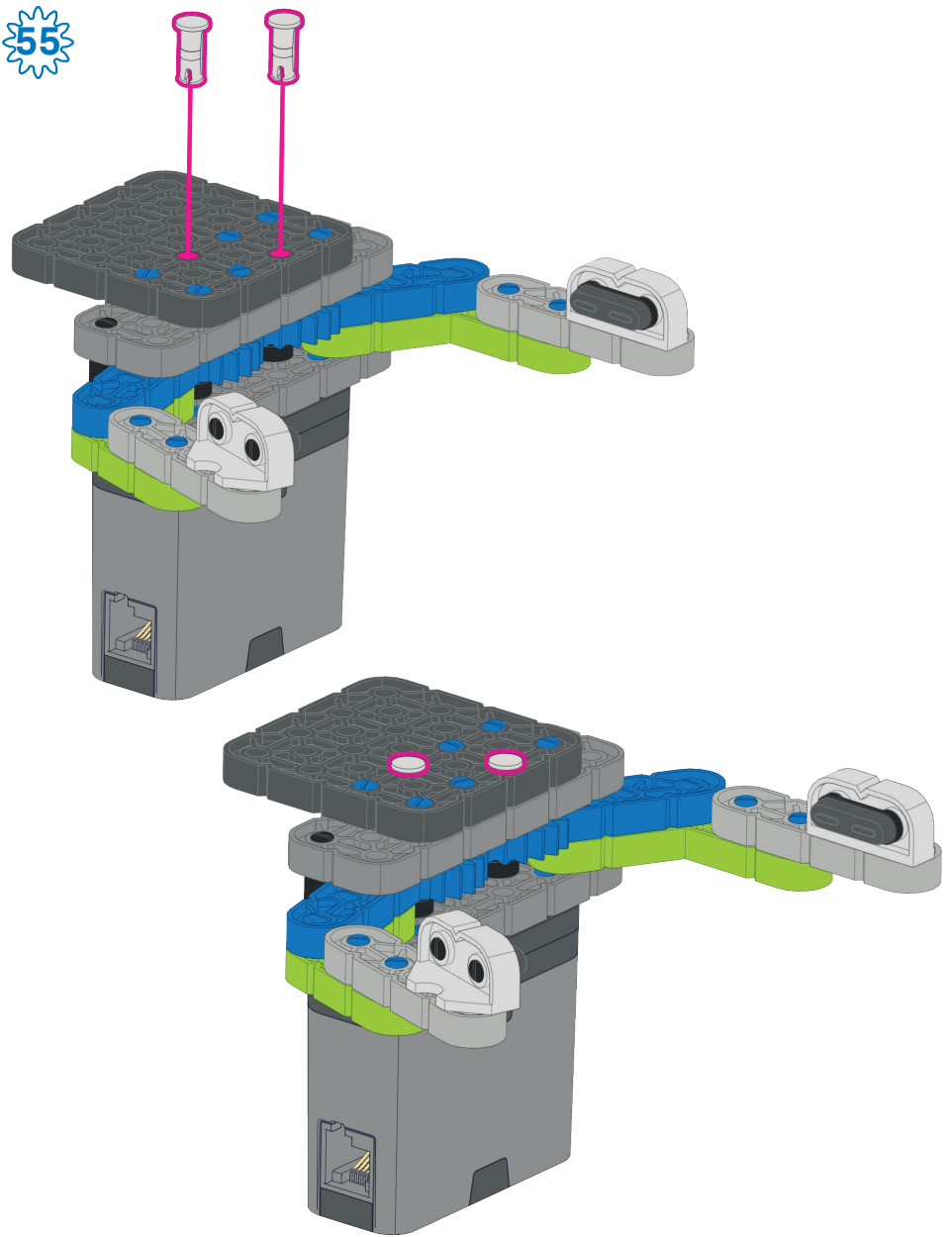




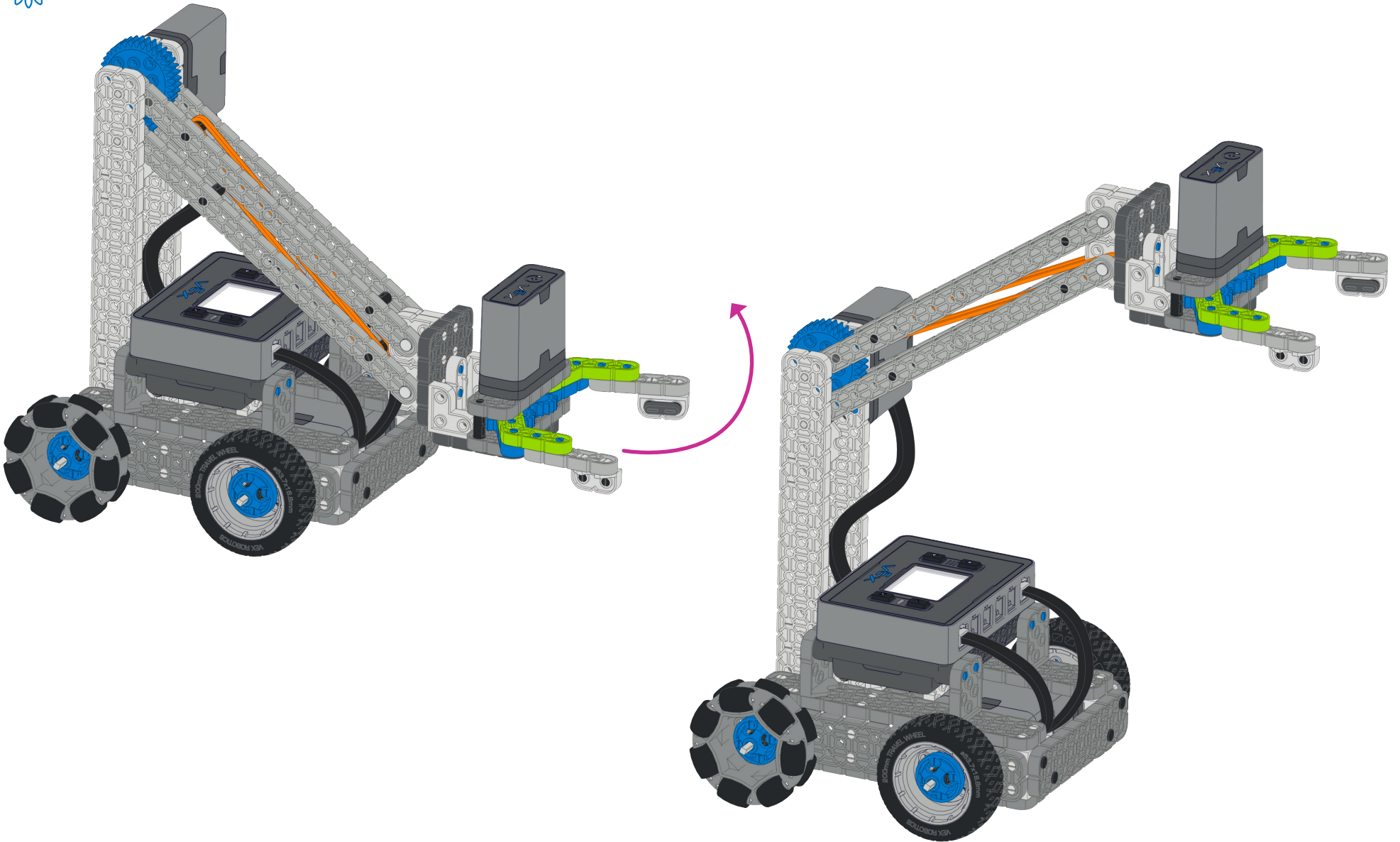
54



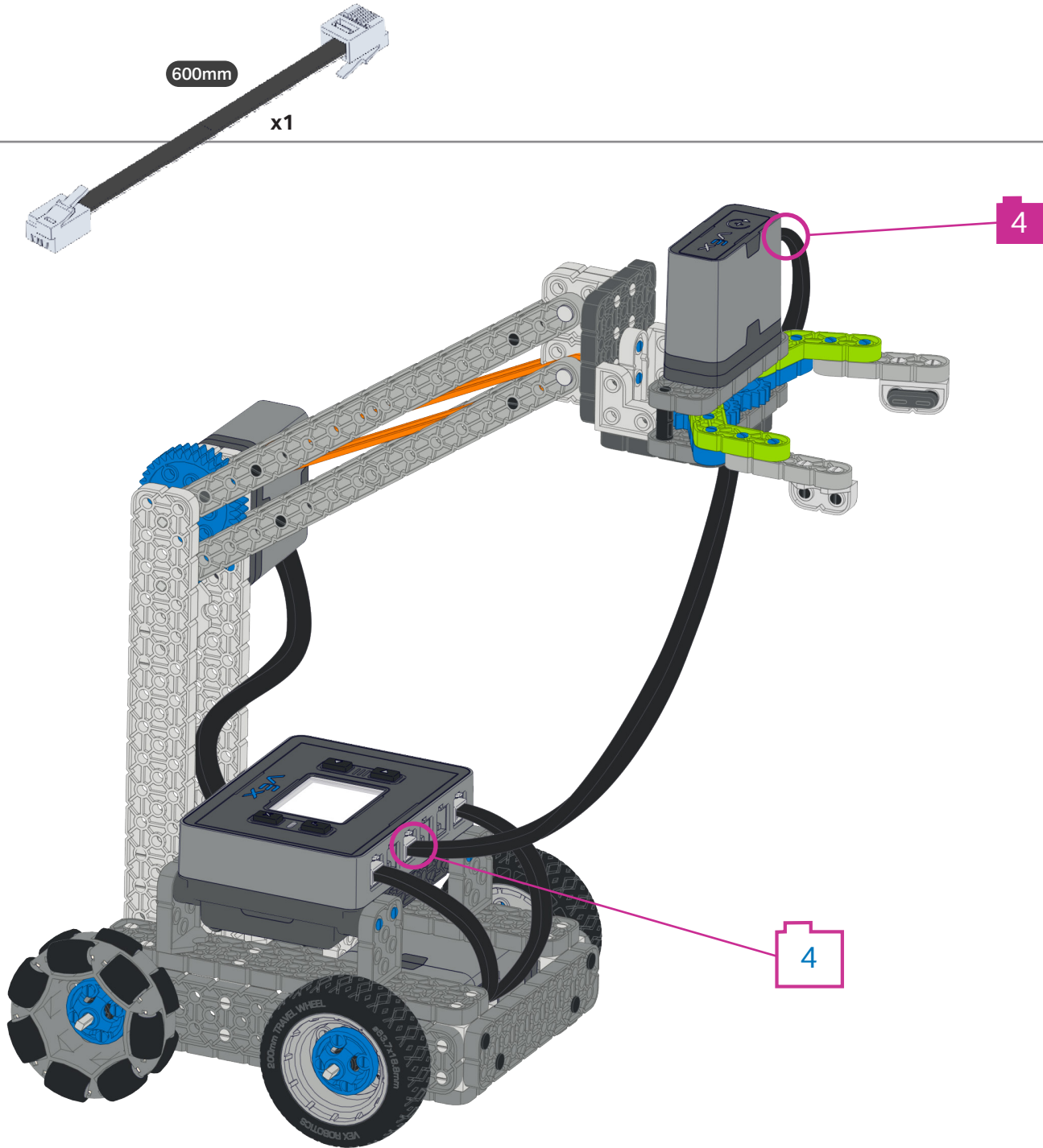
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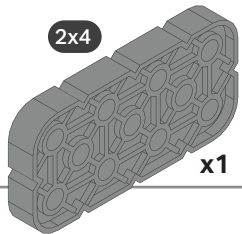




58

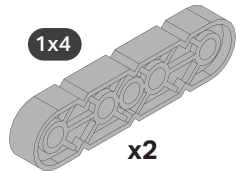


2x4

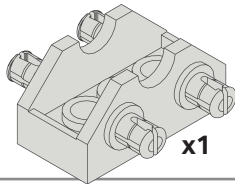


x1

1x4

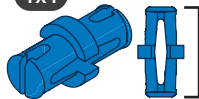


x2



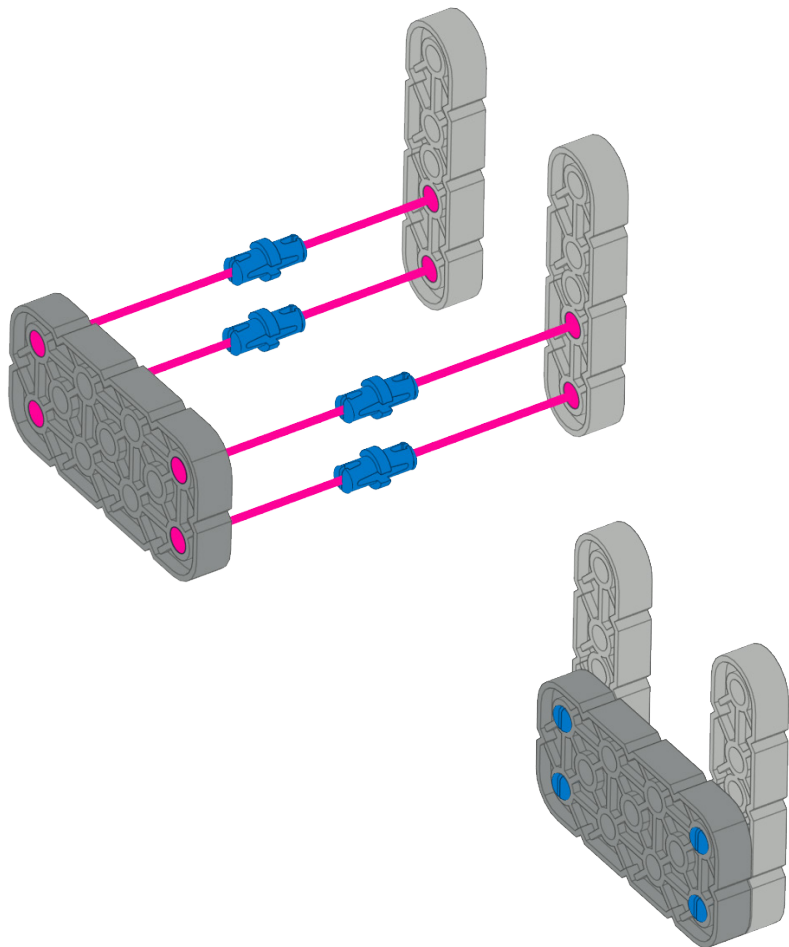
x1

x4  
1x1

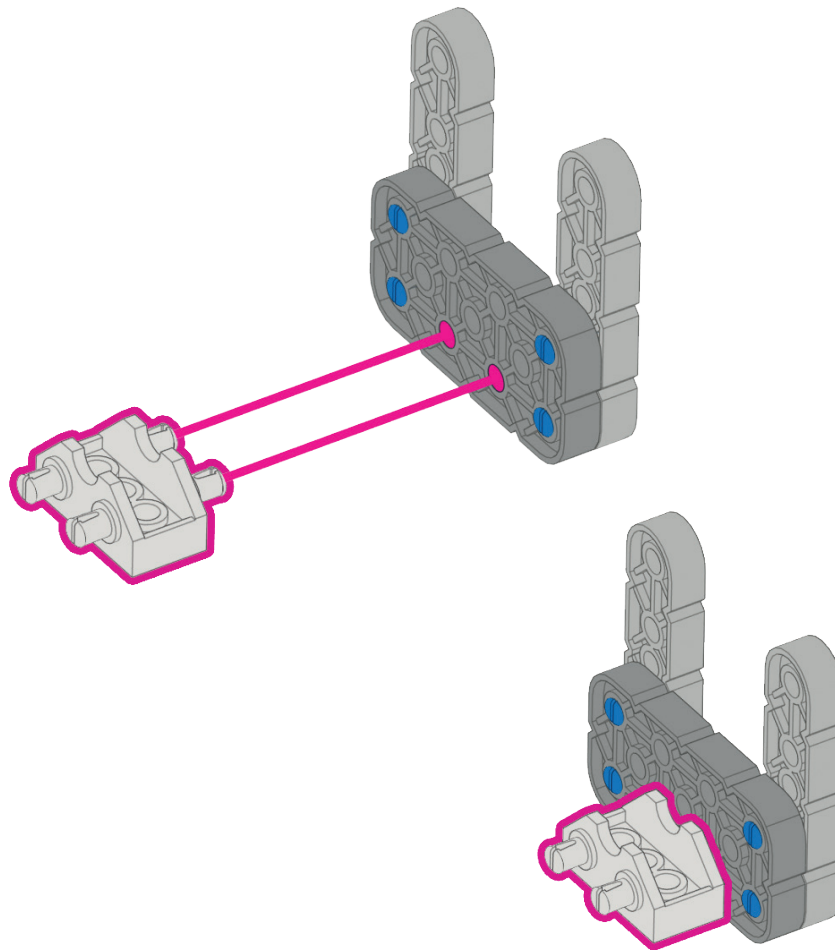


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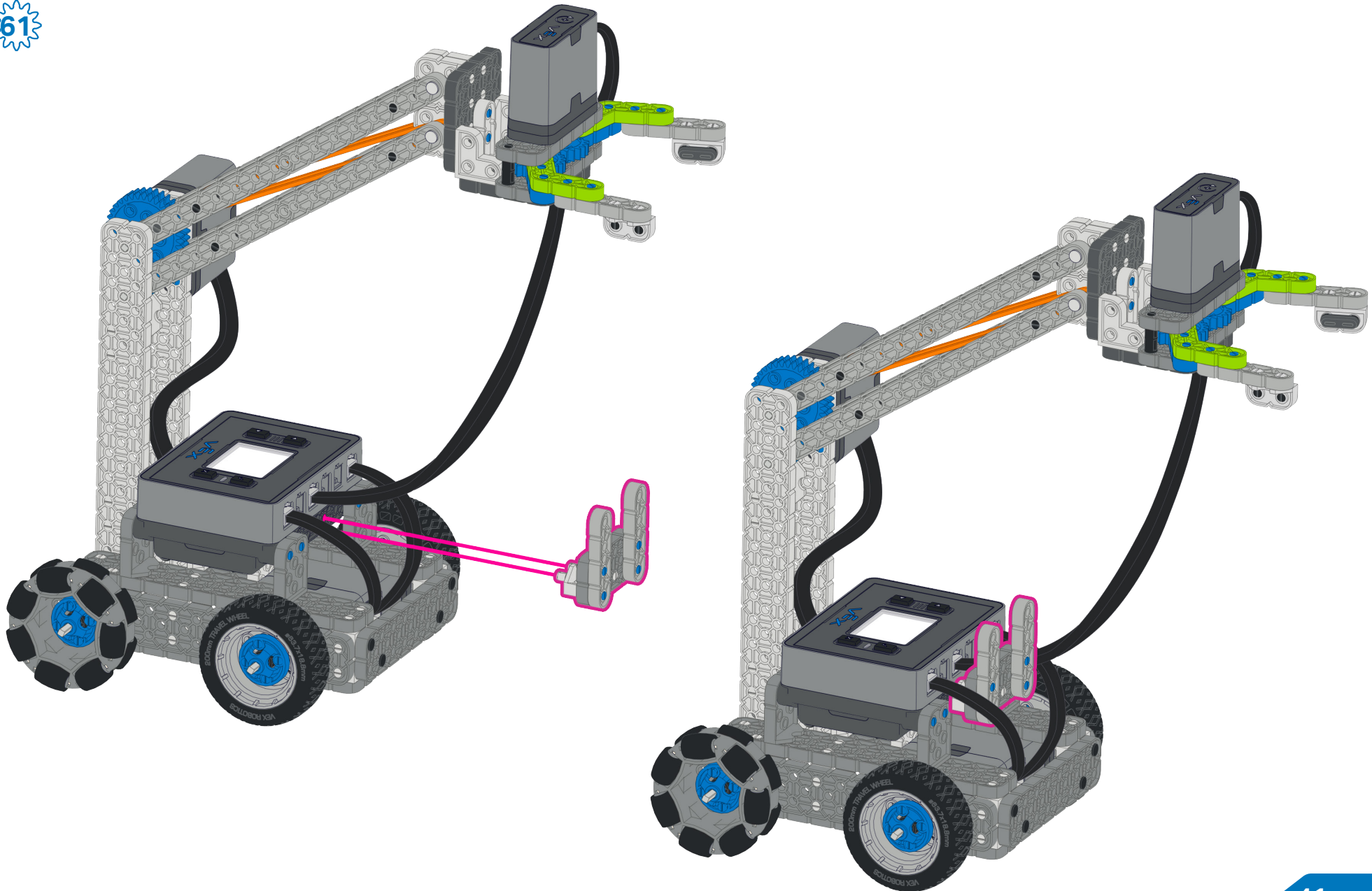
59



60







# Clawbot Build Instructions

228-8899 Rev2



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