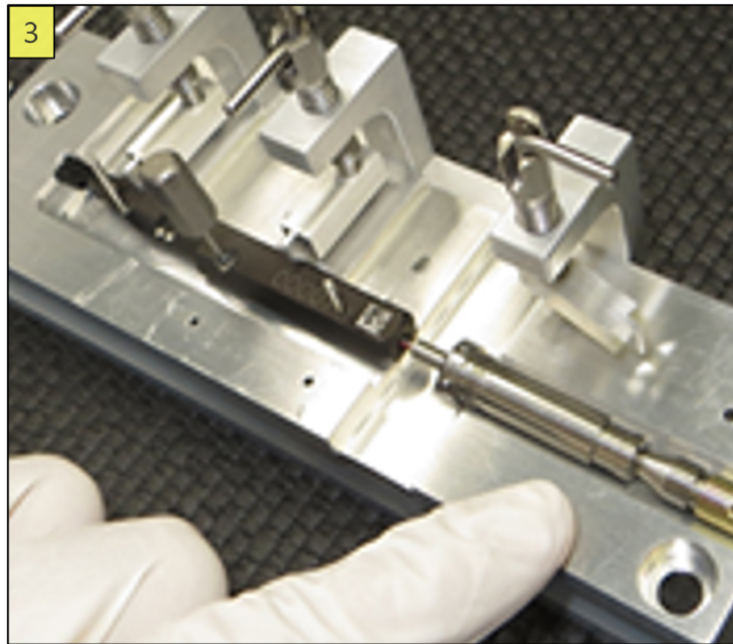


Figure 27. from
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1. **θ bearing + θ coupling**: θ bearing is the mechanical interface to the petal, controlling central axis rotation, piston and tilt of the overall robot.
2. **ϕ motor + ϕ bearing + ferrule holder**: Ferrule holder is directly attached to the ϕ bearing + motor drivetrain.
3. **'Critical' assembly**: Items (1) + (2) are bonded together, simultaneously aligning the rotation and ferrule holder axes on one jig.
4. **Main assembly**: Item (3) is connected to the aft structure, containing theta coupler and hard stop mechanism.
5. **θ motor assembly**: θ motor is bonded into the aft structure of item (4).
6. **ϕ motor wiring, friction tab**: Wires for ϕ motor are strung through the central axis and friction tabs are installed.



7. **Board installation**: Electronics board is screwed to robot, motor wires soldered and encapsulated.

