

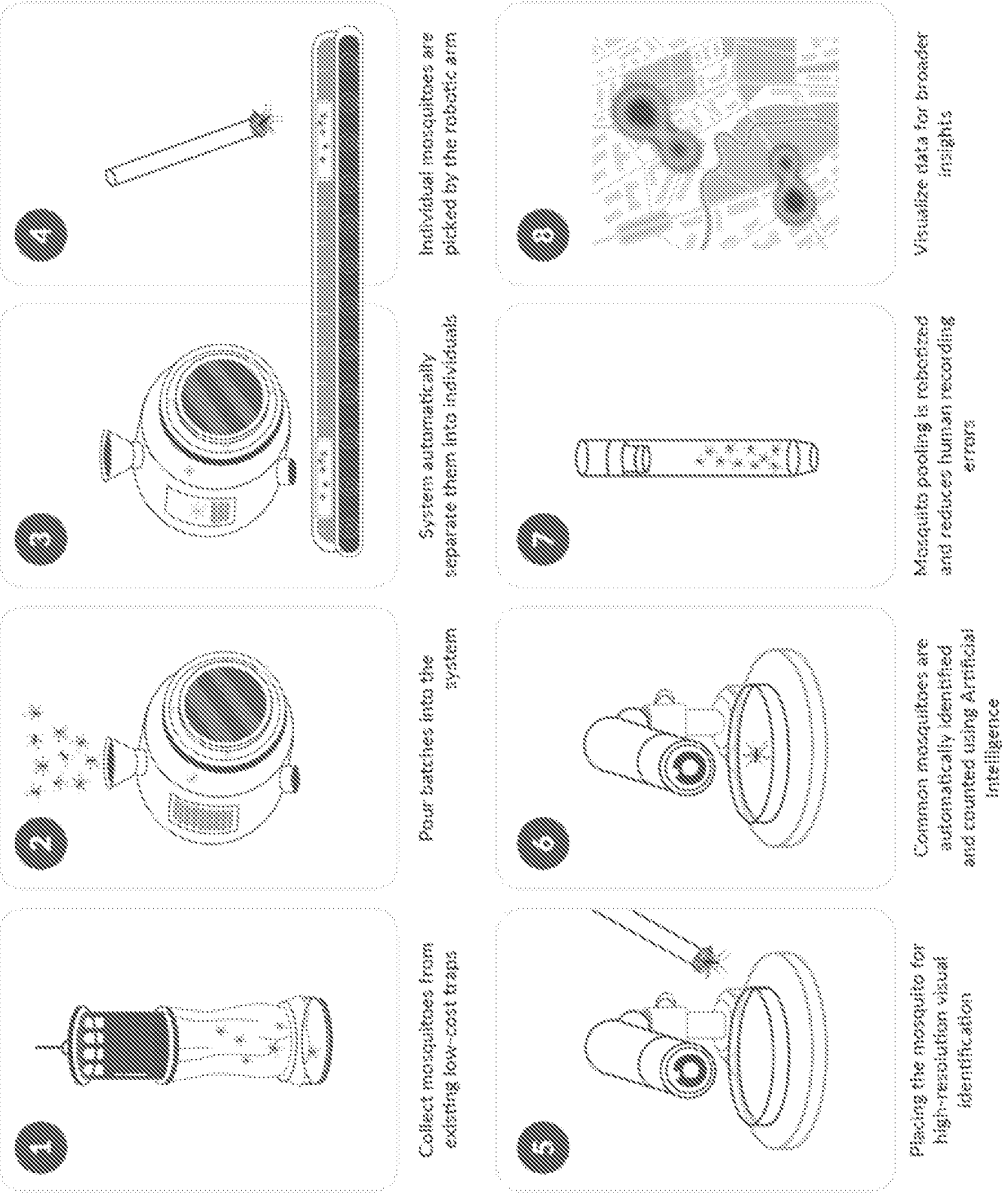


Fig. 1

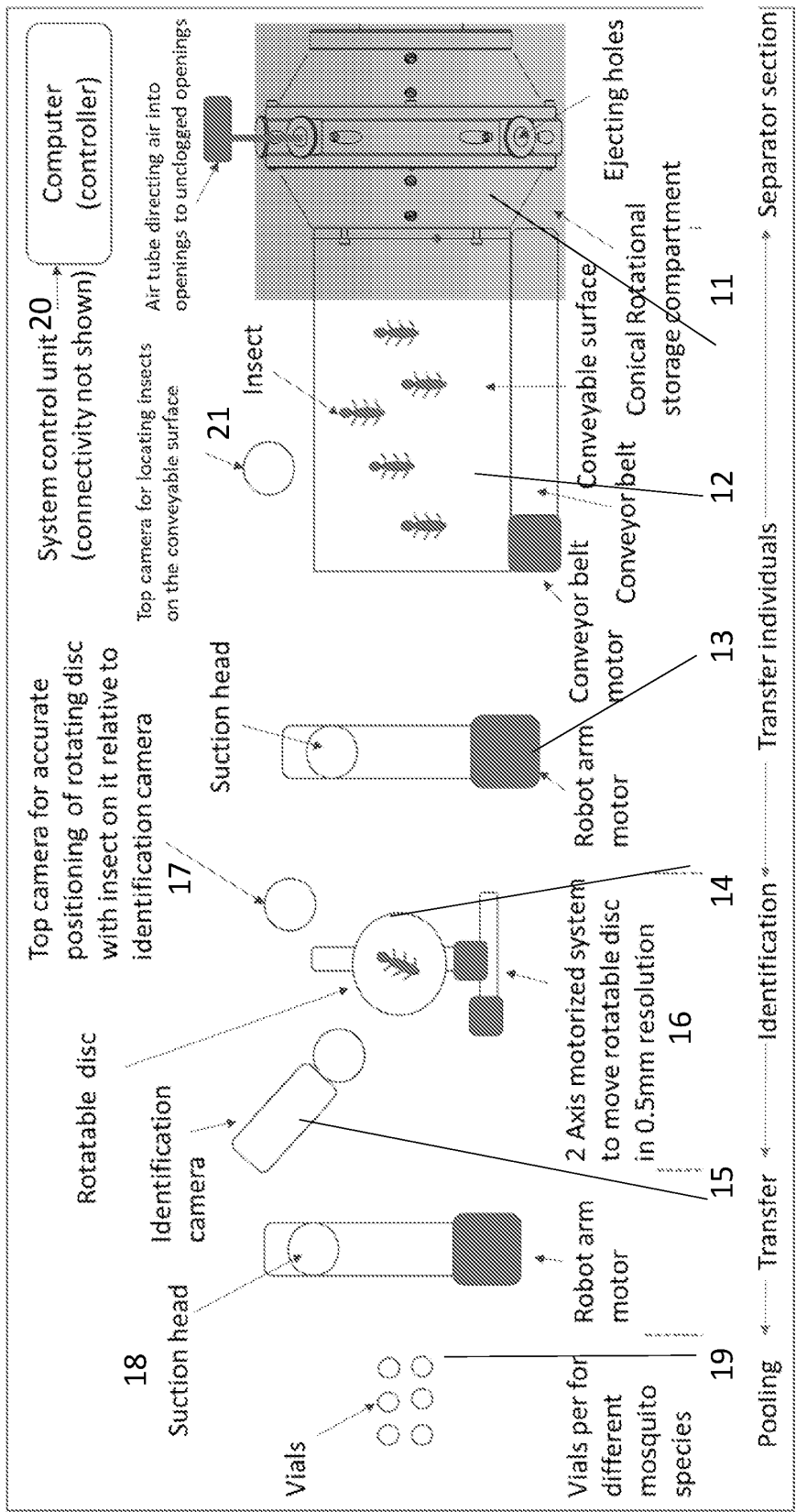


Fig. 2

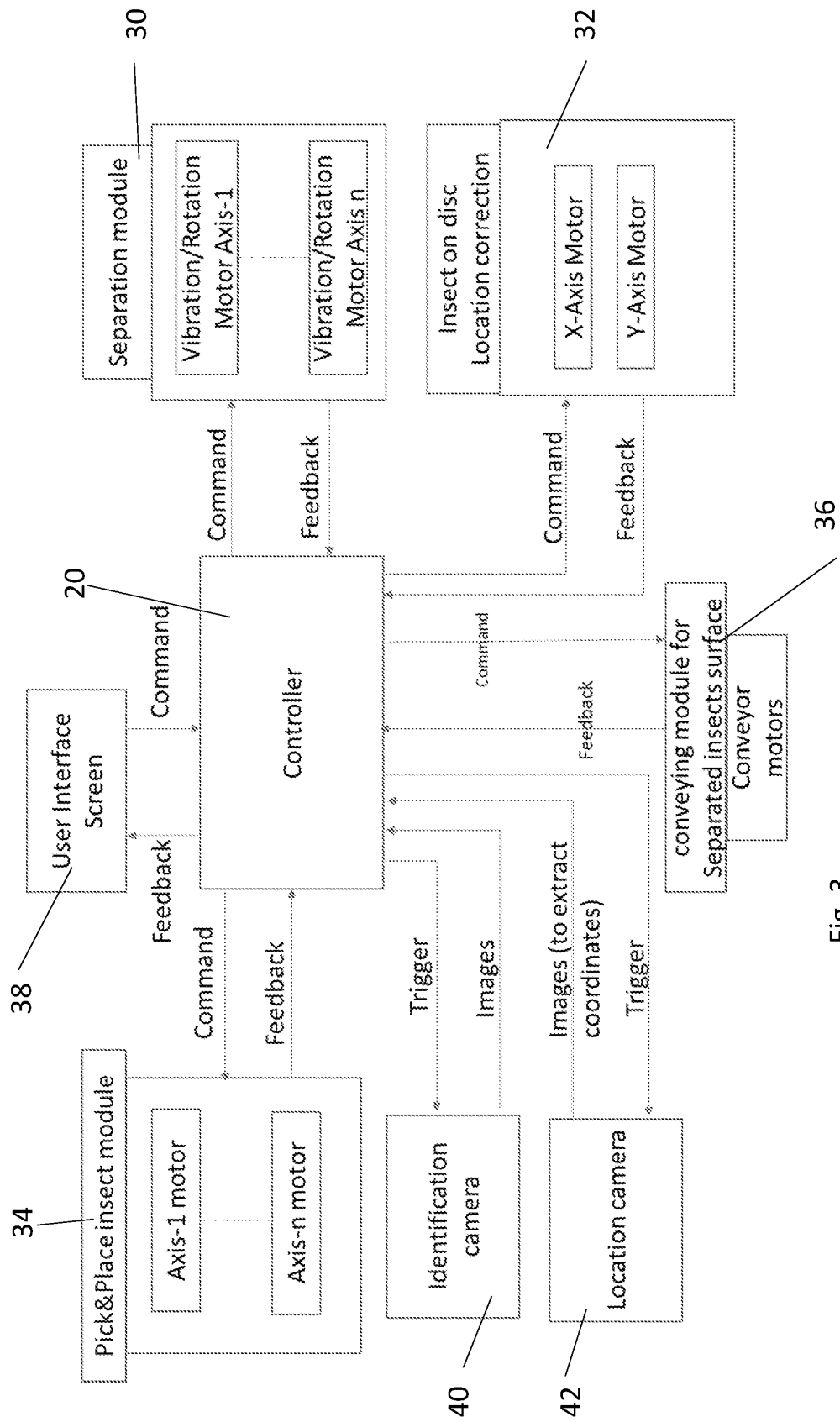


Fig. 3

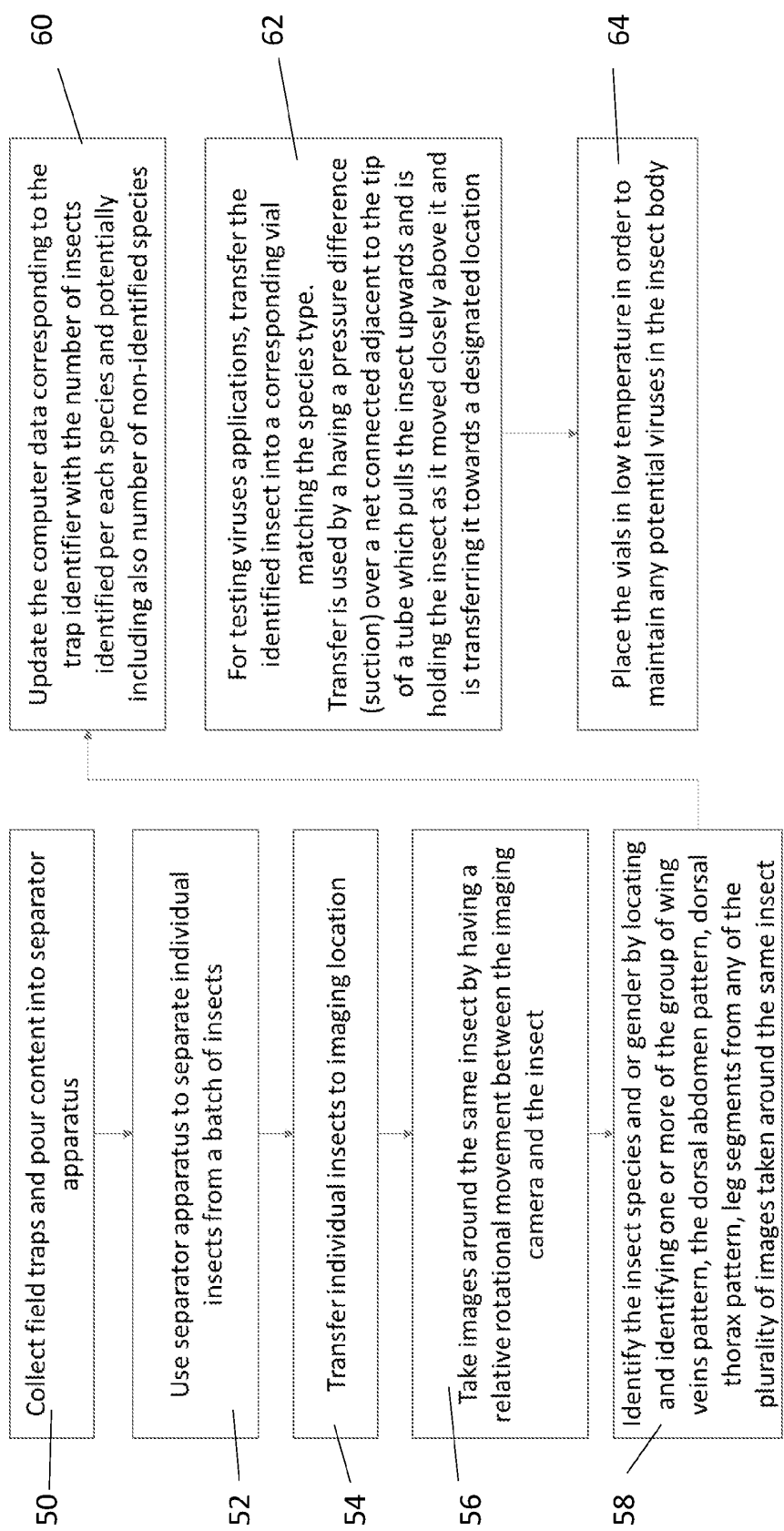


Fig. 4



Fig. 5A

Fig. 5B

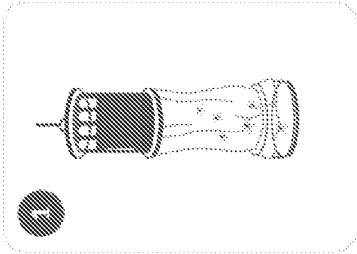


Fig. 6A

Collect mosquitoes from existing low-cost traps

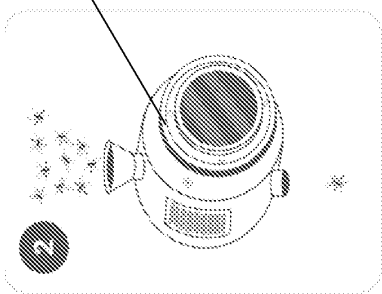


Fig. 6B

Pour batches into the system

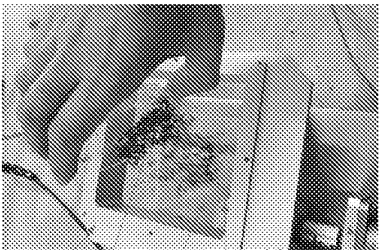


Fig. 6C

- 72 Insect compartment
- Insects
- 74 Separating surface
- 76 Separation exit holes
- 78 Vibrating motor

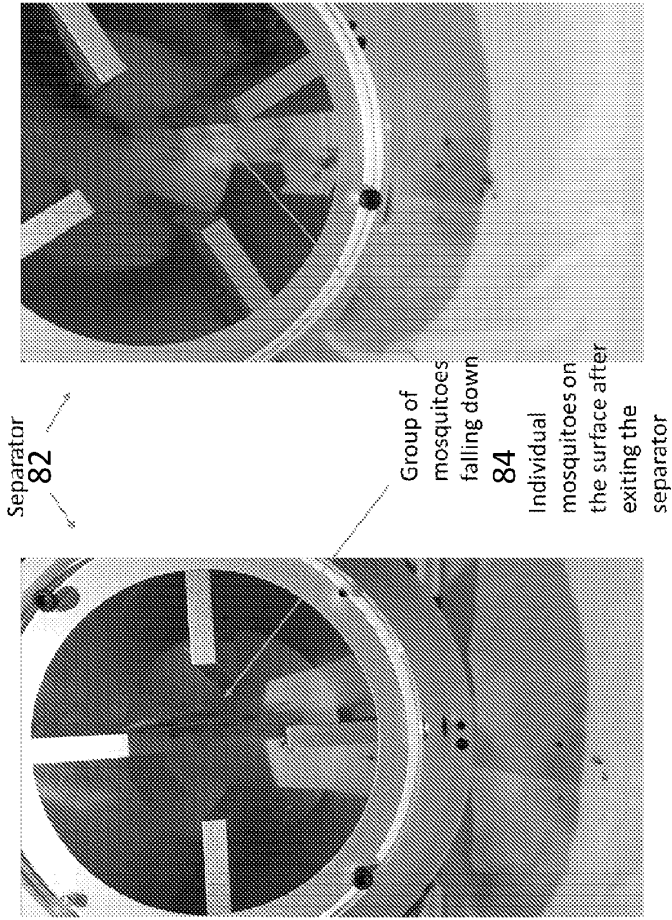
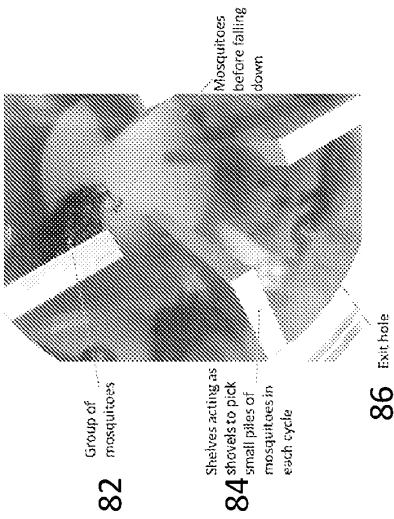
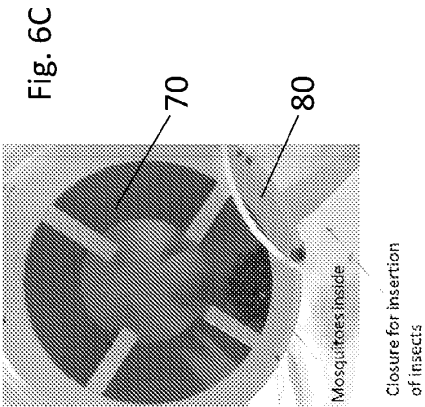


Fig. 6E

Fig. 6D

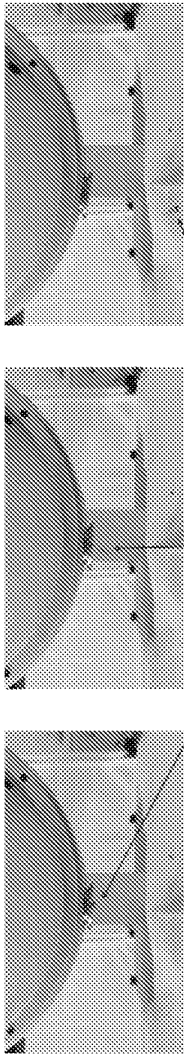


Fig. 6F

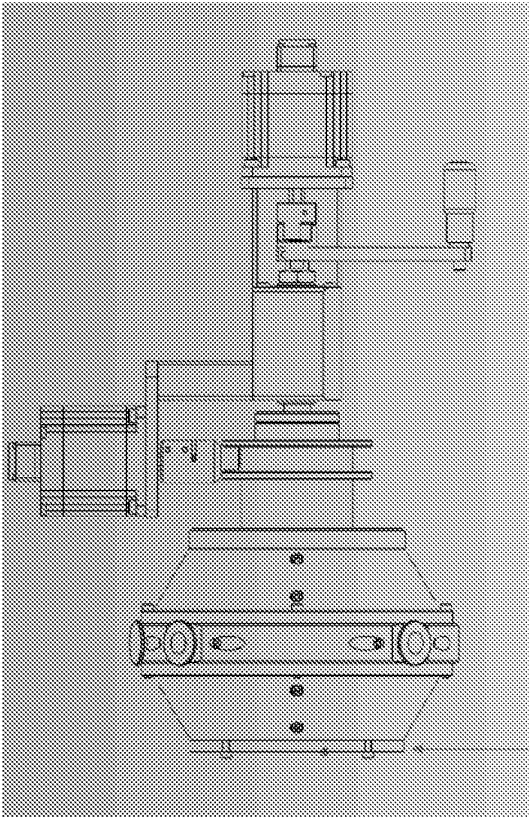
Single mosquito coming out from the separator ejecting hole



Mosquitoes that were ejected from the separator, as the surface moved, shows mosquitoes separated on from the other

Fig. 6G

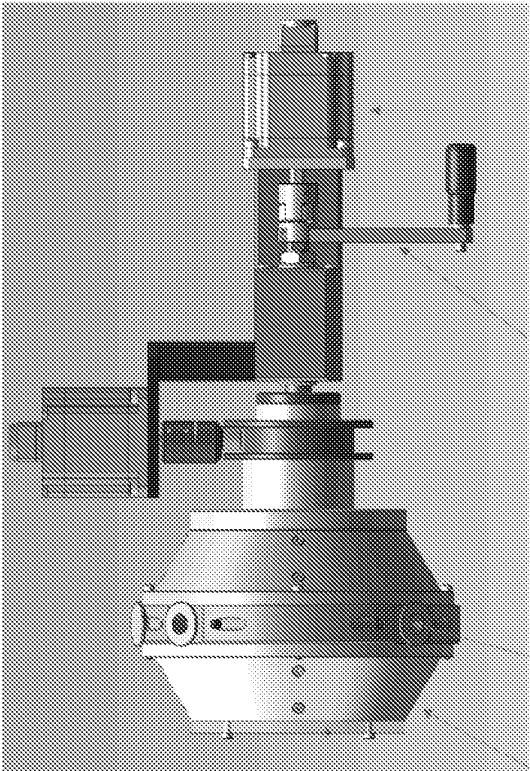
94
Rotational motor creating a linear movement to generate vibration, supporting clamped mosquitoes to fall separately throw the exit holes



Closure for pouring insects 80

Conical shape Storage compartment 72

Fig. 7A



Exit hole 86

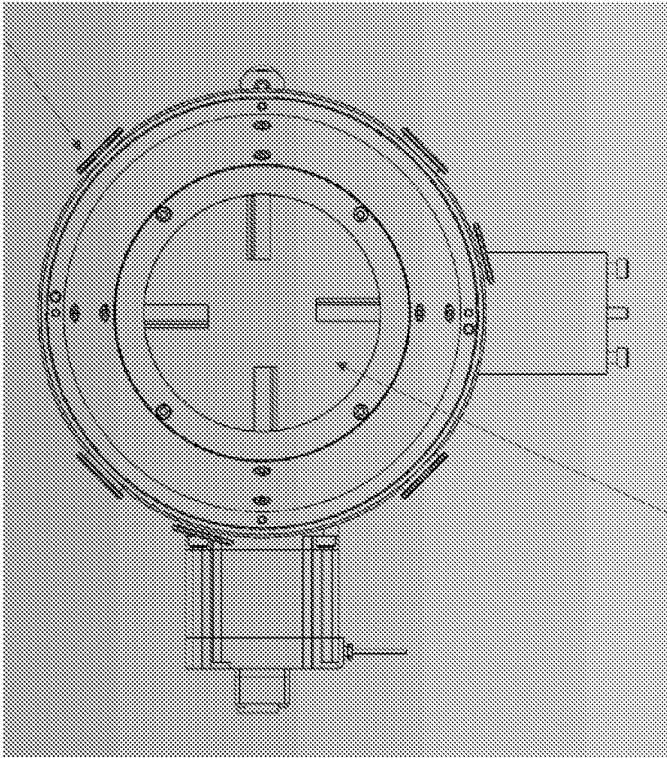
Optional held clamp to rotate the motor and the storage compartment 90

Rotational motor to rotate in both directions the storage with insects 92

Fig. 7B

Fig. 8A

82
Exit holes (at least one,
around the perimeter)



Rotational storage compartment

72

94
Rotational motor
creating linear vibration

92
Rotational motor for
rotating the storage
compartment

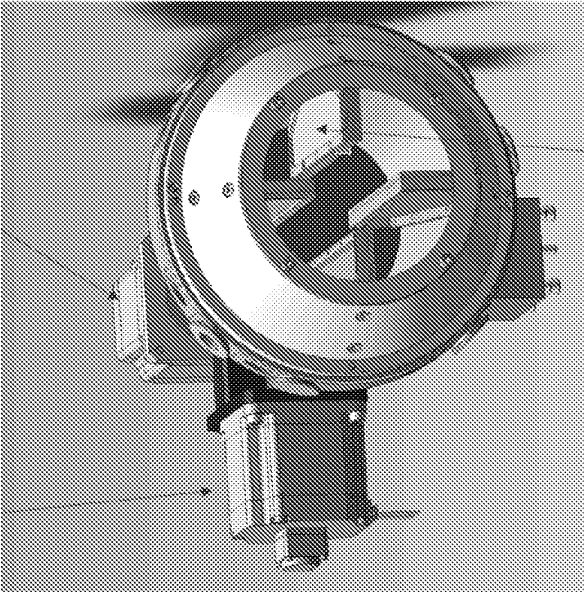
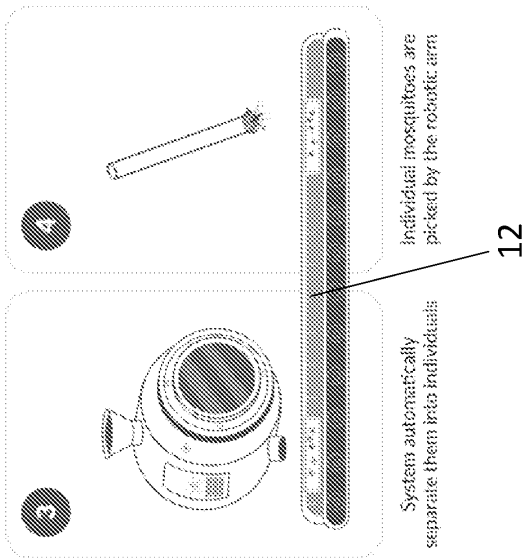


Fig. 8B
Internal shelves to hold batches of
mosquitoes, push them or grab them as the
compartment rotates, and then let them fall
downwards toward the exit holes below

84



110

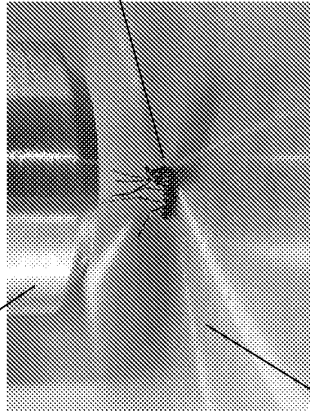


Fig. 11A

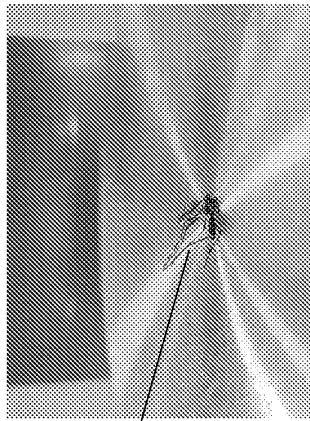


Fig. 11B

112

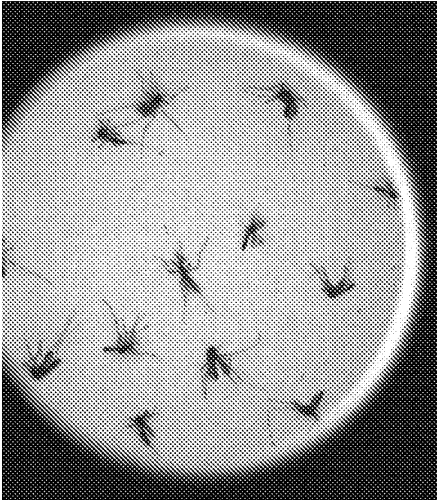


Fig. 13

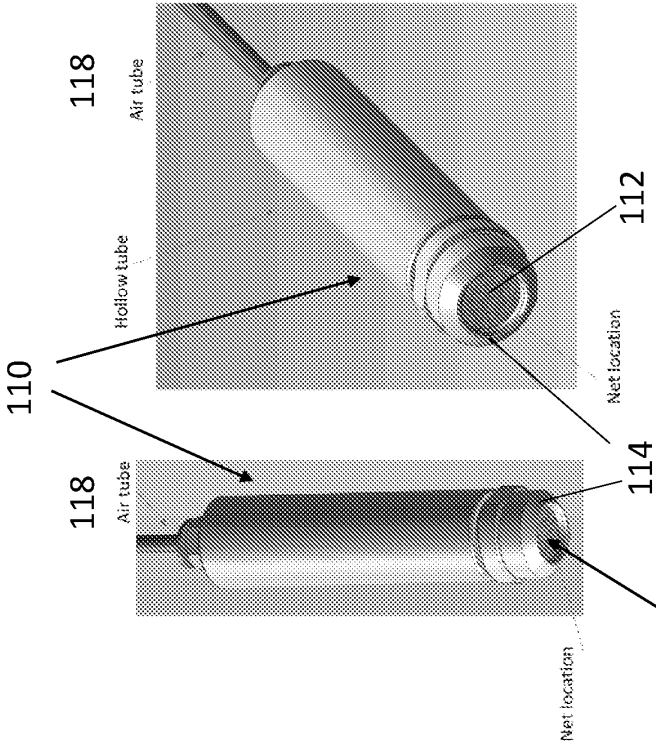
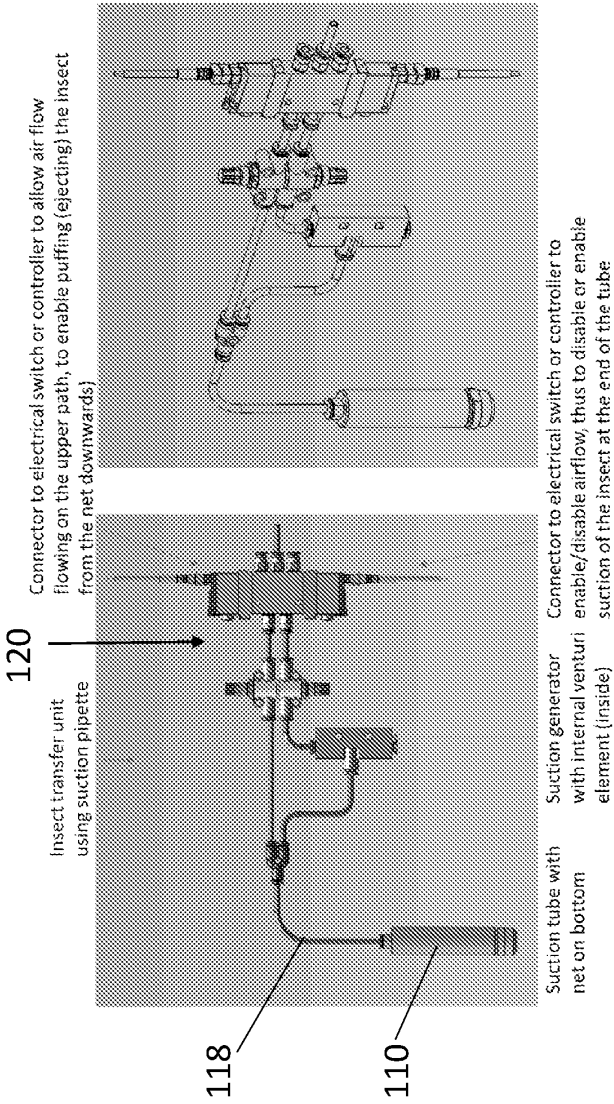
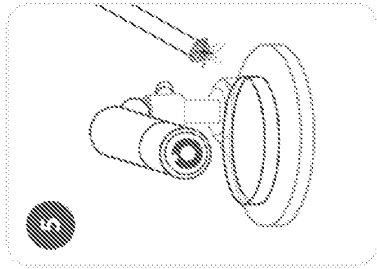


Fig. 10A Fig. 10B





Placing the mosquito for high-resolution visual identification

Fig. 14A

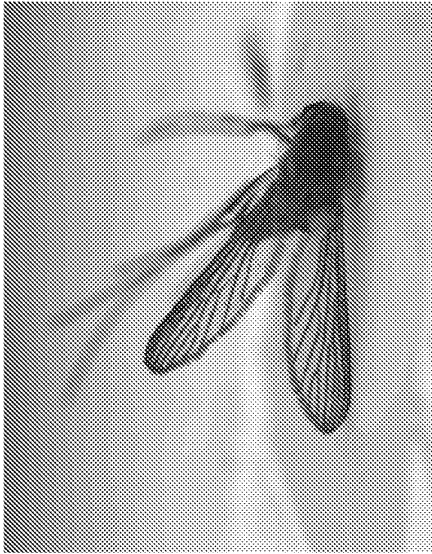


Fig. 14B

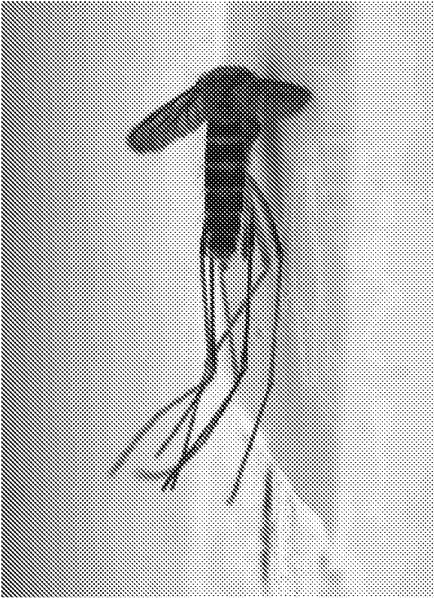
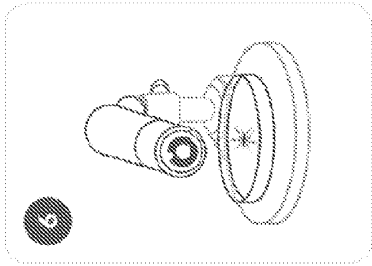


Fig. 14C



Common mosquitoes are
automatically identified
and speculated using Artificial
intelligence

Fig. 15A

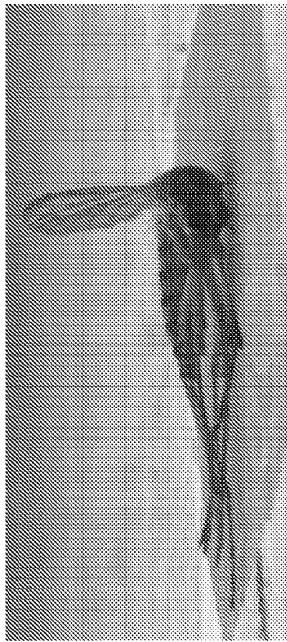


Fig. 15B



Fig. 15C

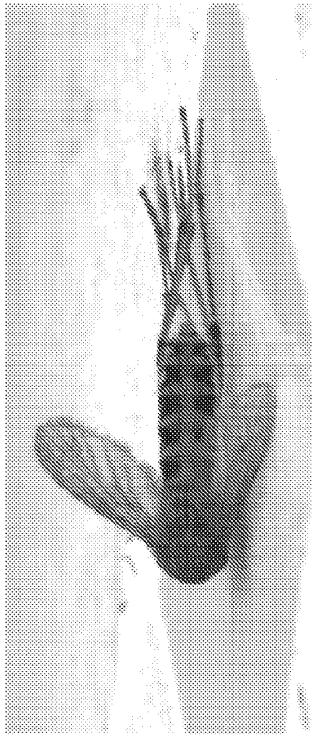


Fig. 15D

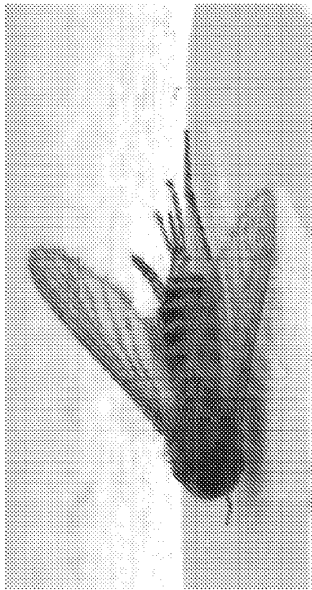


Fig. 15E

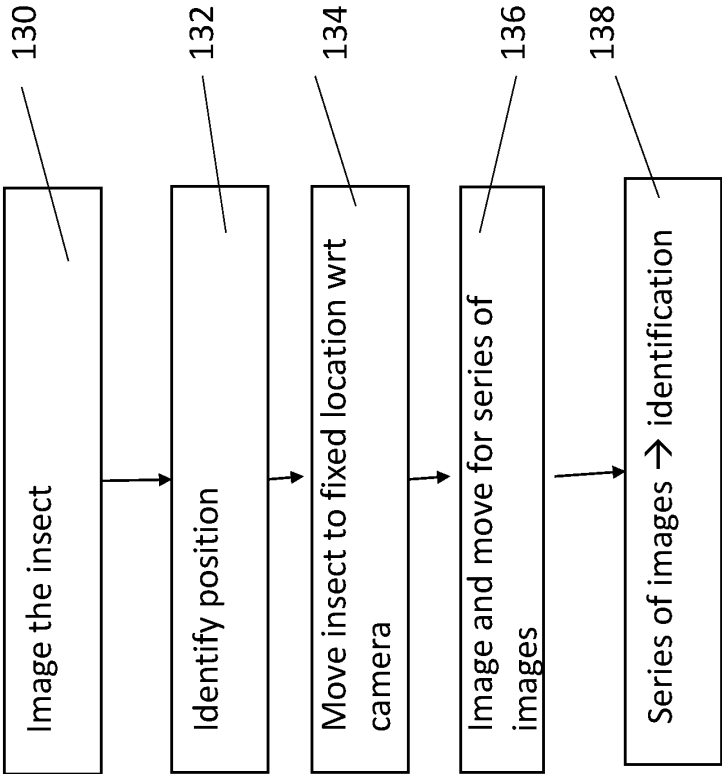
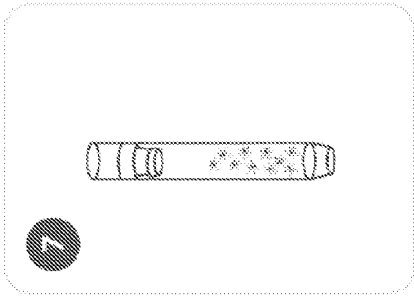


Fig. 16



Mosquito pooling is robotized and reduces human recording errors

Fig. 17A

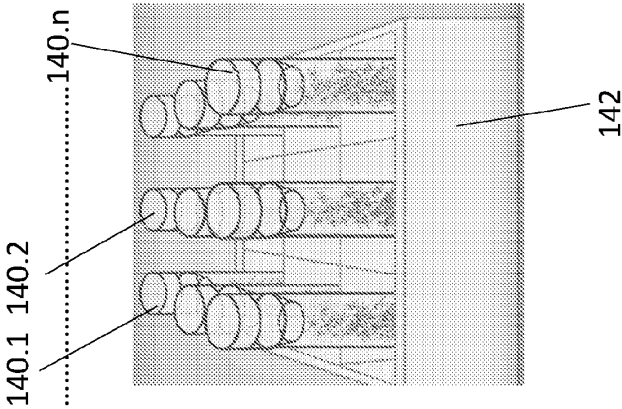


Fig. 17B

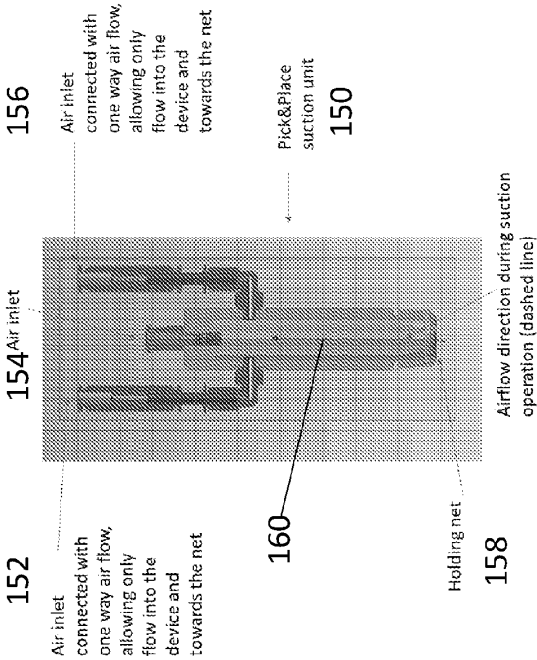


Fig. 18A

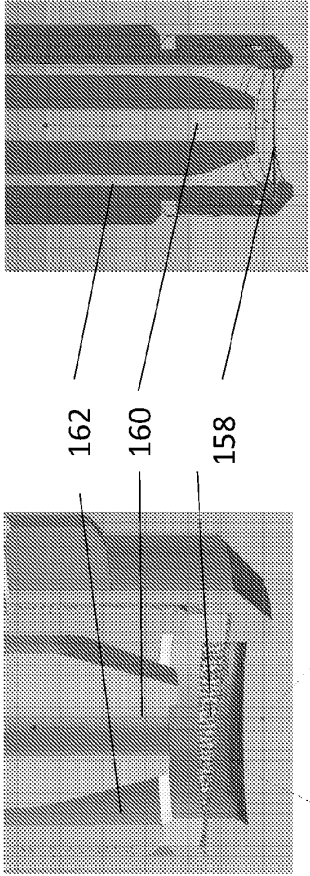


Fig. 18B

Airflow direction during suction operation (dashed line)

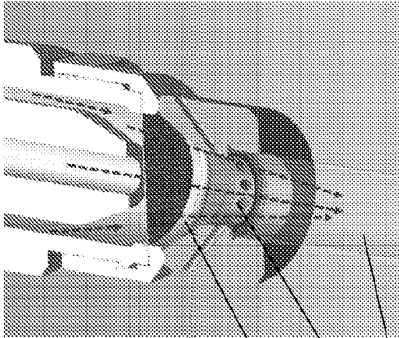


Fig. 18E

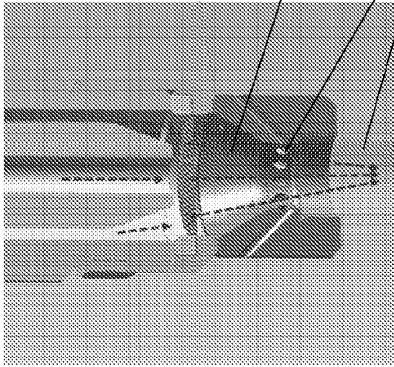


Fig. 18D

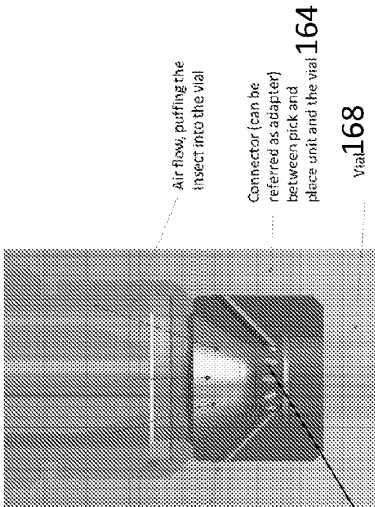


Fig. 18F

Exhaust area, letting air getting out from the vial as insects are puffed with air into the vial, and the air can then escape from such hole (or holes)

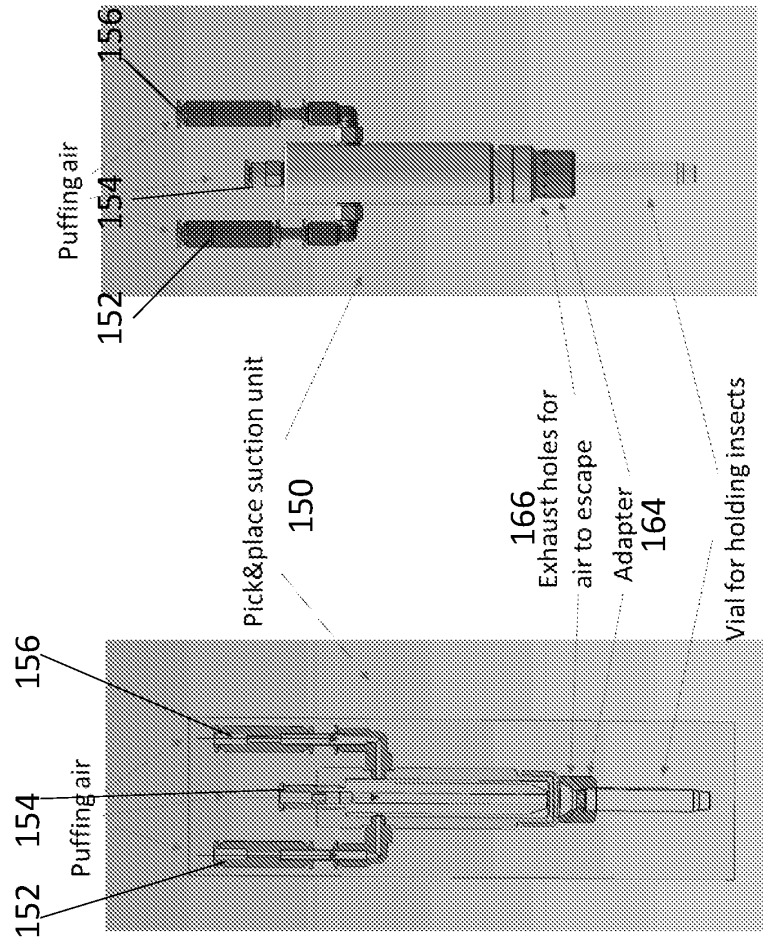


Fig. 18G

Fig. 18H

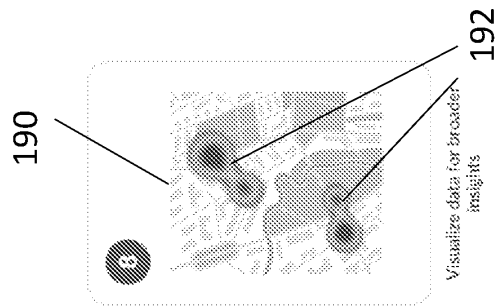


Fig. 20

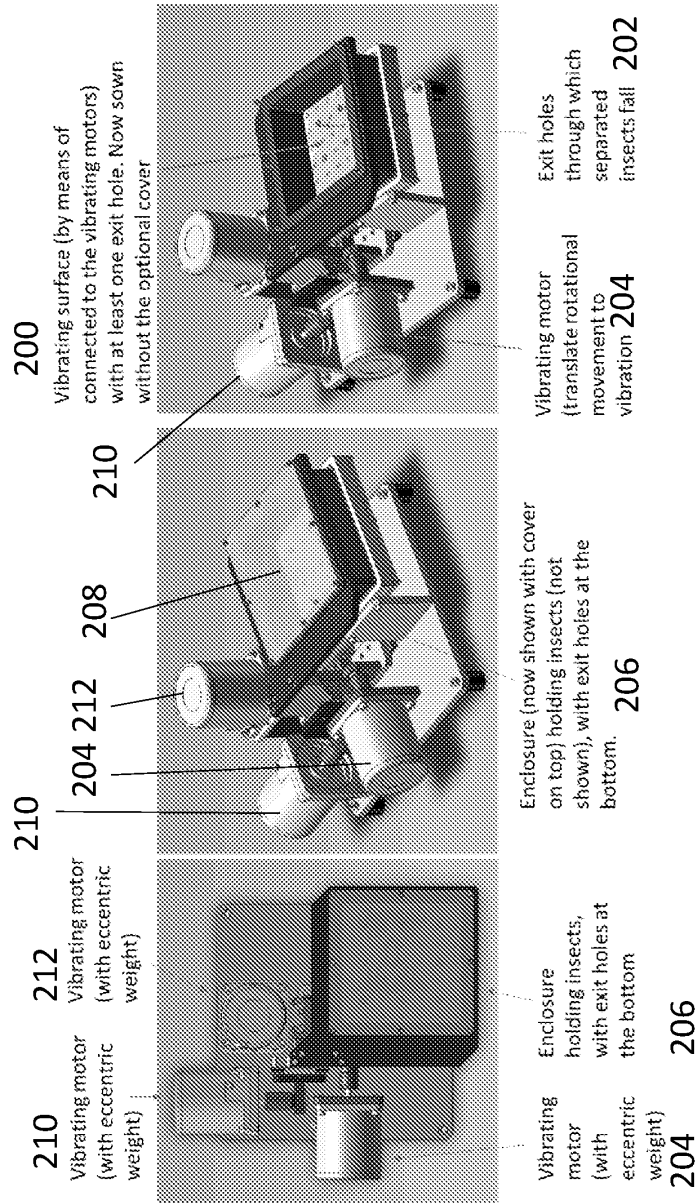


Fig. 21A

Fig. 21B

Fig. 21C

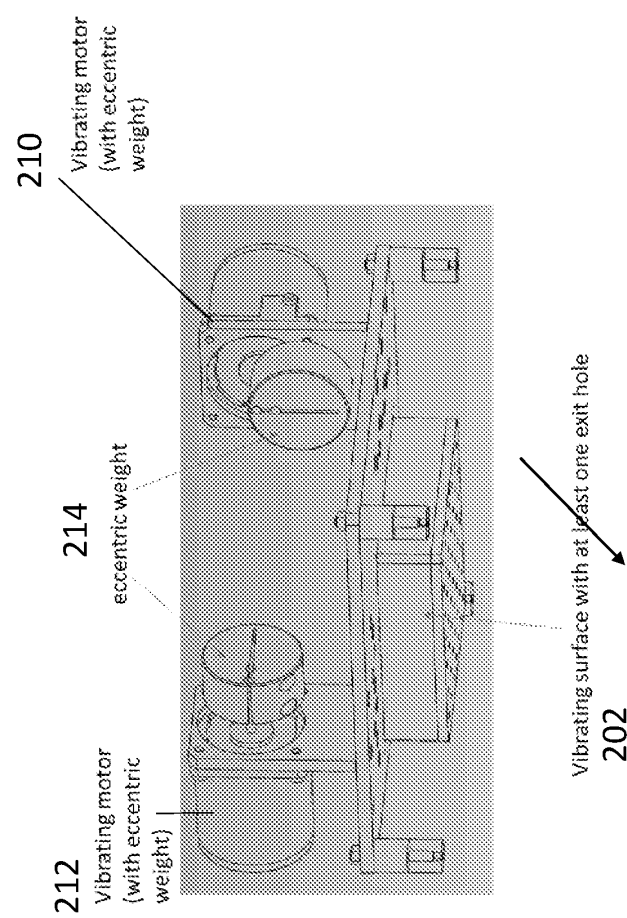
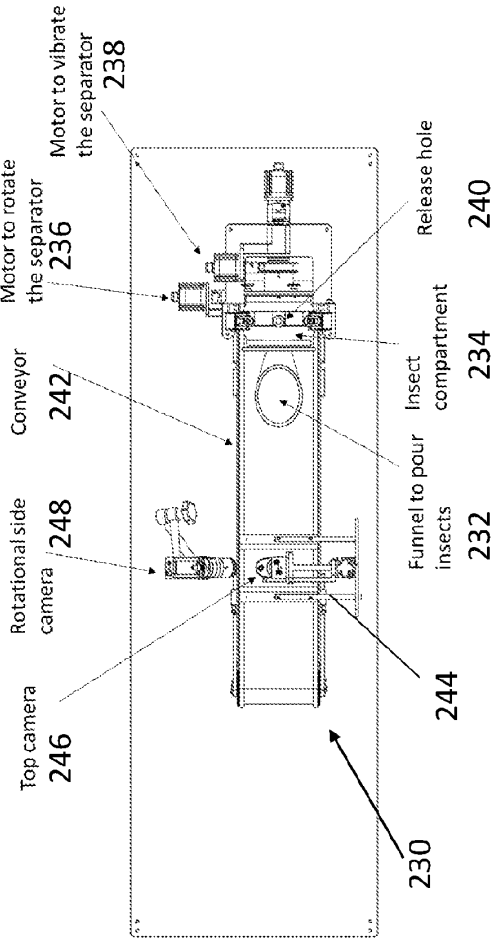
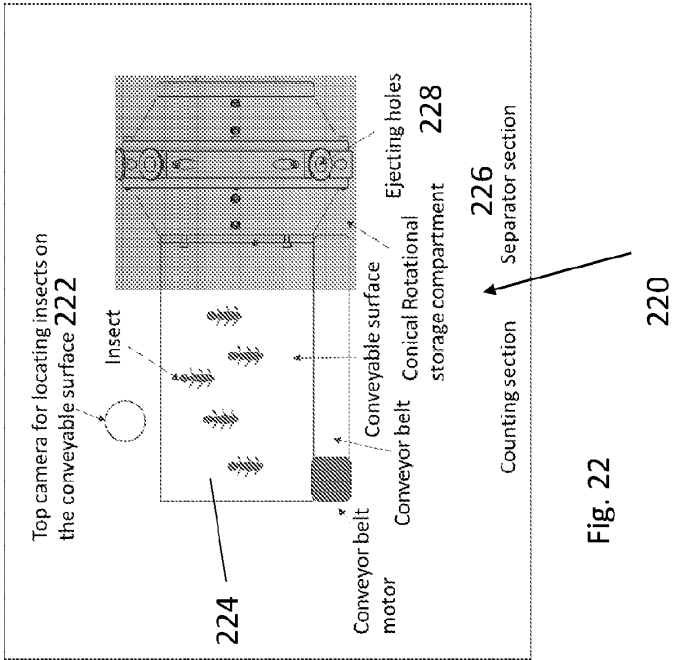


Fig. 21D



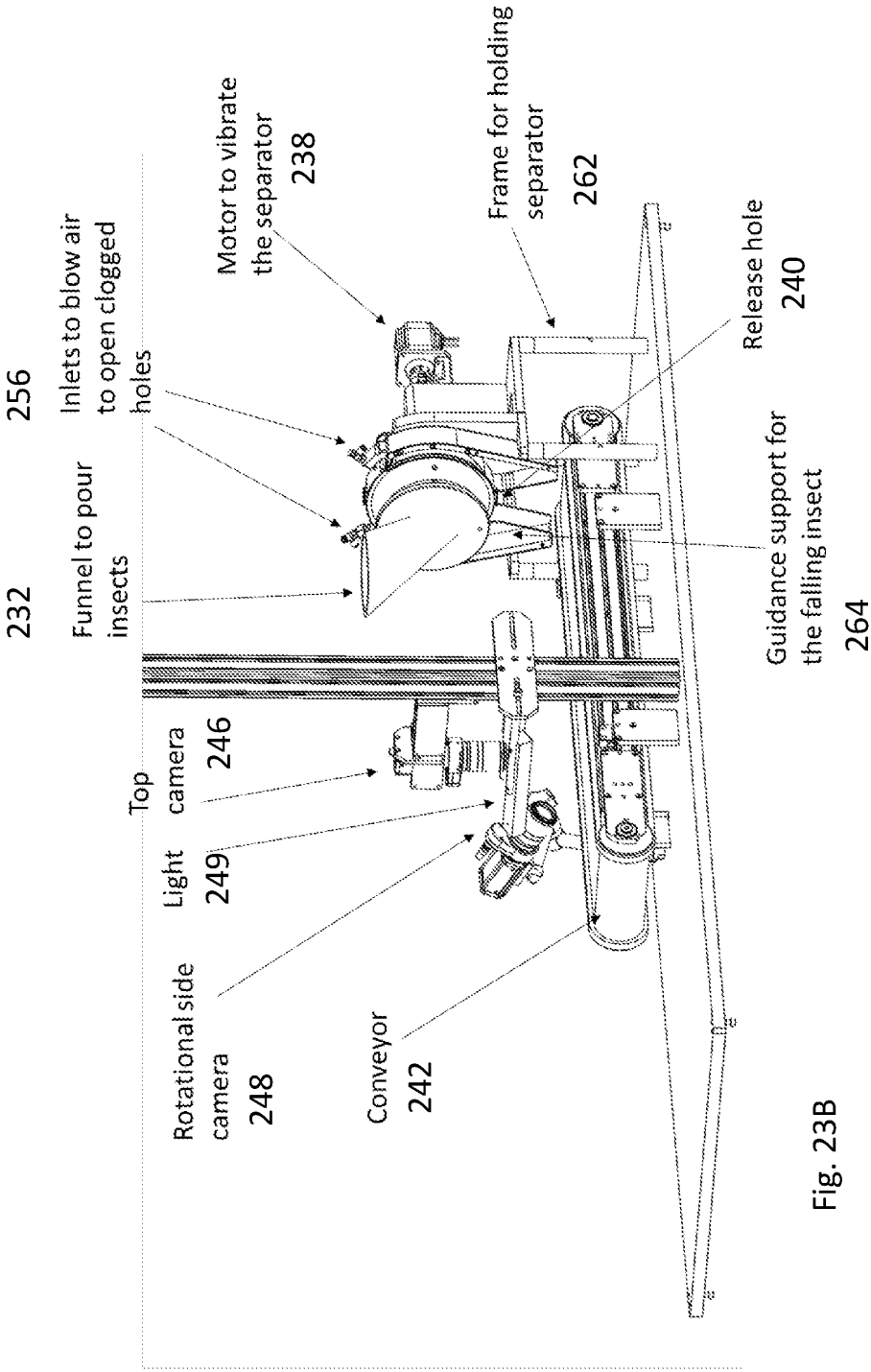


Fig. 23B

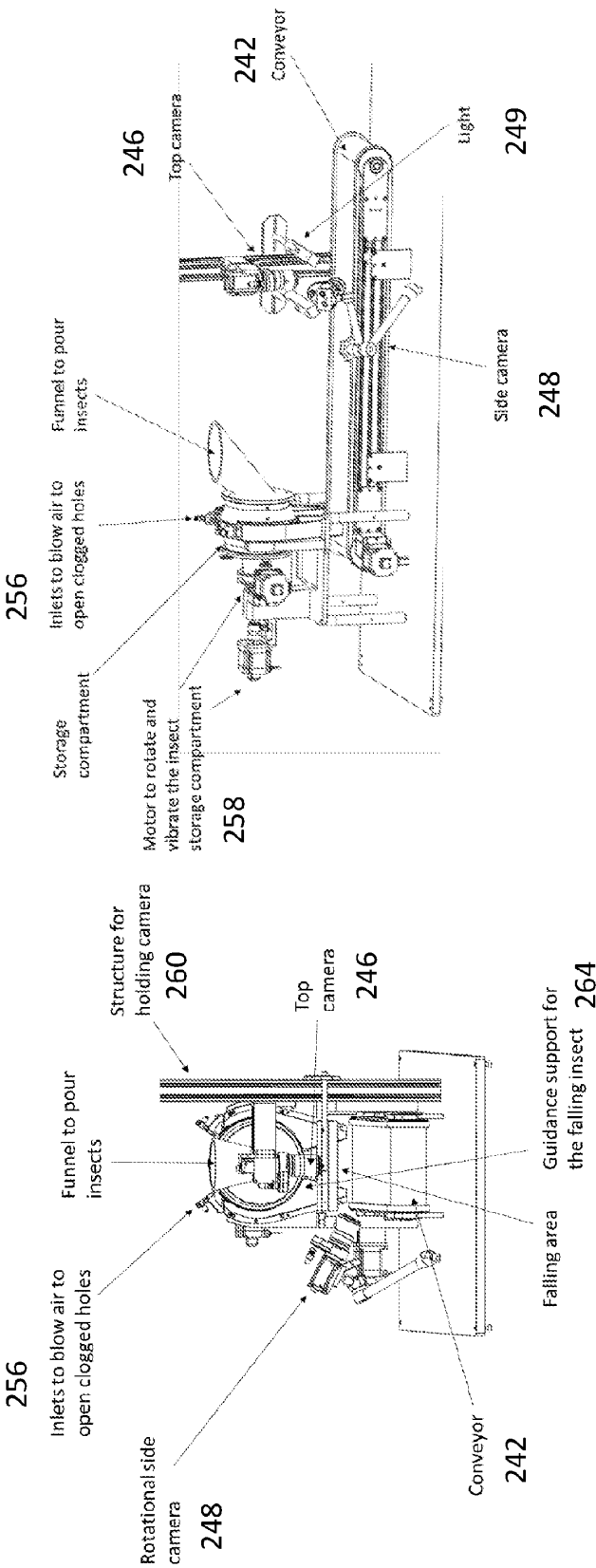
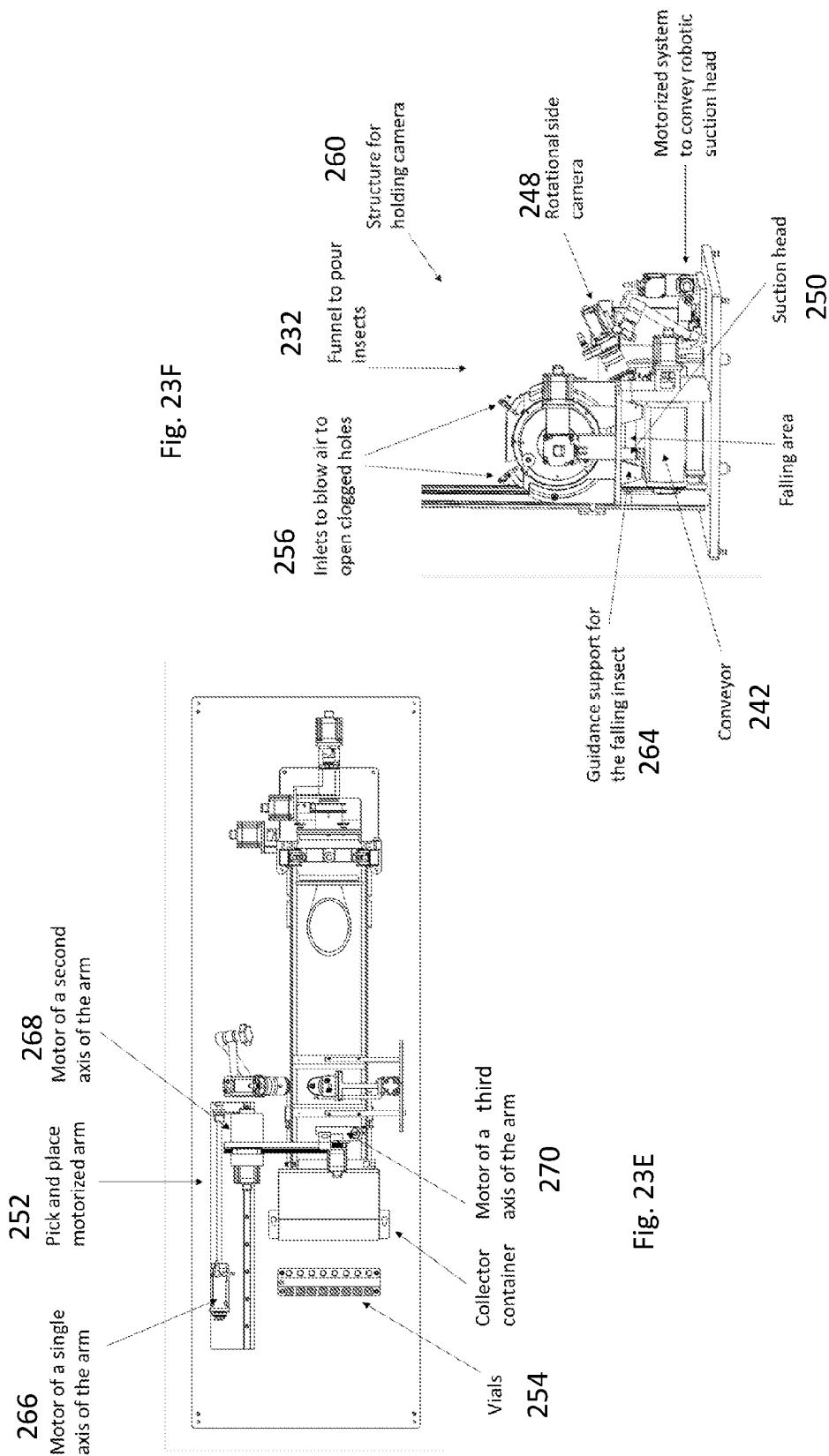
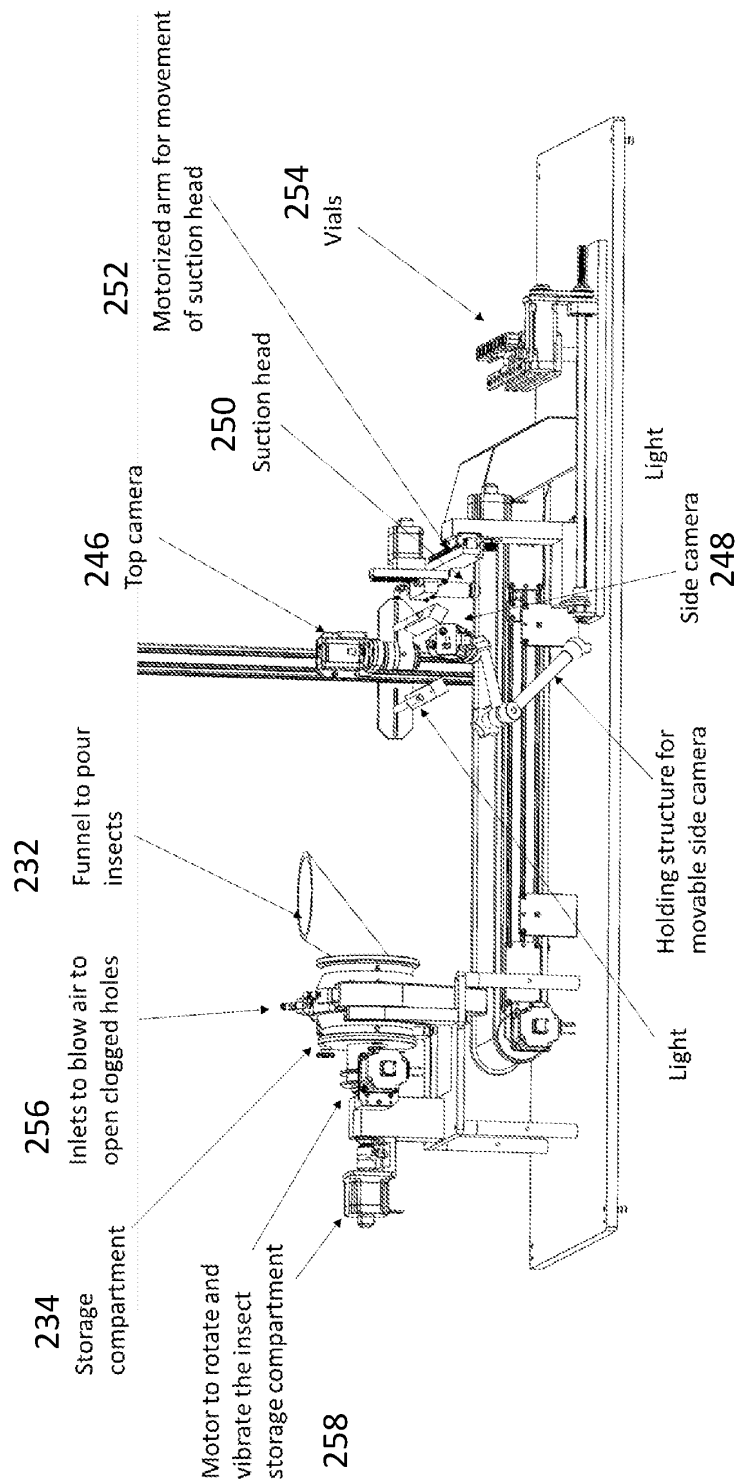
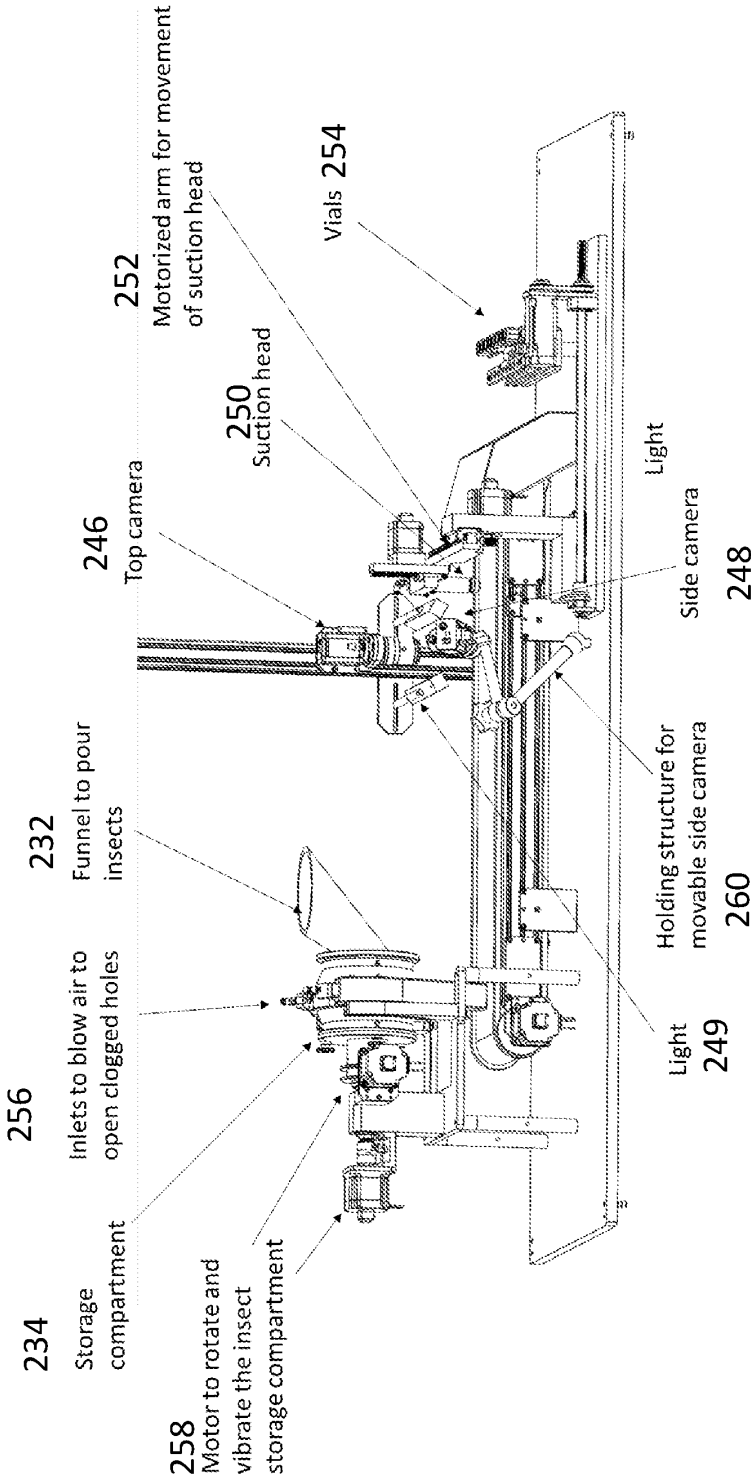


Fig. 23D

Fig. 23C







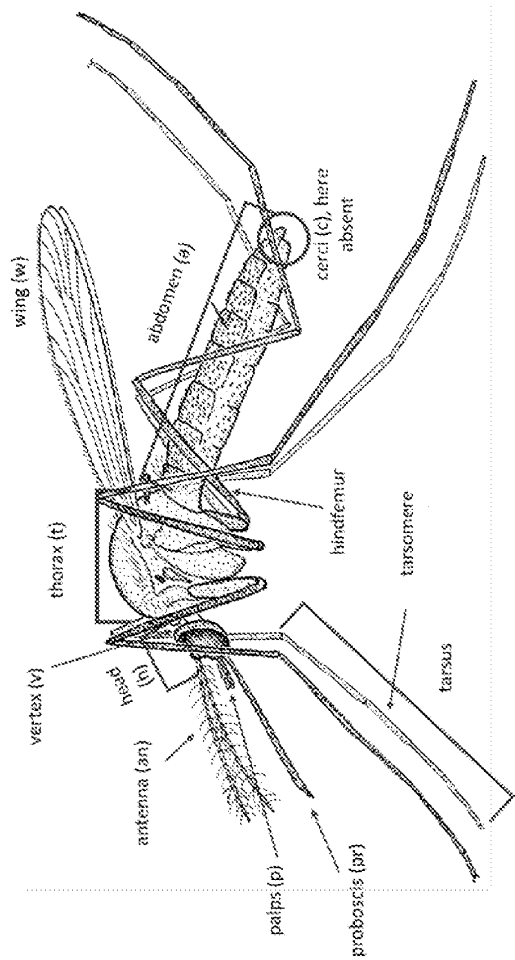


Fig. 24

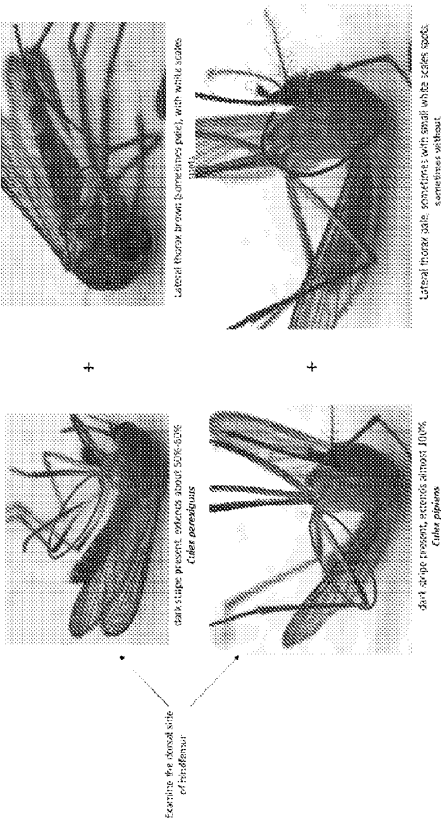
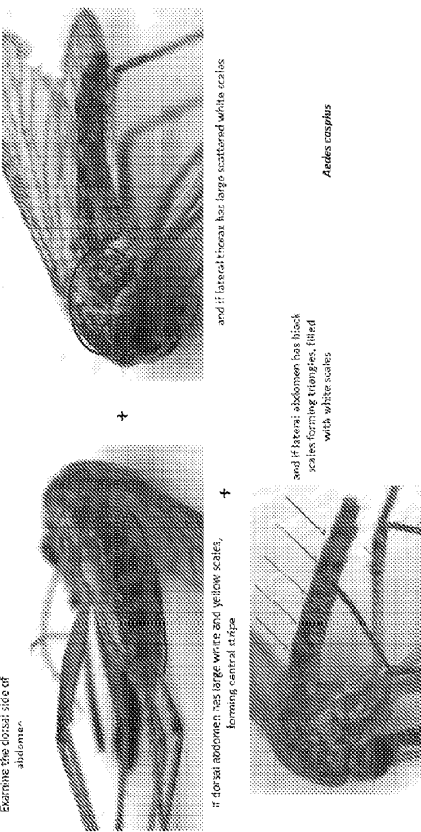


Fig. 25B



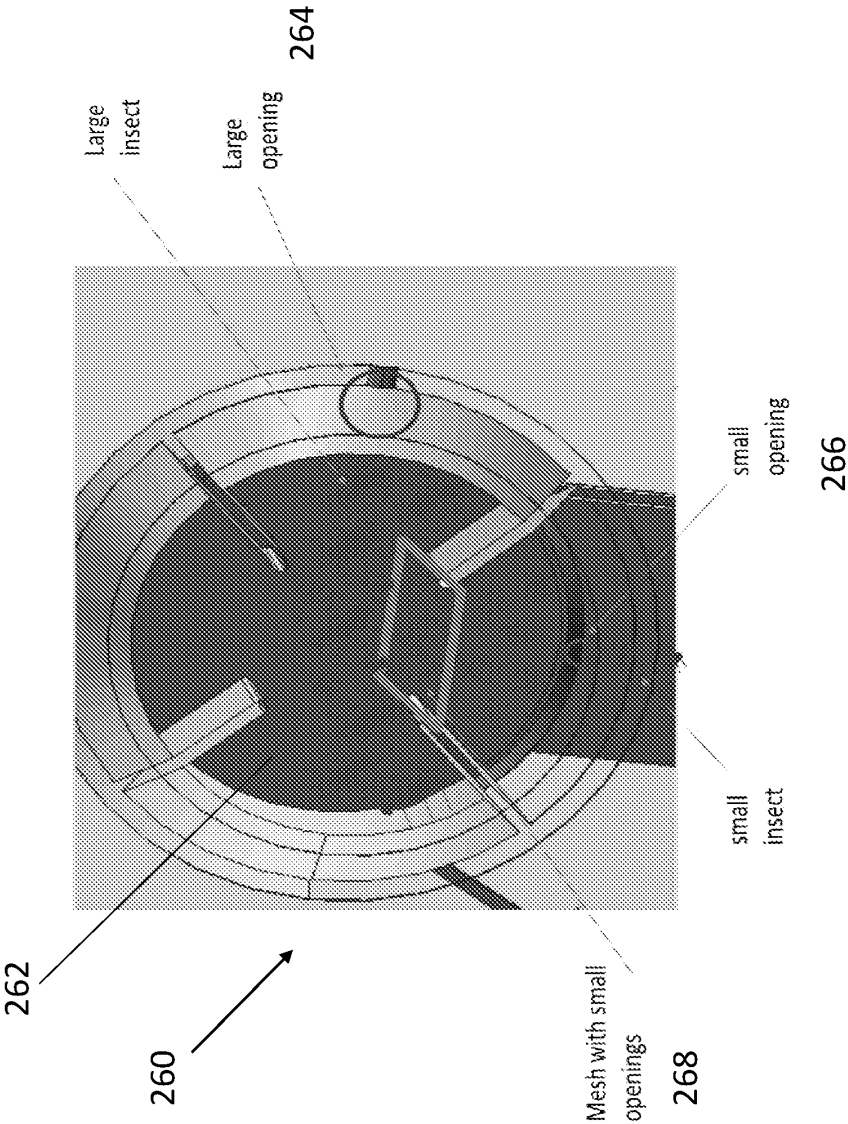


Fig. 26