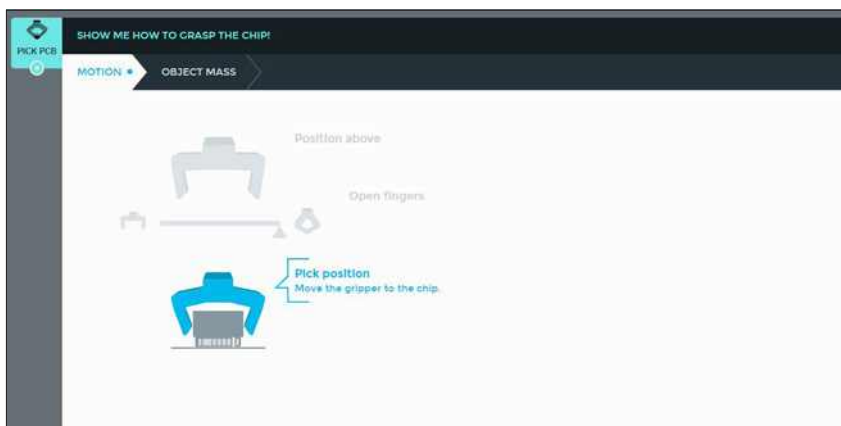


Programming with one swipe

A Task can be composed in Desk by arranging Apps, which are then parametrized directly at the robot in the operating area.



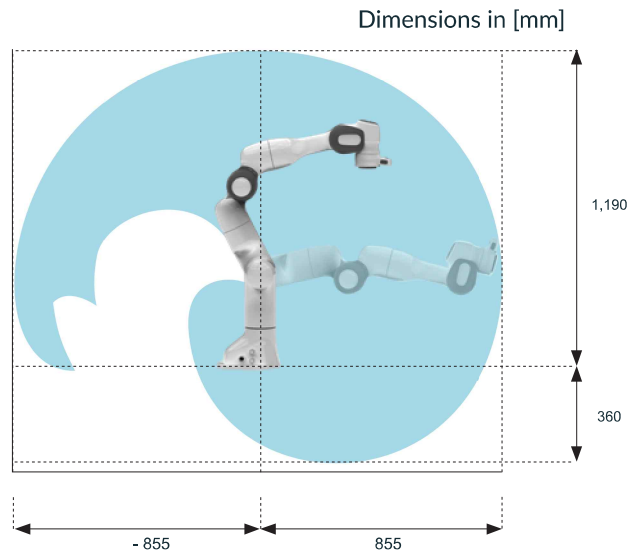
Pilot is the interface integrated in the Arm, which allows for smooth interaction between Arm and Desk.

Teaching by demonstration

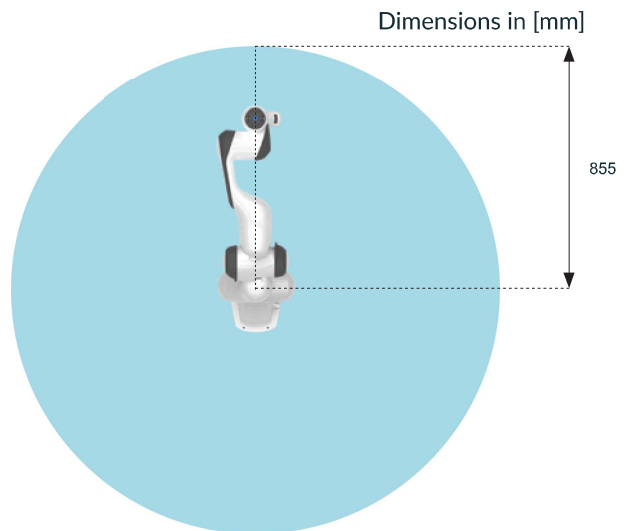


# SPECIFICATION

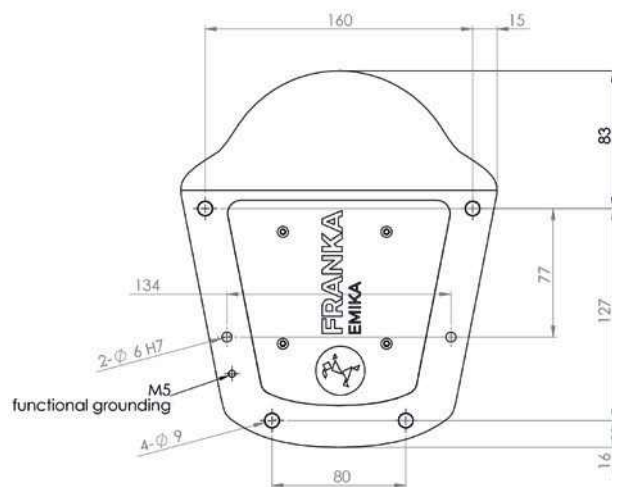
Operating space  
Side view of motion range



View from above

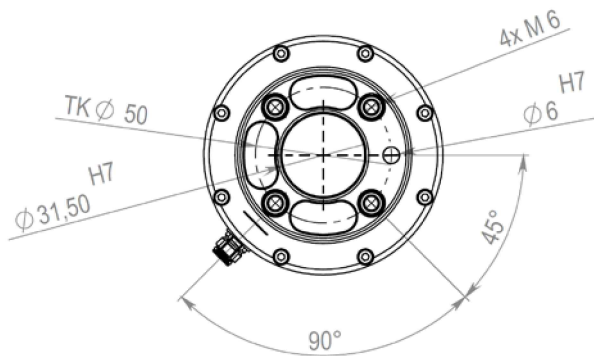


Footprint  
View from below

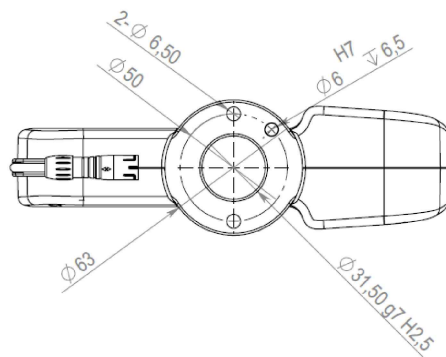




Base of the Arm

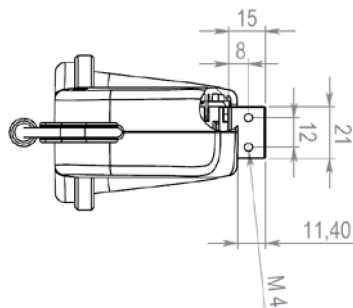


End effector flange



For optional mounting of the Hand to the end effector flange the following tools are required:

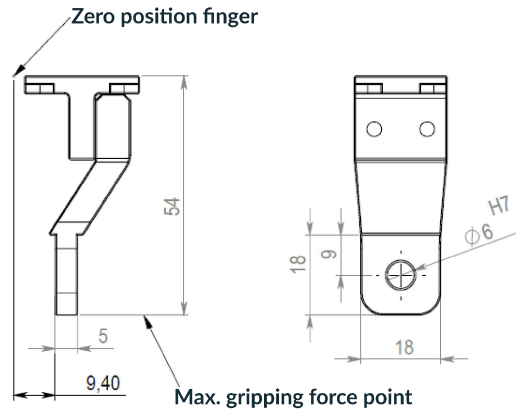
- Assembly material (included in scope of delivery of the Hand)
  - 2 x DIN7984 M6X12 ST 8.8 screw
  - 1 x ISO2338B 6X10 H8 A2 cylindrical pin
- Tools (not included in scope of delivery of the Hand):
  - Hex key, size M4



Interface Hand to fingers

# SPECIFICATION

Interface finger to fingertips



- These fingers are included in the scope of delivery of the Hand and are suitable for being mounted to the Hand
- Should you design and mount other fingers to the Hand, the following needs to be noted:
  - Carry out a risk assessment and implement the measures resulting from it
  - Gripping of an object at a distance of the finger to the Hand will lead to tilting loads. The Hand is designed and tested for a finger length of 54mm.

Mechanical data of Hand

The following 4 data sets are to be set in Desk, as soon as the Hand has been attached to the Arm.

e.g. at the Arm's start up: for more information, see chapter: Start-up

Weight of hand [kg]

0.73

center of mass of Hand to end effector flange [m]

-0.01 | 0 | 0.03

Inertia sensor [kg x m<sup>2</sup>]

0.001	0	0
0	0.0025	0
0	0	0.0017

Transformation matrix of end effector flange to Hand (center point of finger tips when closed)

0.707	0.707	0	0
-0.707	0.707	0	0
0	0	1	0.1034
0	0	0	1