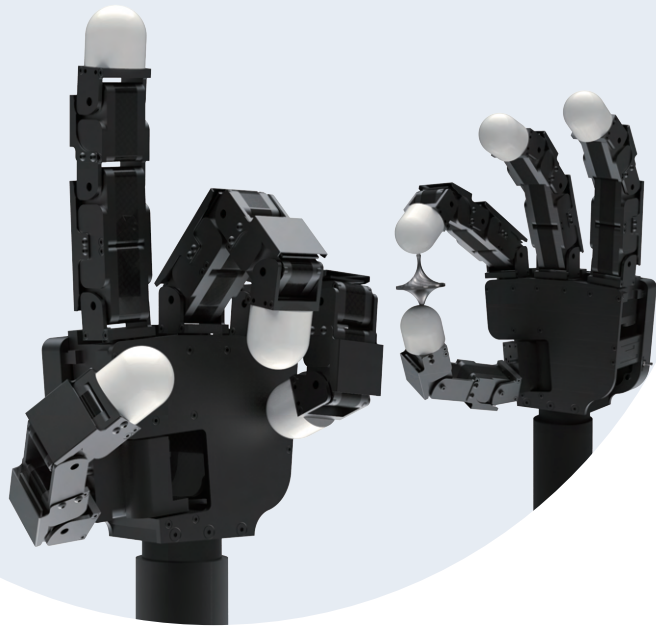


Allegro Hand

Highly Adaptive Robotic Hand with DOF

- Light weight and portable anthropomorphic design
- Low-cost dexterous manipulation with applicaitons in research and industry
- Multiple ready-to-use grasping algorithms capable of handling a variety of object geometries





Specifications

Number of Fingers	Four (4) fingers including a thumb	
Degrees of Freedom	4 fingers x 4 = 16	
Actuation	Type	DC Motor
	Gear Ratio	1:369
	Max. Torque	0.70 Nm
	Max. Joint Speed	0.11sec/60degree
	Total	1.08 kg
Mass	Finger	0.17 kg
	Thumb	0.19 kg
	Total	1.08 kg
Joint Resolution	Measurement	Potentiometer
	Resolution(Nominal)	0.002 deg
Communication	Type	CAN
	Frequency	333 Hz
Payload	5kg	
Power Requirement	12~24V, 120W	

Purchase Options

Included

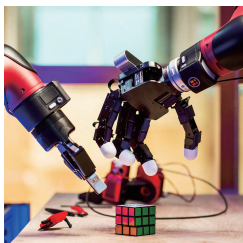
- Allegro Hand (left or right)
- Allegro Hand Console Application (linux/Windows) Download Instructions
- Allegro Hand Console Application (linux/Windows) Single-user license
- AllegroHand stand
- CAN/Power cable *terminated at hand-end only
- 2mm hex wrench
- Spare screws and wire terminals
- Hard plastic case
- Power supply

System Requirement

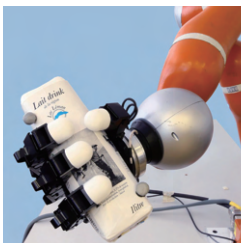
CPU	Intel Core™ 2 Duo or higher
RAM	2GB or more
HDD	2GB or more
Graphics	OpenGL 3.0 HW Acceleration enabled
OS	64Mb of videos RAM or higher
CAN Interface	MS Windows XP, 7 & 8, Linux (ROS)
Other Software	NI / Peak*
	*Any CAN interface can be user-configured for use with the AllegroHand.
	Windows: Visual Studio *optional

Cooperation with Clients world wide

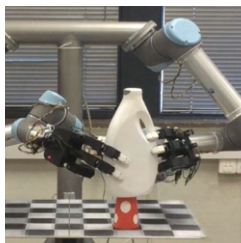
Allegro Hand have worked with various research institutes and corporations.



Facebook
Facebook's robotic institute AI with robot machines



EPFL
Ultra-fast robotic hand catching the object on the fly



UPC
Grasping bulky objects with two anthropomorphic hands

University



Corporate Research Institute

