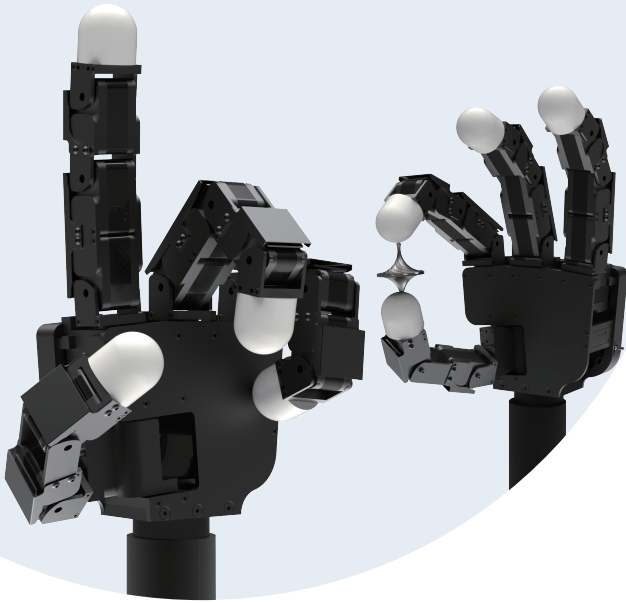


Allegro Hand

- Lightweight and portable anthropomorphic design
- Cost-effective dexterous manipulation with applications in research and industry
- Multiple ready-to-use grasping algorithms capable of handling a variety of object geometries





Allegro Hand is a Cost-effective and highly adaptive robotic hand

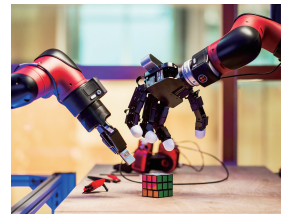
With four fingers and sixteen independent torque-controlled joints, it's the perfect platform for grasp and manipulation research

Specifications

Number of Fingers	Four (4) fingers, including thumb	
Degrees of Freedom	4 fingers x 4 = 16 (Active)	
Actuation	Type	DC Motor
	Gear Ratio	1:369
	Max. Torque	0.70 (Nm)
	Max. Joint Speed	0.11(sec/60degree)
Weight	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	5 (kg)	
Power Requirement	12, 24, 48Vdc / 100W	

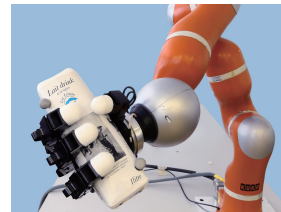
Cooperation with Clients world wide

Allegro Hand have worked with various research institutes and corporations.



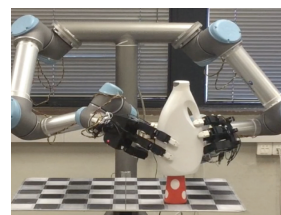
Meta

Meta's robotic institute
AI with robot machines



EPFL

Ultra-fast robotic hand
catching the object
on the fly



UPC

Grasping bulky objects
with two anthropo-
morphic hands

Research Partners



Stanford



YALE

KAIST



KRISs

