

qbrobotics*

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technical data

MECHANICAL	UNIT	NOMINAL	MIN	MAX
weight	[kg]	0.77	_	_
joints	[#]	19	_	_
motor	[#]	1	_	_
power grasp payload	[kg]	_	_	2.1
pinch grasp payload	[kg]	_	_	1.1
hanging payload	[kg]	_	_	5.0
full closing time	[s]	_	_	1.1

INERTIAL 1	UNIT	х	Y	Z
center of mass, open	[mm]	2.7	82.9	-0.5
center of mass, closed	[mm]	1.3	76.6	3.5

 1 all values refer to the right version, mirrows the ${f x}$ value for the left one

UNIT	1-FINGER	4-FINGER	5-FINGER
[1]	98	98	19
[m/s]	4.7	4.7	_
[N]	_	_	200
	[J] [m/s]	[J] 98 [m/s] 4.7	[J] 98 98 [m/s] 4.7 4.7

ENVIRONMENTAL	UNIT	NOMINAL	MIN	MAX
operating temperature	[°C]	20	-5	50
storage temperature	[°C]	_	-20	50
noise level	[dB]	62	44	72

ELECTRICAL	UNIT	NOMINAL	MIN	MAX
operating voltage	[V]	24	23.1	24.8
power consumption	[W]	18	1.4	30

CONTROL

communication protocol: RS485

FEATURES			
plug-and-play			
soft, human-like fingers			
right and left versions			
different cover colours			

NORMATIVE COMPLIANCE

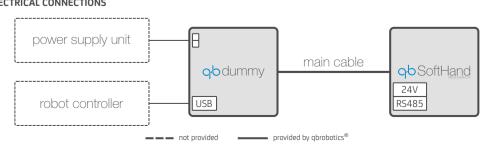
ISO 9409-1-31.5-4-M5

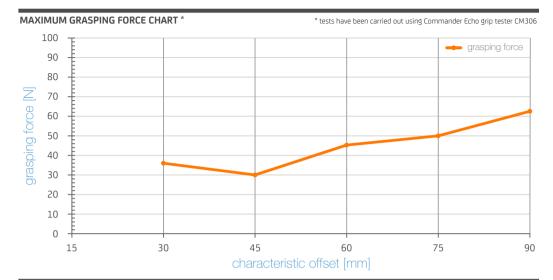
ISO 9409-1-40-4-M6



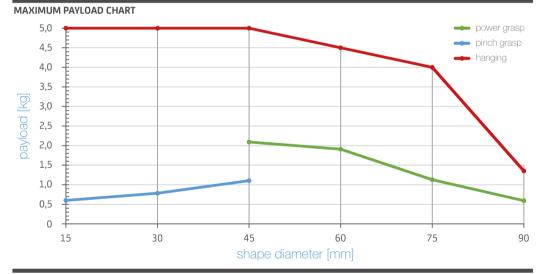


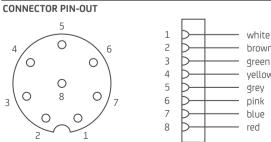
additional technical data FINGERS WORKSPACE 163 87 KINEMATICS **CHART NOTES** shapes diameters: 15-30-45-60-75-90 [mm] cylinder length: 150 [mm] friction factor: 0,8±0,1 ¹ hand rubber glove vs ABS plastics hand fingers mass M mass M mass M power grasp pinch grasp hanging **ELECTRICAL CONNECTIONS** power supply unit

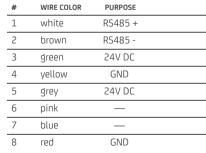


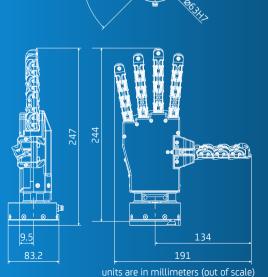


The Seller grants the conformity of the product. A slight — non essential approximation of the technical characteristics of the Product as represented in Seller's catalogues, price lists, advertisements or any other publications shall not be considered as lack of conformity.









-n4 ø6.4 thru-hole

-n4 holes ø6H7

96 SoftHand

DRAWINGS