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	24Vdc / 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

MIT | Stanford | Berkeley | YALE | KAIST | KRISS | KITECH

SAMSUNG | LG | HYUNDAI | Google | NVIDIA | Tencent 腾讯 | TOYOTA | Meta

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