## ClamArm Technical Diagram

4/6/2012 - Dave Coleman

I\_gripper\_pincher

I\_gripper\_fwd\_link I\_gripper\_aft\_link

## Servos:

7: gripper\_grip\_controller AX-12, TTL, open 240, close 424

6: gripper\_roll\_controller AX-12, TLL, min 0, max 1023

5: wrist\_pitch\_controller RX-28, RS-485, min 200, max 900

4: wrist\_roll\_controller RX-28, RS-485, min 0, max 1023

3: elbow\_pitch\_controller RX-64, RS-485, max 890, min 200

2: elbow\_roll\_controller RX-64, RS-485, min 0, max 650

1: shoulder\_pitch\_controller EX-106, RS-485, min 926, max 3825

0: shoulder\_pan\_controller AX-12, TTL, min 0, max 900



r\_gripper\_pincher

r\_gripper\_fwd\_link r\_gripper\_aft\_link

**gripper\_grip\_joint** → I\_gripper\_aft\_link gripper\_roll\_link

gripper\_roll\_joint

wrist\_pitch\_link wrist\_pitch\_joint

wrist\_roll\_link

wrist\_roll\_joint

elbow pitch link

elbow\_pitch\_joint

elbow\_roll\_link

elbow\_roll\_joint

shoulder pitch link

shoulder\_pitch\_joint

shoulder\_pan\_link

shoulder\_pan\_joint

base link

