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# PhantomX Pincher Specifications

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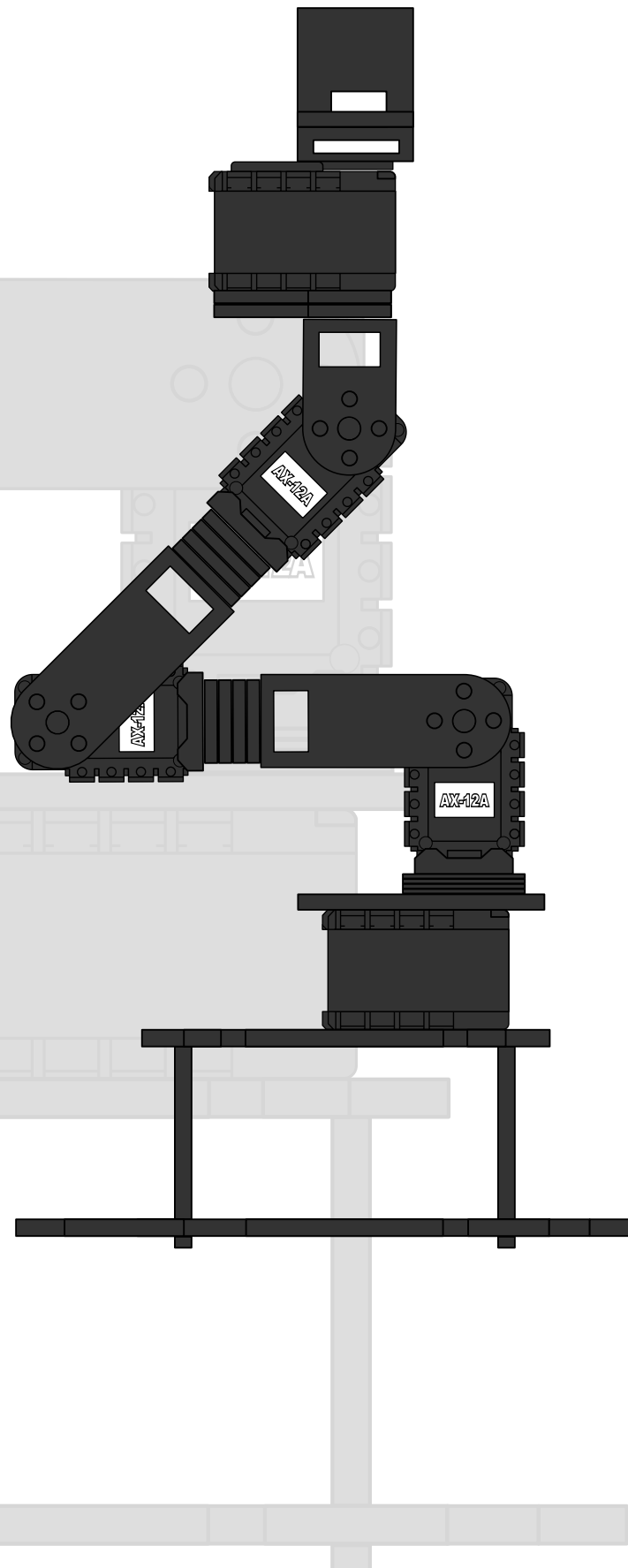
# PhantomX Pincher Specifications

By Hans Toquica

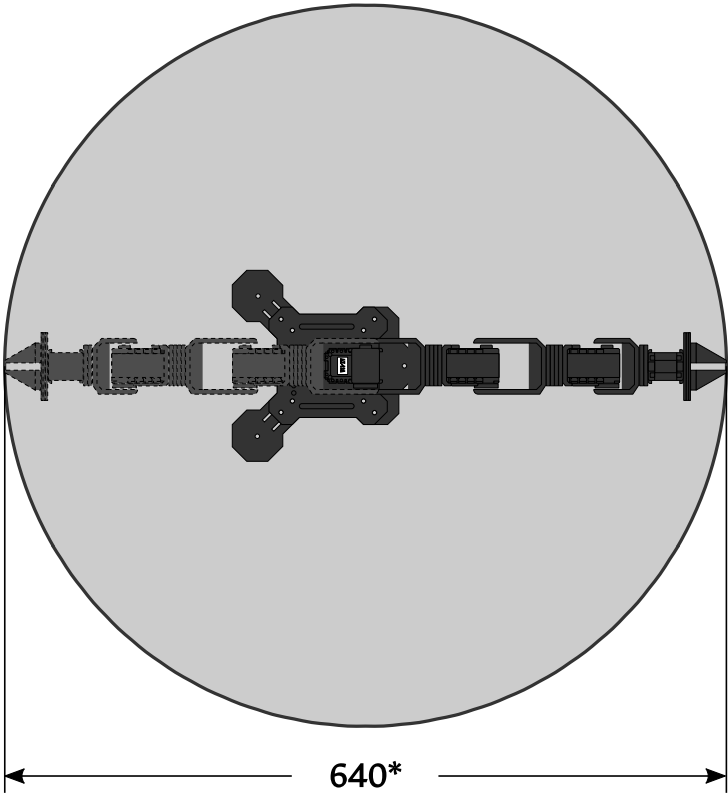
The PhantomX Pincher is a 4 Degrees of Freedom Robotic Arm that is commonly used in the classroom for teaching robotics to students.

Not so much technical information can be found online for this robot, ergo, this document is intended to provide the robot specifications in regards to the kinematics dimensions and the workspace.

Dimensions in millimeters unless otherwise indicated.

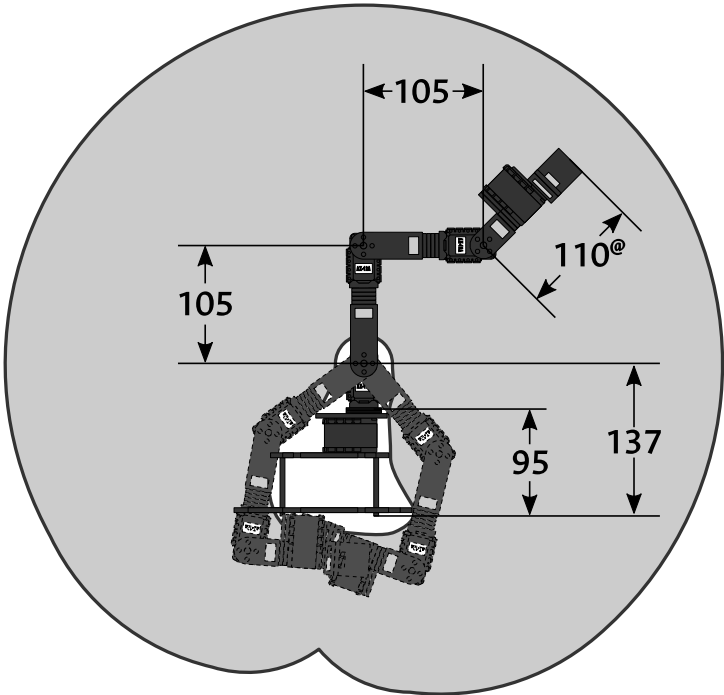


PhantomX Pincher Simplified Workspace



\* Effective Grasping at 610 mm.

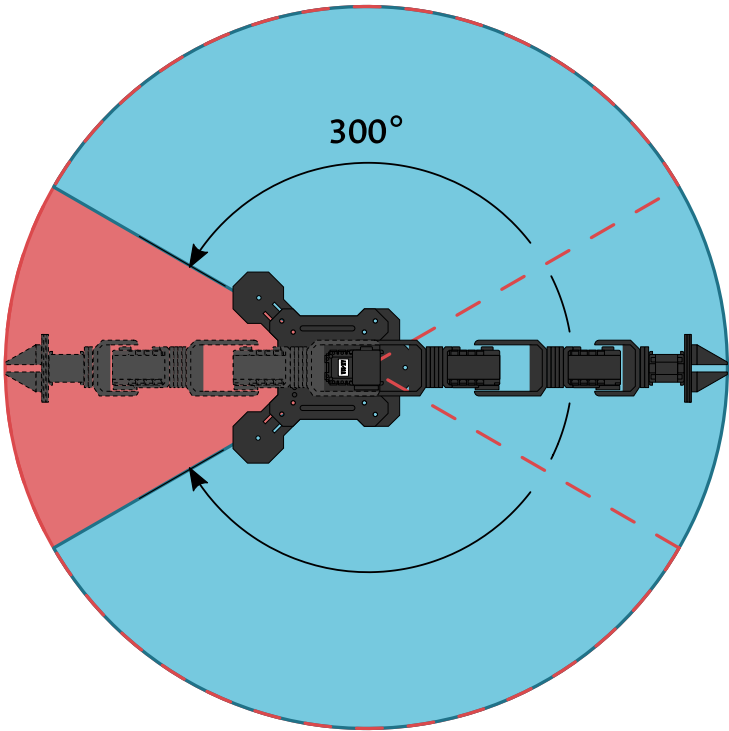
Top View



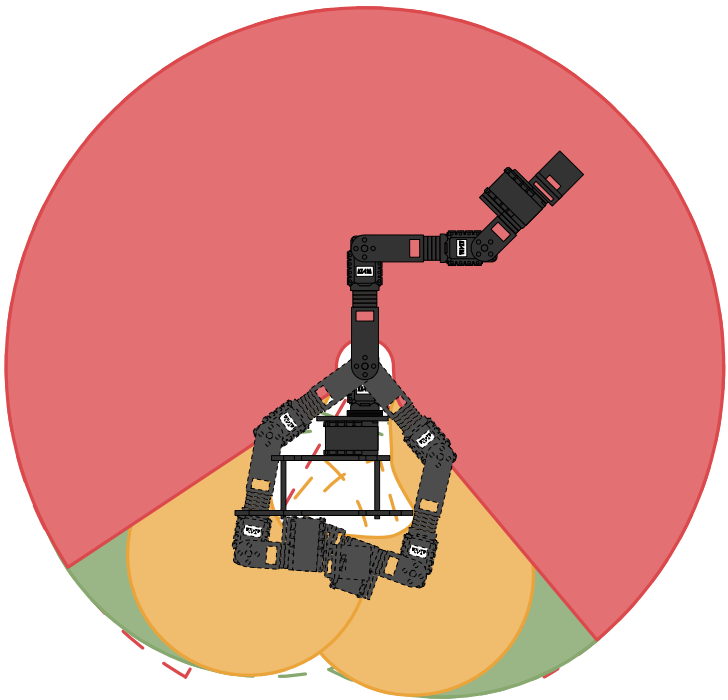
@ Effective Grasping at 95 mm.

Planar View

PhantomX Pincher Extended Workspace



Top View

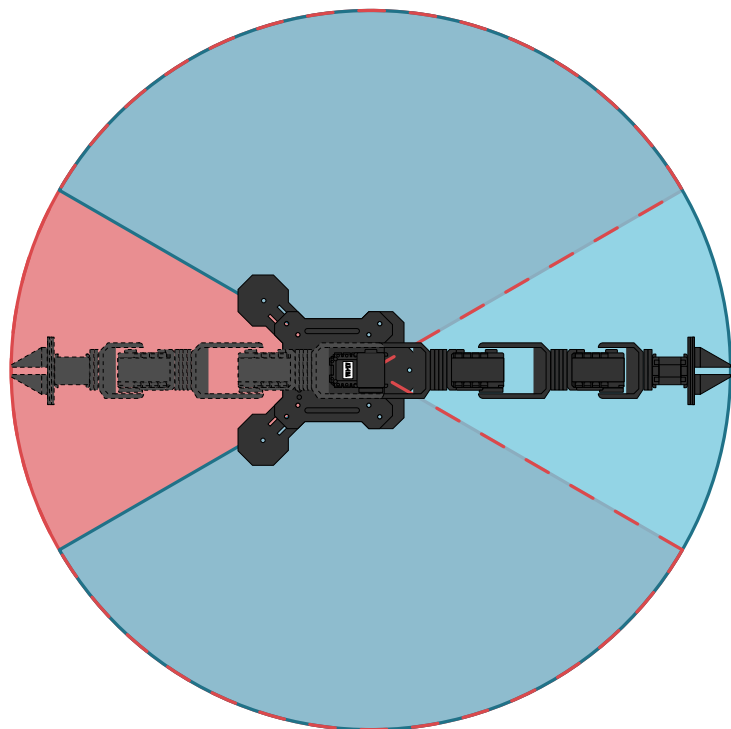


Planar View

- Second Joint Between  $0^{\circ}$  and  $150^{\circ}$
- Second Joint Between  $150^{\circ}$  and  $300^{\circ}$
- - Second Joint Between  $150^{\circ}$  and  $300^{\circ}$  (Superimposing First Workspace)

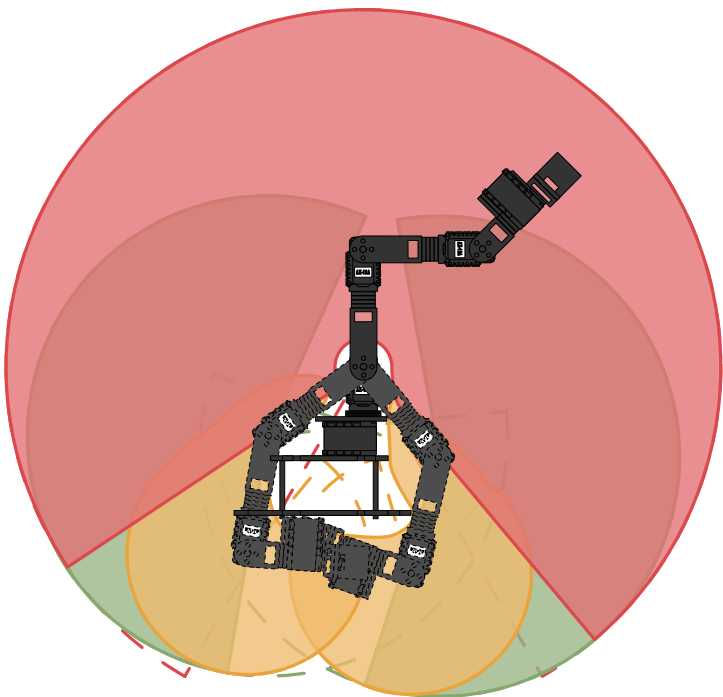
- Due to Second Joint
- Due to Third Joint
- Due to Fourth Joint
- Dashed Lines Different from Black Stand for Workspace if There Were No Obstacles
- Black Dashed Lines Stand for Robot Pose in Maxed Out Joints (Ascending)

PhantomX Pincher Extended Workspace



Top View

- Second Joint Between  $0^{\circ}$  and  $150^{\circ}$
- Second Joint Between  $150^{\circ}$  and  $300^{\circ}$
- - Second Joint Between  $150^{\circ}$  and  $300^{\circ}$  (Superimposing First Workspace)



Planar View

- Due to Second Joint
- Due to Third Joint
- Due to Fourth Joint
- Dashed Lines Different from Black Stand for Workspace if There Were No Obstacles
- Black Dashed Lines Stand for Robot Pose in Maxed Out Joints (Ascending)

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By Hans Toquica



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