

Serial Number: SAH030D041L (Left, v3.0)

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Getting Started

- Allegro Application Studio (Installation)
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More information is accessible using the navigation bar at the top of the page.

Allegro Hand Application Studio (AHAS)

AHAS Download

Allegro Hand Application Studio!

Below you can download your copy of Allegro Application Studio for your Allegro Hand.
Please refer to Allegro Application Studio (Installation) for installation instructions.

File:Allegro Hand Setup 20140407.zip (for AH v3.0)

Note: This AHAS installation is not yet configured for your hand. See *DMLs* section below before installing.

DMLs

DML files used in Allegro Hand Application Studio (AHAS) contain joint offsets and directions and are specific to each hand.

After Installing AHAS, please locate and download the DML files for your hand below (according to your hand's serial number). Replace the files of the same name in the 'devices' directory (below) with the files downloaded from the wiki.

C:\Program Files\SimLab\Allegro Hand Application Studio\bin\models\Etc\AllegroHand\devices

If you chose an installation directory other than the default when installing, you can find your DMLs here:

[Installation Location]\Allegro Hand Application Studio\bin\models\Etc\AllegroHand\devices

- **Download DMLs for your hand:** File:SAH030D041L DMLs.zip

RoboticsLab Project

See the Allegro Hand RoboticsLab Project page for source code and documentation.

Visual Studio Project

Note: This software does not require RoboticsLab.

See the Allegro Hand MSVS Project page for source code and documentation.

Offsets and Directions

SAH030D041L (Left)

Note: These are the offsets and directions for your Allegro Hand

Finger	Joint	Encoder Offsets <i>encoder_offset</i>	Encoder Directions <i>encoder_direction</i>	Motor Directions <i>motor_direction</i>
0	0	3981	+	+
0	1	-4463	+	+
0	2	4798	+	+
0	3	4874	+	+
1	0	6188	+	+
1	1	-3798	+	+
1	2	3458	+	+
1	3	2112	+	+

2	0	3934	+	+
2	1	-3222	+	+
2	2	4383	+	+
2	3	6110	+	+
3	0	-3358	+	+
3	1	-3564	+	+
3	2	-2985	+	+
3	3	-4282	+	+

Template:SAH030D041L Offsets and Directions (ROS)

File:SAH030D041L DMLs.zip for use in AHAS/RoboticsLab

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SimLab's Allegro Hand is based on licensed technology developed by the Humanoid Robot Hand research group at the Korea Institute of Industrial Technology (KITECH).

Any references to the BHand Library or the Allegro Hand Motion and/or Grasping Library refer to a library of humanoid robotic hand grasping algorithms and motions developed and published by KITECH researchers.

J.-H. Bae, S.-W. Park, D. Kim, M.-H. Baeg, and S.-R. Oh, "A Grasp Strategy with the Geometric Centroid of a Groped Object Shape Derived from Contact Spots," Proc. of the 2012 IEEE Int. Conf. on Robotics and Automation (ICRA2012), pp. 3798-3804

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