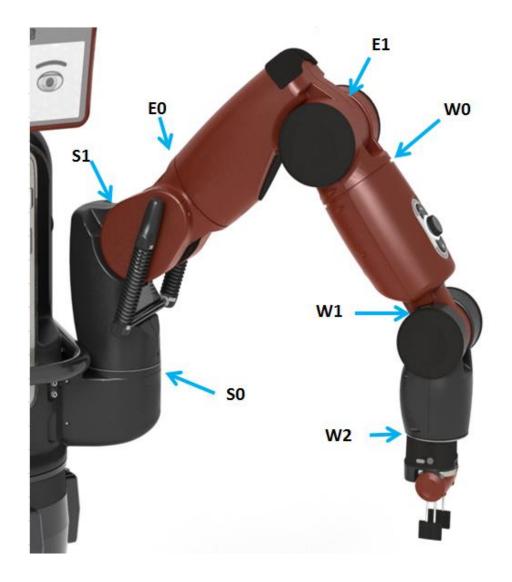


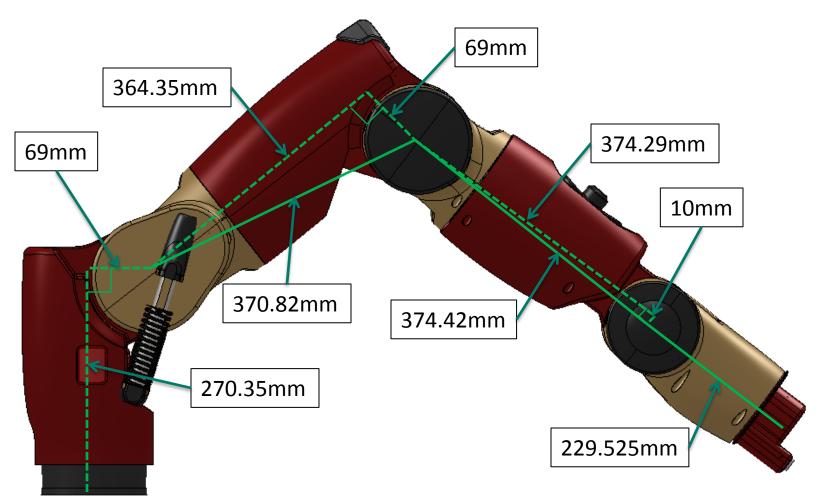
BAXTER JOINT NAMES





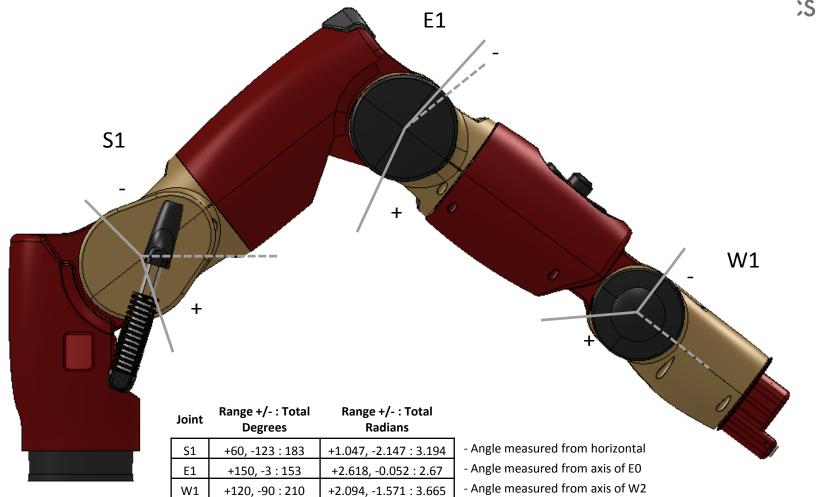
BAXTER P2 LINK LENGTHS





BAXTER P2 JOINT RANGES OF MOTION

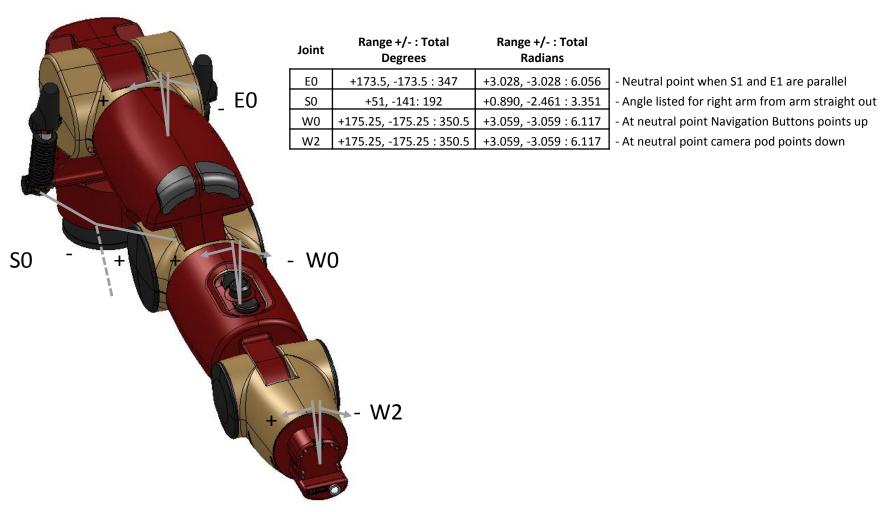




4

BAXTER P2 JOINT RANGES OF MOTION





OTHER HARDWARE SPECIFICATIONS



Joint Hardware Peak Torque (per joint)	
S0, S1, E0, E1	50 Nm
W0, W1, W2	15 Nm

Camera Specifications		
Max Resolution	1280 x 800 pixels	
Effective Resolution	640 x 400 pixels	
Frame Rate	30 frames per second	
Focal Length	1.2 mm	

On Board CPU	
Processor	3rd Gen Intel Core i7-3770 Processor (8MB, 3.4GHz) w/HD4000 Graphics
Memory	4GB, NON-ECC, 1600MHZ DDR3
Hard Drive	128GB Solid State Drive

OTHER HARDWARE SPECIFICATIONS



Other Specifications		
Screen Resolution	1024 x 600 pixels	
Positional Accuracy	+/- 5 mm	
Max Payload (including end-effector)	5 lb / 2.2 kg	
Gripping Torque (max)	10 lb / 4.4 kg	
Infrared Sensor Range	1.5 – 15 in / 4 – 40 cm	

Component Weights		
Total weight (with pedestal)	298 lbs / 135.2 kg	
One arm	47 lbs / 21.3 kg	
Torso	70 lbs / 31.8 kg	
Pedestal	134 lbs / 60.8 kg	

OTHER HARDWARE SPECIFICATIONS



	Electrical Power
Battery Operation	DC-to-120V AC Inverter (Note: the Baxter robot has an internal PC, which cannot be powered directly off of 24V DC)
Interface	Standard 120VAC power. Robot power bus and internal PC both have "universal" power supplies and support 90 - 264V AC (47 - 63Hz)
Max Consumption	6A at 120V AC 720W max per unit
Electrical Efficiency	87% to 92%
Power supply	Uses medical-grade DC switching power supply for robot power bus
Tolerance to sags	Sags tolerated to 90V. Sustained interruption will require manual power-up
Voltage Flicker	Holdup time 20mS
Voltage Unbalance	Single phase operation only