





Compact & Lightweight



Dexterous & Flexible



Sufficient Payload



Sufficient Accuracy

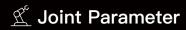


Support Joint Force Control



With Collision Protection





FUNCTION	PARAMETER
Backlash	~6 arcmin
Maximum Torque	33N·m
Weight	405g
Size	ф65*50mm
Reducer	Harmonic Reducer
Reduction Ratio	60+
Voltage	24V (Recommend)
Communication Method	RS 485
Encoder Resolution	15bit
Bearing	Industrial grade cross roller
Motor Sensing Feedback	Torque, angle, angular velocity
Motor Control Command	Torque, angle, angular velocity,
	stiffness, damping
Force Control Accuracy	~0.2N·m
Control Frequency	1KHz





Model	Z1 AIR	Z1 PRO	
DOF	6	6	
Weight	4.3kg	4.5kg	
Payload	2 kg	≥3kg	
Reach	740mm		
Repeatability [1]	~0.1mm		
Power Supply	Voltage 24V Current > 20A		
Interface	Ethernet		
User Operating System	Ubuntu		
Force Feedback and Collision Detection	Provide		
Power	MAX 500w		
Control Interface [2]	Position + Force Control		

1		
Joint	Range	Max Speed
J1	±150°	180°/s
J2	0–180°	180°/s
J3	-165°-0	180°/s
J4	±80°	180°/s
J5	±85°	180°/s
J6	±160°	180°/s



- [1] It depends on the actual test according to the use requirements (the test standards of manipulator vary greatly, and the accuracy varies greatly under different test conditions)
- [2] Since the reduction ratio used by each joint is relatively low, the position control stiffness of the whole machine is low. If the control mode is not optimized, there will be large position control error and shaking when the manipulator moves.

The manipulator control program and control interface will be successively opened, and different actuators can be quickly replaced at the end of the manipulator.







Various mobile robots' onboard manipulator, e-commerce logistics, new consumption, daily life, etc.





⊈ Synergy

It can cooperate with Aliengo or B1 robot and other mobile robots to complete complex tasks and explore various application scenarios.





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SMART & LIGHTWEIGHT

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