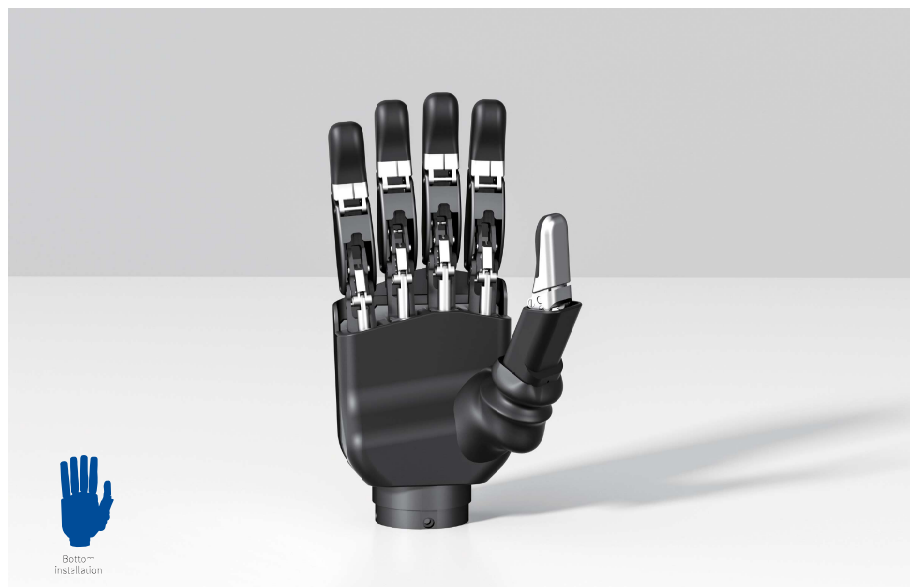


DH-5-6

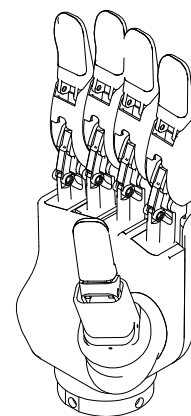
Dexterous Hand



Selection Method

Serie	Number of Fingers	Hand Shape	Active Degrees of Freedom	Degrees of Freedom	Wrist Interface	Cable Direction	Sensors	Cable Configuration	Mounting Flange
DH	5	L	6	11	N	M3	C0	L3	Z0
3 3 Fingers 5 5 Fingers	L Left Hand R Right Hand	6 Degrees of Freedom	11 Joint	N Standard Interface F Quick-release interface	M3 MODBUS-RTU M4 Custom communication protocol over RS485	Z0 Standard Flange without Adapter Z1 With Adapter Flange 1 (Mounting PCD Ø50 mm / Locating Boss Ø21.5 mm) Z2 With Adapter Flange 2 (Mounting PCD Ø49 mm / Locating Boss Ø18mm) Z3 Others	C0 Without Sensor	L1 Extension Cable 1m L3 Extension Cable 3m L5 Extension Cable 5m L10 Extension Cable 10m	

TECHNICAL SPECIFICATIONS



✓ Built-in Controller	✓ Gripping Force Adjustable	✓ Position Adjustable	✗ Speed Adjustable
✓ Plug & Play			

Product Parameter	
Total degrees of freedom	11
Active degree of freedom	6
Working speed	0.8 s
Four-finger bending angle	83°+87°
Thumb bending angle	38°+7°
Thumb lateral swing angle	85°
Single fingertip force	25 N
Recommended maximum friction load	2 kg
Recommended maximum structural lifting load	4 kg
Hand grip strength	80 N
Lifting load	10 kg
Weight	790 g
Sensors	Multi-point Tactile Sensing (Optional)
Safety features	Anti-collision Buffering for Inward Grasping
Driving method	Coreless motor + planetary reducer + ball screw + linkage
Size	236 mm*116 mm*96 mm
Working Environment	
Communication interface	Modbus-RTU/Custom communication protocol over RS485
Rated voltage	24 V DC ± 10%

Technical Drawings

