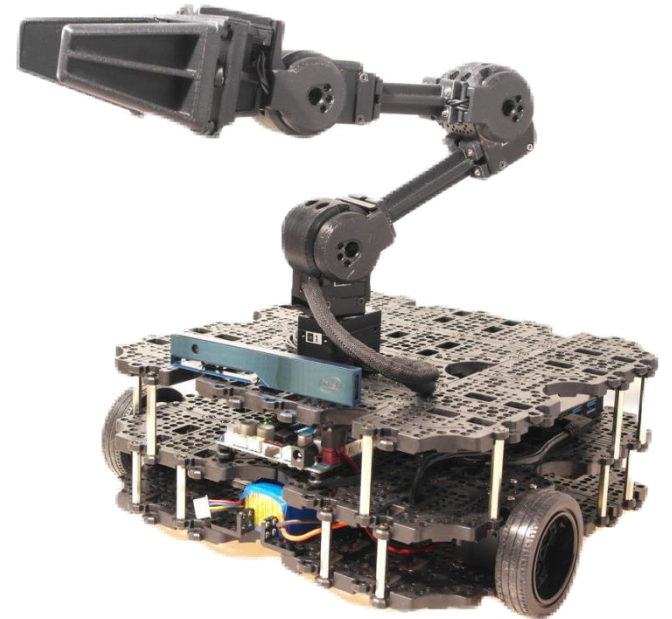


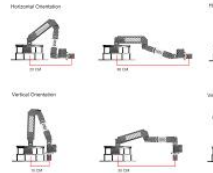
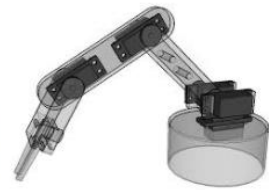
Introducing **OpenManipulator** : Build your own manipulator





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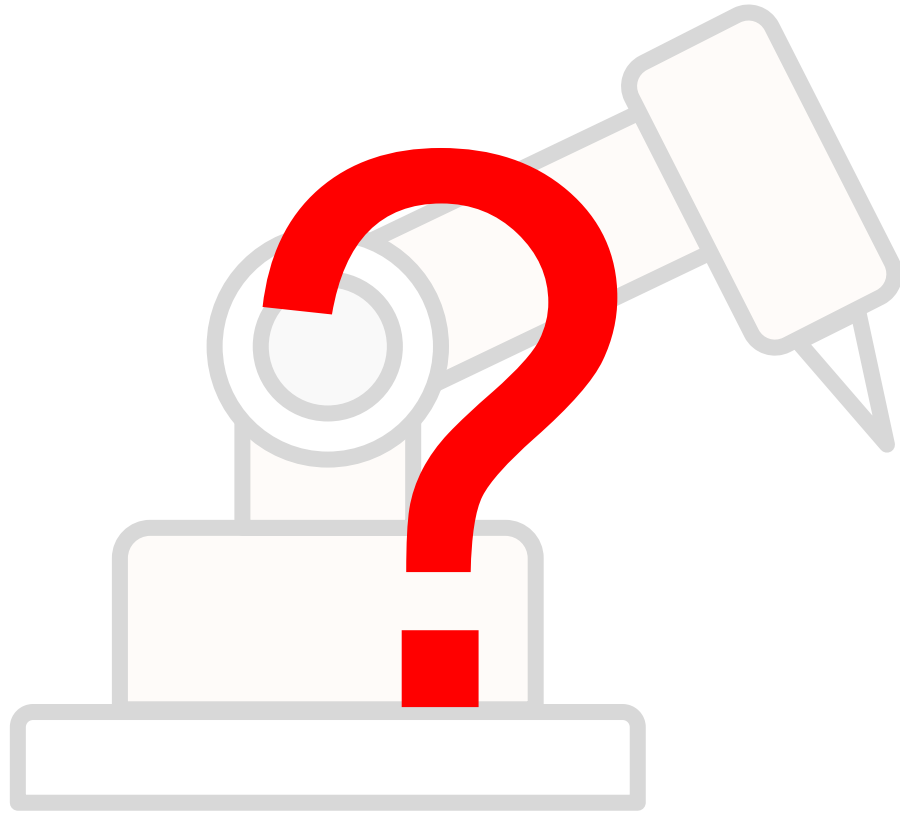
ROBOTIS

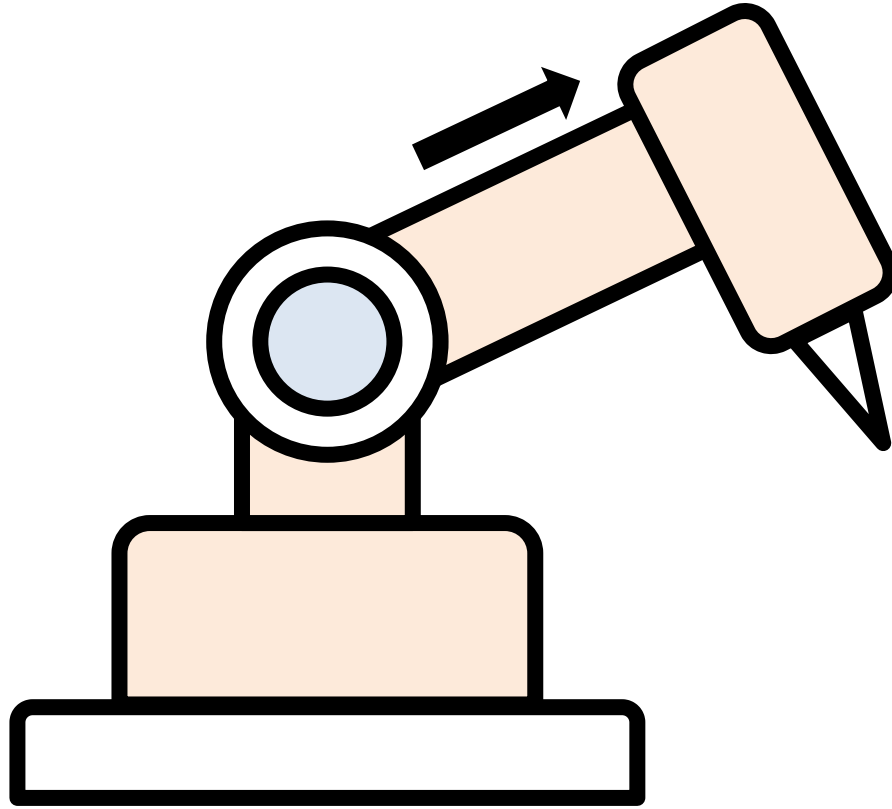


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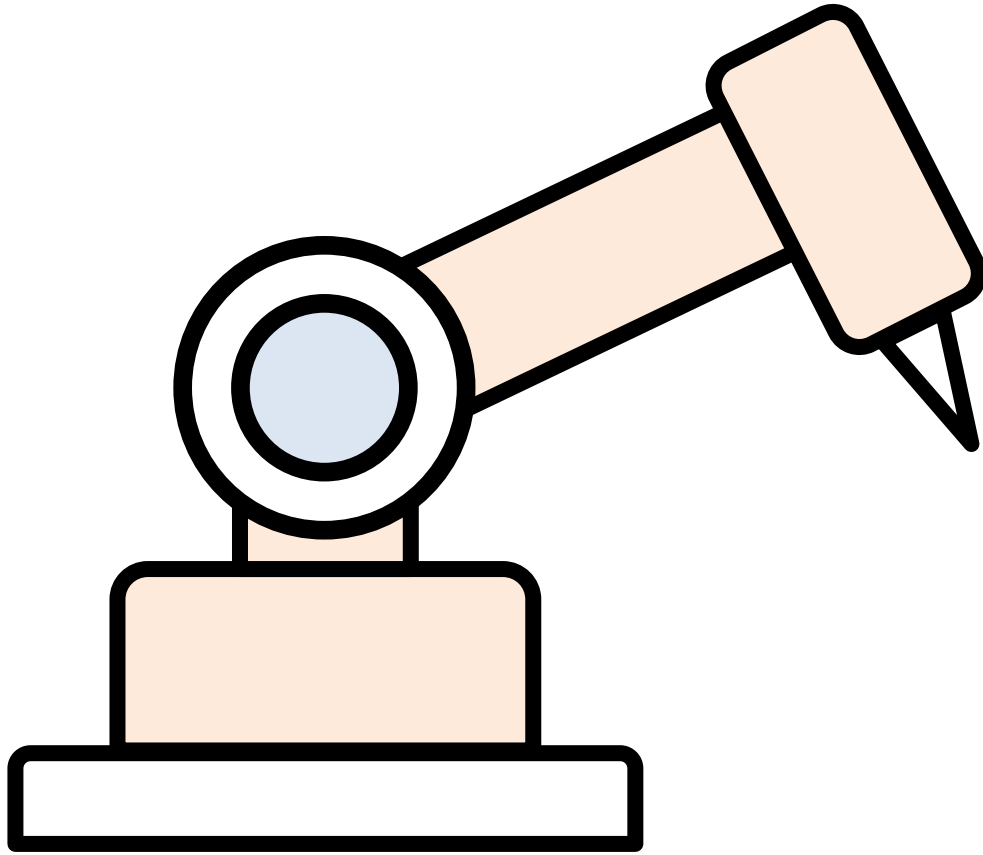


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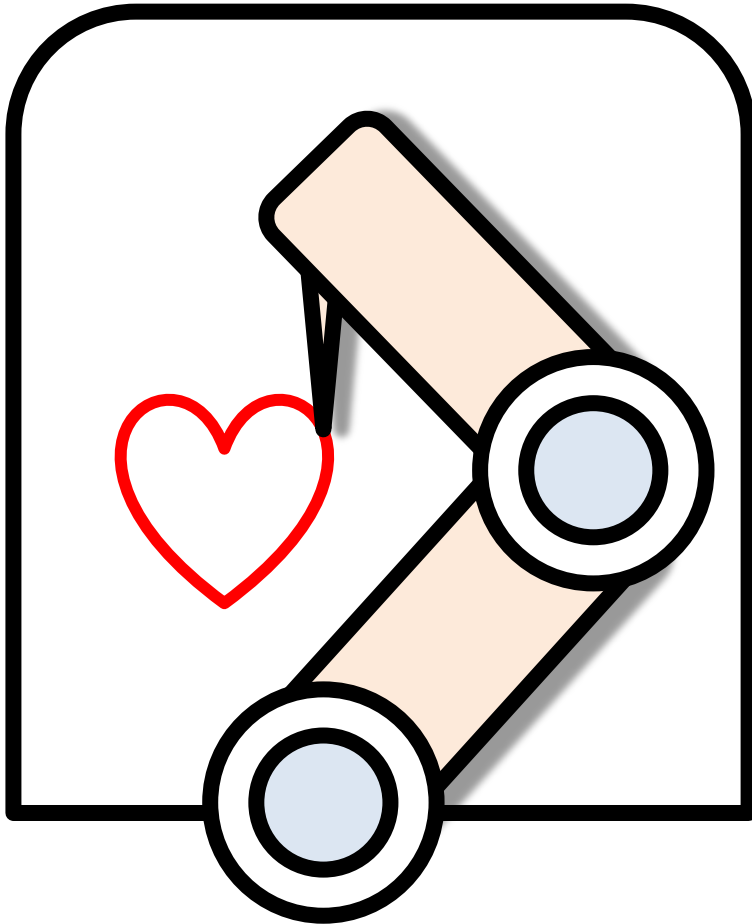




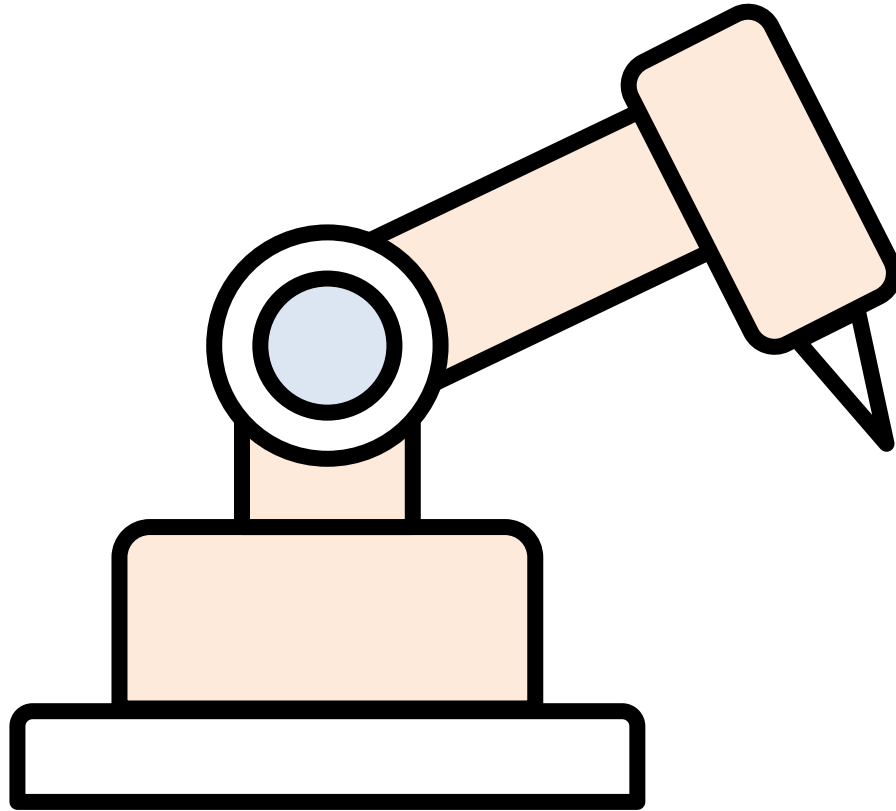
- Customization



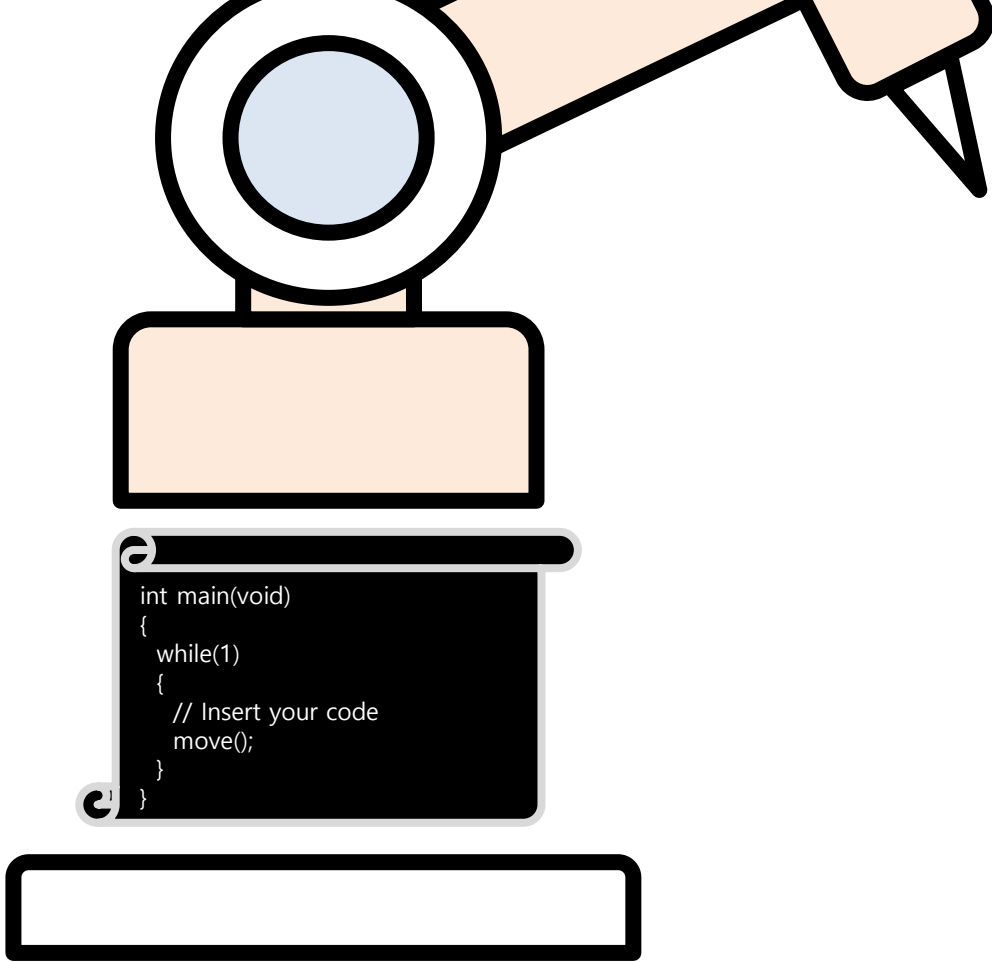
- Customization
- Extensibility



- Customization
- Extensibility



- Customization
- Extensibility
- Open-source



- Customization
- Extensibility
- Open-source



OpenManipulator

3D printed parts

Aluminium frames

ROS

Dynamixel





Customization

Onshape **ROBOTIS OpenManipulator Chain** Main 0 9 4 [App Store](#) [Share](#) ROBOTIS OpenSourceTeam

Instances (8)

- Origin
- > MPX-ASM01-JOI...
- > MPX-ASM24-JOI...
- > MPX-ASM26-JOI...
- > MPX-ASM27-JOI...
- > NEW_GRIPPER_A...
- ↳ LINK_LONG <1>
- ↳ LINK_SHORT <1>
- ↳ 170621...

▼ Mate Features (0)

+ NEW_CHAIN_ASSY_ASM Parts Assy's



Customization



Dynamixel XL

Affordable Prices

Dynamixel XM

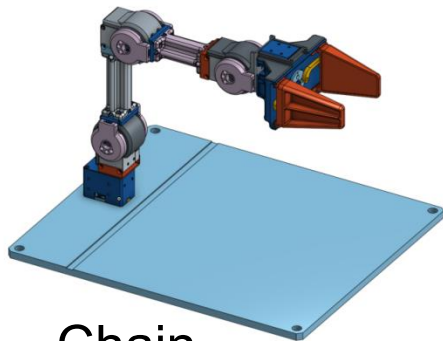
High Torque

Dynamixel XH

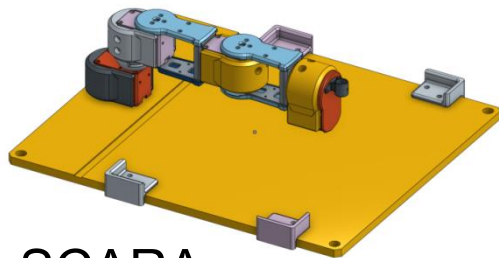
More Durability



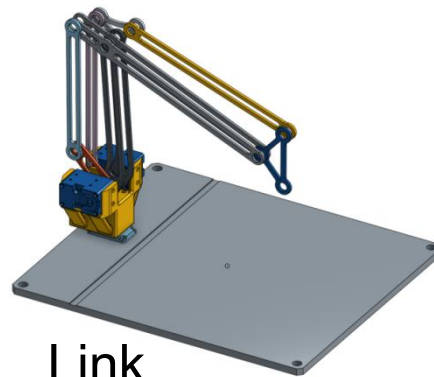
Extensibility



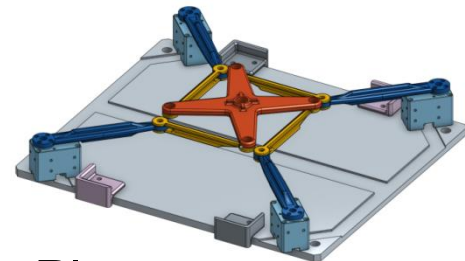
Chain



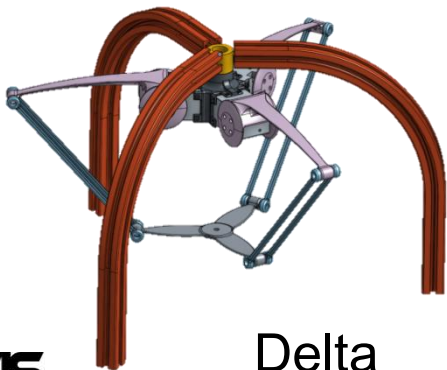
SCARA



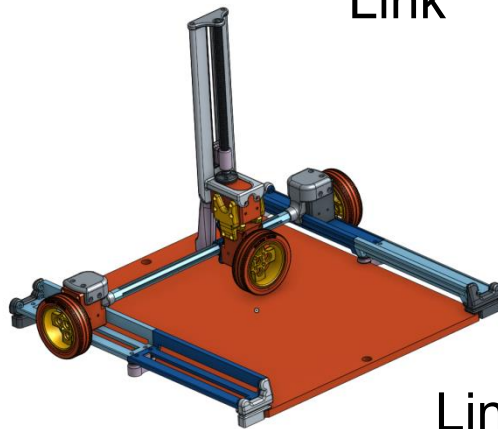
Link



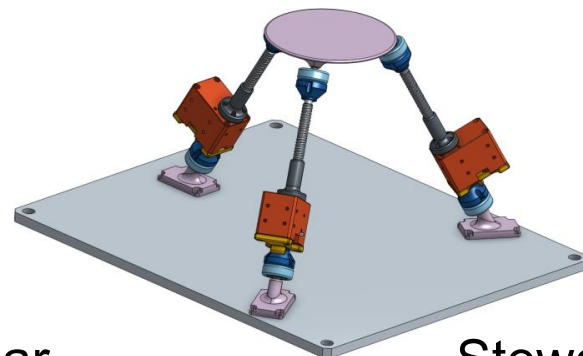
Planar



Delta



Linear

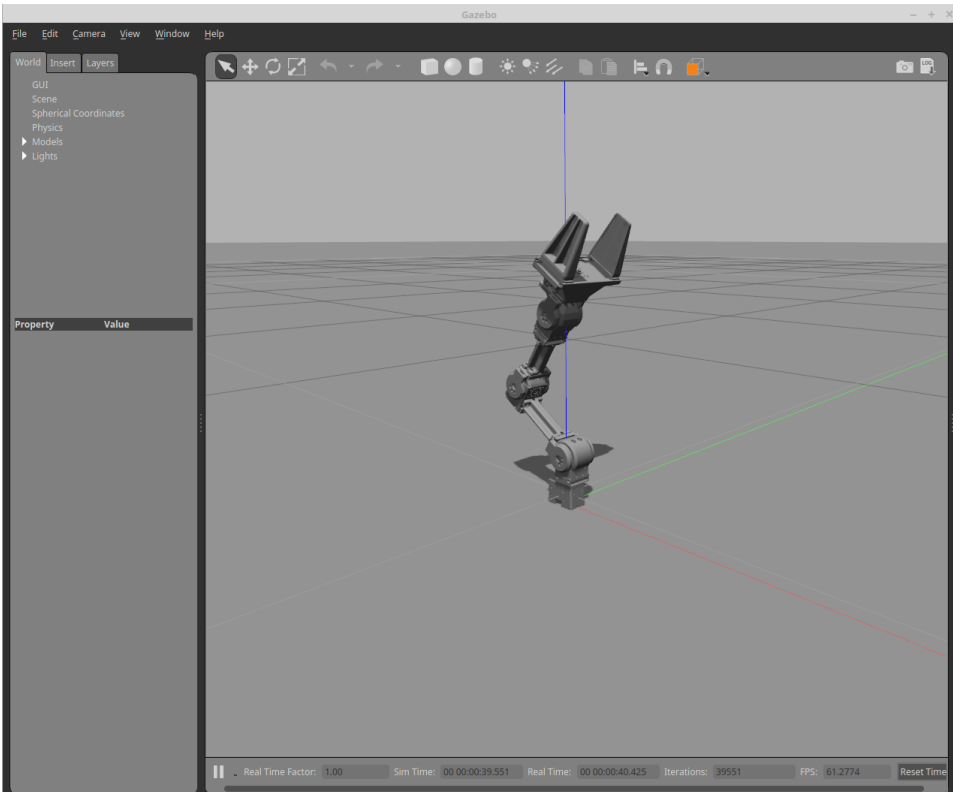


Stewart

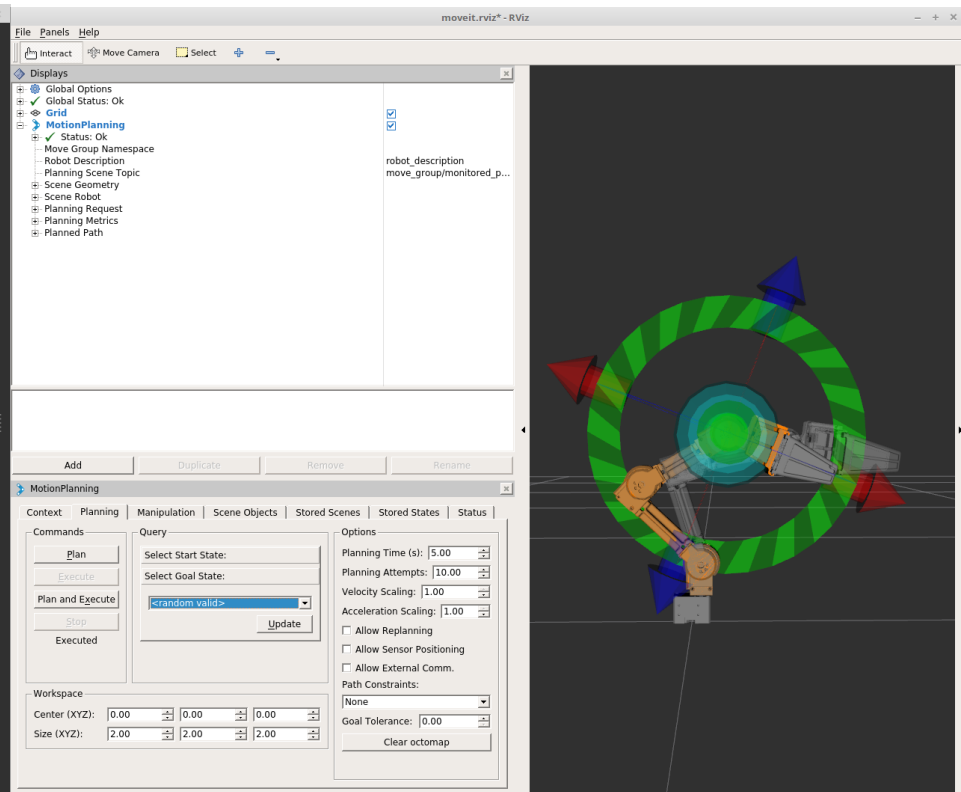


Robot Operating System

Gazebo



Movelt!



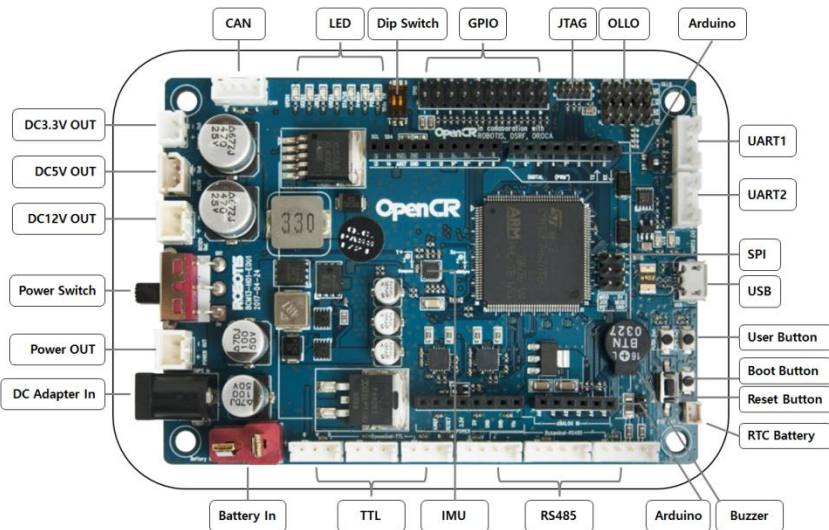


ROS



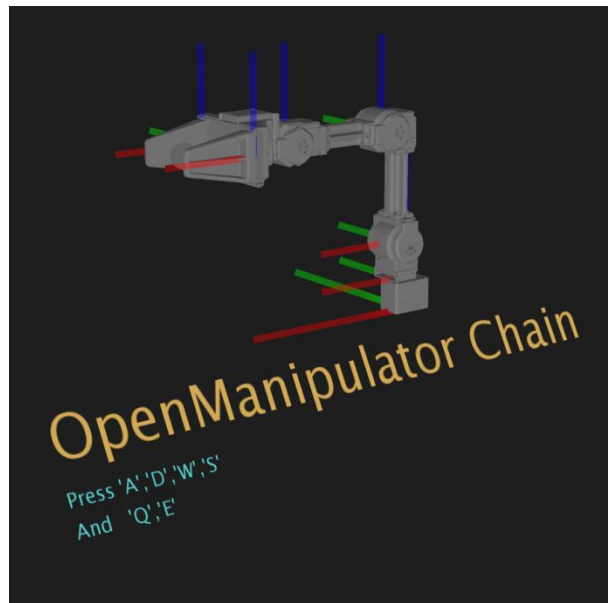
Embedded system

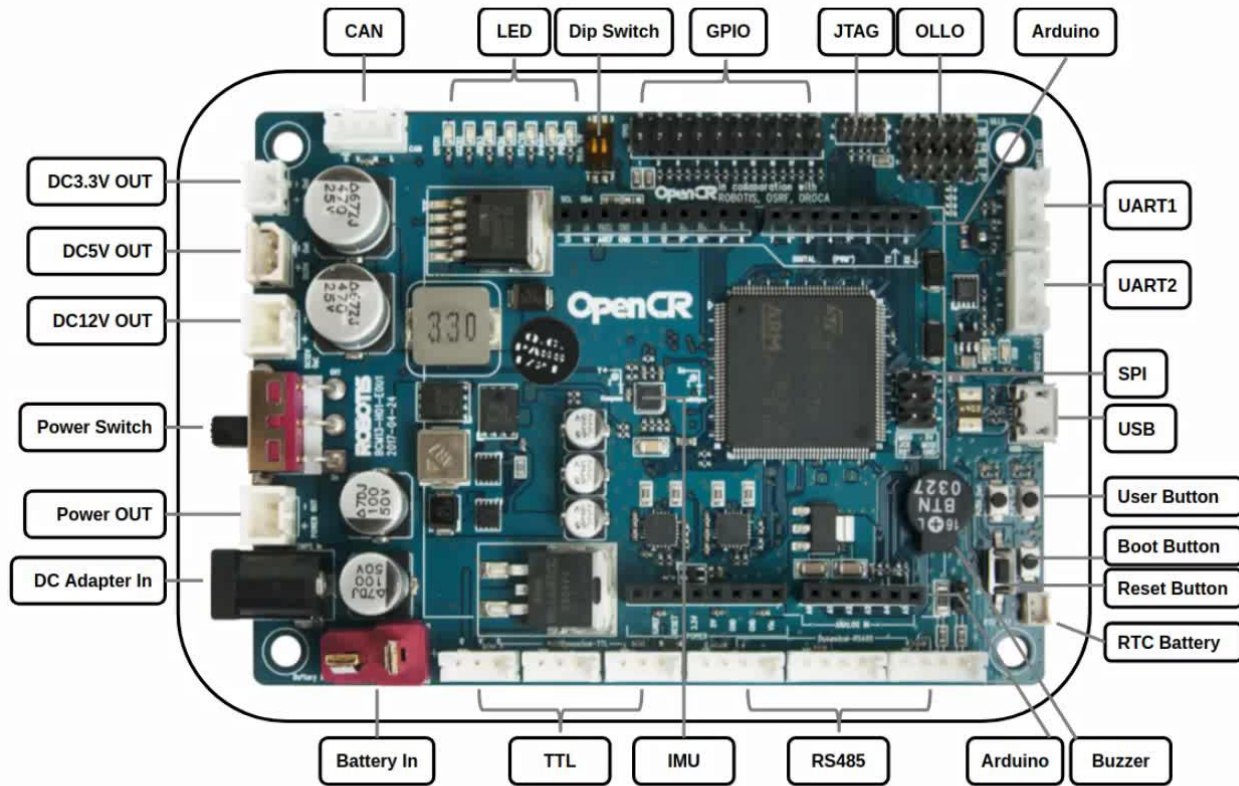
Arduino for control



Open-source Control
module for ROS

Processing for visualization





OpenCR

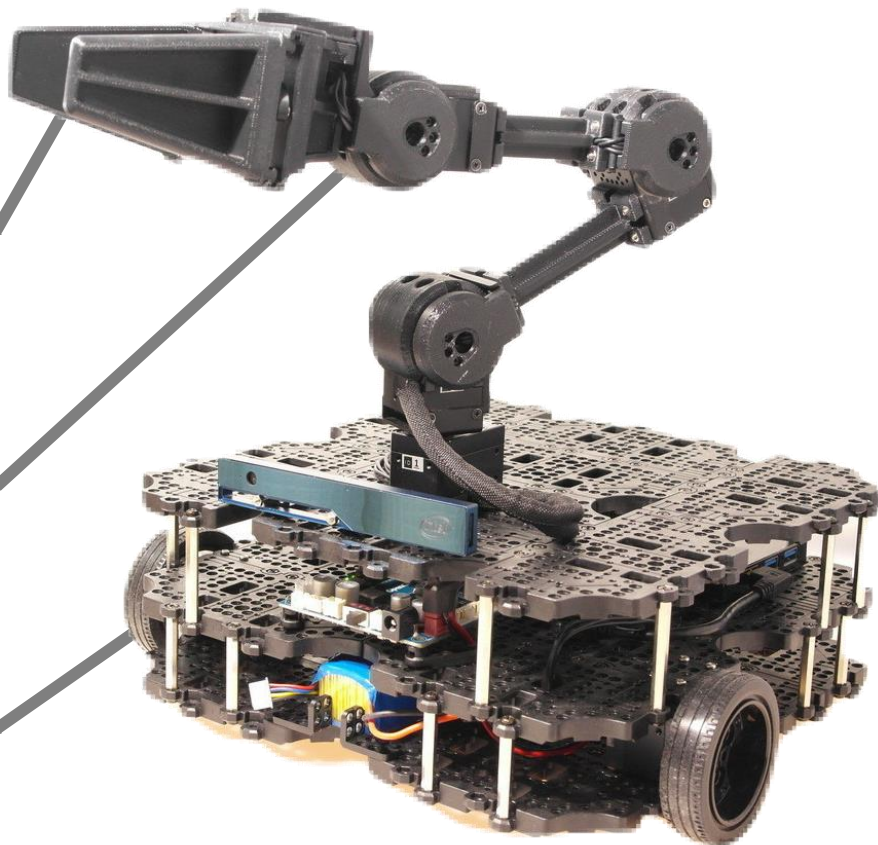


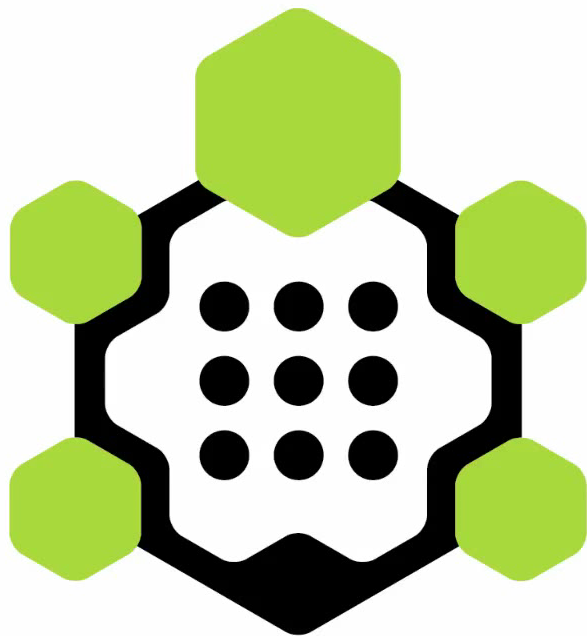
Mobile manipulator

Current based
position control

Position control

Velocity control





TURTLEBOT3



Full Open-source

Open-source Hardware

- ◆ CAD Data : OnShape (Search “ROBOTIS”)
 - Chain : <https://goo.gl/NsqjMu>
 - SCARA : <https://goo.gl/oVsK8m>
 - Link : <https://goo.gl/MJ6C8K>

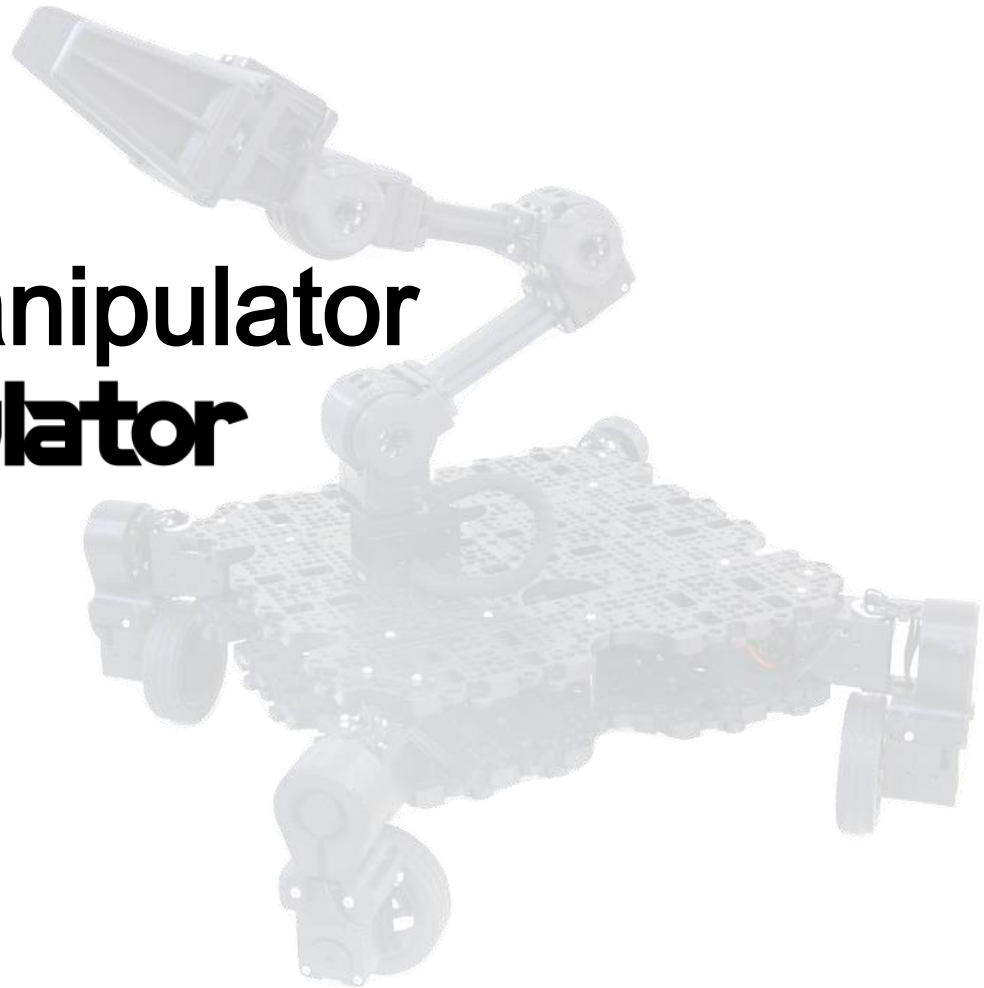
And more coming soon!!

Open-source Software

- ◆ Firmware & ROS package : Github (Search “ROBOTIS-GIT”)
 - OpenManipulator : https://github.com/ROBOTIS-GIT/open_manipulator
 - OpenCR : <https://github.com/ROBOTIS-GIT/OpenCR>

Your contribution is welcome!!

Build your **own** manipulator With **OpenManipulator**





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