### Specifications

<table>
<thead>
<tr>
<th>Specification</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>Number of axis</td>
<td>6</td>
</tr>
<tr>
<td>Max payload</td>
<td>1 Kg</td>
</tr>
<tr>
<td>Max reach</td>
<td>478 mm</td>
</tr>
<tr>
<td>Stroke (Speed)</td>
<td></td>
</tr>
<tr>
<td>Axis 1</td>
<td>+/- 180 ° (38 °/sec)</td>
</tr>
<tr>
<td>Axis 2</td>
<td>+/- 113 ° (38 °/sec)</td>
</tr>
<tr>
<td>Axis 3</td>
<td>+/- 113 ° (38 °/sec)</td>
</tr>
<tr>
<td>Axis 4</td>
<td>+/- 180 ° (56 °/sec)</td>
</tr>
<tr>
<td>Axis 5</td>
<td>+/- 104 ° (56 °/sec)</td>
</tr>
<tr>
<td>Axis 6</td>
<td>+/- 2700 ° (56 °/sec)</td>
</tr>
<tr>
<td>Total weight</td>
<td>11.1 kg</td>
</tr>
<tr>
<td>Robot arm weight</td>
<td>5.4 kg</td>
</tr>
<tr>
<td>Structure material</td>
<td>Ixef 1022</td>
</tr>
<tr>
<td>Power source</td>
<td>Universal external power source with 12V power adapter</td>
</tr>
<tr>
<td>Connectivity</td>
<td></td>
</tr>
<tr>
<td></td>
<td>1 external USB port</td>
</tr>
<tr>
<td></td>
<td>1 RJ45 Ethernet</td>
</tr>
<tr>
<td></td>
<td>1 DSub-9 Serial Port</td>
</tr>
<tr>
<td>Motherboard</td>
<td>Raspberry Pi running Raspbian Jessie</td>
</tr>
<tr>
<td>ROS</td>
<td>Kinetic Kame</td>
</tr>
<tr>
<td>Control Logic</td>
<td>Proprietary open-source e.DO</td>
</tr>
<tr>
<td>Additional Features</td>
<td>External emergency stop button</td>
</tr>
</tbody>
</table>

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