

The Virtuose 6D TAO HF is a 6 active degrees-of-freedom haptic device with a passive gripper.
Thanks to its large workspace, interaction capacities and EtherCAT interface, it enables and eases a slave robot control.

Nuclear Teleoperation # Industrial Teleoperation



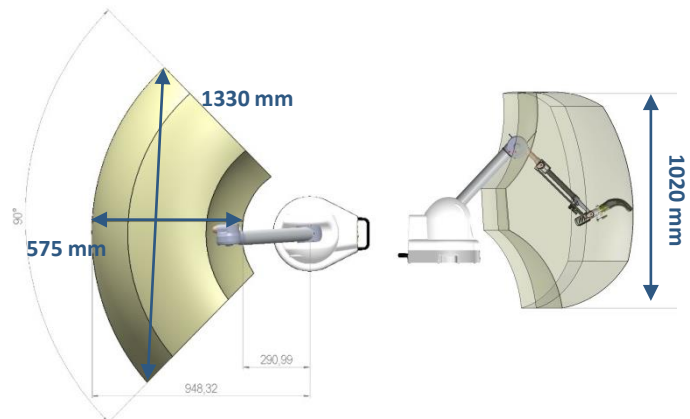
6 ACTIVE DEGREES-OF-FREEDOM – PASSIVE GRIPPER

- ✓ Passive weight balancing
- ✓ Ethernet or Ethercat communication system
- ✓ TREQ Handle (TeleRobotic Ergonomic Handle), designed for Master – Slave operations, including a dead-man function
- ✓ Button Box: 4 dedicated buttons with switch to freeze the pinch
- ✓ Reduced weight, allowing transportation without specific equipment
 - ✓ Haption TREQ teleRobotics Extender
 - ✓ Dedicated plug-ins for: 3DExperience™, Catia™ & Delmia™ V5, Solidworks™
 - ✓ Drivers (binary and/or source code) available for: Python™, ROS™, CHAI3D™, ODE™, Matlab Simulink™
 - ✓ By Partner: Unity3D™



MODULARITY

The user takes hold of the haptic device using a gripper or handle placed at the tip (called “end-effector”).
The gripping tool is equipped with two buttons, one 3 position-button and a 7th DOF with a passive gripper. The button box is equipped with three buttons and three multiple-position buttons.



TECHNICAL

Translation workspace	1330 x 575 x 1020 mm
Rotation Workspace	330° x 120° x 270°
Payload (center of the workspace):	70 N (peak)/ 30 N (continuous)
Rotation force: Peak, Continuous	5 Nm , 1.4 Nm
Position resolution	0.013 mm
Rotation resolution	0.0018°
Device Weight	12 kg

ELECTRICAL

Power supply	100-240 VAC 50/60Hz single phase
Consumption	Average consumption 200W Max consumption: 540W

SOFTWARE

Maximum translation stiffness	2000 N/m
Maximum rotation stiffness	40 Nm/rad
Update Rate	1000 Hz

The Virtuose 6D, Virtuose 6D TAO and Virtuose 3D are also available upside-down.
We are available to discuss with you any specific request for integration.

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