AGIBOT OmniHand 2025 – Technical Specification Sheet

		OmniHand 2025 (with Tactile)	OmniHand 2025 (with Tactile)
Hardware	**Weight (excluding wrist end cap and screws)**	≤510 g	≤520 g
	Dimensions	180×85×38.5 mm	
	Degrees of Active Freedom (DoA)	10	
	Degrees of Freedom (DoF)	16	
	Minimum opening/closing time (Typ)	0.5 s / 0.5 s	
	Fingertip repeat Positioning Accuracy (Typ)	0.3 mm	
	Five-finger grip force (hybrid force control mode)	≥ 5 kg	
	Working Voltage	18–27 V	
	Communication Interface	CAN-FD / RS485	
	Working Temperature Range	0~45℃	
	Online Upgrade	Supports OTA Upgrade	
Tactile Sensor	**Force Detection**	/	Fingertip + palm + hand back: One-dimensional force
	Array Resolution	/	0.1 N
	Range of Perception	/	0–20 N
	Maximum Acceptance (Undamaged)	/	200 N

1. The above parameters may vary in practical applications depending on different business scenarios and model configurations. Please refer to the actual specifications.

2. The product appearance may be subject to upgrades and adjustments in the future. Please refer to the physical product delivered at the time of purchase.

3. The five-finger grip force data represents the test results when the dexterous hand was operating in hybrid force-control mode.

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AGIBOT OmniHand 2025 Quadruped Robot – Joint Angle Range

Finger	Joint	Left		Right	
		Min (°)	Max (°)	Min (°)	Max (°)
Thumb	thumb_roll_joint	-2	64	-64	2
	thumb_abad_joint	-94	3	-3	94
	thumb_mcp_joint	0	48	-48	0
	thumb_pip_joint	NA /Coupled joints, coupling relationship reference in the SDK.			
	thumb_dip_joint	NA /Coupled joints, coupling relationship reference in the SDK.			
Index Finger	index_abad_joint	-9	0	0	9
	index_pip_joint	0	85	0	85
	index_dip_joint	NA /Coupled joints, coupling relationship reference in the SDK.			
Middle Finger	middle_pip_joint	0	85	0	85
	middle_dip_joint	NA /Coupled joints, coupling relationship reference in the SDK.			
Ring Finger	ring_abad_joint	0	10	-10	0
	ring_pip_joint	NA /Coupled joints, coupling relationship reference in the SDK.			
	ring_dip_joint	0	85	0	85
Fifth Finger	ring_abad_joint	0	11	-11	0
	pinky_pip_joint	0	85	0	85
	pinky_dip_joint	NA /Coupled joints, coupling relationship reference in the SDK.			

- Please refer to the values in the table

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