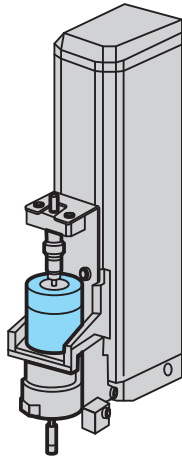


Example of implementation

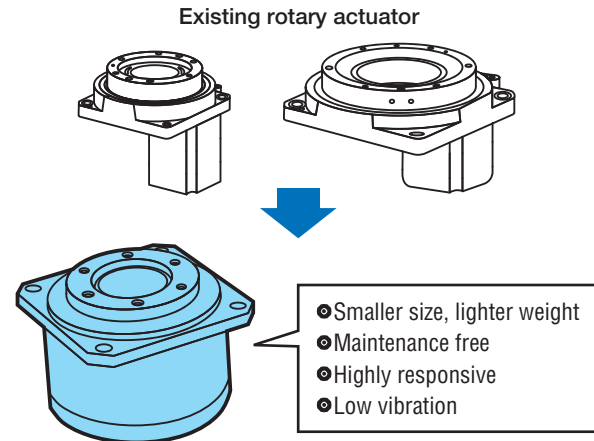
Although we aim to improve takt time,
existing servomotor is too big



θ drive shaft

By using μ DD motor to the θ drive shaft of the end effector, it is possible to realize smaller size and lighter weight. It can also contribute to picking up workpieces by passing air tube in hollow shaft and the highly-precise, gear-less positioning.

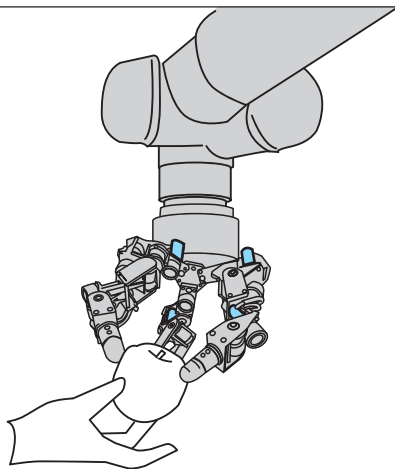
Although hollow shaft is indispensable,
considering precision,
we don't want to increase machine elements



Instead of rotary actuator

By using μ DD it is possible to consist hollow shaft only with motor.

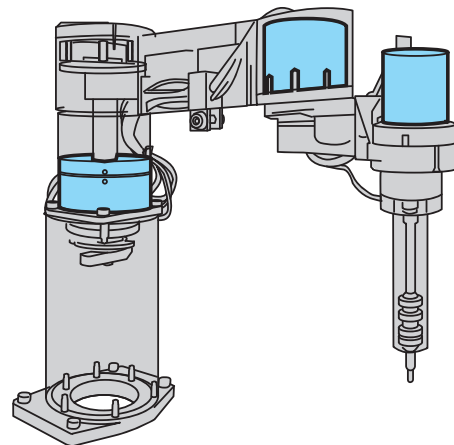
Want to make robot hand that can
pick up various work



Sensor-less torque control

It can realize small / high backdrivability robot hand. It provides highly responsive torque control.

Less human resource for production facility
Want to develop automation robot



Scalar development

By using μ DD motor, it can develop easy-to-use, essentially safe, small scalar. It is possible to consist elements required for cobot such as direct teaching, external force detection, quiet operation only with motor.