

The Desktop 6D is a 6 active degrees-of-freedom haptic device. Its workspace and small footprint address it to an individual use, in front of a desktop screen, a HMD or inside a simulator.

# Industrial training

# Medical teleoperation

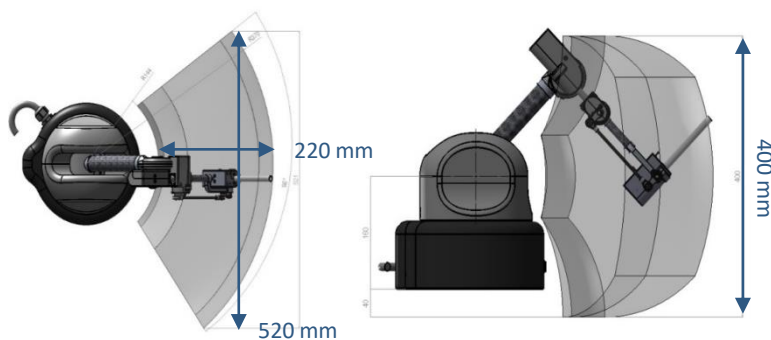
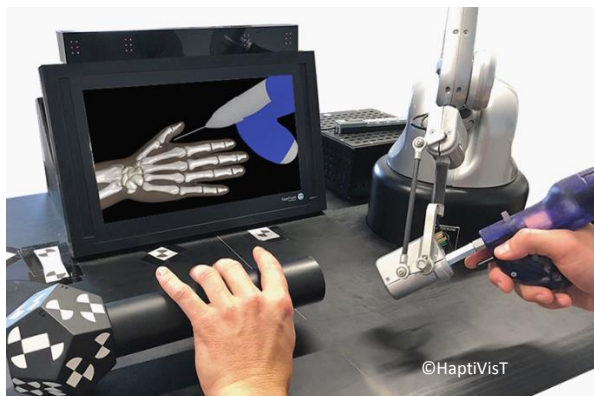
# Medical training & simulation

# Virtual Reality



## 6 ACTIVE DEGREES-OF-FREEDOM

- ✓ Passive weight balancing
- ✓ Ethernet/UDP communication system
- ✓ Easily removed handle: standard M6 connector
- ✓ Software interface:
  - ✓ Dedicated plug-ins for: 3DExperience™, Catia™ & Delmia™ V5, Solidworks™
  - ✓ Drivers (binary and/or source code) available for: Python™ for IPSI™, ROS™, ROS2™, CHAI3D™, ODE™, Matlab Simulink™, LabVIEW™
  - ✓ By Partner: Unity3D™ by LS Group, TOIA™ by Generic Robotics



## MODULARITY

The user takes hold of the haptic device using a gripper or handle placed at the tip (called “end-effector”).

The end-effector uses a M6 standard connector.

It is easy to remove and replace, so that a frequent change of tool is possible, in order to customize the application and reinforce the sensation of immersion. The gripping tool is equipped with three push-buttons. One of the push-buttons is dedicated to the offset function, while the state of the other buttons can be accessed using the VIRTUOSE API.



## TECHNICAL

Translation workspace	520 x 220 x 400 mm
Rotation Workspace	260° x 95° x 240°
Payload (center of the workspace):	10 N (peak)/ 3 N (continuous)
Rotation force: Peak, Continuous	0.8 Nm, 0.2 Nm
Position resolution	0.023 mm
Rotation resolution	0.0023 °
Device Weight	4.6 kg

## ELECTRICAL

Power supply	100-240 VAC 50/60Hz single phase
Consumption	Less than 200W

## SOFTWARE

Maximum translation stiffness	1000 N/m
Maximum rotation stiffness	4 Nm/rad
Update Rate	1000 Hz

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

### HAPTION S.A.

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