


## Configuring RIOS for the AL5 Series Robot Arms.

Lynx Arm Config \*\*\* NOT Connected !...Virtual robot \*\*\*

**Arm size**

 Arm...

**Base**

Height: 6.193

Radius: 4.803

**Length**

Forearm: 15.4

Arm: 15.4

**Hand/Grip**

Max Open: 3.175

Max Length: 10.16

Servo H: 3

**Joint deg - Angle moves**

Base: 0

Shoulder: 90 Neutral: 90

Elbow: -65 Distance: -15.4 Y: 6.193 Neutral/A: -90

**Wrist**

Z Rotate: 0

Angle / Table: -15 Distance: -1.443 Y: 12.701 Neutral/F: 0

**Grip**

Open/Close: 57 Opening: 1.733 Length: 10.16

X: 8.35 Distance: 8.35 Y: 9.995 Z: 0

**Linear moves**

Y Z

X Distance

**Torques**

	Angle	Torque	Servo load
Wrist	-15.44	0.37	<div></div>
Elbow	25	1.87	<div></div>
Shoulder	180	-1.22	<div></div>

Gravity compensate: ☐ On ☒ Off

Empty  Load  Edit

Save Exit

Figure 1.

Click on "Arm..." then select "SES" and "New Design" base. This will give you the most similar setup, with the correct gripper option. You will need to change the following dimensions under the "Arm Size" heading.

## Arm Size Values

### ***All Arms***

Base: Height = 6.9 cm

Hand/Grip: Max Length (No Wrist Rotate) = 8.7 cm

Hand/Grip: Max Length (With LW Rotate) = 11.3 cm

Hand/Grip: Max Length (With HD Rotate) = 10.0 cm

### ***AL5A***

Length: Forearm = 10.8 cm

Length: Arm = 9.4 cm

### ***AL5B***

Length: Forearm = 12.7 cm

Length: Arm = 11.9 cm

### ***AL5C***

Length: Forearm = 15.4 cm

Length: Arm = 15.6 cm

### ***AL5D***

Length: Forearm = 18.7 cm

Length: Arm = 14.7 cm