

Franka Emika AI Platform Main Specifications

Proposal for standard manipulation learning platform

by Franka Emika and NVIDIA

| | | |
|--------------------------------------|---|-----------------------|
| Price of every component | Panda Robot (including Arm, Hand and controller with FCI interface, without taxes) | € 15.500 ¹ |
| | Camera, e.g. Intel RealSense D435i | € 200 ² |
| | Computer, e.g. Nvidia Jetson Xavier | € 1.349 ² |
| Where is it available? | All hardware components are available globally. | |
| Hardware configuration | | |
| How many parts are there in total? | (Arm, Hand, Mount, Camera) + Controller + Computer | 3 |
| Power requirements | (Average / Maximum) | (140 / 430) W |
| Cable connections | Controller power cable + controller-robot cable + controller-computer cable + camera-computer cable + computer power cable | 5 |
| Sensors | | |
| In robot arm | Dedicated position, current and torque (link-side) sensors in all 7 joints | |
| In robot gripper | Position and force (via current) sensing | |
| In camera | The Intel Real Sense offers complete depth cameras integrating vision processor, stereo depth module, RGB sensor with color image signal processing and Inertial Measurement Unit (IMU) | |
| Additional sensors | | |
| Low-level interface | | |
| API language(s) | Open Source C++ library with official integration into MATLAB Simulink, ROS, MoveIt! and NVIDIA Isaac | |
| Interface frequency (read and write) | | 1000 Hz |
| Command level | Joint position, joint velocity, cartesian pose, cartesian velocity and torque control | |
| Robot state | Joint level signals: motor and estimated joint angles and their derivatives, joint torque and derivatives, estimated external torque, joint collision/contacts | |
| | Cartesian level signals: cartesian pose, configured end effector and load parameters, external wrench acting on the end effector, cartesian collision | |
| Model | Numerical values of M, C, G, J are available at 1 kHz | |
| Gripper commands | Gripper width, velocity and grasping force | |
| Gripper state | Gripper width and force | |
| Gripper access | Gripper is accessed via TCP/IP-based commands, not in real-time. | |
| Hardware connection | Ethernet cable, using the Franka Control Interface | |
| Protocol | UDP-based | |
| Minimum PC requirements | Linux with PREEMPT_RT patched kernel, 100BASE-TX network card | |

¹: ICRA 2019 promotional price (Europe), valid until June 30th, 2019.

²: Reference price from the manufacturer's web store.