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ROBO Cylinder RCS2-SA7C - Intelligent Actuator

9.5 71 64 14 50 33 73 71 43 Ma Moment Offset Reference Position *3 A Details Of A (mounting Holes And Reference Surface) ø9.5 ø6 5.5 6 6 71 73 Reference Surface 18 18 (4.8) 3 ME SE 13.3 44.7 16.3 52 73 13.3 5.1 48 58 1 52 7 5 BR: Brake Cable Exiting From Right BE: Brake Cable Exiting From Mar 27th, 2024

RCA2 ROBO Cylinder RCA2-TCA3NA - Intelligent Actuator

28 1. 4 15 6 2-M4 Depth 6 22 4 30 32 2 32 2-M3 Depth 3 17 15 Reference Position For The Moment Offset Home ME *2 ST 2 8 L 8L 2 26 40 7 L1 M 9.5 Secure At Least 100mm ST : Stroke ME : Mechanical End +0.03 ø3 0 Depth 3 3 +0 0.0 5 Depth 3 4 11.5 16 7 16 4-M4, Through 32 31 23 43 45 23.6 K3 K2 3 0 +0.0 5 Depth Jan 25th, 2024

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¥Mobile Robotics ÐDetect The Structure Of Ground; Detect Obstacles; Convoying ¥Graphics/video ÐDetect Foreground Objects And Matte In Other Objects (super-ma Trixefc) ¥Surveillance ÐDetect And Classify Vehicles On A Street Or In A Parking Garage ¥Medical ÐMeasurement)(e.g.'sizing Tumors) ÐVisualization (e.g. Register With Pre-operative CT) Feb 19th, 2024

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On The Manipulator. In Addition, The Dynamic Model Described By Equation (3) Can Be Parameterized As: $M\ddot{q} + B\dot{q} = Y(q;\dot{q})\mu$, Where $Y(q;\dot{q})$ 2