# ROHand Dexterous Hand User Guide V1.0.5

Overview

The ROHAND dexterous hand has a total of 11 motion joints, with 6 built-in motor drivers and the motor control circuit. With 6 active degrees of freedom, and a built-in PID motor control algorithm, the hand can mimic the human hand to achieve a variety of grasping grips. Typical applications include robot end effectors, educational and scientific research equipment, bionic prosthetics, etc.

ROHand dexterous hand with UART, RS485(Download driver) or CAN(Download driver) physical interface, support SerialCtrl dedicated serial protocol, ModBus-RTU protocol and CAN protocol, can provide ROS / ROS2 platforms for secondary development with SDK. ROHand is currently divided into the following versions:

ROH-A001/ROH-A002	*ROH-AP001*	*ROH-LiteS001*

184mm   **183mm**   **169mm**
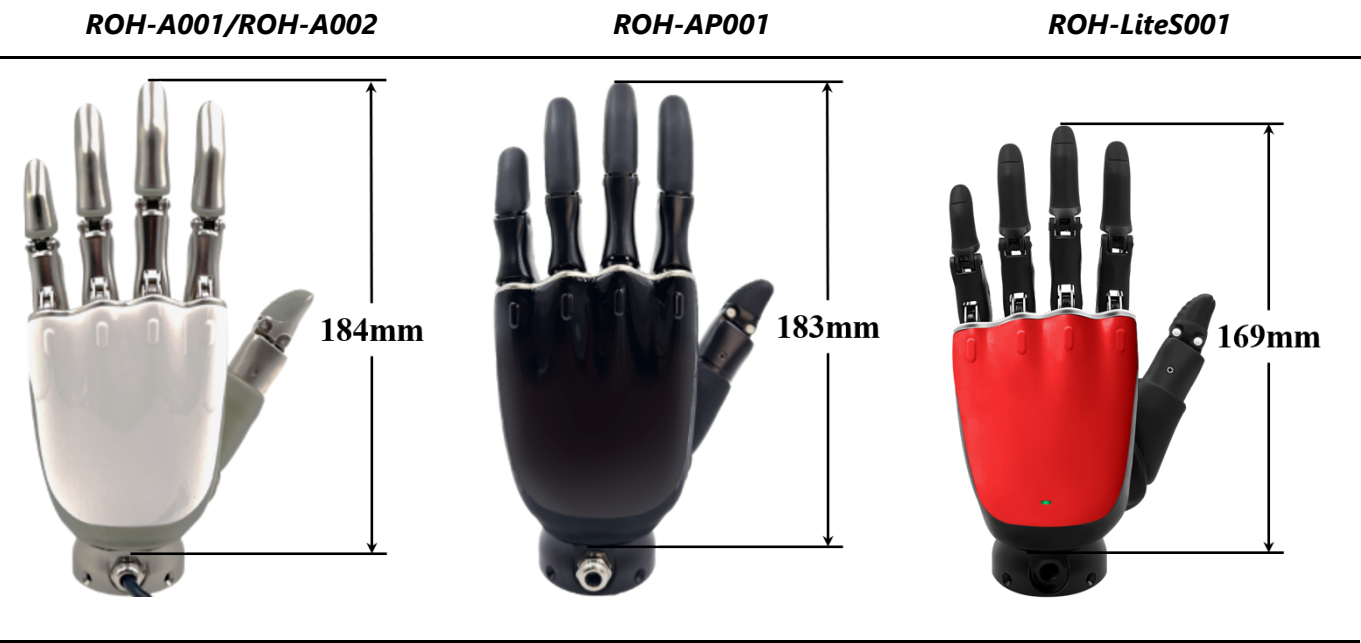
Resources

Resource Type	ROHand Type		
	ROH-A001/ROH-A002	**ROH-AP001**	**ROH-LiteS001**
Software, Firmware and Protocol	A001/A002 firmware	AP001 firmware	LiteS001 firmware
User Manual	A002	AP001	LiteS001
Developing Tools	C/C++ SDK | Python SDK		
ROS_URDF	ROS1 | ROS2	ROS1 | ROS2	ROS1 | ROS2
MuJoCo	MuJoCo		
ROS Package	ROS package | ROS2 package		
Python Example Code	Python Demos	Python Demos	
RM65 Robotic Arm Demos	ROH With RM65		

Revision history

Version	Date	Content
1.0.0	2025.09.03	Initial version
1.0.1	2025.09.03	Added size identification to the picture
1.0.2	2025.09.03	Adjusted the size identification of the picture
1.0.3	2025.09.05	Adjusted the table of resources
1.0.4	2025.10.14	Added python sdk and MuJoCo model, change LiteS001 picture
1.0.5	2025.10.31	Added manual link, add revision history