



Quick Guide for Installation

# FRANKA GELLO

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Product Reference:

Franka article number	Revision	Model number	Description
315200	00-01	10074730	Franka GELLO
313684	00-05	10074108	Franka GELLO Arm (part of Franka GELLO)



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## TABLE OF CONTENTS

TABLE OF CONTENTS .....	3
1 PURPOSE AND SCOPE .....	4
2 LEGAL DISCLAIMER .....	4
3 ABOUT FRANKA GELLO .....	5
4 SCOPE OF DELIVERY / INCLUDED IN THE BOX .....	6
5 ASSEMBLY INSTRUCTIONS.....	8
6 SOFTWARE .....	10

# 1 PURPOSE AND SCOPE

The quick guide for installation provides step-by-step instructions for assembling and connecting Franka GELLO system. It is intended to help users quickly set up the hardware and prepare it for initial operation with Franka Research 3.

The guide covers:

- Components included in the package
- Correct assembly procedures
- Reference to further resources for teleoperation and programming

## Intended Audience

This guide is designed for:

- **Researchers** working with robotic systems
- **Technicians** responsible for hardware setup
- **Developers** integrating GELLO into custom applications

Basic familiarity with robotic hardware and safe handling of electronic components is recommended.

# 2 LEGAL DISCLAIMER

Franka GELLO-Arms are experimental development tools that are provided solely for testing and evaluation purposes. They are not part of the certified product portfolio of Franka Robotics GmbH and are supplied 'as-is' without any express or implied warranties, including but not limited to warranties of merchantability, fitness for a particular purpose, or conformity. The Supplier does not provide any support, maintenance, or updates for these tools. Any liability for material or legal defects is excluded, except in cases of willful misconduct or gross negligence. This clause shall not affect mandatory liability under applicable product liability laws or for injury to life, body, or health.

### 3 ABOUT FRANKA GELLO

Franka GELLO is a teleoperation device for Franka FR3 robot. It is kinematically equivalent to the FR3 robot, but scaled down in dimensions, allowing users to control the FR3 directly at joint level. The hardware is an upgraded version of the hardware used in the original GELLO paper by Philipp Wu et al. <sup>1</sup>

It is especially useful for researchers who want to explore:

- Intuitive joint-level teleoperation
- Large-scale data recording for imitation Learning, e.g., training of Vision-Language-Action models

Comparing GELLO with VR controllers and 3D spacemouses for teleoperation tasks, the authors of the paper have found that “utilizing GELLO results in consistently faster completion times. This not only signifies that GELLO is easier to use with a higher success rate but also indicates its efficiency; faster completion times would enable users to achieve more successful operations in a given time frame”.



Figure 1: Franka GELLO in resting pose

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<sup>1</sup> Wu, P., Shentu, Y., Yi, Z., Lin, X., & Abbeel, P. (2023). *GELLO: A General, Low-Cost, and Intuitive Teleoperation Framework for Robot Manipulators*.

Available at: [https://wuphilipp.github.io/gello\\_site/](https://wuphilipp.github.io/gello_site/)

## SCOPE OF DELIVERY / INCLUDED IN THE BOX

The hardware and software of Franka GELLO Duo are open source, so anyone in the community can access and use them freely. Franka Robotics has contributed a ROS 2 implementation of the GELLO software and 3D-printable parts compatible with Franka FR3 Duo to the original author's repositories:

- [https://github.com/wuphilipp/gello\\_software](https://github.com/wuphilipp/gello_software)
- [https://github.com/wuphilipp/gello\\_mechanical](https://github.com/wuphilipp/gello_mechanical)

### NOTICE

Franka GELLO is designed to match the kinematics of Franka FR3 Robot Arm v2.0 and later versions. Previous robot versions slightly differ.

## 4 SCOPE OF DELIVERY / INCLUDED IN THE BOX

Item No.	Components	Quantity
1	Franka GELLO Arm	1 pc.
2	Table Base Mount Single	1 pc.
3	Screws M4x12	4 pcs.
4	OpenRB-150 Controller	1 pc.
5	Screws C2x8 black	4 pcs.
6	Cable USB-A to USB-C 2m	1 pc.
7	Reference to Assembly Guide	1 document



See Figure 2 below for a visual reference

SCOPE OF DELIVERY / INCLUDED IN THE BOX

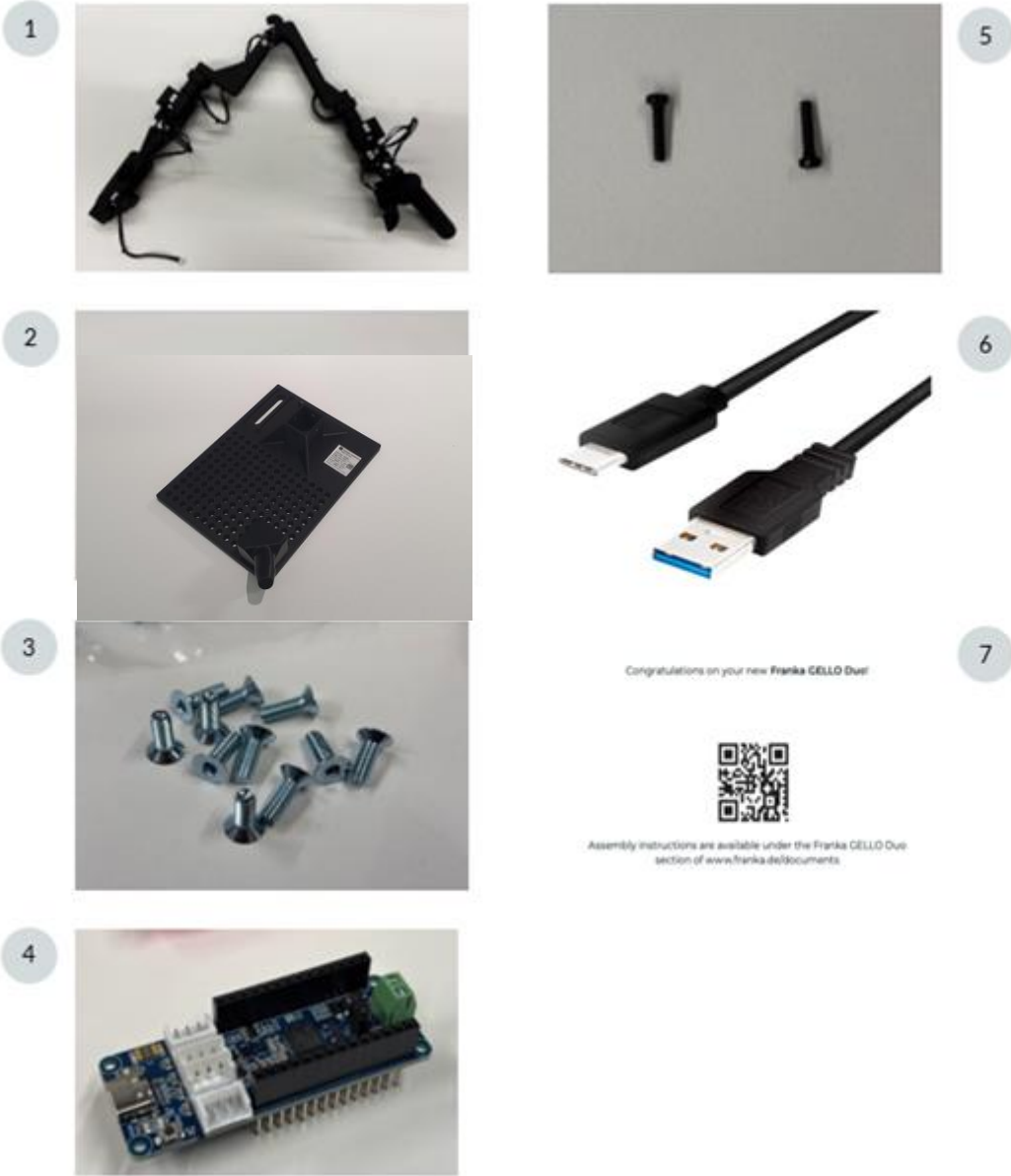


Figure 2: Visualization of included items

## 5 ASSEMBLY INSTRUCTIONS

### Step 1 – Install the Controllers

1. Position the **OpenRB-150 Controller** (4) on the left side of the base (top corner).
2. Check that the USB-C port faces outward for easy access.
3. Fix the controller using **four screws C2×8 black** (5).

### Step 2 – Mount Franka GELLO Arm

1. Place the **Table Base Mount** (2) on a stable surface.
2. Attach **Franka GELLO Arm** (1) to the base.
3. Use four **M4×12 screws** (3) to secure them firmly.

### Step 3 – Connect the System

1. Plug **Franka GELLO Arm** (1) cable connector into any of the four white connectors on the controller (4).
2. Ensure all connections are secure before continuing.
3. Connect the **OpenRB-150 controller** (4) to your **PC** using the **USB-A to USB-C cable** (6).

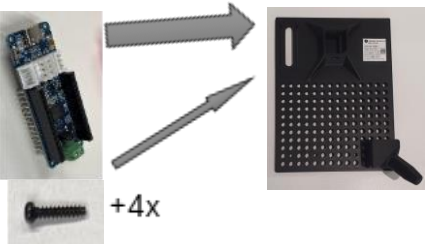


Step	Instruction
1	
2	
3	

Figure 3: Assembly

ASSEMBLY INSTRUCTIONS

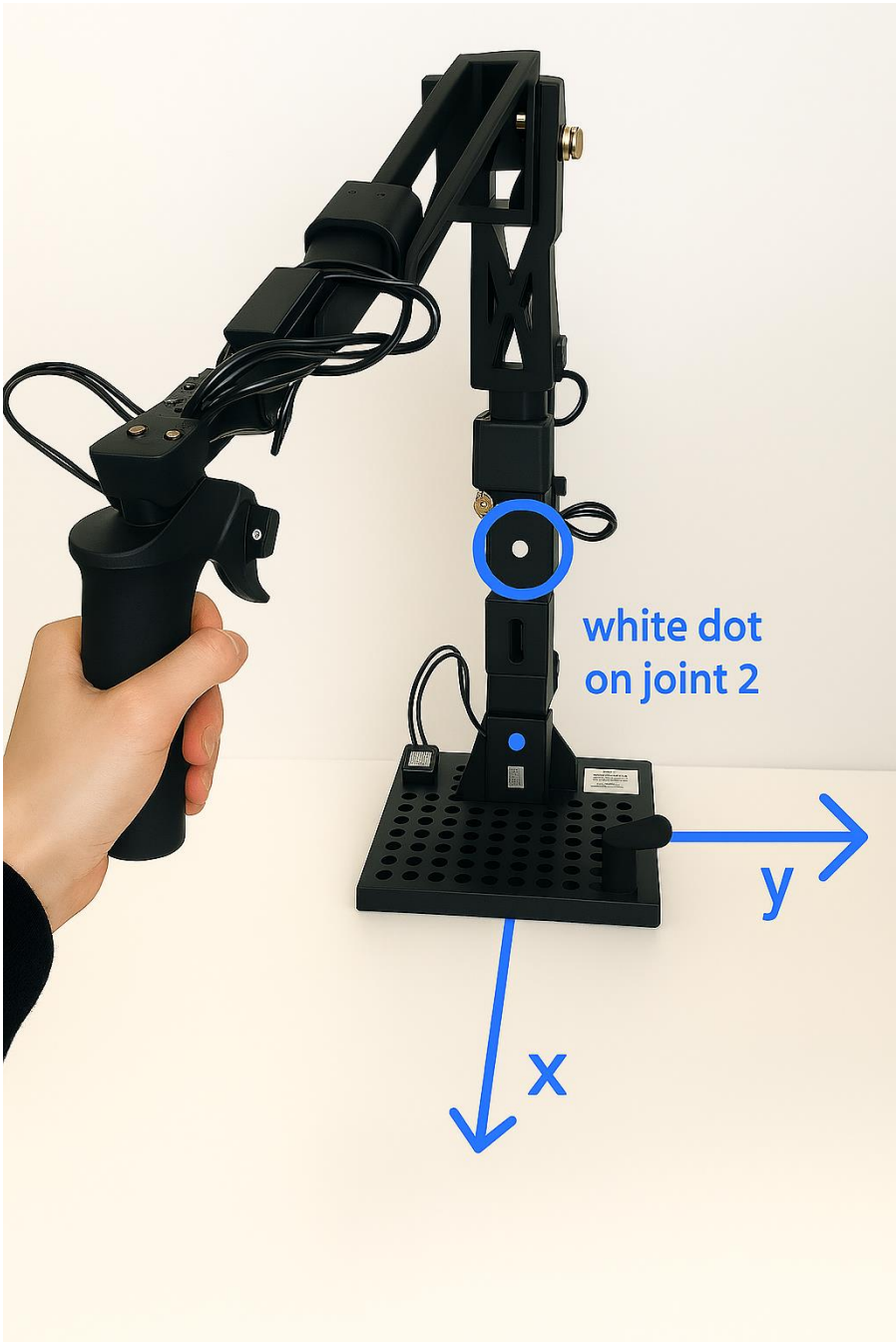


Figure 4: Correct orientation of Franka GELLO

## 6 SOFTWARE

The ROS 2 integration to control a Franka FR3 robot system using Franka GELLO is available in the “ros2” subfolder of the “gello\_software” repository: [https://github.com/wuphilipp/gello\\_software/tree/main/ros2](https://github.com/wuphilipp/gello_software/tree/main/ros2).

*Refer to the README of the “ros2” folder for instructions on launching ROS 2 nodes.*

### NOTICE

The ROS 2 package “franka\_gello\_state\_publisher” requires a configuration file for each individual GELLO system which defines its hardware properties and settings.

For Franka GELLO a suitable configuration file is provided:

```
ros2/src/franka_gello_state_publisher/config/franka_gello_single.yaml
```

To use it:

- Update the **com\_port** entries so they match the ID of your controller.
- Refer to the **README** for detailed instructions on how to identify this ID.

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