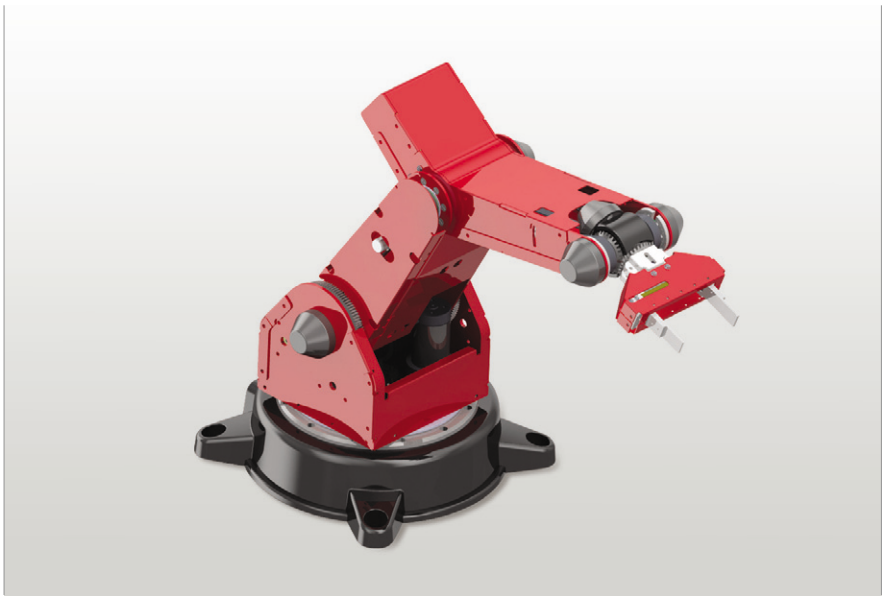
New

5-AXIS ARM ROBOT TRAINER

ED-7255

- Consists of one gripper and 5-axis vertical multi joints
- Absolute-type RVDT Position Sensor applied to each axis and requires no Limit switch
- High performance CPU enables real-time control of each axis
- PID gain tuning and real-time control
- Emergency switch on the robot controller and teaching pendant
- Control by USB and Ethernet interface
- Expandible 2-axis and digital or analog I/O port
- 3D graphic simulation and real-time connectivity with a real robot



> EXPERIMENTS

- Introduction to the System
  - » Basic Configuration
  - » Description of components
  - » Overview of Program
  - » Architecture
  - » Installation
- Program Composition
  - » Menu and Toolbar
  - » View and Windows
  - » Simulator and Screen control
  - » Industrial language editor
- Arm Viewer and Robot Manipulation
  - » How to use "3D Arm Viewer"
  - » Manual mode for controlling the robot
  - » Storage and utilization of the position data
- Programming
  - » How to use Program Editor
  - » Program syntax
  - » Programming
  - » Program execution and debugging
- Robot Simulation
  - » Virtual simulation and robot manipulation methods
  - » Basic experiments 1
  - » Basic experiments 2
  - » Basic experiments 3
- Robot Control Basic Experiment
  - » Position transfer methods
  - » Velocity transfer methods
  - » Position determination methods
  - » How to use "Teach Pendant"
- Applications for Robot Manipulation
  - » Accurate transfer through block repetitions
  - » Grip and transfer for a certain object
  - » Position transfer for a certain object
  - » Repetitive operation and simulation-linked transfer

> CONFIGURATION

- Introduction to the System
  - » Basic Configuration
  - » Description of components
  - » Overview of Program
  - » Architecture

5-AXIS ARM ROBOT TRAINER

ED-7255

> SPECIFICATIONS

ARM PROCESSOR

- **CPU**
  - » 666MHz, Min : 1ea
- **NAND FLASH**
  - » 128MByte : 1ea
- **NOR FLASH**
  - » 1MByte : 1ea
- **DRAM**
  - » 128MByte : 1ea
- **DPRAM**
  - » 128k : 1ea

DSP PROCESSOR

- **TMS320F2811**
  - » 150MHz : 1ea
- **Motion Control**
  - » Closed loop operation : 1ea
- **Avaliable motor 8-axis**
  - » CPLD : 1ea
- **Avaliable PWM Generation**
  - » 8 axis : 1ea
- **Absolute encoder counter**
  - » 8 channels : 1ea

DRIVER PACK

- **Operating environment**
  - » 24V, 120W Max : 8ea

INTERFACE

- **USB**
  - » USB 1.1 A-Type(Pendant) : 1ea
  - » USB 2.0 B-Type(Host PC) : 1ea
- **Ethernet**
  - » 10Base-T : 1ea
- **RTC**
  - » Real Time Clock : 1ea
- **State LED**
  - » Alarm, Start/stop : 3ea
- **Character LCD**
  - » 20 x 2 : 1ea
- **Digital Input**
  - » 0~24V : 8ea
- **Digital output**
  - » 0~24V : 8ea
- **Analog Input**
  - » 0~10V : 4ea
- **Analog output**
  - » 0~10V : 4ea
- **Relay Output**
  - » SC, OC : 4ea

ROBOT BODY

- Width : 280mm
- Depth : 280mm
- Height : Max. 786mm
- Weight : 12.7kg
- Operating Part

Link Number	Operating Range	Link Length	Weight
No. 0(Base)	0	80mm	5.9kg
No. 1	-170~+170°	107mm	3.4kg
No. 2	-30~+94°	230mm	3.3kg
No. 3	-0~+130°	230mm	1.9kg
No. 4	-110~+110°	0mm	0.6kg
No. 5	-110~+110°	0mm	0.05kg
No. 6(Gripper)	0 ~ 80mm (Rubber Pad)	139mm	0.35kg

TEACH PENDANT

- Display : 20 x 2 Character LCD
- Interface : USB 1.1
- Key : 37 user key(Emergency switch included)

ROBOT CONTROLLER DIMENSION

- Width : 250mm
- Depth : 309mm
- Height : 88.1mm
- Weight : 3.8kg

TEACH PENDANT DIMENSION

- Width : 138mm
- Depth : 190mm
- Height : 40mm
- Weight : 0.55kg

SIMULATOR ENVIRONMENT

- CPU : Pentium IV 2GHz or higher
- Memory : Above 512MB
- Operating System : Windows XP
- Graphic Card
  - » 3D accelerated graphic card

ACCESSORIES

- AC Power Cord
- USB Cable
- Controller Connection Cable
- Teach Pendant Cable
- RJ-45 Cable
- Software and User Manual