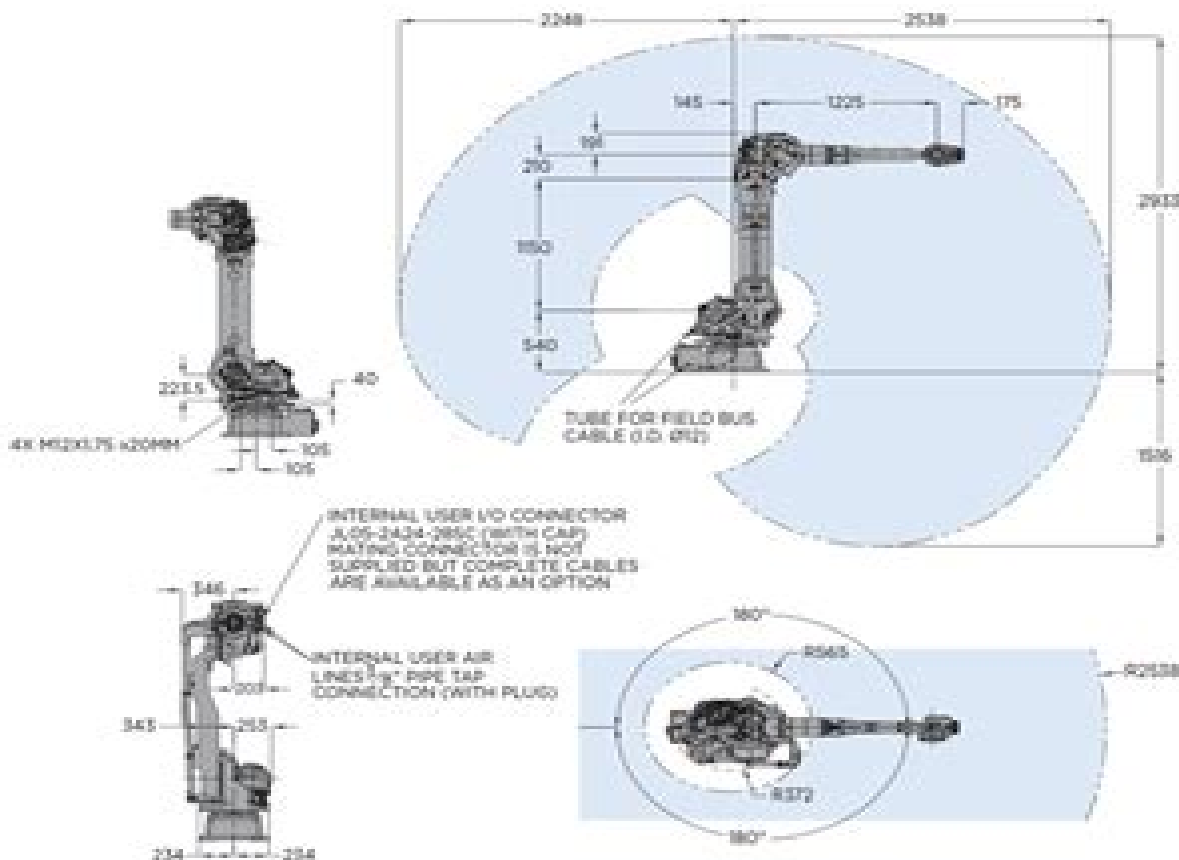




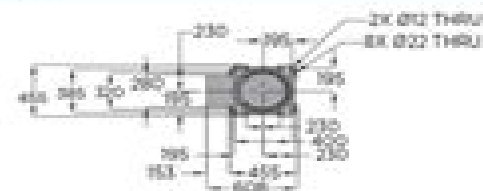
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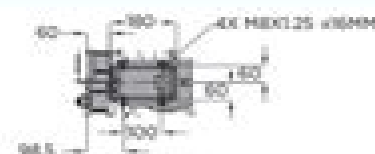
VIEW B



VIEW C



VIEW D



All dimensions are metric (mm) and for reference only. Request detailed drawings for all design/engineering requirements.

## SPECIFICATIONS

| Axes | Maximum motion range | Maximum speed | Allowable moment | Allowable moment of inertia |
|------|----------------------|---------------|------------------|-----------------------------|
|      | degrees              | °/sec         | Nm               | kgm <sup>2</sup>            |
| S    | ±180                 | 180           | -                | -                           |
| L    | +135/-90             | 140           | -                | -                           |
| U    | +205/-80             | 178           | -                | -                           |
| R    | ±360                 | 250           | 147              | 10                          |
| B    | ±125                 | 250           | 147              | 10                          |
| T    | ±360                 | 360           | 78               | 4                           |

| Item                    | Unit | GP35L                   |
|-------------------------|------|-------------------------|
| Controlled axes         |      | 6                       |
| Maximum payload         | kg   | 35                      |
| Repeatability           | mm   | 0.07                    |
| Horizontal reach        | mm   | 2,538                   |
| Vertical reach          | mm   | 4,449                   |
| Weight                  | kg   | 600                     |
| Internal user I/O cable |      | 24 conductors w/ ground |
| Internal user air line  |      | (2) 3/8" connection     |
| Power requirements      |      | 380-480 VAC             |
| Power rating            | kVA  | 4.5                     |

Specifications for GP35L with KP package may be different. Mounting Options: Floor, Wall, Tilt or Ceiling

\* The MLX500 software option is not available for use with arc or spot welding applications. MLX500 fieldbus cards, I/O cards and vision equipment must be purchased separately from the supplier. All peripherals are programmed using a PLC.

# Motoman Robot Parts Manual

**D Keegan**



### **Motoman Robot Parts Manual:**

*Introduction to Robotics* Phillip McKerrow, 1991 This book provides an introductory text for students coming new to the field of robotics and a survey of the state of the art for professional practitioners Some of the outstanding features of this book include A unique approach which ties the multi disciplinary components of robotics into a unified text Broad and in depth coverage of all the major topics from the mechanics of movement to modelling and programming Rigorous mathematical treatment of mature topics combined with an algorithmic approach to newer areas of research Practical examples taken from a wide range of fields including computer science electronic engineering mechanical engineering and production engineering Step by step development of problems and many worked examples **Robotics Today**, 1987

**International Robotics Industry Directory**, 1984 **Mechatronics** Ajay Kumar, Parveen Kumar, Sarita Rathee, Brijesh Kumar, 2025-02-19 This text describes how the design analyzing capacity and optimization criteria of mechatronics systems can be improved using numerical experimental and computational approaches and how it helps in data sensing fault detection and diagnosis It further discusses topics such as intelligent mechatronics systems and their applications in manufacturing robotics and automation This book Discusses the applications of mechatronics systems in manufacturing automation robotics medical pharmaceuticals ground and air transportation sectors Presents numerical experimental and computational approaches for signal sensing fault detection and diagnosis Highlights the importance of using smart technologies such as artificial intelligence the Internet of Things digital twins machine learning and deep learning for mechatronic systems Illustrates the concept of controlling mechatronics devices using virtual reality VR augmented reality and mixed reality Explains the need for the Internet of Things for mechatronics systems and applications in biomedical and pharmaceutical industries It is primarily written for senior undergraduates graduate students and academic researchers in the fields of mechanical engineering industrial and manufacturing engineering electrical engineering electrical and electronics engineering automotive engineering and computer engineering *New Technology Japan*, 1991 *Precision Assembly in the Digital Age* Svetan Ratchev, 2018-12-31 This book constitutes the refereed post conference proceedings of the 8th IFIP WG 5.5 International Precision Assembly Seminar IPAS 2018 held in Chamonix France in January 2018 The 20 revised full papers were carefully reviewed and selected from numerous submissions The papers address topics such as machine vision and metrology for assembly operations gripping and handling technologies numerical methods and planning in assembly digital technologies and Industry 4.0 applications precision assembly methods assembly systems and platforms and human cooperation and machine learning They are organized in the following topical sections design and deployment of assembly systems human robot cooperation and machine vision assembly methods and models digital technologies and industry 4.0 applications and gripping and handling solutions in assembly **Springer Handbook of Robotics** Bruno Siciliano, Oussama Khatib, 2008-05-20 With the science of robotics undergoing a major

transformation just now Springer's new authoritative handbook on the subject couldn't have come at a better time Having broken free from its origins in industry robotics has been rapidly expanding into the challenging terrain of unstructured environments Unlike other handbooks that focus on industrial applications the Springer Handbook of Robotics incorporates these new developments Just like all Springer Handbooks it is utterly comprehensive edited by internationally renowned experts and replete with contributions from leading researchers from around the world The handbook is an ideal resource for robotics experts but also for people new to this expanding field

Intelligent Assembly and Disassembly 2001 Peter Kopacek, Carlos Eduardo Pereira, Dragica Noe, 2002 Rapid development observed in modern production systems is firmly connected with the development of new assembly and disassembly systems One of the oldest forms of industrial production assembly and its twin area disassembly have both enjoyed tremendous modernisation in the era of the Information Revolution New enabling technologies including prominent examples such as virtual CAD Design for Assembly and Disassembly DFAD Robotic and Intelligent Assembly and Flexible Assembly FA are now becoming commonplace This volume presents the papers from the 2nd IFAC Workshop on Intelligent Assembly and Disassembly IAD 2001 The colloquium highlighted the issues of IAD showed the actual results of the research and development work set the direction of future development and analysed the possibility of introducing IAD into production processes Including 3 invited papers and 17 technical papers authored by researchers from across the globe the papers cover important fields of product development such as product design development of planning systems simulation and modelling as well as sessions on e manufacturing and education

**The Engineer**, 1998

Wearable Robots José L. Pons, 2008-04-15 A wearable robot is a mechatronic system that is designed around the shape and function of the human body with segments and joints corresponding to those of the person it is externally coupled with Teleoperation and power amplification were the first applications but after recent technological advances the range of application fields has widened Increasing recognition from the scientific community means that this technology is now employed in telemanipulation man amplification neuromotor control research and rehabilitation and to assist with impaired human motor control Logical in structure and original in its global orientation this volume gives a full overview of wearable robotics providing the reader with a complete understanding of the key applications and technologies suitable for its development The main topics are demonstrated through two detailed case studies one on a lower limb active orthosis for a human leg and one on a wearable robot that suppresses upper limb tremor These examples highlight the difficulties and potentialities in this area of technology illustrating how design decisions should be made based on these As well as discussing the cognitive interaction between human and robot this comprehensive text also covers the mechanics of the wearable robot and its biomechanical interaction with the user including state of the art technologies that enable sensory and motor interaction between human biological and wearable artificial mechatronic systems the basis for bioinspiration and biomimetism general rules for the development of biologically inspired designs and how these could serve

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