

装卸机器人用多用途夹持装置 Multi-purpose gripper for handling robot

柔性抓手 FLEXhand



FH360-01(3指)



FH150F3-01(3指)



FH150F2-01(2指)



FH360-01

特点

宽范围 & 柔性可变行程

- 自由的夹持行程,支持多种工件
- 也可夹持异形工件
- 可在拿取密集的工件方面发挥威力

方便的测量功能

- 自动检测工件尺寸,并可进行筛选

柔性的夹持力控制

- 可夹持易变形、损坏的零件

防止坠落功能

- 关闭电源时亦保持夹持力,不使工件坠落,非常安全
(※制动夹持时)

考虑了节能、环保方面

- 因不用气动,所以削减了运行成本
- 可通过制动夹持进行节电
(※可切换伺服夹持和制动夹持)

Features

Large and flexible variable stroke

- Adjustable gripping stroke covers a wide variety of work pieces
- Able to pick up varied shaped work piece
- Suitable for picking tightly packed parts

Useful Measuring Function

- Automatically detects size of work piece for verification

Programmable grip force control flexibility

- Able to grip fragile parts

E-Stop Gripping Protection

- Maintain grip even if power loss or E-Stop situation with brake grip

Energy saving, environmentally friendly

- Low operating costs with airless system
- Reduced electric costs with brake grip
(can select between servo grip and brake grip)

规格 Specifications

项目 Item		规格 Specifications		
型号 Model		FH360-01	FH150F3-01	FH150F2-01
指数 Number of fingers		3		2
自由度 Number of axes		2(夹紧轴、手臂旋转轴) 2(clamp axis, swivel axis of arm)		1(夹紧轴) 1(clamp axis)
驱动方式 Drive system		AC伺服方式 AC servo system		
最大夹持力 Max. gripping strength ^{※1 ※2}		3,600N	1,500N	
夹持力的可设置范围 Gripping strength range ^{※1}		1,000~3,600 N	500~1,500N	
夹紧方向 Clamp orientation		外夹紧和内夹紧可 Outer clamp & inner clamp		
最大工件质量 Max. weight of work piece ^{※3}		25kg	7kg	
尺寸测量精度 Accuracy of size measuring ^{※4}		±0.2mm		
动作范围(每指) Operating range (per finger)	夹紧轴 Clamp axis	0~60mm	0~50mm	
	手臂旋转轴 Swivel axis of arm	0 ~ 1.05 rad	—	
最快速度(每指) Max. velocity (per finger)	夹紧轴 Clamp axis	45mm/s	60mm/s	
	手臂旋转轴 Swivel axis of arm	1.57rad/s	—	
最大夹持力时的容许爪手长度 Allowable claw length under max. gripping force ^{※5}		150mm	100mm	
周围温度 Ambient temperature		0~45℃		
耐环境性 Resistant to environment ^{※6}		与IP65相当 IP65 equivalent		
本体质量 Weight ^{※7}		24.0kg	12.5kg	8.3kg

1[rad]=180/π[°], 1[N]=1/9.8[kgf]

※1 全指总计

※2 根据爪手形状、夹紧速度、夹持力的不同,该值可能与设置值有所不同。设置值是大致目标而非保证值。

※3 根据爪手形状、工件形状、工件表面性状以及夹持姿势的不同,可能有所限制。

※4 测量精度是使用标准规在同一条件(同一把持力同一夹紧速度)下进行的相对尺寸测量精度。无法进行绝对尺寸的测量。并且测量值是参考值,根据条件不同而不同。

※5 根据夹持力、夹持姿势而不同。

※6 不可在有机溶剂、酸、碱、氯系、汽油系切削液等使密封部件劣化的液体环境中使用

※7 不包括爪手和附加垫板。

※1 Total of all fingers

※2 The real grip force might be different from the set value according to the shape of claw and grip speed. Setting grip force is just an aim, not guaranteed.

※3 Limited by claw shape, work piece shape, surface of work piece, and gripping orientation.

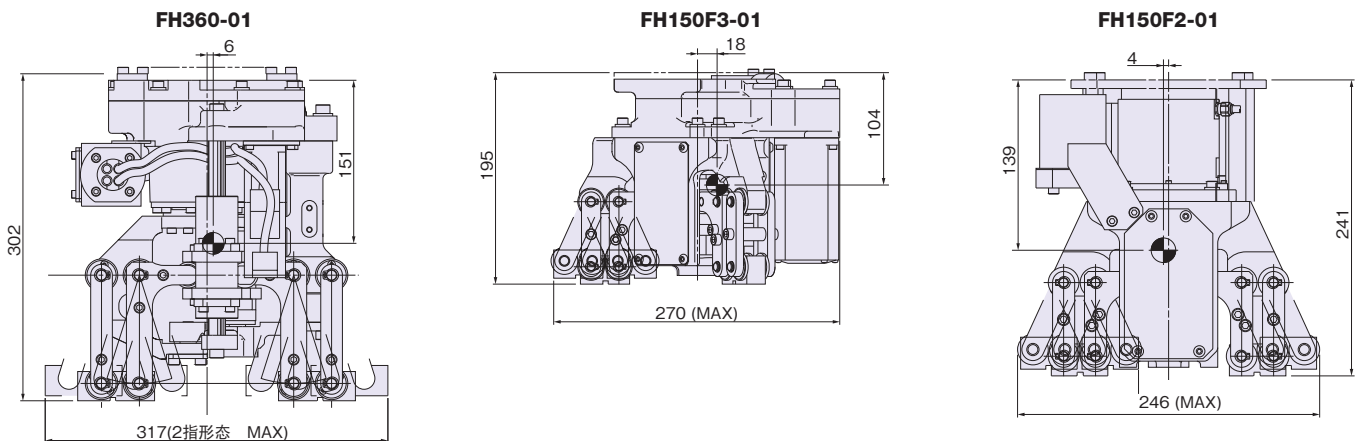
※4 Accuracy of size measuring is the relative measuring compared with the result using master gauge under the same condition (same grip force and same clamp velocity). Absolute size can not be measured. This value is just for reference and may vary according to the condition.

※5 Varies depending on grip strength and orientation.

※6 Cannot be used in an environment in which it may be splashed with fluids that corrode the seal material, such as organic solvents, acids, alkalis, chlorine, and petroleum-based cutting fluids.

※7 Not including claws and adapter plates.

外形尺寸 Exterior dimensions



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