


KUKA | Xpert

Identification number: AR6188

货号	0000-180-193
材料状态	60 - 客户服务
制造商	KUKA Roboter
产品图片	

技术数据

基本数据

	KR 16-2 F
轴数	6
可控制的轴数	6
工作空间体积	14.5 m ³
位姿重复精度 (ISO 9283)	± 0.05 mm
重量	约 235 kg
额定负荷	16 kg
最大负载能力	-
最大运动范围	1611 mm
防护等级 (IEC 60529)	IP65
机器人腕部防护等级 (IEC 60529)	IP67
噪声等级	< 75 dB (A)
安装位置	地面
占地面积	-
运动系统安装面布孔图	C500
允许倾角	-
标准色	底座： 黑色 (RAL 9005); 活动部件： 库卡橙色 2567
控制系统	KR C4; KR C2 edition2005
变压器名称	KR C2: KR16_2 C2 FLR ZH16_2; KR C4: KR16_2 C4 FLR ZH16_2

环境条件

湿度等级 (EN 60204)	EN 60204/4.4.4 F
环境条件分类 (EN 60721-3-3)	-
环境温度	
运行时	10 °C 至 55 °C (283 K 至 328 K)
仓储和运输时	-40 °C 至 60 °C (233 K 至 333 K)

轴数据

运动范围	
A1	±185 °
A2	-155 ° / 35 °
A3	-130 ° / 154 °
A4	±350 °
A5	±130 °
A6	±350 °
额定负载时的速度	
A1	156 °/s
A2	156 °/s
A3	156 °/s
A4	330 °/s
A5	330 °/s
A6	615 °/s

负载能力

额定负荷	16 kg
最大负载能力	-
法兰 I_x 额定质量转动惯量	0.36 kgm ²
法兰 I_y 额定质量转动惯量	0.36 kgm ²
法兰 I_z 额定质量转动惯量	0.36 kgm ²
底座的额定附加负载	0 kg
底座的最大附加负载	-
转盘的额定附加负载	0 kg
旋转机构的最大附加负载	20 kg
大臂的额定附加负载	0 kg
大臂的最大附加负载	20 kg
小臂的额定附加负载	10 kg
小臂的最大附加负载	15 kg
负载重心额定距离	
L_{xy}	120 mm
L_z	150 mm

地基负载

纵向动力 F(v)	
F(v 正常)	-
F(vmax)	4600 N
横向动力 F(h)	
F(h 正常)	-
F(hmax)	5000 N
倾覆力矩 M(k)	
M(k 正常)	-
M(kmax)	5200 Nm
轴 2 转矩 M(r)	
M(r 正常)	-
M(rmax)	4200 Nm

垂直力 $F(v)$ 、水平力 $F(h)$ 、倾斜力矩 $M(k)$ 、轴 1 的转矩 $M(r)$

Process forces

Process forces are forces that are exerted on the robot in a defined manner by an external influence. Causes include pressing processes and machining tasks carried out by the robot. The process forces that the robot can withstand depend to a very great degree on the robot position, payload, direction and duration of action. For this reason, it is not possible for a simple limit value to be specified for permissible process forces.

Permissible process torques are therefore specified for all axes of the robot. These values indicate the torque that each robot axis can withstand on a sustained basis as a result of external forces.

The following load torques must not be exceeded:

A1	1050 Nm
A2	600 Nm
A3	515 Nm
A4	51.9 Nm
A5	51.9 Nm
A6	18.8 Nm

Flange loads

Flange loads

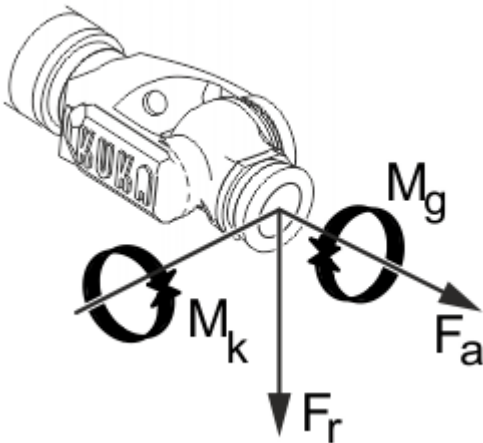
Due to the motion of the payload (e.g. tool) mounted on the robot, forces and torques act on the mounting flange. These forces and torques depend on the motion profile as well as the mass, load center of gravity and mass moment of inertia of the payload.

The specified values refer to nominal payloads at the nominal distance and do not include safety factors. It is imperative for the load data to be entered in the robot controller. The robot controller takes the payload into consideration during path planning. A reduced payload does not necessarily result in lower forces and torques.

The values are guide values determined by means of trial and simulation and refer to the most heavily loaded machine in the robot family. The actual forces and torques may differ due to internal and external influences on the mounting flange or a different point of application. It is therefore advisable to determine the exact forces and torques where necessary on site under the real conditions of the actual robot application.

The operating values may occur permanently in the normal motion profile. It is advisable to rate the tool for its fatigue strength.

The EMERGENCY STOP values may arise in the event of an Emergency Stop situation of the robot. As these should only occur very rarely during the service life of the robot, a static strength verification is usually sufficient.



Flange loads

Flange loads during operation	
F(a)	810 N
F(r)	741 N
M(k)	76 Nm

M(g)	61 Nm
Flange loads in the case of EMERGENCY STOP	
F(a)	859 N
F(r)	1306 N
M(k)	157 Nm
M(g)	117 Nm

Axial force $F(a)$, radial force $F(r)$, tilting torque $M(k)$, torque about mounting flange $M(g)$

轨迹精度

线性运动的轨迹精度:

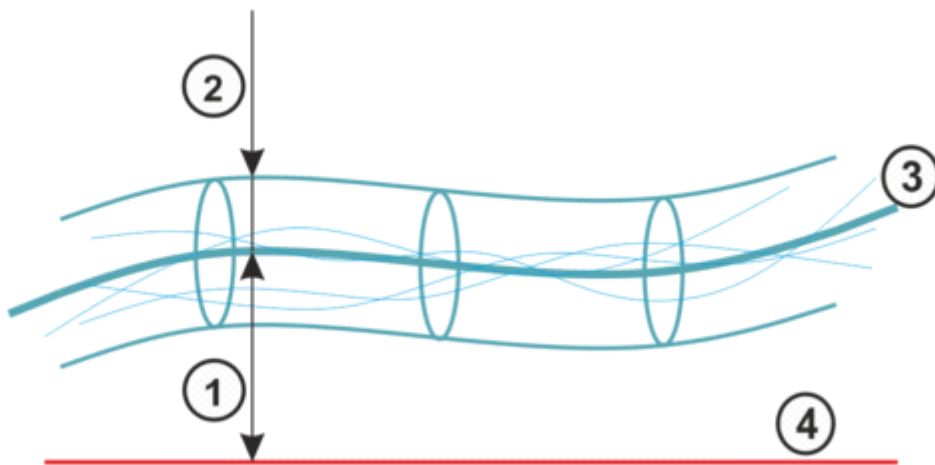
LIN 轨迹绝对精度 (ISO 9283)	$\pm 0.9 \text{ mm}$
SLIN 轨迹绝对精度 (ISO 9283)	-
轨迹重复精度 线性 (ISO 9283)	$\pm 0.2 \text{ mm}$

该数据针对的是 1 m/s 的参考速度。

圆周运动的轨迹精度:

CIRC 轨迹绝对精度 (ISO 9283)	$\pm 0.8 \text{ mm}$
SCIRC 轨迹绝对精度 (ISO 9283)	-
圆周轨道重复精度 (ISO 9283)	$\pm 0.4 \text{ mm}$

该数据针对的是 0.5 m/s 的参考速度。



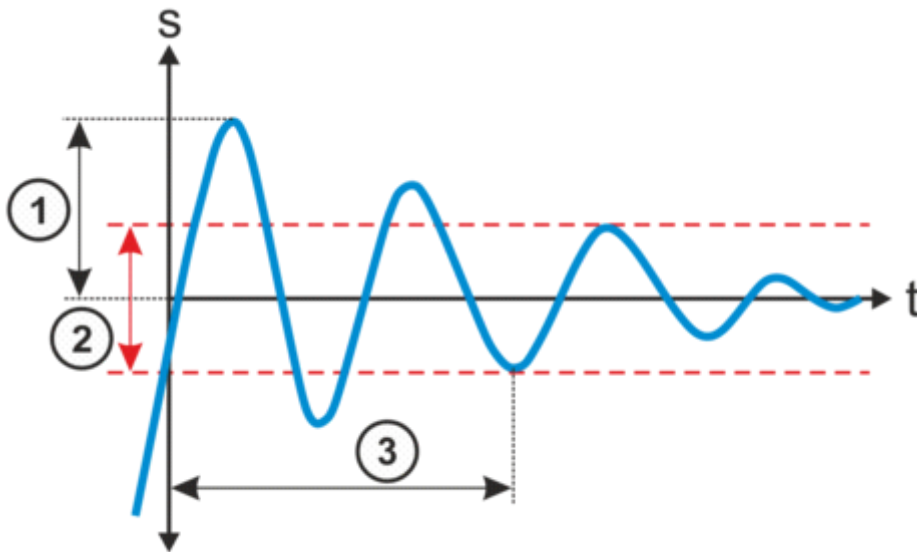
轨迹精度

1	轨迹绝对精度	3	运行轨迹的平均值
2	轨迹重复精度	4	编程的轨迹

- 轨迹精度表示机器人在编程的轨迹上运动的能力。
- 轨迹重复精度表示 10 个运行轨迹与运行轨迹平均值的偏差。

超调状态

振幅	1 mm
定位时间	0.5 s



超调状态

1	超调振幅	3	定位时间
2	公差范围		

- 超调振幅影响机器人在特定位置执行受控的精确暂停的能力。
- 定位时间表示机器人在特定位置上停止的速度。

更多的信息

- 给出的数据基于 ISO 9283，并使用 Krypton/Metris 的基于摄像机的系统测得。因此重复精度被定义为 3 sigma 值。
- 所有数值均以额定负载测得。

关税信息

统计货号	84795000
原产地	DE
制造商	KUKA ROBOTER
重量	235 kg

- > **KR 16-2 F** 带有如下的标准组件 (4)
- > **KR 16-2 F** 需要 (25)
- > **KR 16-2 F** 带有如下的工具 (5)
- > **KR 16-2 F** 有以下选项 (32)