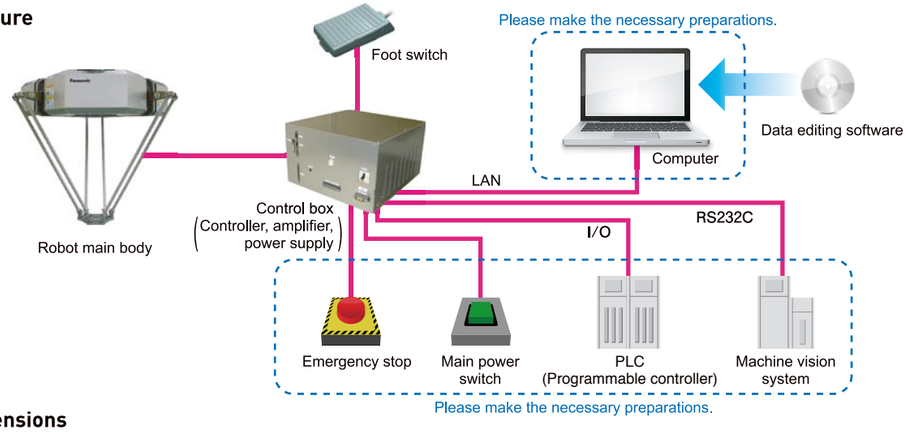
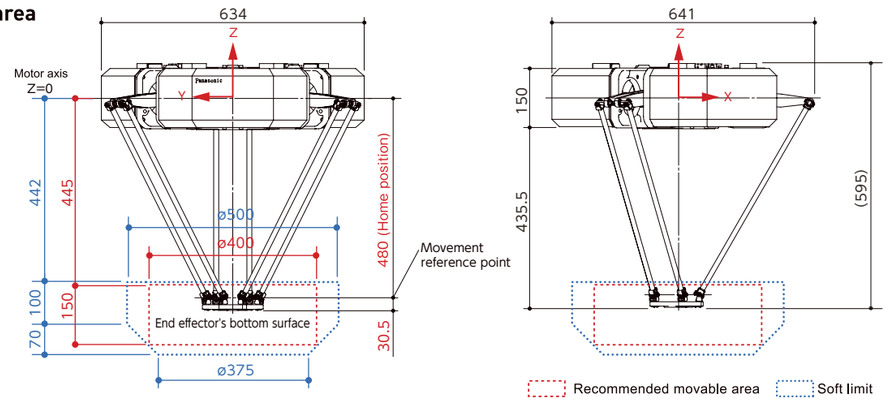
■ System structure



■ External dimensions and movable area



Basic specifications	Model number		AP-3310A0010
	Control axis numbers / drive system		6-axis/AC servomotor
	Teaching method		Point teaching, direct teaching
	External dimensions	Body	634 W x 641 D x 595 H mm (On installation)
		Control box	400 W x 420 D x 250 H mm
	Mass	Body	53kg
		Control box	20kg
	Recommended movable area		Diameter φ400mm, height 150mm (during horizontal movement)
	Swing/revolving angle		±30°(dependent on position)
	Repeatability		±0.02mm
	Maximum movable mass		1.5kg
	Power supply		Single phase 200 - 230V AC ±10%　50/60Hz　6A

Panasonic Parallel Link Robot　Search

http://industrial.panasonic.com/jp/products/product_cat2/AJAH000/AJAH000.html

⚠Safety Cautions

・Please read the User's Manual carefully to familiarize yourself with safe and effective usage procedures.

eco ideas　Panasonic Group products are built with the environment in mind.

http://panasonic.net/eco

ISO 14001　Panasonic Group builds Environmental Management System in the factories of the world and acquires the International Environmental Standard ISO 14001:2004.

Inquiries...

Panasonic Co.,Ltd.

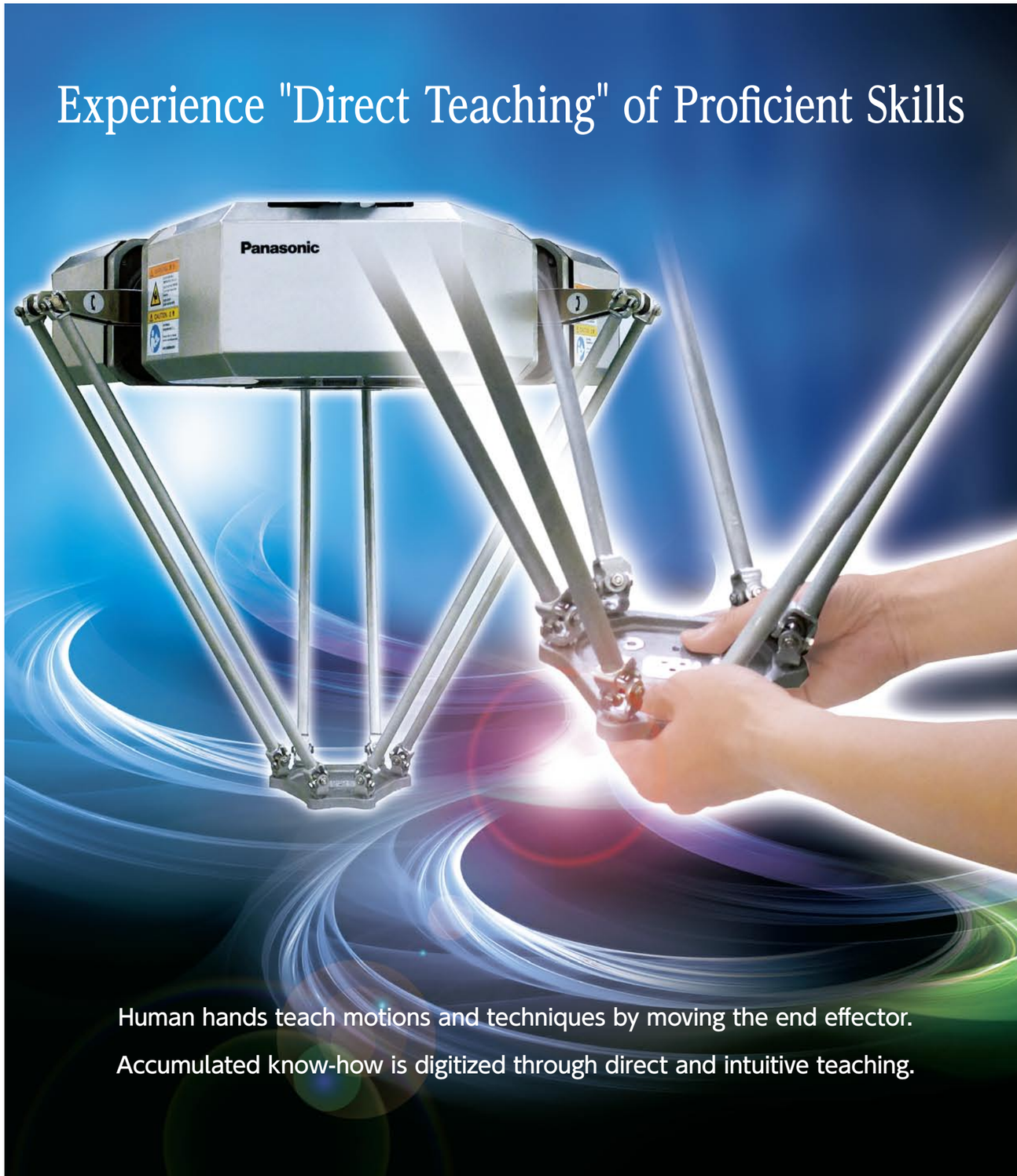
2-7 Matsuba-cho, Kadoma City, Osaka 571-8502, Japan

All Data as of January. 1. 2014.　Ver.2014.1.1

Panasonic

PARALLEL LINK ROBOT
catalog

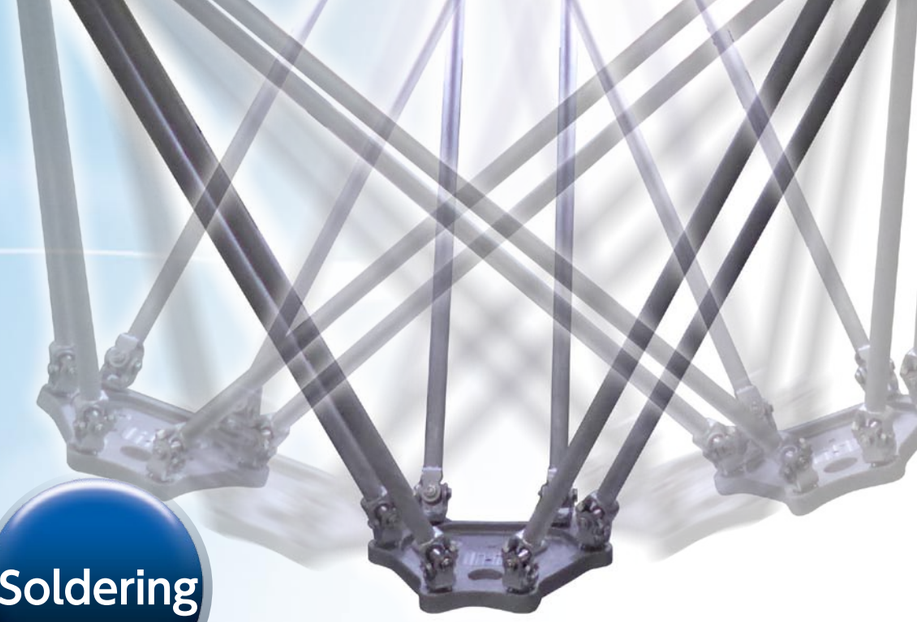
Experience "Direct Teaching" of Proficient Skills



Human hands teach motions and techniques by moving the end effector.

Accumulated know-how is digitized through direct and intuitive teaching.

Soft and firm —Parallel Link Robot for assembly process innovation



Flexible posture control for delicate work
Firm support of productivity enhancement and cost reduction

Major applications

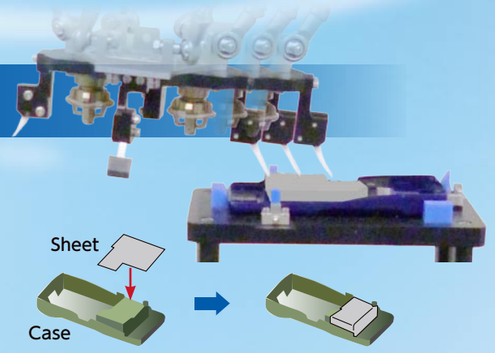
Parts insertion | Sheet application | Assembly | Coating application | Wiring | Soldering

Example 1

Sheet application using spatulas

- The robot automatically folds a sheet along the workpiece contour and applies it using four spatulas.
- All processes for folding and applying the sheet can be taught by direct teaching.

Direct teaching

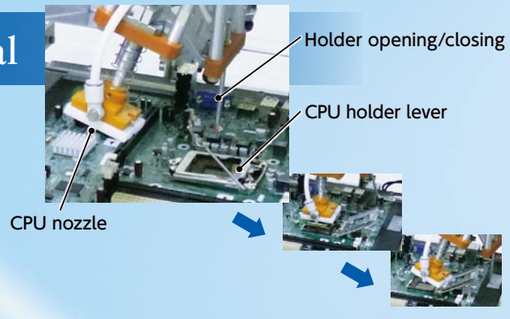


Example 2

CPU transfer, positioning, and removal

- The robot automatically transfers, positions, and removes CPUs using a CPU nozzle and a holder opening/closing bar.
- The holder opening/closing operations are taught by direct teaching.

Direct teaching

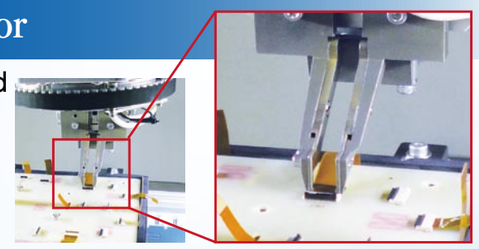


Example 3

FPC board insertion into a connector

- A camera recognizes the FPC board position, and a special chuck holds both ends of the board.
- The held board is slid and inserted into a connector and then locked.
- The insertion and locking operations are taught by direct teaching.

Direct teaching

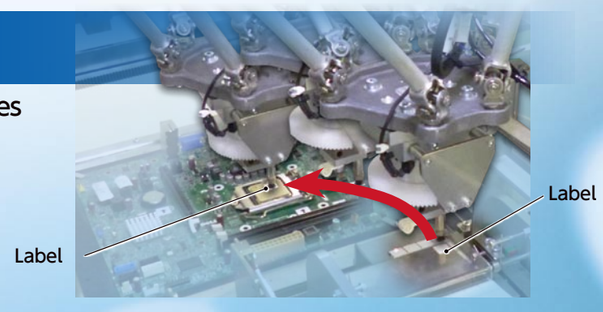


Example 4

Label application

- The label nozzle picks up a label and removes it from the liner from one end to the other.
- The nozzle applies the label to a workpiece, and presses it to prevent removal.
- The removal and pressing operations are taught by direct teaching.

Direct teaching



■Optional functions

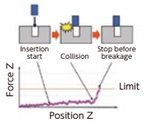
Collision detection function

Software

Collision detection prevents workpieces from breaking

This function detects a collision of the robot hand and stops the robot operation. External force with three degrees of freedom can be detected.

Detection range: 3 to 120 N
An external force log can be output.



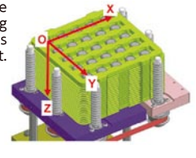
Palletizing function

Software

A position in a grid pattern can be easily specified

This function can teach the pallet position and define the number of divisions, eliminating the need to teach the positions of components to be taken out.

Up to 127 divisions can be set for each axis.
Tilted pallets can also be handled.

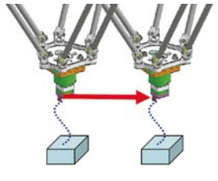


Direct teaching offset function

Software

Offset playbacks of direct teaching are available

Offset playbacks are available in the translation directions (X, Y, and Z) and the directions of rotation around the robot hand (θX, θY, and θZ).



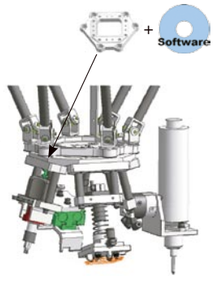
Multi-tool function and special end effector

Software

Multiple operations can be performed without tool change work

Multiple tools can be attached to the special end effector. The tool coordinate system can be switched.

Coordinate system switching: Cartesian system/Tool system
Maximum tool coordinate systems: 64
* Including the direct teaching offset function



3D recognition correction function

Software

Offset operations can be performed according to the recognition results

Offset operations in relation to the teaching coordinates are available in the translation directions (X, Y, and Z) and the directions of rotation around the robot hand (θX, θY, and θZ).