

MULTI-AXIS ROBOTS

Yaskawa – POWERED BY ARBURG
Handling weight: 12-25 kg

ARBURG

MULTI-AXIS ROBOTS

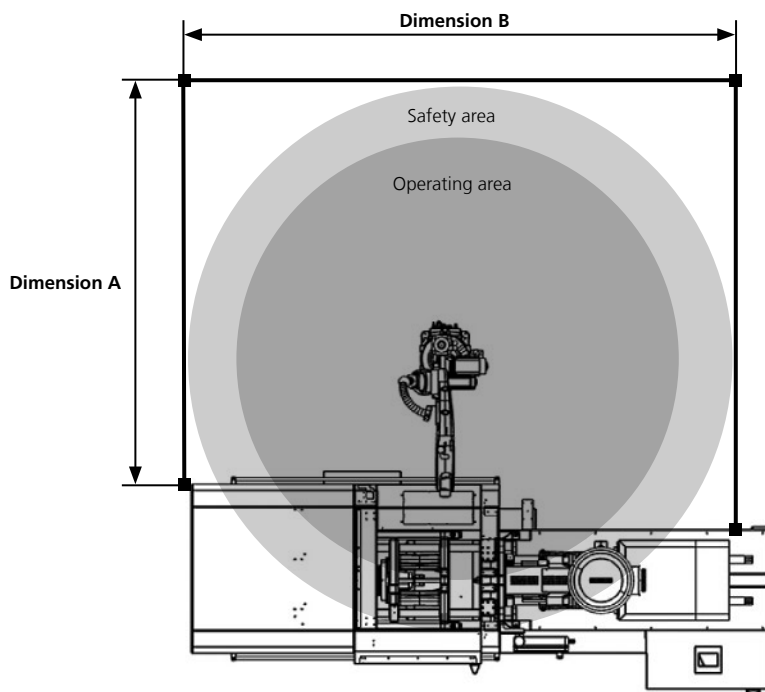
Multi-axis robots		ALLROUNDER machine sizes / models											
Yaskawa - powered by ARBURG	Nominal load ¹ [kg]	270	370	470	520	570	630	720	820	920	1120	V	T
GP12	12	•	•	•	•							•	•
GP20	20	•	•	•	•	•	•	•	•	•		•	•
GP25	25	•	•	•	•	•	•	•	•			•	•

1) Depending on the centre of gravity of the gripper

MULTI-AXIS ROBOTS

Multi-axis robots				ALLROUNDER machine sizes / models									
Yaskawa - powered by ARBURG	Nominal load ¹⁾ [kg]	Operating area - radius [mm]	In-line wrist [mm]	270		370		470		520		570	
				A*	B*	A*	B*	A*	B*	A*	B*	A*	B*
GP12	12	1440	100	2633	3620	2457	3820	2427	4020	2427	4120	4120	4220
GP20	20	1802	105	3300	4354	3124	4554	3194	4754	3194	4854	4854	4954
GP25	25	1730	100			2947	4400	3017	4600	3017	4700	4700	4800

Installation dimensions A and B



*) Installation dimensions A and B in mm
 1) Depending on the centre of gravity of the gripper

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Yaskawa - powered by ARBURG	Nominal load ¹⁾ [kg]	Operating area - Radius [mm]	In-line wrist [mm]	630		720		820		920		1120	
				A*	B*	A*	B*	A*	B*	A*	B*	A*	B*
GP12	12	1440	100										
GP20	20	1802	105	2930	5074	3120	5254	3170	5454	3120	5654		
GP25	25	1730	100	2753	4920	2943	5100	2993	5300				

*) Installation dimensions A and B in mm

1) Depending on the centre of gravity of the gripper

EQUIPMENT | MULTI-AXIS ROBOTS

An ARBURG ALLROUNDER is required in order to use the multi-axis robot.

Pneumatic valves for grippers

- Pneumatic valve for actuating functions, such as grippers, gripper tongs, cylinders, lifting and units (see additional information):
 - 1 with blocked middle position (5/3)
- Additional pneumatic valves (maximum 15) in any combination of the following versions (see additional information):
 - with blocked middle position (5/3)
 - with vented middle position (5/3)
 - with spring return (2 x 3/2)

Pneumatic maintenance unit

- One pneumatic maintenance unit
- Manually adjustable filter pressure reducing valve for adjusting the pressure level
- Pressure level monitoring
- Electric switch on/switch-to-standby function

Control system

- Mobile GESTICA or Mobile SELOCIGA
- Implemented user interfaces
 - Uniform operating system: graphic sequence programming for machine and robotic system
 - Teach-in function
 - Screen selection via function and shortcut keys
 - Robotic system can be moved set-wise analogously to the cycle
 - Programmable sequence branches
- Interface between robotic system and injection moulding machine (EUROMAP 67)
- Varan interface for extended real-time communication with the injection moulding machine and:
 - Single data set for injection moulding machine and robotic system
 - Coordinated movement to home position
 - Separation of test samples, reject parts and sprue
 - Creation of individual sequences for the first and last cycle
 - Cycle time reduction by movement into the mould from stroke position marker
 - Communication with more than two core pulls possible

Inputs/outputs for grippers

- Interface with 8 freely programmable inputs for querying sensors for gripper functions. All inputs connected to plugs, including mating plugs
- Additional interfaces (up to 3) for querying up to 24 sensors (in total)
- Freely programmable outputs for controlling pneumatic valves for gripper functions. All outputs directly connected to pneumatic valves

Inputs/outputs for peripheral equipment

- Additional interfaces (24V DC) with freely programmable inputs and outputs (up to 60). Not potential-free. Connected to socket on control cabinet, including mating plug
- Conveyor belt interfaces (maximum of 2, 230 V AC) for a conveyor belt to be supplied separately. Mating plug included.

Additional options

- Clean-room version
- Base for multi-axis robotic system
- Material for fastening the robot to the floor

Additional information

- 5/3 pneumatic valve with blocked middle position for gripper functions, the position of which should be maintained when not actuated, e.g. if the safety door is open, EMERGENCY STOP
- 5/3 pneumatic valve with vented middle position for gripper functions, which should be depressurised when not actuated, e.g. to ensure gentle transfer of parts by the ejector of the machine
- 2 x 3/2 pneumatic valve with spring return for gripper functions with spring return, e.g. for sprue grippers or single-acting pneumatic cylinders

■ Basic machine

○ Option

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