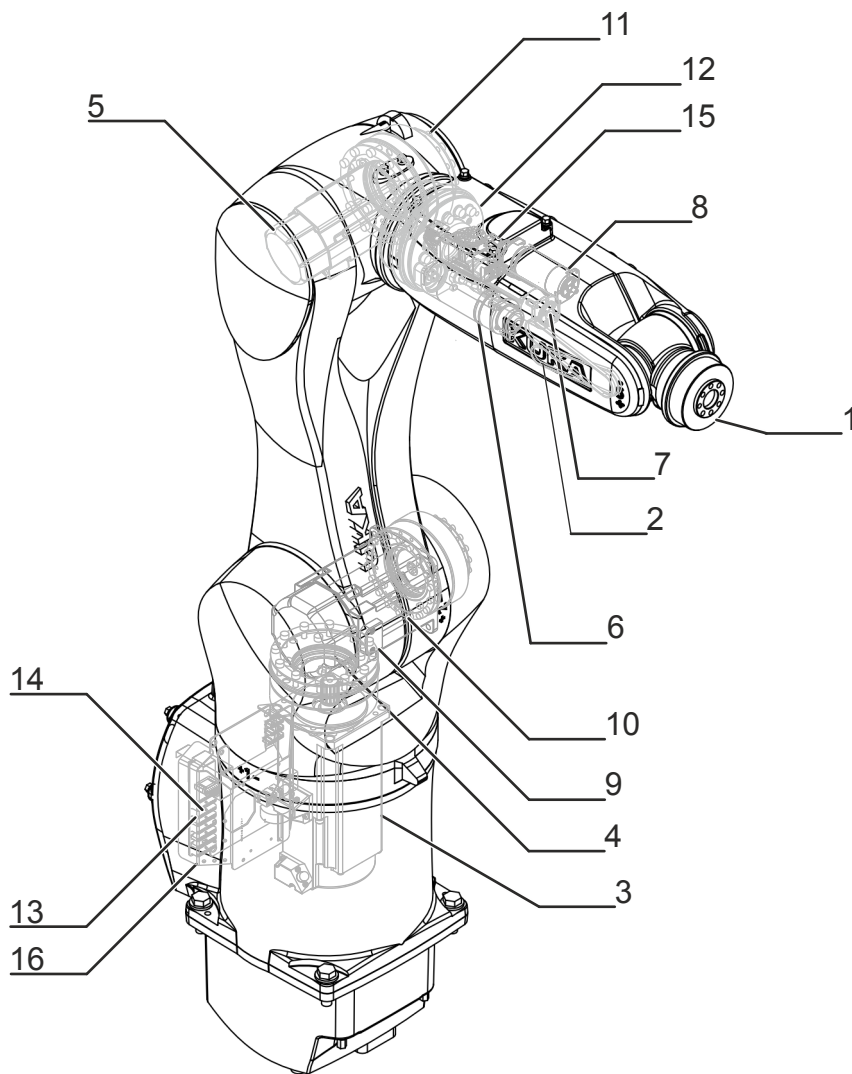


# KUKA | Xpert

Identification number: AR23956

货号	0000-293-598
材料状态	10 - 批准预生产
制造商	KUKA Roboter
产品图片	

# Spare parts



Spare parts graphic – schematic representation

Pos.	Article number	Designation	Component
1	0000-285-271	SPP sw.hous. A6 HM (w/o gr/ad)KR10R1100	In-line wrist
2	0000-256-761	SPP wrist belt set HM	Toothed belt
3	0000-252-708	SPP Motor A1 HM (without grease)	Motor A1
4	0000-256-591	SPP Motor A2 HM (wgg)	Motor A2

Pos.	Article number	Designation	Component
5	0000-256-592	SPP Motor A3 HM (wgg)	Motor A3
6	0000-252-712	SPP Motor A4 HM R900	Motor A4
7	0000-252-713	SPP motor A5 HM R900	Motor A5
8	0000-256-479	SPP motor A6 HM R900	Motor A6
9	0000-282-138	SPP gear unit A1 HM; KR10 (w/o gr/ad)	Gear A1
10	0000-282-139	SPP gear unit A2 HM; KR10 (w/o gr/ad)	Gear A2
11	0000-282-140	SPP gear unit A3 HM; KR10 (w/o gr/ad)	Gear A3
12	0000-256-480	SPP gearbox A4 HM(wgg) R900	Gear A4
13	0000-284-202	SPP RDC cool HM (Agilus)	RDC
14	0000-284-204	SPP EDS cool HM (Agilus)	EDS
15	0000-284-704	SPP valve unit assy HM (w/o gr/ad)	
16	0000-284-205	SPP I/O module cool HM (Agilus)	
17	0000-284-206	SPP connecting cable HM (Agilus)	
18	0000-203-379	Needle bearing w/o inner ring 139x145x17	
19	0000-203-381	Needle bearing w/o inner ring 118x123x10	
20	0000-200-304	Mini gauge cartridge	Gauge cartridge

Export to Excel 

# Maintenance information

## Toothed belt tension

Toothed belt tension inline wrist	
A5	205 ± 5 Hz
A6	205 ± 5 Hz

# 技术数据

## 基本数据

	<b>KR 10 R1100 HM-SC</b>
轴数	6
可控制的轴数	6
工作空间体积	5.14 m <sup>3</sup>
位姿重复精度 (ISO 9283)	± 0.03 mm
重量	约 64 kg
额定负荷	5 kg
最大负载能力	10 kg
最大运动范围	1101 mm
防护等级 (IEC 60529)	IP65 / IP67
机器人腕部防护等级 (IEC 60529)	IP65 / IP67
噪声等级	< 70 dB (A)
安装位置	地面; 屋顶; 墙壁; 任意角度
占地面积	320 mm x 320 mm
运动系统安装面布孔图	C246
允许倾角	-
标准色	底座: 交通白 (RAL 9016); 活动部件: 交通白 (RAL 9016)
控制系统	KR C4 compact
变压器名称	KR C4: KR10R1100 HM C4SR

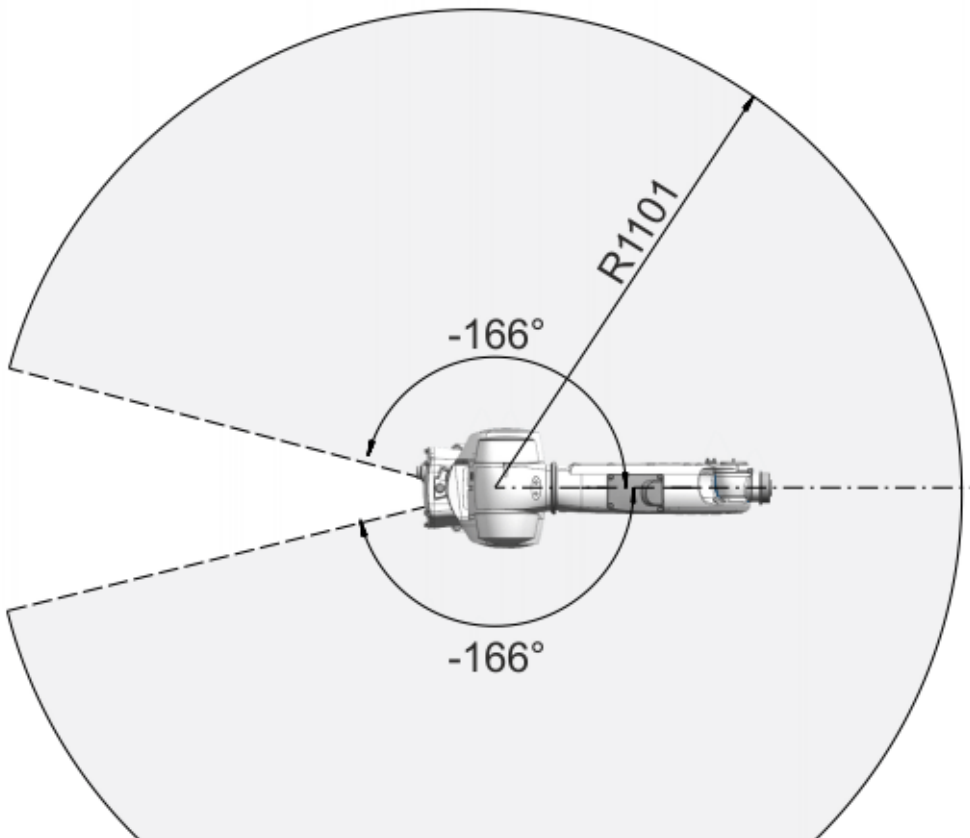
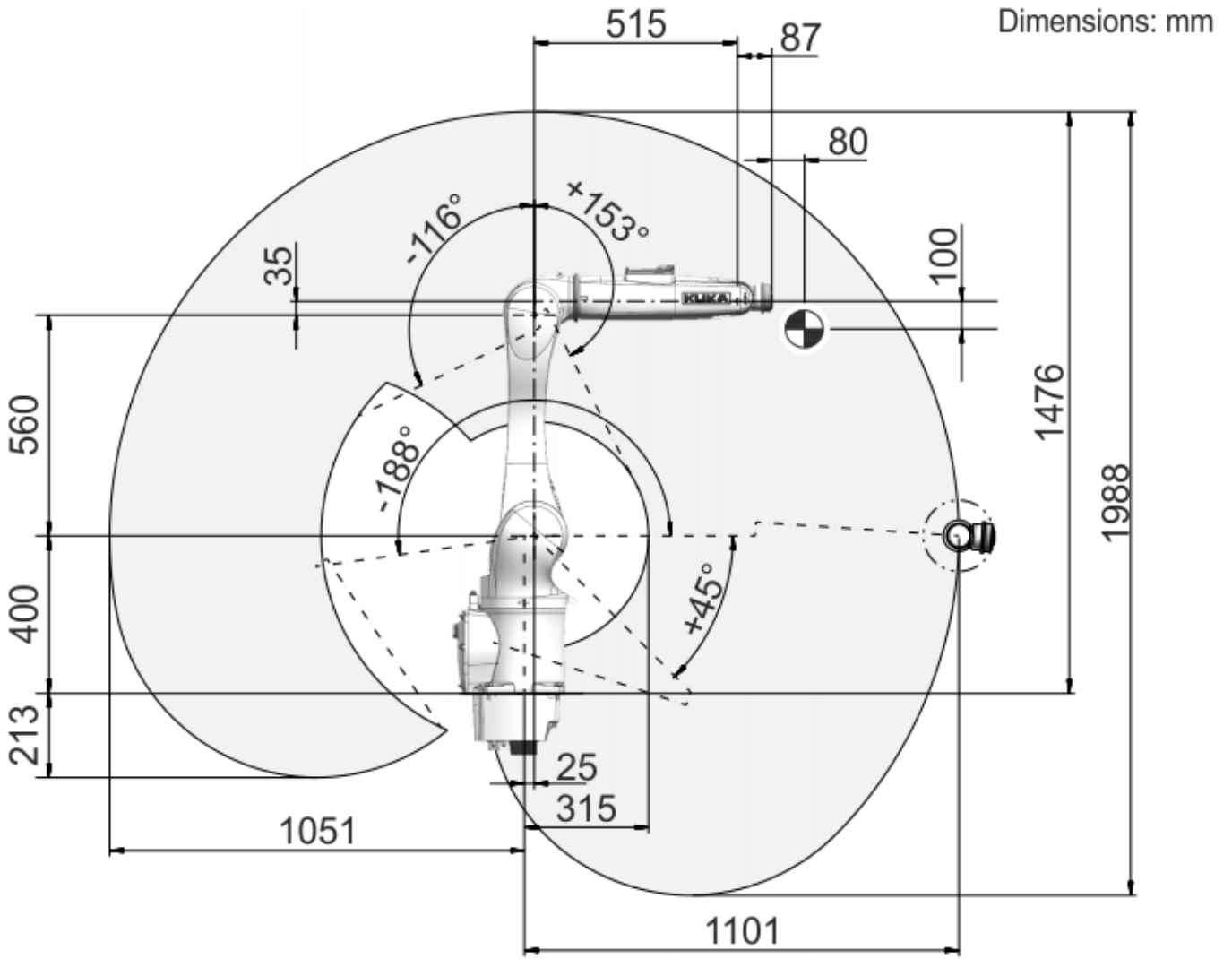
# 环境条件

湿度等级 (EN 60204)	-
环境条件分类 (EN 60721-3-3)	3B2; 3Z10
环境温度	
运行时	0 °C 至 35 °C (273 K 至 308 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	±166 °
A2	-188 ° / 45 °
A3	-116 ° / 153 °
A4	±185 °
A5	±110 °
A6	±350 °
额定负载时的速度	
A1	300 °/s
A2	225 °/s
A3	225 °/s
A4	381 °/s
A5	262 °/s
A6	414 °/s

# 工作区域





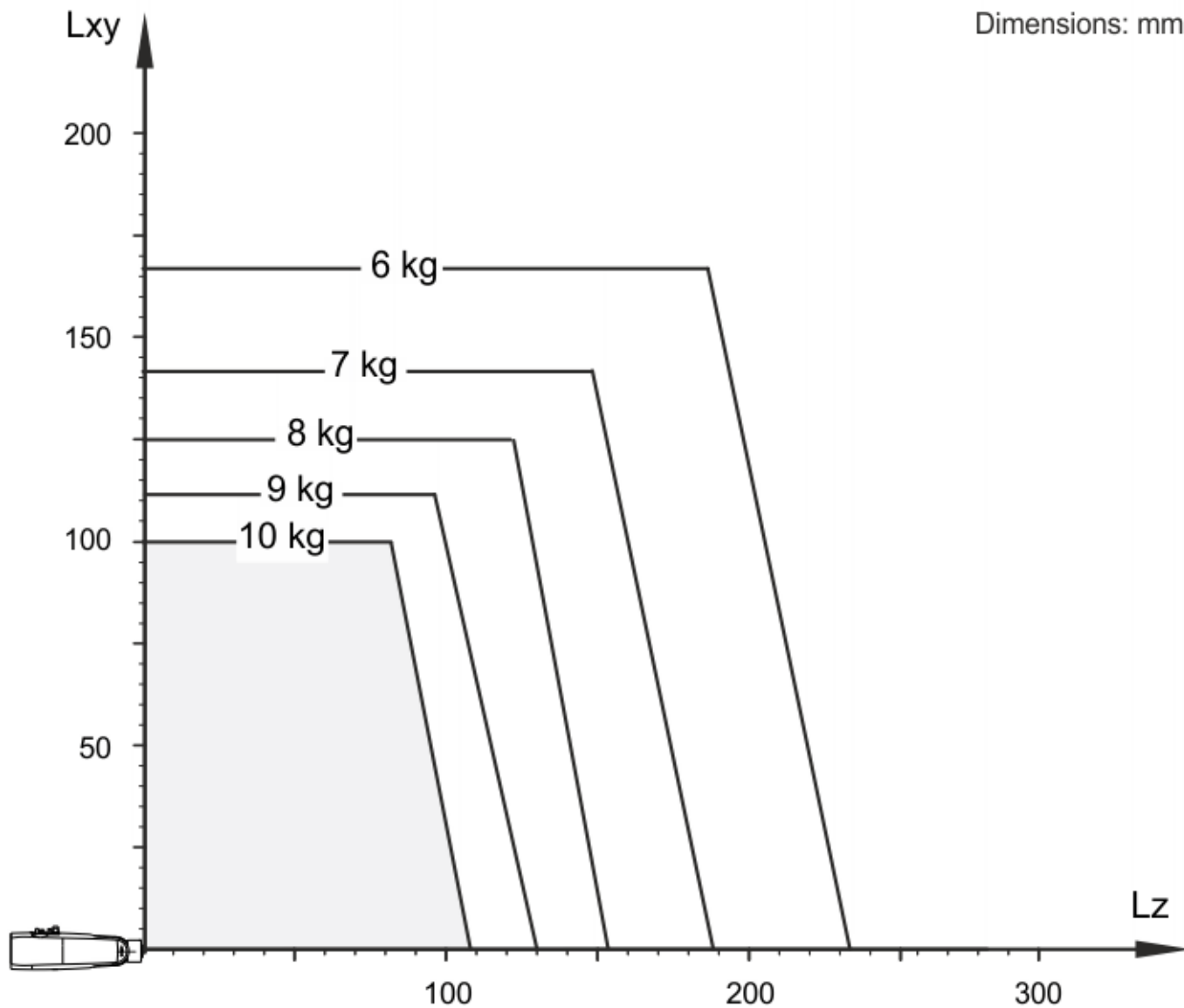
KR 10 R1100 HM-SC 工作区域



# 负载能力

额定负荷	5 kg
最大负载能力	10 kg
法兰 <b>I<sub>x</sub></b> 额定质量转动惯量	0.045 kgm <sup>2</sup>
法兰 <b>I<sub>y</sub></b> 额定质量转动惯量	-
法兰 <b>I<sub>z</sub></b> 额定质量转动惯量	-
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	-
大臂的额定附加负载	0 kg
大臂的最大附加负载	-
小臂的额定附加负载	0 kg
小臂的最大附加负载	-
负载重心额定距离	
<b>L<sub>xy</sub></b>	100 mm
<b>L<sub>z</sub></b>	80 mm

Dimensions: mm

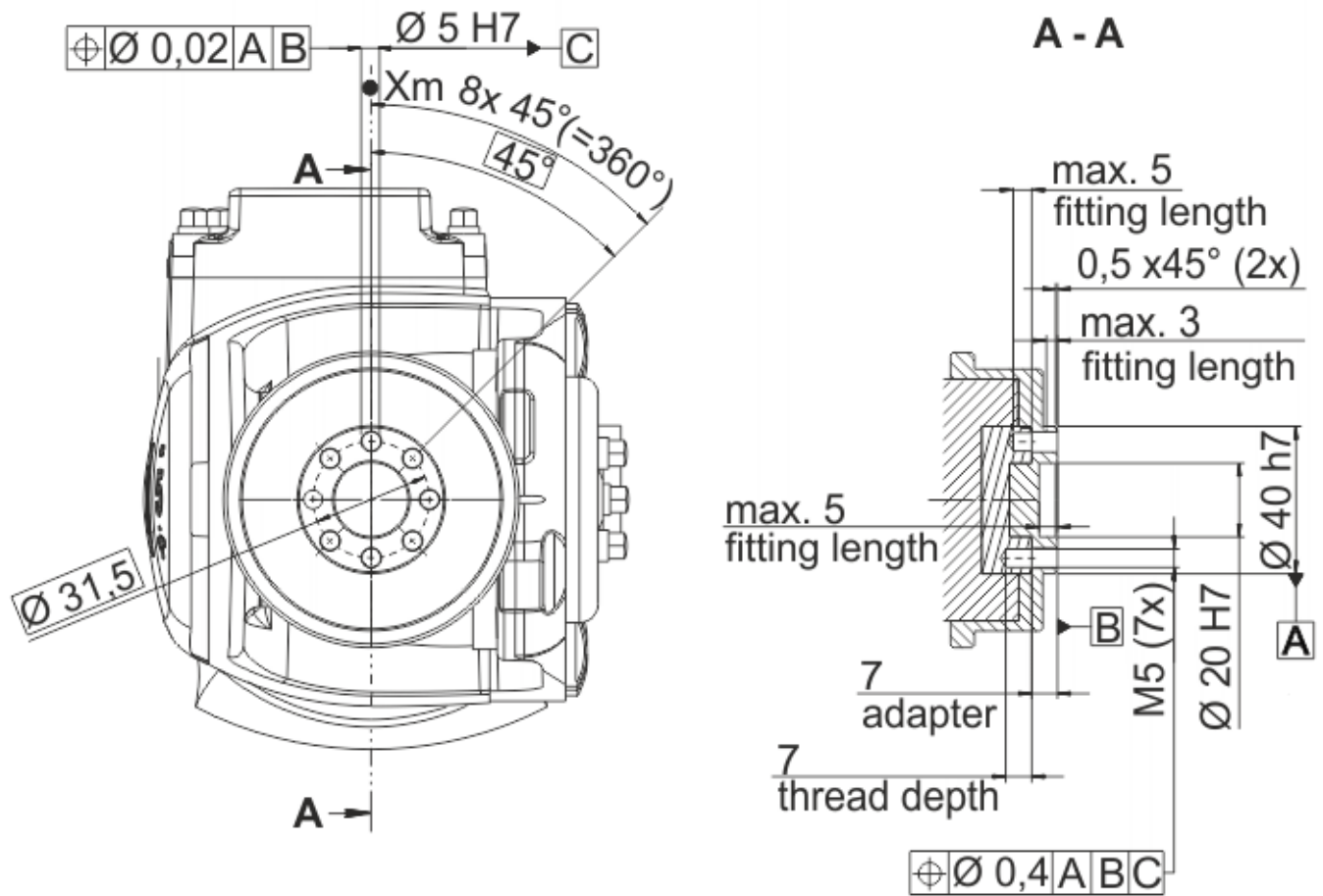


负载能力图表，负载能力 10 kg

# 连接法兰

机器人腕部类型	ZH 10 R1100 HM
连接法兰	见图纸

Dimensions: mm



连接法兰

# 地基负载

地面安装位置时的地基负载	
<b>F(v normal)</b>	944 N
<b>F(v max)</b>	1285 N
<b>F(h normal)</b>	617 N
<b>F(h max)</b>	1032 N
<b>M(k normal)</b>	602 Nm
<b>M(k max)</b>	595 Nm
<b>M(r normal)</b>	342 Nm
<b>M(r max)</b>	741 Nm
天花板安装位置时的地基负载	
<b>F(v normal)</b>	1015 N
<b>F(v max)</b>	1258 N
<b>F(h normal)</b>	622 N
<b>F(h max)</b>	1013 N
<b>M(k normal)</b>	582 Nm
<b>M(k max)</b>	953 Nm
<b>M(r normal)</b>	358 Nm
<b>M(r max)</b>	776 Nm
墙壁安装位置时的地基负载	
<b>F(v normal)</b>	415 N
<b>F(v max)</b>	775 N
<b>F(h normal)</b>	1125 N
<b>F(h max)</b>	1488 N
<b>M(k normal)</b>	742 Nm
<b>M(k max)</b>	1142 Nm

<b>M(r normal)</b>	307 Nm
<b>M(r max)</b>	654 Nm

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

# Flange loads

## Flange loads

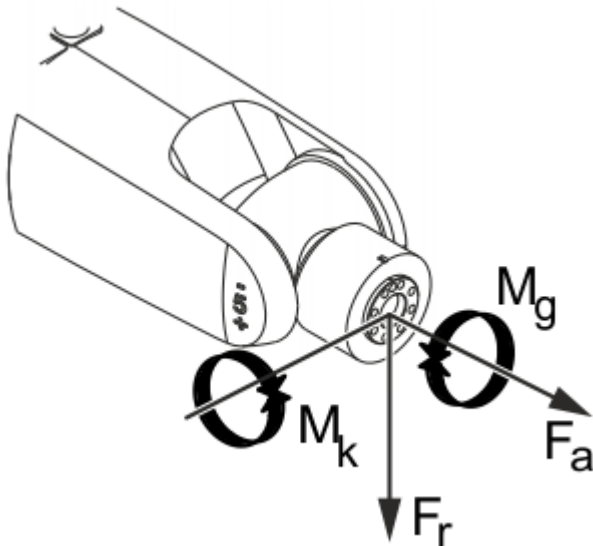
Due to the motion of the payload (e.g. tool) mounted on the robot, forces and torques act on the mounting flange. These forces and torques depend on the motion profile as well as the mass, load center of gravity and mass moment of inertia of the payload.

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	
<b>F(a)</b>	187 N
<b>F(r)</b>	318 N

<b>M(k)</b>	29 Nm
<b>M(g)</b>	25 Nm
<b>Flange loads in the case of EMERGENCY STOP</b>	
<b>F(a)</b>	412 N
<b>F(r)</b>	524 N
<b>M(k)</b>	65 Nm
<b>M(g)</b>	51 Nm

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

# 关税信息

统计货号	84795000
原产地	DE
制造商	-
重量	64 kg

- > **KR 10 R1100 HM-SC** 需要 (11)
- > **KR 10 R1100 HM-SC** 带有如下的工具 (13)
- > **KR 10 R1100 HM-SC** 带有如下的备件 (18)
- > **KR 10 R1100 HM-SC** 有以下选项 (16)