



Ultra TT
Robot system specification
May-09

Work Area X x Y x Z	Torque-325Mate 325 x 325 x 100 mm	Torque-525Mate 525 x 525 x 100 mm
Resolution	10 μ	10 μ
Repeatability	25 μ	25 μ
Max Speed	500 mm / secc	500 mm / se
Acceleration	0.25 g	0.25 g
Mechanical Configuration	H-Bridge De-coupled Axes	H-Bridge De-coupled Axes
Control Method	Closed Loop DC Servo	Closed Loop DC Servo
Drive System	Cable Drive	Cable Drive
Footprint Width x Depth x Height	560 x 670 x 750 mm	760 x 850 x 750 mm
Weight	45 kg	70 kg
Tool Payload	5kg	5 kg
Work Piece Payload	10 kg	10 kg
Programming Interface	Front Panel Buttons,Palm™ Handheld	Front Panel Buttons,Palm™ Handheld
Program Capacity	100	100
Point Capacity	10,000	10,000
Theta Axis	Upgradeable	Upgradeable
General Purpose I / O	16 inputs / 16 outputs	16 inputs / 16 outputs
Discrete I / O	1 analog input / output 4 inputs / 4 outputs 2 solenoid drivers	1 analog input / output 4 inputs / 4 outputs 2 solenoid drivers
External Communications	1 RS232 / 1 Palm	1 RS232 / 1 Palm
Height Sensor	Optional	Optional
Software Compatibility	Palm™ OS 4.0 or higher	Palm™ OS 4.0 or higher
Current Consumption	320 Watts	320 Watts
Input Voltage	100 VAC~240 VAC (\pm 10%)	100 VAC~240 VAC (\pm 10%)
Number of Screwdrivers	1 or 2	1 or 2