
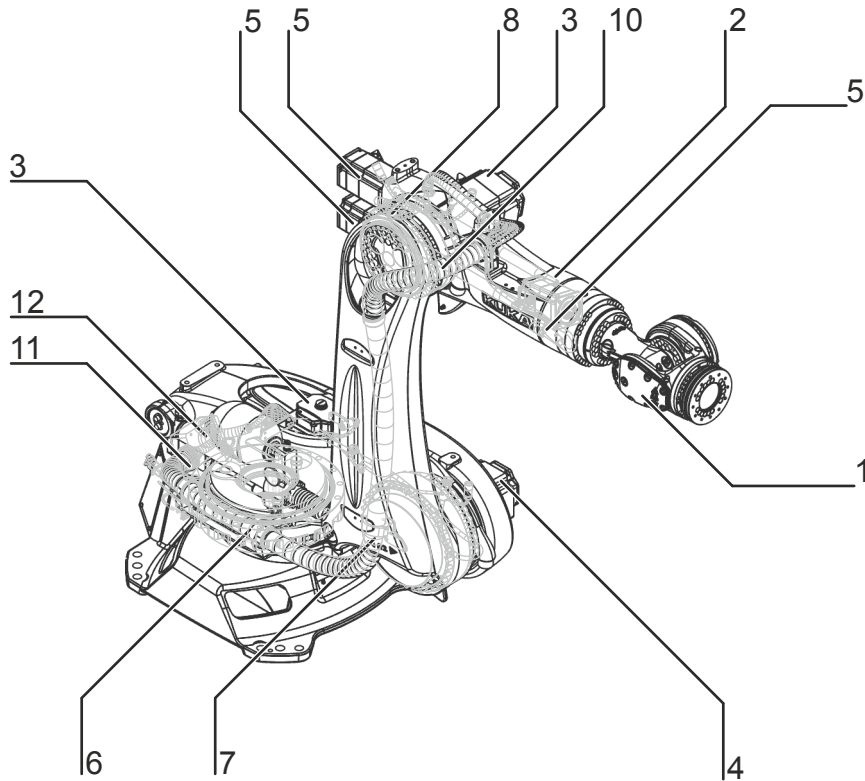


KUKA | Xpert

Identification number: AR1144

货号	0000-188-655
材料状态	40 - 停产
制造商	KUKA Roboter
产品图片	

Spare parts



Spare parts graphic KR 270 R2900 ultra K , schematic representation

Pos.	Article number	Designation	Component	Work instruction
1	0000-192-227	SPP ZH270/300	In-line wrist	Exchanging the in-line wrist
2	0000-192-309	SPP Connection shaft 1000 A4,A5	Connecting shaft	Exchanging connecting shafts A4 and A5
3	0000-192-295	SPP AC servomotor I2/1FK7101	Motor A1 Motor A3	Exchanging motor A1 Exchanging motor A3
4	0000-192-293	SPP AC servomotor K2/1FK7103	Motor A2	Exchanging motor A2
5	0000-192-297	SPP AC servomotor D01/1FK7063	Motor A4 Motor A5 Motor A6	Exchanging motor A4 Exchanging motor A5 Exchanging motor A6
6	0000-192-315	SPP gear RV-700CS i=256,85, w/o oil	Gear A1	Exchanging gear unit A1

Pos.	Article number	Designation	Component	Work instruction
7	0000-192-320	SPP gear RV-700N i=267,43, without oil	Gear A2	Exchanging gear unit A2
8	0000-192-325	SPP gear RV-500N I=252,33, without oil	Gear A3	Exchanging gear unit A3
9	0000-192-284	SPP counterbalancer shelf	Gear unit input shaft	Exchanging the counterbalancing system
10	0000-186-096	KRC4 Rob.cab.set compl. FSR KR180 R3100K	Cable set	Exchanging the cable set
11	0000-246-872	Resolver Digital Converter RDC	RDC	Exchanging the RDC
12	0000-172-903	Electronic Data Storage EDS	EDS	Exchanging the EDS

Export to Excel 

Maintenance information

Gear oil



The quantity of oil drained depends on the draining time and the oil temperature. The refilling quantity is the quantity of oil that was drained from the gear unit at the correct operating temperature and with the correct draining time. This oil quantity must be determined. Only this quantity of oil may be used when refilling.

If less than 70 % of the specified oil quantity flows out, flush the gear unit with the determined quantity of drained oil once, then pour in the amount of oil that was drained. If less than 50% of the specified oil quantity flows out (e.g. inclined installation), the flushing operation must be repeated twice. During the flushing procedure, move the axis at jog velocity throughout the entire axis range.

The oil quantities specified in the table correspond to the oil quantities in the gear unit at first filling.

Gear oil new filling quantity	
A1	6.50 l
A2	2.90 l
A3	1.80 l
A4	2.10 l
A5	1.10 l
A6	1.20 l
Gear oil refilling quantity	
A1	5.20 l
A2	2.50 l
A3	1.70 l
A4	2.00 l
A5	0.90 l
A6	0.90 l

Counterbalancing system

Gas pressure p0	162 bar
Oil pressure p1	182 bar

技术数据

基本数据

	KR 270 R2900 ultra K
轴数	6
可控制的轴数	6
工作空间体积	77.9 m ³
位姿重复精度 (ISO 9283)	± 0.06 mm
重量	约 1189 kg
额定负荷	270 kg
最大负载能力	-
最大运动范围	2901 mm
防护等级 (IEC 60529)	IP65
机器人腕部防护等级 (IEC 60529)	IP65
噪声等级	< 75 dB (A)
安装位置	地面
占地面积	830 mm x 830 mm
运动系统安装面布孔图	S934
允许倾角	≤ 0°
标准色	底座： 黑色 (RAL 9005); 活动部件： 库卡橙色 2567
控制系统	KR C4
变压器名称	KR C4: KR270R2900K ULTRA C4 FLR

环境条件

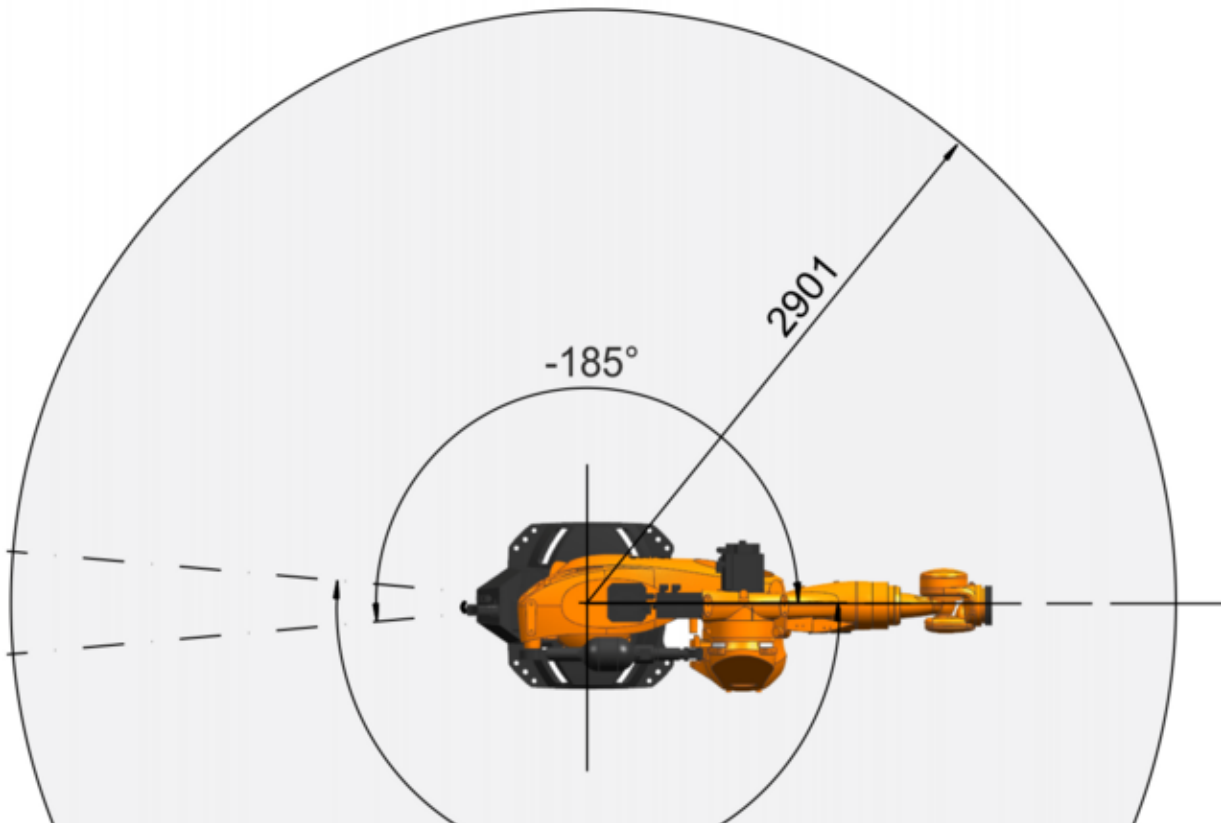
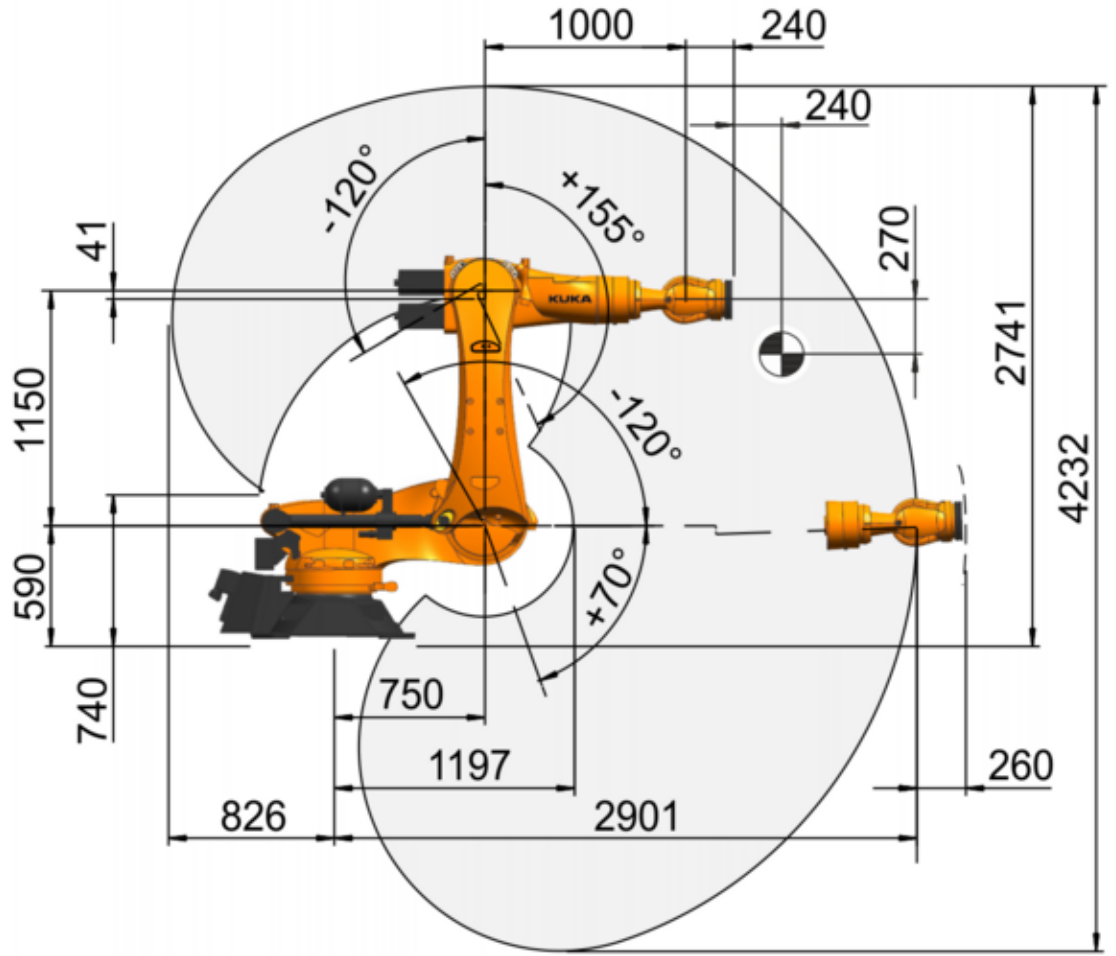
湿度等级 (EN 60204)	-
环境条件分类 (EN 60721-3-3)	3K3
环境温度	
运行时	10 °C 至 55 °C (283 K 至 328 K)
仓储和运输时	-40 °C 至 60 °C (233 K 至 333 K)

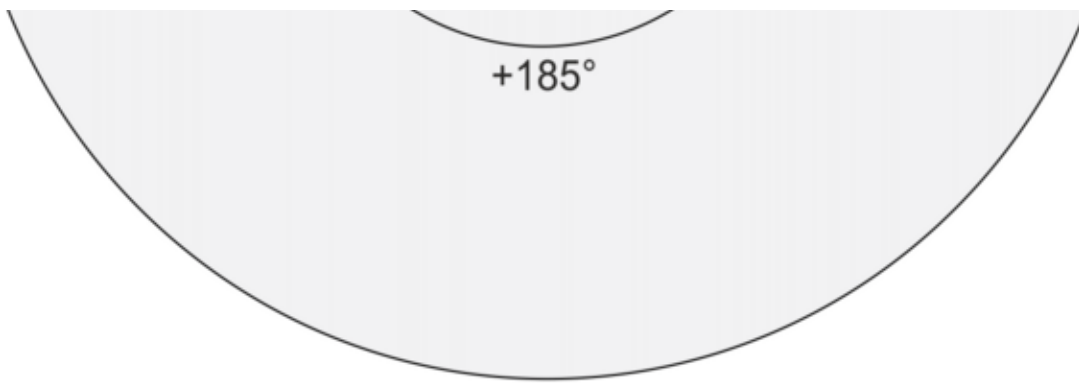
轴数据

运动范围	
A1	±185 °
A2	-120 ° / 70 °
A3	-120 ° / 155 °
A4	±350 °
A5	±122.5 °
A6	±350 °
额定负载时的速度	
A1	105 °/s
A2	101 °/s
A3	107 °/s
A4	122 °/s
A5	113 °/s
A6	175 °/s

工作区域

Dimensions: mm

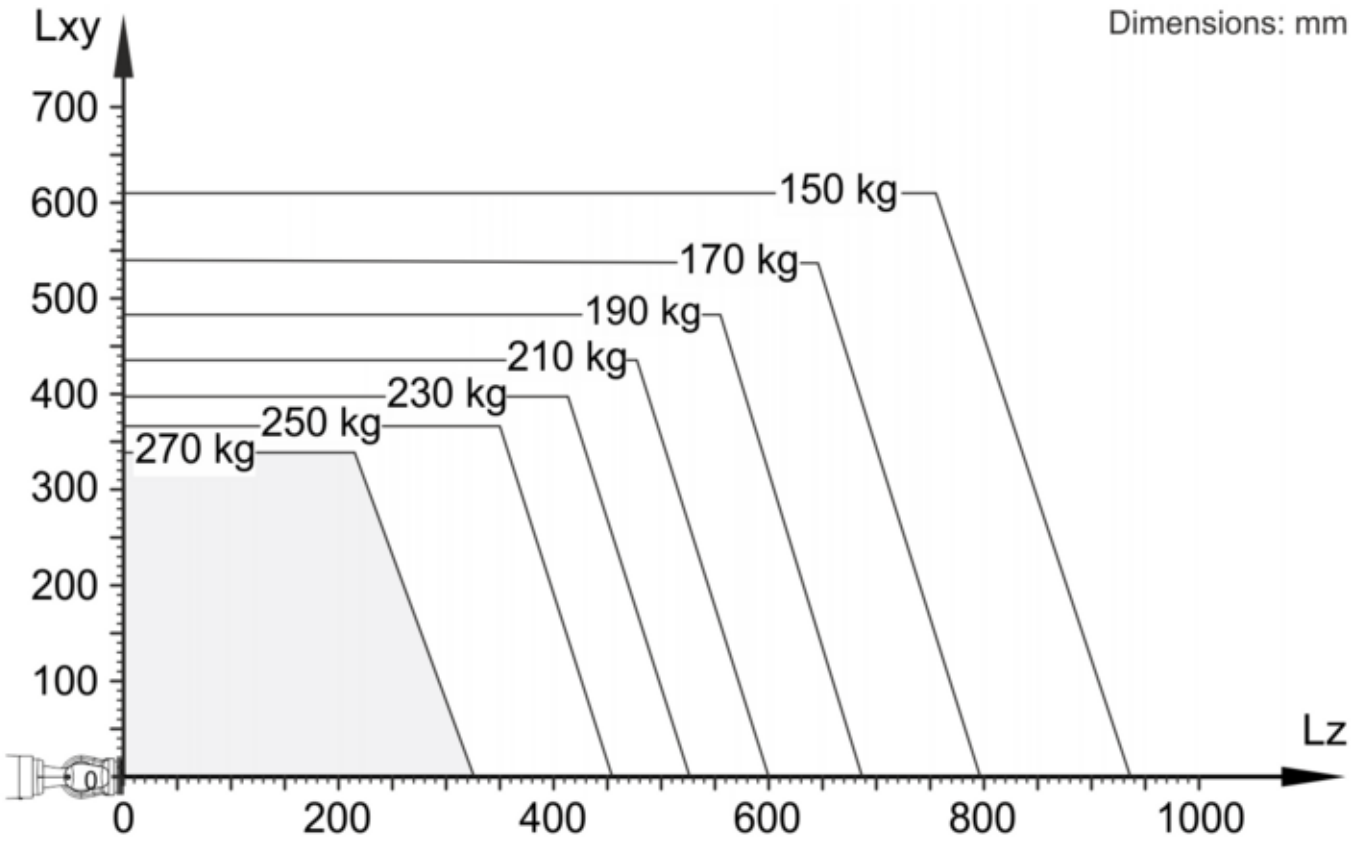




KR 270 R2900 ultra K 工作区域

负载能力

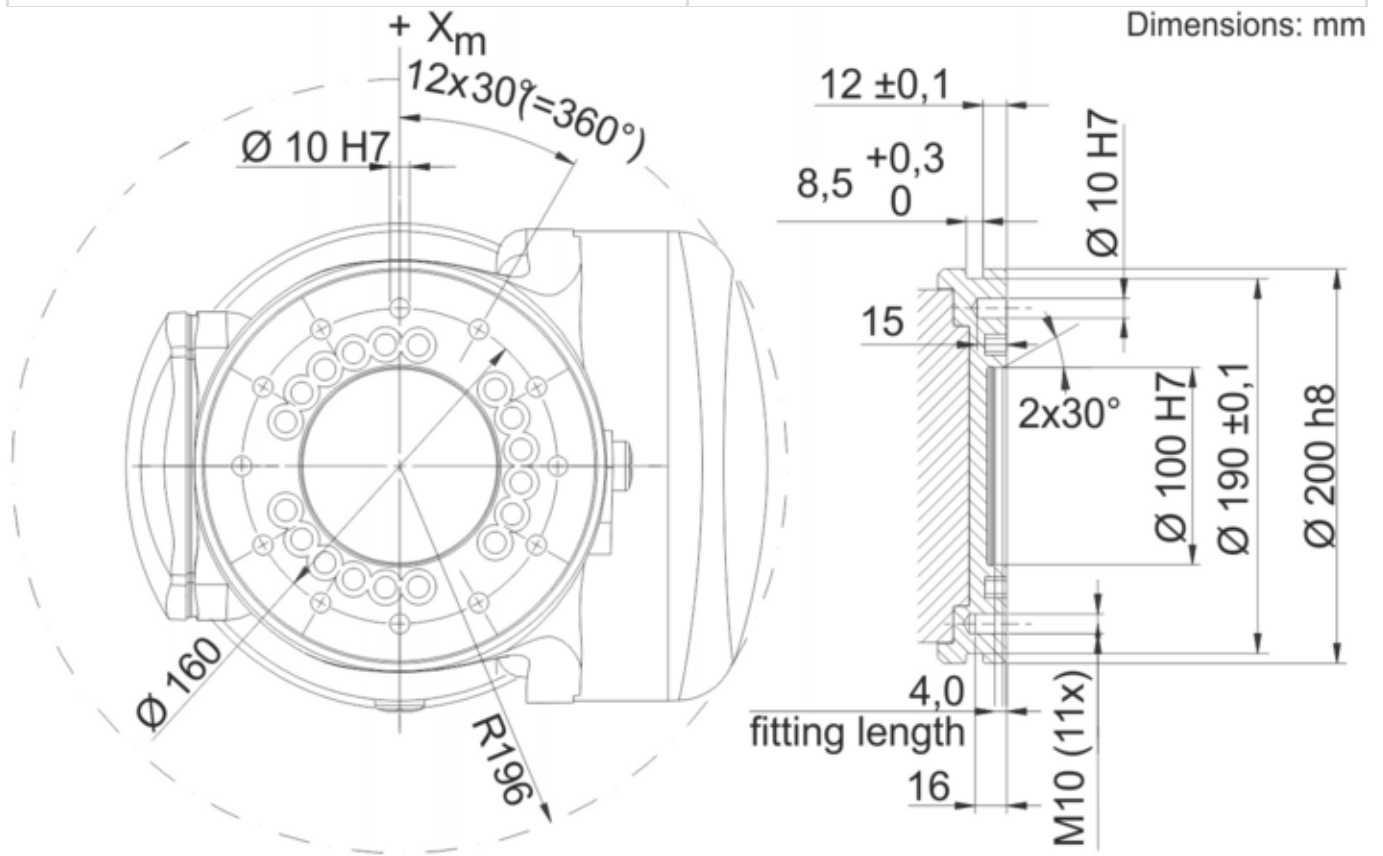
额定负荷	270 kg
最大负载能力	-
法兰 I_x 额定质量转动惯量	135 kgm ²
法兰 I_y 额定质量转动惯量	135 kgm ²
法兰 I_z 额定质量转动惯量	135 kgm ²
底座的额定附加负载	0 kg
底座的最大附加负载	-
转盘的额定附加负载	0 kg
旋转机构的最大附加负载	0 kg
大臂的额定附加负载	0 kg
大臂的最大附加负载	0 kg
小臂的额定附加负载	50 kg
小臂的最大附加负载	100 kg
负载重心额定距离	
L_{xy}	270 mm
L_z	240 mm



KR QUANTEC ultra 负载能力图表，负载能力 270 kg

连接法兰

机器人腕部类型	ZH 270/300
连接法兰	见图纸



连接法兰 D=160

地基负载

纵向动力 $F(v)$	
$F(v)$ 正常)	19100 N
$F(v_{max})$	24000 N
横向动力 $F(h)$	
$F(h)$ 正常)	9200 N
$F(h_{max})$	16000 N
倾覆力矩 $M(k)$	
$M(k)$ 正常)	24000 Nm
$M(k_{max})$	49000 Nm
轴 2 转矩 $M(r)$	
$M(r)$ 正常)	10200 Nm
$M(r_{max})$	35000 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	4700 Nm
A2	6300 Nm
A3	5400 Nm
A4	1650 Nm
A5	1650 Nm
A6	1000 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)	4500 N
F(r)	5100 N
M(k)	1800 Nm

M(g)	1250 Nm
Flange loads in the case of EMERGENCY STOP	
F(a)	5700 N
F(r)	7600 N
M(k)	4200 Nm
M(g)	3500 Nm

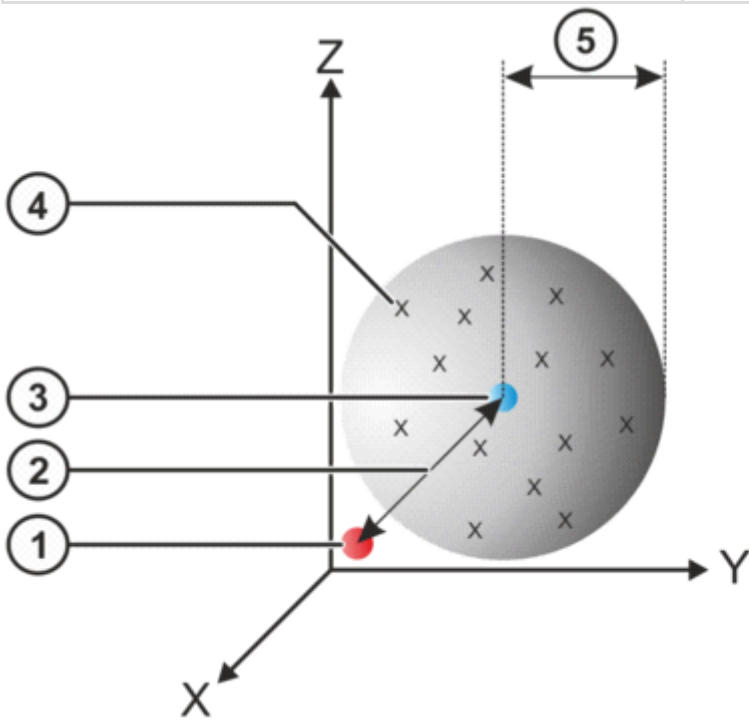
Axial force $F(a)$, radial force $F(r)$, tilting torque $M(k)$, torque about mounting flange $M(g)$

精度数据

i 仅适用于带定位精确的机器人选项（用于地面或天花板安装）的机器人在地面位置测量的机器人只允许在地面位置运行。这同样适用于天花板位置的机器人。

位置精度

位置绝对精度 (ISO 9283)	$\pm 0.7 \text{ mm}$
位姿重复精度 (ISO 9283)	$\pm 0.06 \text{ mm}$



位置精度

1	编程设定的位置	4	测得的位置
2	位置绝对精度	5	位置重复精度
3	测得位置的平均值		

- 位置精度表示编程的机器人位置和实际占用的机器人位置之间的偏差，并用坐标测量机（CMM）在 9 个位置测量。
- 重复精度由重复 30 次测量时实际占用的机器人位置的偏差得出。
- 对于定位精确的机器人，这些值针对的是机器人基座。

轨迹精度

线性运动的轨迹精度:

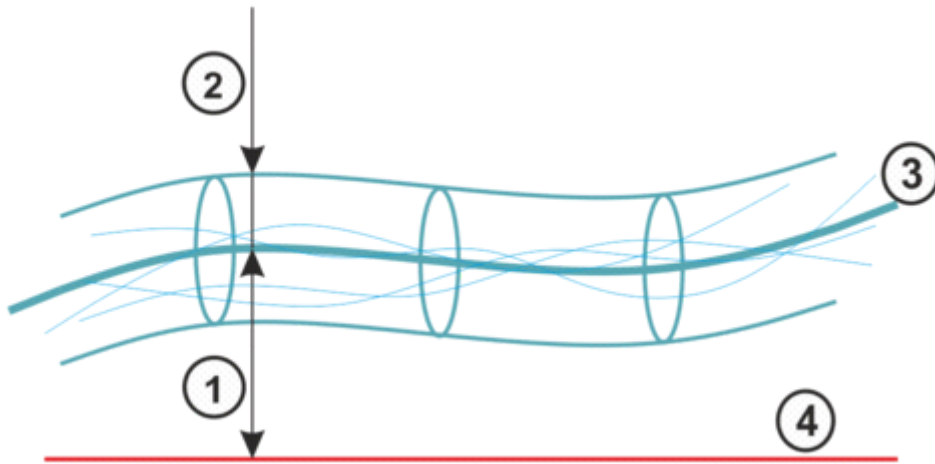
LIN 轨迹绝对精度 (ISO 9283)	$\pm 1.4 \text{ mm}$
SLIN 轨迹绝对精度 (ISO 9283)	$\pm 1.2 \text{ mm}$
轨迹重复精度 线性 (ISO 9283)	$\pm 0.2 \text{ mm}$

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)	$\pm 1 \text{ mm}$
SCIRC 轨迹绝对精度 (ISO 9283)	$\pm 0.8 \text{ mm}$
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。



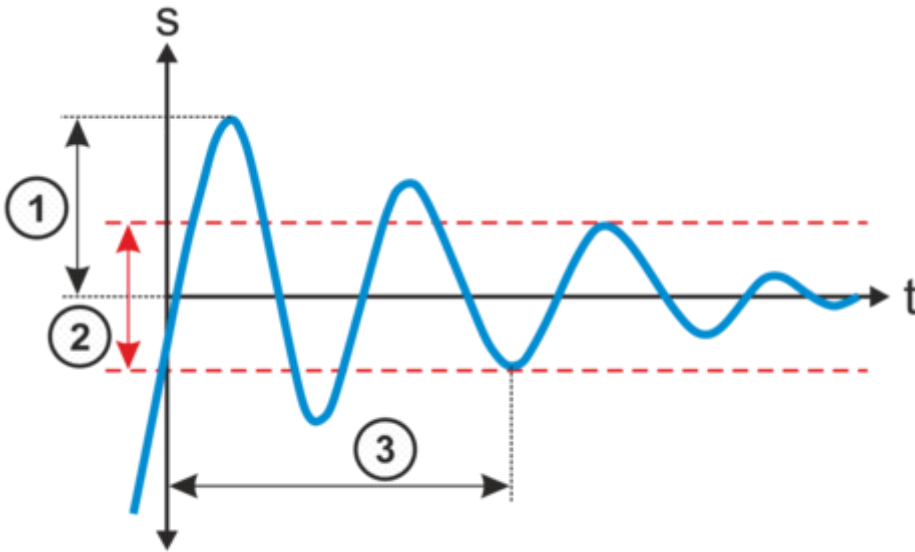
轨迹精度

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	0.5 mm
定位时间	0.9 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。

Dangerous goods information

The following parts of the product must be considered dangerous goods with regard to their transportation in public spaces:

Pos.	Article number	Designation	Gas pressure p0	Nitrogen mass
1	0000-183-637	Counter Balance System console filled	162 bar	0.652 kg

Export to Excel 

For sea or air freight, the following UN number shall apply:

UN 3164 Articles, pressurized, hydraulic (with non-flammable, non-toxic gases)

UN number	UN 3164
Proper shipping name	Articles, pressurized, hydraulic (with non-flammable, non-toxic gases)
Class	2.2
Explanation of class	Non-flammable, non-toxic gases
Example	Filled hydropneumatic CBSs
Hazard	<ul style="list-style-type: none"> • Bursting of the pressure vessels (100 - 160 bar) • Splintering not possible • Freezing due to sudden escape of gas
Measures	<ul style="list-style-type: none"> • Do not loiter in low-lying areas • If possible, drain oil and depressurize CBS

关税信息

统计货号	84795000
原产地	DE
制造商	KUKA ROBOTER
重量	1189 kg

- > **KR 270 R2900 ultra K** 带有如下的工具 (27)
- > **KR 270 R2900 ultra K** 有以下选项 (39)
- > **KR 270 R2900 ultra K** 带有如下的标准组件 (3)
- > **KR 270 R2900 ultra K** 包含以下危险品 (1)
- > **KR 270 R2900 ultra K** 需要 (16)
- > **KR 270 R2900 ultra K** 带有如下的备件 (12)