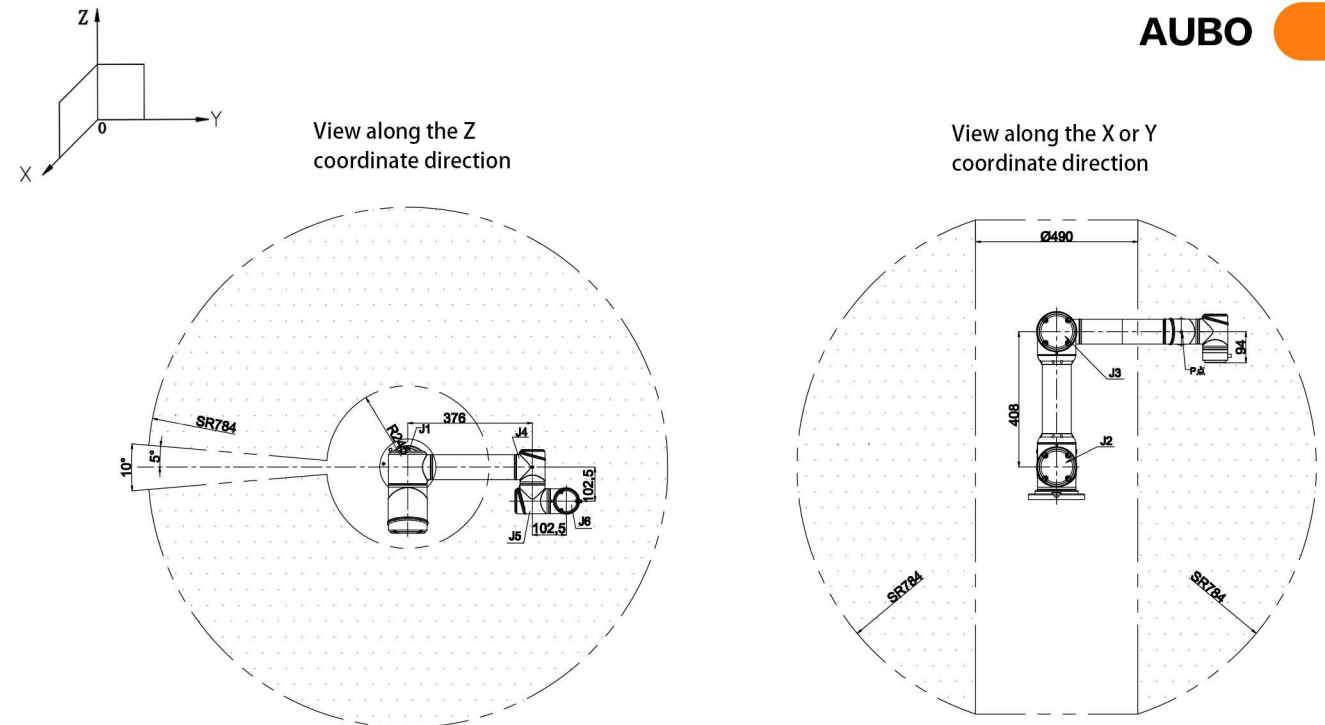


# AUBO i5

## TECHNICAL SPECIFICATIONS

<b>Robot</b>	
Degrees of freedom	6
Reach:	886.5 mm
Payload:	5 Kg
Weight:	24 Kg
Lifetime:	30000h
Collaboration :	Collaborative operation according to ISO 10218-1:2001
Repeatability:	± 0.05 mm
Linear velocity	≤2.8 m/s
Power consumption:	200W(Under normal working conditions)
Materials:	Aluminum, steel, Plastic
Ambient humidity:	25%-85%
Ambient temperature:	0-45° C
IP Classification:	IP54
programming:	Teach pendant with user interface
Communication:	CAN bus
Motor Type:	DC 48V
Installation orientation:	Any ceiling, Floor, Wall



**NOTE:**

1. The two-dot chain line indicates: the area boundary
2. The space area enclosed by the double-dot-dash line is the area where the robot arm is mounted, and the hoisting and vertical installation suggest the area of the tool end trajectory when the robot arm works best
3. The limit trajectory of the tool end movement of the robotic arm may exceed the area enclosed by the two-dot chain line
4. The double-dot-dash-contained space region is the intersection of the space region contained on the inner surface of a defective sphere and the space region on the outer surface of a cylinder.

Axis Movement	Working Range	Maximum Speed
J1 Axis Base:	± 175°	150° /s
J2 Axis Shoulder:	± 175°	150° /s
J3 Axis Elbow:	± 175°	150° /s
J4 Axis Wrist:	± 175°	180° /s
J5 Axis Wrist:	± 175°	180° /s
J6 Axis Wrist:	± 175° /360° (Optional)	180° /s

I/O Port On Wrist						
Voltage	Current	Digital In	Digital out	Analog In	Analog Out	
0V/12V/24V	0.8A	4	4	2	0	

<b>Control Box</b>	
Dimensions:	727mm*623mm*235mm
Weight:	29Kg
Cabling:	5m
Color:	Black
Communication:	Ethernet、Modbus-RTU/TCP
Interface:	SDK (Support C\C++\Lua\Python)、Support ROS、API
Power Supply:	100-240VAC, 50-60 Hz

I/O PORTS	GENERAL I/O	SAFETY I/O
Digital In	16	16
Digital Out	16	16
Analog In	4	-
Analog Out	4	-
Output Voltage	24V	
Output Current	3A	

<b>Teach Pendant</b>	
Dimensions:	355x235x54 mm
Weight:	1.57Kg
Display Screen:	30cm Touch LCD Screen
Cabling:	4 m
Color :	Orange+Black

