ControlTech

Authorised Distributor

A ROCKWELL AUTOMATION PARTNER

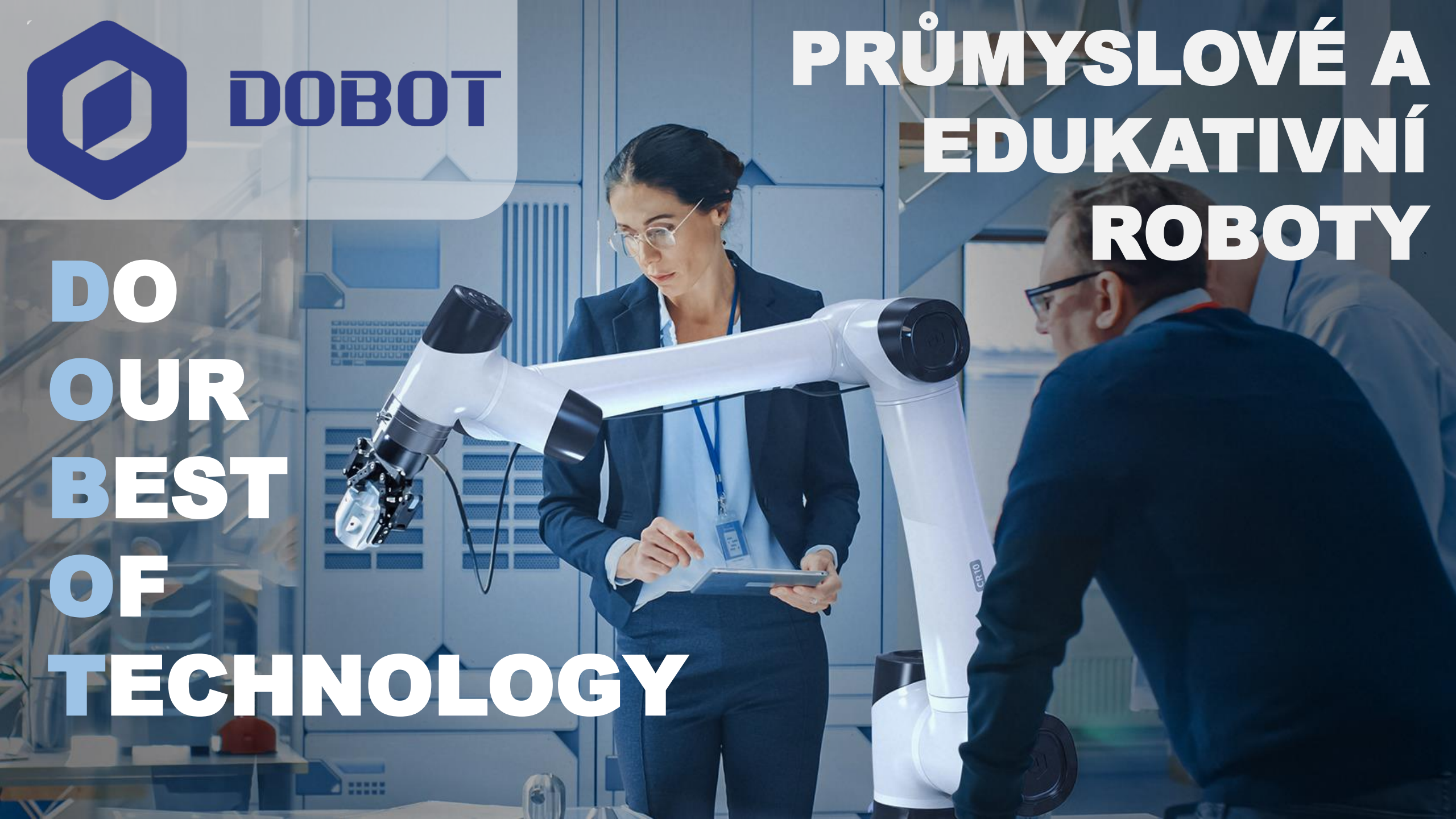
PRŮMYSLOVÉ A EDUKATIVNÍ ROBOTY

VLADYKA PAVEL

DOBOT

PRŮMYSLOVÉ A EDUKATIVNÍ ROBOTY

DO OUR BEST OF TECHNOLOGY



DOBOT

PRŮMYSLOVÉ A EDUKATIVNÍ ROBOTY

DO OUR BEST OF TECHNOLOGY

DOBOT

DOBOT CR5

ROBOTA PRACOVAT NAUČTE
jednoduše i bez programování

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DOBOT CR5

DOBOT

CR5

5 kg

1096 mm

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DOBOT

CR3 CR5

3 kg
795 mm

5 kg
1096 mm

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DOBOT

CR3 CR5 CR10

3 kg
795 mm

5 kg
1096 mm

10 kg
1525 mm

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CR16

16 kg

1223 mm

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DOBOT

DOBOT

DOBOT

NEUTRÁCEJTE ZA TEACH PENDANT

ANDROID iOS

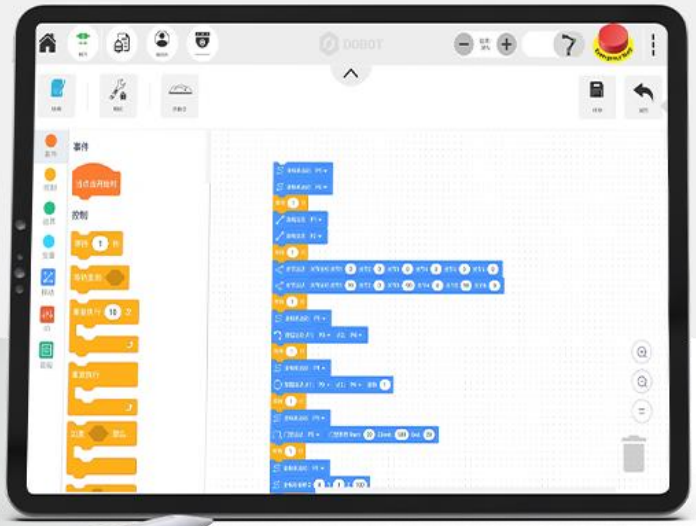
POUŽÍVEJTE TABLET

doporučíme Vám tablet, kterým můžete robota ovládat

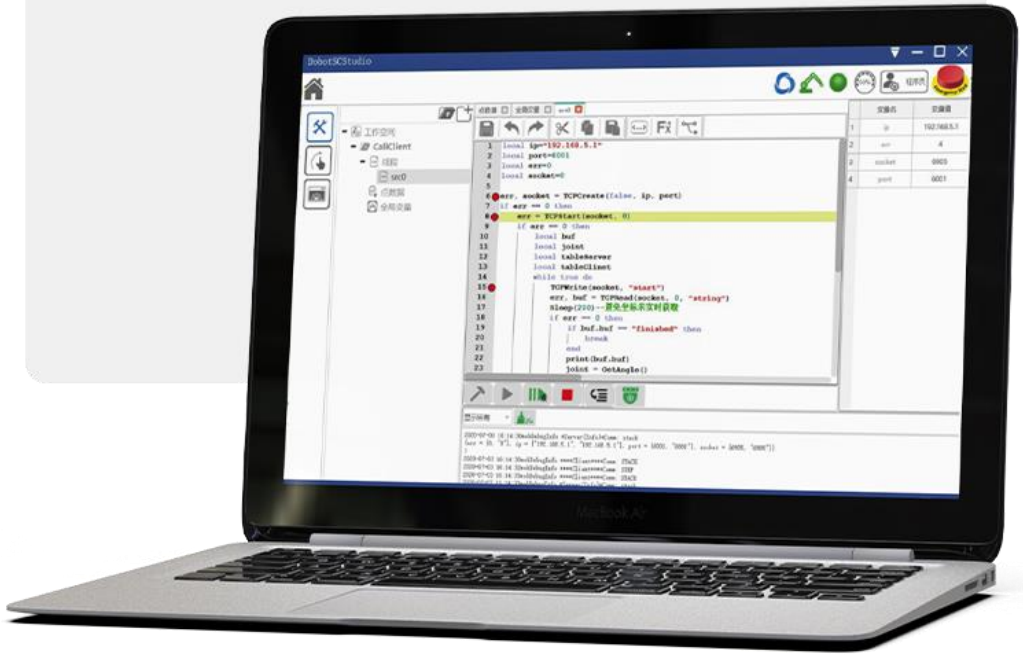
DOBOT

DOBOT

CR Studio



DOBOT SCStudio



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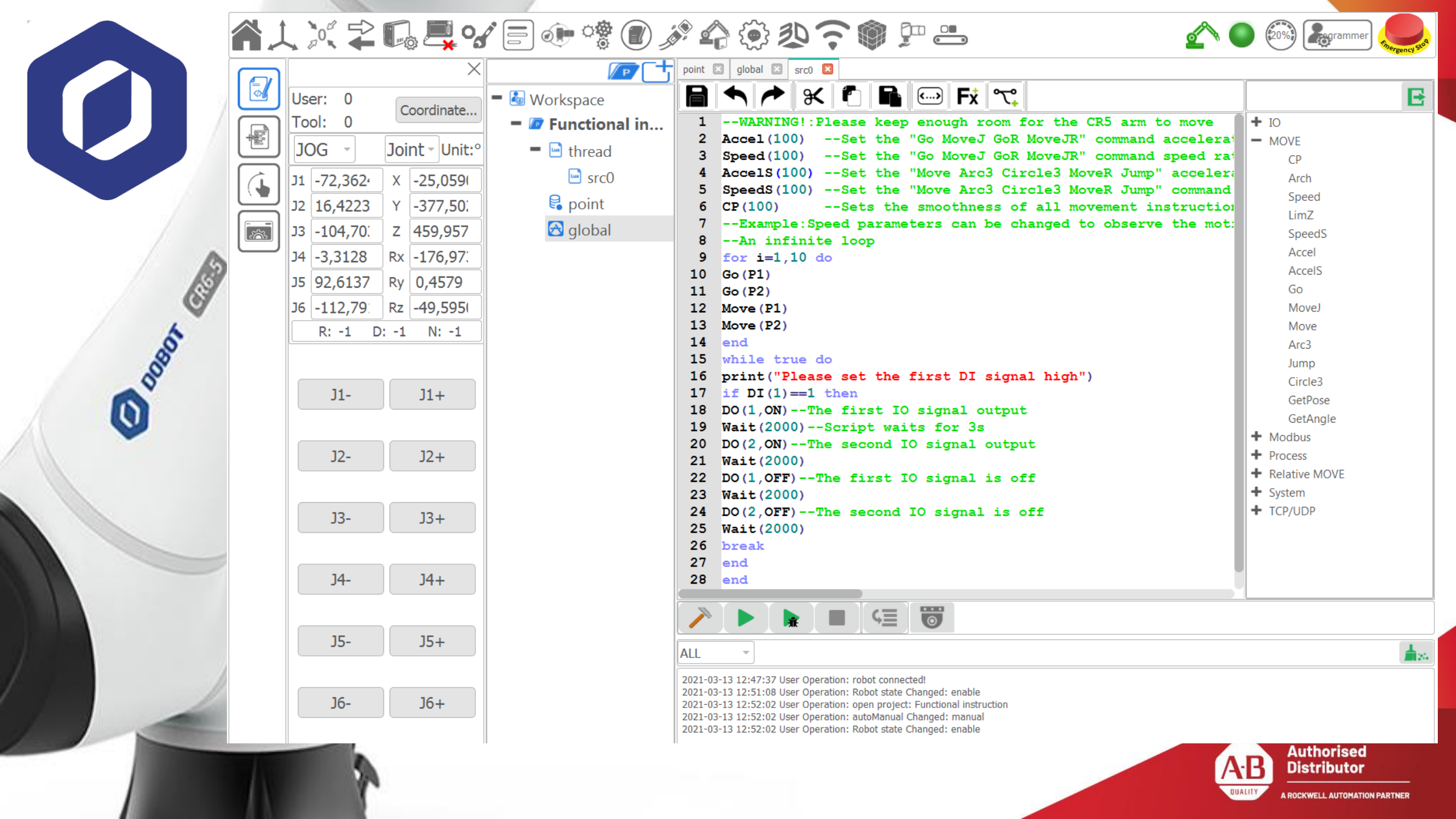
DOBOT
CR6-5
User: 0
Tool: 0
Coordinate...
JOG
Joint
Unit:°
J1 -72,362
J2 16,4223
J3 -104,70
J4 -3,3128
J5 92,6137
J6 -112,79
X -25,059
Y -377,50
Z 459,957
Rx -176,97
Ry 0,4579
Rz -49,595
R: -1 D: -1 N: -1
J1- J1+
J2- J2+
J3- J3+
J4- J4+
J5- J5+
J6- J6+
Workspace
Functional in...
thread
src0
point
global
point
global
src0
--WARNING!:Please keep enough room for the CR5 arm to move
Accel(100) --Set the "Go MoveJ GoR MoveJR" command accelera
Speed(100) --Set the "Go MoveJ GoR MoveJR" command speed ra
AccelS(100) --Set the "Move Arc3 Circle3 MoveR Jump" acceler
SpeedS(100) --Set the "Move Arc3 Circle3 MoveR Jump" command
CP(100) --Sets the smoothness of all movement instructio
--Example:Speed parameters can be changed to observe the mot
--An infinite loop
for i=1,10 do
Go(P1)
Go(P2)
Move(P1)
Move(P2)
end
while true do
print("Please set the first DI signal high")
if DI(1)==1 then
DO(1,ON)--The first IO signal output
Wait(2000)--Script waits for 3s
DO(2,ON)--The second IO signal output
Wait(2000)
DO(1,OFF)--The first IO signal is off
Wait(2000)
DO(2,OFF)--The second IO signal is off
Wait(2000)
break
end
end
IO
MOVE
CP
Arch
Speed
LimZ
SpeedS
Accel
AccelS
Go
MoveJ
Move
Arc3
Jump
Circle3
GetPose
GetAngle
Modbus
Process
Relative MOVE
System
TCP/UDP
ALL
2021-03-13 12:47:37 User Operation: robot connected!
2021-03-13 12:51:08 User Operation: Robot state Changed: enable
2021-03-13 12:52:02 User Operation: open project: Functional instruction
2021-03-13 12:52:02 User Operation: autoManual Changed: manual
2021-03-13 12:52:02 User Operation: Robot state Changed: enable
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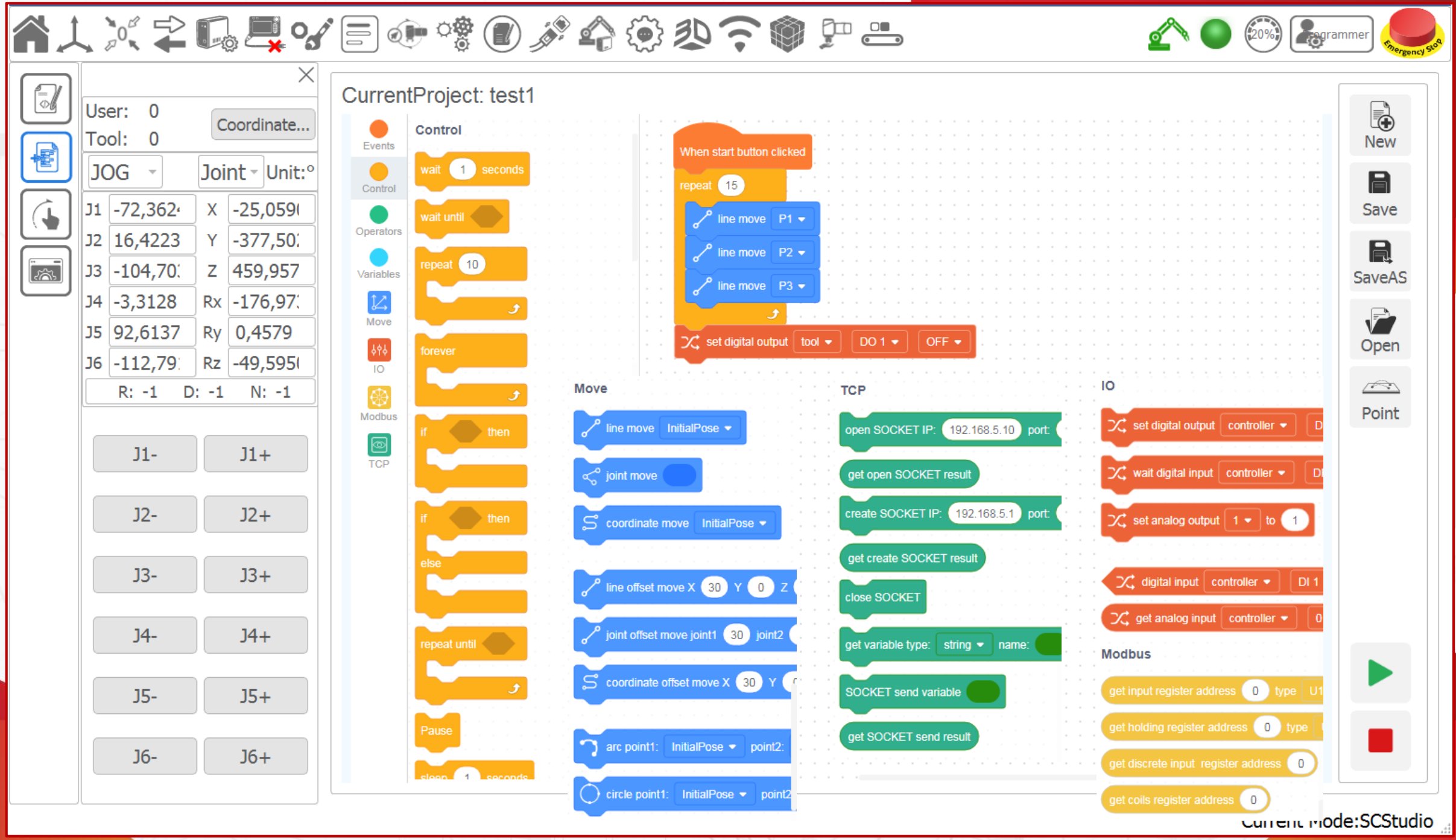

User: 0
Tool: 0
Coordinate...
JOG
Joint
Unit:°
J1 -72,362
J2 16,4223
J3 -104,70
J4 -3,3128
J5 92,6137
J6 -112,79
X -25,059
Y -377,50
Z 459,957
Rx -176,97
Ry 0,4579
Rz -49,595
R: -1 D: -1 N: -1
J1- J1+ J2- J2+ J3- J3+ J4- J4+ J5- J5+ J6- J6+
CurrentProject: test1
Events
Control
Operators
Variables
Move
IO
Modbus
TCP
wait 1 seconds
wait until
repeat 10
forever
if then
if then else
repeat until
Pause
When start button clicked
repeat 15
line move P1
line move P2
line move P3
set digital output tool DO 1 OFF
Move
line move InitialPose
joint move
coordinate move InitialPose
line offset move X 30 Y 0 Z
joint offset move joint1 30 joint2
coordinate offset move X 30 Y
arc point1: InitialPose point2:
circle point1: InitialPose point2
TCP
open SOCKET IP: 192.168.5.10 port:
get open SOCKET result
create SOCKET IP: 192.168.5.1 port:
get create SOCKET result
close SOCKET
get variable type: string name:
SOCKET send variable
get SOCKET send result
IO
set digital output controller
wait digital input controller
set analog output 1 to 1
digital input controller DI 1
get analog input controller
Modbus
get input register address 0 type
get holding register address 0 type
get discrete input register address 0
get coils register address 0
New
Save
SaveAS
Open
Point
Emergency Stop
Current Mode:SCStudio

DOBOT

FESTO

DOBOT

SMC®

Magnetická úchopná hlavice | SMC
smc.eu

MHS3, Úchopná hlavice, 3 čeli...
smc.eu

MDHR2, Úchopná hlavice, 2 čeli...
smc.eu

MHC2, Úchopná hlavice, 2 čeli...
smc.eu

MHSH3, Úchopná hlavice, 3 čeli...
smc.eu

MHS4, Úchopná hlavice, 4 čelist...
smc.eu

JMHZ2, Úchopná hlavice, parale...
smc.eu

MHZA2, Úchopná hlavice, 2 čeli...
smc.eu

MHS3-X6708, Úchopná hlavice,...
smc.eu

JMHZ2-X7400B, Úchopná hlavi...
smc.eu

MHS2, Úchopná hlavice, 2 čelis...
smc.eu

MDHR3, Úchopná hlavice, 3 čelis...
smc.eu

MHT2, Úchopná hlavice, 2 čelist...
smc.eu

MHZAJ2, Úchopná hlavice, 2 čeli...
smc.eu

MHR3, Úchopná hlavice, 3 čelisti,...
smc.eu

MHY2, Úchopná hlavice, 2 čelisti,...
smc.eu

MHZ2, Úchopná hlavice, 2 čelisti,...
smc.eu

MHL2, Úchopná hlavice, 2 čelisti,...
smc.eu

LEHS, Elektrická paralelní úchop...
smc.eu

LEHF
smc.eu

MHW2, Úchopná hlavice, 2 čelist...
smc.eu

Robotické aplikace | SMC
smc.eu

MHF2-F, Úchopná hlavice, 2 čelis...
smc.eu

Úchopná hlavice, 2 čelisti, průměr 25mm, z...
eshop.technoline.cz

MHZL2-X6110, Úchopná hlavice, ...
smc.eu

Nové prvky 2020 | SMC
smc.eu

DOBOT

VAKUUM technik

DOBOT

Robotiq
Gripper

Schunk
Gripper

Onrobot
Gripper

SIASUN
Gripper

DH-Robotics
Gripper

Rochu
Gripper

HITOBOT
Gripper

SRT
Gripper

Robotiq
Sensor

Onrobot
Sensor

LINKTOUCH
Sensor

ATI
Sensor

COGENEX
Vision

MICROSCAN
Vision

Hikvision
Vision

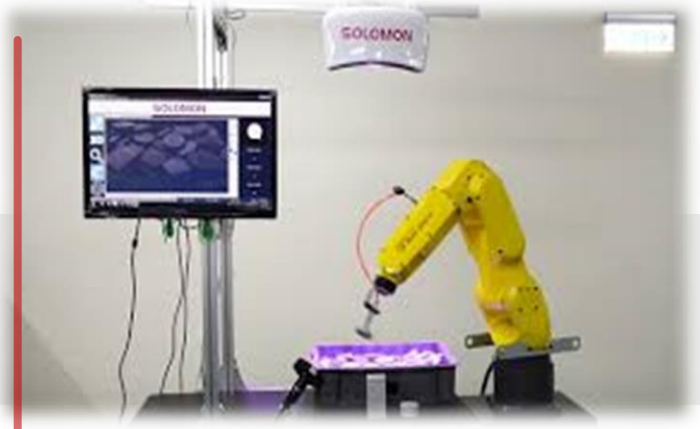
Hikvision
Vision

SOLOMON

- Taipei, Taiwan
- Založeno 1973

SOLOMON

2D a 3D stojové vidění pro roboty



Customers' Reference

SOLOMON

SOLOMON

Vision

3D Camera Technologies

Structured Light

Active Stereo Vision

Time-of-Flight (ToF)

KINECT

SOLOMON AI Brain

Application

- Accupick
  (AI 3D random bin picking)
- Solmotion
  (AI 3D robot guiding)
- Solvision
  (AI 2D Inspection)

Robot

UNIVERSAL ROBOTS · Kawasaki · STÄUBLI · YASKAWA
mecademic · DENSO · ABB · KUKA · FANUC
MITSUBISHI · NACHI · DOOSAN · OMRON
TOSHIBA MACHINE · OTC · YAMAHA
AUBO · TM · EPSON · rethink robotics · DOBOT

Rockwell Automation
MITSUBISHI
SIEMENS
OMRON

SOLOMON

AccuPick 3D

Solmotion

Solvision

Solscan

SOLOMON Camera

Intel RealSense Depth Camera

Microsoft Azure Kinect

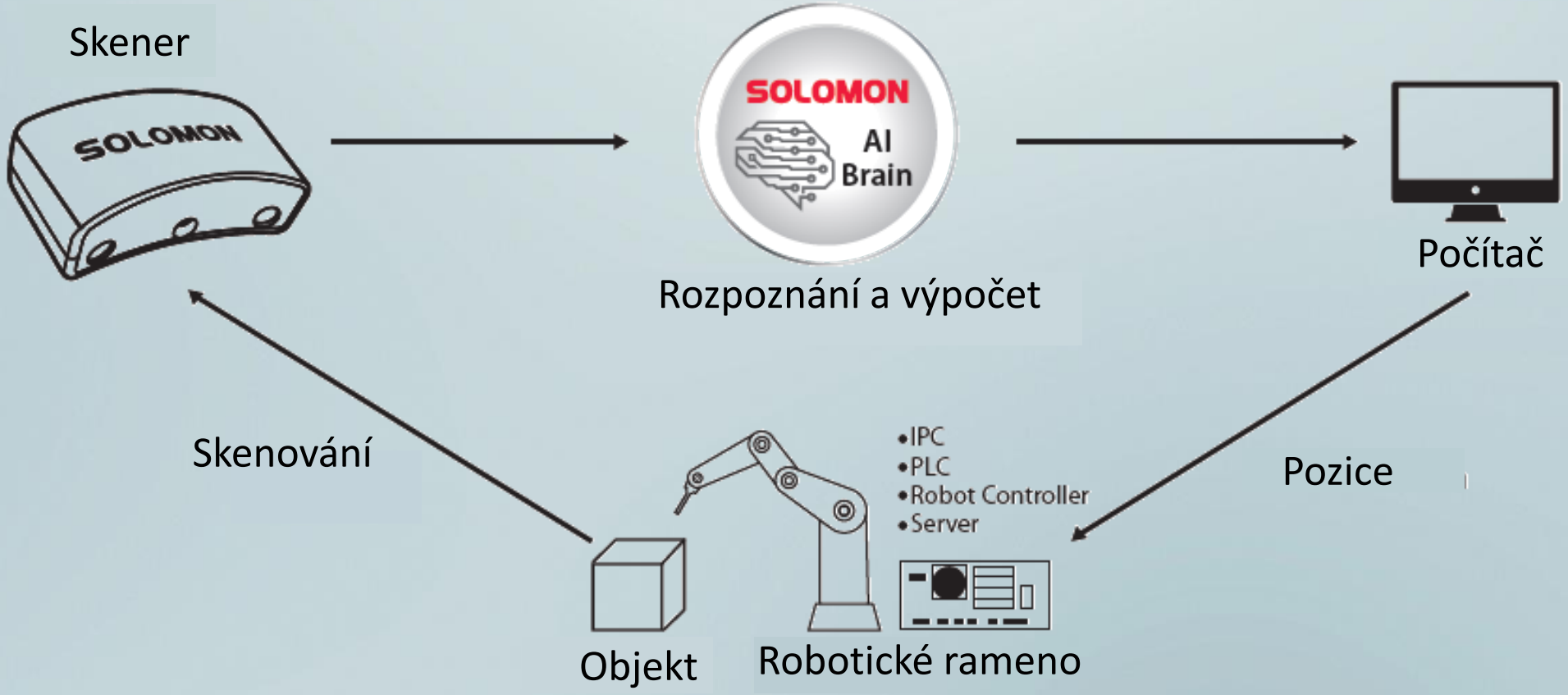
AccuPick 3D

Rychlý • Spolehlivý • Jednoduchý • Univerzální

AccuPick

reddot winner 2020
best of the best interface design

Vision Systems Design 2019 Innovators Awards GOLD



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ACCUPICK

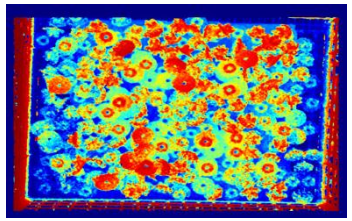
SOLOMON

Snímání

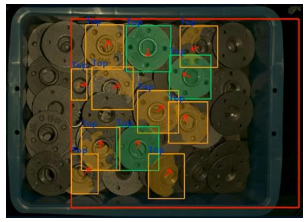
Rozpoznání a lokalizace

Pick-and-place operace

3D Skener

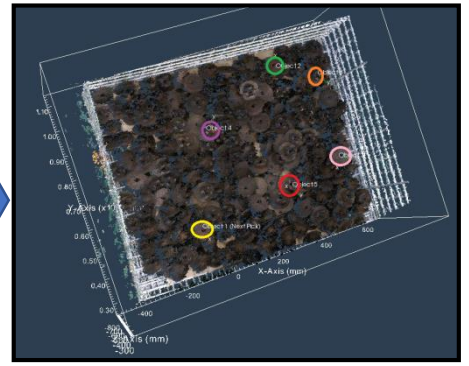


3D hloubkový obraz



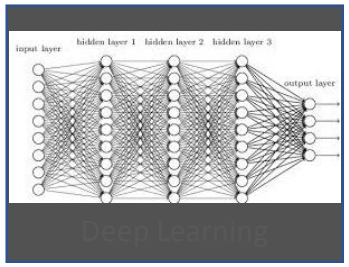
2D obraz textury

Rozpoznávání objektů a lokalizace s 3D informacemi.



Stanovení bodu uchopení

Robot Pick & Drop

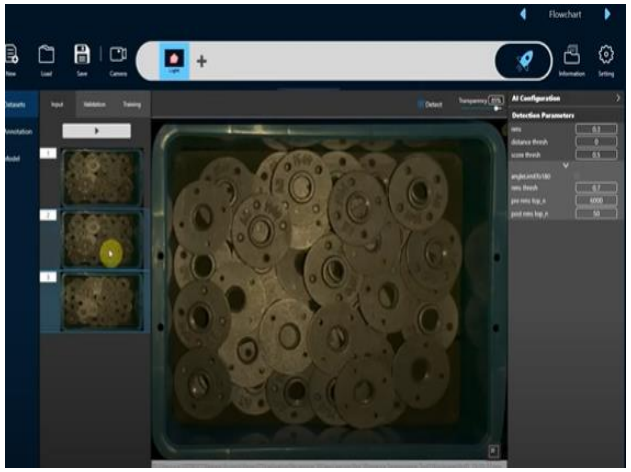


Rozpoznání „super“modelu

AI-based Localization

SOLOMON

2D



Pořízení 2D obrazu

Rozpoznávání a segmentace

Výběr kusu a definice bodů uchopení.

3D

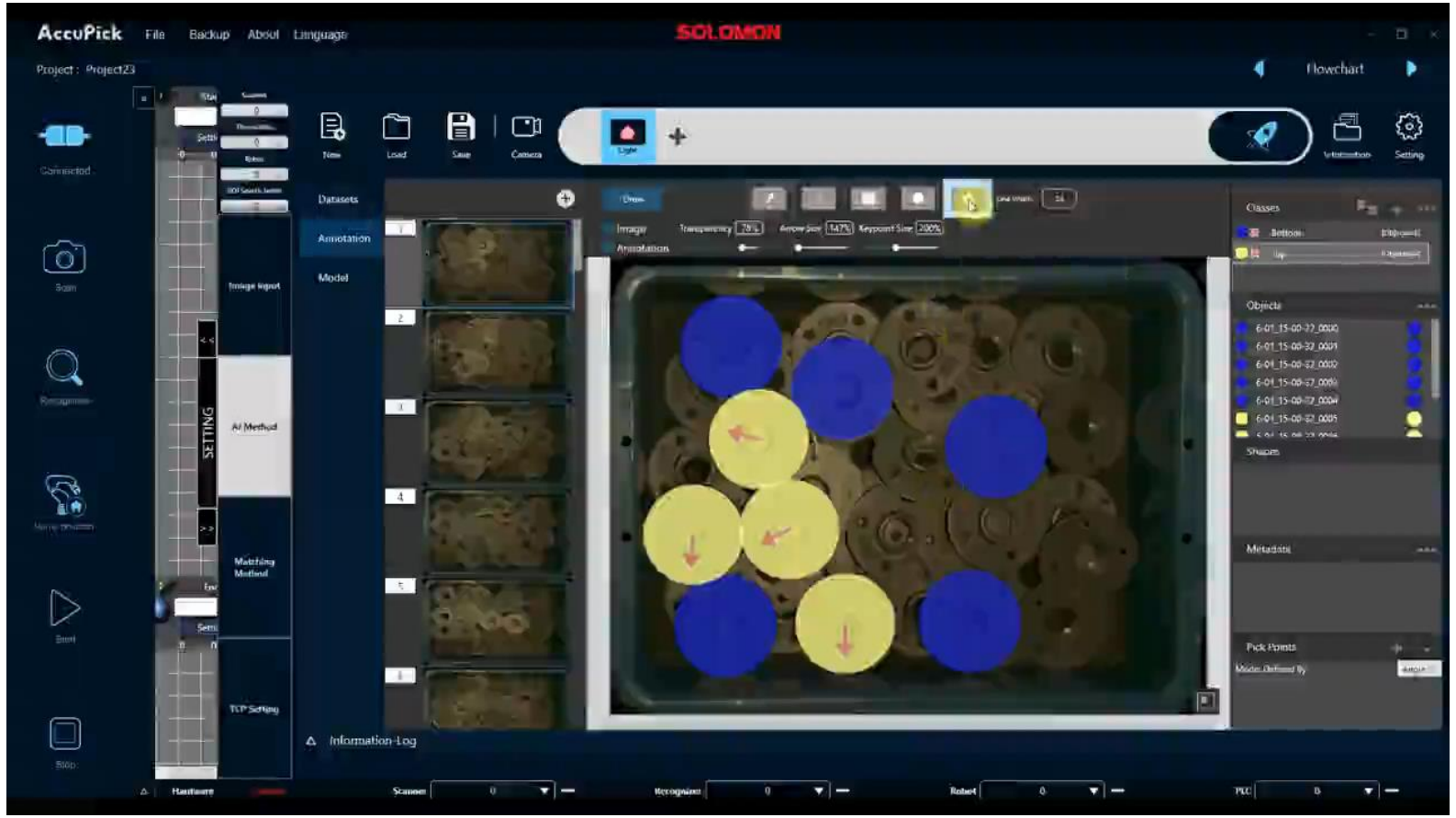
Získání 3D bodového cloudu

Přizpůsobení geometrického vzoru

Software Standard Functions

SOLOMON

AI Based Localization



- Funkce označování vybavená různými nástroji pro kreslení tvarů
- Úhel uchopení může být definován šipkou
- Nástroj pro automatické označování objektů, které vyžadují testování
- Podle potřeby zákazníka lze uspořádat a přidat různé nástroje pro deep-learning


DOBOT
Magician Pro
DOBOT
Shake Hands With The Future

DOBOT

MG400

Nosnost	500 g / 750 g
Dosah	440 mm
Opakovatelnost	±0.05 mm
Komunikace	TCP/IP, MODBUS
Hmotnost	8 kg
Základna	190 x 190 mm

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MG400

Nosnost	500 g / 750 g
Dosah	440 mm
Opakovatelnost	±0.05 mm
Komunikace	TCP/IP, MODBUS
Hmotnost	8 kg
Základna	190 x 190 mm

Kompaktní provedení se snadným přístupem a obsluhou

Enkodér - 1x

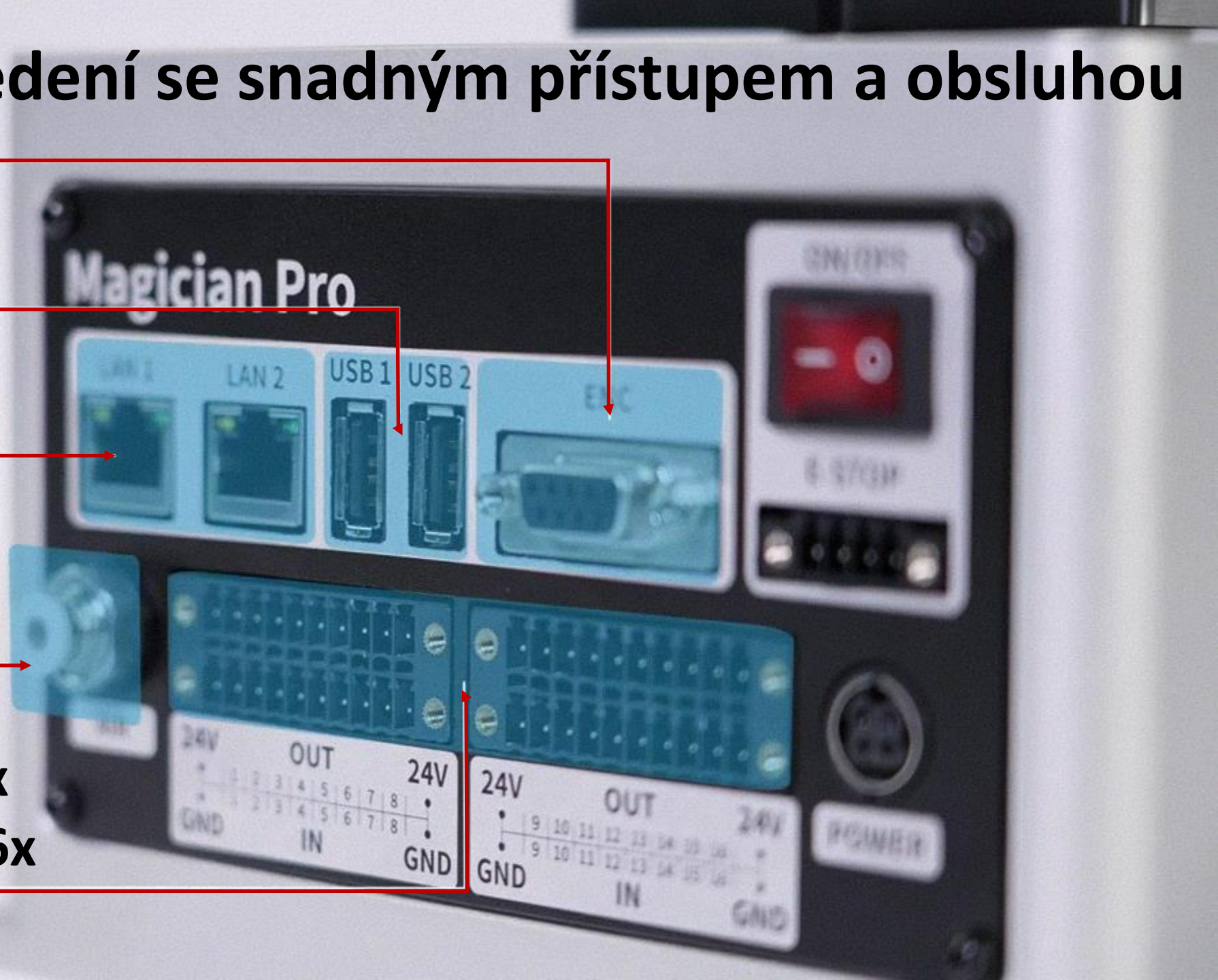
USB 2.0 - 2x

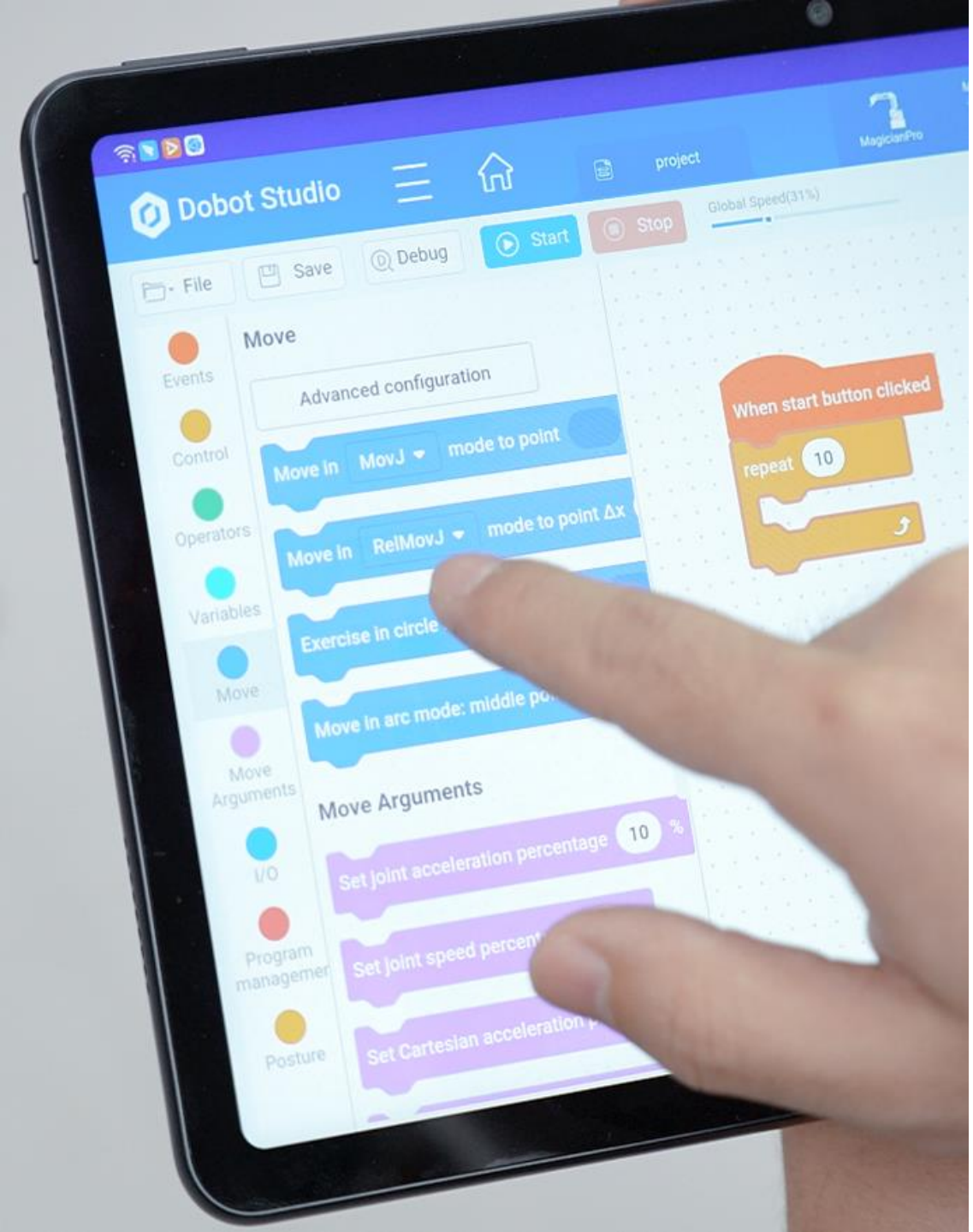
Ethernet - 2x

Pneumatika - 1x

Digitální vstupy - 16x

Digitální výstupy - 16x





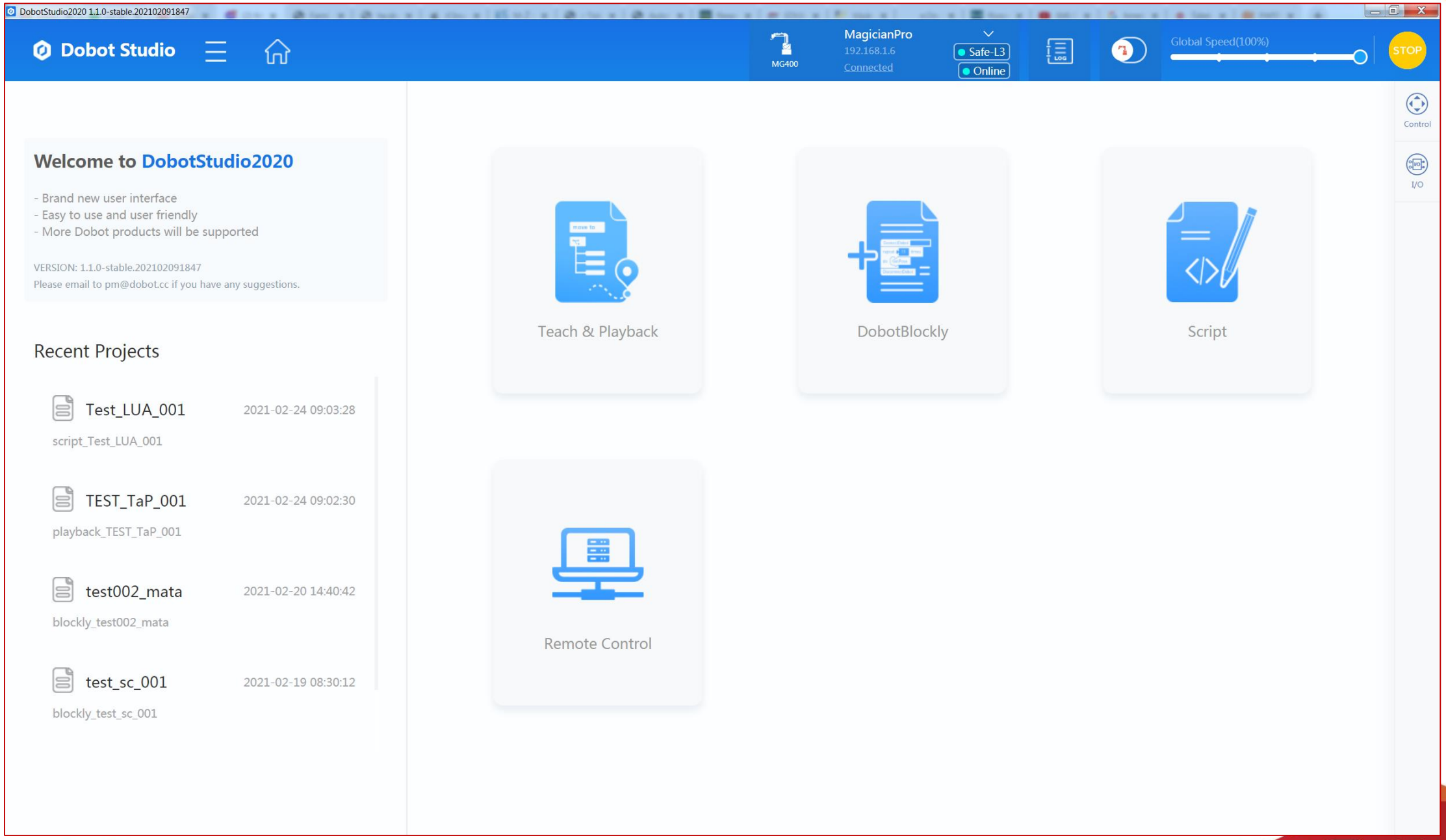
MG400

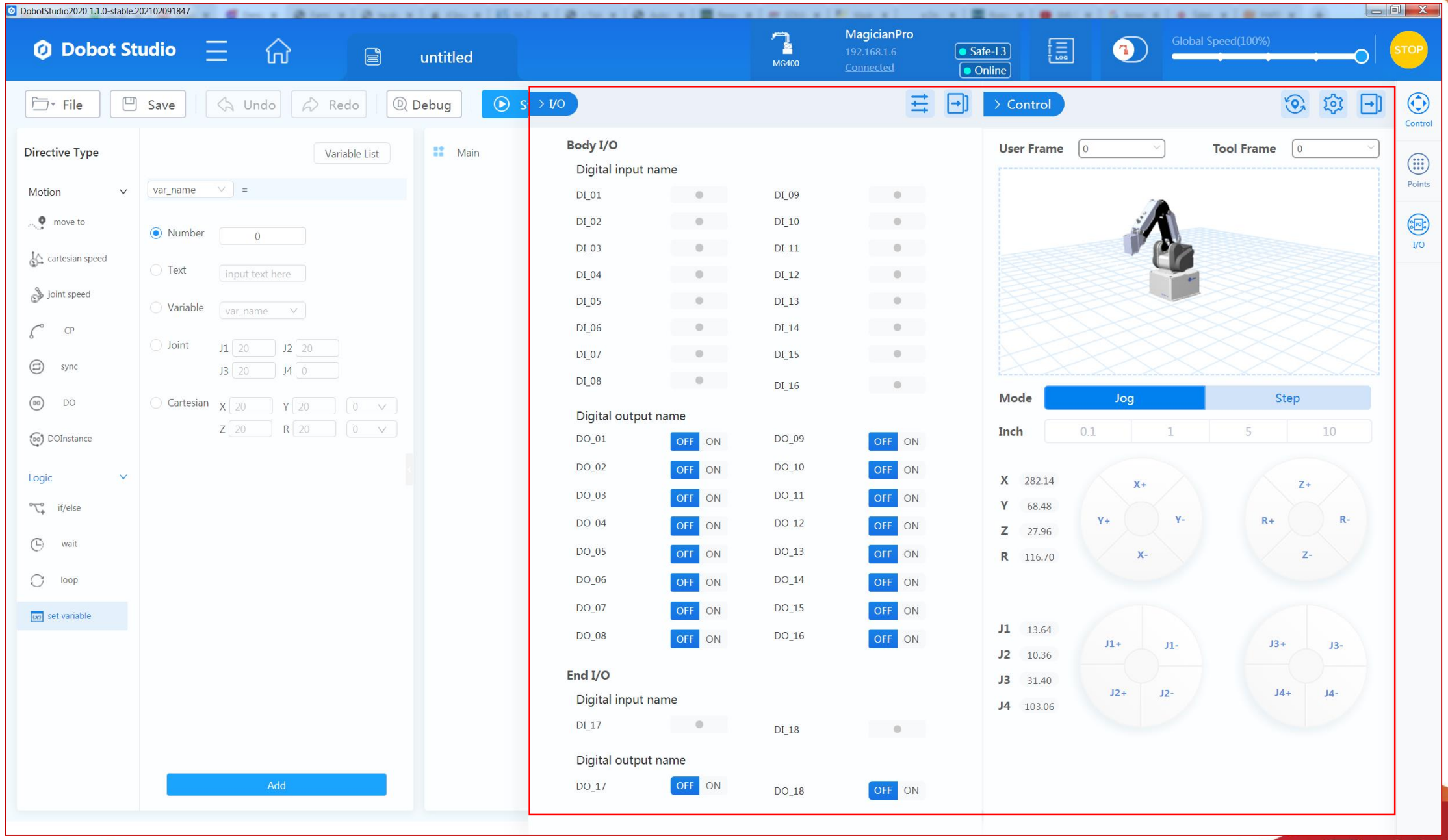
programování

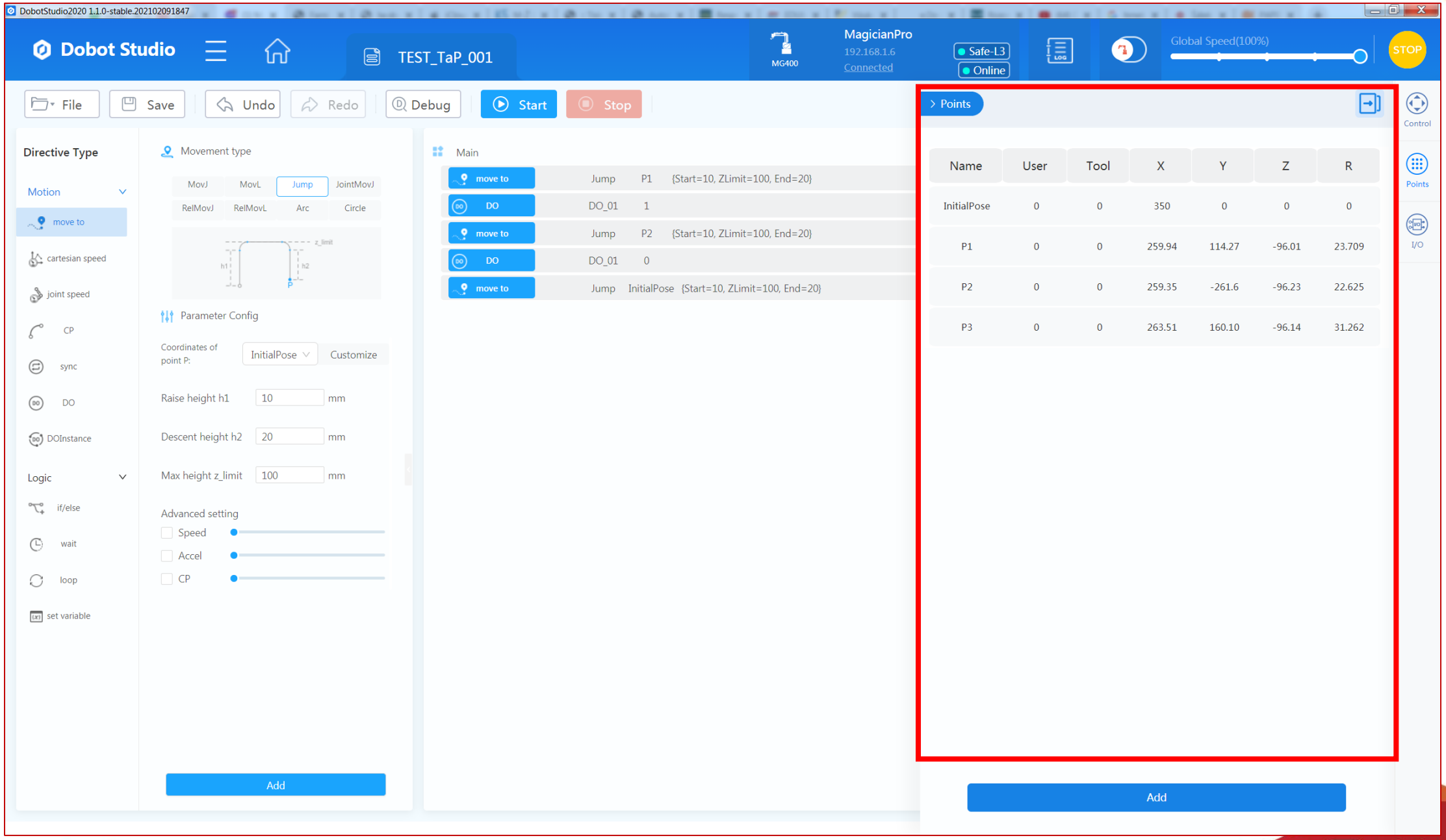
FORMOU UČENÍ
bez znalosti programovacích jazyků

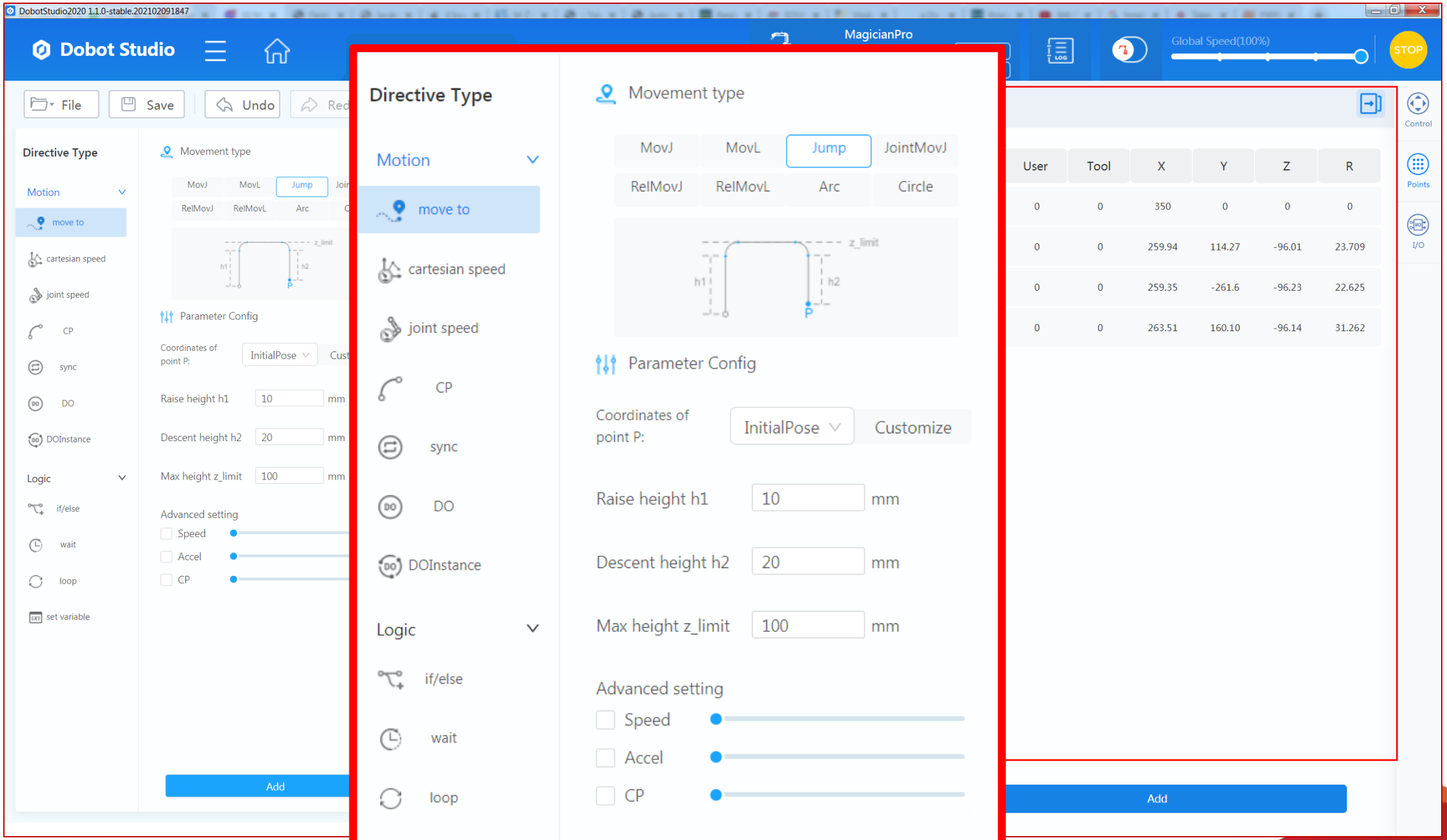
INTUITIVNÍ GRAFICKÉ PROGRAMOVÁNÍ
bez znalosti přesné syntaxe

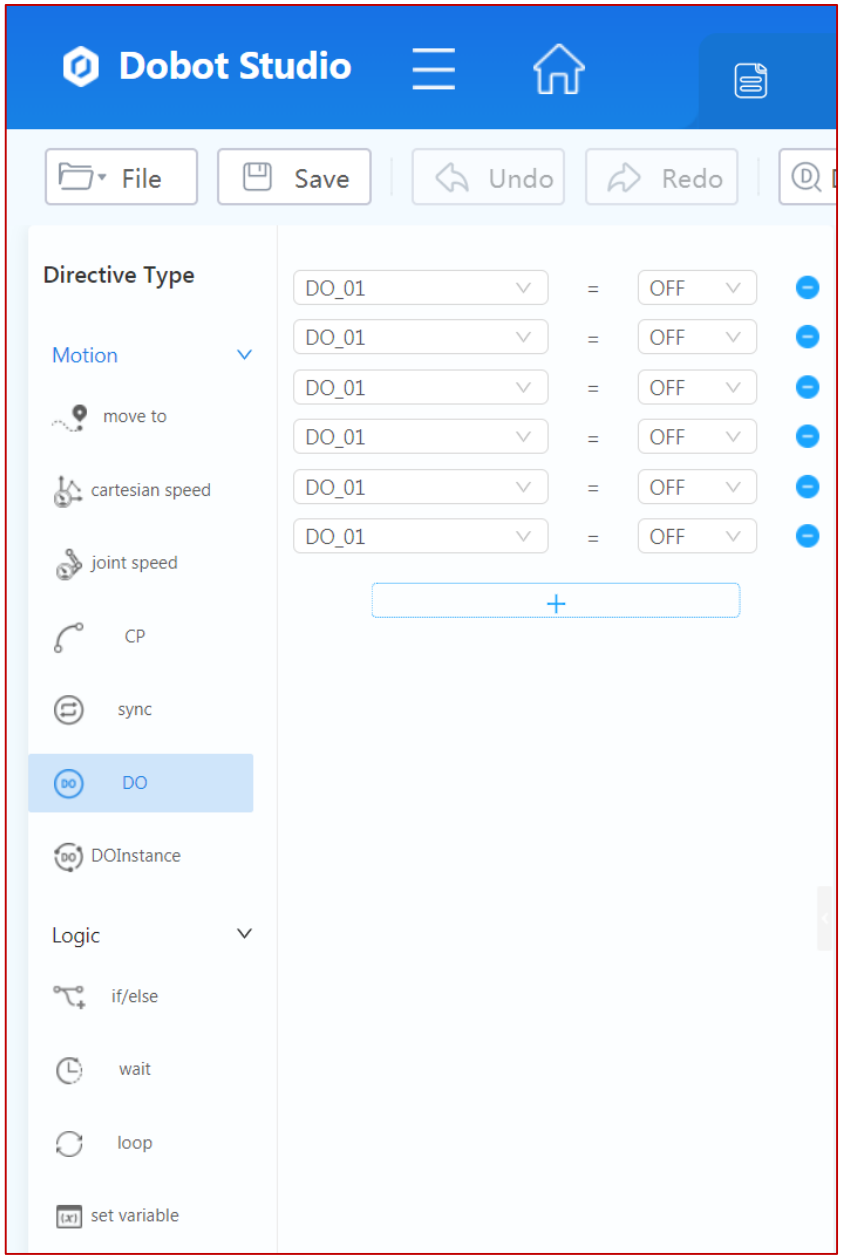
STANDARNÍ PROGRAMOVÁNÍ
pomocí skriptů LUA

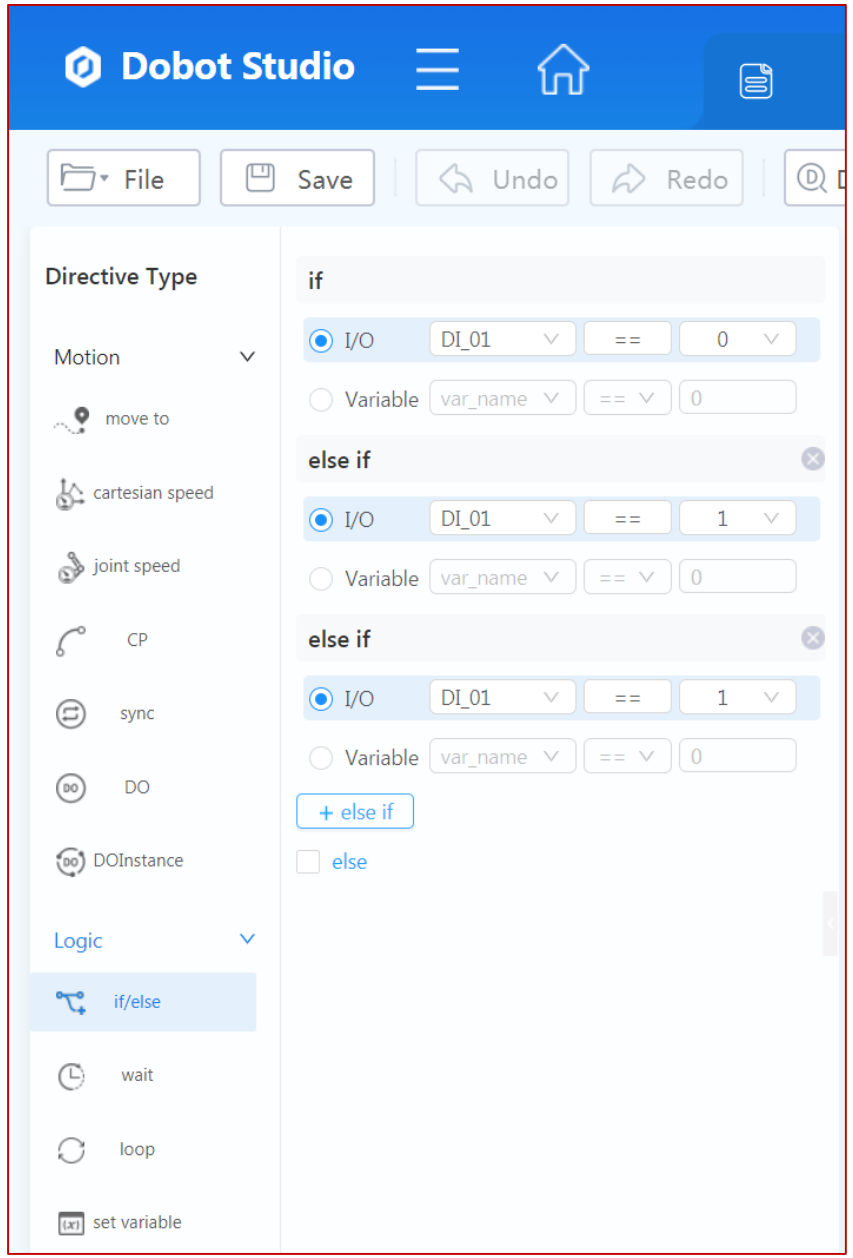


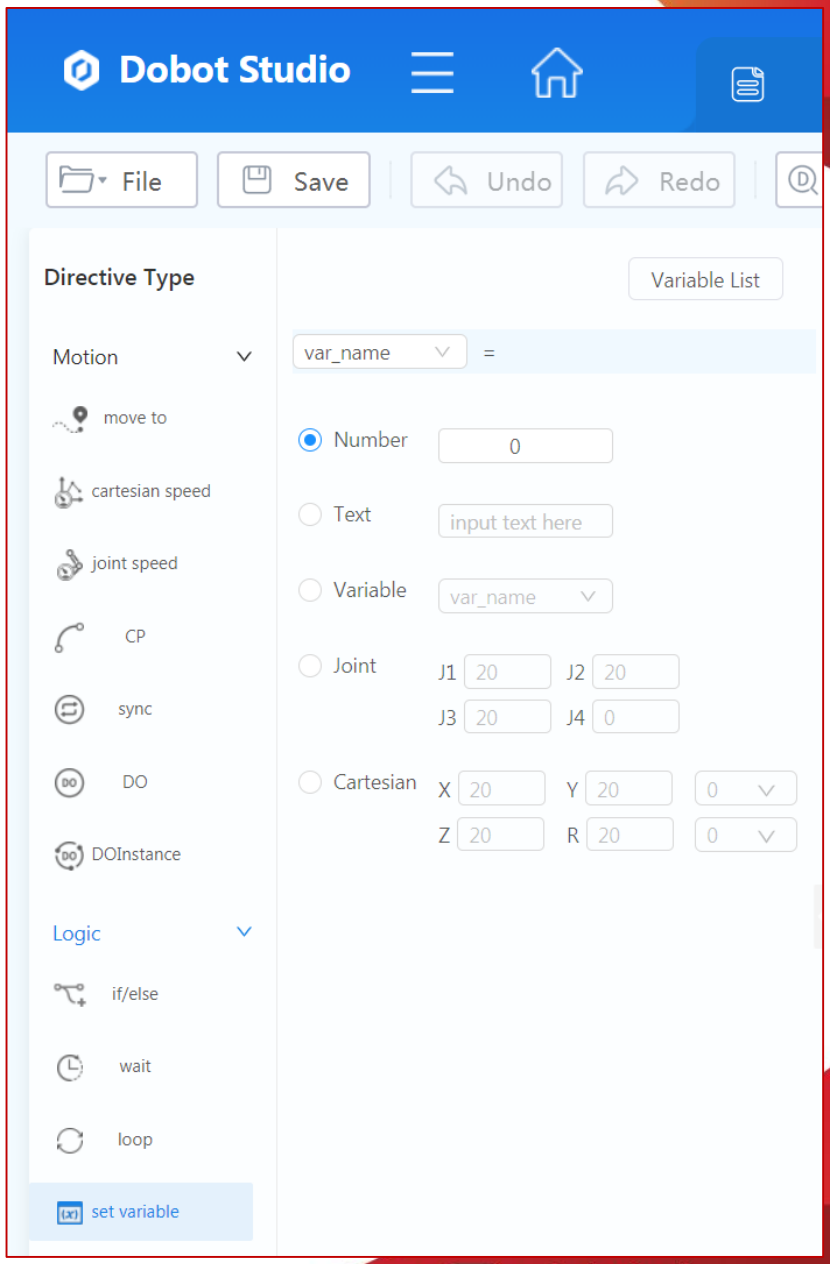


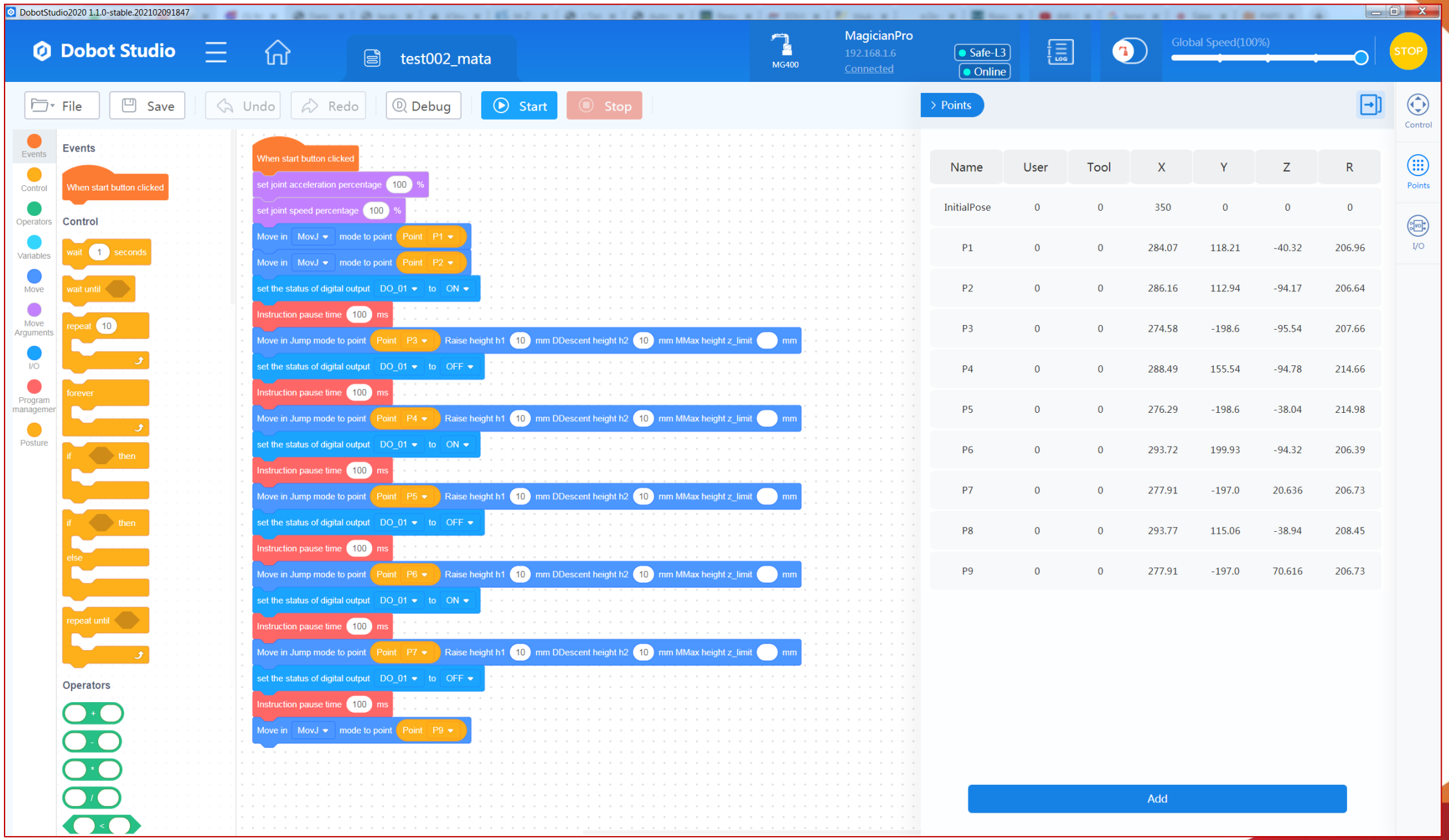


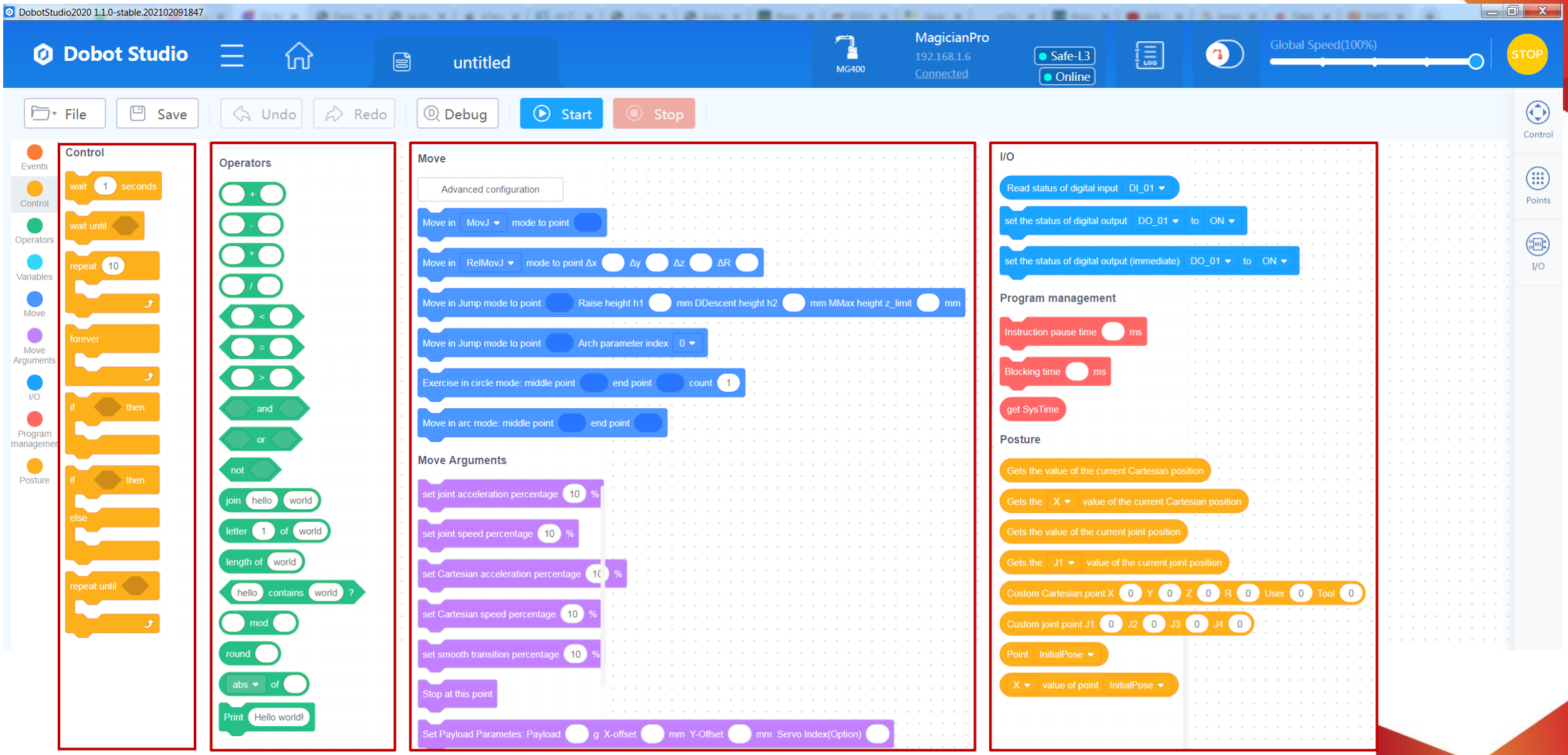


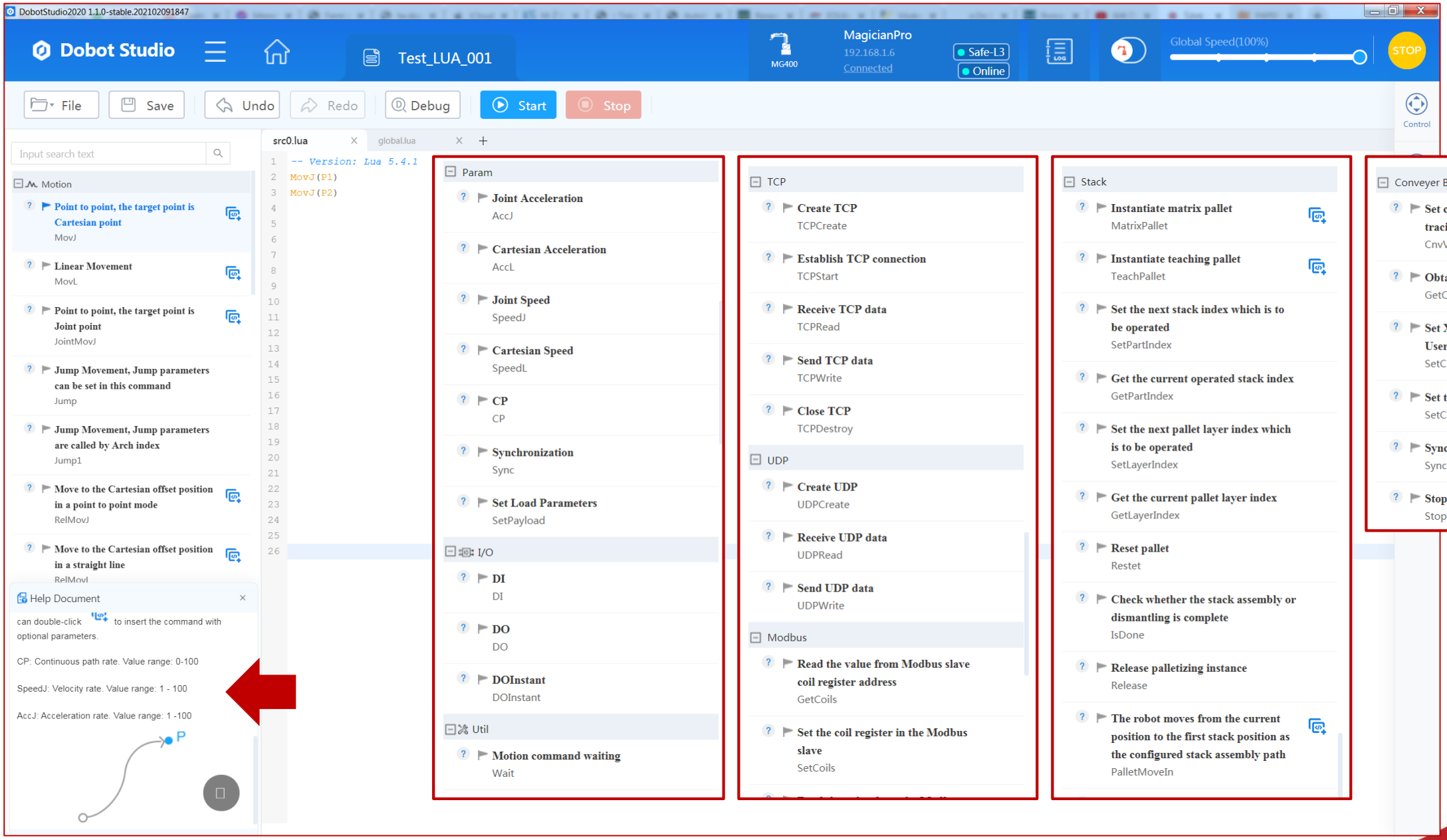


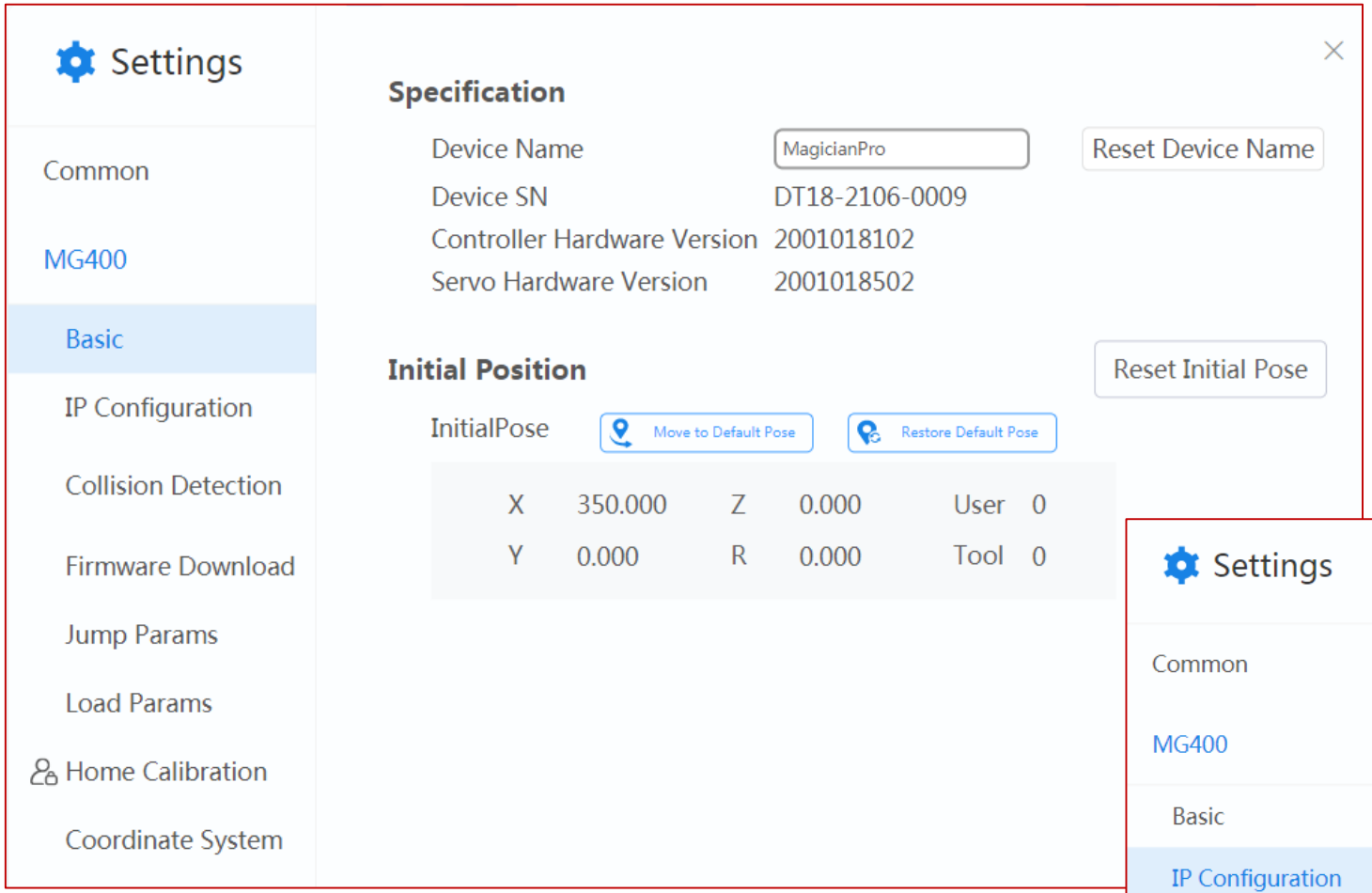


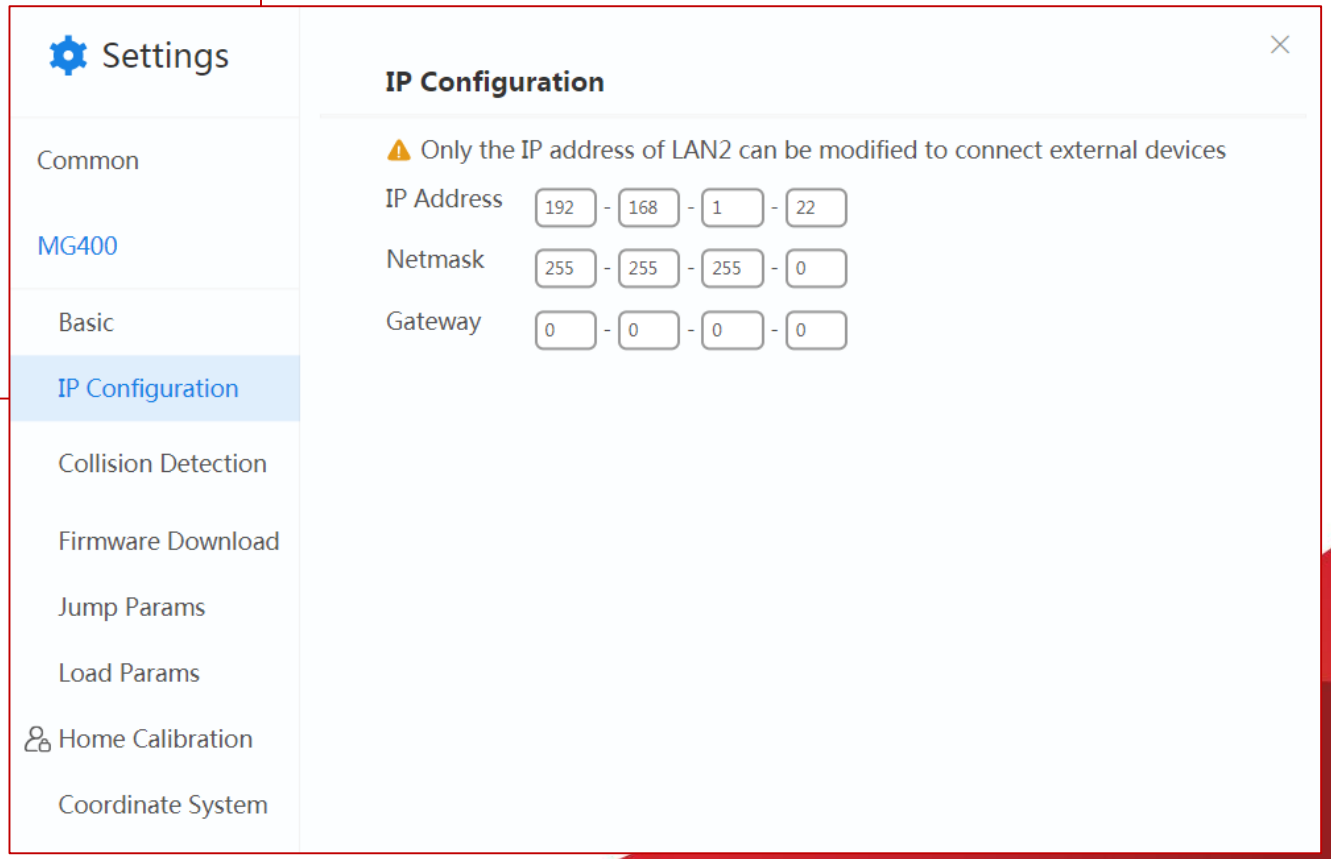












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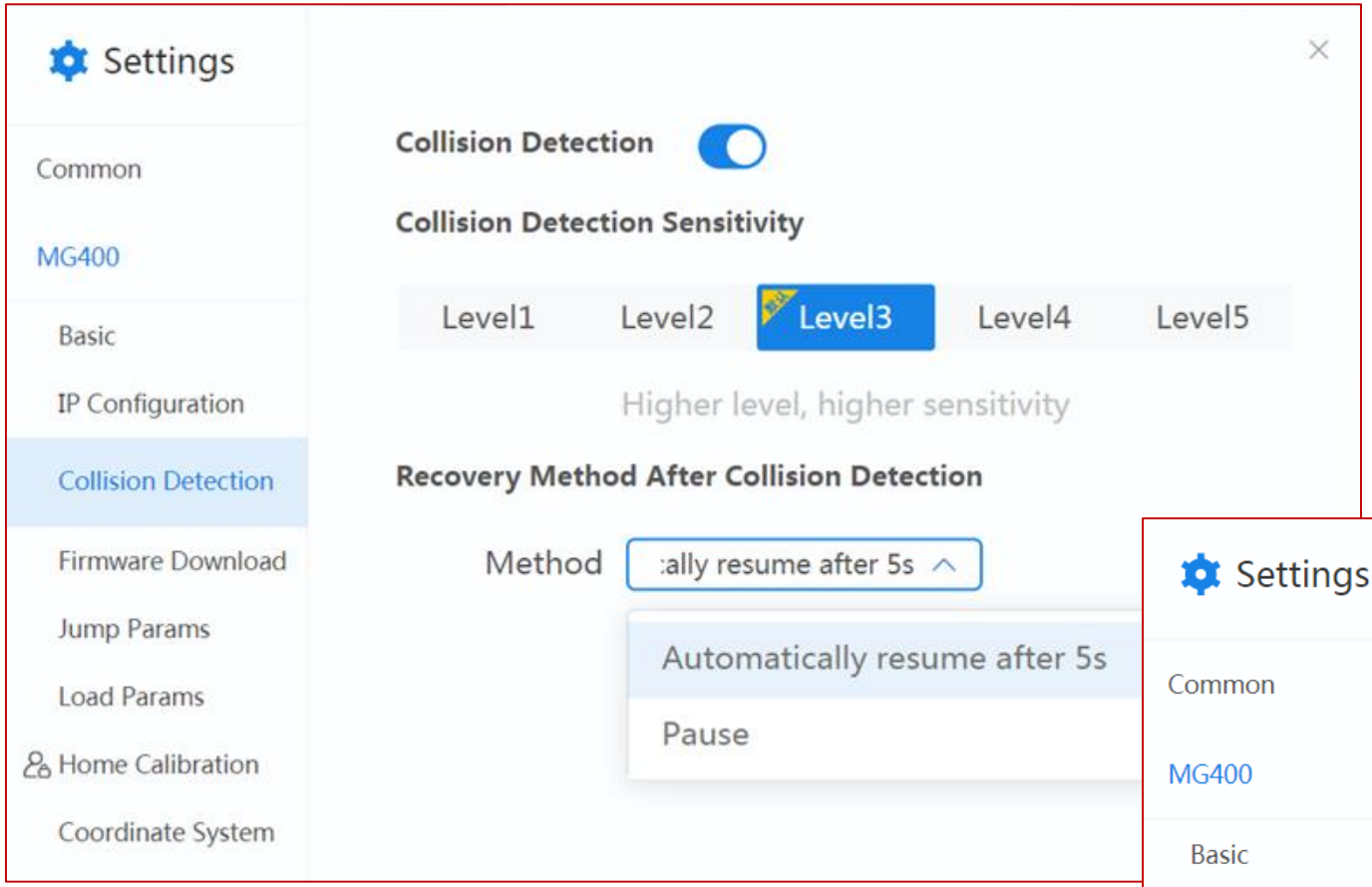
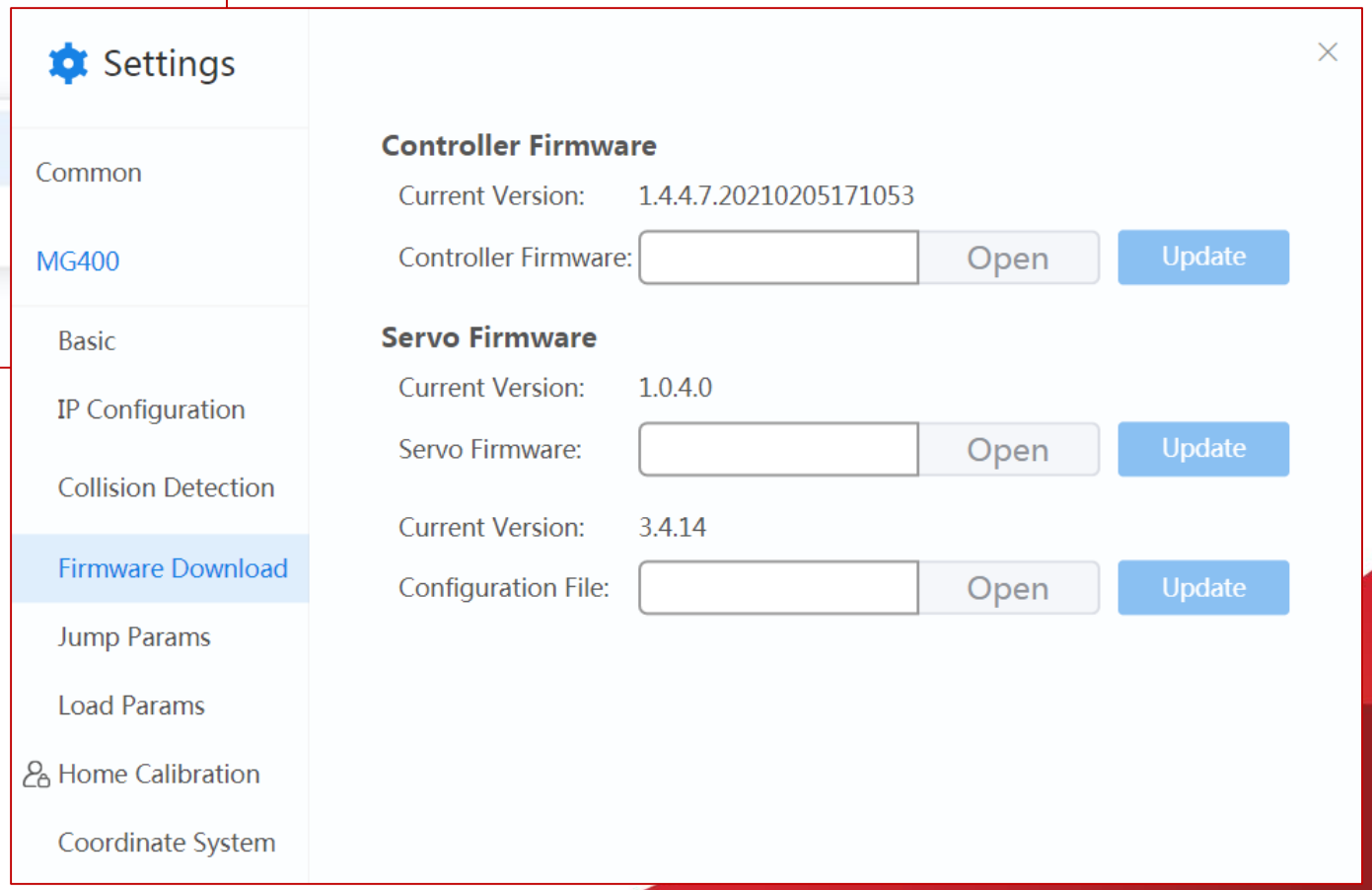




ControlTech

Settings

Common

MG400

Basic

IP Configuration

Collision Detection

Firmware Download

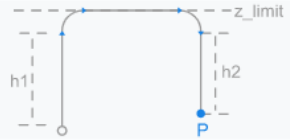
Jump Params

Load Params

Home Calibration

Coordinate System

Jump parameter setting



Number	h1(mm)	h2(mm)	zLimit(mm)
0	5	50	50
1	0	0	135
2	6	24	
3	7	50	
4	7	50	
5	7	31	
6	7	50	
7	7	50	
8	7	50	
9	7	50	

Settings

Common

MG400

Basic

IP Configuration

Collision Detection

Firmware Download

Jump Params

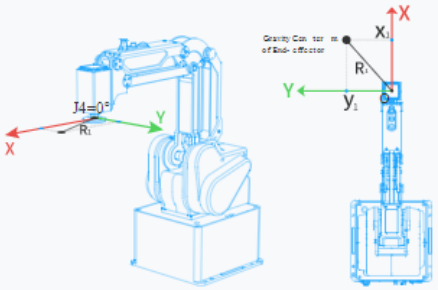
Load Params

Home Calibration

Coordinate System

Load Params

In order to ensure the smooth operation of the manipulator and avoid the phenomenon of collision detection, it is necessary to set the eccentric coordinates (x1, Y1) of the end load when the J4 axis angle is 0 degrees



Payload	0	g
Offset-x	0	mm
Offset-y	0	mm

Cancel OK

ControlTech

Settings

Common

MG400

Basic

IP Configuration

Collision Detection

Firmware Download

Jump Params

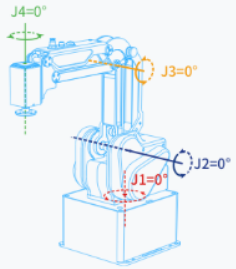
Load Params

Home Calibration

Coordinate System

Home Calibration

Home calibration is only used when the home position changes, please operate carefully。



Schematic diagram of home position

Please enable and move the device to the home position and click home calibration.

Home

Settings

Common

MG400

Basic

IP Configuration

Collision Detection

Firmware Download

Jump Params

Load Params

Home Calibration

Coordinate System

User Frame | Tool Frame

copy | Modify | Add

index	X	Y	Z	R
0	0.000	0.000	0.000	0.000
1	0.000	0.000	0.000	0.000
2	123.595	43.286	0.000	0.000
3	70.063	5.412	0.000	0.000
4	0.000	0.000	0.000	0.000
5	0.000	0.000	0.000	0.000
6	0.000	0.000	0.000	0.000
7	0.000	0.000	0.000	0.000

Apply

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DOBOT SCARA M-1

Opakovatelnost
0,02 mm

Rychlost
200°/s

Nosnost
1,5 kg

Dosah
400 mm

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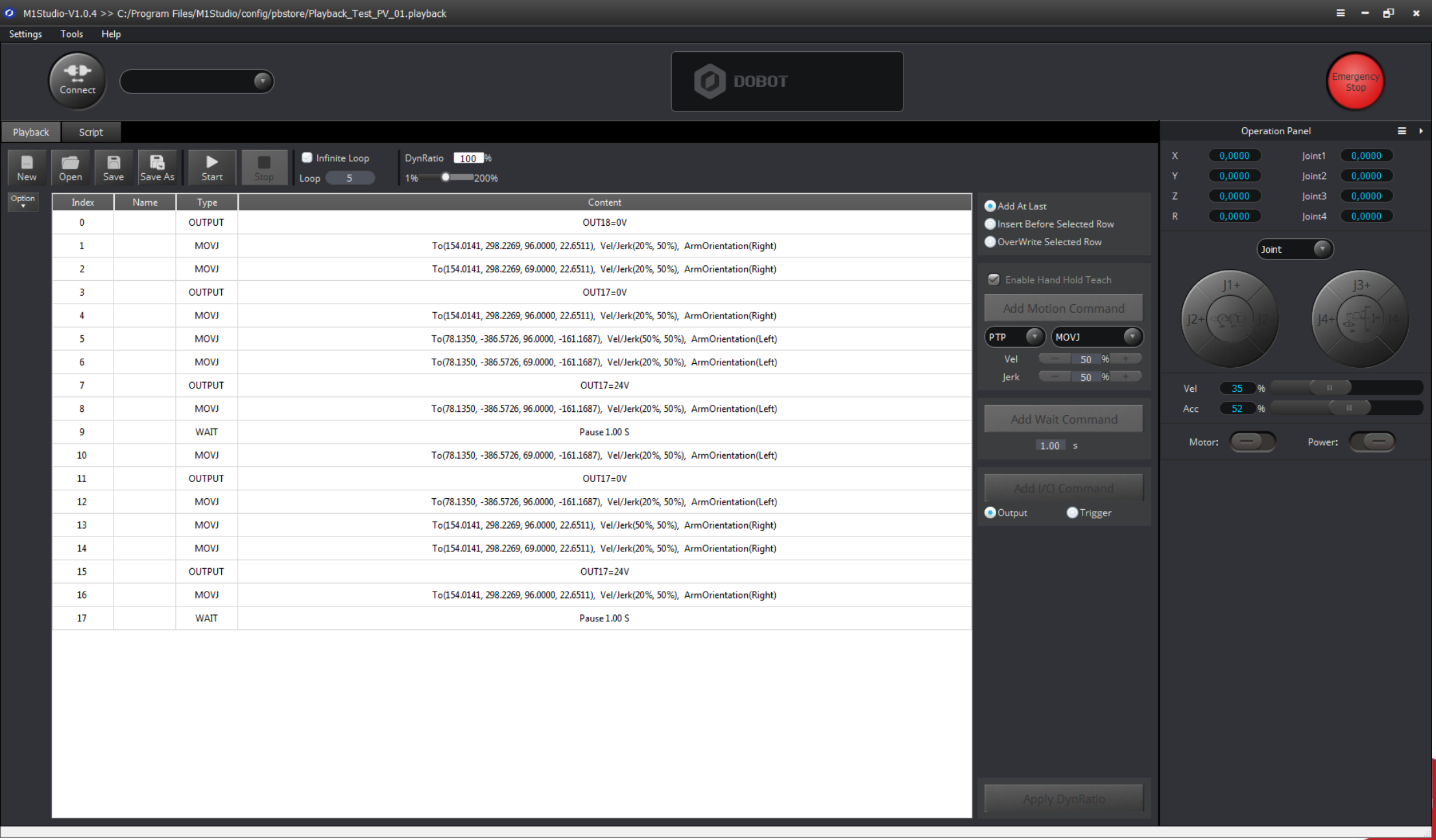

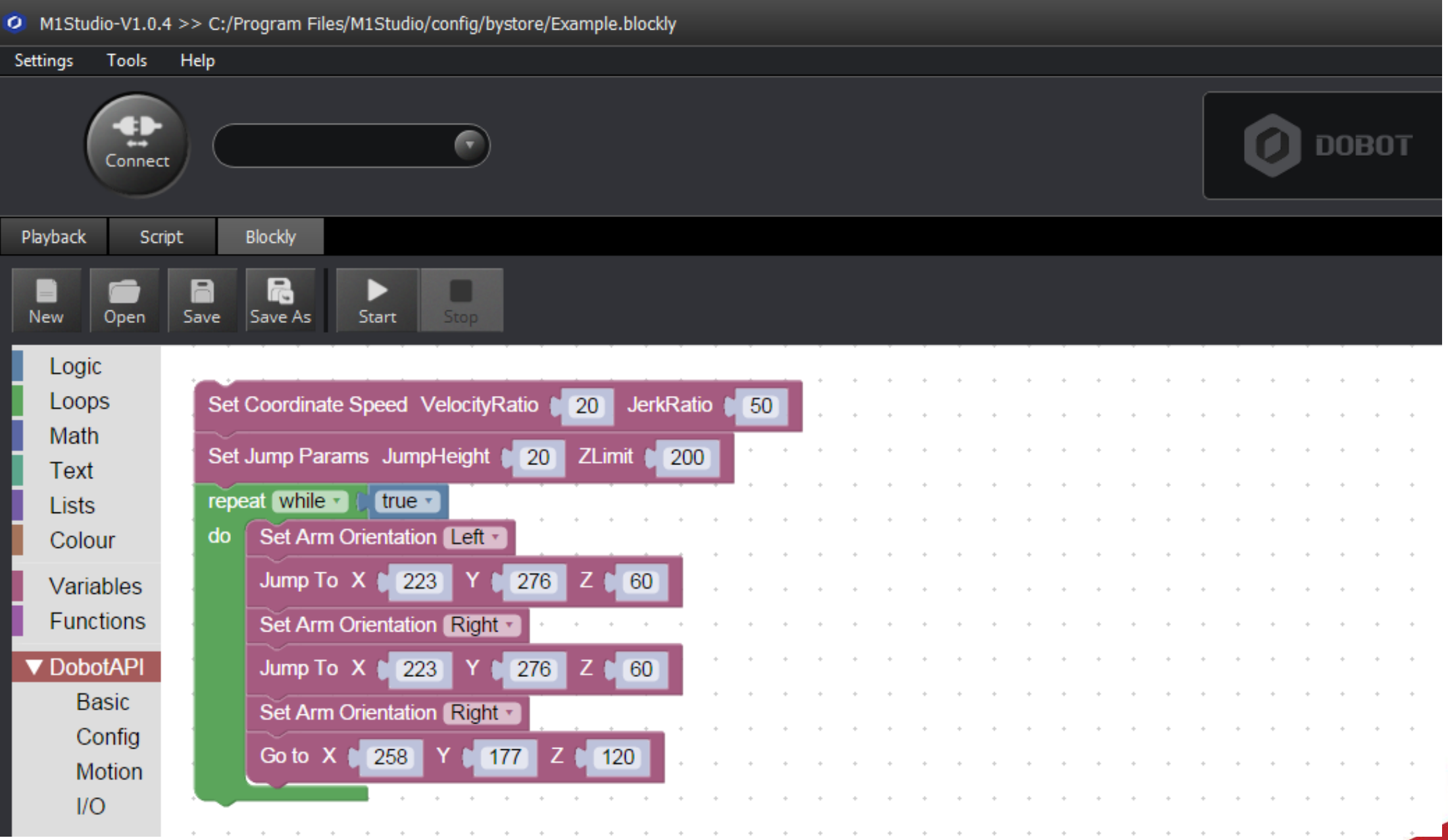

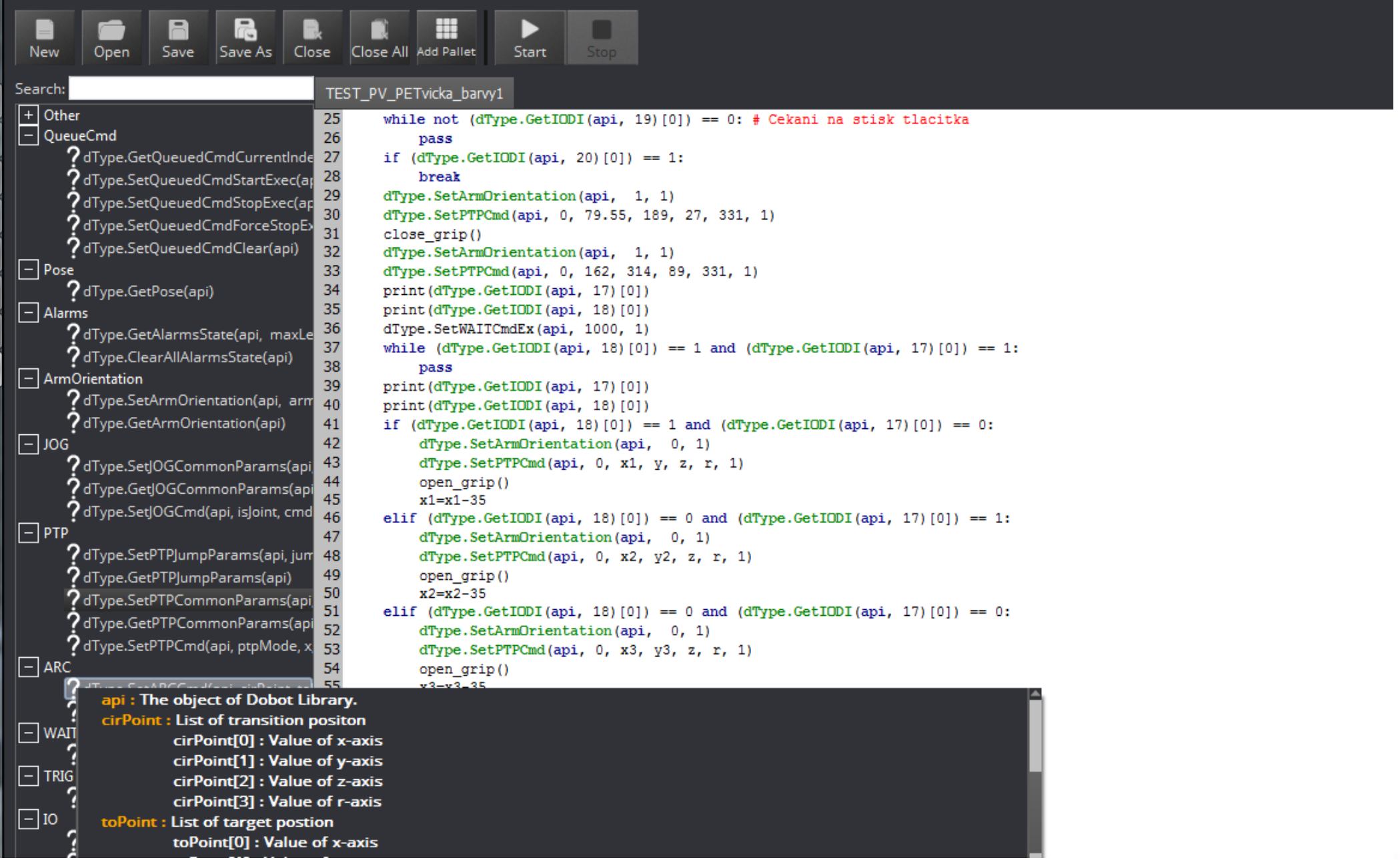

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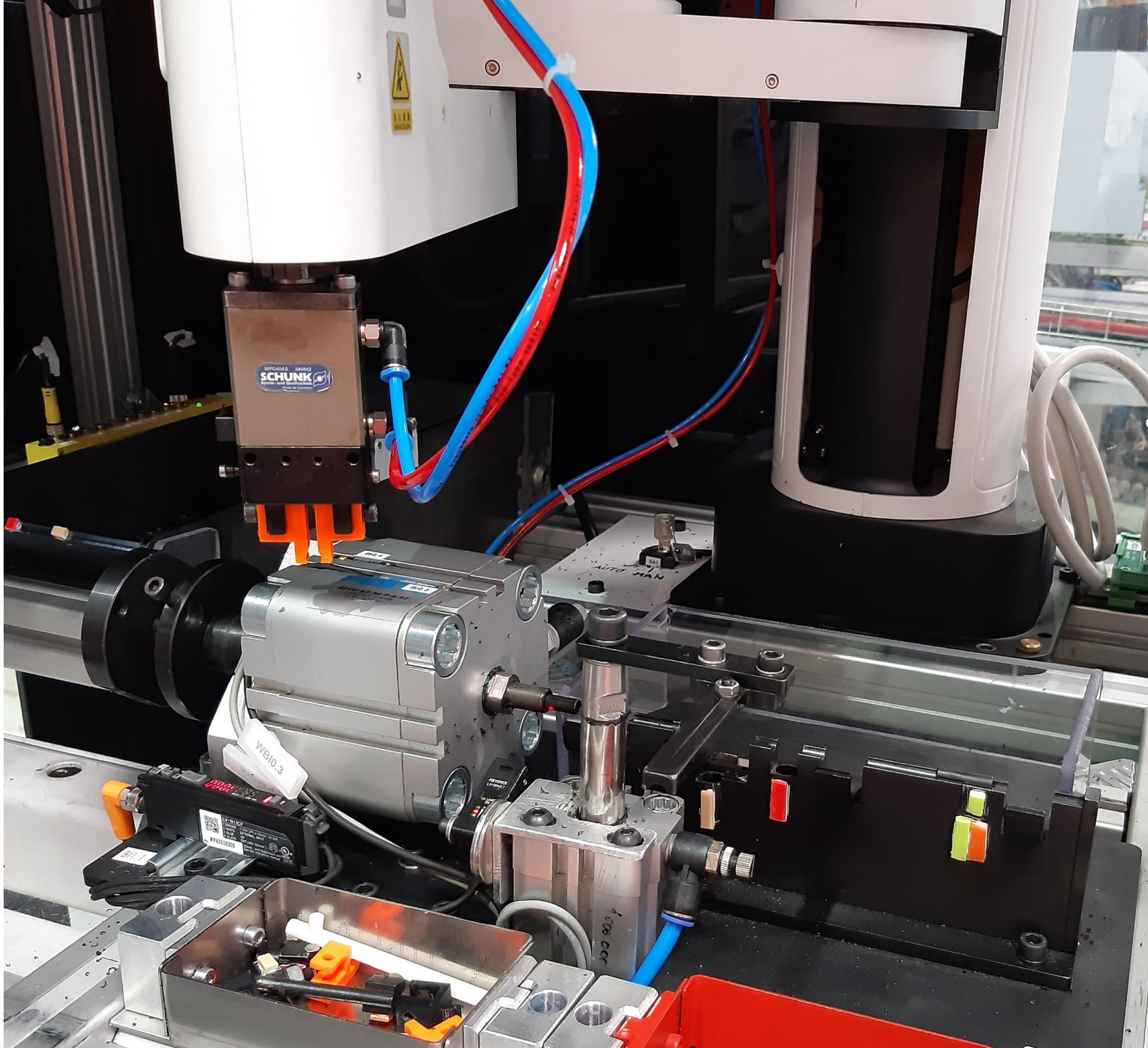
BIOMEDICA

AICOBOTIX
ARTIFICIAL INTELLIGENCE

Rendszer

NICO
TECHNIKA

u-shin



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EDUKATIVNÍ ROBOTY

nejen pro školy

DESIGN AWARD 2018

reddot award 2018 winner

CES 2018

红星奖 Red Star Design Award

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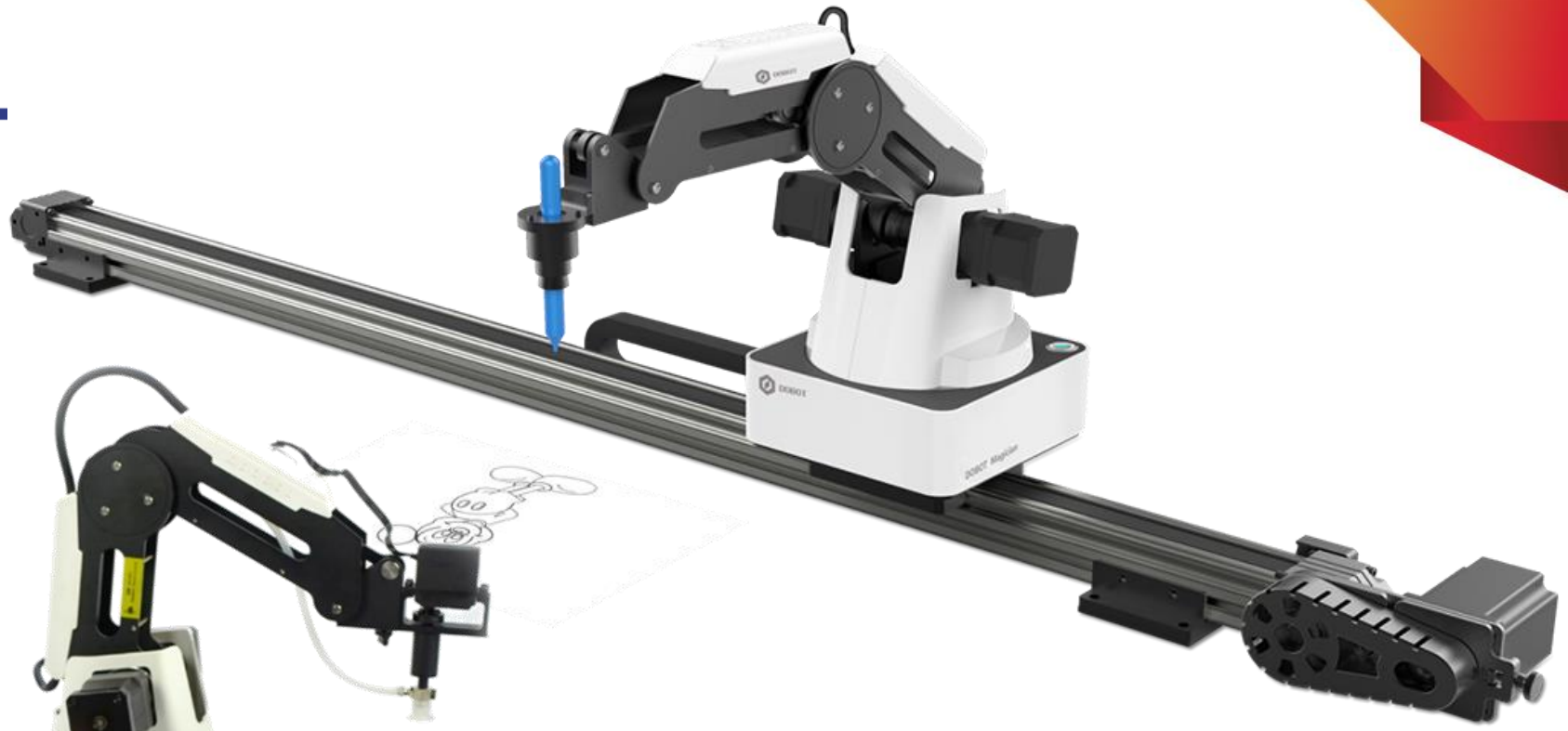

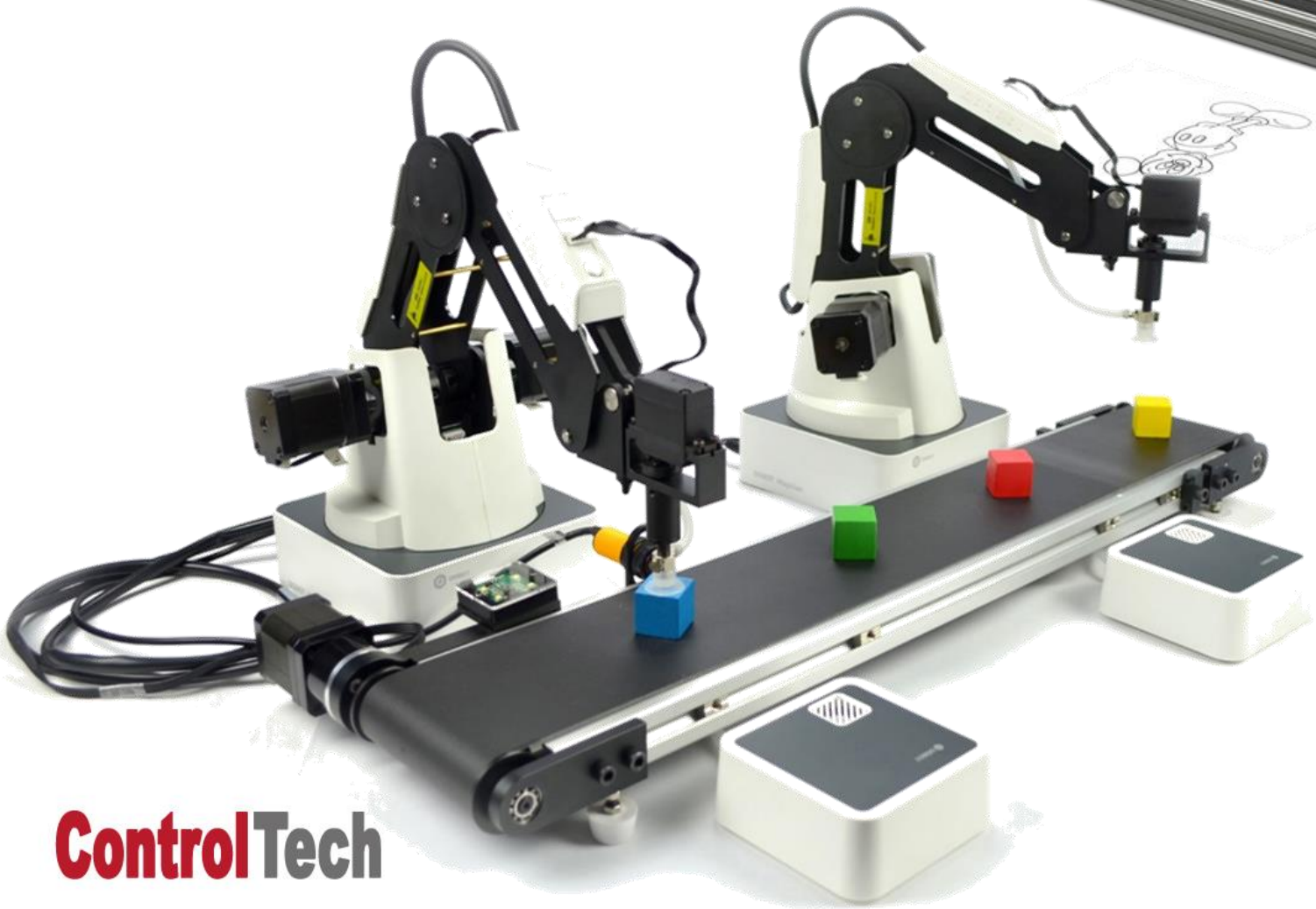

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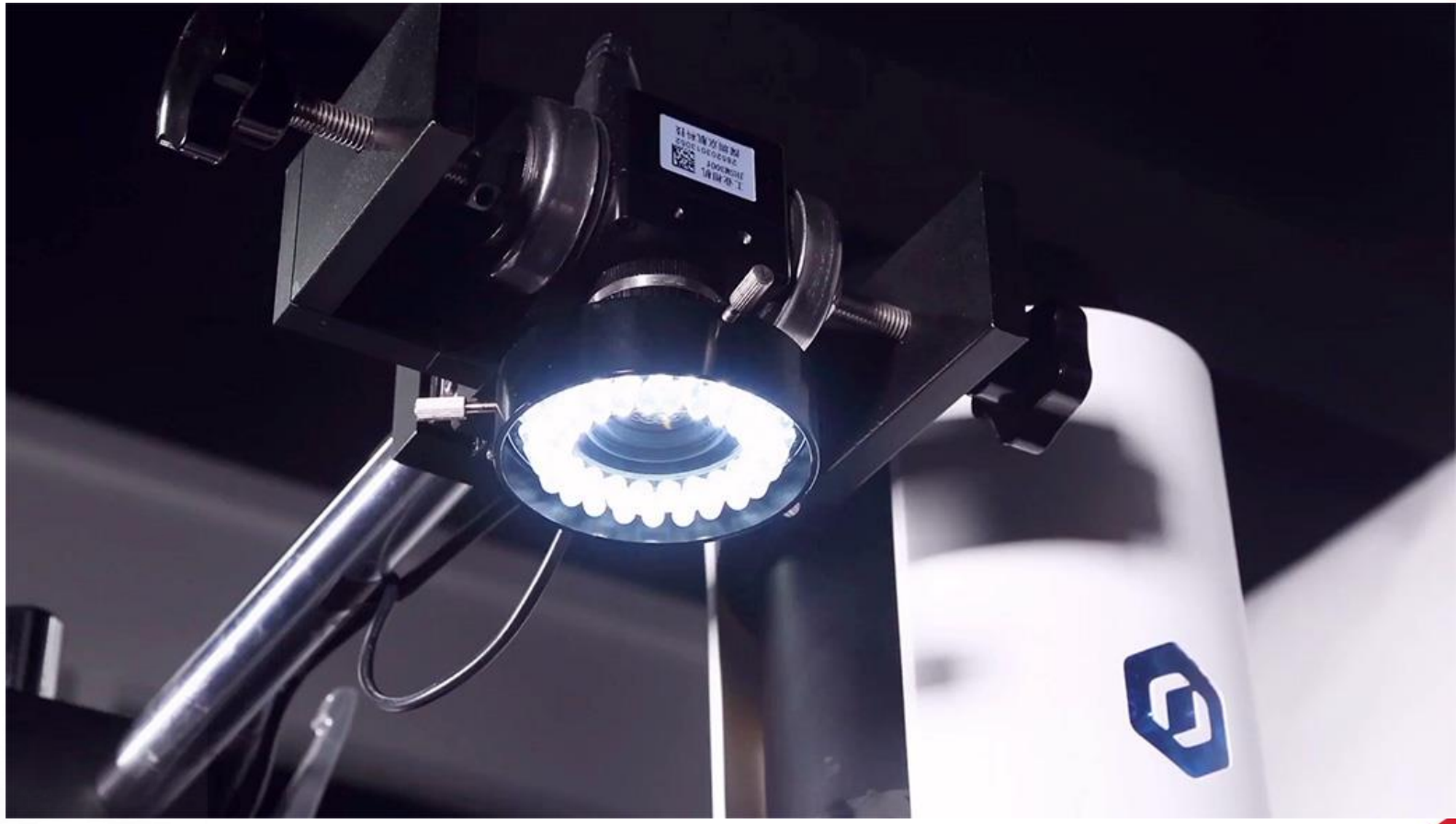

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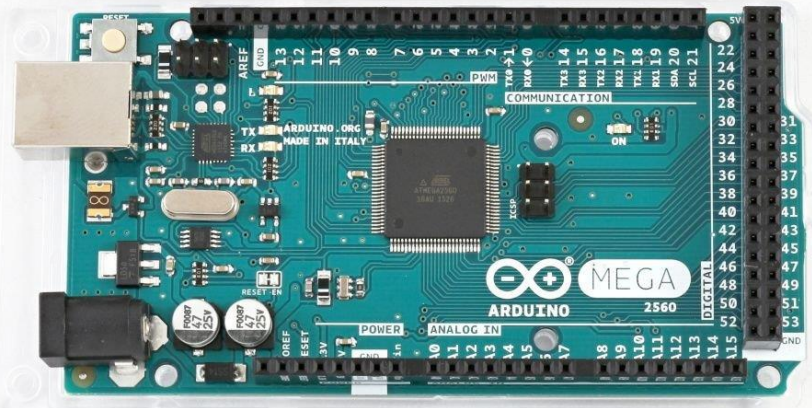
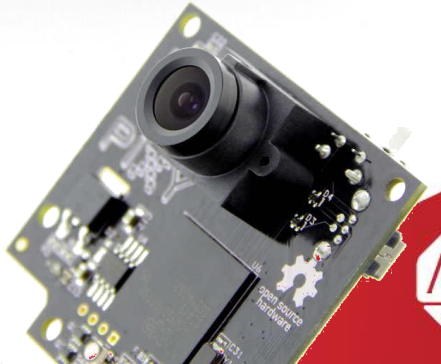
ARDUINO

EDUCATION





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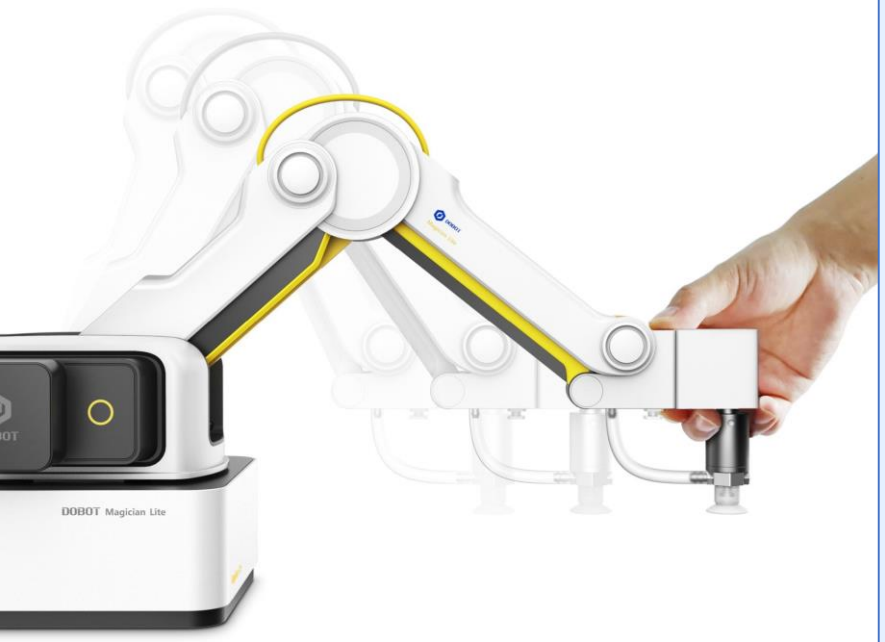

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DOBOT | Soubor | Upravit | Nápověda | Výukové centrum | Projekt Scratch

Scénáře

Zařízení | Sprite

Magician

Souřadnice | Rychlost

X 0
Y 0
Z 0
R 0

Y+ Z+ X- X+ Z- Y-

R- R+

Lineární pojezd L- L+

Uchopit | Pustit | Přísavka

Ovládání
Operátory
Proměnné
Vnímání
Události
Nastavení
Pohyb
Stav
I/O
Moje bloky

Pohyb

Kalibrovat
Skoč na X 0 Y 0 Z 0 R 0
Jdi na X 0 Y 0 Z 0 R 0 Způsob pohybu Lineární pohyb
Relativní pohyb ΔX 0 mm ΔY 0 mm ΔZ 0 mm ΔR 0 °
Otoč klouby na Kloub 1 0 ° Kloub 2 0 ° Kloub 3 0 ° Kloub 4 0 °
Nastavit R 0 °
Uchopovač Uchopit
Přísavka Uchopit

Stav

Získat současné souřadnice X
Získat současné úhly kloubů Kloub 1
Smazat alarm

I/O

Nastavit Pin EIO1 Režim IO Funkce Dummy
Nastavit PWM výstup Pin EIO1 Frekvence 0 Střída 0 %
Nastavit digitální výstup Pin EIO1 Hodnota Logická 1

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Technická Univerzita v Košiciach
Slovenská technická univerzita v Bratislave
Žilinská univerzita v Žiline
Vyšší odborná škola a Střední průmyslová škola Děčín
VOŠ, SPŠ a JŠ Kutná Hora
Stredná odborná škola Dubnica nad Váhom
Stredná odborná škola polytechnická
Střední průmyslová škola Ostrov
Střední průmyslová škola Otrokovice
Střední průmyslová škola Klatovy
Střední průmyslová škola automobilní České Budějovice
Smíchovská střední průmyslová škola Praha
6. Základní škola Kolín, Základní škola Neštěmická Ústí nad Labem
a další ...

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ROBOTY OBVYKLE SKLADEM, IHNED K DODÁNÍ.

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