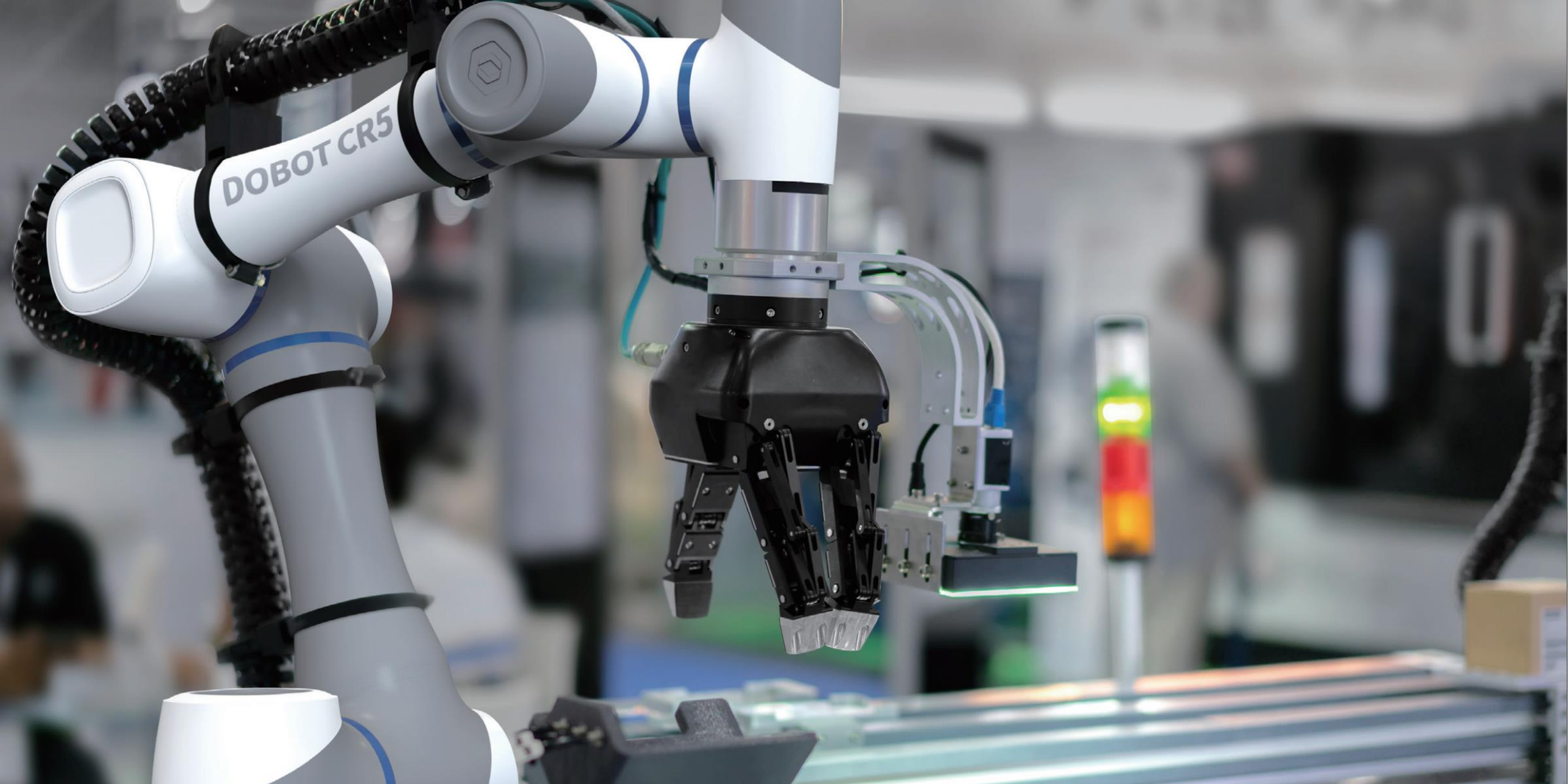

DOBOT CR5

ControlTech

Authorised Distributor
A ROCKWELL AUTOMATION PARTNER

PRŮMYSLOVÉ A EDUKATIVNÍ ROBOTY

VLADYKA PAVEL

DOBOT

Dobot každoročně uvádí na trh nové technologie a nové produkty, aby vyhověl potřebám rozvoje průmyslu.

CR3 CR7 CR5 CR16 CR12 CR10 CR3L

CR Collaborative Robot Series

Specifications

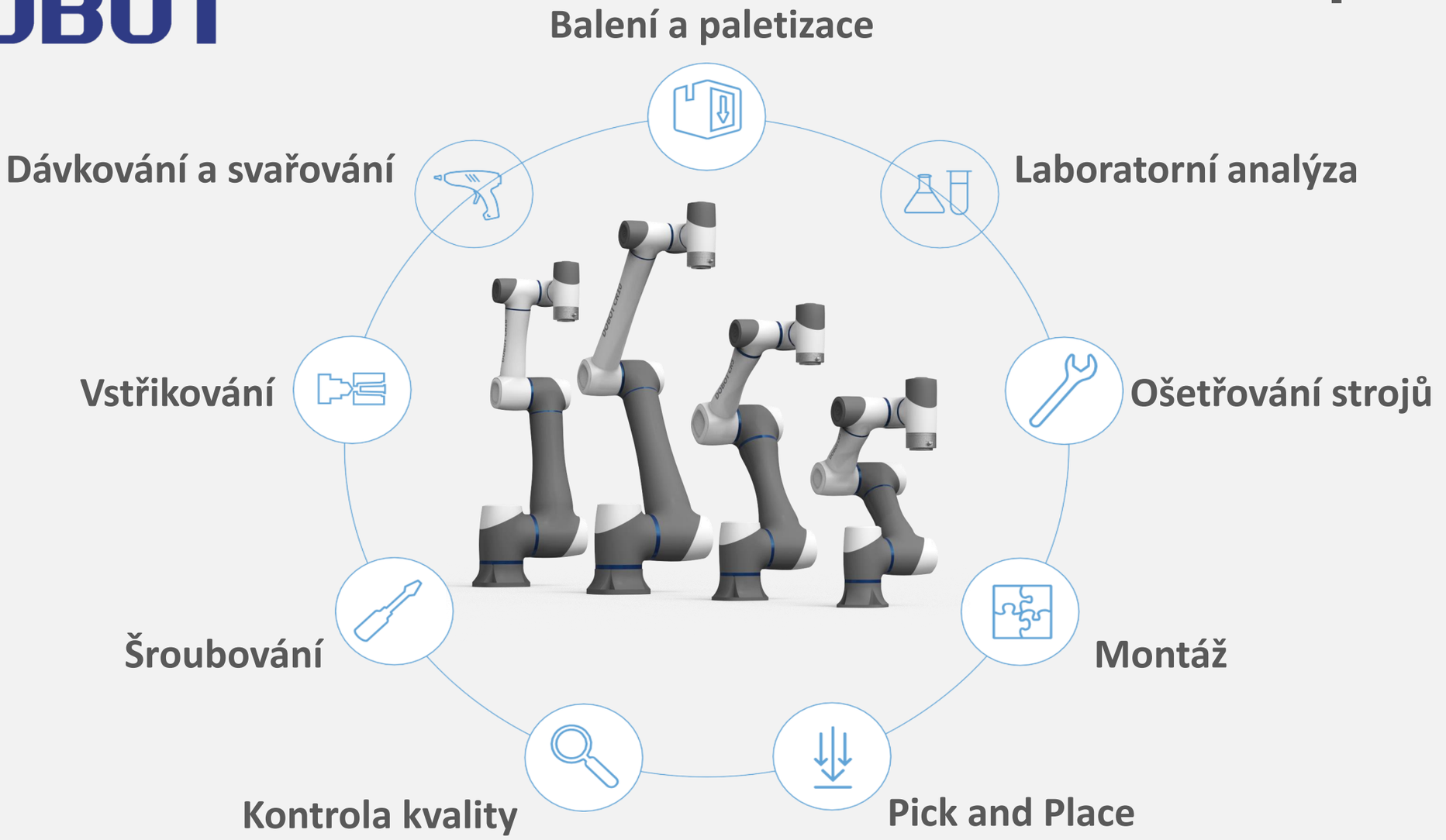
Product Name	 CR3	 CR3L	 CR5	 CR7
Weight	16.5kg	39.5kg	25kg	24.5kg
Rated Payload	3kg	3kg	5kg	7kg
Reach	620mm	1700mm	900mm	800mm
Max. Reach	795mm	1919mm	1096mm	990mm

DOBOT

Product Name	 **CR10**	 **CR12**	 **CR16**
Weight	40kg	39.5kg	40kg
Rated Payload	10kg	12kg	16kg
Reach	1300mm	1200mm	1000mm
Max. Reach	1525mm	1425mm	1223mm

DOBOT

Aplikace



DOBOT

BEZPEČNÝ

- Monitorování v reálném čase každých 10 ms
- Rozsah detekce narušení 15 cm
- Bez kolizí
- Vyhýbání se překážkám

FLEXIBILNÍ

- 20 minut nastavení
- 1 hodina na uvedení do provozu
- Více vstupně-výstupních a komunikačních rozhraní
- Široká kompatibilita s periferními komponentami

JEDNODUCHÝ

- Ruční navádění robotů
- Grafické programování
- Ovládání v systémech Android, iOS a Windows

ODOLNÝ

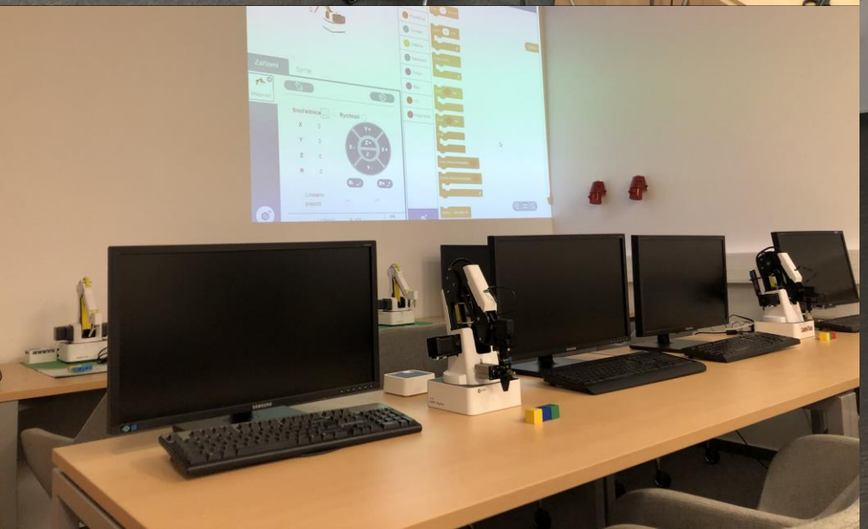
- **30000** hodin životnost
- ISO9001 ISO14001 GB/T29490
- **12-měsíční** záruka

competitive price

2 to 3 times price of Dobot

Brand		Dobot CR5	UR5e	TM5-900	HCR-5
Weight(kg)		23kg	20.6kg	22.6kg	21kg
Payload(kg)		5kg	5kg	4kg	5kg
Reach(mm)		900mm	850mm	900mm	915mm
Repeatability		±0.03mm	±0.03mm	±0.05mm	±0.1mm
Maximum tool speed		3m/s	1m/s	1.4m/s	1m/s
Joints move range	J1	±360	±360	±270	±360
	J2	±360	±360	±180	±360
	J3	±160	±360	±155	±165
	J4	±360	±360	±180	±360
	J5	±360	±360	±180	±360
	J6	±360	±360	±270	±360

DOBOT



DOBOT

DOBOT

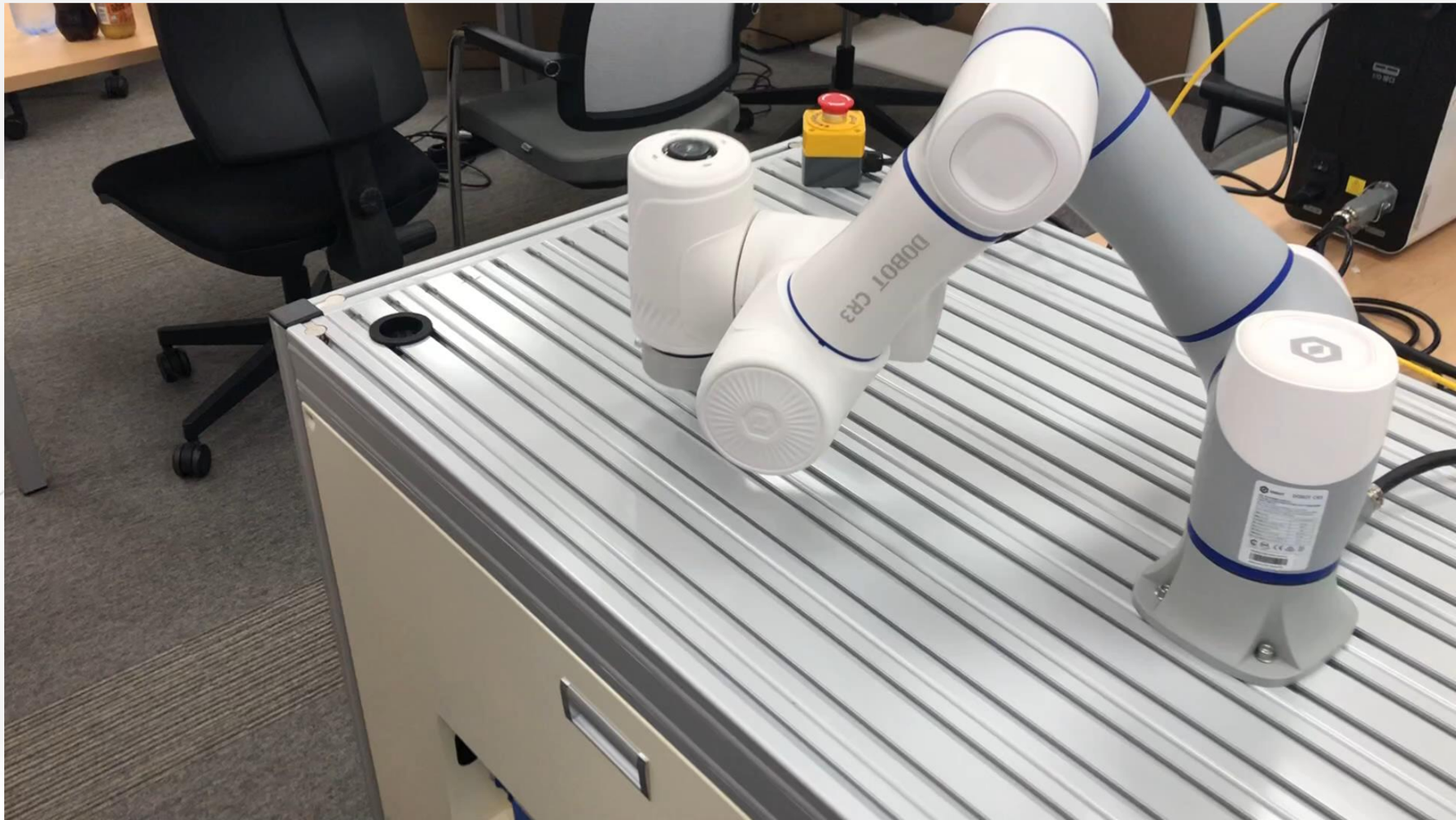
Robot DOBOT CR – SAFE SKIN

PRŮMYSLOVÝ, KOLABORATIVNÍ, DESKTOPOVÝ


```
1  SetSafeSkin(1)
2  SetSafeSkin(0)
3
```

DOBOT

Robot DOBOT CR – SAFE SKIN



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

DOBOT

NEUTRÁCEJTE ZA TEACH PENDANT

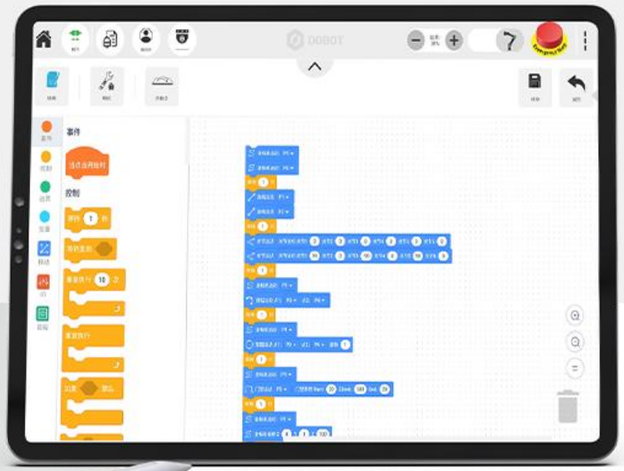
android iOS

POUŽÍVEJTE TABLET

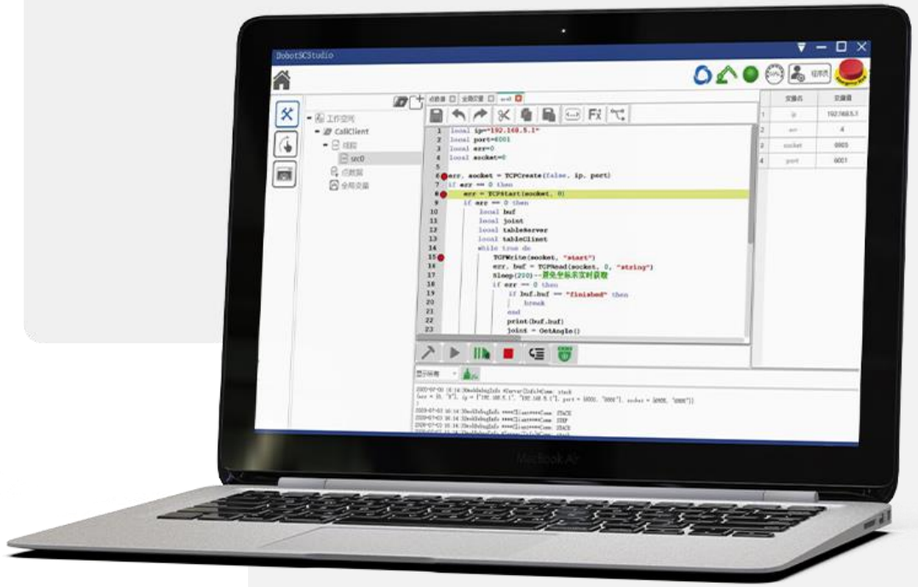
doporučíme Vám tablet, kterým můžete robota ovládat

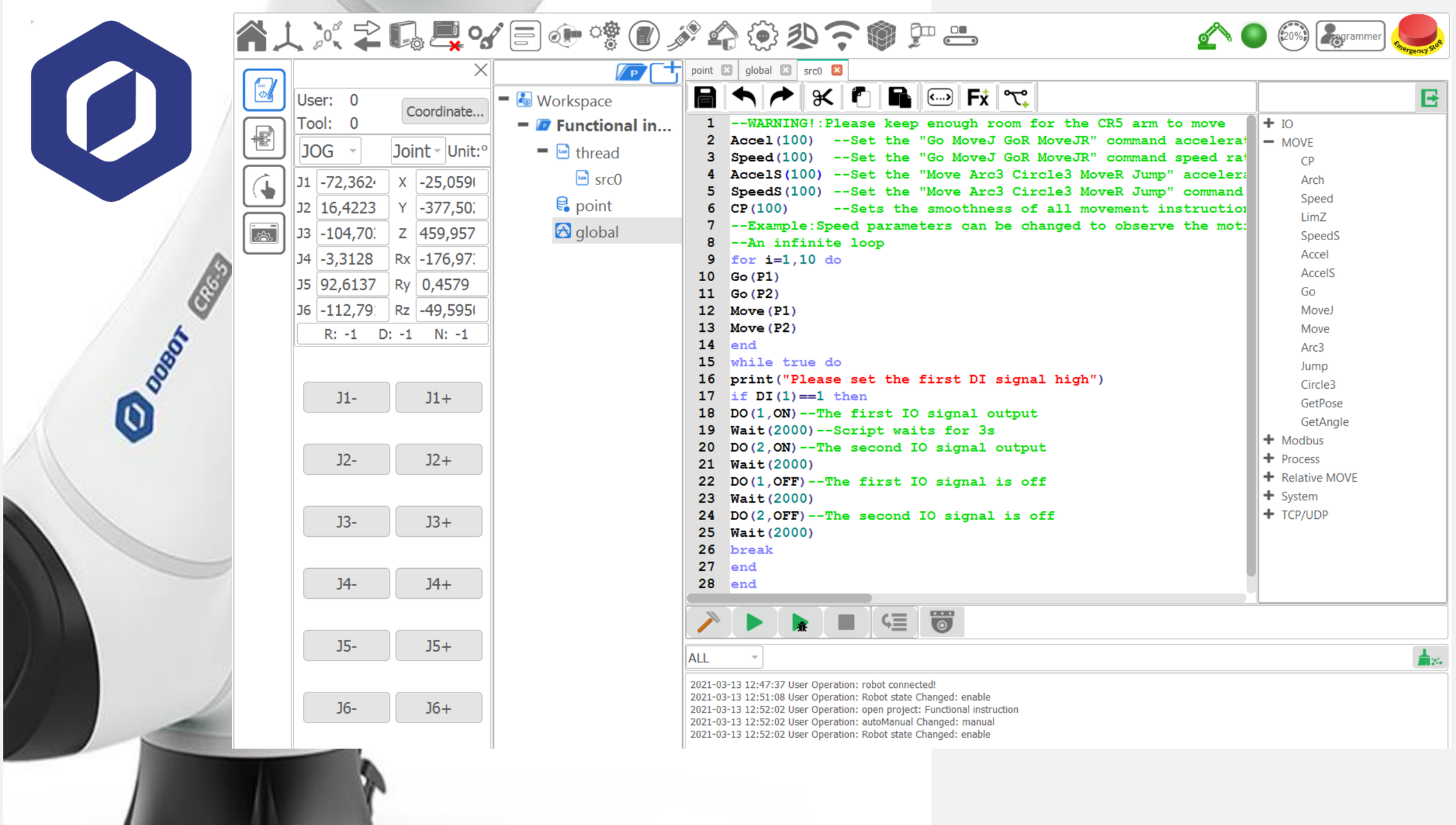
DOBOT

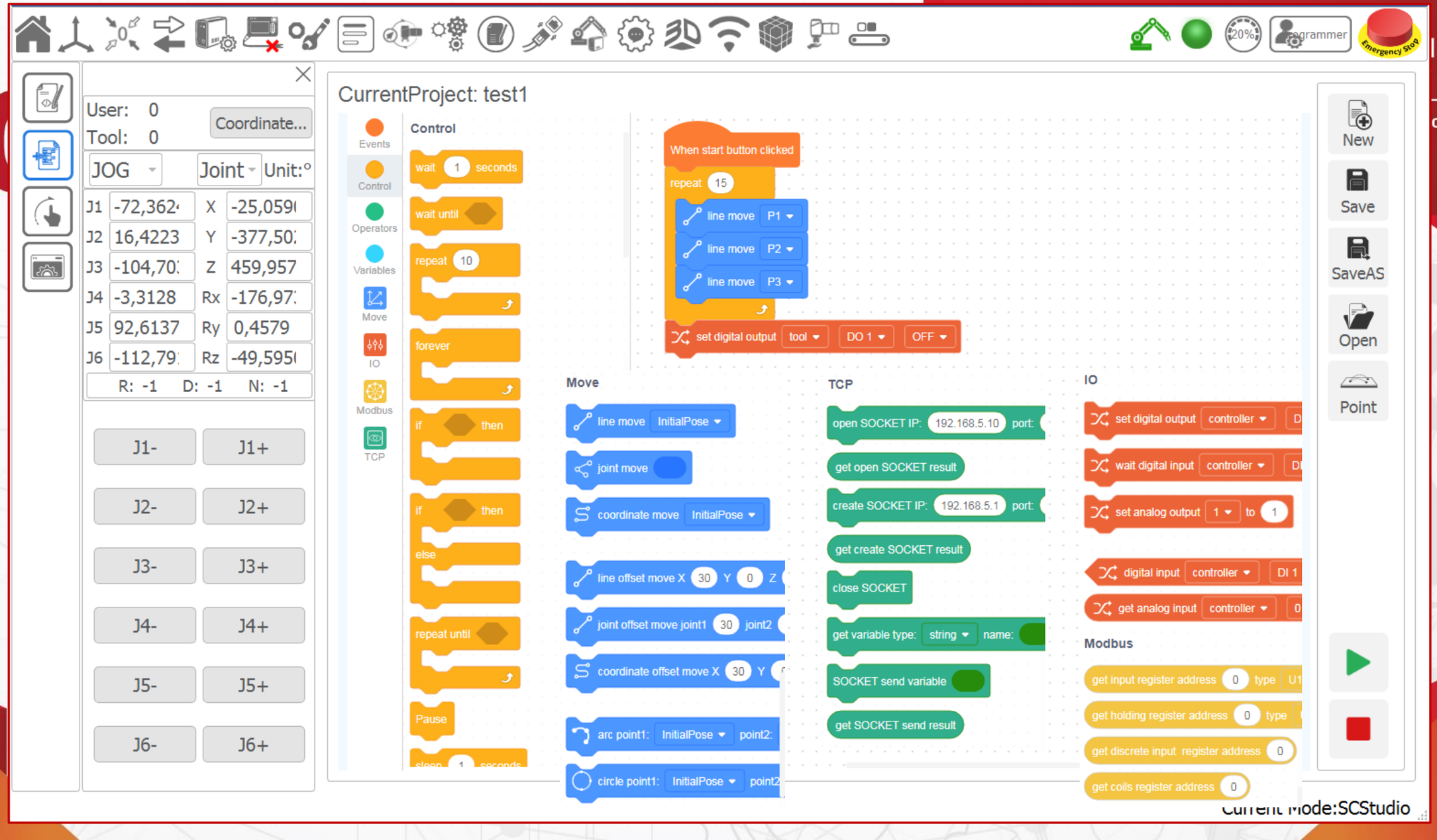
CR Studio



DOBOT SCStudio




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
1 --WARNING!:Please keep enough room for the CR5 arm to move
2 Accel(100) --Set the "Go MoveJ GoR MoveJR" command accelera
3 Speed(100) --Set the "Go MoveJ GoR MoveJR" command speed ra
4 AccelS(100) --Set the "Move Arc3 Circle3 MoveR Jump" acceler
5 SpeedS(100) --Set the "Move Arc3 Circle3 MoveR Jump" command
6 CP(100) --Sets the smoothness of all movement instructio
7 --Example:Speed parameters can be changed to observe the mot
8 --An infinite loop
9 for i=1,10 do
10 Go(P1)
11 Go(P2)
12 Move(P1)
13 Move(P2)
14 end
15 while true do
16 print("Please set the first DI signal high")
17 if DI(1)==1 then
18 DO(1,ON)--The first IO signal output
19 Wait(2000)--Script waits for 3s
20 DO(2,ON)--The second IO signal output
21 Wait(2000)
22 DO(1,OFF)--The first IO signal is off
23 Wait(2000)
24 DO(2,OFF)--The second IO signal is off
25 Wait(2000)
26 break
27 end
28 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


CurrentProject: test1
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+
Events
Control
Operators
Variables
Move
IO
Modbus
TCP
Control
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
Current Mode:SCStudio

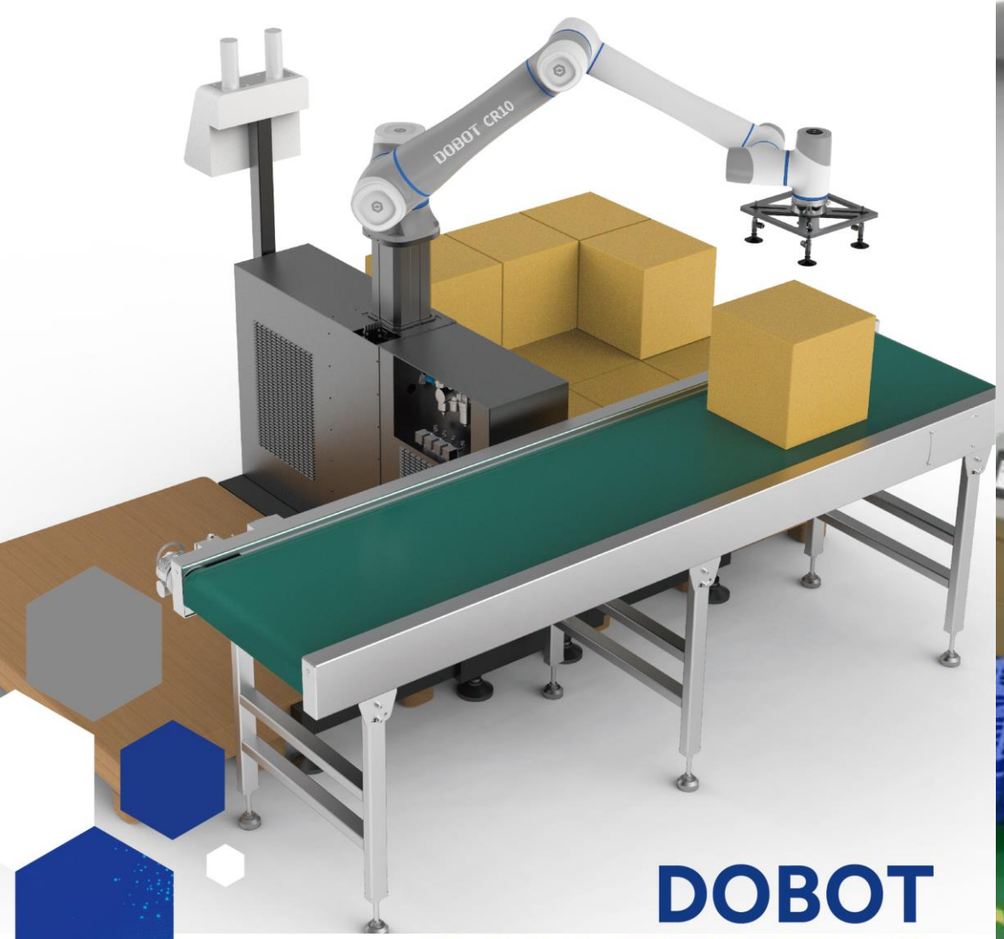
DOBOT

+

C | C++ | C# | Python

ROS | Matlab | LabView | Android

DOBOT



DOBOT PALLETIZING SOLUTION

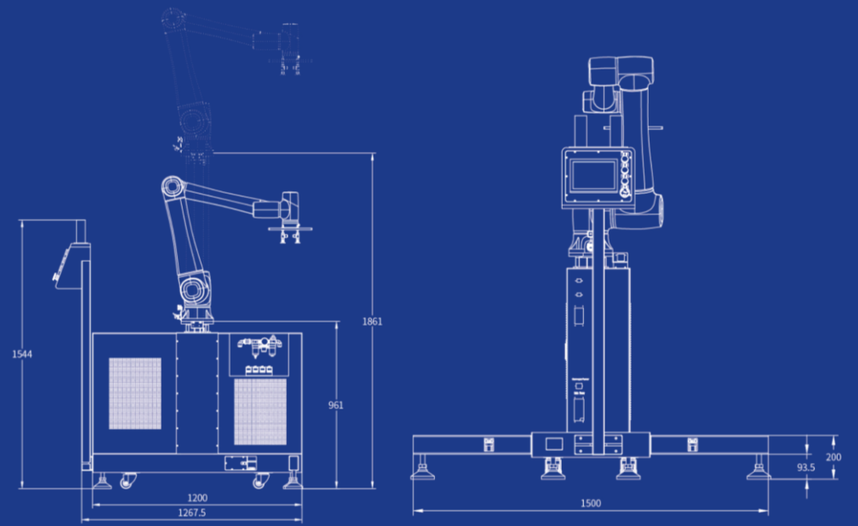
STARTS IN 5 TO 10 MINUTES

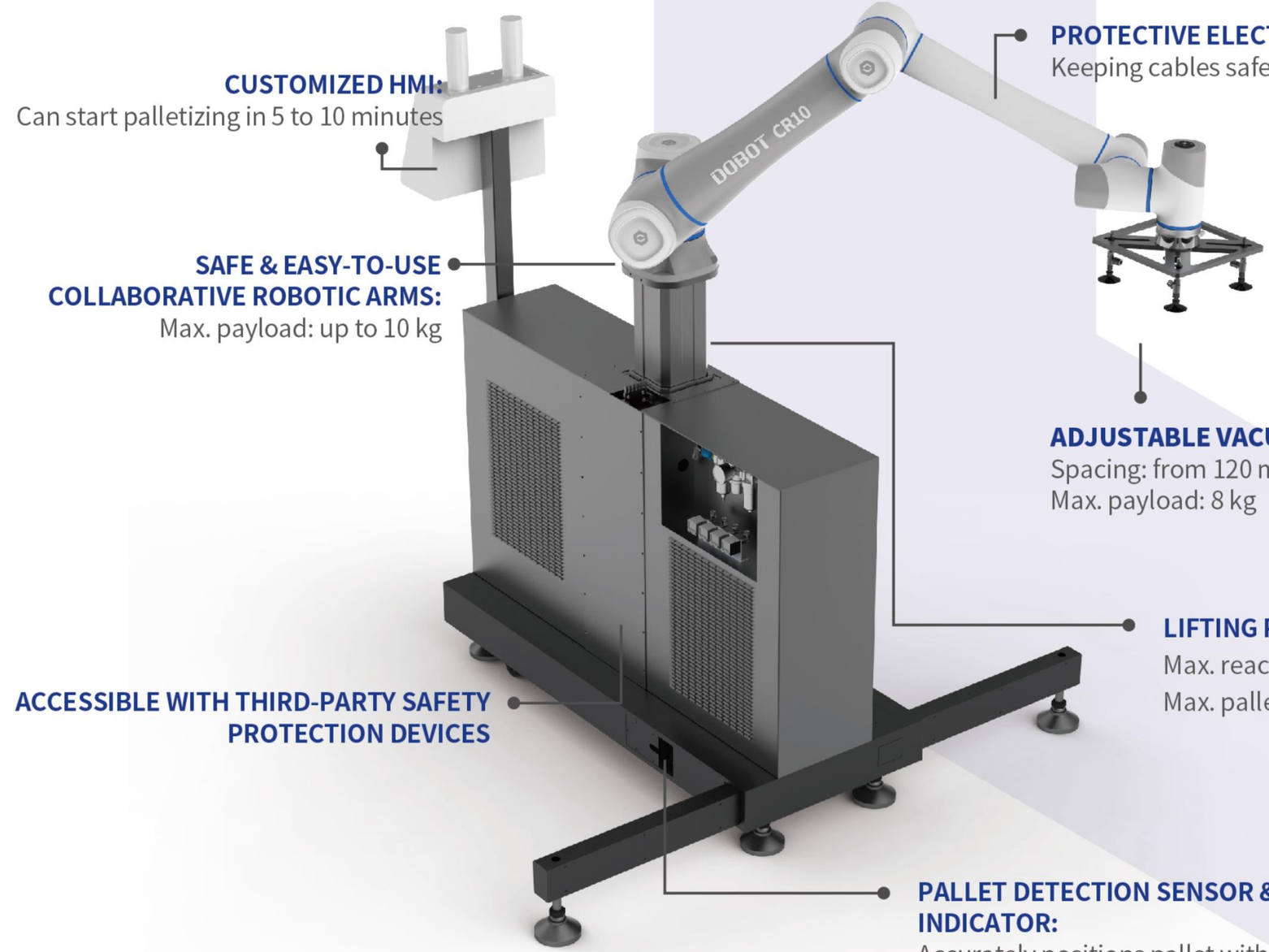
DOBOT Palletizing Solution Specification

Item	Specification
Gripper	Vacuum Suction Cup
Max. Payload	8 kg (CR 10)
Min. Box Dimensions	50 X 50 X 50 mm
Max. Box Dimensions	300 X 300 X 300 mm
Max. Pallet Speed	Up to 7 boxes/object per minute（*1）
Pallet Height	500 mm to 1800 mm（*2）
Max. Pallet Dimensions	1219 mm X 1219 mm
Max. Lifting Pillar Speed	80 mm/s
Device Weight	250 kg
Power Supply	100~240V AC，50/60Hz

(*1:Differences in box size, box layout and gripper might affect actual pallet speed.)
(*2:Differences in the height of the center point of the second axis of the arm from the ground, the size and placement of the box, and different grippers may affect the actual stack height.)

Product Size





CUSTOMIZED HMI:
Can start palletizing in 5 to 10 minutes

SAFE & EASY-TO-USE COLLABORATIVE ROBOTIC ARMS:
Max. payload: up to 10 kg

ACCESSIBLE WITH THIRD-PARTY SAFETY PROTECTION DEVICES

PROTECTIVE ELECTRICAL CONDUIT:
Keeping cables safe up to 3 million twists

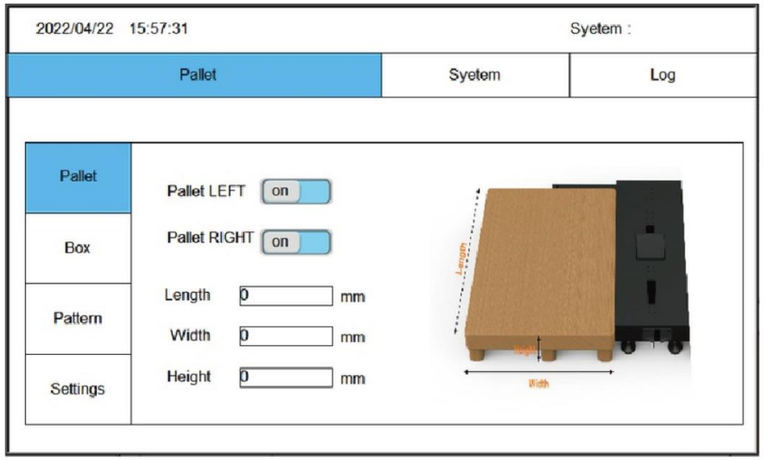
ADJUSTABLE VACUUM SUCTION CUP:
Spacing: from 120 mm to 290 mm
Max. payload: 8 kg

LIFTING PILLAR:
Max. reach: 900 mm
Max. pallet height: 1800 mm

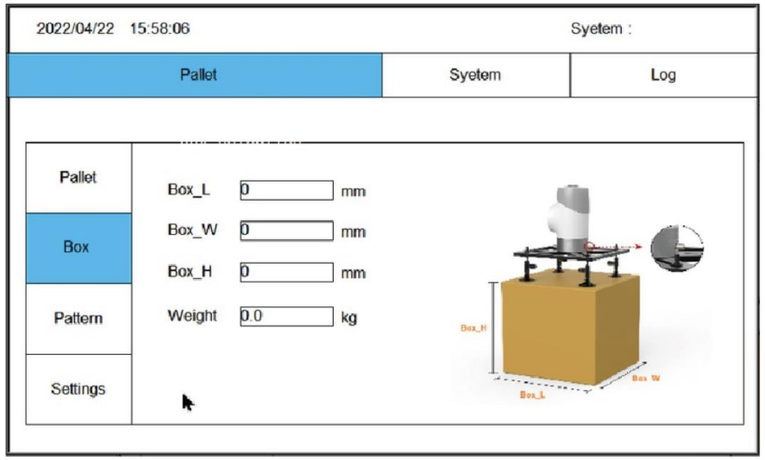
PALLET DETECTION SENSOR & INDICATOR:
Accurately positions pallet within 1 mm

4-Step to Set Up

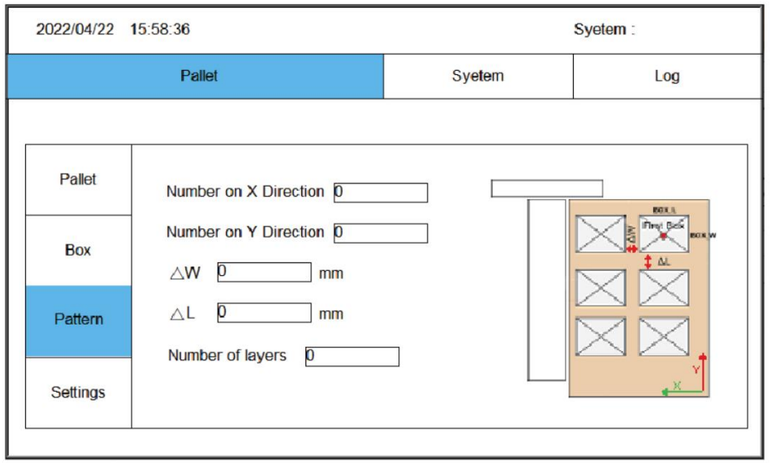
Start to Palletize in 5 to 10 Minutes



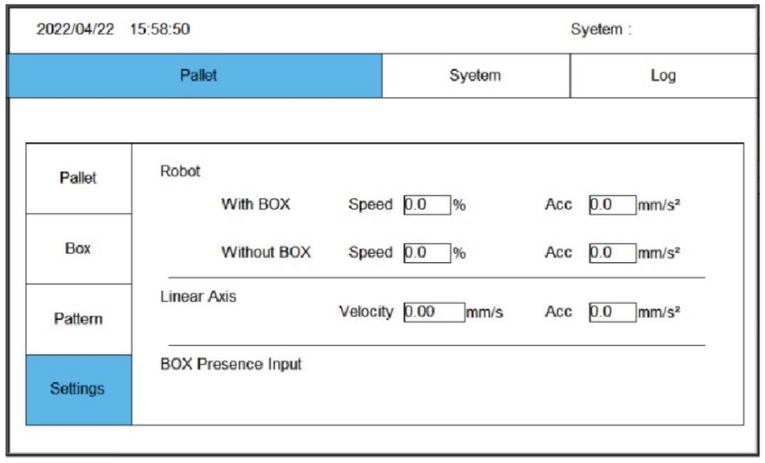
STEP 1： Enter pallet dimensions



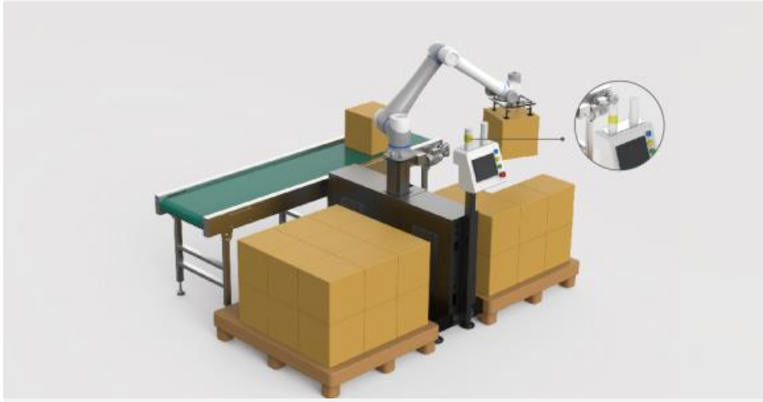
STEP 2： Enter the box dimensions & weight



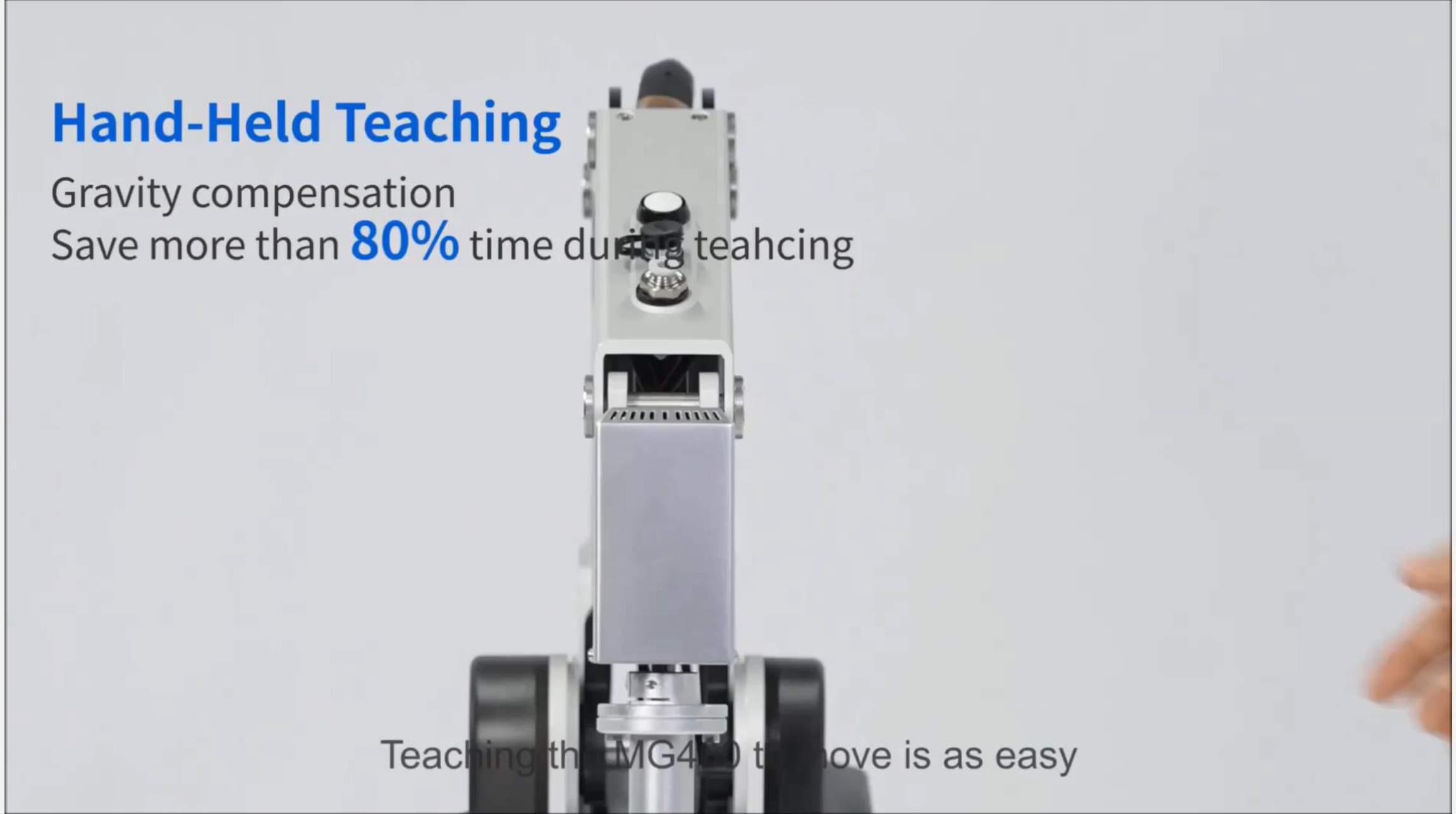
STEP 3： Set pallet pattern

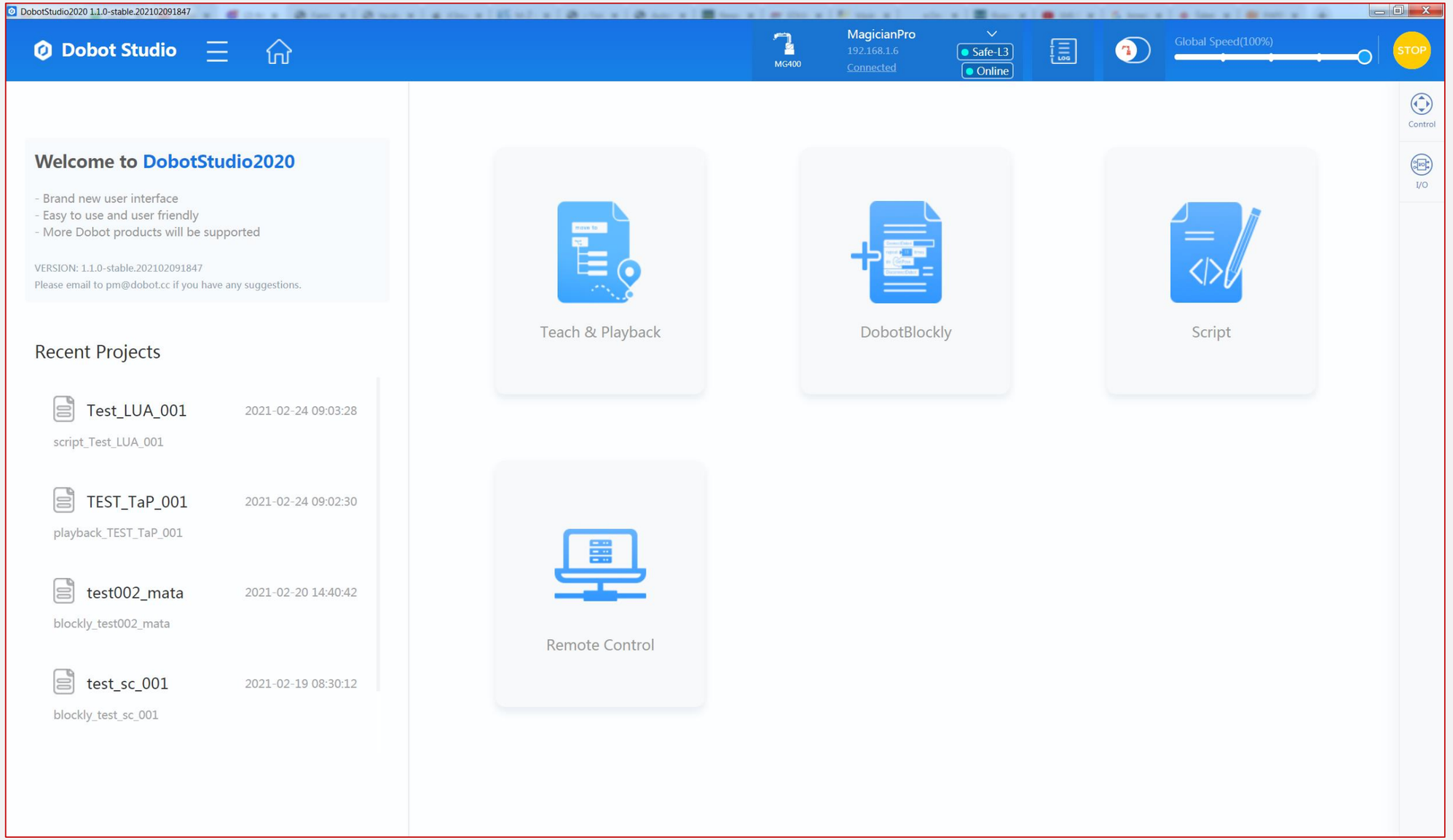


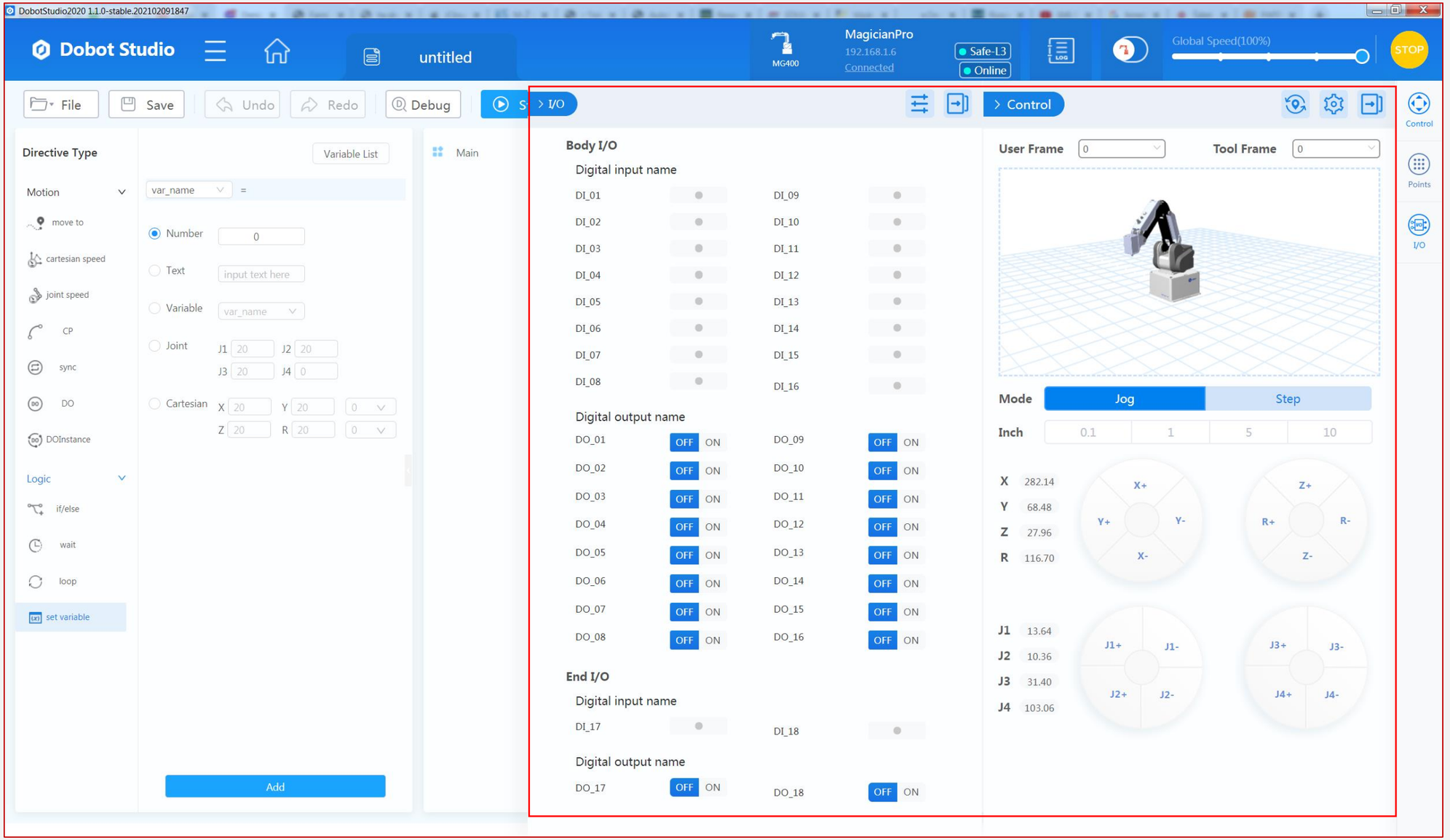
STEP 4： Set movement speed and acceleration

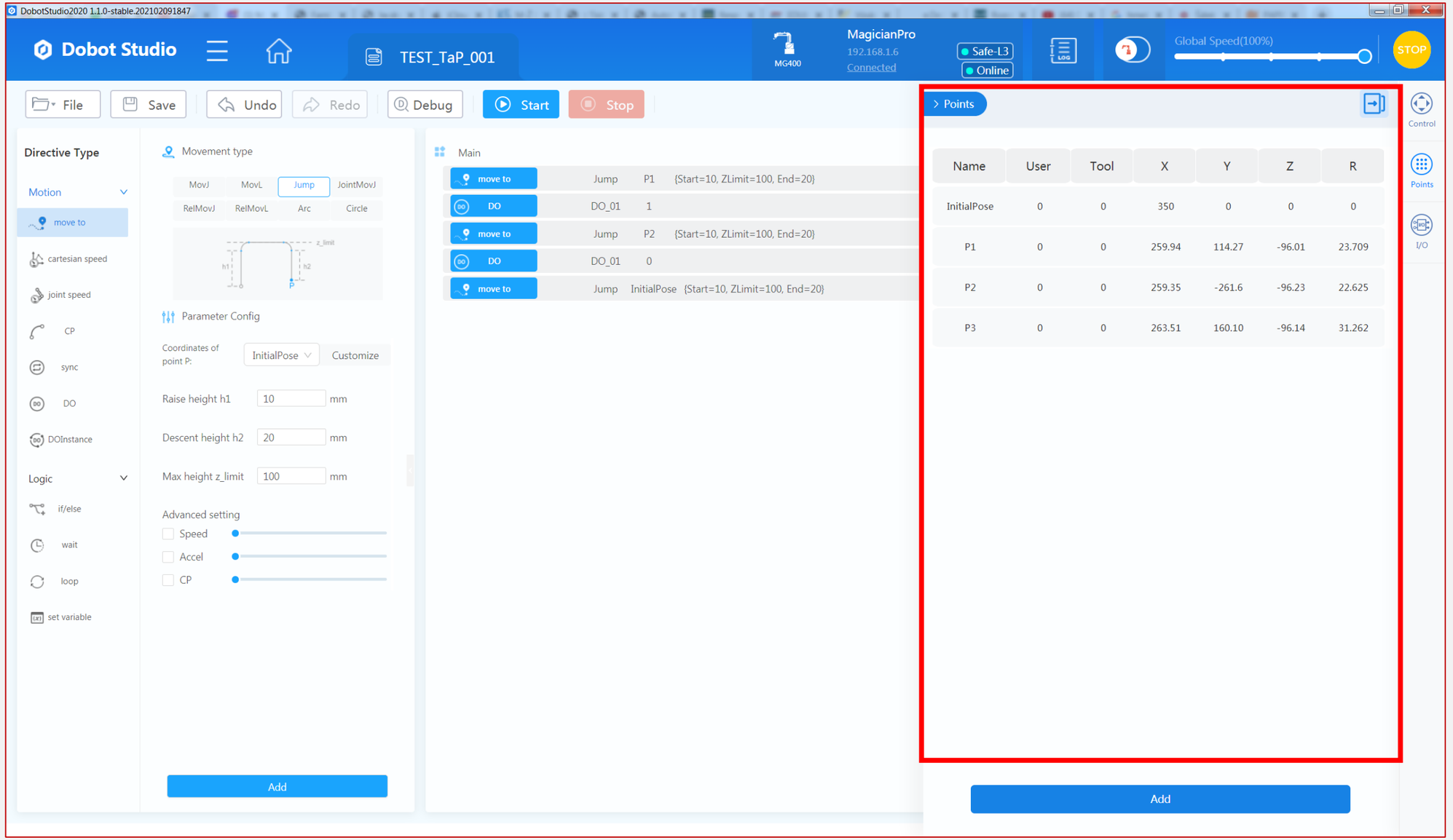


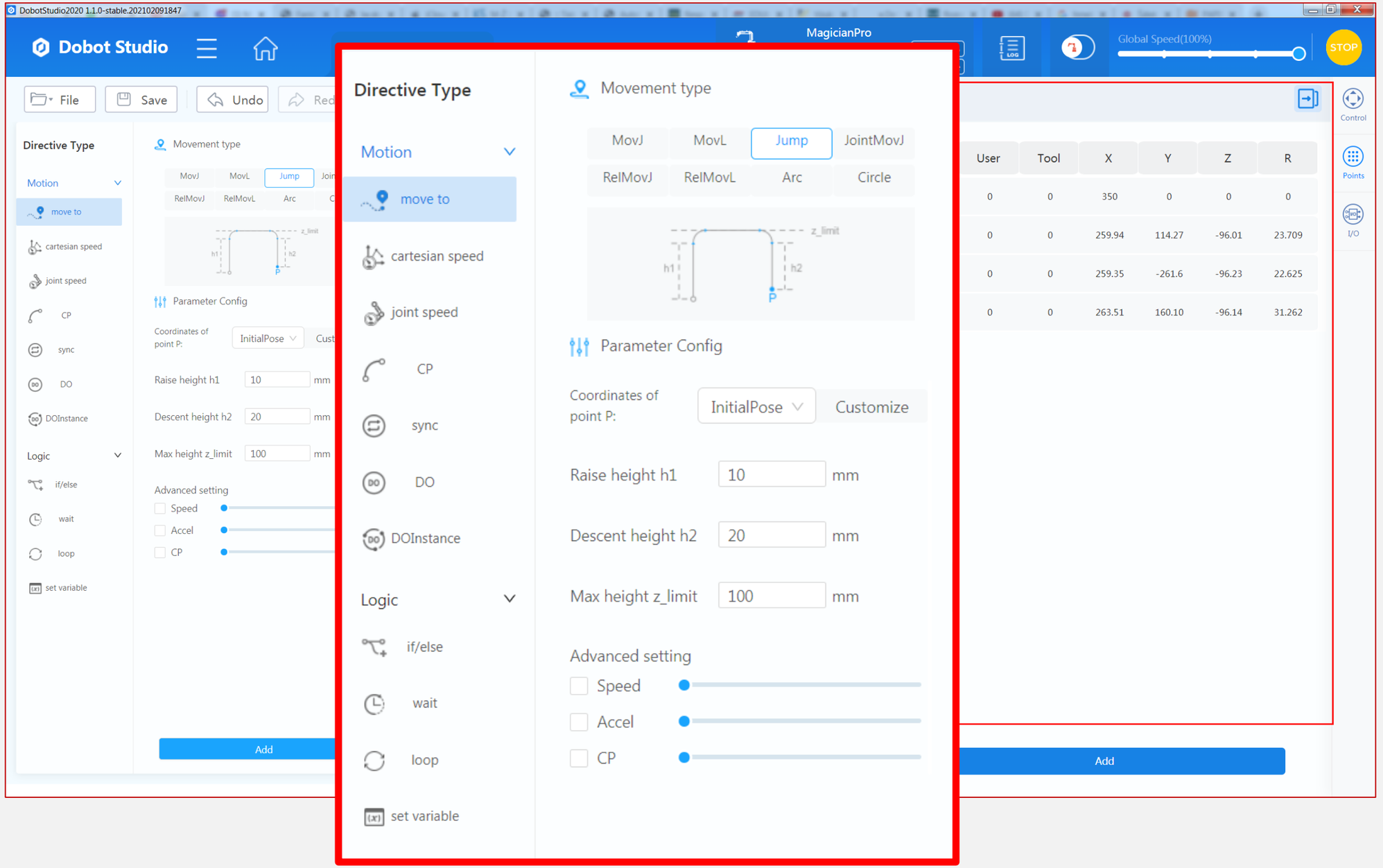

Introducing DOBOT MG400, a desktop collaborative robot


Hand-Held Teaching
Gravity compensation
Save more than 80% time during teahcing
Teaching th MG4 0 t ove is as easy


DobotStudio2020 1.1.0-stable.202102091847
Dobot Studio
MG400
MagicianPro
192.168.1.6
Connected
Safe-L3
Online
Global Speed(100%)
STOP
Control
I/O
Welcome to DobotStudio2020
- Brand new user interface
- Easy to use and user friendly
- More Dobot products will be supported
VERSION: 1.1.0-stable.202102091847
Please email to pm@dobot.cc if you have any suggestions.
Recent Projects
Test_LUA_001
2021-02-24 09:03:28
script_Test_LUA_001
TEST_TaP_001
2021-02-24 09:02:30
playback_TEST_TaP_001
test002_mata
2021-02-20 14:40:42
blockly_test002_mata
test_sc_001
2021-02-19 08:30:12
blockly_test_sc_001
Teach & Playback
DobotBlockly
Script
Remote Control


DobotStudio2020 1.1.0-stable.202102091847
Dobot Studio
untitled
MG400
MagicianPro
192.168.1.6
Connected
Safe-L3
Online
Global Speed(100%)
STOP
File
Save
Undo
Redo
Debug
I/O
Control
Directive Type
Motion
move to
cartesian speed
joint speed
CP
sync
DO
DOInstance
Logic
if/else
wait
loop
set variable
Variable List
var_name
Number
Text
Variable
Joint
Cartesian
Add
Main
Body I/O
Digital input name
Digital output name
End I/O
User Frame
Tool Frame
Mode
Jog
Step
Inch
X
Y
Z
R
J1
J2
J3
J4
Points


DobotStudio2020 1.1.0-stable.202102091847
Dobot Studio
TEST_TaP_001
MG400
MagicianPro
192.168.1.6
Connected
Safe-L3
Online
Global Speed(100%)
STOP
File
Save
Undo
Redo
Debug
Start
Stop
Directive Type
Motion
move to
cartesian speed
joint speed
CP
sync
DO
DOInstance
Logic
if/else
wait
loop
set variable
Movement type
MovJ
MovL
Jump
JointMovJ
RelMovJ
RelMovL
Arc
Circle
Parameter Config
Coordinates of point P:
InitialPose
Customize
Raise height h1
10
mm
Descent height h2
20
mm
Max height z_limit
100
mm
Advanced setting
Speed
Accel
CP
Add
Main
move to Jump P1 {Start=10, ZLimit=100, End=20}
DO DO_01 1
move to Jump P2 {Start=10, ZLimit=100, End=20}
DO DO_01 0
move to Jump InitialPose {Start=10, ZLimit=100, End=20}
Points
Name User Tool X Y Z R
InitialPose 0 0 350 0 0 0
P1 0 0 259.94 114.27 -96.01 23.709
P2 0 0 259.35 -261.6 -96.23 22.625
P3 0 0 263.51 160.10 -96.14 31.262
Add
Control
Points
I/O


DobotStudio2020 1.1.0-stable.202102091847
Dobot Studio
MagicianPro
Global Speed(100%)
STOP
File
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Motion
move to
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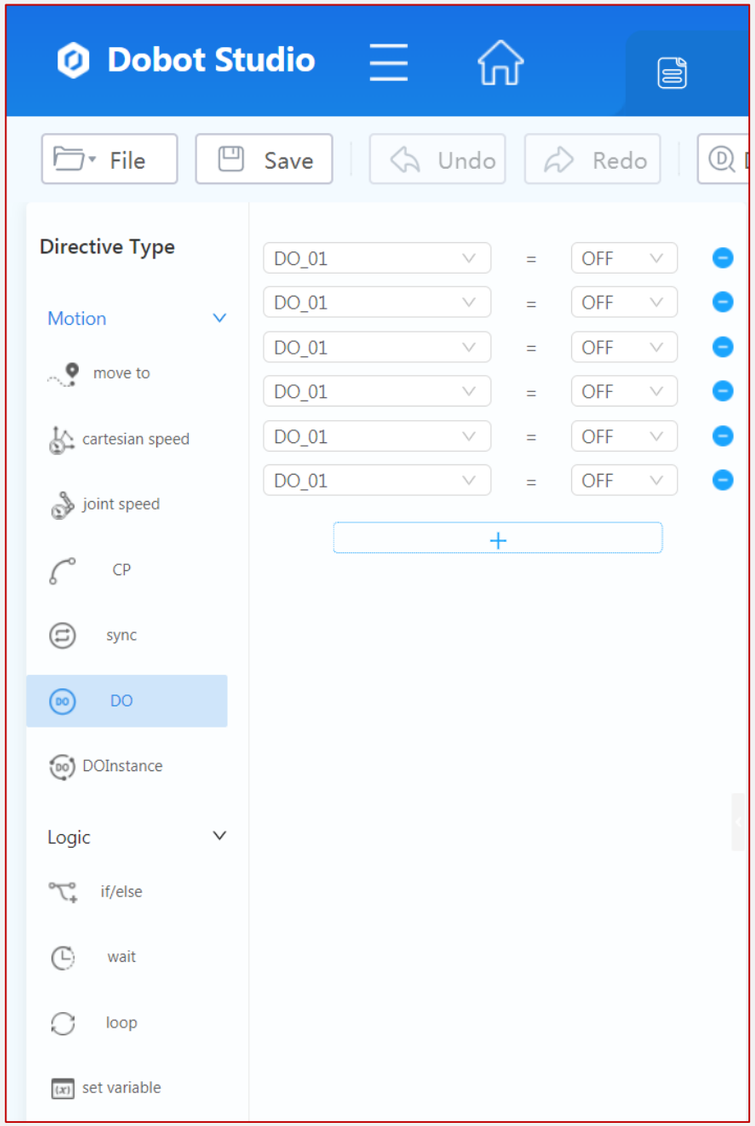
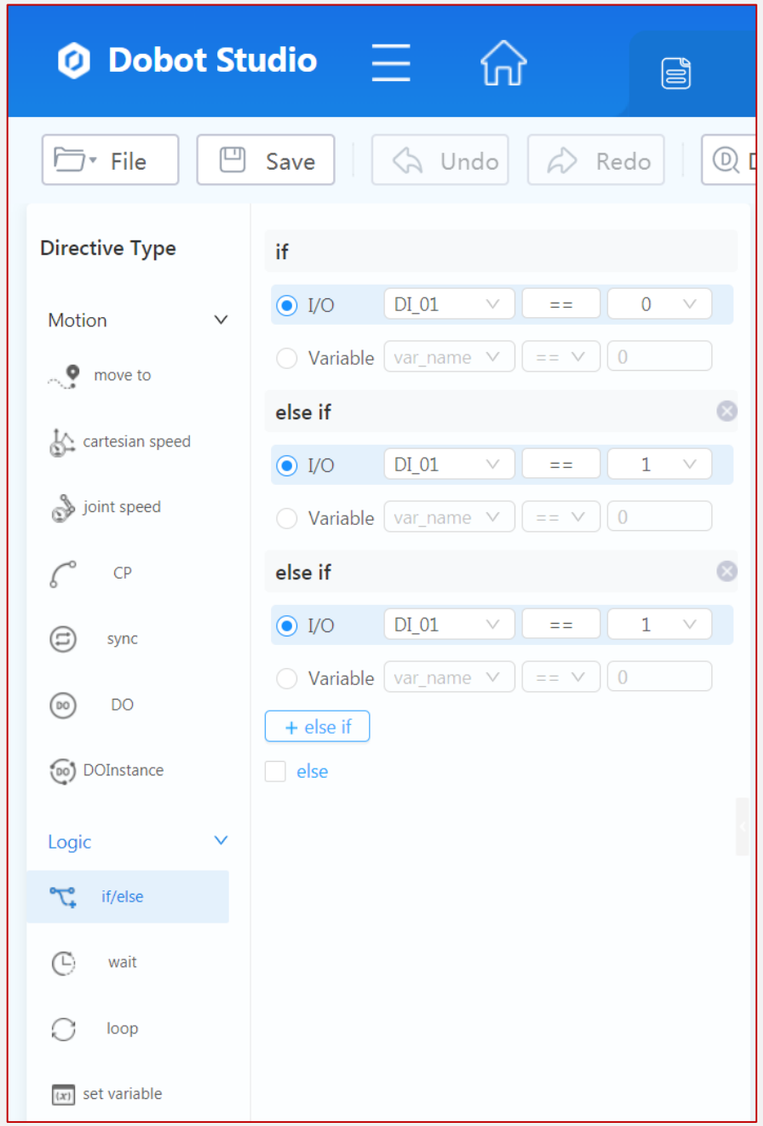
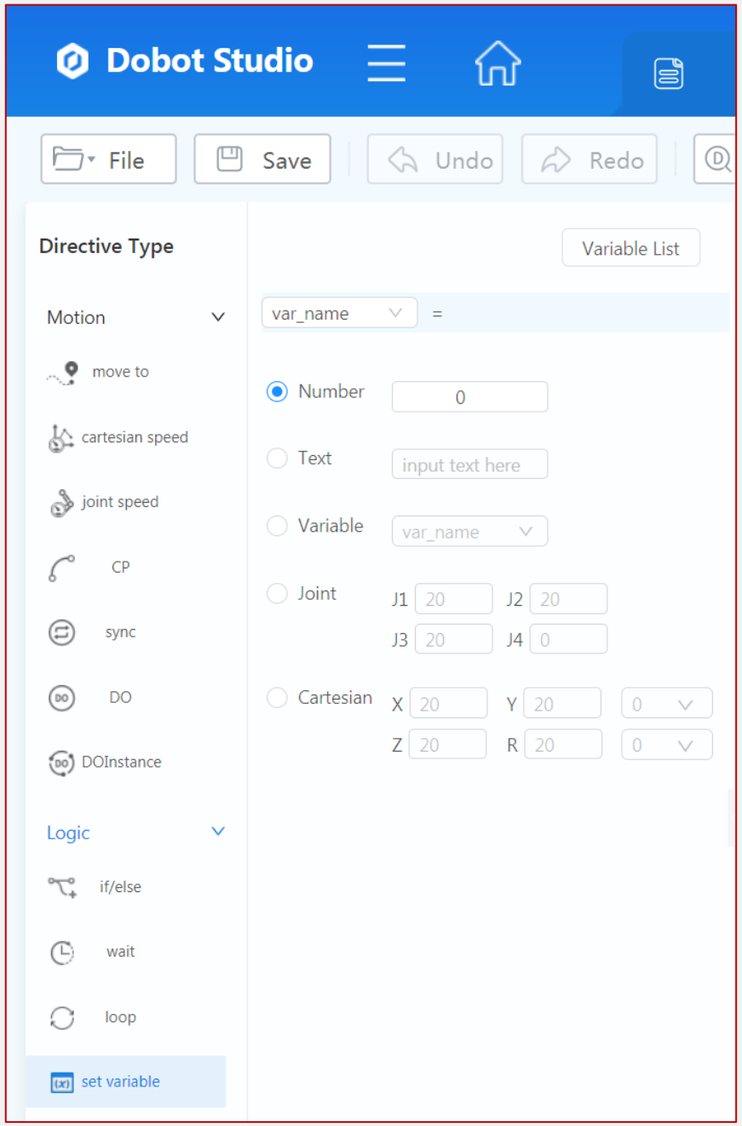
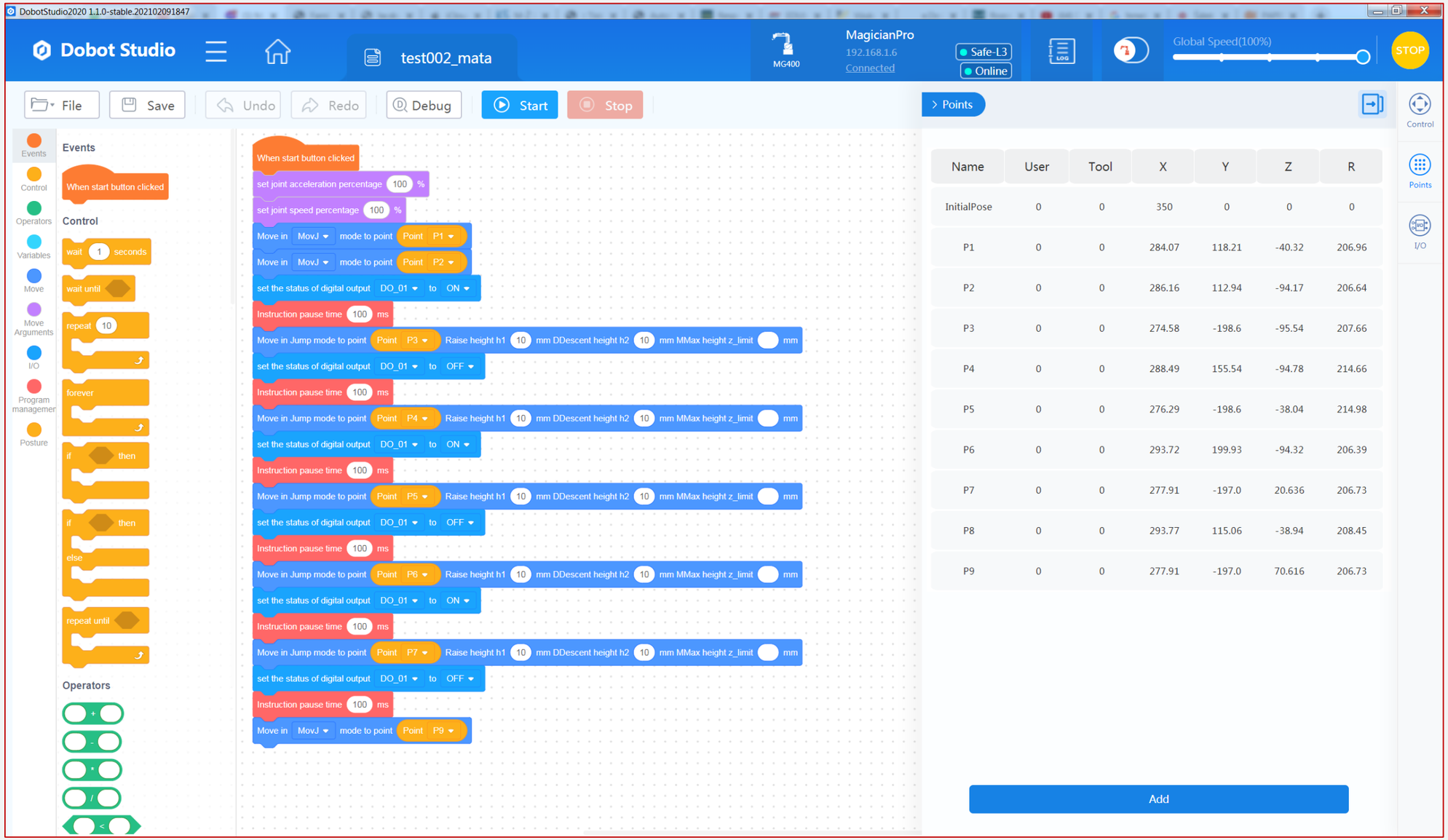
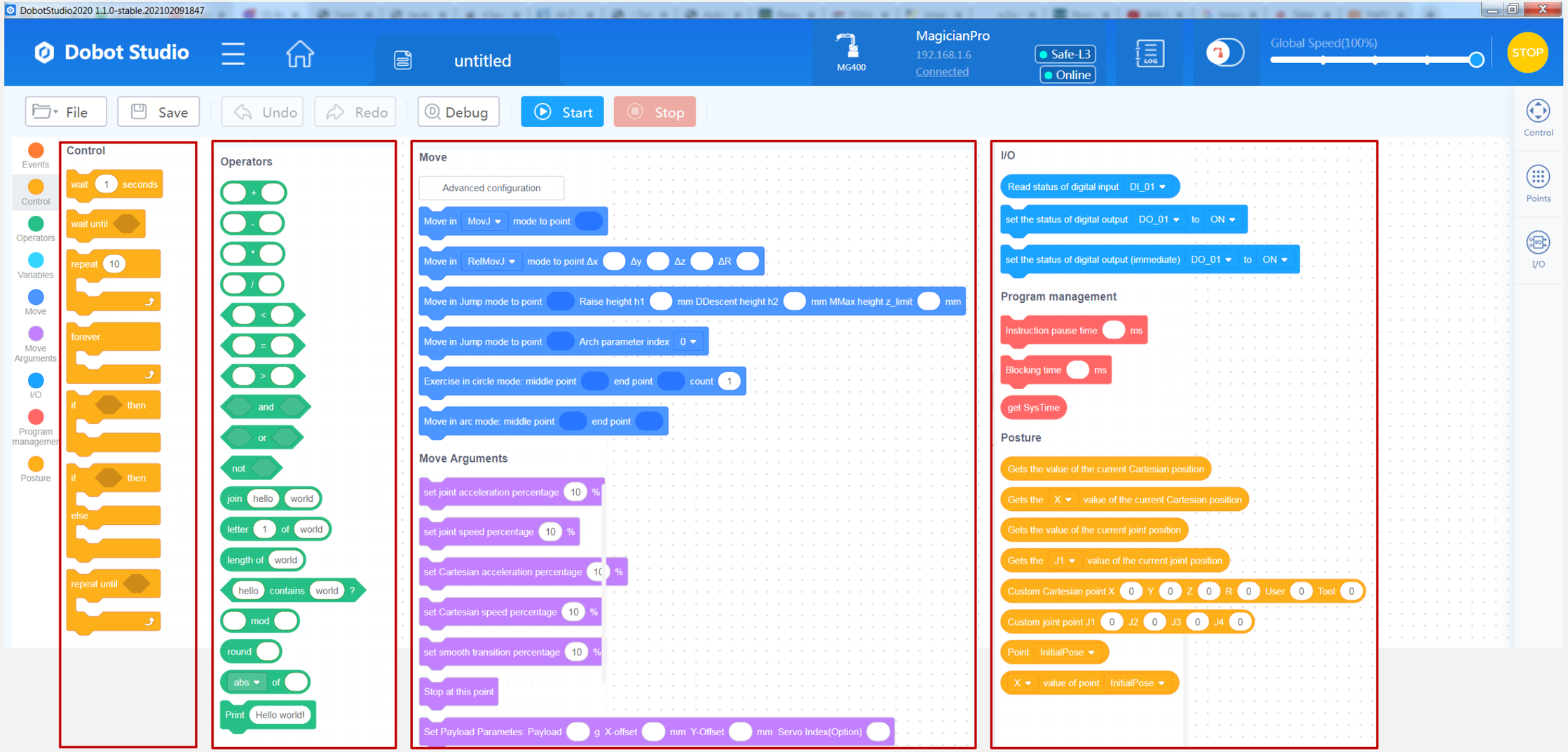
joint speed
CP
sync
DO
DOInstance
Logic
if/else
wait
loop
set variable
Movement type
MovJ
MovL
Jump
JointMovJ
RelMovJ
RelMovL
Arc
Circle
z_limit
h1
h2
P
Parameter Config
Coordinates of point P:
InitialPose
Customize
Raise height h1
10
mm
Descent height h2
20
mm
Max height z_limit
100
mm
Advanced setting
Speed
Accel
CP
Add
User
Tool
X
Y
Z
R
0
0
350
0
0
0
0
0
259.94
114.27
-96.01
23.709
0
0
259.35
-261.6
-96.23
22.625
0
0
263.51
160.10
-96.14
31.262
Control
Points
I/O

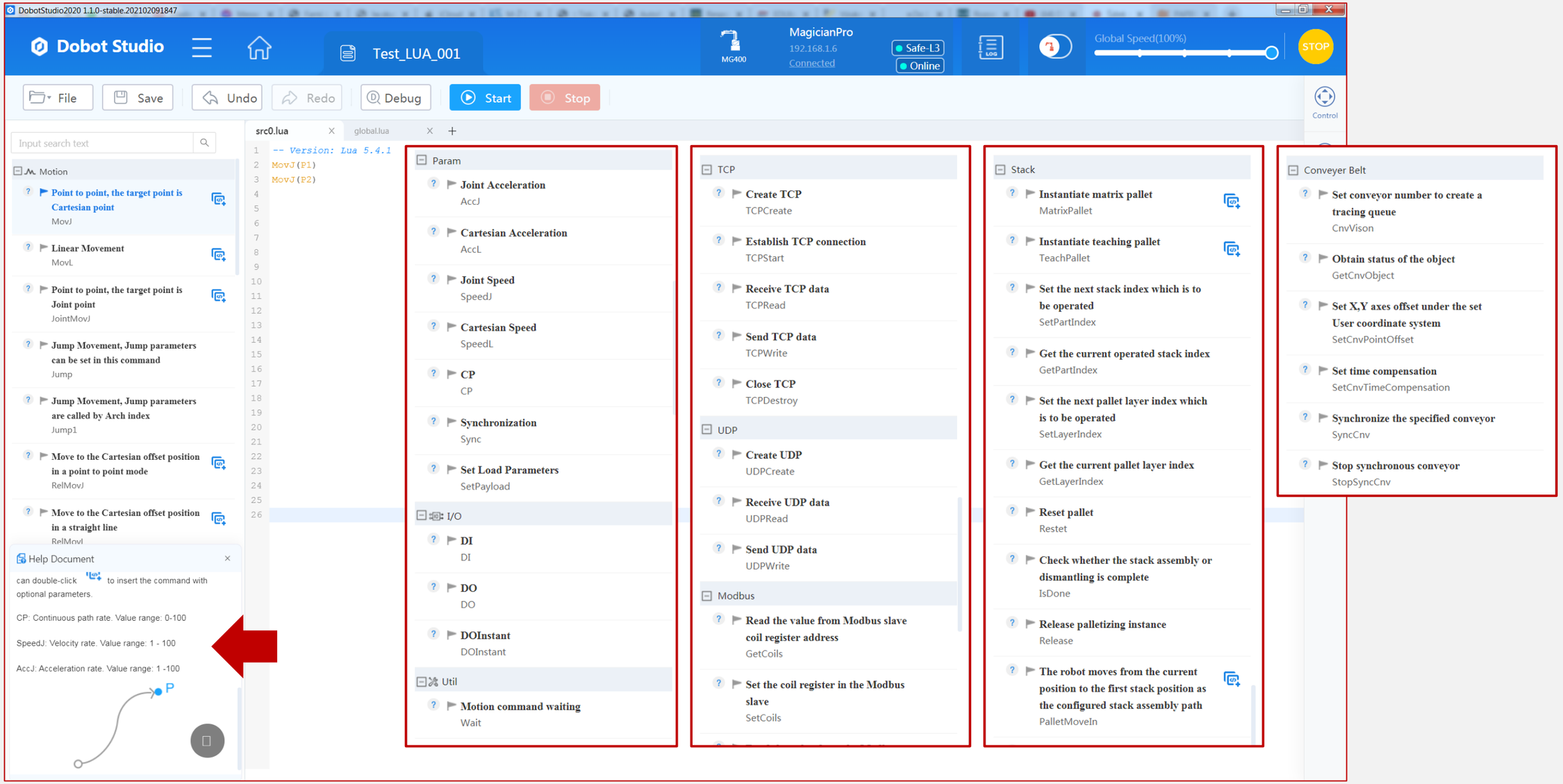

Dobot Studio
File
Save
Undo
Redo
Directive Type
Motion
move to
cartesian speed
joint speed
CP
sync
DO
DOInstance
Logic
if/else
wait
loop
set variable
DO_01 = OFF
DO_01 = OFF
DO_01 = OFF
DO_01 = OFF
DO_01 = OFF
DO_01 = OFF
+

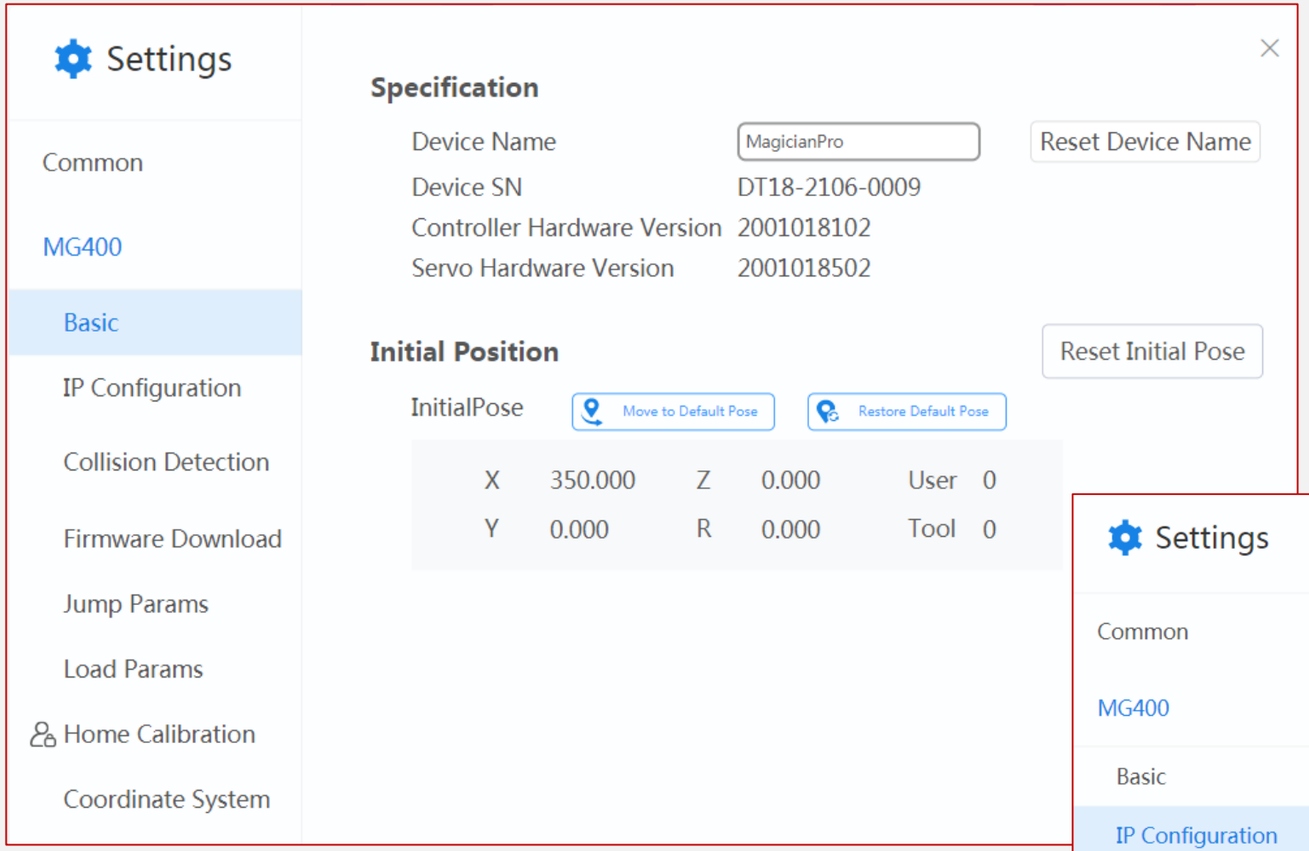

Dobot Studio
File
Save
Undo
Redo
Directive Type
Motion
move to
cartesian speed
joint speed
CP
sync
DO
DOInstance
Logic
if/else
wait
loop
set variable
if
I/O DI_01 == 0
Variable var_name == 0
else if
I/O DI_01 == 1
Variable var_name == 0
else if
I/O DI_01 == 1
Variable var_name == 0
+ else if
else

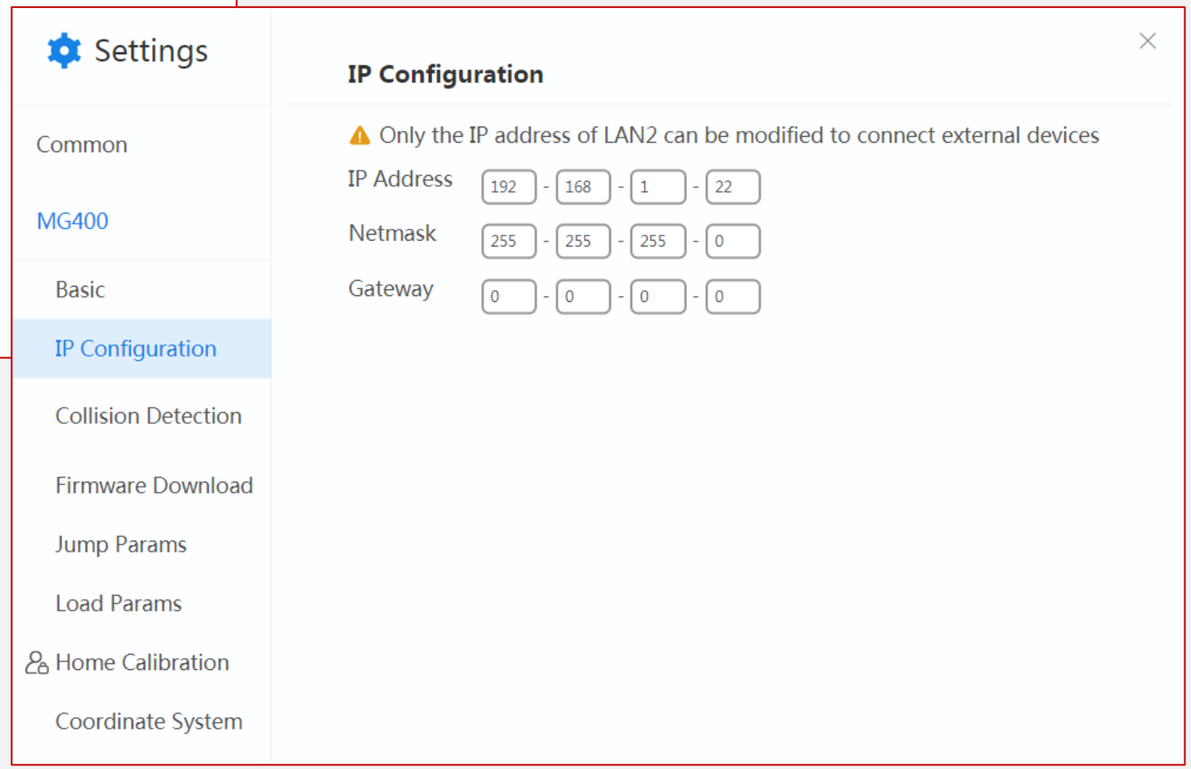

Dobot Studio
File
Save
Undo
Redo
Directive Type
Motion
move to
cartesian speed
joint speed
CP
sync
DO
DOInstance
Logic
if/else
wait
loop
set variable
Variable List
var_name =
Number 0
Text input text here
Variable var_name
Joint J1 20 J2 20 J3 20 J4 0
Cartesian X 20 Y 20 0 Z 20 R 20 0

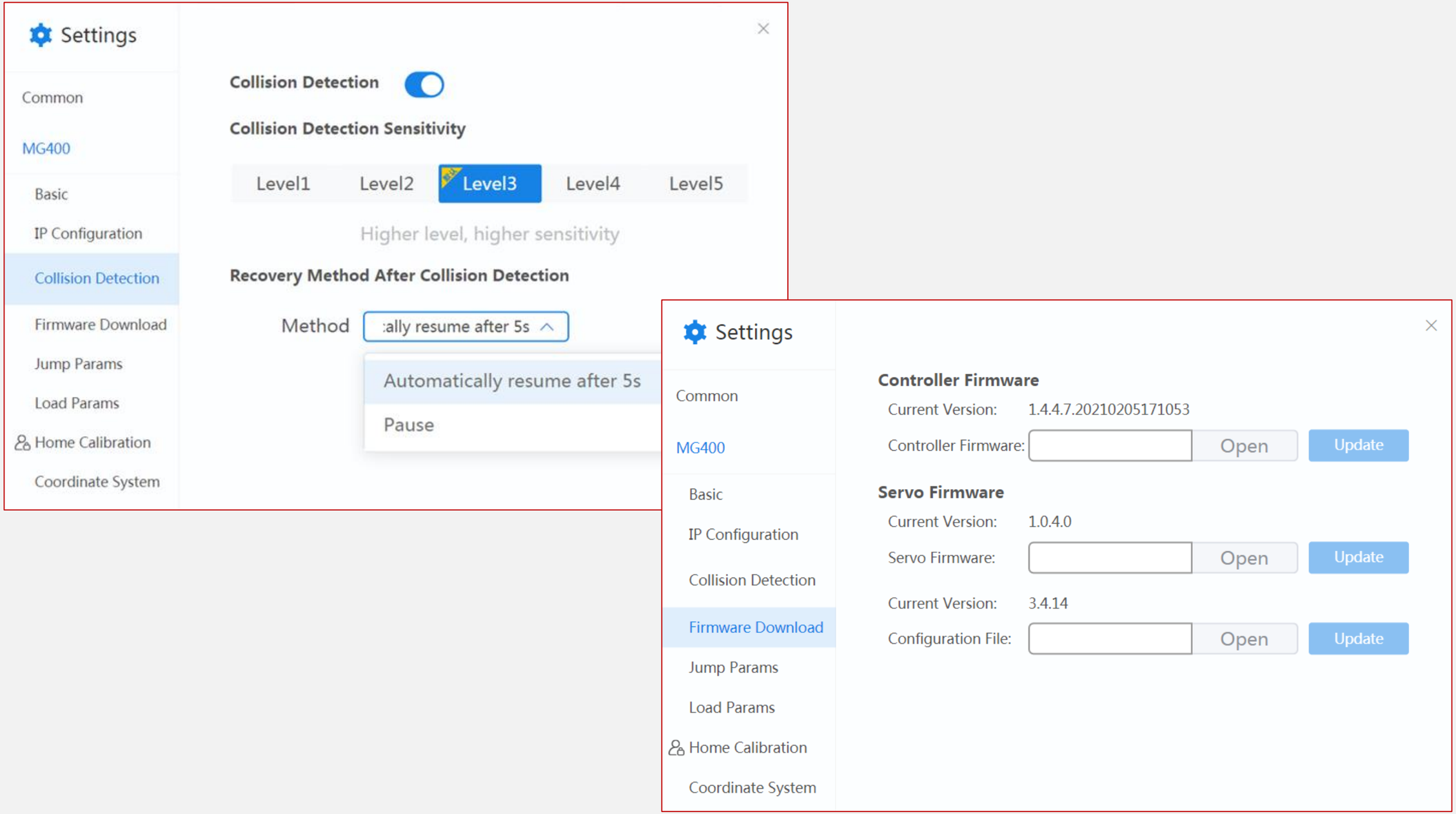

DobotStudio2020 1.1.0-stable.202102091847
Dobot Studio
test002_mata
MG400
MagicianPro
192.168.1.6
Connected
Safe-L3
Online
Global Speed(100%)
STOP
File
Save
Undo
Redo
Debug
Start
Stop
Points
Control
Points
I/O
Events
Control
Operators
Variables
Move
Move Arguments
I/O
Program management
Posture
Events
When start button clicked
Control
wait 1 seconds
wait until
repeat 10
forever
if then
if then else
repeat until
Operators
When start button clicked
set joint acceleration percentage 100 %
set joint speed percentage 100 %
Move in MovJ mode to point Point P1
Move in MovJ mode to point Point P2
set the status of digital output DO_01 to ON
Instruction pause time 100 ms
Move in Jump mode to point Point P3 Raise height h1 10 mm DDescent height h2 10 mm MMax height z_limit mm
set the status of digital output DO_01 to OFF
Instruction pause time 100 ms
Move in Jump mode to point Point P4 Raise height h1 10 mm DDescent height h2 10 mm MMax height z_limit mm
set the status of digital output DO_01 to ON
Instruction pause time 100 ms
Move in Jump mode to point Point P5 Raise height h1 10 mm DDescent height h2 10 mm MMax height z_limit mm
set the status of digital output DO_01 to OFF
Instruction pause time 100 ms
Move in Jump mode to point Point P6 Raise height h1 10 mm DDescent height h2 10 mm MMax height z_limit mm
set the status of digital output DO_01 to ON
Instruction pause time 100 ms
Move in Jump mode to point Point P7 Raise height h1 10 mm DDescent height h2 10 mm MMax height z_limit mm
set the status of digital output DO_01 to OFF
Instruction pause time 100 ms
Move in MovJ mode to point Point P9
Name User Tool X Y Z R
InitialPose 0 0 350 0 0 0
P1 0 0 284.07 118.21 -40.32 206.96
P2 0 0 286.16 112.94 -94.17 206.64
P3 0 0 274.58 -198.6 -95.54 207.66
P4 0 0 288.49 155.54 -94.78 214.66
P5 0 0 276.29 -198.6 -38.04 214.98
P6 0 0 293.72 199.93 -94.32 206.39
P7 0 0 277.91 -197.0 20.636 206.73
P8 0 0 293.77 115.06 -38.94 208.45
P9 0 0 277.91 -197.0 70.616 206.73
Add


DobotStudio2020 1.1.0-stable.202102091847
Dobot Studio
untitled
MG400
MagicianPro
192.168.1.6
Connected
Safe-L3
Online
Global Speed(100%)
STOP
File
Save
Undo
Redo
Debug
Start
Stop
Events
Control
Operators
Variables
Move
Move Arguments
I/O
Program management
Posture
Control
wait 1 seconds
wait until
repeat 10
forever
if then
if then else
repeat until
Operators
+
-
*
/
<
=
>
and
or
not
join hello world
letter 1 of world
length of world
hello contains world ?
mod
round
abs of
Print Hello world!
Move
Advanced configuration
Move in MovJ mode to point
Move in RelMovJ mode to point Δx Δy Δz ΔR
Move in Jump mode to point Raise height h1 mm DDescent height h2 mm MMax height z_limit mm
Move in Jump mode to point Arch parameter index 0
Exercise in circle mode: middle point end point count 1
Move in arc mode: middle point end point
Move Arguments
set joint acceleration percentage 10 %
set joint speed percentage 10 %
set Cartesian acceleration percentage 10 %
set Cartesian speed percentage 10 %
set smooth transition percentage 10 %
Stop at this point
Set Payload Parametes: Payload g X-offset mm Y-Offset mm Servo Index(Option)
I/O
Read status of digital input DI_01
set the status of digital output DO_01 to ON
set the status of digital output (immediate) DO_01 to ON
Program management
Instruction pause time ms
Blocking time ms
get SysTime
Posture
Gets the value of the current Cartesian position
Gets the X value of the current Cartesian position
Gets the value of the current joint position
Gets the J1 value of the current joint position
Custom Cartesian point X 0 Y 0 Z 0 R 0 User 0 Tool 0
Custom joint point J1 0 J2 0 J3 0 J4 0
Point InitialPose
X value of point InitialPose
Control
Points
I/O


DobotStudio2020 1.1.0-stable.202102091847
Dobot Studio
Test_LUA_001
MG400
MagicianPro
192.168.1.6
Connected
Safe-L3
Online
Global Speed(100%)
STOP
File
Save
Undo
Redo
Debug
Start
Stop
Control
Input search text
Motion
Point to point, the target point is Cartesian point
MovJ
Linear Movement
MovL
Point to point, the target point is Joint point
JointMovJ
Jump Movement, Jump parameters can be set in this command
Jump
Jump Movement, Jump parameters are called by Arch index
Jump1
Move to the Cartesian offset position in a point to point mode
RelMovJ
Move to the Cartesian offset position in a straight line
RelMovL
Help Document
can double-click to insert the command with optional parameters.
CP: Continuous path rate. Value range: 0-100
SpeedJ: Velocity rate. Value range: 1 - 100
AccJ: Acceleration rate. Value range: 1 -100
P
src0.lua
global.lua
-- Version: Lua 5.4.1
MovJ(P1)
MovJ(P2)
Param
Joint Acceleration
AccJ
Cartesian Acceleration
AccL
Joint Speed
SpeedJ
Cartesian Speed
SpeedL
CP
CP
Synchronization
Sync
Set Load Parameters
SetPayload
I/O
DI
DI
DO
DO
DOInstant
DOInstant
Util
Motion command waiting
Wait
TCP
Create TCP
TCPCreate
Establish TCP connection
TCPStart
Receive TCP data
TCPRead
Send TCP data
TCPWrite
Close TCP
TCPDestroy
UDP
Create UDP
UDPCreate
Receive UDP data
UDPRead
Send UDP data
UDPWrite
Modbus
Read the value from Modbus slave coil register address
GetCoils
Set the coil register in the Modbus slave
SetCoils
Stack
Instantiate matrix pallet
MatrixPallet
Instantiate teaching pallet
TeachPallet
Set the next stack index which is to be operated
SetPartIndex
Get the current operated stack index
GetPartIndex
Set the next pallet layer index which is to be operated
SetLayerIndex
Get the current pallet layer index
GetLayerIndex
Reset pallet
Restet
Check whether the stack assembly or dismantling is complete
IsDone
Release palletizing instance
Release
The robot moves from the current position to the first stack position as the configured stack assembly path
PalletMoveIn
Conveyer Belt
Set conveyor number to create a tracing queue
CnvVison
Obtain status of the object
GetCnvObject
Set X,Y axes offset under the set User coordinate system
SetCnvPointOffset
Set time compensation
SetCnvTimeCompensation
Synchronize the specified conveyor
SyncCnv
Stop synchronous conveyor
StopSyncCnv


Settings
Common
MG400
Basic
IP Configuration
Collision Detection
Firmware Download
Jump Params
Load Params
Home Calibration
Coordinate System
Specification
Device Name
MagicianPro
Reset Device Name
Device SN
DT18-2106-0009
Controller Hardware Version
2001018102
Servo Hardware Version
2001018502
Initial Position
Reset Initial Pose
InitialPose
Move to Default Pose
Restore Default Pose
X
350.000
Z
0.000
User
0
Y
0.000
R
0.000
Tool
0


Settings
Common
MG400
Basic
IP Configuration
Collision Detection
Firmware Download
Jump Params
Load Params
Home Calibration
Coordinate System
IP Configuration
Only the IP address of LAN2 can be modified to connect external devices
IP Address
192
168
1
22
Netmask
255
255
255
0
Gateway
0
0
0
0


Settings
Common
MG400
Basic
IP Configuration
Collision Detection
Firmware Download
Jump Params
Load Params
Home Calibration
Coordinate System
Collision Detection
Collision Detection Sensitivity
Level1
Level2
Level3
Level4
Level5
Higher level, higher sensitivity
Recovery Method After Collision Detection
Method
:ally resume after 5s
Automatically resume after 5s
Pause
Settings
Common
MG400
Basic
IP Configuration
Collision Detection
Firmware Download
Jump Params
Load Params
Home Calibration
Coordinate System
Controller Firmware
Current Version: 1.4.4.7.20210205171053
Controller Firmware:
Open
Update
Servo Firmware
Current Version: 1.0.4.0
Servo Firmware:
Open
Update
Current Version: 3.4.14
Configuration File:
Open
Update

Settings

Common

MG400

Basic

IP Configuration

Collision Detection

Firmware Download

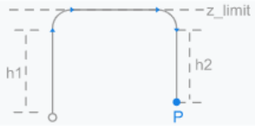
Jump Params

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

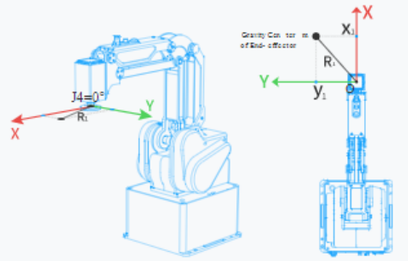
Load Params

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

Settings

Common

MG400

Basic

IP Configuration

Collision Detection

Firmware Download

Jump Params

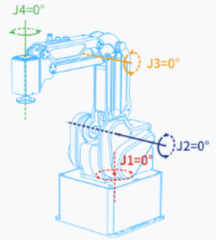
Load Params

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

ControlTech

Authorised Distributor

A ROCKWELL AUTOMATION PARTNER

MG400 Accessories

DOBOT

DOBOT

Vacuum Suction Cup kit

For picking up object having big surface or in long strip shape
Changeable suction cup for different size
Adjustable distance for quick setup

DOBOT

DOBOT

Soft Gripper Kit -1

Picking soft, irregularly shaped and high-level objects
Adjustable distance for quick setup

DOBOT

DOBOT

Electric gripper (SERVO type)

Designed for advanced application
Size 65 x 43 x 18 mm
Gripping force \ speed \ distance adjustable

DOBOT

DOBOT

Mini ElectroMagnetic Gripper

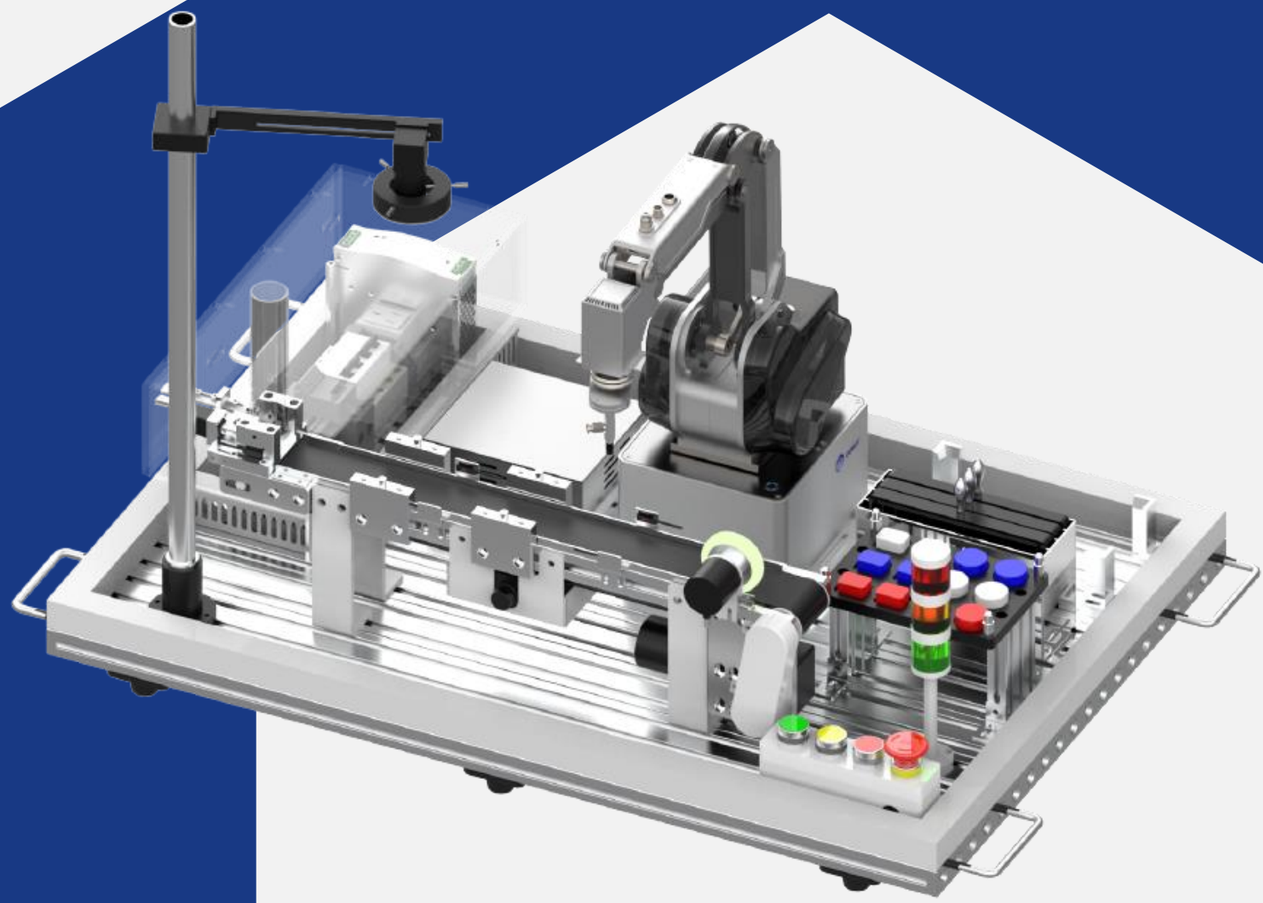
For picking small solid object
Simple & Easy to use
I\O control for opening & closing I\O


DOBOT MG400


DOBOT
DOBOT M6400

DOBOT

MG400 Robotic Training System



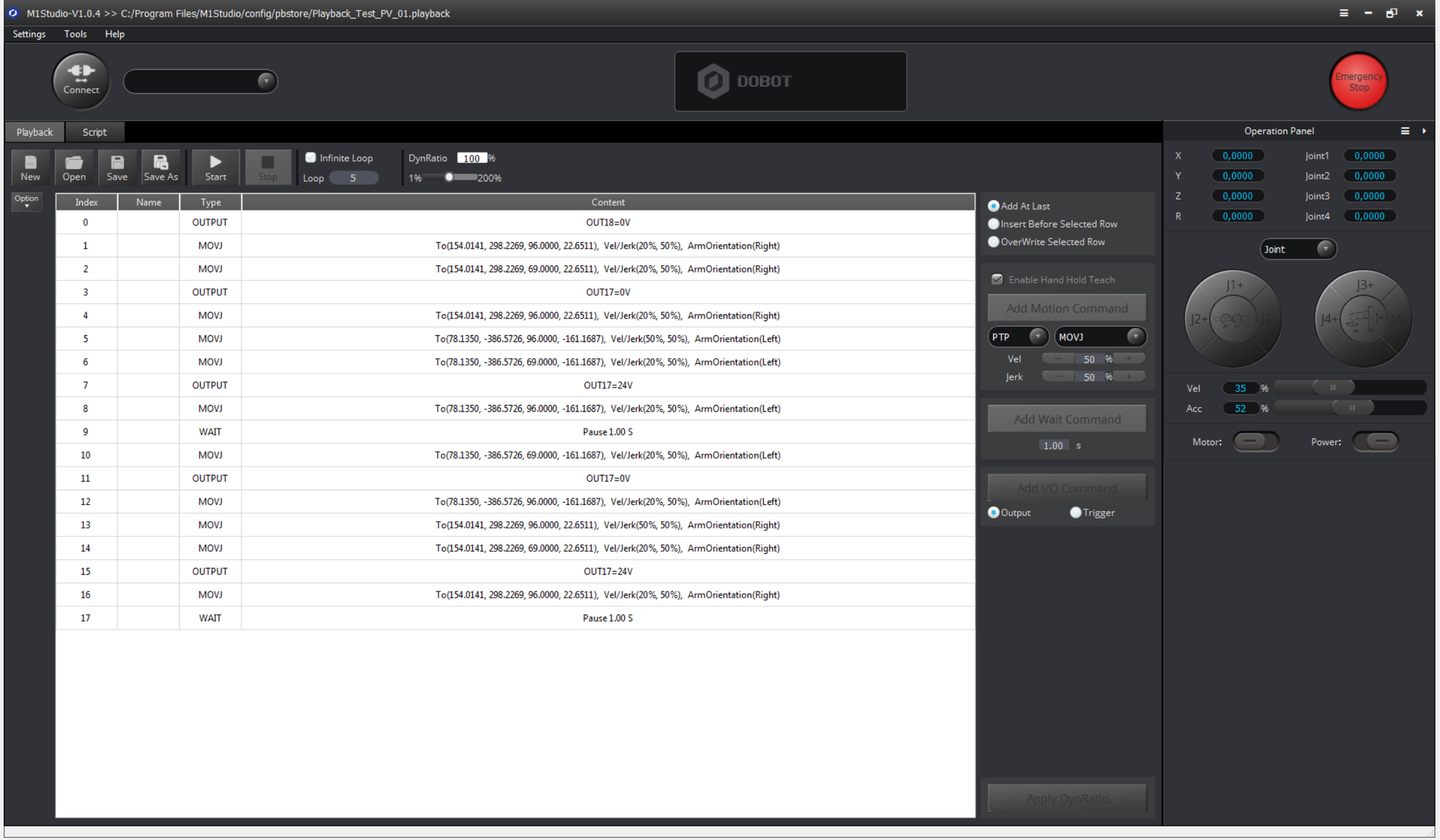
DOBOT SCARA M-1

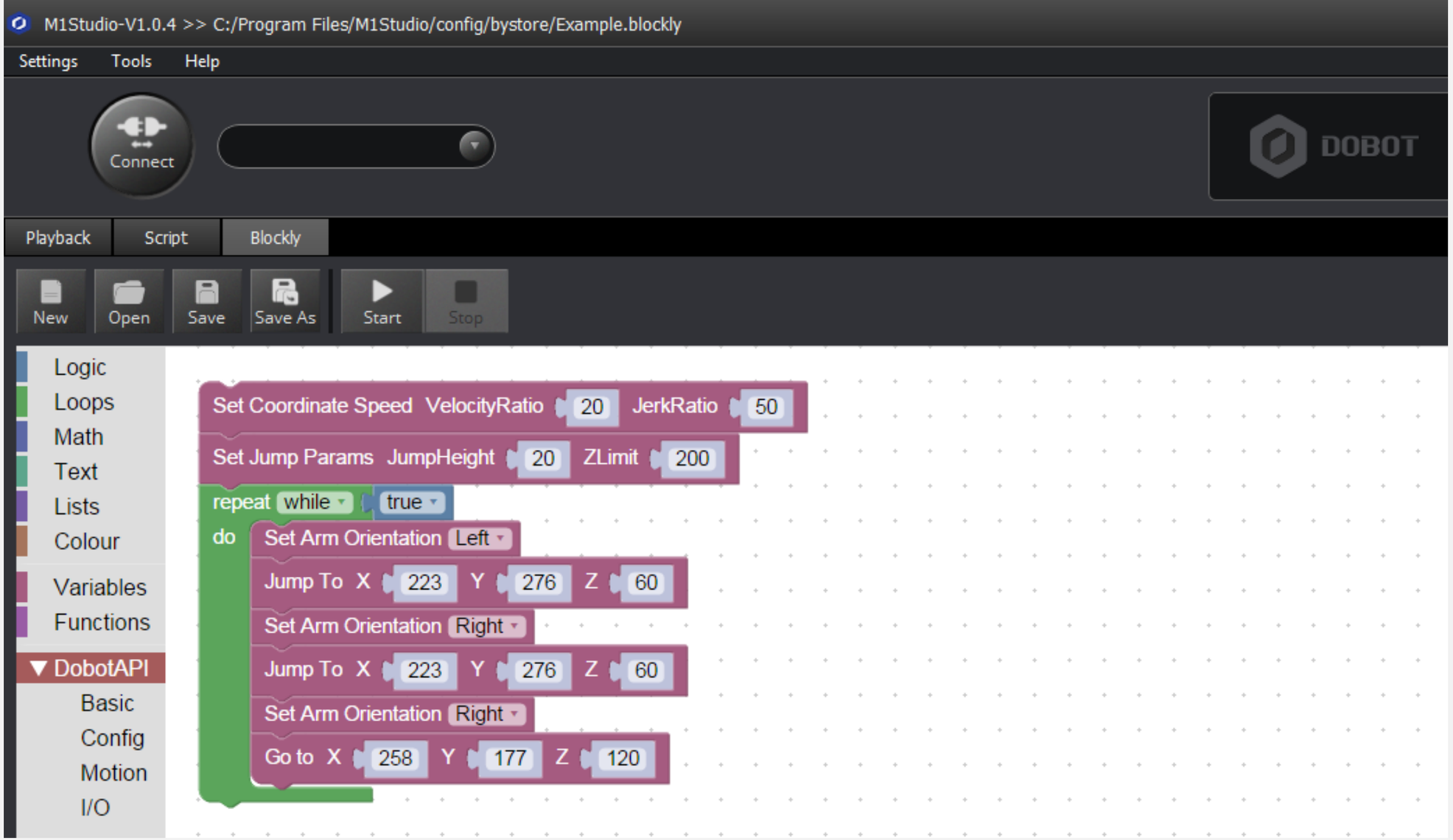
Opakovatelnost
0,02 mm

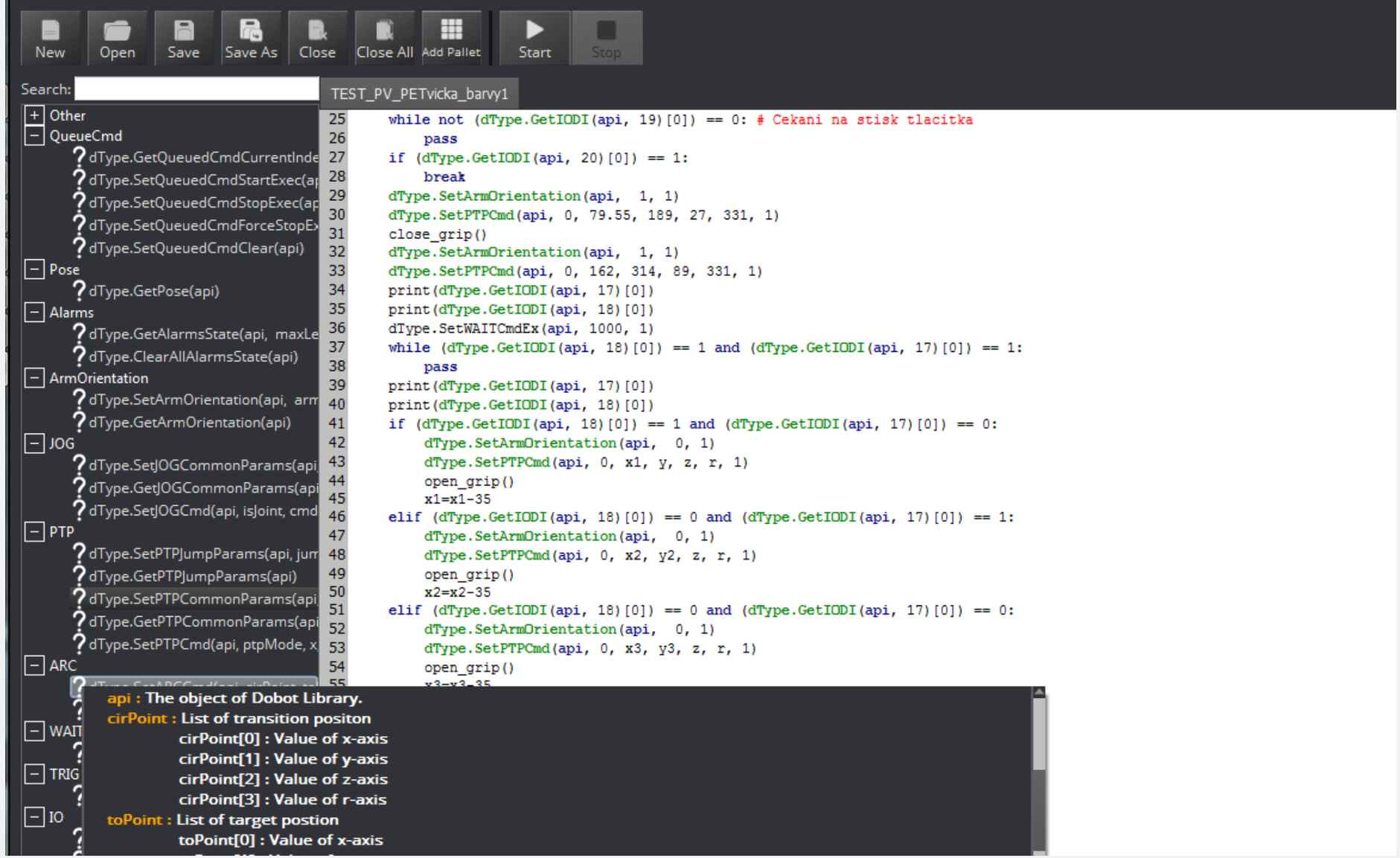
Rychlost
200°/s

Nosnost
1,5 kg

Dosah
400 mm


M1Studio-V1.0.4 >> C:/Program Files/M1Studio/config/pbstore/Playback_Test_PV_01.playback
Settings
Tools
Help
Connect
DOBOT
Emergency Stop
Playback
Script
New
Open
Save
Save As
Start
Stop
Infinite Loop
Loop 5
DynRatio 100 %
1%
200%
Option
Index Name Type Content
0 OUTPUT OUT18=0V
1 MOVJ To(154.0141, 298.2269, 96.0000, 22.6511), Vel/Jerk(20%, 50%), ArmOrientation(Right)
2 MOVJ To(154.0141, 298.2269, 69.0000, 22.6511), Vel/Jerk(20%, 50%), ArmOrientation(Right)
3 OUTPUT OUT17=0V
4 MOVJ To(154.0141, 298.2269, 96.0000, 22.6511), Vel/Jerk(20%, 50%), ArmOrientation(Right)
5 MOVJ To(78.1350, -386.5726, 96.0000, -161.1687), Vel/Jerk(50%, 50%), ArmOrientation(Left)
6 MOVJ To(78.1350, -386.5726, 69.0000, -161.1687), Vel/Jerk(20%, 50%), ArmOrientation(Left)
7 OUTPUT OUT17=24V
8 MOVJ To(78.1350, -386.5726, 96.0000, -161.1687), Vel/Jerk(20%, 50%), ArmOrientation(Left)
9 WAIT Pause 1.00 S
10 MOVJ To(78.1350, -386.5726, 69.0000, -161.1687), Vel/Jerk(20%, 50%), ArmOrientation(Left)
11 OUTPUT OUT17=0V
12 MOVJ To(78.1350, -386.5726, 96.0000, -161.1687), Vel/Jerk(20%, 50%), ArmOrientation(Left)
13 MOVJ To(154.0141, 298.2269, 96.0000, 22.6511), Vel/Jerk(50%, 50%), ArmOrientation(Right)
14 MOVJ To(154.0141, 298.2269, 69.0000, 22.6511), Vel/Jerk(20%, 50%), ArmOrientation(Right)
15 OUTPUT OUT17=24V
16 MOVJ To(154.0141, 298.2269, 96.0000, 22.6511), Vel/Jerk(20%, 50%), ArmOrientation(Right)
17 WAIT Pause 1.00 S
Add At Last
Insert Before Selected Row
OverWrite Selected Row
Enable Hand Hold Teach
Add Motion Command
PTP
MOVJ
Vel 50 %
Jerk 50 %
Add Wait Command
1.00 s
Add I/O Command
Output
Trigger
Apply DynRatio
Operation Panel
X 0,0000
Y 0,0000
Z 0,0000
R 0,0000
Joint1 0,0000
Joint2 0,0000
Joint3 0,0000
Joint4 0,0000
Joint
J1+
J2+
J3+
J4+
Vel 35 %
Acc 52 %
Motor:
Power:


M1Studio-V1.0.4 >> C:/Program Files/M1Studio/config/bystore/Example.blockly
Settings
Tools
Help
Connect
DOBOT
Playback
Script
Blockly
New
Open
Save
Save As
Start
Stop
Logic
Loops
Math
Text
Lists
Colour
Variables
Functions
DobotAPI
Basic
Config
Motion
I/O
Set Coordinate Speed VelocityRatio 20 JerkRatio 50
Set Jump Params JumpHeight 20 ZLimit 200
repeat while true
do
Set Arm Orientation Left
Jump To X 223 Y 276 Z 60
Set Arm Orientation Right
Jump To X 223 Y 276 Z 60
Set Arm Orientation Right
Go to X 258 Y 177 Z 120


New
Open
Save
Save As
Close
Close All
Add Pallet
Start
Stop
Search:
TEST_PV_PETvicka_barvy1
Other
QueueCmd
dType.GetQueuedCmdCurrentInde
dType.SetQueuedCmdStartExec(ap
dType.SetQueuedCmdStopExec(ap
dType.SetQueuedCmdForceStopEx
dType.SetQueuedCmdClear(api)
Pose
dType.GetPose(api)
Alarms
dType.GetAlarmsState(api, maxLe
dType.ClearAllAlarmsState(api)
ArmOrientation
dType.SetArmOrientation(api, arm
dType.GetArmOrientation(api)
JOG
dType.SetJOGCommonParams(api,
dType.GetJOGCommonParams(api
dType.SetJOGCmd(api, isJoint, cmd
PTP
dType.SetPTPJumpParams(api, jum
dType.GetPTPJumpParams(api)
dType.SetPTPCommonParams(api,
dType.GetPTPCommonParams(api
dType.SetPTPCmd(api, ptpMode, x
ARC
WAIT
TRIG
IO
25 while not (dType.GetIODI(api, 19)[0]) == 0: # Cekani na stisk tlacitka
26 pass
27 if (dType.GetIODI(api, 20)[0]) == 1:
28 break
29 dType.SetArmOrientation(api, 1, 1)
30 dType.SetPTPCmd(api, 0, 79.55, 189, 27, 331, 1)
31 close_grip()
32 dType.SetArmOrientation(api, 1, 1)
33 dType.SetPTPCmd(api, 0, 162, 314, 89, 331, 1)
34 print(dType.GetIODI(api, 17)[0])
35 print(dType.GetIODI(api, 18)[0])
36 dType.SetWAITCmdEx(api, 1000, 1)
37 while (dType.GetIODI(api, 18)[0]) == 1 and (dType.GetIODI(api, 17)[0]) == 1:
38 pass
39 print(dType.GetIODI(api, 17)[0])
40 print(dType.GetIODI(api, 18)[0])
41 if (dType.GetIODI(api, 18)[0]) == 1 and (dType.GetIODI(api, 17)[0]) == 0:
42 dType.SetArmOrientation(api, 0, 1)
43 dType.SetPTPCmd(api, 0, x1, y, z, r, 1)
44 open_grip()
45 x1=x1-35
46 elif (dType.GetIODI(api, 18)[0]) == 0 and (dType.GetIODI(api, 17)[0]) == 1:
47 dType.SetArmOrientation(api, 0, 1)
48 dType.SetPTPCmd(api, 0, x2, y2, z, r, 1)
49 open_grip()
50 x2=x2-35
51 elif (dType.GetIODI(api, 18)[0]) == 0 and (dType.GetIODI(api, 17)[0]) == 0:
52 dType.SetArmOrientation(api, 0, 1)
53 dType.SetPTPCmd(api, 0, x3, y3, z, r, 1)
54 open_grip()
55 x3=x3-35
api : The object of Dobot Library.
cirPoint : List of transition positon
cirPoint[0] : Value of x-axis
cirPoint[1] : Value of y-axis
cirPoint[2] : Value of z-axis
cirPoint[3] : Value of r-axis
toPoint : List of target postion
toPoint[0] : Value of x-axis

DOBOT

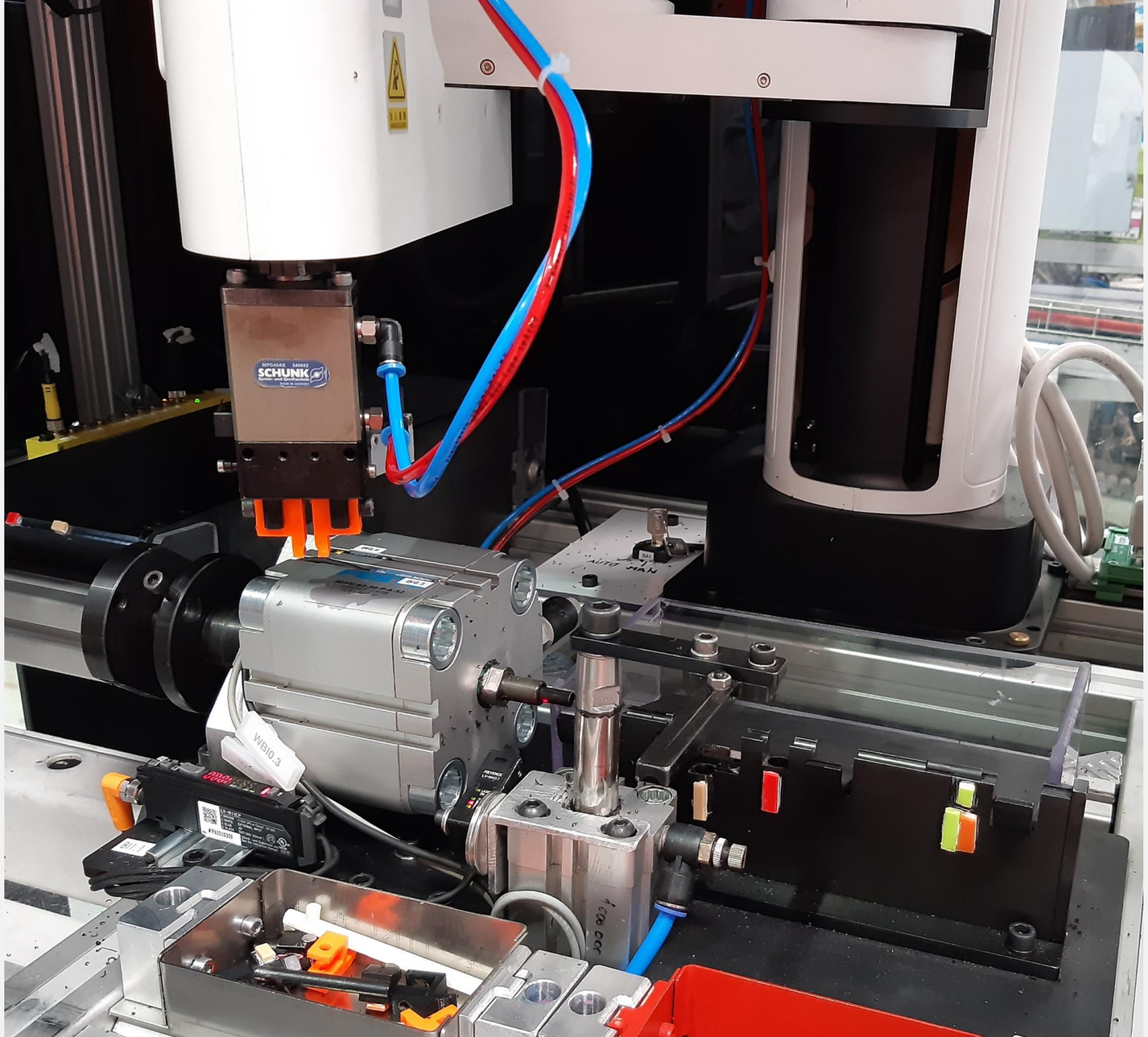
BIOMEDICA

AICOBOTIX
ARTIFICIAL INTELLIGENCE

Rendszer

NICO TECHNIKA

u-shin



DOBOT

AICOBOTIX
ARTIFICIAL INTELLIGENCE

DOBOT M1 je levný a cenově dostupný SCARA robot vhodný pro 1-2 směnný provoz pro malou výrobu. Přesnost +-0,1 mm dosažitelná pomocí kamerově vedené montáže a kontroly kvality AicobotiX pomocí řešení QiCHECK (TM) Vedení QiCHECK naviguje robota, aby vybral a umístil malé součásti o průměru až 3 mm. Kromě toho provádí kontrolu kvality. levná alternativa k EPSON, YAMAHA, TOSHIBA, FANUC, KUKA atd.

https://www.aicobotix.com/

DOBOT

M1 PRO

NOVINKA

VÝUKOVÉ A TRÉNINKOVÉ ROBOTY DOBOT

Magician a Magician Lite

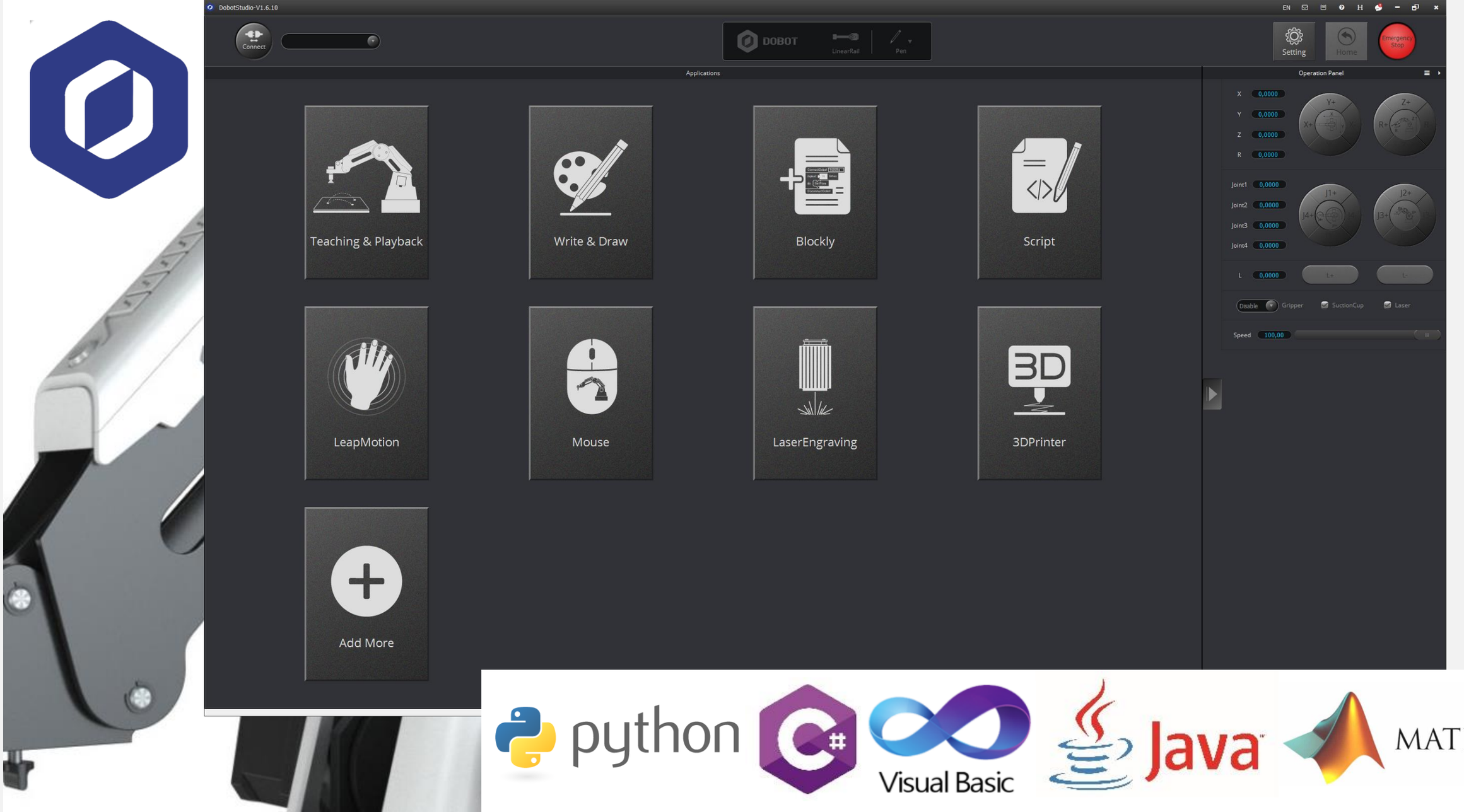
DESIGN AWARD 2018

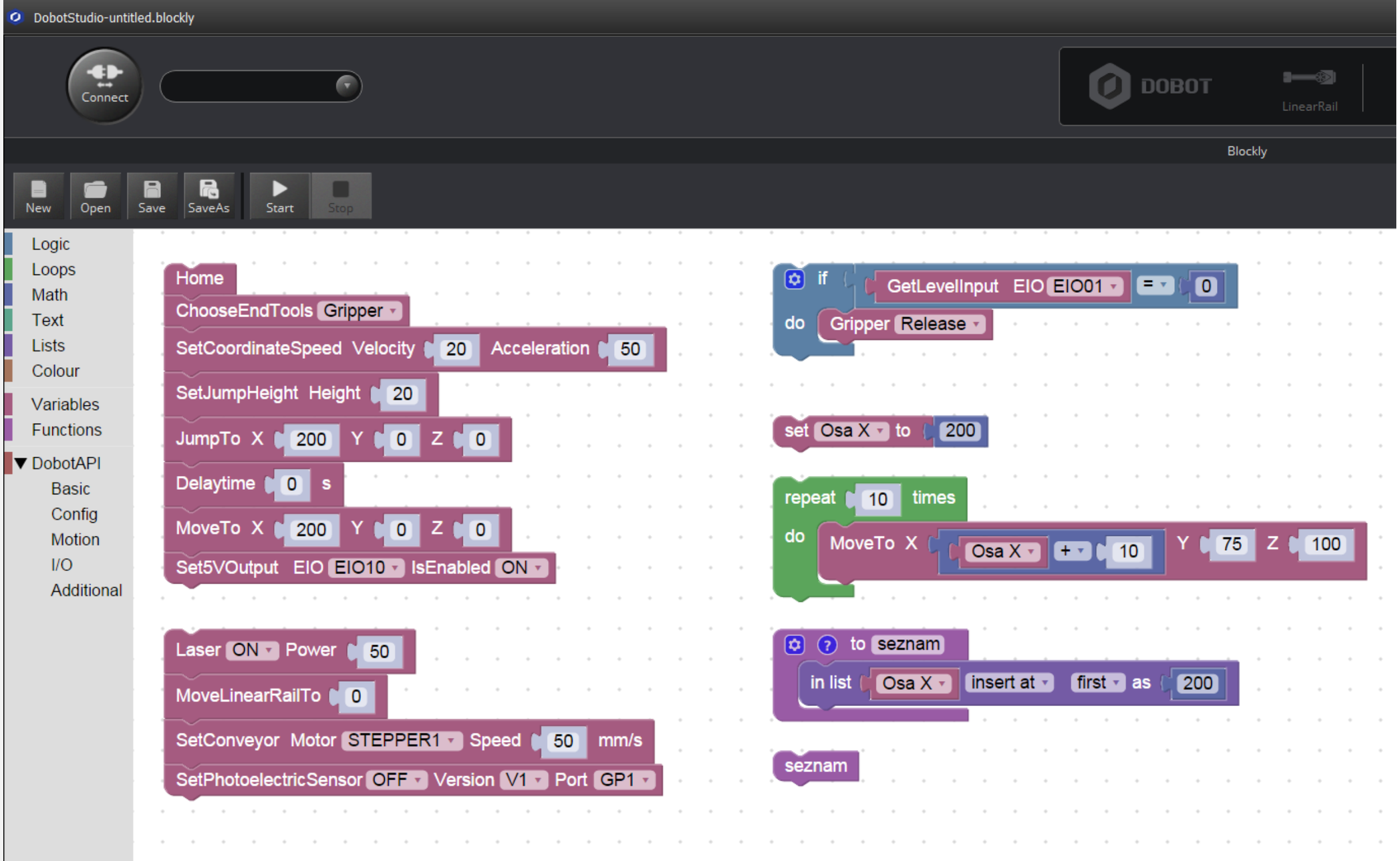
reddot award 2018 winner

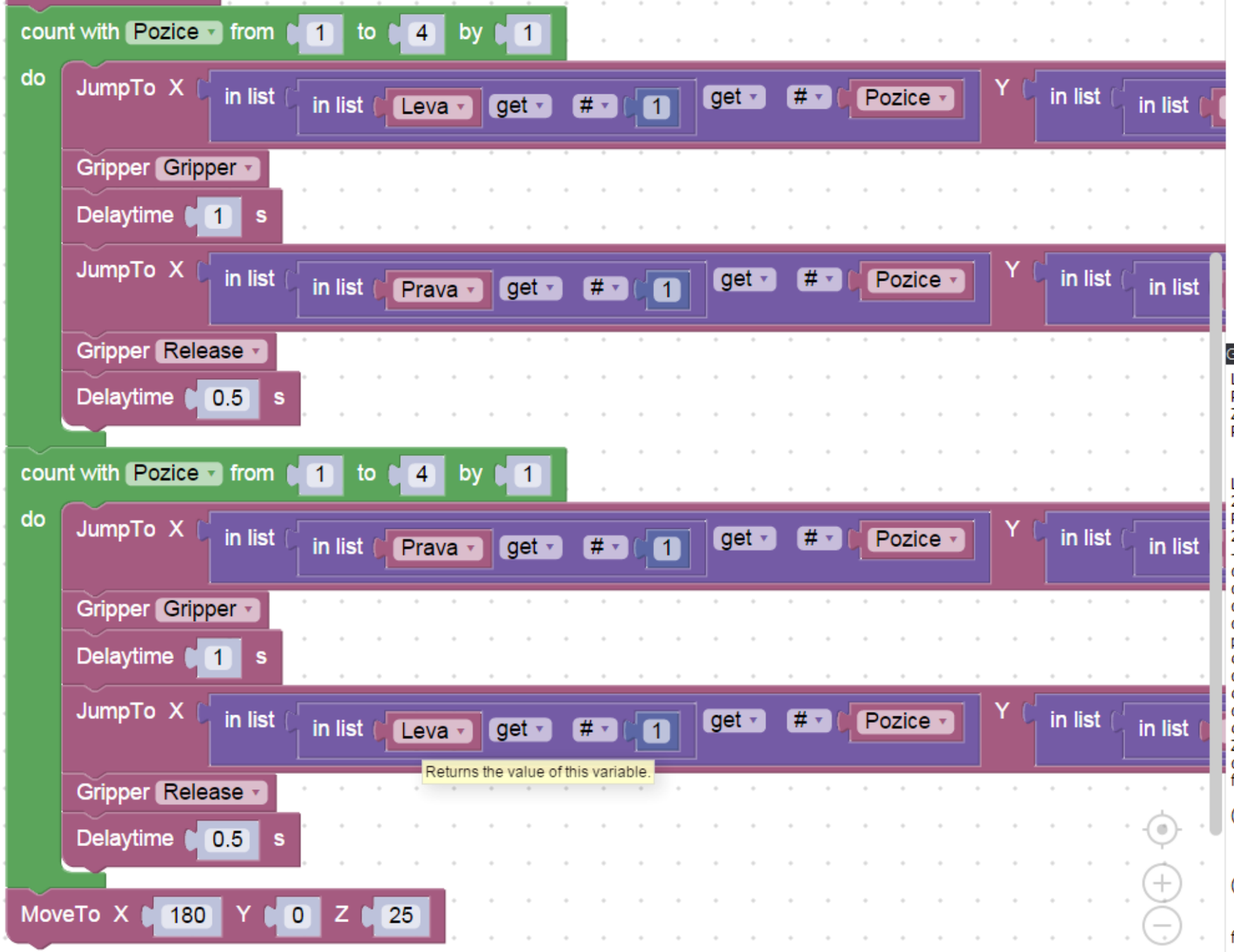
CES 2018

红星奖 Red Star Design Award

DOBOT


DobotStudio-V1.6.10
Connect
DOBOT
LinearRail
Pen
Setting
Home
Emergency Stop
Applications
Teaching & Playback
Write & Draw
Blockly
Script
LeapMotion
Mouse
LaserEngraving
3DPrinter
Add More
Operation Panel
X
Y
Z
R
Joint1
Joint2
Joint3
Joint4
L
Disable
Gripper
SuctionCup
Laser
Speed
100,00
python
Visual Basic
Java
MATLAB

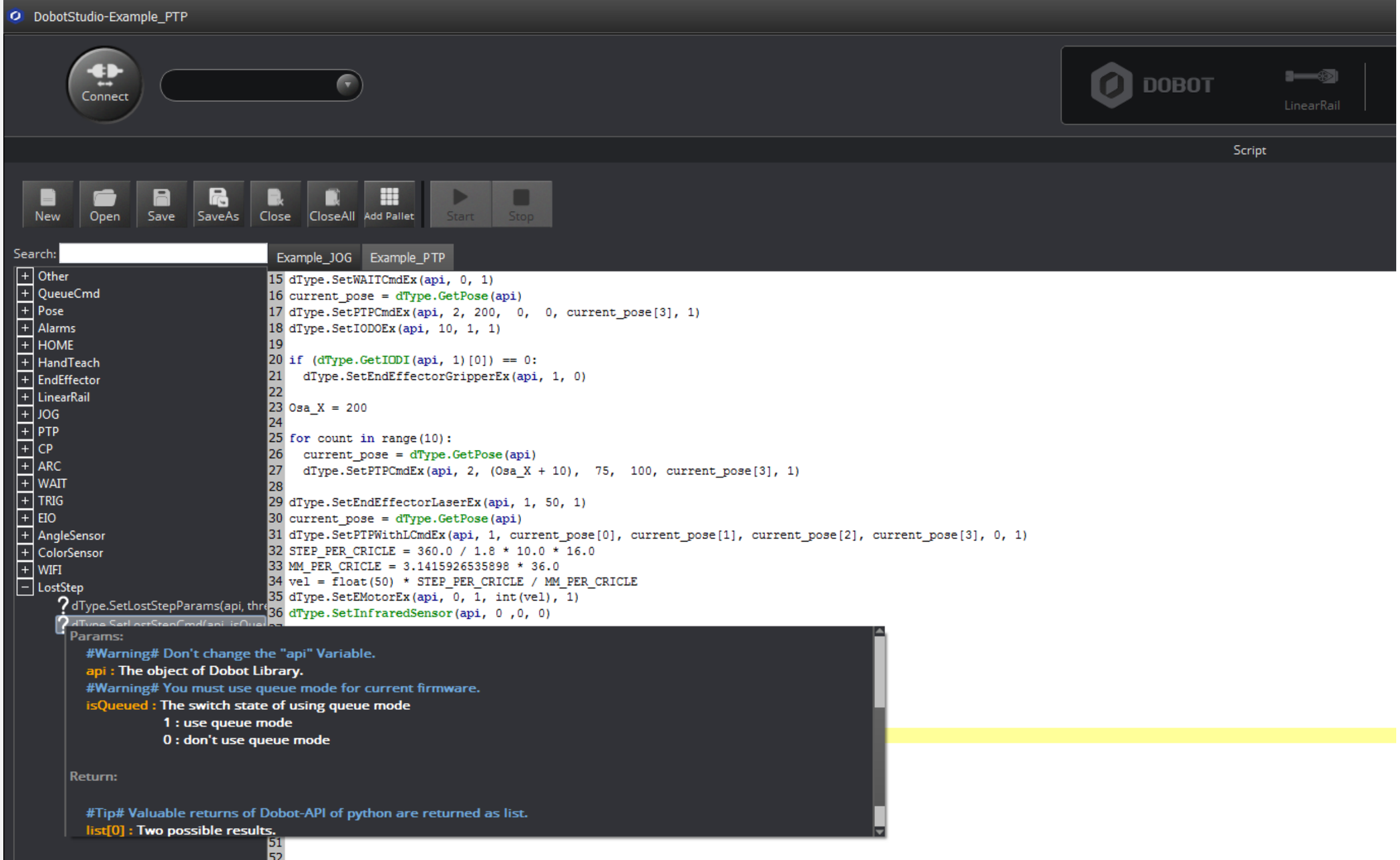

DobotStudio-untitled.blockly
Connect
DOBOT
LinearRail
Blockly
New
Open
Save
SaveAs
Start
Stop
Logic
Loops
Math
Text
Lists
Colour
Variables
Functions
DobotAPI
Basic
Config
Motion
I/O
Additional
Home
ChooseEndTools Gripper
SetCoordinateSpeed Velocity 20 Acceleration 50
SetJumpHeight Height 20
JumpTo X 200 Y 0 Z 0
Delaytime 0 s
MoveTo X 200 Y 0 Z 0
Set5VOutput EIO EIO10 IsEnabled ON
Laser ON Power 50
MoveLinearRailTo 0
SetConveyor Motor STEPPER1 Speed 50 mm/s
SetPhotoelectricSensor OFF Version V1 Port GP1
if GetLevelInput EIO EIO01 = 0
do Gripper Release
set Osa X to 200
repeat 10 times
do MoveTo X Osa X + 10 Y 75 Z 100
to seznam
in list Osa X insert at first as 200
seznam

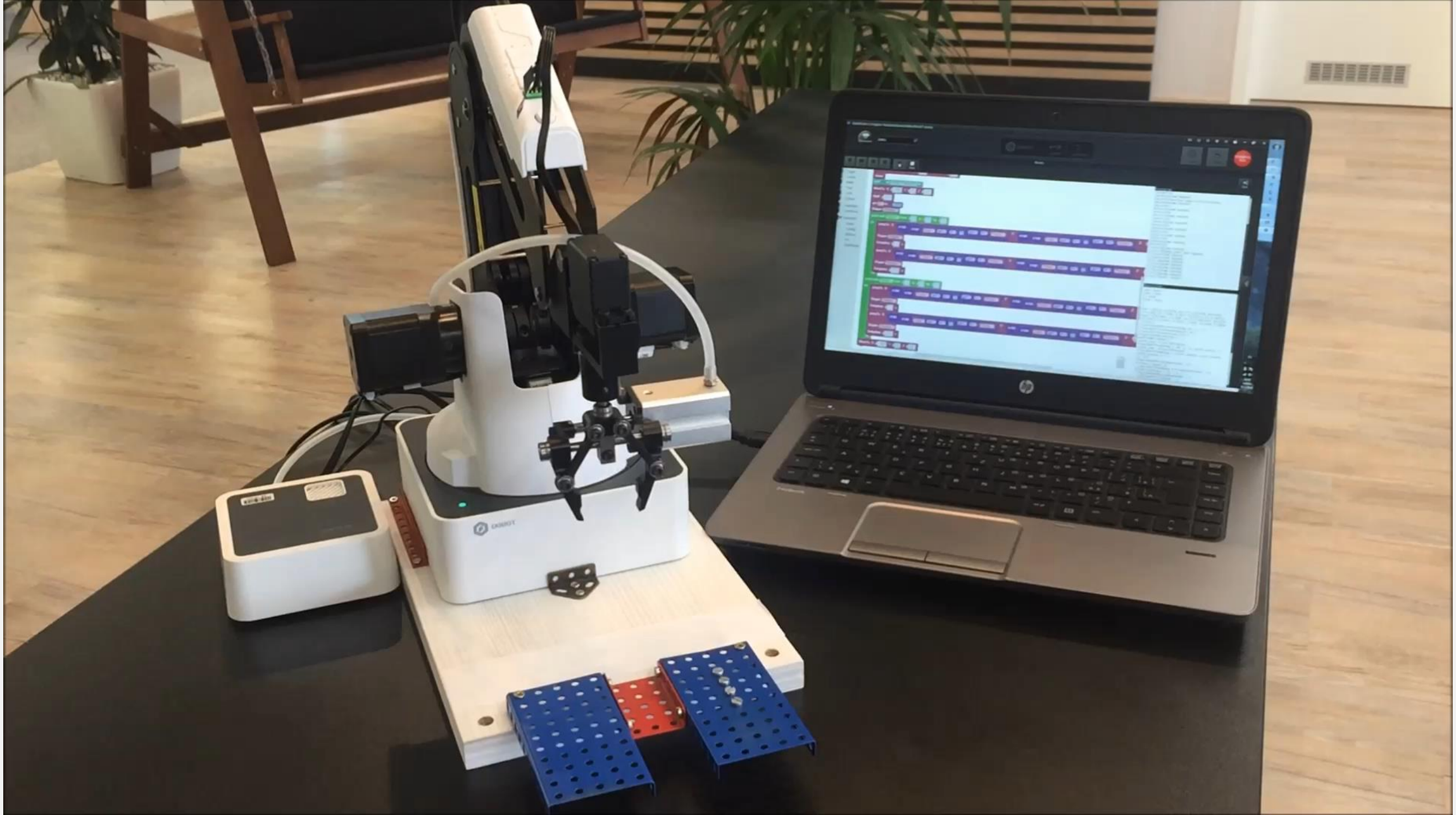


General Code:

```
Leva = None
Prava = None
Z = None
Pozice = None


Leva = [[225.5, 235.6279, 245.4217, 255.5538, 265.4469,
274.8148], [43, 42.999, 42.5677, 42.2319, 42.28, 41.8972]]
Prava = [[223.6901, 233.7885, 243.7215, 253.4057, 263.3534,
273.2444], [-42.9919, -43.1828, -43.5424, -43.5426, -43.8326,
-44.0512]]
dType.SetEndEffectorParamsEx(api, 59.7, 0, 0, 1)
dType.SetPTPJumpParamsEx(api,40,100,1)
dType.SetPTPLParamsEx(api,20,50,1)
dType.SetHOMECmdEx(api, 0, 1)
print('HOME FINISHED')
current_pose = dType.GetPose(api)
dType.SetPTPCmdEx(api, 2, 180,  0,  25, current_pose[3], 1)
current_pose = dType.GetPose(api)
dType.SetPTPCmdEx(api, 4, current_pose[4], current_pose[5],
current_pose[6], 8.4, 1)
Z = -20.5
dType.SetEndEffectorGripperEx(api, 1, 0)
for Pozice in range(1, 5):
  dType.SetPTPCmdEx(api, 0, ((Leva[0])[int(Pozice - 1)]),
((Leva[1])[int(Pozice - 1)]),  Z, 0, 1)
  dType.SetEndEffectorGripperEx(api, 1, 1)
  dType.SetWAITCmdEx(api, 1, 1)
  dType.SetPTPCmdEx(api, 0, ((Prava[0])[int(Pozice - 1)]),
((Prava[1])[int(Pozice - 1)]),  Z, 0, 1)
  dType.SetEndEffectorGripperEx(api, 1, 0)
  dType.SetWAITCmdEx(api, 0.5, 1)
for Pozice in range(1, 5):
  dType.SetPTPCmdEx(api, 0, ((Prava[0])[int(Pozice - 1)]),
```


DobotStudio-Example_PTP
Connect
DOBOT
LinearRail
Script
New
Open
Save
SaveAs
Close
CloseAll
Add Pallet
Start
Stop
Search:
Example_JOG
Example_PTP
Other
QueueCmd
Pose
Alarms
HOME
HandTeach
EndEffector
LinearRail
JOG
PTP
CP
ARC
WAIT
TRIG
EIO
AngleSensor
ColorSensor
WIFI
LostStep
dType.SetLostStepParams(api, thre
dType.SetLostStepCmd(api, isQue
Params:
#Warning# Don't change the "api" Variable.
api : The object of Dobot Library.
#Warning# You must use queue mode for current firmware.
isQueued : The switch state of using queue mode
1 : use queue mode
0 : don't use queue mode
Return:
#Tip# Valuable returns of Dobot-API of python are returned as list.
list[0] : Two possible results.
15 dType.SetWAITCmdEx(api, 0, 1)
16 current_pose = dType.GetPose(api)
17 dType.SetPTPCmdEx(api, 2, 200, 0, 0, current_pose[3], 1)
18 dType.SetIODOEx(api, 10, 1, 1)
19
20 if (dType.GetIODI(api, 1)[0]) == 0:
21 dType.SetEndEffectorGripperEx(api, 1, 0)
22
23 Osa_X = 200
24
25 for count in range(10):
26 current_pose = dType.GetPose(api)
27 dType.SetPTPCmdEx(api, 2, (Osa_X + 10), 75, 100, current_pose[3], 1)
28
29 dType.SetEndEffectorLaserEx(api, 1, 50, 1)
30 current_pose = dType.GetPose(api)
31 dType.SetPTPWithLCmdEx(api, 1, current_pose[0], current_pose[1], current_pose[2], current_pose[3], 0, 1)
32 STEP_PER_CRICLE = 360.0 / 1.8 * 10.0 * 16.0
33 MM_PER_CRICLE = 3.1415926535898 * 36.0
34 vel = float(50) * STEP_PER_CRICLE / MM_PER_CRICLE
35 dType.SetEMotorEx(api, 0, 1, int(vel), 1)
36 dType.SetInfraredSensor(api, 0 ,0, 0)




DOBOT
DOBOT Magician Lite
Magician Lite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Script
DOBOT


AI Teaching Kit
AI 教学配件包
DOBOT
Image Recognition
Voice Recognition
Face Recognition
OCR Text Recognition
Garbage Classification


cola
water
coffee
milk

DOBOT

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

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

Scénáře

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

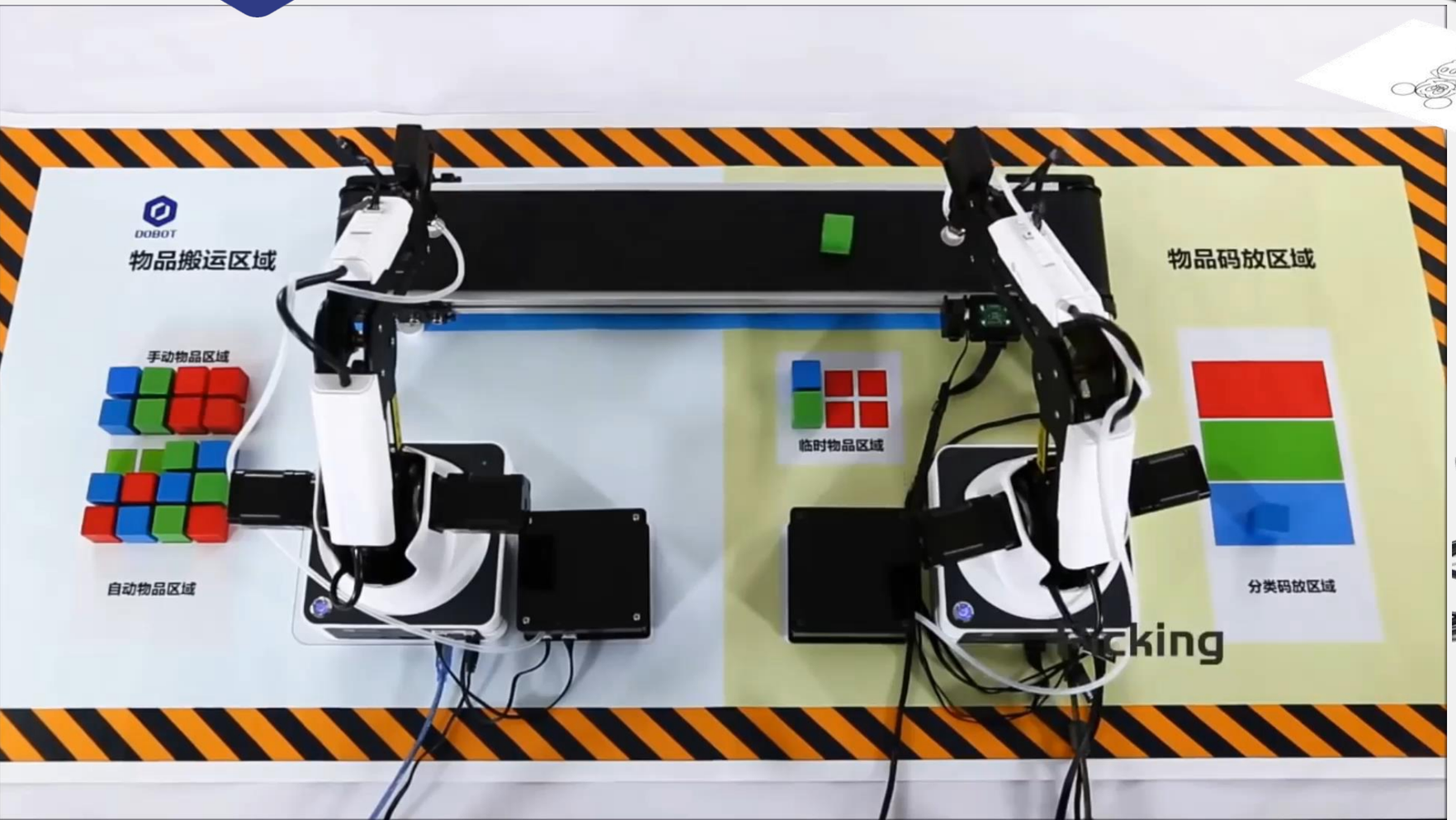
Stav

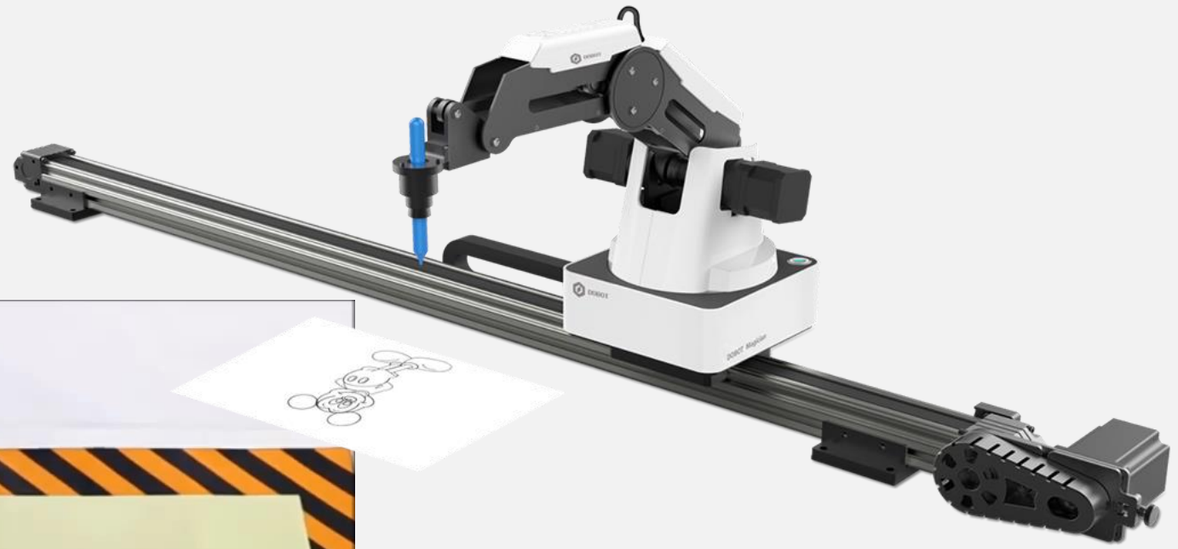
- Získat současné souřadnice X
- Získat současné úhly kloubů Kloub 1
- Smazat alarm

I/O

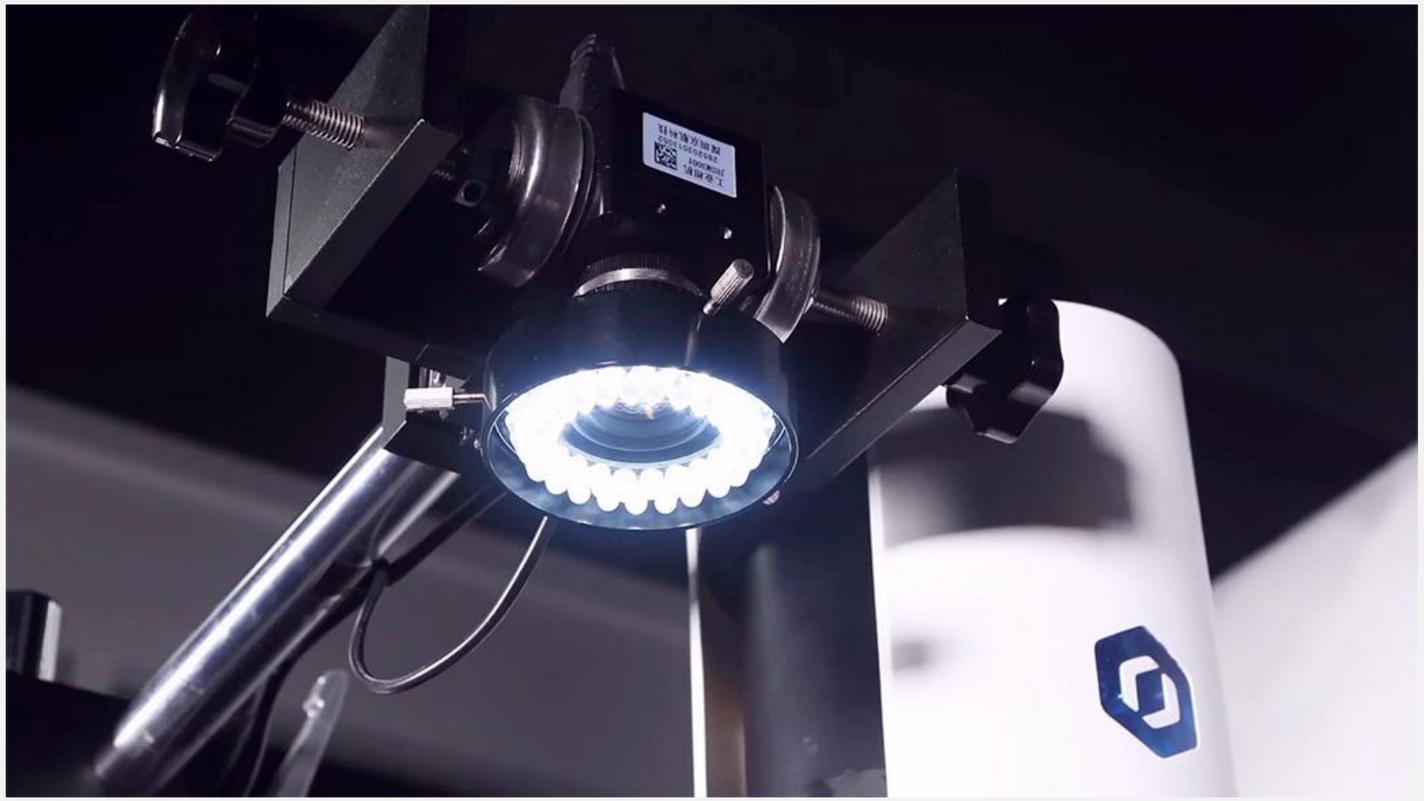
- Nastavit Pin EIO1 Režim IO Funkce Dummy
- Nastavit PWM výstup Pin EIO1 Frekvence 0 Střída 0 %
- Nastavit digitální výstup Pin EIO1 Hodnota Logická 1

DOBOT

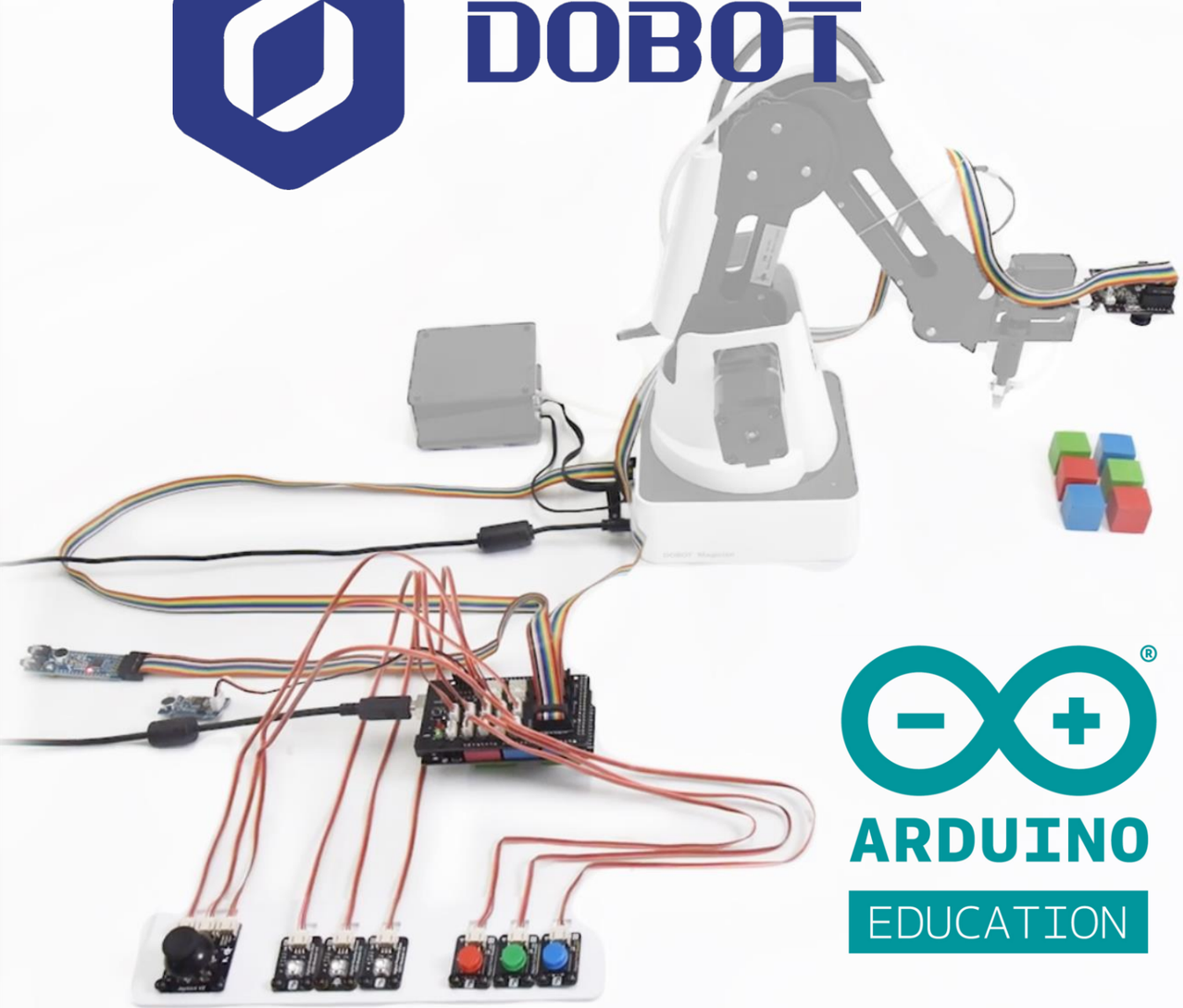




DOBOT

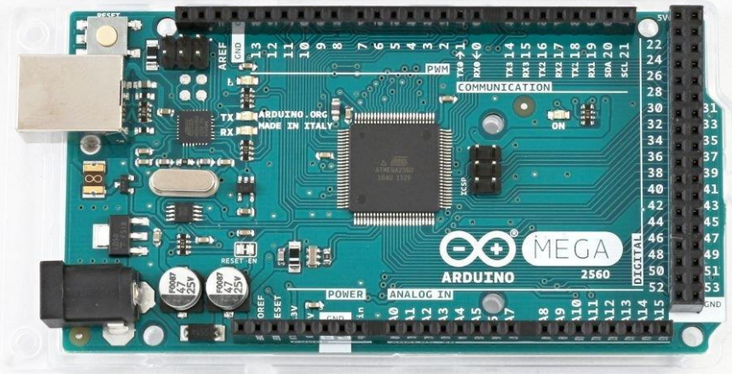


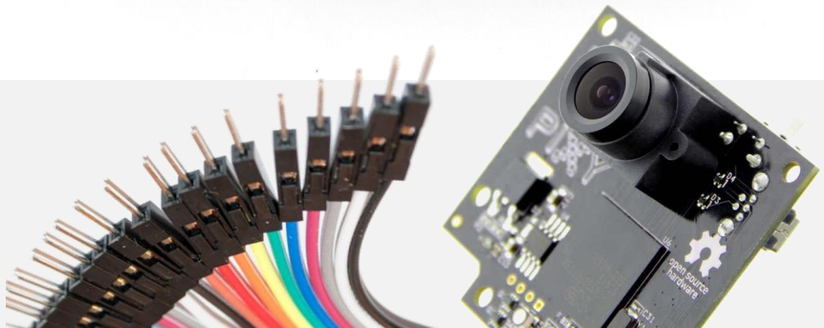
DOBOT



ARDUINO

EDUCATION





DOBOT

DOBOT SENSOR KIT pro Magician

Joystick, Dvojtlačítko, PIR senzor, Snímač gest, Fotoelektrický snímač, Snímač zvuku, Snímač vlhkosti, Barevné čidlo, Senzor barvy, LED modul, Světelný senzor, Potenciometr, mikroservo, Sada AI kamery, Magic Box.

DOBOT SENSOR KIT pro Lite

DOBOT

GO

PŘIPRAVUJE SE
NOVINKA

越疆科技

Magician Go

智能移动机器人

ROBOTY OBVYKLE SKLADEM, IHNED K DODÁNÍ.

DOBOT

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