

PANDA - DATASHEET ¹

April 2019

HARDWARE

Arm

Degrees of freedom	7
Payload	3 kg
Workspace	see backside
Maximum reach	855 mm
F/T Sensing	link-side torque sensors in all 7 axes
Expected nominal lifetime ^{3,4}	20,000 h
Joint position limits [°]	A1, A3, A5, A7: -166/166 A2: -101/101 A4: -176/-4 A6: -1/215
Mounting flange	DIN ISO 9409-1-A50
Installation position	upright
Weight	~ 17.8 kg
Moving mass	~ 12.8 kg
Protection rating	IP30
Ambient temperature ²	15 – 25 °C (typical) 5 – 45 °C (extended)
Air humidity	20 – 80 % non-condensing
Interfaces	<ul style="list-style-type: none"> • ethernet (TCP/IP) for visual intuitive programming with Desk • input for external enabling device • input for external activation device or safeguard • Control connector • Connector for end-of-arm tooling

Control

Controller size (19")	355 x 483 x 89 mm (D x W X H)
Supply voltage	100 – 240 V _{AC}
Mains frequency	47 – 63 Hz
Power consumption	<ul style="list-style-type: none"> • max. 600 W • average ~ 300 W
Active power factor correction (PFC)	yes
Weight	~ 7 kg
Protection rating	IP20
Ambient temperature	15 – 25 °C (typical) 5 – 45 °C (extended)
Air humidity	20 – 80 % non-condensing
Interfaces	<ul style="list-style-type: none"> • ethernet (TCP/IP) for internet and/or shop-floor connection • power connector IEC 60320-C14 (V-Lock) • Arm connector

SOFT-ROBOT PERFORMANCE

Motion

Joint velocity limits [°/s]	A1, A2, A3, A4: 150 A5, A6, A7: 180
Cartesian velocity limits	up to 2 m/s end effector speed
Pose repeatability	< +/- 0.1 mm (ISO 9283)
Path deviation ³	< +/- 1.25 mm

Force

Sensing ³

Force resolution	<0.05 N
Relative force accuracy	0.8 N
Force repeatability	<0.05 N
Force noise (RMS)	<0.035 N
Torque resolution	<0.02 Nm
Relative torque accuracy	0.15 Nm
Torque repeatability	<0.05 Nm
Torque noise (RMS)	<0.055 Nm

1 kHz Control ³

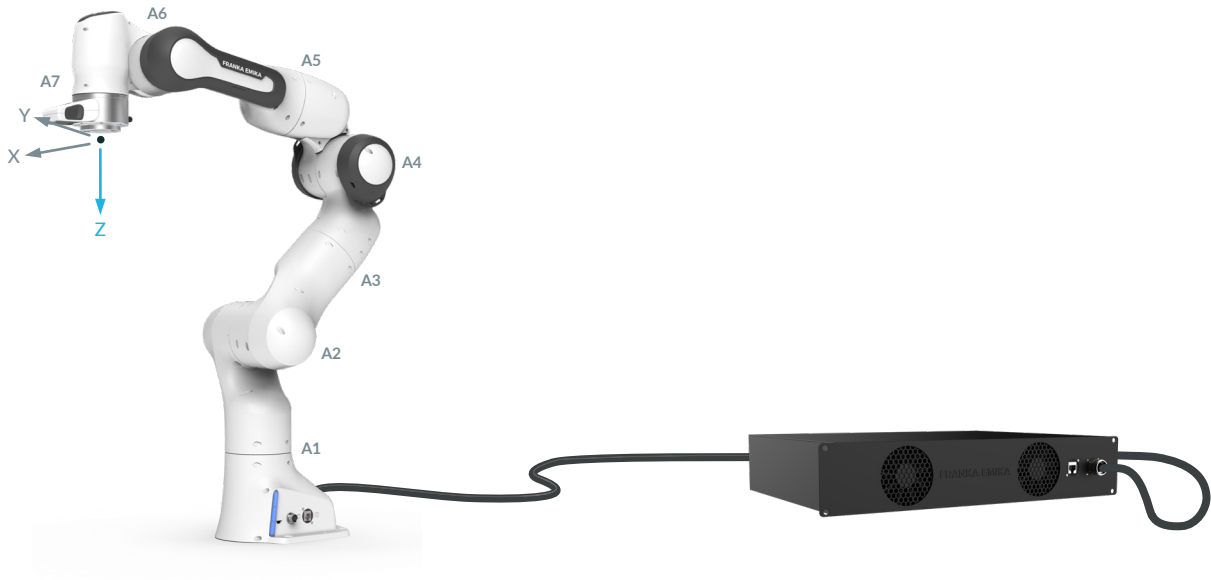
Minimum controllable force (Fz)	0.05 N
Force controller bandwidth (-3 dB)	10 Hz
Force range [N]	Nominal case Best case
Fx	-125 – 95 -150 – 115
Fy	-98 – 98 -270 – 270
Fz	-50 – 150 -115 – 155
Torque range [Nm]	Nominal case Best case
Mx	-10 – 10 -70 – 65
My	-10 – 10 -11 – 11
Mz	-10 – 10 -11 – 11

Interaction

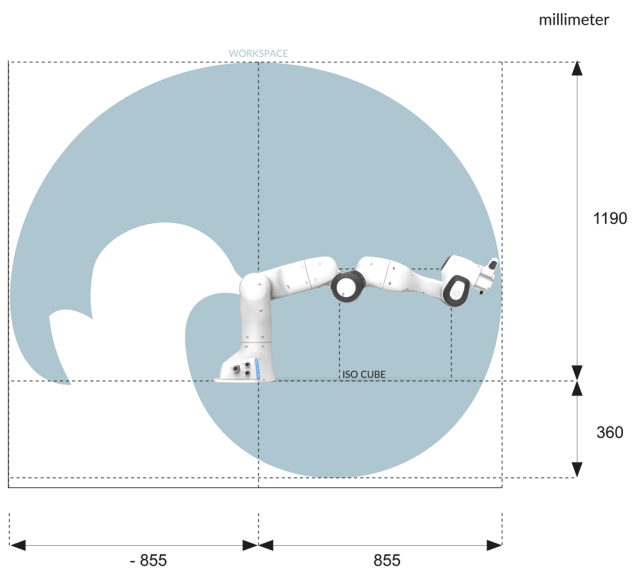
Guiding force	~ 2 N
Collision detection time	<2 ms
Nominal collision reaction time ^{3,4}	<50 ms
Worst case collision reaction time ³	<100 ms
Translational compliance / stiffness	0 – 3000 N/m
Rotational compliance / stiffness	0 – 300 Nm/rad
Monitored signals	Joint position, velocity, torque Cartesian position, velocity, force

ADD-ONS

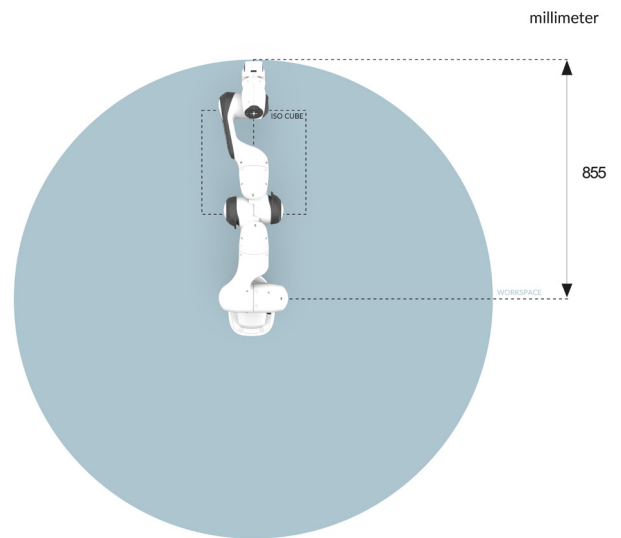
Retrofit option with safety-rated PLC	PLd Cat. 3 <ul style="list-style-type: none"> • Safe torque off (STO) • Safe OSSD inputs
Fully integrated end effectors	<ul style="list-style-type: none"> • 2-finger gripper • Vacuum gripper
Fast mounting	Panda Paw
Travelling case	Panda Case
Research interface	1kHz Franka Control Interface ⁵



Arm & Control



Workspace side-view



Workspace top-view

1. Technical data are subject to change.
2. Lifetime and performance can potentially be reduced when operating outside the typical temperature range.
3. Based on ISO 9283 (Annex A), specified values refer to a workspace of 0.4 x 0.4 x 0.4 m centered at [0.515, 0.0, 0.226] m, with the Z-Axis of the flange oriented parallel to earth-gravity and the elbow positioned upwards.
4. Nominal conditions (66% load).
5. Additional FCI license necessary.