MANIPULATING ARM
Mod. RDIDA/EV

Manipulating arm mod. RDIDA/EV is designed to grab and release pieces in two different positions. It includes a double effect cylinder to move the piece up and down, a rotary cylinder to transport the piece between the two positions and a pneumatic gripper.
Different types of sensors (magnetic / inductive) enable the identification of the arm's position and of the gripper state (close/open).

A typical working cycle is as follows. When the piece is placed on the starting point, the arm:
- Rises and turns until it is above the piece
- Lowers and grips the piece
- Rises again and makes a 180° turn
- Lowers, opens the gripper to release the piece and rises again

TRAINING PROGRAM:
- Working cycle analysis
- System I/O definition
- Process diagram
- Working cycle phases list
- Logic scheme definition
- Analysis of potential problems
- Program writing

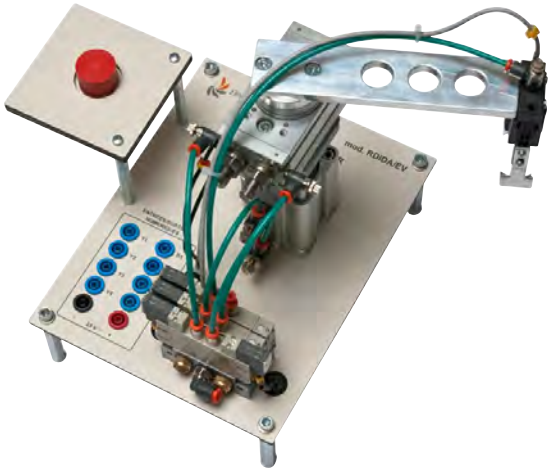
TECHNICAL SPECIFICATIONS:
Electric characteristics
- Rotary actuator with flange
- Gripper
- 1 inductive sensor
- 3 magnetic sensors
- 2 5/2 monostable electrovalves
- 1 5/2 bistable electrovalves
- 5 flow regulators
- 10 Terminals ø 4mm

Mechanic characteristics
Silk screen synoptic bakelite panel with pins.

A PLC (not included) is needed to control the process. Minimum requirements:
- 4 24Vcc digital inputs
- 4 24Vcc transistor digital outputs

Suggested PLC:
- PLC training panel mod. PLC-V7/EV to control the system.

Alternative:
- PLC training panel mod. PLC-V8/EV



Mechatronic system composed by units RDIDA/EV and TDIDA/EV

Power supply: 24 Vcc – 0.5A (from the PLC)
Dimensions: 340 x 300 x 340 mm
Net weight: 2 kg

REQUIRED
UTILITIES (PROVIDED BY THE CUSTOMER)
- Compressed Air: 4 bar

SUPPLIED WITH
THEORETICAL – EXPERIMENTAL HANDBOOK WITH SYSTEM PRESENTATION AND OPERATIONAL INSTRUCTIONS.