



Barrett Technology[®] Inc.

<http://www.barrett.com>

DATA SHEET

Barrett Technology, Inc.

625 Mount Auburn Street

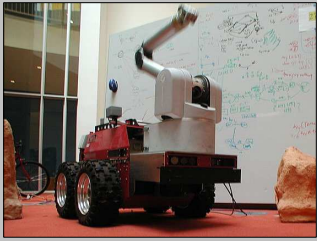
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APPLICATIONS



MOBILE PLATFORM ROBOTICS



WHOLE ARM HAPTICS
REHABILITATION
MEDICAL

FEATURES

- No controller cabinet
- Low power
- AC or DC operation
- Superb payload-to-weight ratio
- Long, slender link structure
- High backdrivability
- Direct-teach recording without force sensors, with or without power, for safety
- Cartesian force control
- Gravity compensation
- Quiet operation
- Human-like kinematics
- Highest performance S-V commutation
- Integrated current amplifiers
- Brushless motors
- Open-source C-language control software
- 1kHz motor torque control
- Upgradeable firmware
- 4-wire bus (2 power, 2 communication)
- 2 auxiliary digital I/O signals per axis
- 2 auxiliary analog input signals per axis
- Joints never locked, for safety

Force-controllable robotic arm

The WAM[™] Arm is a highly dexterous backdrivable manipulator. It is the only commercially available robotic arm with direct-drive capability supported by transparent dynamics[™] between the motors and joints, so its joint-torque control is unmatched and guaranteed stable. It is built to outperform today's conventional robots by offering extraordinary dexterity, zero backlash, and near-zero friction.

The WAM[™] Arm is available in 3 main configurations, 4-degree-of-freedom, 7-degree-of-freedom, and 4-DOF high speed, all with human-like kinematics. The joint ranges exceed those for conventional robotic arms.

All axes are driven by high-performance brushless motors, which use space-vector electronic commutation for the smoothest, most precise motions in both position and force control. Since the joints are highly backdrivable, true dynamic controls can be applied, resulting in much higher performance than is achievable with conventional manipulators. The high backdriveability enables inherent force-control, haptics, hybrid control, and teleoperation.

With its advanced and patented cabled differential, the WAM[™] Arm is the ideal platform for implementing Whole-Arm Manipulation (WAM) techniques.

To operate in and around obstacles in the workspace, the arm link surfaces are simple, smooth, and slender to prevent task interference.



“Most advanced robotic arm in the world.”

-Guinness World Records, 2000

WAM Arm

Power: 30 W

Total Mass: 25 kg

Payload Capacity: 4 kg

Combined with Whole-Arm force sensing, the WAM[™] can manipulate large, heavy objects with its large links as well as smaller objects with an attached grasper, such as the BarrettHand (shown above). Furthermore, the WAM[™] Arm will operate with industrial hands, end of arm tooling, and toolchangers.

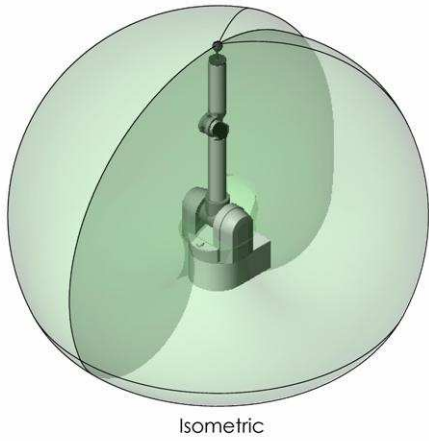
No hassle, open source software

The new WAM[™] Arm software enhances the customer's ability to learn the dynamic capabilities, key concepts and features, and extensive possibilities associated with the WAM[™] Arm. Some of the highlighted features include "Teach and Play", force control, and gravity compensation.

The "Teach and Play" software allows the user to record trajectories manually and play the same trajectories back at different speeds and accelerations with a touch of a key, even if you are not a programmer.

Force control of the robot in Cartesian space is as easy as calling a single high-level force function. If you prefer to have low-level control of the motor torques, you have access to the raw torque output functions which form the basis of the higher-level control.

The WAM[™] Arm's zero-gravity compensation permits the user to move the WAM[™] Arm in a floating motion through any trajectory.



Isometric

The Barrett WAM has a nearly spherical workspace approximately 2 meters in diameter.

SPECIFICATIONS

Input voltage	Typ	48 V
Active power	Typ	50 W
	Peak	250 W
Reach	4-DOF	1000 mm
	7-DOF	1000 mm
Payload	4-DOF	4 kg
	7-DOF	3 kg
Endtip velocity	Max	1 m/s
Mass of robot	4-DOF	25 kg
	7-DOF	27.2 kg
Work volume		3.5 m ³
Repeatability		50 μm
Total joint friction		3 Nm
Mechanical stiffness		1.5E6 N/m
Control stiffness		5000 N/m

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