



Datasheet

FRANKA RESEARCH 3

Datasheet¹ Franka Research 3

Arm (Art. No. 309969) & Control (Art. No. 295341)

Document number: R02212

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ARM (v2.1)			
Degrees of freedom	7	Interfaces	• Ethernet (TCP/IP) for programming and administration via Desk • safety-rated input for external enabling device • safety-rated input for emergency stop • 2 configurable safety-rated inputs for e.g., emergency stop devices, safeguards or other protective devices (OSSD devices via external OSSD converter connectable) • Control connector • connector for end effector
Rated payload	3 kg		
Maximum reach	855 mm		
Force/Torque sensing	link-side torque sensor in all 7 axes		
Joint position limits	A1: -166/166 deg		
	A2: -105/105 deg		
	A3: -166/166 deg		
	A4: -176/-7 deg		
	A5: -165/165 deg		
	A6: 25/265 deg		
	A7: -175/175 deg		
Joint torque limits	A1-A4: ±87 Nm A5-A7: ±12 Nm		
Mechanical interface to end effector	DIN ISO 9409-1-A50		
Installation position	upright		
Weight	~ 18.3 kg		
Ingress protection	IP40		
Ambient temperature ²	+5 °C to +45 °C		
Air humidity	20 – 80 %, non-condensing		
CONTROL		PERFORMANCE	
Rackmount form factor	19", 355 x 483 x 89 mm (D x W x H)	Motion	
Supply voltage	100 – 240 V _{AC}	Joint velocity limits	A1-A4: 150 deg/s A5-A7: 301 deg/s (FCI use, A6: 239 deg/s)
Mains frequency	50– 60 Hz	Cartesian velocity limits	up to 2 m/s at TCP
Power consumption	~ 80 W	Position repeatability ³	< +/- 0.1 mm (ISO 9283)
Active power factor correction (PFC)	yes	Interaction	
Weight	~ 7 kg	Guiding force	~ 2.5 N
Ingress Protection	IP20	Adjustable translational stiffness	10 – 3000 N/m
Ambient temperature ²	+5 °C to +45 °C	Adjustable rotational stiffness	1 – 300 Nm/rad
Air humidity	20 – 80 %, non-condensing	Monitored signals	joint position, velocity, torque cartesian position, force
Permitted mounting orientation	horizontal	ADD-ONS	
Interfaces	• ethernet (TCP/IP) for internet, shop-floor connection, fieldbuses and 1 kHz Franka Control Interface (FCI) • power connector IEC 60320C14 (V-Lock) • Arm connector	Fully integrated end effectors	• 2-finger gripper • Vacuum gripper
		Fieldbuses	• Modbus/TCP • OPC UA

1. Technical data are subject to change.
2. For more details see Product Manual Franka Research 3.
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 [0.498, 0.0, 0.226] m, with the Z-Axis of the flange oriented parallel to earth-gravity and the elbow positioned upwards.

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SAFETY			
Certification			
EN ISO 13849-1:2015 safety of machinery - safety-related parts of control systems		certified by TÜV SÜD RAIL	
EN ISO 10218-1:2011 Robots and robotic devices - safety requirements for industrial robots Part1: Robots		certified by TÜV SÜD Product Service	
Collaborative operation modes			
Monitored stop		fully integrated in PL d, Cat 3	
Hand-guiding		fully integrated in PL d, Cat 3	
Speed and separation monitoring		realizable in combination with external protective devices up to PL d, Cat 3	
Safety Functions			
Emergency Stop (X3.1)		PL d, Cat 3	
External Enabling Device (X4)		PL d, Cat 3	
Enabling Button		PL d, Cat 3	
Two configurable safe inputs (X3.2 and X3.3)		PL d, Cat 3	
SLP-C: Safely limited Cartesian position		PL d, Cat 3	note: FCI cannot control the robot while SLP-C is active
SLS-C: Safely limited Cartesian speed		PL d, Cat 3	note: FCI cannot control the robot while SLS-C is active
SLP-J: Safely limited joint angle		PL d, Cat 3	
SLS-J: Safely limited joint speed		PL d, Cat 3	
SLD: Safely limited distance		PL d, Cat 3	
SEEPO: Safe End Effector Power off		PL b, Cat b	
Stopping Functions			
Category 0 stop		PL d, Cat 3	
Category 1 stop		PL d, Cat 3	
Category 2 stop		PL d, Cat 3	
Worst case safe Cartesian position accuracy for stopping functions		50 mm	
Safety values according to EN ISO 13849-1			
PFH of PL d, Cat 3 safety functions (Probability of Failures per Hour)		$< 1 \times 10^{-7}$	
PFH of PL b, Cat b safety functions (Probability of Failures per Hour)		$< 1 \times 10^{-7}$	

DIMENSIONS & WORKSPACE

