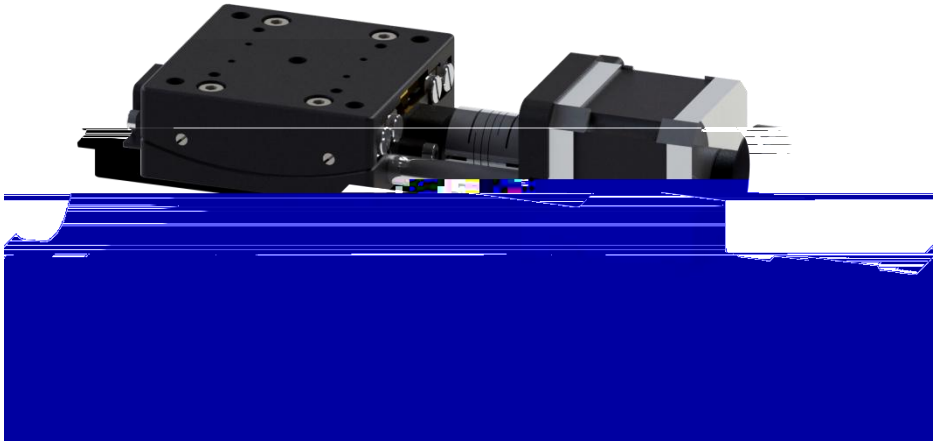
Npmbsar Glqrpsargml K_ls_j

DKQ?43



Qgafs_l Dcglgvq Rcaflmjmew Am,* Jrb

1 1
2 3
2.1 3
2.2 4
2.3 5
2.4 6
3 7
3.1 7
3.2 10
4 11
4.1 11
4.2 12
4.3 12
4.4 13
4.5 14
5 15
5.1 15
5.2 15
5.3 15
6 16

1





"H Ψ

Bv ħ



20

1

2

FMSA65 ±15°

X

2.1

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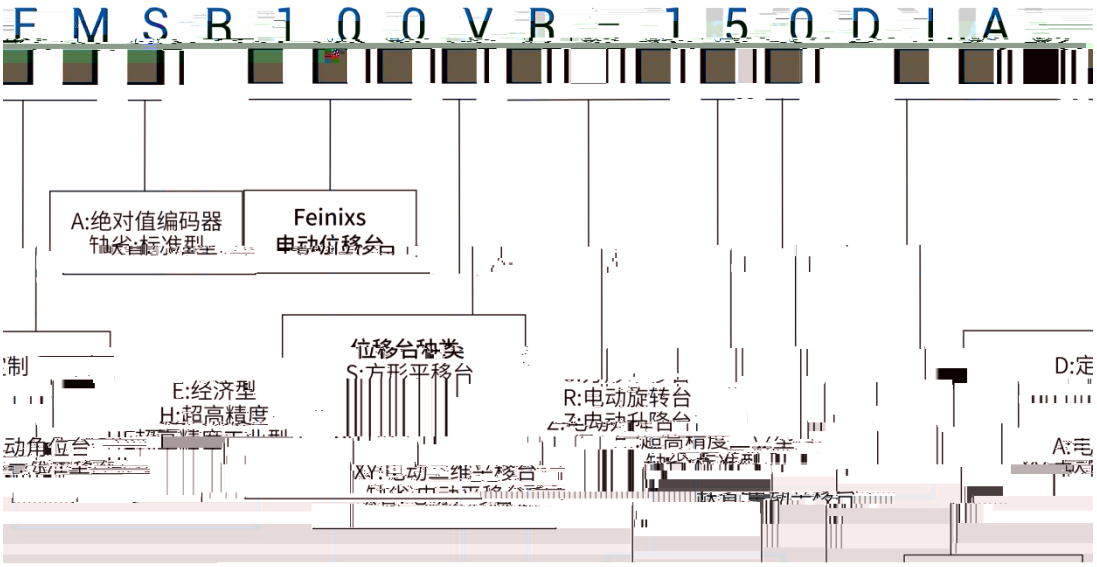
±10° ±15°

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· SDK

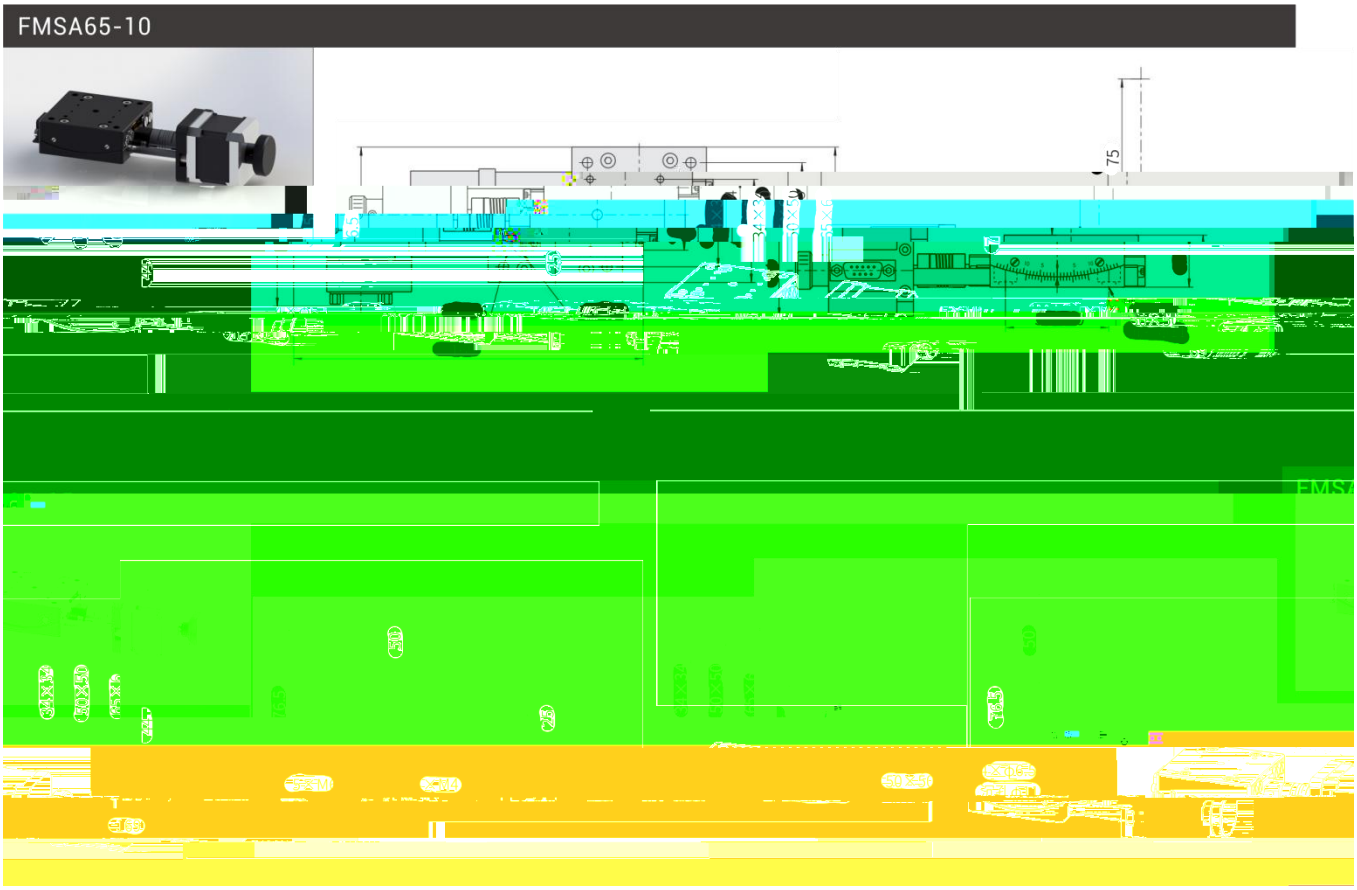
Window Linux C/C++ C# Matlab LabVIEW

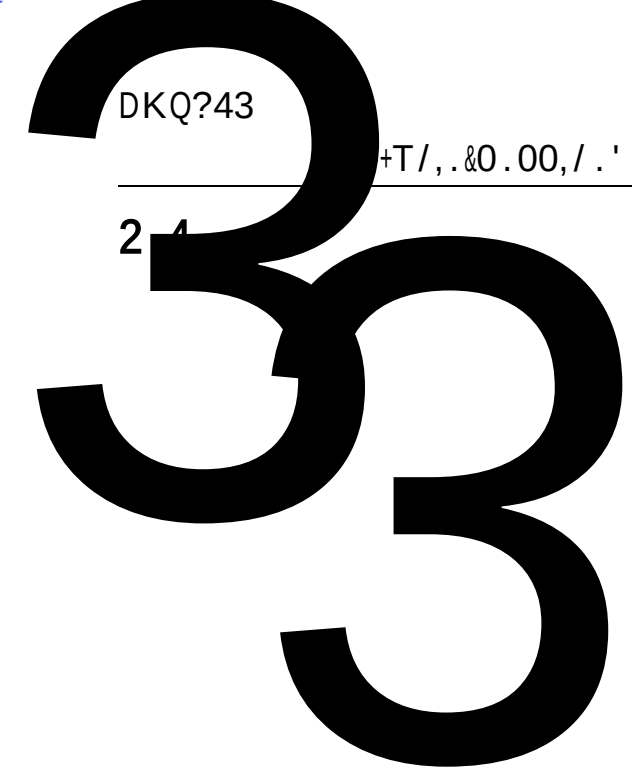
2.2



：FMSA65-10 + 65mm+ + + ±10°

2.3

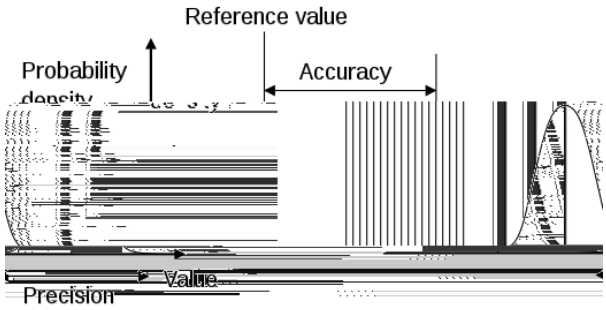




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3

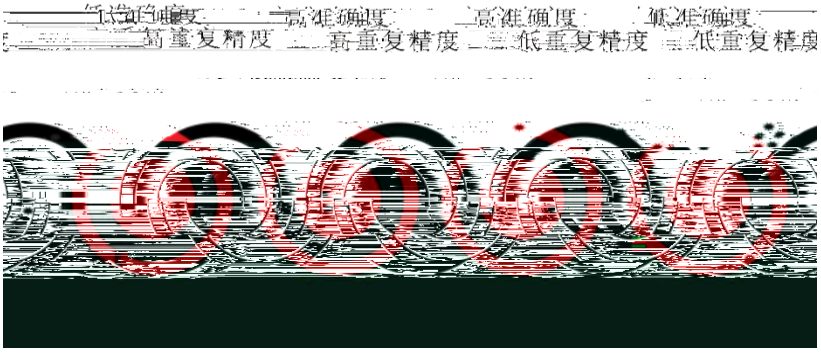
3.1



Feinixs

1

Feinixs



1.

1

1

- -

Pitch Yaw

2

XYZ X

Z Y

X (Roll) Y

(Pitch Z (Yaw) 2(a)

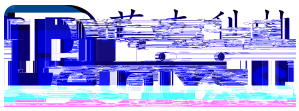
X Y Z

Y Y Z

Y (Straightness Z

(Flatness) 2

2.



3.2

Model	FMSA65-10	FMSA65-15
Travel(°)	±10	±15
Load Capacity(Kg)[1]	4	4
Resolution(°)	0.00032	0.00045
Min.Incremental Motion(°)[2]	0.005	0.005
Undirection Repeatability[3]/Guaranteed(°)[4]	±0.005 or 0.01	±0.005 or 0.01
Undirection Repeatability/Typical(°)	±0.003 or 0.006	±0.003 or 0.006
Bi-Directional Repeatability/Guaranteed(°)	±0.01 or 0.02	±0.01 or 0.02
Bi-Directional Repeatability/Typical(°)	±0.005 or 0.01	±0.005 or 0.01
Accuracy[3]/Guaranteed(°)	±0.05 or 0.1	±0.05 or 0.1
Accuracy/Typical(°)	±0.03 or 0.06	±0.03 or 0.06
Max.Speed(°/s)[5]	5	7
Weight(kg)	0.6	0.6

[1]

[2]

[3]

GB/T17421-2000

[4]

[5]

4

4.1

4.1.1

4.1.2

4.1.3

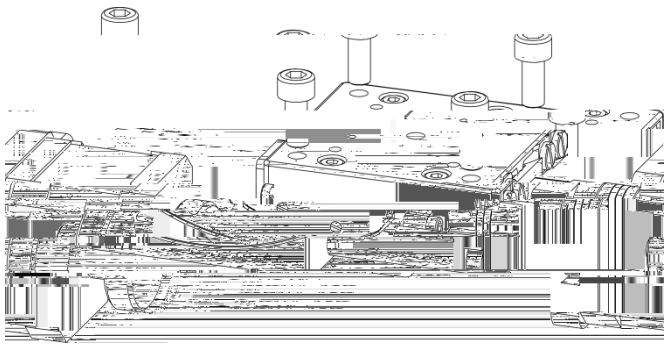
4.1.4

4.2

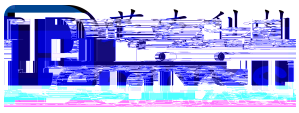
Electric wiring diagram		
DB9		
	1	24V+
	2	
	3	
	4	
	5	24V-
	6	A+
	7	A-
	8	B+
	9	B-

4.3

FMSA65 M6



(2.3)



4.5

4.5.1

4.5.2

4.5.3 FMC01

5

5.1

5.1.1 3 1

5.1.2

5.2

5.2.1

5.2.2

5.2.3

5.2.4

5.2.5

5.2.6

5.3

		0

6

6.1

A

B

C

D

E

F

6.2

6.3

6.4

6.5

6.6

: 111
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