



OTC DAIHEN EUROPE

**Roboter – Technische Daten  
Manipulator Specifications**

**FD-V6S**

Model		<b>FD-V6S</b>	
Kinematic		Vertical artic. type	
No. of Axes		7	
P-Point (Working Range)		R 1,427 mm	
Maximum Payload Capacity		6 kg	
Positional Repeatability(*1)		± 0.08 mm	
Driving Method		AC Servo Motor	
Working Range	Arm	J1 (Rotation)	± 170°
		J2 (Vertical)	-145° ~ +70°
		J7	± 90°
	Wrist	J3* (Rotation)	-170° ~ +149°
		J4 (Rotation)	± 180°
		J5 (Bending)	-50° ~ +230°
		J6 (Rotation)	± 360°
Maximum Speed	Arm	J1 (Rotation)	210°/s
		J2 (Vertical)	210°/s
		J7	180°/s
	Wrist	J3* (Rotation)	210°/s
		J4 (Rotation)	420°/s
		J5 (Bending)	420°/s
		J6 (Rotation)	620°/s
Maximum Payload	Allowable Moment	J1 (Rotation)	11.8 Nm
		J2 (Vertical)	9.8 Nm
		J3* (Rotation)	5.9 Nm
		J4 (Rotation)	0.30 kg/m <sup>2</sup>
		J5 (Bending)	0.25 kg/m <sup>2</sup>
		J6 (Rotation)	0.06 kg/m <sup>2</sup>
Ambient Temp./Humidity		0 ~ 45°, 20 ~ 80%	
Mass (weight)		178 kg	
Upper arm max. Carrying capacity(*2)		10 kg (Note 3)	
Origin Return		Note 3	
Installation Position		Floor type	



J3\* (Rotation): A combined rotation of the axes J2 and J3

Note 1: Measured value obtained after sufficient repetition of automatic operation for stabilizing conditions.

Note 2: When the output flange of the wrist axis is loaded with maximum payload capacity.

Note 3: Positional data protected by battery-backed storage inside the manipulator.

F = Floor W = Wall C = Ceiling

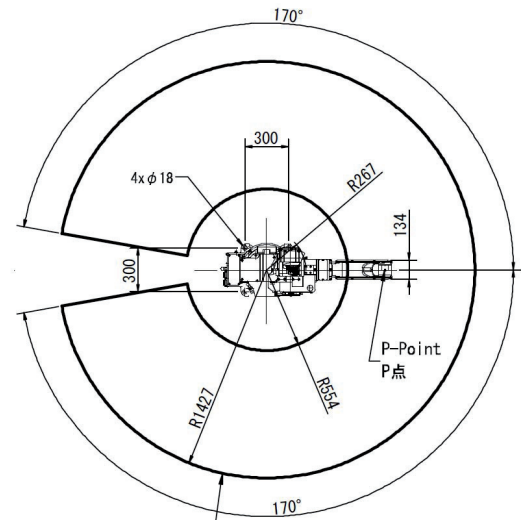


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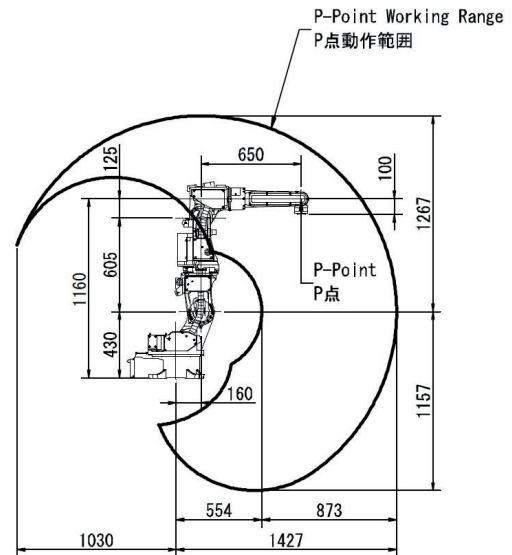
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P-Point Working Range  
P点動作範囲



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