

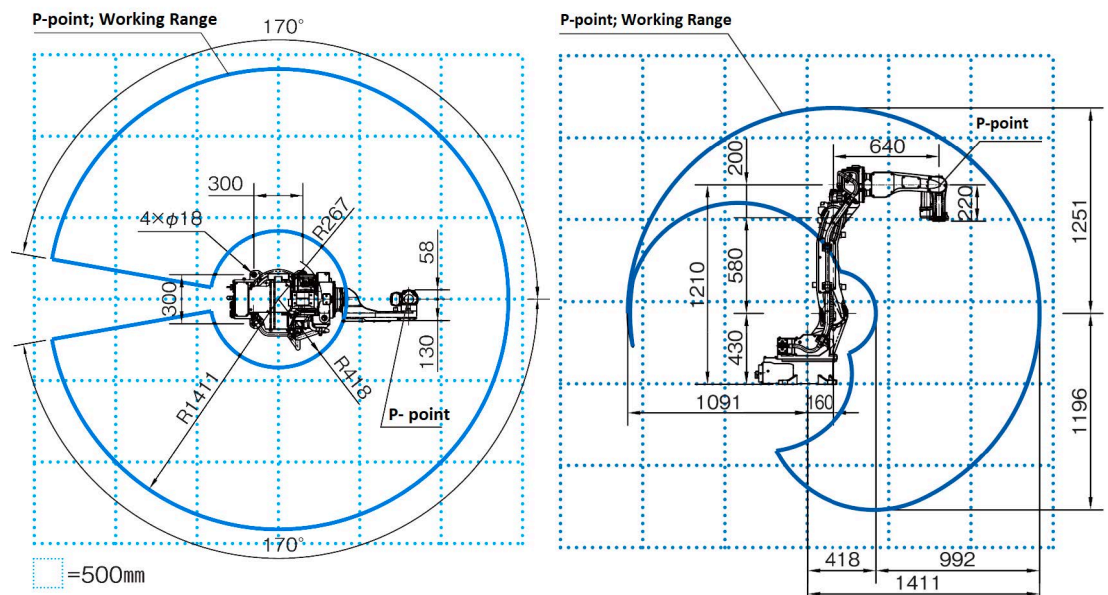
FD-B4

Simple & slim arm shape

- Cable built-in mechanism prevents cable hook during robot operation.
- By reducing the turning area of the robot, it can be installed in a narrower space than before.



[Manipulator operating range diagram]



[Manipulator specifications]

		FD-B4
Construction		Vertical multi-joint
Number of axes		6
Payload		4kg
Position repeatability		±0.08mm(Note 1)
Driving method		AC Servomotor
Driving capacity		2550W
Position feedback		Absolute value encoder
Working range	Arm	J1(Rotation1) ±170° (±50°) (Note 2)
		J2(Lower arm) -155° ~+90°
		J7(Rotation2) -
		J3(Upper arm) -170° ~+180°
	Wrist	J4(Swing) ±155°
		J5(Bending) -45° ~+225° (Note 3)
Maximum speed	Arm	J1(Rotation1) 3.66rad/s[210°/s] (3.32rad/s[190°/s]) (Note 2)
		J2(Upper arm) 3.66rad/s[210°/s]
		J7(Rotation2) -
		J3(Upper arm) 3.66rad/s[210°/s]
	Wrist	J4(Swing) 7.33rad/s[420°/s]
		J6(Twist) 10.5rad/s[600°/s]

		FD-B4
Wrist Allowable Load	Allowable Moment	J4(Swing) 10.1N · m
		J5(Bending) 10.1N · m
		J6(Twist) 2.94N · m
	Allowable Moment of inertia	J4(Swing) 0.38kg · m ²
		J5(Bending) 0.38kg · m ²
		J6(Twist) 0.03kg · m ²
Arm Cross-sectional Area		2.94m ² × 340°
Ambient Conditions		Temp : 0~45°C, Hmd: 20~80% RH (No condensation)
Mass (weight)		154kg
Upper Arm Payload Capacity		10kg(注4)
Installation Type		Floor, wall, or ceiling
Paint Color		White (Munsell notation 10GY 9/1)

Note) 1 Repeatability accuracy is in conformity with JIS - B - 8 4 3 2.

It is the value at the standard tool center point (T.C.P.).

2. () The value is the specification at the time of hanging.

3) The operation range of the 6 axis may be controlled by the attitude of J 5 axis. 4. When the maximum allowable load carrying capacity is loaded as an end effector.

※ This use is subject to change without notice.

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