



OTC DAIHEN EUROPE

**Roboter – Technische Daten  
Manipulator Specifications**

**FD-MR35**

Model		<b>FD-MR35</b>	
Kinematic		Vertical artic. type	
No. of Axes		7	
P-Point (Working Range)		R 2,050 mm	
Maximum Payload Capacity		35 kg	
Positional Repeatability(*1)		± 0.07 mm	
Driving Method		AC Servo Motor	
Working Range	Arm	J1 (Rotation)	± 165°
		J2 (Vertical)	+55° ≈ -120°
		J3* (Rotation)	+140° ≈ -146°
	Wrist	J4 (Rotation)	± 360°
		J5 (Bending)	± 125°
		J6 (Rotation)	± 450°
		J7	± 190°
Maximum Speed	Arm	J1 (Rotation)	180°/s
		J2 (Vertical)	175°/s
		J3* (Rotation)	180°/s
	Wrist	J4 (Rotation)	305°/s
		J5 (Bending)	305°/s
		J6 (Rotation)	420°/s
		J7	130°/s
Maximum Payload	Allowable Moment	J4 (Rotation)	160 Nm
		J5 (Vertical)	160 Nm
		J6 (Rotation)	90 Nm
	Allowable Payload	J4 (Rotation)	16.00 kg/m <sup>2</sup>
		J5 (Bending)	16.00 kg/m <sup>2</sup>
		J6 (Rotation)	5.00 kg/m <sup>2</sup>
Ambient Temp./Humidity		0 ≈ 45°	
Mass (weight)		745 kg	
Upper arm max. Carrying capacity(*2)		15 kg	
Origin Return		Note 3	
Installation Position		F	



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

