



OTC DAIHEN EUROPE

**Roboter – Technische Daten**  
**Manipulator Specifications**

**FD-V6**

Model		<b>FD-V6</b>	
Kinematic		Vertical artic. type	
No. of Axes		6	
P-Point (Working Range)		R 1,402 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)	-155° ≈ +90°
		J7	
	Wrist	J3 (Rotation)	-170° ≈ +190°
		J4 (Rotation)	± 180°
		J5 (Bending)	-50° ≈ +230°
Maximum Speed	Arm	J6 (Rotation)	± 360°
		J1 (Rotation)	210°/s
		J2 (Vertical)	210°/s
	Wrist	J7	
		J3 (Rotation)	210°/s
		J4 (Rotation)	420°/s
Maximum Payload	Allowable Moment	J5 (Bending)	420°/s
		J6 (Rotation)	620°/s
		J1 (Rotation)	11.8 Nm
		J2 (Vertical)	9.8 Nm
		J3 (Rotation)	5.9 Nm
		J4 (Rotation)	0.30 kg/m <sup>2</sup>
Ambient Temp./Humidity		0 ≈ 45°, 20 ≈ 80%	
Mass (weight)		144 kg	
Upper arm max. Carrying capacity(*2)		10 kg (Note 2)	
Origin Return		Note 3	
Installation Position		F, W, C	



- 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

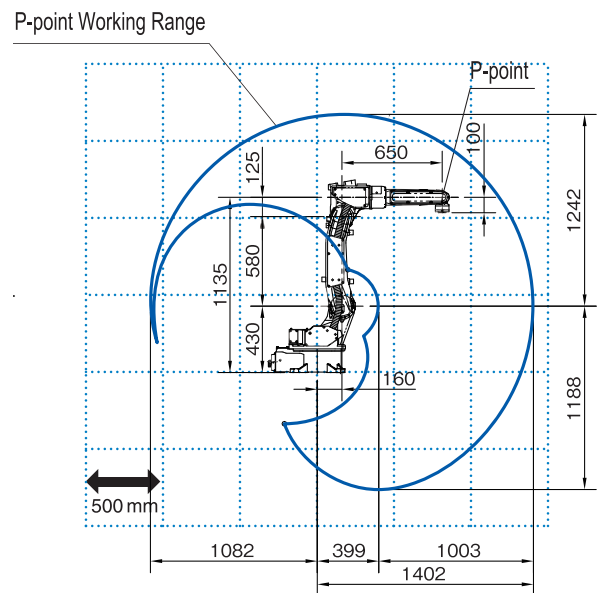
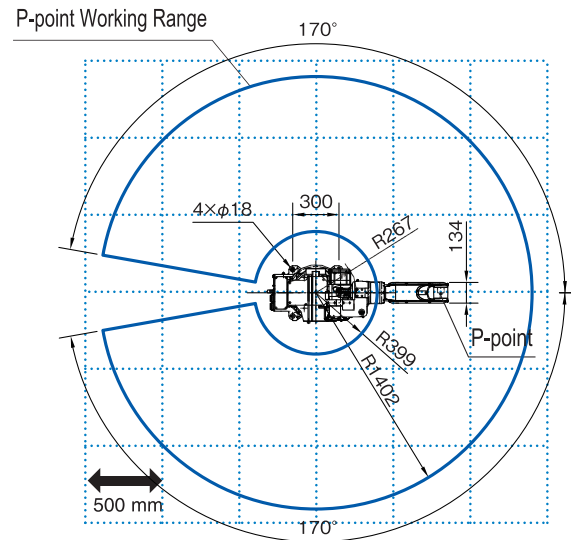


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	J3 (Rotation)	-170° ≈ +190°
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	J1 (Rotation)	210°/s
	J2 (Vertical)	210°/s
	J7	
	Wrist	
	J3 (Rotation)	210°/s
Maximum Payload	Allowable Moment	
	J1 (Rotation)	11.8 Nm
	J2 (Vertical)	9.8 Nm
	J3 (Rotation)	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)	144 kg	
Upper arm max. Carrying capacity(*2)	10 kg (Note 2)	
Origin Return	Note 3	
Installation Position	F, W, C	



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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