	e of company/ ertment in charge	Na lot	Dainichi Kiko Co., Ltd.			Address/ Telephone		5-13, Nishi- el. (03) 34	shinjuku, 6-chor 8-6311	ne, Shinjul	cu-ku, Tokyo
Mod	el Name	ROBO	SKY SD-250	Main applications	Hear	vy duty ha	indling, palle ange	Weight	of robot itself	Robore	Model Name
			ut information teaching mode	Variable sequence	ce robot		odor tossi	Degree of moti	of freedom on	ognie a	
Class	ification		tion form	Cylindrical coord	dinates 1	robot	roos testala	Load ca	pacity	250 kg	
	Axes	936	Operating space	Speed			Axes	101	Operating s	space	Speed
	Right-left trav	verse	°0E 30°	edwa riel-rigiff.			Right-left s	wing	350 mm	0210	en stollingin en
	Right-left turn	ning	350°	Up-down swaller			Up-down s	wing		gn	Right-left turn
	Up-down trav	erse	9	Right left trailers		Hand	Right-left t	raverse	300 mm	481	up-down trav
Arm	Up-down turn	ing	210°	(dp-down travers			Up-down to	raverse		04	muf nwab-qU
	In-out			Revolution			Revolution				Juo-nl
	Revolution		120°	Clamp	-m-1	Fin- ger	Clamp		585°		Revolution
	Travelling			- Plemarks			Remarks				Travelling
	peatability sitioning precision	on)	7°04 - °0	0.5 mm	Alfa Rico	Allow condi	vable environ tions	mental	B10 mags	$0^{\circ} \text{C} \sim 40^{\circ}$	Repeatability (Positioning preci
	Sequential me	ode		Sequential mode			Sequential	mode	Matrix switch		
ng contro ion	Positioning Miscellany Power-External		Hydraulics, Pneuma DC servo motor	tics,	envertice.	Teaching functions	Position an	d speed	Positioning D.C. servo		Positioning
funct			P.T.P.	Memory mode	goldbe	eaching f	Memory me	ode	E trans		Miscellany
Po	ower-External -Internal	RAM 2	EN SE MON	Memory capacity		۲	Memory ca	pacity	1000 steps		Power-External - Insural
	ternal measuring		Potentiometer	- Vestleori	NA .	Mis	cellany	151	Optical anco		Internal measuring
	kternal measurin ecognizing abilit			uxillary Juget) ops, otrops etc.	A to		kiliary functi ions etc.	ons,	"Profiling se "Are sensor"		External measurin Recognizing abilit
	Outward f	igure	Characteristics of the	Operation spa	ce	9596	Obsertion s	Cha	aracteristics of th	ne robot	l briowatuO
(plan)		system, a sensor a se					(bal mar exte sligh 2. The to f	ance)", a finipulators, ernal motion test extern nongravita follow up ev	unction not end which enables the on and acts faithen all force.	owed with his to react fully in res	ravitational state the conventional sharply to the ponse to the enables this robot xternal machines,
(side vi	iew)	n be acom									
			B		SD-2		A B 570 960	C D	#600000 # 1		
								1925 2450			
								-	+		

Mod	el Name	RORO	OSKY SD-350	Main	Heavy duty	handling, pal-	Weight o	of robot itself	OROSI	ernsVI labati
Wida	or reality	-	out information	applications	letizing, to	ol changing		f freedom	udni s	
Class	ification	and	d teaching mode	Variable sequence		valuable sequen	of motio	n tiom gnidaes	bns	350 kg
	101.076	b. Mo	tion form	Cylindrical coord	linates robot	soos (sombil) (CS	Load cap	pacity		
	Axes	806	Operating space			Axes	8366	Operating s	pace	Speed
	Right-left tra	verse	081	- Bightsleit swing		Right-left sw		21907	9239	van stell/dpilk.c.
	Right-left tur		180°	grove awabadi/		Up-down sw		2008	900	mit flebrisht tim
Arm -	Up-down trav			Alght (eff 14) erse	Hand	Right-left tra			961	tip-down traw
	Up-down turi	ning	210°	Up-down traverse		Up-down tra	verse		QR	mut nwoh-qU
	In-out		00	hoituloys8	and Fin-	Revolution				PRINCE ADDS
	Revolution		90°	gmsl3	ger	Clamp				neitulovaR
	Travelling		300 mm	Remarks		Remarks				gnilleverT
	peatability sitioning precisi	on)		± 0.5 mm		owable environn ditions	nental	6 Stroke 10	0°C ~	40°C
	Sequential m	ode	alwa xanaMa 🕳 🗀	Sequential mode.		Sequential m	node			
function	Positioning		Hydraulic, DC se	rvo motor	Teaching functions	Position and	speed	Hydraulics	lessi es Lesso de	Positioning
func	Miscellany		P.T.P.		aching	Memory mod	de			
P	ower-External -Internal		Potentiometer	Mediciny capitaty	Teg	Memory cap	acity	250 steps	1900	Jamesty 3-rawo 1 Jamesty 1
	ternal measuring	9		Miscellany S.J. The	N	liscellany		File Service		tribernal nessuring
	xternal measurir ecognizing abilit			A gallery functions.		uxiliary function	ns,	100 pt 100	000 C 11 N	External massuring Racognizing abili n
	Outward	figure	Characteristics of th	Operation space	ce	о полачео	Chai	racteristics of th	ne robot	if breward
(plan)	and materials of the second		A	Jon all 15		(bala mani exter lighte	nce)", a fu pulators, v nal motion est externa	nction not end which enables the nand acts faithful force. tional state pro- indefinite moti-	owed with his to react fully in res	gravitational state in the conventional t sharply to the sponse to the c enables this robot t ternal machines,
				SD-35	A 50-51 2230	B C D	-			

	e of company/ artment in charge	Sloanjul	Dainichi Kiko Co., Ltd.	16-E3-3 06 Tel: (0	Addres Teleph			13, Nishi . (03) 34	-shinjuku, 6-chor 48-6311	ne, Shinj	juku-ku, Tokyo
Mod	del Name	ROB	OSKY SD-500	Main applications	Heavy duty letizing, to	handling, p	al-	Weight	of robot itself	ROBOS	amel/ (abo
			nput information and teaching mode	Variable sequenc	ce robot	ale sequentia	10	Degree of moti	of freedom	ont a	
Class	sification		lotion form	Cylindrical coord	dinates robot	broos issort	4 10	-	pacity	2000	
	Axes	184.80	Operating space	Speed		Axe	s	777838	Operating s	pace	Speed
	Right-left trav	erse		Rightleft svang		Right-le	eft sw	ing	180°	561	Alghi lott trave
	Right-left turr	ning	300°	grisys nwab-gU		Up-dow	n swi	ng	081	gni	Piget-left turi
	Up-down trave	erse	97	Right left traffer	based Hand	Right-le	ft tra	verse		921	Up-down travi
Arm	Up-down turn	ing	32	Up-down traver		Up-dow	n trav	verse	210°	gri	turus mwobiqti
	In-out			Revolution		Revolut	ion		90°		live-al
	Revolution			Clamp	Fin- ger	Clamp			90%		Revolution
	Travelling			Remarks		Remark	s		300 mm		griffeyarT
	peatability sitioning precisio	n)	Stroke: ± 0.5% ~ 2	%		owable envi nditions	ronme	ental		0°C ~ 4	-0°C
0	Sequential mo	de		Supplement mod	S	Sequent	ial mo	ode	Matrix switc	h	om fannagas?
function	Positioning		Hydraulics, DC-serv	o motor	Teaching functions	Position	and s	peed	Hydrautic, E		Postioning
funci	Miscellany		P.T.P. (C-P)	Memory mode	aching f	Memory	mode	9	P.C.P.		Miscellany
Po	wer-External -Internal		Potentiometer	Memory capav		Memory	capad	city	32 steps		PowerExternal
	ternal measuring			y radina M	N	liscellany					internal medaulog
	ternal measuring cognizing ability			Anxiliar y Tunetions optimise to		uxiliary fun	ctions	5,		**************************************	e steinst tileasurin Recognising abiliti
	Outward fig	jure	on To enamed wiedl?	Operation space	е	a nonciae		Char	racteristics of the	robot	F brawh/O
(plan)	the land in lives up to the land of warder or sample or	ton" 13 med we				2. T	baland nanipu xterna lightes The no	ce)", a fuulators, wal motion st externation on gravitatow up even	nction not endown thich enables this and acts faithful force.	wed with to react lly in res	gravitational state in the conventional sharply to the sponse to the enables this robot external machines,
			B	S	SD-500-51	A B 2960 1440 3780 1920 4600 2400	C 2200 2750 3300	3500			

	of company/ ment in charg	e I	Dainichi Kiko C	o., Ltd.	Telephio	e N	akakoma- 5528(2)5	gun, Yamana 581	mplex, ashi	Kosaimachi,
Model	Name	BA-14	40 / 921 lades la 161	Main applications	Handling ing, asso	palletiz embly, loa arc weldir	ad-Weight	of robot itself	800kg	Model Name
			ut information teaching mode	Playback rob		lyback ro		f freedom	6	
Classifi	cation		tion form	Cylindrical	coordinates	robot	Load cap	pacity	50kg	(Max.)
	Axes	906.	Operating space	Speed		Axes	9950	Operating s	pace	Speed
	Right-left tra	verse	*081± 110°	- Right dolt sweep		Right-left s	wing	±150°	11218	60°/sec
	Right-left tur	ning	±150°	60°/sec		Up-down s	wing	±60°	gnl	60°/sec
	Up-down trav	verse	700mm	600mm/s	ec Hand	Right-left t	traverse	133008	ben	VER down trav
Arm —	Up-down tur	ning	- 5	Up down traver		Up-down to	raverse		-80	mut awah qU
	In-out		100mm	600mm/s	ec	Revolution	le le	±90°		60°/sec
	Revolution			ems(0)	Fin- ger	Clamp				neituloveR
	Travelling			ShamaH		Remarks				griffeverT
	atability tioning precisi	ion)	±0.5mm	lowable controllnent hthBons		wable enviror ditions	nmental	0 - 45	5°C	Repeatability Positioning precision
0	Sequential m	node	Microcomputer	Sequential mode	S	Sequential	mode			with input ching box
Moving control function	Positioning	o beags Slevel	Electric DC s	ervo	unction	Position an	d speed	- do -, s	speed c levels	an be set at
funct	Miscellany		CP control/vaing functions	rious interpol	r - Teaching functions	Memory m	ode	IC memory	7	Miscollary
Pov	wer-External -Internal	x840 .ad	AC200/220V 50 6.5kg/cm ² G 3		h P	Memory ca	pacity	1000 step	s (Max	.3000 steps)
Inte	ernal measurin lity	g	Optical shaft	encoder	М	iscellany	naft end	PTP teach	ning	Internal measuring ability
	ternal measuring		ell-liss	Auxiliary functions, options etc.		uxiliary functi otions etc.	ions,	Self-dia	gnostic	function
	Outward	figure	Charattainana of th	Operation spa	ce	Operational	Cha	racteristics of th	ne robot) hiemfoO
(side vie	ew)	1207 (12	300 (3) 300 (3) 300 (3) 300 (3) 300 (3) 300 (3) 300 (3)	SHOOL STANDARD STANDA		2. The state of th	upports ieces by nergy-sa obot to ith smal he high- talled i ioning p he balan o move a o 50kg. he robot oves fle ork. he direc alancing	the gravity air pressiving effect be easily of driving a performance in the robot recision (scing funct; heavy world has a "mustibly to post teaching	y of thure. To the control of the co	function that e arm and work his produces mitting the d by a motor ervomotor in- es high posi bles the robot weighing up system that any type of l using the lies the work

	ne of company/ partment in charge	D.	ainichi Kiko Co	., Ltd.	Address, Telepho	ne Nak	ai Indu akoma-g 28(2)55	strial Com un, Yamana 81	plex, K shi	Kosaimachi,
Mo	del Name	BA-26	00 (163) 30/01 10 3/10	Main applications		, palletiz welding	Weight	of robot itself	1100k	rg
			ut information teaching mode	Playback rob	oot for	Spack rol	Degree of motion	of freedom	6	
Clas	sification		tion form	Cylindrical	coordinate	s robot	Load ca	pacity	100kg	g(Max.)
	Axes	9011	Operating space	Speed		Axes	00160	Operating s	space	Speed
	Right-left trav	verse	±150°	grawa that telpiff		Right-left s	ving	±150°	5215	60°/sec
	Right-left turi	ning	±135°	60°/sec		Up-down sv	ving	+30° -	-90°	60°/sec
	Up-down trav	erse	1330mm	600mm/se	ec Hand	Right-left to	averse	ZOOnan	9216	Updawn tree
Arm	Up-down turn	ing	01	Updown trater		Up-down tr	averse	40	profe	Trut neoli qU
	In-out		1480mm	600mm/se	ec 393	Revolution		±90°		60°/sec
	Revolution			Clamp	Fin- ger	Clamp				Revolution
	Travelling			Remarks-		Remarks				Travelling
	peatability ositioning precision	on)	±1.0mm	nemonivas sidisvali maltions		owable environi ditions	mental	0 - 4	5°C	Reprodukty of G Positioning precision
ō	Sequential mo	ode	Microcomputer	Sequentist mod	v	Sequential r	node			with input aching box
Moving control function	Positioning	peed c levels	Electric DC se	ervo montanti	Teaching functions	Position and	speed	- do -, any of 8		an be set at
Movii	Miscellany		CP control/varing functions	rious interpol	at- guild	Memory mo	de	IC memor	у	ynaffscailt
Р	ower-External -Internal	xsM) a	AC200/220V 50, 6.5kg/cm ² G 15		P P	Memory cap	acity	1000 ste	ps (Max	.3000 steps)
	nternal measuring pility	gnl	Optical shaft	encoder week	М	iscellany	naft en	PTP teac	hing	Angered teasures
	xternal measuring ecognizing ability		mib-ligh	Auxiliary functions, options sic.		uxiliary function	ns,	Self-dia	gnostic	function
	Outward fi	igure	Characteristics of 4	Operation space	e son	Operation up	Cha	racteristics of th	ne robot	Datwied
(side v	function the produce of the produce the pr	(1) (Kr.) 86(C				rob or 100 2. A c ele rob wor 3. Thi an 4. The thi ele giv 5. Dir	ot suit spot we kg or 1 ombinat ctric s ot to e k that s cylin extensi balanc s syste ctric p en weig ect tea	ess. ion of pneervo system sure accur has to be drical coo ve, useful ing functi m helps re ower to mo	recision or kpied umatic mais us rate per done at operation inconduce the vera wo	n handling ces weighing power and sed for the erformance of a high speed a robot has ing space. Proporated in the required orkpiece of

	ne of company/ artment in charg	е	Dainichi Kiko Co	o., Ltd.	Address/ Telephor	ne Nak		ustrial Comp gun, Yamanas 581		saimachi,
Мо	del Name	BA-4	4700	Main applications	Heavy du handling	ty materia , palletiz	Weight	of robot itself	32001	cg omstillsbold
Ol-	-16141		nput information nd teaching mode	Playback robo	tos sonsup	alable se	Degree of moti	of freedom on	6	
Clas	sification	b. N	Notion form	Cylindrical o	coordinates	robot	Load ca	apacity	350kg(Max.)	
	Axes	90	Operating space	Speed		Axes	806	Operating s	pace	Speed
	Right-left tra	verse	100000	enwestelseine	299	Right-left s	wing	mm00±135°	52487	45°/sec
	Right-left tur	ning	±135°	40°/sec	2	Up-down sv	wing	±60°	gine	45°/sec
	Up-down trav	verse	1350mm	400mm/s	sec Hand	Right-left to	raverse		Saya	Ubidovn tra
Arm	Up-down turn	ning	1	Up down travers		Up-down tr	averse		901	Up-down ton
	In-out		1480mm	400mm/s	sec	Revolution		180°		45°/sec
	Revolution		10 mg 1 mg 1 mg 1	- attento	Fin- ger	Clamp				netiutoveA
	Travelling	rd sid	ve bna goiwe w	anemak)		Remarks				entlever
	peatability ositioning precisi	on)	±1.0r	mm anathba		wable environ	mental	0	- 45°C	Repensability (Postsiqualne pregistr
5	Sequential m	ode	Microcomputer	Sequential mode	S	Sequential r	mode	Direct tea		with input hing box
Moving control function	Positioning		Electric DC se	ervo	Suriting functions	Position and	d speed	- do -, sp		n be set at
funct	Miscellany		CP control/var	cious interpola	ting build	Memory mo	ode	IC memory		yestloosiM E
Р	ower-External		AC200/220V 50/ 7.0kg/cm ² G 60		H H	Memory cap	pacity	1000 steps	s (Max.	3000 steps)
	nternal measuring bility	9	Optical shaft	encoder Maria	М	scellany		PTP teach	ing	Internal measuring ability,
	xternal measurin lecognizing abilit			Aux Bary functions, options etc.		exiliary functions etc.	ons,	Self-diagn	nostic	function
	Outward f	igure	Chara-genutics of the	Operation space	e som	Ороженов	Cha	aracteristics of th	e robot	lanwingO
(side v	1207 A	148	1300 1100 1500 1100 1500 1500 1500 1500			cia to pur 2. The the cit eff of 3. It hig wit 4. Gooc by 5. The	ally design NC No poses. It is balance robot by of 3 cicient workpie has a poses let he other the place of robot probot p	signed to fee bender or had cing function provides a 50kg, enablid ly carry and eces.	on incommaximum ing the distribution in the distribution accurate a ±1.0 mm obts. The compact is compact.	m load capa- robot to e all types cy of the m), compared e provided ly designed

	ne of company/ artment in charg		Dainichi Kiko Co.	, Ltd.	Address Telepho	one	Nak 055	ai Ind akoma- 28(2)5	ustrial Com gun, Yamana 581	nplex, K	Kosaimachi,
Mod	del Name	HANBO	T lissit redouted hip for	Main applications	Loading/ of work	unload ieces	ing	Weight	of robot itself	135kg	g words let die
		a. Int	out information	Variable sequ	ience robo	ot	Ad B	Degree of moti	of freedom on	3	
Clas	sification		d teaching mode	Cylindrical o	coordinate	s robo	t	Load ca	apacity	10kg	(Max.)
	Axes	0.00	Operating space	Speed		Α	xes	930	Operating s	space	Speed
	Right-left tra	verse	150mm	Max.600mm/se	ec ec	Righ	t-left sw	ving		9719	Right-left tran
	Right-left tu	ning	±60°	Max.90°/sec		Up-d	own sw	ing	73812575	- eni	north Witte
	Up-down tra	verse	100	ione is should storie	Hand	Righ	t-left tra	averse	te:02f1	9819	vs ir narobiqU
Arm	Up-down tur	ning		renting awab a U		Up-d	own tra	verse		gne	nur ewob qU
	In-out		450mm	Max.600mm/se	ec ec	Revo	lution		months.		Juo-al
	Revolution			n Lata gardia	Fin- ger	Clam	np				
	Travelling			Limmon		Rem	arks		Swing and hand avail		functions of y option
	peatability psitioning precisi	on)	±0.2	2mm		lowable e	nvironn	nental		0 - 45	
	Sequential m	and the	Sequential cont	rol with the	s	Sequ	ential m	node	Programmah	le con	troller
Moving control function	Positioning	ec bee	Mechanical stop	pper	unction	Posit	ion and	speed	Stopper		
Moving c function	Miscellany		(Electric serve	available by	Teaching functions	Mem	ory mod	de	CP control		vestioniti .
Р	ower-External -Internal	(3.P)	AC200/220V 50/6 6.0kg/cm ² G 300		– a	Mem	ory capa	acity	-Ad200/220		Ignore 3 - 1000 (
	nternal measurin pility	g	Massi 919	to the second		Miscellany	,		a Zwalago		
	xternal measurir ecognizing abilit		self-dias	Anatheur Jackson		Auxiliary options et		ns,			untraem laman 3 Bilde patemport A
	Outward	figure	ell to saltanon a serio	Operation space		an books	ag()	Cha	aracteristics of the	he robot	1 training
(side v		rr and	-50 -50(x)			3.	Many fere the requ Many syst ator are Some can nece All	ose, a versient mix standa diremen versient diffe tems, see, rota availa e addit be rea sssary. drivin umatic	daptable rooms are averses of modulard model, outs. The combination of	bbot. ailable les can dependi nations neumati r, and e robot and mu ned to re supp ch has	because dif- be added to ng on the user of driving c linear actu- electric serve. lti-axis hands the robot as lied by the a simple mecha- maintenance.

	ne of company/ artment in charg	je .	Dainichi Kiko C		Address/ Telepho	ne Na 05	kakoma- 528(2)5		nplex, i	Kosaimachi,
Mod	del Name	PALE	ВОТ 150	Main Pagarant Pagaran	lletizing/ g, sorting ass, and s jects	by type a eparation	nd Weight	of robot itself	1800	kg malf tehold
			put information nd teaching mode	Playback robo		yback ro		of freedom	4 8	
Clas	sification	b. M	otion form	Cartesian coor	rdinates r	obot	Load ca	apacity	150k	g(Max.)
	Axes	100	Operating space	Speed		Axes	200	Operating	space	Speed
	Right-left tra	averse	1600mm	600mm/s	ec	Right-left s	wing	*00±	gnias	1 Halangin
	Right-left tu	rning		griez resebigU		Up-down s	wing	*65*	- pro	na Nebragia
۸	Up-down tra	verse	1000mm	600mm/se	ec Hand	Right-left t	raverse	mm021	821	Up-down trail
Arm	Up-down tur	ning		Clordoven trainers		Up-down to	raverse		90	Lipedown Inse
	In-out		1000mm	600mm/se	ec	Revolution				tuo-nl
	Revolution		90°(or 180)°) 60°/sec	Fin- ger	Clamp				Revolution
	Travelling	1 1 1	lisve base	Remarks		Remarks		Bending fravailable	unction by opt	of the hand
	peatability ositioning precis	ion)	±1.0)mm		owable environ	mental	1 2 4 4	Fig. to	Appealability (Positioning precision
	Sequential n	17.6%	Microcomputer	Sequential med-	9	Sequential	mode			with input aching box
Moving control function	Positioning	n porás Parad	Electric serv	70 100 100 100 100	unction	Position an	d speed	- do -, any of 8	speed o	ean be set at
Movi			CP control/va	arious interpola	Burge functions	Memory m	ode	IC memory		
Р	ower-External -Internal		AC200/220V 50)/60Hz 3.5kVA	F	Memory ca	pacity	1000 ste	ps (Max	(.3000 steps)
	nternal measurin bility	g	Optical shaft	encoder	N	liscellany	na 13aa	PTP teac	hing	edility edility
	xternal measuring abili		e naiseass			uxiliary functi otions etc.	ons,	Self-dia	gnosti	function
	Outward	figure	Characteristics of the	Operation space	e sor	Operation un	Ch	aracteristics of t	he robot	B brawno B
(side v		Hopinas	3500 3500(v) 350(v) 350 350 350 350 350 350 350 350 350 350			pri 2. A w men fer 3. Wor in 4. The 5. The wit is hig 6. It rej pie 7. The spe unl	marily vide varies are the control of the control o	available pes of work s on the pa afferent wa ing space has a well ar motion c e of convey i. pped with correct t placed inc may be sup onfiguratio	or pall ngers/H for pal pieces llet ca ys and can be design haracte ing won a senso he post orrect plied H n that materi	netizing. nands and attack letizing dif- n be arranged combinations. easily changed net construction eristics which ckpieces at a or to separate tion of work- y. yo option in a can load and als to and from

	ne of company/ partment in chargo	e Da	ainichi Kiko Co	., Ltd.	Address, Telepho	ne	Nak 055	ai Indakoma- 28(2)	-gun, Yamana	plex, shi	Kosaimachi,
Mo	del Name	FACERO	OBO FR-10	Main applications	Automati ting, se assembly	c gas aling	cut- and	Weight	of robot itself	500	kg man seem
			ut information teaching mode	Playback robo		do z al	n Bac	Degree of mot	of freedom	3	
Clas	ssification		tion form	Articulated 1	robot	gar un	tanin	Load c	apacity	10k	g(Max.)
	Axes	1060	Operating space	Speed		А	xes	901	Operating s	pace	Speed
	Right-left t	urning	±90°	45°/sec	598	Righ	t-left sw	ing	mm00e1	9819	eart that-thigh
	Right-left tur	ning	±65°	45°/sec		Up-d	own swi	ing		goh	nur Baf Jidgi B
	Up-down trav	/erse	150mm	100mm/sec	Hand	Righ	t-left tra	verse	m/0001	BINE	vsn ewebgt
Arm	Up-down turn	ning	91	Up down traver		Up-d	own tra	verse		- Din	mut owob-qU
	In-out			- Notatovan	0.98	Revo	lution		E000m		ruo-ni
	Revolution			Clamp	Fin- ger	Clam	p	(1081	m) 200		Revolution
	Travelling	nolijak	Bending fi	Remarks		Rem	arks		Swing and hand avail		functions of t y option
	epeatability ositioning precision	on)	±0.5m	Mewable environment		wable e	nvironm	ental	0	- 45°	C white sent l
0	Sequential m	ode	Microcomputer	Saquential arod		Sequ	ential m	ode	Direct te		with input ching box
Moving control function	Positioning	peed c levels	Electric DC s	ervo	unctions	Posit	ion and	speed	- do -, s any of 32	peed c level	an be set at
Movir	Miscellany		CP control/va	rious interpola	Teaching functions	Mem	ory mod	le	IC memory		yaallaagii S
Р	ower-External -Internal	zaH) H	AC200/220V 50 6.0kg/cm ² G	/60Hz 2.0kVA	- F	Memo	ory capa	city	1000 step	s (Max	.3000 steps)
	nternal measuring bility	gali	Optical shaft	encoder	М	iscellany	alenom:	e iden	PTP teach	ing	
	xternal measurin lecognizing abilit		sif-fia8	Auxiliary functions, options sto		uxiliary tions et		ıs,	Sensing f	unctio	External massing
	Outward f	igure	Characteristics of t	Operation space	paris	pa moita	990	Cha	aracteristics of the	e robot	InexteO
(side v	iew)	m in	The state of the s			3.	ing plas seal This servand main brak toge The ing thos hand and the	space ma, ar ing. artic atting gh to 9 x 24 s driv omotor also i tenances, tather i robot not one with s with y axes	culated robo radius of 2 cover an ir (38). The properties of the	such w ting o t has 870mm on pla h-perf perati esigne servom or, an t. for c kpiece faces s of f tached	perations and a maximum which is long te of 4 x 8 ormance DC ons or motions, d for easy otor, solenoid d encoder put utting or seal-

	ne of company/ artment in charge	e kole	Dainichi Kiko Co	., Ltd.		ress/ phone	Na		ustrial Con gun, Yamana 581	de .	osaimachi,
Mo	del Name	PT-20	00н	Main applications	Assem and c	bly, se conveyar	aling, ce	Weight	of robot itself	45kg	Madel Name
			out information d teaching mode	Playback rob	oot	lodor s	1.ybac	Degree of	of freedom	4	
Clas	sification		otion form	Articulated	robot	ated ro	Ipoi x	Load ca	pacity	2kg(Max.)	
	Axes	998	Operating space	Speed		base	Axes	508	Operating s	space	Speed
	Right-left	rning	(θ) ±120°	120°/sec		Ri	ght-left sw	ving		98369	Bugint July 1
	Right-left tur	ning	(X) ±135°	120°/sec		Up	-down sw	ing	±150°		Right-left ter
Arm	Up-down trav	verse	7 5mm	120mm/sec	Ha	and Ri	ght-left tra	averse	0021±	garan	pu nwoh-qU
AIIII	Up-down turi	ning		Up-down traver		o o Up	-down tra	verse	9881±	gris	nut awab qU
	In-out			ne theirelletten			volution				Juo ni
	Revolution		±150°	120°/sec	Fi ge	r CI	amp		00S±		Revolution
	Travelling			Remarks		Re	marks				gnitteven?
	epeatability ositioning precisi	on)	±0.05mm	owable en uraniment nditions	RA 100	Allowable	environn s	nental	0 - 45	°c	Repeatability (Positioning precisi
lo I	Sequential m	ode	Microcomputer	Stepantial mode			quential n	node	through	the tead	with input ching box
ig cont on	Positioning		Electric DC s	ervo	9 9	Po Po	sition and	speed	- do -, of 8 lev		an be set at a
Moving control function	Miscellany		CP control/va	rious interpol	lat-	Po Po Me	mory mo	de snoi	IC memor	у	ymallinaiAf Š.
P	ower-External -Internal	xaM) a	AC200/220y 50 (6.5kg/cm ² G	/60Hz 45kVA 25Nl/m)	H		mory cap	acity	1000 ste	ps (Max	.3000 steps)
	nternal measuring bility	gal	Optical shaft	encoder		Miscella	ny boor		PTP teac	hing	laternal measurmi sbility
	xternal measurin Recognizing abilit		Self-diag	Auxiliary functions, options etc.		Auxilia options	y functio etc.	ns,	Self-dia	gnostic	function
	Outward f	igure	Characteristics of the	Operation space	ce	9060 no	Operati	Cha	racteristics of tl	he robot	lnawro0
(side v		inght and in the control of the cont	156 257 13 277 13 278 13 279 1			3	for spac inco line Its exte The ing stab the Its easi Dain tise	assemble for i rporate . articul nsive o well-de at a hi ly and specifi simple er. ichi's have b	y, require nstallation d into an ated const perating s signed rob gh speed (accurately ed position mechanism s	s only a n; it can existing ruction pace. ot, even 1400mm/s (within n). makes maxperience orated in the case of th	marily designed a very small an be easily groduction provides an an while operation while operation at 0.05mm of aintenance work at the robot to ties.

	ne of company/ artment in charge		Dainichi Kiko Co	o., Ltd.	Address Telepho	ne Na	akakoma 5528(2)	-gun, Yamana		Kosaimachi,
Mod	del Name	PT-20	Not observed the VOC	Main applications	Assembland lo	ly, sealing ading	Weight	of robot itself	50k	g man Haban
			out information	Playback rob	ot jos	os Spade I	Degree of mot	of freedom	5	
Clas	sification		tion form	Articulated	robot	berslusi a	Load c	apacity	2kg	(Max.)
	Axes	908	Operating space	Speed		Axes	90	Operating sp	pace	Speed
	Right-left trav	erse		prive thi high		Right-left sv	ving	(0) ±120°	gaxt	Right-Ist
	Right-left turr	ning	±150°	120°/sec		Up-down sw	ring	±120°	gri	120°/sec
	Up-down tur	ning	±120°	120mm/sec	Hand	Right-left tra	averse	75980	921	Up-down trave
Arm	Up-down turn	ing	±135°	120°/sec		Up-down tra	verse			enur nwob-eU
	In-out			Revolution		Revolution				luo ni
	Revolution		±200°	240°/sec	Fin- ger	Clamp		±150°		nodulovaEl
	Travelling			Remarks		Remarks		Solgal woods	abled	Britisväyr
	peatability sitioning precisio	n)	±0.05mm	Melne three sidewell/ and there		wable environm ditions	nental	0 - 45°	'c	Repeatability 2
lo	Sequential mo	de	Microcomputer	Sequential mod	10	Sequential m	ode			with input aching box
Moving control function	Positioning	geed c	Electric DC s	ervo	unction	Position and	speed	- do -, s of 8 leve		an be set at an
Movir	Miscellany		CP control/vaing functions	rious interpola	Teaching functions	Memory mod	le av 1	IC memory		voeltsteiM \$1
Po	ower-External -Internal	tolf) e	AC200/220V 50	/60Hz 45kVA	- S	Memory capa	icity	1000 step	s (Max	.3000 steps)
	ternal measuring	gni	Optical shaft	encoder	Mi	scellany	o Tish	PTP teach	ing	goisutism ismeral villide
	ternal measuring, cognizing ability		Self-dia	Auxiliary functions, options etc.		xiliary function	ıs,	Self-diag	nostic	function
	Outward fig	jure	Characteristics of 0	Operation space	908	Gperation at	Cha	racteristics of the	robot	Outward
side vie		a only extend cycleta pace. pace. (with makes	38 39 39 39 39 39 39 39 39 39 39 39 39 39	I. This space for an incompanies of the art line. It was a second of the art line at l		be in as ir 2. It had (±0.0 robot 3. Anoth lity workp 4. The r sfact work,	nstallenthe not a version of the not a version of the not a version of the notation of the not	d the wrong ormal positions of the position of	way a ion. itioning the other transfer of the	er assembly h-speed capabi- perly handle workers. enough to sati- of assembly at a low price
				(r) (g)		the the training of training of the training of training of the training of training o				schut also Pensuse modula resise (c. f. tarthe end of rice of job co

	ne of company/ artment in charge	,	Dainichi Kiko (Address Telepho	ne N	akakoma- 5528(2)5	ustrial Com gun, Yamana 581	shi	Avieznos le amakl.
Mod	del Name	PT-30	OOH Test seden to an	Main Ass applications fer	sembly, se ring, load iving, and	aling, ch ing, scre bosing	am w Weight	of robot itself	125k	B email isboth
			out information d teaching mode	Playback robo		iyback ro		of freedom on	4	
Clas	sification		otion form	Articulated	robot	hogalusi.	Load ca	pacity	5kg(Max.)
	Axes	994	Operating space	Speed		Axes	80%	Operating s	space	Speed
	Right-left tu	rning	(θ) ±90°	90°/sec		Right-left	swing		- 1916	Rightleft mas
	Right-left tur	ning	(X) +145° -115°	90°/sec		Up-down	swing	0 (8) ±135	y grif	mut thel-stips?
Λ	Up-down trav	erse	A O Com	snorm plainting.	Hand	Right-left	traverse	O0± (X)	BELL	Dp-down
Arm	Up-down turr	ning		srays it revolved.		Up-down	traverse	0511+ (2)	01	cour nweb-qU
	In-out		100mm	100mm/sec		Revolution	n	1123		i bio at
	Revolution		±150°	90°/sec	Fin- ger	Clamp				Revolution
	Travelling			Remorks		Remarks				gnillaystT
	peatability ositioning precision	on)	±0.1mm	laviable environmental		owable enviro	nmental	0 - 45	°c	Repeatsivility (Positioning practition
Jo.	Sequential m	ode	Microcompute	erobom ladvaupoč	s	Sequentia	l mode			with input ching box
Moving control function	Positioning	paed c ls	Electric DC	servo	unction	Position a	nd speed	- do -, s		an be set at an
funct	Miscellany		CP control/v	various interpola as	r 	Memory m	node	IC memory	у	yeshseM E
P	ower-External -Internal	KBB) e	AC 200/220V 5	60/60Hz 45kVA	Te	Memory ca	apacity	1000 step	ps (Max	.3000 steps)
	nternal measuring pility	gni	Optical shaf	t encoder	N	liscellany	one iled	PTP teach	ning	lovernal executing ability
	xternal measuring ecognizing ability		Self-diag	Auxiliary functions, options ste.		uxiliary funct	ions,	Self-diag	gnostic	function
	Outward f	gure	Characteristics of the	Operation space	987	Operation	Cha	racteristics of th	ne robot	it biswigO
(side vi	200 (2012) 2			The control of the co		req lig 2. Sin the be pro 3. Pow tor	uirement ht, swift ce it is require readily duction ered by , the ro ed of 16	s of users; t, versati compactly d space for incorporate line. a high-periodot achieve	; it is le, and design r insta ed into formances a maprocess	inexpensive. ed to minimize llation, it can an existing e DC servomo- ximum resultant ing or handling

	ne of company/ partment in chargo	е	Dainichi Kiko C	o., Ltd.	rigele T	ddress elepho	ne N	1ak 155	ai In akoma 28(2)	-gun, Yaman	mplex ashi	, Kosaimachi,
Мо	del Name	PT-3	300V	Main applications	Ass	embl welling	y, handlin ding and	g,	Weight	of robot itself	155	ökg
			put information d teaching mode	Playback rob			lou Japane.	19	Degree of moti	of freedom	5	
Clas	sification		otion form	Articulated	robot	odos	basalusi			apacity	5kg	(Max.)
	Axes	90	Operating space	Speed			Axes		18218	Operating sp	pace	Speed
	Right-left trav	verse		prive that swing			Right-left s	win	g	000 (5)	saka	us delanger
	Right-left turr	ning	(θ) ±135°	90°/sec			Up-down sv	win	g	±105°	pa	90°/sec
	Up-down tur	ning	(X) ±90°	90°/sec	msH H	Hand	Right-left to	rave	erse		- 1	vat riwoli gti
Arm	Up-down turn	ing	(Z) +145° -115°	90°/sec			Up-down tr	ave	rse		na	muit nyob-qu'i
	In-out			neitblovsFl			Revolution			±135°		90°/sec
	Revolution			Ciamp		Fin-	Clamp			00812		noitulovaH
	Travelling			Remarks	3	,,,,	Remarks					Travelling
	peatability sitioning precision	n)	±0.1mm	Allowable environment conditions	T		wable environr litions	men	tal	0 - 450	C (m	Repuscibility (Pod::ionling precisio
ion	Sequential mo	de	Microcomputer	Sequential mod		S	Sequential n	nod	e			with input
function	Positioning	beed t	Electric DC s	ervo noliso		Teaching functions	Position and	spe	ed	- do -, sp of 8 level	eed c	an be set at a
fun	Miscellany		CP control/varing functions	rious interpolat	t-	aching f	Memory mod	de	L/va Linns	IC memory		Vinellenzi Miscelleny
Po	wer-External -Internal	s (Ma	AC200/220y 50, (6.5kg/cm ² G)	60Hz 45kVA		Te	Memory capa	acit	у	1000 steps	(Max	.3000 steps)
	ernal measuring lity	gai	Optical shaft	encoder ManiM		Mis	cellany	192	1) BOS	PTP teachi	ng	constant demand
	ternal measuring/ cognizing ability	kieon;	Self-diag	Apxillary functions options atc.	T		ciliary function	ns,		Self-diagn	ostic	function
	Outward fig	ure	Characteristics of th	Operation space		9080	Operation		Chara	acteristics of the r	obot	biologij@
		A 198 (17) 42	(5) (87(x)) (17(x)) (1	5-3-3-3-3-3-3-3-3-3-3-3-3-3-3-3-3-3-3-3			permi ling incor line. 2. The sof th that robot 3. The D ensur ±0.lm good 4. It is can be	pe e car	other ated cial robot mot seed system fast, and remains multipes assily	be installer r similar plinto an exi "dome-shaped covers such be performed stems. motor instal, accurate o the robot c ship and highly purpose rob	ed on laces sting "ope an a a laby c led in perat an be h proof who meet	of the robot the plant cei- and readily production rating space rea of work onventional n the robot ion (within relied on for duct quality. ose program the require- ck.
	, pol											

	ne of company/ artment in charg	ge is	Dainichi Kiko Co	., Ltd.	Address, Telepho	ne N		gun, Yamana		Kosaimachi,
Mod	del Name	PT-5	ont of cobot inself 00	Main applications	Handlin and arc	g, assemb welding	Ly Weight	of robot itself	180k	Model Marre
			put information d teaching mode	Playback rol	bot	or speck re	Degree of	of freedom	4	
Clas	sification		otion form	Cylindrical	coordinate	es robot	Load ca	pacity	5kg(Max.)
	Axes	(2)	Operating space	Speed		Axes	556	Operating s	pace	Speed
	Right-left tra	averse		Right-left swing		Right-left s	wing		9216	valit Hal-FrigiPi
	Right-left tu	rning	±100°	75°/sec		Up-down sv	wing	00 ELELES	gni	Signification
Arm	Up-down tra	verse	400mm	400mm/sec	Hand	Right-left t	raverse	500mm	963	Up down trev
AIIII	Up-down tur	ning	±60° s	rievsu awejshiji), ac		Up-down tr	averse		E/A	Sant umab-qO
	In-out		400mm	400mm/sec	2	Revolution		±135°		75°/sec
	Revolution			Clamp	Fin- ger	Clamp				Revolution
	Travelling			Remarks		Remarks				Travelling
	peatability esitioning precisi	ion)	±0.2mm	lowable environmen editions		wable environ ditions	mental	0 - 45°	°c	Repeatsthilty (Postfioning precision
rol	Sequential m	node	Microcomputer	Sequential mod	v	Sequential	mode			with input sching box
Moving control function	Positioning	peed co	Electric DC s	ervo manag	unction	Position and	d speed	- do -, s of 32 lev		an be set at an
Moving c function	Miscellany		CP control/varing functions	rious interpol	- t - Teaching functions	Memory mo	ode	IC memory		ynational 5 3
Po	ower-External -Internal	og) a	AC200/220V 50, 6.0kg/cm ² G	/60Hz 2.0kVA	H H	Memory cap	pacity	1000 step	s (Max	.3000 steps)
	ternal measuring	g ani	Optical shaft	encoder	М	iscellany	na 13 peti	PTP teach	ing	laternal messuring bility
	cternal measuring		Sensing	Auxiliary functions, options atc.		uxiliary functions etc.	ons,	Sensing f	unctio	External mastures Recognizing ships
	Outward f	figure	Charge teristics of the	Operation space	e o 606	Operation en	Cha	racteristics of the	e robot	LaweryO
(side vie	w)	645 (00.02)	20 775 390 390 390 390 390 390 390 390 390 390			mini tior allo desi 2. The how bala 3. A cc will arms hand othe tem as f work comp 4. Its func prod sepa ble	mize the Its was it to red. To move the more to move the control of the red to move the control of the red to move the control of the red to move the red to m	e required well devise o be instal an be taugh and what t unction inc these robo fficiently uman worker workpiece i s will enab orm those d insertion, which have a robot to combined w can perform pection, re defective p	space d moun led in t very o do b orpora ts com just 1 with ndepen le the ifficu and c been do. ith ot a com moving product tly and	y designed to for installa- ting flange any position easily exactly ecause of the ted in it. bined properly ike the two each of them dently of the robotized sys- lt jobs, such ombination of considered too her excellent plicated job of rejects or s from accepta- d reliably than

		1 3 3 4	Dainichi Kiko Co	o., Ltd.	Addre Teleph	ione		-gun, Yaman		Kosaimachi,
Мо	del Name	PT-5	50 They lived to top	Main applications	Arc we sembly	lding, as- , handling aling	Weight	t of robot itself	3501	kg
	Axes Right-left traverse Right-left turning Up-down traverse		out information d teaching mode	Playback rob		dow stone	Degree of mot	of freedom	5	
Clas	Axes Right-left traverse Right-left turning Up-down traverse Up-down turning In-out Revolution Travelling Repeatability Positioning precision) Sequential mode Positioning Miscellany Power-External -Internal Internal measuring ability Outward figure		otion form	Cylindrical	coordina	es robot		apacity	7kg((Max.)
		Operating space	Speed		Axes	90	Operating sp	pace	Speed	
	Right-left trav	erse		Right left swing		Right-left	swing		9211	van Heladgill
	Right-left turn	ing	±135°	60°/sec		Up-down s	wing	±105°	277	90°/sec
	Up-down trave	rse	500mm	500mm/sec	Hand	Right-left	traverse	60000A	en	Up down trav
Arm	Up-down turni	ng	50	teren resolego		Up-down t	raverse		gn	tip-dawn turn
	In-out		60 Omm	500mm/sec		Revolution		±200°		180°/sec
	Revolution			quisiO	Fin- ger	Clamp				Revolution
	Travelling			Raiparics		Remarks				gnilleveiT
		1)	±0.2mm	Travolita environmen enfittore		owable enviror	mental	0 - 45°	С	Reportability Postioning precisi
rol	Sequential mod	de	Microcomputer	Segmential tripe	S	Sequential	mode	Direct te		with input ching box
Moving control function	Positioning	basq els	Electric DC se	ervo minus	unction	Position an	d speed	- do -, s of 32 leve		an be set at a
Movi	Miscellany		CP control/var	cious interpola	Teaching functions	Memory me	ode	IC memory		- vosilisasiM
Po		M) sy	AC200/220V 50/ 6.0kg/cm ² G	60Hz 2.0kVA	F e	Memory cap	pacity	1000 steps	s (Max.	.3000 steps)
		gni	Optical shaft	encoder	N	liscellany	no Bladi	PTP teachi	ing	ri iuzesin lumenil yillide
		3589	galens8 .	Auxiliary functions options atc.		uxiliary function	ons,	Sensing fu	nction	instruction of the second
	Outward figu	ure	Characteristics of th	Operation space	10	Operation pr	Chai	racteristics of the	robot	harvania)
side viev		to do	90			gina the desc Thes rato 2. A pn the appl lope and piec the in. 3. The poss sppe 4. It h requ tion 5. Advan trol robot as an 6. Linea	Il paral fore en ribed i e featur to te eumatic X/Z-axe ied load by Dars save the es, whire robot is ible so d (1000m as an enires only the post availate weldiar and a	lel link ted d of which m n cylindrica res make it ach the robo balancing f s that are d d. This spe inichi helps e required p le ensuring natever posi s made as lig that it can am/sec). Attensive open by a small specification of the bible for such ing.	hnique loves i l coor leasier t. local loc	for the open is used for y affected by echnique devele applied load o move workle motion of he arm may be drigid as te at a high space but or installations are functions are

	ne of company/ artment in charg	e	Dainichi Kiko Co	o., Ltd.	Address/ Telephor	ne Nal	sai Ind kakoma- 528(2)5	ustrial Com gun, Yamana 581	plex,	Kosaimachi,
Mod	del Name	PT-6	00 ment reder to m	Main applications	Arc well sembly ing	ding, as- and handl-	Weight o	of robot itself	360k	g
			put information d teaching mode	Playback rob		on standy D	Degree o	f freedom	5	
Clas	sification		otion form	Articulated	robot	basalani s	Load cap	pacity	12kg	(Max.)
	Axes	90	Operating space	Speed		Axes	306	Operating s	pace	Speed
	Right-left tra	verse		priess stat-statistic		Right-left sw	ing		6214	kan stelangin
	Right-left tur	ning	±150°	90°/sec		Up-down sw	ing	±105°	prii	90°/sec
	Up-down	rning	±60°	90°/sec	Hand	Right-left tra	verse	- 988 - 793	Snkr	nereb-qU
Arm	Up-down turr	ning	±60°	90°/sec		Up-down tra	verse	025 1+ (2)	18/1	mut meab-gU
	In-out		£150°	nottuloveR		Revolution		±200°		180°/sec
	Revolution		3333	gmst0	Fin- ger	Clamp				notraloseR
	Travelling			Replanks	3-1	Remarks				- ghilloroiT-v
	peatability ositioning precision	on)	±0.1mm	logable environment		wable environm ditions	ental	0 - 45°	°c	Reparability - Prestioning precision
ō	Sequential m	ode	Microcomputer	Sequential mode		Sequential m	ode			with input ching box
Moving control function	Positioning	seed c	Electric DC s	ervo	inctions	Position and	speed	- do -, s of 32 lev		an be set at an
functi	Miscellany		CP control/vaing functions	rious interpol	Teaching functions	Memory mod	le	IC memory		Vindersilla S
P	ower-External -Internal	ивм) в	AC 200/220V 50, 6.0kg/cm ² G	/60Hz 2.0kVA	Tea	Memory capa	city	1000 step	s (Max	.3000 steps)
	nternal measuring	gnl	Optical shaft	encoder	Mi	scellany	s_18 bri	PTP teach	ing	Internal measuring
	xternal measuring		Self-diag	Auxifiary functions,		ixiliary function	ıs,	Sensing f	unctio	n suksam tanawa 3
	Outward f	igure	China distinction of the	Operation space		normeon .	Char	acteristics of the	e robot	- Outward
(plan)	ew)	A CLUB CONTRACTOR OF THE CONTR	1710 658			to the to co	e best ver exiompact minim ation, e down ar plac chi's c ensure during 5 degre f movir suital for ins	advantage tensive are, light conizes the repermitting on the places. Original mees a high phigh-speed tes of free ag freely,	to ena as of struct quired it to nt cei chanis ositio opera dom an the rol plicatt weldin	ion of the space for in- be installed ling or other m used for the ming accuracy tion. d a wrist capa- bot is particu- ed jobs includ- ng.

	ne of company/ artment in charge	e in	Dainichi Kiko C	05528(Addres Teleph	one	Nakakoma 05528(2)	a-gun, Yaman	mplex, ashi	Kosaimachi,
Мо	del Name	PT-80	00 Heal Seden for the	Main Ha	andling, s elding, au utting, an	pot arc tomatic g	as Weigh	t of robot itself	8001	(g
			out information d teaching mode	Playback rol		yback rob		e of freedom tion	5	
Clas	sification		otion form	Articulated	robot	icalated	Load	capacity	25kg	(Max.)
	Axes	306	Operating space	Speed		Axes	93	Operating s	pace	Speed
	Right-left tra	verse		Right-laft swing		Right-left	swing		9819	veig statistique
	Right-left turi		(θ) ±135°	60°/sec		Up-down	swing	±105°	800	60°/sec
	Up-down tur	ning	(X) ±60°	60°/sec	Hand	Right-left	traverse	0001	3810	nvah-qU
Arm	Up-down turn	ning	(Z) +135° -120°	60°/sec		Up-down	traverse	oat	- fgn	may nivot-qU
	In-out		0.065 per	norralinan all		Revolution	1	±150°		90°/sec
	Revolution			Clared	Fin- ger	Clamp				noiteloveR
	Travelling			Remarks		Remarks				goaliseast
	peatability sitioning precision	on)	±0.5mm	inomerivae sidevol editions		owable environ	nmental	0 - 45°	С	Scored Williams
rol	Sequential mo	ode	Microcomputer	abom tsittmups3	S	Sequential	mode	Direct te		with input
Moving control function	Positioning	peed c s ls	Electric DC s	servo	functions	Position ar	d speed	- do -, s of 8 leve		n be set at an
Mov	Miscellany		CP control/va	rious interpol		Memory m	ode	IC memory		VintlesonM
Po	ower-External -Internal	(May	AC200/220y 50 (6.5kg/cm ² G,	/60Hz 45kVA 100Nl/m)	T _e	Memory ca	pacity	1000 steps	s (Max.	3000 steps)
	ternal measuring ility	gni	Optical shaft		M	liscellany	hafft en	PTP teachi	ing	e sizeen det istol-
	cternal measuring ecognizing ability		Sensing	Auxiliary functions, options etc.		uxiliary functi otions etc.	ons,	Self-diagr	nostic	function
	Outward fig	gure	Characteristics of th	Operation space	9 898	Operation	Cha	racteristics of the	robot	lawini)
-ni boli side vie	ew) a sa dodo:	echioi postil	2800			25kg pose spee such form 2. Its cove perf 3. Anot easi duct	d even as as er. special rs such ormed be her adv. ly incomion line	ge load capa rial robot. when carryin pot gun with "dome-shape an area of y convention	city for It work a build of the a build open work the all robots at the color an expension of the state of th	robot can be

	ne of company/ artment in charg	e	Dainichi Kiko Co	o., Ltd.	Address/ Telephon	e Nal		ustrial Com gun, Yamana 581		Kosaimachi,
Мо	del Name	PT-1	.000	Main Ha	andling, sp elding, aut utting, ass ealing	ot arc omatic gas	Weight	of robot itself	1000	kg
	estimate)		put information	Playback rol	ealing bot	upsasidan V	Degree of	of freedom	6	AND DECEMBER OF THE PROPERTY O
Clas	sification		otion form	Articulated	robot	oax Isalahail (1)	Load cap	pacity	30kg	(Max.)
	Axes	etalas	Operating space	Speed		Axes	note	Operating s	pace	Speed
	Right-left tra	iverse	120 mm	anthomial-state Bernard		Right-left sw	ing	150 mm (or	sera	Right-left par
	Right-left tu	-	(θ) ±135°	60°/sec		Up-down sw	ing	±105°	eni	90°/sec
	Up-down ^{‡u}	rning	(X) ±45°	60°/sec	Hand	Right-left tra	iverse	(isoler)	927	Up-down trave
Arm	Up-down tur	ning	(Z) ±45°	60°/sec		Up-down tra	verse	(10-no) °00	97	mur awab-gt/
	In-out	(moit	270° (4 podt	Revelution		Revolution		±150°		90°/sec
	Revolution	ra\ab	±135°	90°/sec	Fin- ger	Clamp		Season Seas	ur fixe	la montalisment
	Travelling			Remarks		Remarks				gnillovstT
	peatability ositioning precisi	on)	±0.5mm	nemnezivas sideveli. Mostibae		wable environm litions	nental	0 - 45	°c	Nepsatability (Positioning prepiale
ō	Sequential m	ode	Microcomputer	Sequential mod	9	Sequential m	ode			with input ching box
Moving control function	Positioning		Electric DC s	ervo	unction	Position and	speed	- do -, s of 8 leve		an be set at an
Movin	Miscellany	grom	CP control/va	rious interpol	- 1 Teaching functions	Memory mod	de	IC memory	7	woodloowild \$
Р	ower-External -Internal		AC200/220V 50 (6.5kg/cm ² G,	/60Hz 45kVA 250N /m)	T e	Memory capa	acity	1000 step	os (Max	.3000 steps)
	nternal measuring	9	Optical shaft	encoder	Mi	scellany	scisting_d	PTP teach	ning	genutzaem textestral
	xternal measurin ecognizing abilit			Ameliary functions options etc.		xiliary function	ns,	Self-diag	gnostic	function
	Outward f	figure	Chargonistics of th	Operation space	ce about	Operations	Cha	racteristics of th	e robot	Etnawro0
(plan)	iew)	25 - Mar. 17 - M	1935 > 200	MAT and the damped an		for m es bo the r minim 2. The p in X/ power and ti surin, in lo motion 3. A high drive also with rator unit. 4. With load factor ilar those to can gun wi er. 5. The wn degree additi X, Z, tial p freed to per commod been c past.	otion pr th in up obot its ize the neumatic Z-axis m to oepr he weigh g smooth ad level n. h-perfor the moto , and en a positi capacity rily per jobs wh rry such tha bu: fist is ses of fre on to ar and 0 ap oart of t om give t form con lious pla considere	reticulation of covides extens indown and outelf is compace required space balancing functions helps ate the robot to f the arm operation by that may occur on all axe y designed for, solenoid becoder put tog oning accurace of 30kg, the form spot well articularly ich require the heavy equipment in energy. Also compactly edom on \$\alpha\$, become a degree to the robot. The robot speed plex jobs or ace, an area ced difficult to the control of the control o	ive oper-in direttly desired for in nction in reduce to under a itself, minimiz ur from omotor i s. The reasy m rakes, tether in y of ±0. robot c ding and t is suite robot ent as a resving y design, and y design, and y design, ease 6 desired cap operate of work to robot in the result of the resu	rating spac- rections, but igned to istallation. Incorporated the required replied load while en- ring changes the arm's s used to robot is aintenance acho-gene- to one Smm and an satis- other sim- table for ized system welding transform- ed with 3 axes in reedom on more essen- agrees of abilities in an in- that has ize in the

	me of company/ partment in charg	e l	FANUC LTD.	Asig to the	Address/ Telephor	e 5-	1, Asahiga el. (0425)	oka 3-chome, Hi 84-1111	no-shi, To	kyo 191, Japan
Mo	del Name	FANU	C ROBOT MODEL 00	Main applications	Unmanne	l machining	Weight	of robot itself	Arm (60 kg piece feeder 100 kg
			put information d teaching mode	Variable sequence	robot	P syback r	Degree of motion	of freedom	3 (up	to wrist)
Cla	ssification		otion form	Cylindrical coordin	nate robot	Agriculate	Load ca		Max.	20 kg at wrist
	Axes	199	Operating space	Speed		Axes	8060	Operating s	pace	Speed
	Right-left tra	verse	150 mm (on-off)	500 mm/s		Right-left sv	ving		8716V	Right-left tr
	Right-left tur	ning	(by workpiece feeder	3s/pallet)		Up-down sw	ving	(6) £135	enim	uz rtel signifi
	Up-down trav	rerse	by workpiece feeder 300 mm	80 mm/s)	Hand	Right-left tr	averse	(X) tas	gning	nwob-qU
Arm	Up-down turr	ning	60° (on-off)	90°/s		Up-down tra	averse	(Z) ±45°	gring	Up-down tur
	In-out		001111111	Revolution		Revolution		270° (4 posi	tions)	90°/s
	Revolution			Glampi	Fin- ger	Clamp		Fanuc Hand	D6/D7	noitulovaA
	Travelling			Stemarks	301	Remarks				goldeverT
	epeatability ositioning precision	on)	±0.3 mm	Anovolue anvironme conditions		wable environr ditions	mental	0 ~ 45°C, 2	20 ~ 90%	RH
	Sequential me	ode	Memory	m lattesupe8		Sequential r	node	Variable	ich istem	didinages
function	Positioning	peed e ls	Air cylinder, and DC	motor	Teaching functions	Position and	speed	Adjustable	eed ca	galaoirest .
function	Miscellany		Palletizing function	hom y would	aching f	Memory mo	de	C-MOS men	mory	Wiscollany
Р	ower-External	calt) a	AC 200 ~ 550 V, 1 Air supply 5 ~ 7 kg/	φ, 0.3 kVA cm ²	Te	Memory cap	acity	600 points	(Bax.	Power-External -Research
	nternal measuring bility	gal	Limit switch, positio	n sensor	М	scellany		Optical		
	xternal measuring		Self-3192 .20	Auxiliary function options etc.		ixiliary functio	ons,	S01 F=8149	\gni	External messur Recognizing abil
	Outward f	igure	in to entained mead.	Operation space	5080	notare O	Cha	racteristics of the	e robot	Outward
(plan)	distriction of the control of the co		70 200 1980 1980 500 (Additable			built-in tunloadin features dimensic 1. The coordinate floor 2. The floo 3. Pnet 4. App feed 5. Mot	type robot g workpie lower pric pric pric pric FANUC I rdinate type rom a lath incorpora r space. umatic cor blication of ler is availa ion path o	ted type robot on trol for the robot with a	ped for lo iC lathe, a ing and si EL 00 is a for loadir in the lath of can real a rotary w be changed	ading/ und it nall outer cylindrical ng/unloading e can save lize lower price. corkpiece

	e of company/ artment in charg	e Italia	FANUC LTD.	for Sel, As	Address/ Telephon		, Asahigao I. (0425) 8	oka 3-chome, Hin 84-1111	io-shi, To	kyo 191, Japan
Mod	lel Name	FANUCE	ROBOT M-MODEL 0	Main applications	Unmanned handling	machining,	Weight	of robot itself	Mech	anical Unit 110 kg ol Unit 100 kg
	m merer qui		ut information teaching mode	Playback robot		P. Shack robot	Degree of motion	of freedom		ralent to 6 o wrist)
Clas	sification		tion form	Dual Cylindrical coord	inate robot	Onthitical coc	Load ca	pacity	Max.	20 kg at wrist
	Axes	9081	Operating space	Speed		Axes	808	Operating s	pace	Speed
	Right-left tra	verse	120 mm	Max. 500 mm/s	ne i	Right-left sv	ving		82%	Right-left trav
	Right-left tur	rning	001 120°	Max. 120°/s		Up-down sw	ving	300°	600	Right-left sure
	Up-down tra	verse	150 mm	Max. 500 mm/s	Hand	Right-left tr	averse	550 nu	927	Up-down trave
\rm	Up-down tur	ning	90°	Max. 120°/s		Up-down tra	averse		90	area awab-gU
	In-out		*00E	Revolution	2,90	Revolution	aun i	-90°, 0, 90° (on-of		Max. 90°/s
	Revolution	s FANUC	ohay 180°	Max. 120°/s	Fin- ger	Clamp		Various FA	ANUC HA	NDs available
	Travelling			Bemarks		Remarks				Travelling
	peatability ositioning precisi	ion)	±0.5 mm	Allowable anvironmen Sodicions		wable environi ditions	mental	$0 \sim 45^{\circ} \text{C},$	20 ~ 90%	6 RH
5	Sequential m	node	Memory	Sequential mod		Sequential r	mode	Variable, T	eaching i	n any sequence
function	Positioning		DC servo motors (Wrist and hand by a	air pressure)	unction	Position and	d speed	Variable		e Positioning
functi	Miscellany	оту	Bubble men	Memory made	Teaching functions	Memory mo	ode	C-MOS me	mory	Miscellany Miscellany
Р	ower-External -Internal	enio	AC $200 \sim 550 \text{ V}$, 3 Air supply $5 \sim 7 \text{ k}$	φ, 2 kVA g/cm ²	H H	Memory cap	pacity	Max. 1320	points	Power-Farman
	nternal measurin	g	Pulse coder, limit sw	vitch, etc.	М	scellany	otiva timil	Pulse codes		Internal measuring spility
	xternal measuring abilities		Bubble cassette i Palletrang C/D.	Auxillary functions options etc.		uxiliary functions etc.	ons,	Bubble cassett Program contr	e (Max. 2 ol, quick	2700 points), instruction method, e
	Outward	figure	Ohara-teristics of th	Operation space	908	Operation	Cha	aracteristics of th	ne robot	Detword fig
iside v	riew)		420ma - 630mas 407	3 340		automat realize a attached. 1. The coo mac too. 2. The floor 3. In a avaince can	te the load in unmann if to a CNC to FANUC le FANUC le ridinate typhining profile for material incorporator space. Addition to illable for a proporated operate a	ocess, which save rial handling. ated type robot to the separated ty my already instatype control (FA machine tool as tion method is a	f workpie a machini patent per EL 0 is a e and spee the idle to a mach ype robot lled machanuc SY well as the idle at the idle to a mach ype robot lled machanuc SY well as the idle at the idle idle idle idle idle idle idle idl	ces, etc. and to mg cell to be nding). dual cylindrical cially developed for time of a machine ine tool can save

	FANUC LTD.	A 1-2 desir endigs	Address/ Telephor	ne 5-1, Tel.	Asahigaoka 3- (0425) 84-11	chome, Hind		yo 191, Japan
Model Name FAN	UC ROBOT M-MODEL 1	Main applications	Unmanr Handlin	ed machining g, etc.	Weight of ro	bot itself	Mech: Contr	anical Unit 570 kg ol Unit 200 kg
d of the large a.	Input information and teaching mode	Playback robot		Payback robo	Degree of fre	eedom	3~5	(up to wrist)
Classification b.	Motion form	Cylindrical coordinat	e robot	faul) oclasification	Load capaci	ty	Max.	47 kg at wrist
Axes	Operating space	Speed		Axes	9364238	Operating sp	pace	Speed
Right-left traverse	150 200 200 200 - 2	niwa Itge <u>re</u> gia	il su	Right-left sw	ving		8219	Right-light was
Right-left turning	300°	Max. 60°/s		Up-down sw	ving	190°	- gni	Max. 60°/s
Up-down traverse	550 mm	Max. 500 mm/s	Hand	Right-left tra	averse	021	GATE	Up down nav
Up-down turning	ar receip do	seed nwob-pU		Up-down tra	averse	00	979	Up-down turn
In-out	500/800/1100 mm	Max. 1000 mm/s		Revolution		300°		Max. 90°/s
Revolution	Various FANUC	Sinc Clamp	Fin- ger	Clamp	1 3 3 3 3	Variou	is FANUC	HANDs available
Travelling		Remarks	gei	Remarks				gmillerarT
Repeatability (Positioning precision)	±1 mm	Alloyable environment conditions		wable environn ditions	nental	0 ~ 45°C, 20	0 ~ 90% I	RH
Sequential mode	Memory	Sequential mo		Sequential m	node	Variable, tea	ching in a	ny sequence
Positioning	DC servo motors, Hand by air pressure	e Position and E	Teaching functions	Position and	speed	Variable		Positioning
Miscellany	Linear control, and Hand direction cont	trol (option)	aching f	Memory mod	de	Bubble mem	ory	ydeileosits
Power-External -Internal	AC 200 ~ 550 V, 4 Air supply 5 ~ 7 kg	kVA, 3 φ /cm ² for wrist B		Memory capa	acity	Max. 6000 p	oints	lametx3-revolt lametal-
Internal measuring ability	Pulse coder, limit sv	vitch, etc.	М	iscellany	tive tigal 15b			
External measuring/ Recognizing ability	ilubbie casetu (M Program contral, q	Auxifory fundings option etc.		uxiliary function	Pall	ble cassette (Netizing C/D, P	rogram cor	
Outward figure	Characteristics of the ro	Operation space	9589	н пантина(О		eristics of the		Disartuo
	to to adiabality without not	Wrist attache surface Tool 333	r, 637 849 049	automatrealize artwo CNC 1. Cyli 2. Operota 110 3. 5-ax 4. Line 5. Palle	e the loading/un unmanned of machine tool indrical coordinating space is atton 300° as woo mm. dis-at-a-time coear control is a	unloading of peration as a s (patent per note type rowith the ran ell as in/out out of the period of	workpiece machinir nding). bot. nge of up/ 500 mm, by DC see	down 550 mm, 800 mm or rvo motors.

	ne of company/ artment in charg	e	FANUC LTD.	ear S-1, Ass bosed Tel. (0-	Address/ Telephor			oka 3-chome, Hin) 84-1111	io-shi, To	kyo 191, Japan
Мо	del Name	FANUC	ROBOT M-MODEL 2	Main applications	Unmanne	d machining	Weight	t of robot itself	Mecha Contr	anical Unit 550 kg rol Unit 120 kg
	TALKU		put information d teaching mode	Playback robot	21	Hyback robo	Degree of mot	of freedom	4 (up	to wrist)
Clas	sification		otion form	Cylindrical coordin	nate robot	oo fashibiliga	Load o	capacity	Max.	60 kg at wrist
	Axes	808	Operating space	Speed		Axes	50	Operating s	pace	Speed
	Right-left tra	verse	500 mm	Max. 500 mm/	/s	Right-left sv	wing		8239	est the trigit
	Right-left tur	ning	°001 300°	ynivälnikoli-lijÜli-		Up-down sv	ving	°006	góir	Right-left tur
	Up-down tra	verse	300 mm	Max. 500 mm/	/s Hand	Right-left to	raverse	1290 mm	5234	viat neobidU
Arm	Up-down tur	ning	180°	Max. 60°/s		Up-down tr	averse		959	Up down turn
	In-out		900 300 mm	Merudaka mala	1 2/100	Revolution		300°		Max. 90°/s
	Revolution	H SUNS	Variable FA	Clamp	Fin- ger	Clamp		Various	FANUC	HANDs available
	Travelling			Remorks		Remarks				Travelling
	peatability ositioning precisi	on)	±1 mm	Allowable environmen conditions		wable environ	mental	0 ~ 45°C, ∶	20 ~ 90%	RH gminoalsoq
IO.	Sequential m	ode	Memory	Sequential mod		Sequential r	mode	Variable, to	eaching in	any sequence
Moving control function	Positioning		DC servo motors, H	land by air pressure	unctions	Position and	d speed	Variable		Positioning 5
Movii	Miscellany	Klou	Linear controls, hand rescuedddddcontrol, High		Teaching functions	Memory mo	ode	C-MOS me	mory	- Viscellary
Р	ower-External -Internal	amlog	AC 200 ~ 550 V, 3 Air supply 5 ~ 7 I	φ, 2 kVA kg/cm ²	Tea	Memory cap	pacity	Max. 840 p	oints	Power-External
	nternal measuring		Pulse coder, limit sy	witch, etc.	M	scellany	niwa nen-	Pulse pales		gongselet (umern) Spilly
	xternal measurin ecognizing abilit			Auxiliary functions options ste.		uxiliary function tions etc.	ons,	Bubble cassette control, Quick		700 points), Program on method, etc.
	Outward f	igure	Characteristics of the	Operation space	305	Operation	Ch	paracteristics of th	e robot	Optward f
(side v	iew)	heavier o	13 900 Wall 1	ond to read one or two ones. 1. Max. 1 .2. Oness	AZSOMA I	automat realize a attached 1. The coo for mac 2. The floor 3. Max 4. Qui	e the load n unmann to a CNO FANUC rdinate ty machinin, thine tool incorpor or space and c. handlate ck instruct	BOT M-MODEL 2 ding/unloading of ned operation as a a C machine tool (p ROBOT M-MODI / per robot suitable g process, which s for material hand atted type robot tund serve operator ole weight of work with the control of the weight of work at the control of the control of the weight of work at the control of the	workpiece machininatent pen EL 2 is a cand speciave the idilling. Do a machining area.	pes etc. and to ng cell to be ding). cylindrical itally developed alle time of a ne tool can save from the color of the c

	ne of company/ artment in char		FANUC LTD.	ine Fel.	Address Telepho	ne Tel.	. (0425) 84	4-1111		yo 191, Japan
Mod	del Name	FANUC	ROBOT M-MODEL 3	Main applications	Machining, I Heavy mater	Handling, rial transfer	Weight	of robot itself		anical unit 1600 kg rol unit 250 kg
	(Jahw)		out information	Playback robot	t	todos kobot	Degree of	of freedom	5 (up	to wrist)
Clas	sification		tion form	Cylindrical coo	ordinate robot	indoses coor	Load ca	pacity	Max.	80 kg at wrist
	Axes	8566	Operating space	Speed		Axes	9080	Operating sp	ace	Speed
	Right-left to	raverse	0	Night-left swik	s/m	Right-left sv	wing	500 mm	9219	van Halistian nav
	Right-left to	ırning	300°	Max. 60°/s		Up-down sv	ving	190°	gnie	Max. 80°/s
	Up-down tra	averse	1200 mm	Max. 500 mm	n/s Hand	Right-left tr	raverse	m 005.	9216	yan nwobfqU
Arm	Up-down tu	rning	920	Un down (ran		Up-down tra	averse	*081	peri	nun nwob-qli
	In-out		1200 mm	Max. 1000 m	m/s	Revolution		300°		Max. 80°/s
	Revolution	H DUNA I	surplies.	Clamp	Fin- ger	Clamp		Variable FA	NUC H	ANDs available
	Travelling			Hemaks		Remarks				geilleverT
	peatability sitioning precis	ion)	±1 mm	lowable environme subtions		owable environr ditions	mental	0 ~ 45°C, 2	0 ~ 90%	RH
5	Sequential r	node	Memory	Sequential ma	s	Sequential n	node	Variable, tea	aching in	any sequence
function	Positioning		DC servo motor, Air pressure for HAN	ID on nomizoq	unction	Position and	d speed	Variable		- Res coning .
function	Miscellany	yion	Linear control, and h	and direction	Teaching functions	Memory mo	de	Bubble men	nory	_ Wiscellany
Po	wer-External -Internal	eanim	AC 200 ~ 550 V, 3 q Air supply 5 ~ 7 kg/	b, 15 kVA cm ²	Te	Memory cap	acity	Max. 6000 p	ooints	lametxii newo9 lametxii-
	ternal measurin	g	Pulse coder, limit sw	itches woodlessing	M	iscellany	trws time!	Bubble cassett Palletizing C/I instruction me	te (Max. 2 D, Prograr ethod, Tw	2700 points) m control, Quick to machine control
	ternal measuri cognizing abili		s. Bubirle cassett control, Outek	Auxilialy function		uxiliary functio	ens,	Bunkle Lavier 18 Palletzing U/D 64 Qulck Bernschung		Exrees mosterio Pacanizing spini
	Outward	figure	ir No cainaver enerili	Operation space	ce eos	Operation to	Char	acteristics of the	robot	thiswayo
(plan)			1.050			automate and to re one or tv 1. Max 2. Oper 1200 3. All t serve 4. Palle	e the loadirealize an unwo CNC manus chandlable rating space 0 mm, in/o che 5 axes a o drives.	or M-MODEL 3 in a g/unloading of hamanned operation in the cools (Pater weight of works) weight of works at a time including the attention in the cool of the cool	neavier we need as a ment pendioniece is 5 erange or rotation g wrist d	orkpieces, etc. achining cell to ing). 0 kg. f up/down a 300° lriven by DC

Name of company/ Department in char	ge	FANUC LTD.	one Tel. (Address/ Telephor		el. (0425) 8	ka 3-chome, Hind 34-1111		egista ni francisco
Model Name	FANUC	ROBOT AMODELOO	Main applications	Assemble sealing, 6	y, washing, etc.	Weight	of robot itself		anical unit 150 kg ol unit 250 kg
		nput information nd teaching mode	Playback robot		Psyback robo	Degree of motion	of freedom	4 (up	to wrist)
Classification	b. N	Notion form valuedes by a	Cylindrical coord	dinate robot	oo laatthally D	Load ca	pacity	Max.	10 kg at wrist
Axes	50	Operating space	Speed		Axes	905	Operating sp	oace	Speed
Right-left tr	averse		Right-left swing		Right-left s	wing		9210	Right-left tras
Right-left tu	rning	300°	Max. 120°/s		Up-down sv	wing	°008 190°	goi	nur HalutdelB.
Up-down tra	verse	150 mm	Max. 100 mm/s	S Hand	Right-left to	raverse	am 00E	50.1	erett nwob-gU
Up-down tu	rning	92	Up-down traver		Up-down tr	averse		gni	risut nwob-gU.
In-out	(3	300 mm	Max. 1200 mm	/s Alem	Revolution		300°		Max. 120°/s
Revolution		123.83.87	Clamp	Fin- ger	Clamp				Revolution
Travelling			Remarks		Remarks				graffaverT
Repeatability (Positioning precis	ion)	±0.05 mm	isonativa sklavali enditions		wable environ	mental	0 ~ 45°C, 2	0 ~ 40%	RH Valide med S
Sequential r	node	Memory	Sequential mod	8	Sequential r	mode	Variable, te	aching in	any sequence
Positioning Miscellany		DC servo motor	Position and sp	unction	Position and	d speed	Variable		Politicalog
Miscellany	yro	Linear control, hand circular control, Hig	l direction control, h-speed circular cont	Teaching functions	Memory mo	ode	Bubble men	nory	Miscellany
Power-External -Internal	atnio	1,0000	φ, 1kVA	Teg	Memory cap	pacity	Max. 6000	points	Power & street
Internal measurir ability	g	Pulse coder, limit sw	vitch, etc.	М	scellany	lingit swite			x. 2700 points) gram control, etc.
External measuri Recognizing abili		Personal and the second	Auxiliary functions		exiliary functions etc.	ons,	engalak inter		External seessyrian Recognizing about
Outward	figure	Characteristics of the	Operation space		Operation	Cha	racteristics of the	robot	Outward I
ide view)	4-M12 tsp th (for eye bolts)	282 282 282 282 282 282 282	ist mounting surface 300 laxis center lole through g bots-M12)		assembly 1. Max 2. The up/e turn 3. Acc 4. 4-ax 5. Line	y, washing, c. load capa robot has down 150 n ning 300°. curate repea cis-at-a-time ear control are possible	-MODEL 00 is a sealing, etc. acity at wrist is 10 the sufficient womm, in/out 300 representation of ±0.05 to control is possible, hand direction of e.	0 kg. ork space mm, and mm.	for assembly; right-left