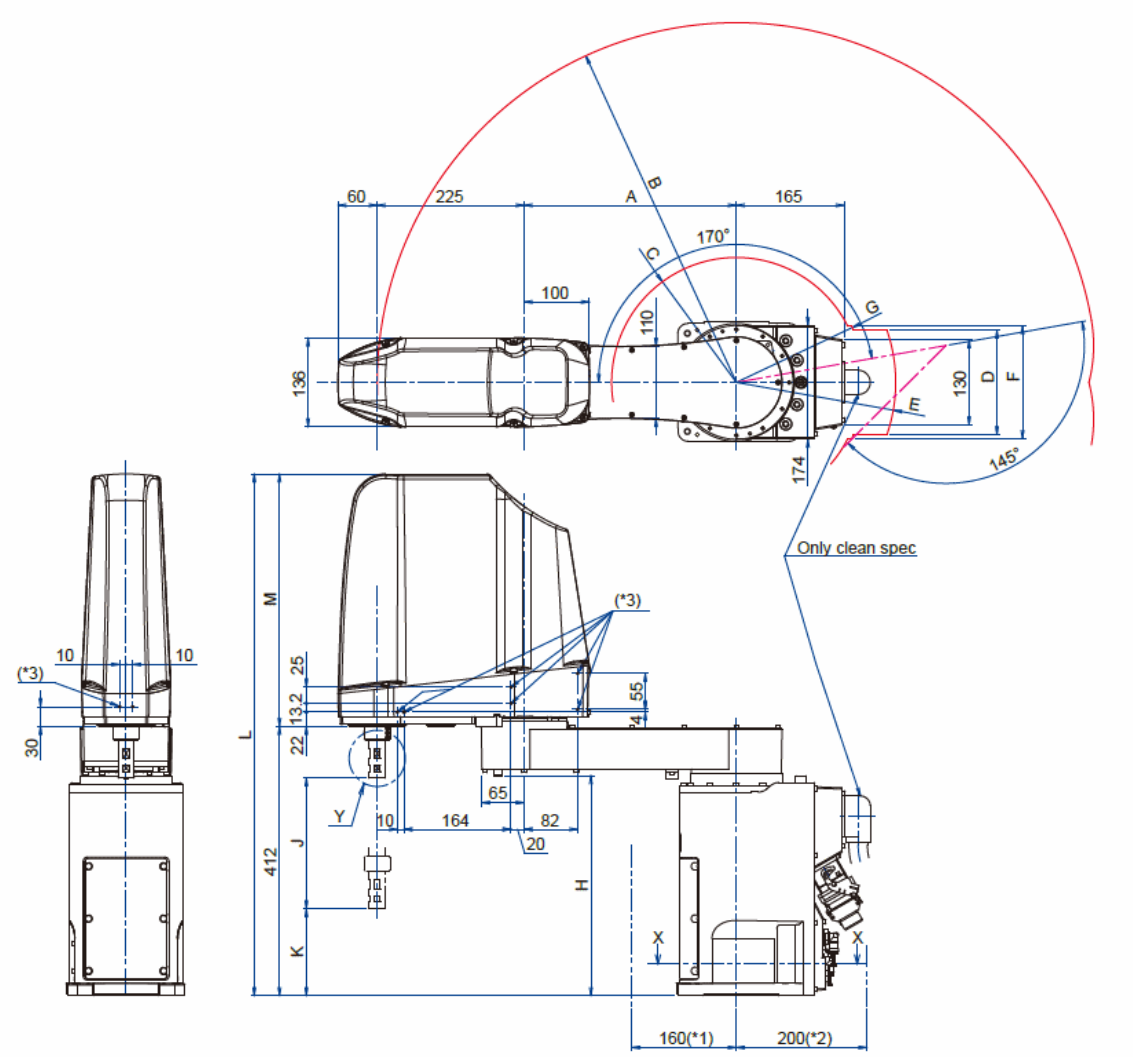
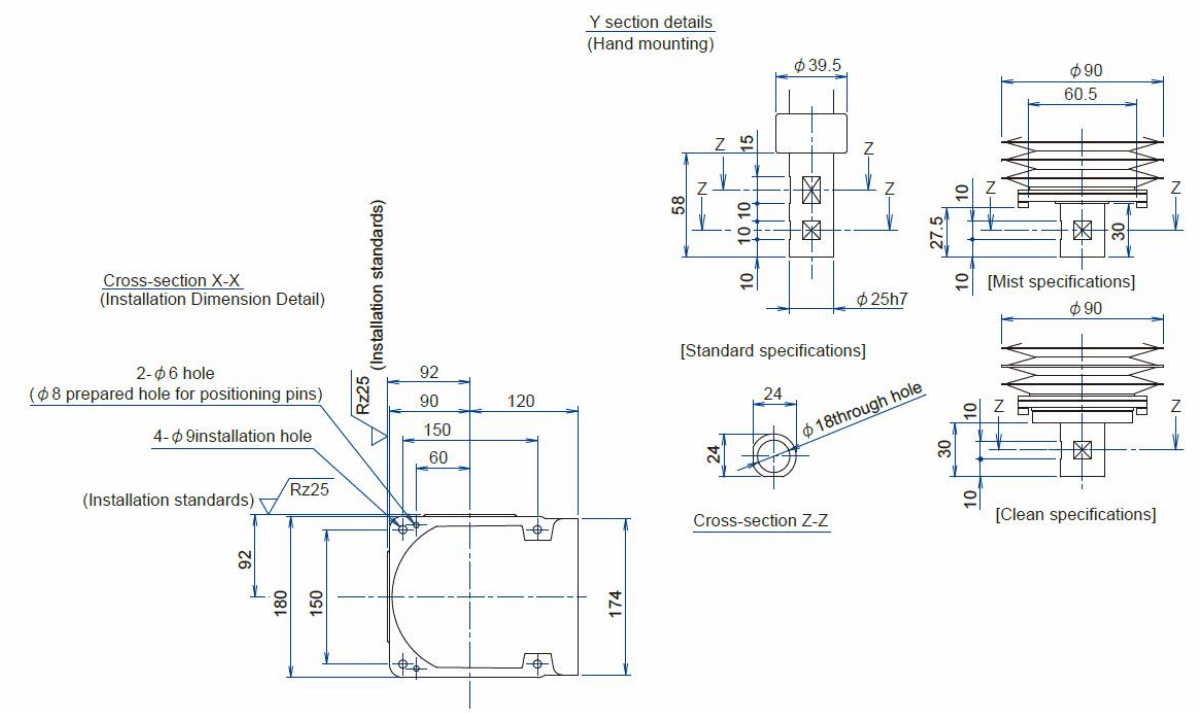
Zał. 05 - "Specyfikacja robota typu Scara"
do Specyfikacja istotnych warunków zamówienia
do projektu i budowy linii przemysłowej - Linia4.0

Robot SCARA - Mitsubishi **RH-6FH5520**-D1-S1 zgodnie ze specyfikacją jak w rys. 1 i 2 oraz tab. 1 i 2.



Rys. 1. Wymiary dla robotów serii **RH-6FH55**



Rys. 2. Wymiary dla robotów serii **RH-6FH55**

Tab. 1. Specyfikacja wymiarowa dla robotów serii **RH-6FH**

Variable dimensions

Robot series	A	B	C	D	E	F	G	H	J	K	L	M
RH-6FH3520	125	R350	R142	210	R253	220	R174	342	200	133	798	386
RH-6FH3520M/C	125	R350	R142	224	R253	268	R196	342	200	133	798	386
RH-6FH3534	125	R350	R142	210	R253	220	R174	342	340	-7	938	526
RH-6FH3534M/C	125	R350	R142	224	R253	268	R196	342	340	-43	938	526
RH-6FH4520	225	R450	R135	210	R253	220	R174	337	200	133	798	386
RH-6FH4520M/C	225	R450	R135	224	R253	268	R197	337	200	133	798	386
RH-6FH4534	225	R450	R135	210	R253	220	R174	337	340	-7	938	526
RH-6FH4534M/C	225	R450	R135	224	R253	268	R197	337	340	-43	938	526
RH-6FH5520	325	R550	R191	160	R244	172	R197	337	200	133	798	386
RH-6FH5520C	325	R550	R191	160	R253	259	R222	337	200	133	798	386
RH-6FH5520M	325	R550	R191	160	R244	259	R222	337	200	133	798	386
RH-6FH5534	325	R550	R191	160	R244	172	R197	337	340	-7	938	526
RH-6FH5534C	325	R550	R191	160	R253	259	R222	337	340	-43	938	526
RH-6FH5534M	325	R550	R191	160	R244	259	R222	337	340	-43	938	526

*1: Space required for the battery replacement
*2: Space required for the interconnection cable
*3: Screw holes (M4, 6 mm long) for affixing user wiring and piping. (6 locations on both sides and 2 locations on the front of the No. 2 arm.)

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Tab. 2. Specyfikacja techniczna dla robotów serii **RH-6FH**

Specifications

Type		Unit	RH-6FH35XX/M/C	RH-6FH45XX/M/C	RH-6FH55XX/M/C
Machine class			Standard/ oil mist/ Clean		
Protection degree *1			IP20 *6/ IP65 *7/ ISO3 *8		
Installation			Floor type		
Structure			Horizontal, multiple-joint type		
Degrees of freedom			4		
Drive system			AC servo motor		
Position detection method			Absolute encoder		
Maximum load capacity		kg	Maximum 6 (rating 3)		
Arm length	NO1 arm	mm	125	225	325
	NO2 arm		225		
Maximum reach radius		mm	350	450	550
Operating range	J1	deg	340 (±170)		
	J2		290 (±145)		
	J3 (Z)	mm	xx = 20 : 200/ xx = 34 : 340		
	J4 (θ)	deg	720 (±360)		
Maximum speed	J1	deg/sec	400		
	J2		670		
	J3 (Z)	mm/sec	2400		
	J4 (θ)	deg/sec	2500		
Maximum composite speed *2		mm/sec	6900	7600	8300
Cycle time *3			0.29		
Position repeatability	Y-X composite	mm	±0.010	±0.010	±0.012
	J3 (Z)		±0.01		
	J4 (θ)	deg	±0.004		
Ambient temperature			0 to 40		
Mass		kg	36	36	37
Tolerable amount of inertia	Rating	kgm^2	0.01		
	Maximum		0.12		
Tool wiring			Hand: 8 input points/8 output points (20 pins total) Serial signal cable for parallel I/O (2-pin + 2-pin power line) LAN X 1 <100 BASE-TX> (8-pin)) *4		
Tool pneumatic pipes			Primary: φ6 x 2 Secondary: φ4 x 8		
Machine cable			5m (connector on both ends)		
Connected controller *5			CR750, CR751		

*1: The range of vertical movement listed in the environmental resistance specifications (M: Oil mist specifications, C: Cleanroom specifications) for the RH-6FH is factory-set custom specifications.
*2: The value assumes composition of J1, J2, and J4.
*3: Value for a maximum load capacity of 2 kg. The cycle time may increase if specific requirements apply such as high work positioning accuracy, or depending on the operating position. (The cycle time is based on back-and-forth movement over a vertical distance of 25 mm and horizontal distance of 300 mm.)
*4: Can also be used as a spare line (0.2 sq. mm, 4-pair cable) for conventional models.
*5: Select either controller according to your application. Note that controllers with oil mist specifications come equipped with a controller protection box (CR750-MB) and "-SM" is appended at the end of the robot model name. If you require it, consult with the Mitsubishi Electric dealer.
*6: IP54 rating for European models.
*7: Please contact Mitsubishi Electric dealer since the environmental resistance may not be secured depending on the characteristics of oil you use. Direct jet to the bellows is excluded.
*8: Preservation of cleanliness levels depends on conditions of a downstream flow of 0.3 m/s in the clean room and internal robot suctioning. A φ8-mm coupler for suctioning is provided at the back of the base.

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