



OTC DAIHEN EUROPE

**Roboter – Technische Daten
Manipulator Specifications**

FD-V6L

Model		FD-V6L	
Kinematic		Vertical artic. type	
No. of Axes		6	
P-Point (Working Range)		R 2,006 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° ≈ +100°
		J7	
	Wrist	J3 (Rotation)	-170° ≈ +260°
		J4 (Rotation)	± 180°
		J5 (Bending)	-50° ≈ +230°
Maximum Speed	Arm	J6 (Rotation)	± 360°
		J1 (Rotation)	195°/s
		J2 (Vertical)	200°/s
	Wrist	J7	
		J3 (Rotation)	200°/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 ²
Ambient Temp./Humidity		0 ≈ 45°, 20 ≈ 80%	
Mass (weight)		280 kg	
Upper arm max. Carrying capacity(*2)		20 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



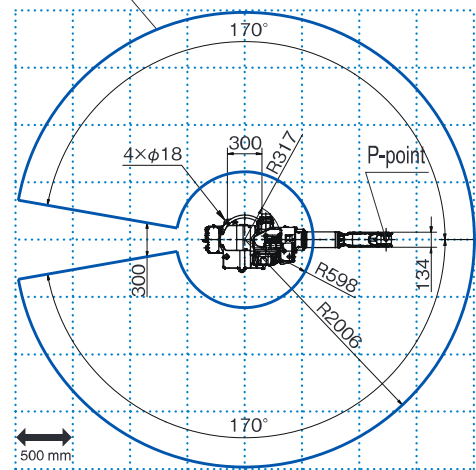
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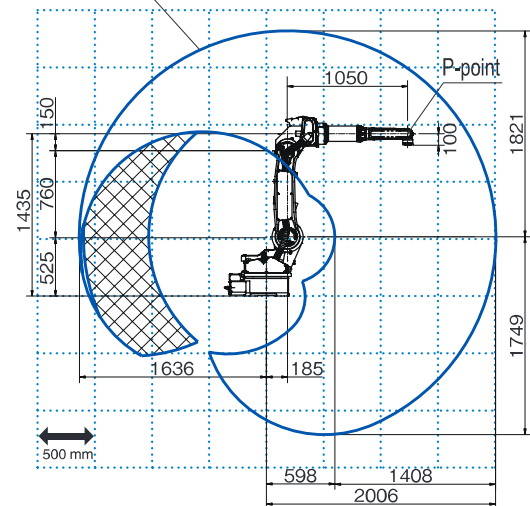
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Maximum Payload Capacity	6 kg			
Positional Repeatability(*1)	± 0.08 mm			
Driving Method	AC Servo Motor			
Working Range	Arm	J1 (Rotation) ± 170° J2 (Vertical) -155° ≈ +100° J7		
	Wrist	J3 (Rotation) -170° ≈ +260° J4 (Rotation) ± 180° J5 (Bending) -50° ≈ +230° J6 (Rotation) ± 360°		
	Maximum Speed	Arm	J1 (Rotation) 195°/s J2 (Vertical) 200°/s J7	
		Wrist	J3 (Rotation) 200°/s J4 (Rotation) 420°/s J5 (Bending) 420°/s J6 (Rotation) 620°/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 ² J5 (Bending) 0.25 kg/m ² J6 (Rotation) 0.06 kg/m ²
			Ambient Temp./Humidity	0 ≈ 45°, 20 ≈ 80%
Mass (weight)			280 kg	
Upper arm max. Carrying capacity(*2)			20 kg (Note 2)	
Origin Return	Note 3			
Installation Position	F, W, C			

P-point Working Range



P-point Working Range



□ : For welding applications when floor-mounted
 ⊞ □ : For other than the above

Note 1: Measured value obtained after sufficient repetition of automatic operation for stabilizing conditions.
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 Note 3: Positional data protected by battery-backed storage inside the manipulator.
 F = Floor W = Wall C = Ceiling