

## 2.3 Robot Specifications

The robot specifications are as shown in Table 2-2

Table 2-2 The robot specifications

Item		Specification	
Model No.		RA620-1739	RA620-1621
Degrees of Freedom		6	
Installation		Floor (wall mounting, ceiling mounting) [*1]	
Load capacity		20kg [*2]	30kg[*2]
Maximum reach radius		1739 mm	1621mm
Cycle time		0.9 s [*3]	
Position Repeatability		±0.06 mm	
Motion range	J1	±180°	
	J2	+100°~-135°	
	J3	+190°~-80°	
	J4	±200°	
	J5	±130°	
	J6	±360°	
Maximum speed	J1	231° / s	
	J2	210° / s	
	J3	205° / s	
	J4	360° / s	
	J5	420° / s	210° / s
	J6	720° / s	360° / s
Allowable load moment at wrist	J4	34.2 N-m	65.5 N-m
	J5	34.2 N-m	65.5 N-m
	J6	22.3 N-m	34 N-m
Allowable load inertia at wrist	J4	1.35 kg- m <sup>2</sup>	4.71 kg- m <sup>2</sup>
	J5	1.35 kg- m <sup>2</sup>	4.71 kg- m <sup>2</sup>
	J6	0.6 kg- m <sup>2</sup>	1.49 kg- m <sup>2</sup>
Weight		230 kg	226 kg
Protection rating		Wrist(J5~J6) :IP65, Arm(J1~J4): IP54	
Acoustic noise level		Less than 75 dBA [*4]	

[Note 1] : The robot arm motion range shall be defined when used by mounting on the wall.  
So that the end effector does not interfere with the rear side of robot arm when mounting on the wall.

[Note 2] : When installing the end effector, please refer to section 2.5.

[Note 3] : The cycle time is the time that the robot is loaded at 20kg to forward and backward move in the vertical height 25mm and the horizontal distance 30mm, as shown in Figure 2-2.

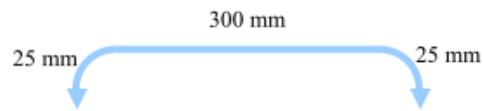


Figure 2-2 Moving path for cycle time

[Note 4] : This is measured at maximum speed and maximum load according to ISO11201:2010.