TSUBISHI INDUSTRIAL ROBOT
ELFA F Series

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his catalog is an introduction to only part of what Mitsubishi Electric has to offer.
litsubishi Electric offers individualized solutions for the challenges in your factory.

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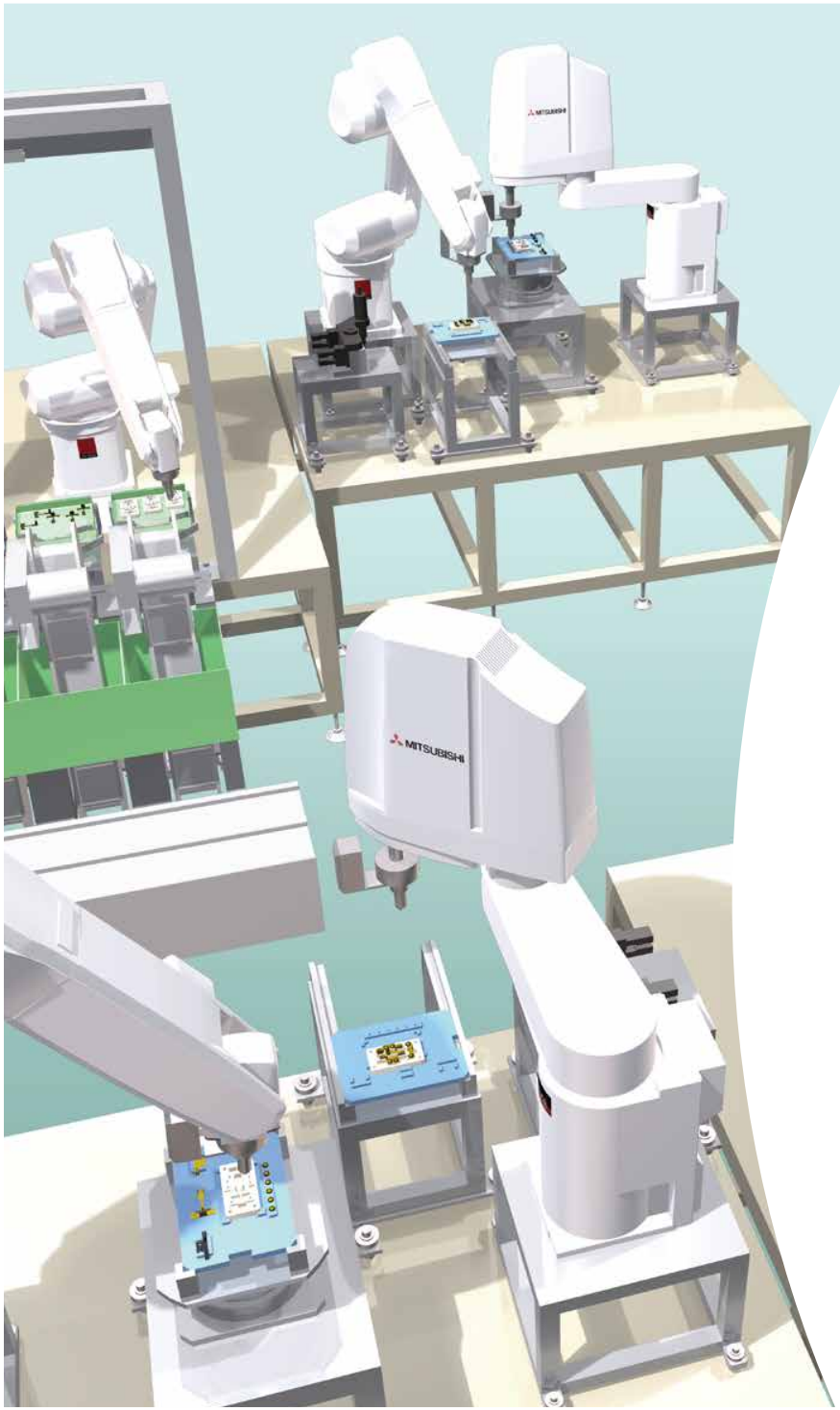
Specifications are subject to change without notice.

Changes for the Bet

MITSUBISHI ELECTRIC

MITSUBISHI INDUSTRIAL ROBOT
MELFA F Series



Features

Mitsubishi Electric's F-Series industrial robots are equipped with technology developed and tested at its own production plants. Equipped with advanced technology and easy-to-use features, these robots are designed to facilitate automation of any production plant.

- Designed for flexible automation
- Compact and powerful
- High reliability

Vertical type

A compact 6-axis jointed robot with an optimal arm length and wider range of movement suited for complex assembly and processing tasks.
Compact body and slim arm design, allowing operating area to be expanded and load capacity increased.
Layout accommodates a wide range of applications from transport of mechanical parts to assembly of electrical parts.
Environmental resistance specifications enable application to a wide range of uses without needing to consider the installation environment.

- The fastest high-speed operation in its class
- Contributes to improved productivity with high-frequency operations
- Prevention of interference with cables
- Compatibility with internal Ethernet cable tools
- Expanded J4 axis operating range
- Compact installation with operation performed near the robot base
- Changes in operating posture made even more quickly
- Full use of installation space

Horizontal type

Matches perfectly to a variety of applications with a wide range of operating areas and variations.
High speed and high accuracy achieved with the highly rigid arm and latest servo control technology.
Suitable for a wide range of fields from mass production of food and pharmaceutical products requiring high-speed operation to assembly operations requiring high precision.

- The fastest high-speed operation in its class
- Improved speed for vertical movements
- Improved continuous operability
- Enhanced wrist axis
- Internal routing of cables results in simplified cable management
- Compatibility with internal Ethernet cable tools
- Full use of installation space

Lineup

With a wide range of variations from Mitsubishi Electric, committed to ease in selection.

The Mitsubishi Electric robot product line is equipped with all of the basic performance features desired in a robot, such as being powerful, speedy, and compact.
The variations that Mitsubishi Electric is confident meet the needs of the current era and have pushed Factory Automation forward in a dramatic way.

Vertical, multiple-joint type (RV)

Type		RV-2F	RV-4F	RV-4FL	RV-7F	RV-7FL	RV-7FLL	RV-13F	RV-13FL	RV-20F
Maximum load capacity (kg)		3	4	4	7	7	7	13	13	20
Maximum reach radius (mm)		504	515	649	713	908	1503	1094	1388	1094
Environmental specifications	Standard	○ (IP30)	○ (IP40)	○ (IP40)	○ (IP40)	○ (IP40)	○ (IP40)	○ (IP40)	○ (IP40)	○ (IP40)
	Oil mist	—	○ (IP67)	○ (IP67)	○ (IP67)	○ (IP67)	○ (IP67)	○ (IP67)	○ (IP67)	○ (IP67)
	Clean	—	○ (ISOclass3)	○ (ISOclass3)	○ (ISOclass3)	○ (ISOclass3)	○ (ISOclass3)	○ (ISOclass3)	○ (ISOclass3)	○ (ISOclass3)
	Medical, food	—	○ (IP65)	○ (IP65)	○ (IP65)	○ (IP65)	○ (IP65)	○ (IP65)	○ (IP65)	○ (IP65)
Controller		CR750				CR751		Controllers with protective specifications (Equipped with controller protection boxes)		

RV - 4 F L C - D 1 - Sxx

- Sxx: Compliant with special models such as CE specification and KC specification etc (separately) SHxx: Internal wiring specifications
- 1: CE/KC specification
- **Controller type** D: CR750-D Q: CR750-Q 1D: CR751-D 1Q: CR751-Q
- **Environment specification** Blank: Standard specifications M: Oilmist specifications C: Clean specifications
- **Arm length** Blank: Standard arm L: Long arm LL: Super long arm
- **Series** F: F series
- **Maximum load capacity** 2: 2kg 4: 4kg 7: 7kg 13: 13kg 20: 20kg
- **Robot structure** RV: Vertical, multiple-joint type

Horizontal, multiple-joint type (RH)

Type		RH-3FH35	RH-3FH45	RH-3FH55	RH-6FH35	RH-6FH45	RH-6FH55	RH-12FH55	RH-12FH70	RH-12FH85	RH-20FH85	RH-20FH100	RH-3FHR
Maximum load capacity (kg)		3	3	3	6	6	6	12	12	12	20	20	3
Maximum reach radius (mm)		350	450	550	350	450	550	550	700	850	850	1000	350
Environmental specifications	Standard	○ (IP20)			○ (IP20)			○ (IP20)			○ (IP20)		○ (IP20)
	Oil mist	—			○ (IP65)			○ (IP65)			○ (IP65)		Water proof: ○ (IP65)
	Clean	○ (ISOclass3)			○ (ISOclass3)			○ (ISOclass3)			○ (ISOclass3)		○ (ISOclass5)
	Medical, food	—			○ (IP65)			○ (IP65)			○ (IP65)		—
Controller		CR750				CR751				Controllers with protective specifications (Equipped with controller protection boxes)			

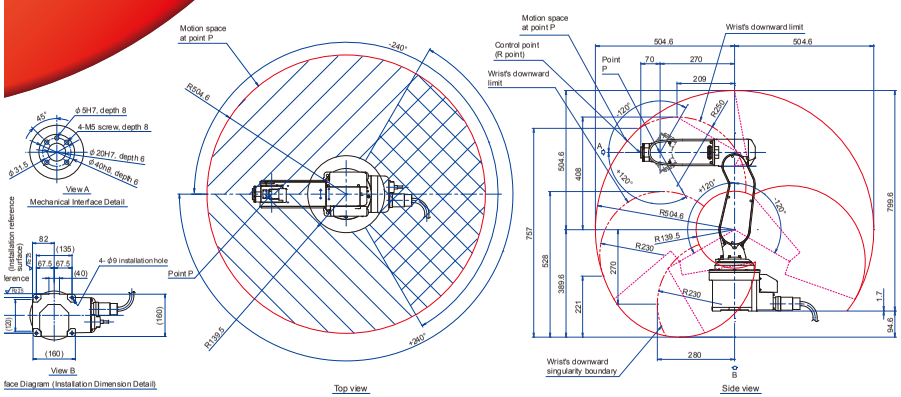
RH - 6 FH 55 20 M - D 1 - Sxx

- Sxx: Compliant with special models such as CE specification and KC specification etc (separately) SM: Specification with protection specification controller (with the protection box)
- 1: CE/KC specification
- **Controller type** D: CR750-D Q: CR750-Q 1D: CR751-D 1Q: CR751-Q
- **Environment specification** Blank: Standard specifications M: Oilmist specifications C: Clean specifications
- **Vertical stroke** 12 : 120mm 34 : 340mm 15 : 150mm 35 : 350mm 20 : 200mm 45 : 450mm
- **Arm length** 35 : 350mm 70 : 700mm 45 : 450mm 85 : 850mm 55 : 550mm 100 : 1000mm
- **Series** FH: F series FHR: F series
- **Maximum load capacity** 3: 3kg 6: 6kg 12: 12kg 20: 20kg
- **Robot structure** RH: Horizontal, multiple-joint type

Vertical 2kg type

RV-2F

External Dimensions/Operating Range Diagram



Specifications

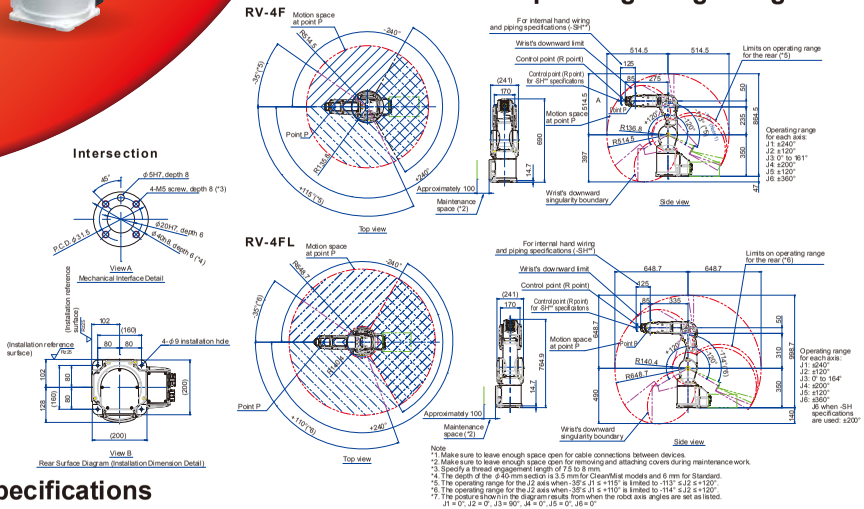
Type		Unit	RV-2F(B)
Environmental specifications			Standard
Protection degree			IP30
Installation			Floor type, ceiling type, (wall-mounted type *2)
Structure			Vertical, multiple-joint type
Degrees of freedom			6
Drive system *1			AC servo motor (J2, J3 and J5: with brake)
Position detection method			Absolute encoder
Maximum load capacity		kg	maximum 3 (Rated 2) *5
Arm length	NO1 arm	mm	230 + 270
Maximum reach radius		mm	504
Operating range	J1	deg	480 (±240)
	J2		240 (-120 to +120)
	J3		160 (-0 to +160)
	J4		400 (±200)
	J5		240 (-120 to +120)
	J6		720 (-360 to +360)
Maximum speed	J1	deg/sec	300
	J2		150
	J3		300
	J4		450
	J5		450
	J6		720
Maximum composite speed *3		mm/sec	4955
Cycle time *4		sec	0.6
Position repeatability		mm	±0.02
Ambient temperature		°C	0 to 40
Mass		kg	19
Tolerable moment	J4	Nm	4.17
	J5		4.17
	J6		2.45
Tolerable amount of inertia	J4	kgm²	0.18
	J5		0.18
	J6		0.04
Tool wiring			Hand: 4 input points/4 output points Signal cable for the multi-function hand
Tool pneumatic pipes			ϕ4 x 4
Machine cable			5m (connector on both ends)
Connected controller			CR750, CR751

*1: The standard model does not have a brake on the J1, J4, or J6 axis. There are models available with brakes included for all axes. (RV-2FB)
*2: The wall-mounted specification is a custom specification where the operating range of the J1-axis is limited.
*3: This is the value at the surface of the mechanical interface when all axes are composited.
*4: The cycle time is based on back-and-forth movement over a vertical distance of 25 mm and horizontal distance of 300 mm when the load is 1 kg.
*5: The maximum load capacity indicates the maximum payload when the mechanical interface is facing downward (±10° to the perpendicular).

Vertical 4kg type

RV-4F
RV-4FL

External Dimensions/Operating Range Diagram



Note
*1: Make sure to leave enough space open for cable connections between devices.
*2: Make sure to leave enough space open for removing and attaching covers during maintenance work.
*3: Specify a thread engagement length of 7.5 to 8 mm.
*4: The depth of the ϕ40 mm section is 3.5 mm for CleanMist models and 6 mm for Standard.
*5: The operating range for the J2 axis when -35° ≤ J1 ≤ +115° is limited to -113° ≤ J2 ≤ +120°.
*6: The operating range for the J2 axis when -35° ≤ J1 ≤ +110° is limited to -114° ≤ J2 ≤ +120°.
*7: The posture shown in the diagram results from when the robot axis angles are set as listed.
J1 = 0°, J2 = 0°, J3 = 90°, J4 = 0°, J5 = 0°, J6 = 0°

Specifications

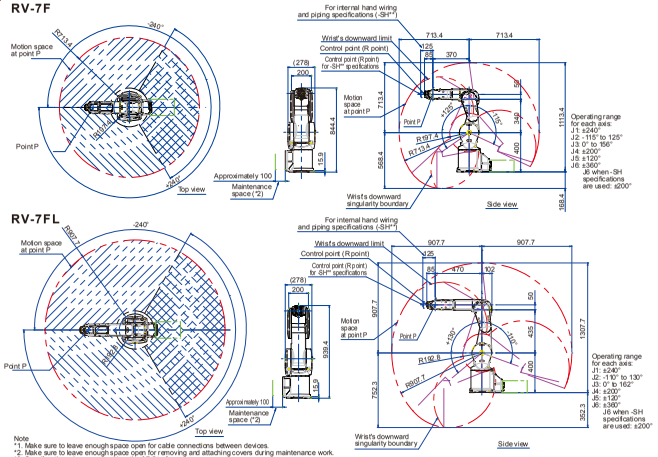
Type		Unit	RV-4F(M)(C)	RV-4FL(M)(C)
Environmental specifications			Standard/ Oil mist/ Clean	
Protection degree			IP40 (standard)/ IP67 (oil mist) *1/ ISOclass3 *7	
Installation			Floor type, ceiling type, (wall-mounted type *2)	
Structure			Vertical, multiple-joint type	
Degrees of freedom			6	
Drive system *1			AC servo motor	
Position detection method			Absolute encoder	
Maximum load capacity		kg	4	
Arm length	NO1 arm	mm	240 + 270	245 + 300
Maximum reach radius		mm	515	649
Operating range	J1	deg	480 (±240)	
	J2		240 (-120 to +120)	
	J3		161 (-0 to +161)	164 (-0 to +164)
	J4		400 (±200)	
	J5		240 (-120 to +120)	
	J6		720 (±360)	
Maximum speed	J1	deg/sec	450	420
	J2		450	336
	J3		300	250
	J4		540	540
	J5		623	623
	J6		720	720
Maximum composite speed *3		mm/sec	9027	9048
Cycle time *4		sec	0.36	0.36
Position repeatability		mm	±0.02	
Ambient temperature		°C	0 to 40	
Mass		kg	39	41
Tolerable moment	J4	Nm	6.66	
	J5		6.66	
	J6		3.96	
Tolerable amount of inertia	J4	kgm²	0.2	
	J5		0.2	
	J6		0.1	
Tool wiring			Hand: 8 input points/8 output points Signal cable for the multi-function hand and sensors LAN X 1 <100 BASE-TX> (8-pin)) *5	
Tool pneumatic pipes			Primary: ϕ6 x 2 Secondary: ϕ4 x 8, ϕ4 x 4 (from base portion to forearm)	
Machine cable			5m (connector on both ends)	
Connected controller *6			CR750, CR751	

*1: Please contact Mitsubishi Electric dealer since the environmental resistance may not be secured depending on the characteristics of oil you use. Air will need to be purged from the lines. For details, refer to the specifications sheet.
*2: The wall-mounted specification is a custom specification where the operating range of the J1-axis is limited.
*3: This is the value at the surface of the mechanical interface when all axes are composited.
*4: The cycle time is based on back-and-forth movement over a vertical distance of 25 mm and horizontal distance of 300 mm when the load is 1 kg.
*5: Can also be used as a spare line (0.2 sq. mm, 4-pair cable) for conventional models.
*6: Select either controller according to your application. CR751-D: Standalone type, CR751-Q: iQ Platform compatible type.
*7: 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.

Vertical 7 kg type

RV-7F
RV-7FL

External Dimensions/Operating Range Diagram



Note
*1. Make sure to leave enough space open for cable connections between devices.
*2. Make sure to leave enough space open for removing and attaching covers during maintenance work.
*3. Specify a thread engagement length of 7.5 to 8 mm.
*4. The depth of the φ40-mm section is 3.5 mm for Clean/Mist models and 6 mm for Standard.
*5. The posture shown in the diagram results from when the robot axis angles are set as listed.
J1 = 0°, J2 = 0°, J3 = 90°, J4 = 0°, J5 = 0°, J6 = 0°

Specifications

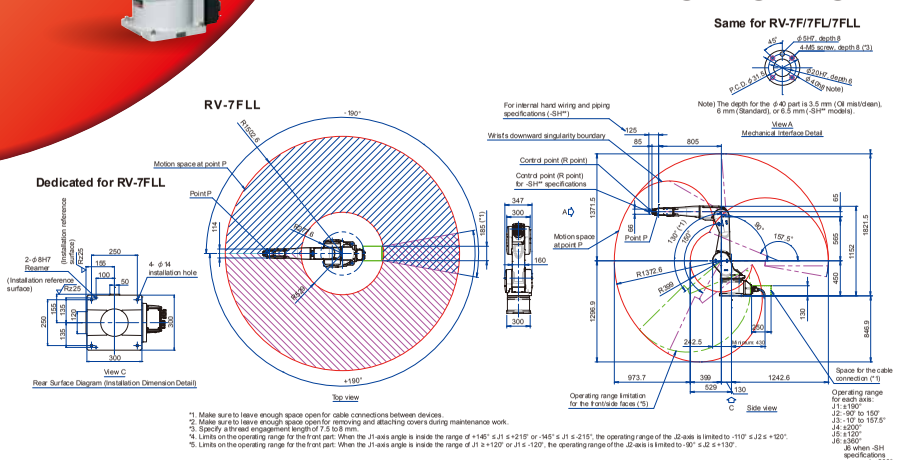
Type		Unit	RV-7F(M)(C)	RV-7FL(M)(C)
Machine class			Standard/ Oil mist/ Clean	
Protection degree			IP40 (standard)/ IP67 (oil mist) *1/ ISOclass3 *7	
Installation			Floor type, ceiling type, (wall-mounted type *2)	
Structure			Vertical, multiple-joint type	
Degrees of freedom			6	
Drive system			AC servo motor	
Position detection method			Absolute encoder	
Maximum load capacity		kg	7	
Arm length	NO1 arm	mm	340 + 370	435 + 470
Maximum reach radius		mm	713	908
Operating range	J1	deg	480 (±240)	
	J2		240 (-115 to +125)	240 (-110 to +130)
	J3		156 (-0 to +156)	162 (-0 to +162)
	J4		400 (±200)	
	J5		240 (-120 to +120)	
	J6		720 (±360)	
Maximum speed	J1	deg/sec	360	288
	J2		401	321
	J3		450	360
	J4		337	337
	J5		450	450
	J6		720	720
Maximum composite speed *3		mm/sec	11064	10977
Cycle time *4		sec	0.32	0.35
Position repeatability		mm	±0.02	
Ambient temperature		°C	0 to 40	
Mass		kg	65	67
Tolerable moment	J4	Nm	16.2	
	J5		16.2	
	J6		6.86	
Tolerable amount of inertia	J4	kgm²	0.45	
	J5		0.45	
	J6		0.10	
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)) *5	
Tool pneumatic pipes			Primary: φ6 x 2 Secondary: φ4 x 8, φ4 x 4 (from base portion to forearm)	
Machine cable			5m (connector on both ends)	
Connected controller			CR750, CR751	

*1: Please contact Mitsubishi Electric dealer since the environmental resistance may not be secured depending on the characteristics of oil you use. Air will need to be purged from the lines. For details, refer to the specifications sheet.
*2: The wall-mounted specification is a custom specification where the operating range of the J1-axis is limited.
*3: This is at the hand flange surface when all axes are composited.
*4: The cycle time is based on back-and-forth movement over a vertical distance of 25 mm and horizontal distance of 300 mm when the load is 1 kg.
*5: Can also be used as a spare line (0.2 sq. mm, 4-pair cable) for conventional models.
*6: Select either controller according to your application.
*7: 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.

Vertical 7 kg type

RV-7FLL

External Dimensions/Operating Range Diagram



Note) The depth for the φ40 part is 3.5 mm (Oil mist/clean), 6 mm (Standard), or 6.5 mm (-SH** models).

*1. Make sure to leave enough space open for cable connections between devices.
*2. Make sure to leave enough space open for removing and attaching covers during maintenance work.
*3. Specify a thread engagement length of 7.5 to 8 mm.
*4. Limits on the operating range for the front part: When the J1-axis angle is inside the range of +146° ≤ J1 ≤ +215° or -145° ≤ J1 ≤ -215°, the operating range of the J2-axis is limited to -110° ≤ J2 ≤ +120°.
*5. Limits on the operating range for the front part: When the J1-axis angle is inside the range of J1 ≥ +120° or J1 ≤ -120°, the operating range of the J2-axis is limited to -90° ≤ J2 ≤ +130°.

Specifications

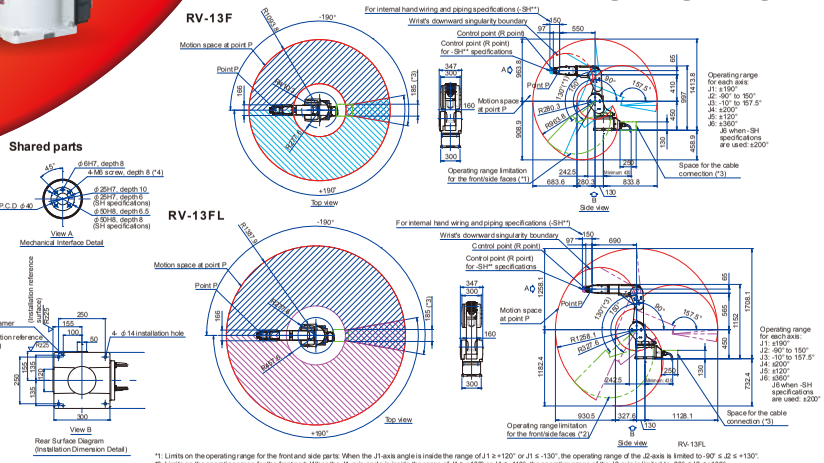
Type		Unit	RV-7FLL(M)(C)
Machine class			Standard/ Oil mist/ Clean
Protection degree			IP40 (standard)/ IP67 (oil mist) *1/ ISOclass3 *7
Installation			Floor type, ceiling type, (wall-mounted type *2)
Structure			Vertical, multiple-joint type
Degrees of freedom			6
Drive system			AC servo motor
Position detection method			Absolute encoder
Maximum load capacity		kg	Maximum: 7 (Rated: 7)
Arm length	NO1 arm	mm	565 + 805
Maximum reach radius		mm	1503
Operating range	J1	deg	380 (±190)
	J2		240 (-90 to +150)
	J3		167.5 (-10 to +157.5)
	J4		400 (±200)
	J5		240 (-120 to +120)
	J6		720 (±360)
Maximum speed	J1	deg/sec	234
	J2		164
	J3		219
	J4		375
	J5		450
	J6		720
Maximum composite speed *3		mm/sec	15300
Cycle time *4		sec	0.63
Position repeatability		mm	±0.06
Ambient temperature		°C	0 to 40
Mass		kg	130
Tolerable moment	J4	Nm	16.2
	J5		16.2
	J6		6.86
Tolerable amount of inertia	J4	kgm²	0.45
	J5		0.45
	J6		0.10
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)) *5
Tool pneumatic pipes			Primary: φ6 x 2 Secondary: φ4 x 8, φ4 x 4 (With wrist attached)
Machine cable			7m (connector on both ends)
Connected controller			CR750, CR751

*1: Please contact Mitsubishi Electric dealer since the environmental resistance may not be secured depending on the characteristics of oil you use.
*2: The wall-mounted specification is a custom specification where the operating range of the J1-axis is limited.
*3: This is the value at the surface of the mechanical interface when all axes are composited.
*4: The cycle time is based on back-and-forth movement over a vertical distance of 25 mm and horizontal distance of 300 mm when the load is 1 kg.
*5: Can also be used as a spare line (0.13 sq. mm, 4-pair cable) for conventional models. Provided up to the inside of the forearm.
*6: Select either controller according to your application.
*7: 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.

Vertical 13kg type

RV-13F
RV-13FL

External Dimensions/Operating Range Diagram



*1: Limits on the operating range for the front and side parts: When the J1-axis angle is inside the range of J1 ≥ +120° or J1 ≤ -130°, the operating range of the J2-axis is limited to -90° ≤ J2 ≤ +130°.
*2: Limits on the operating range for the front part: When the J1-axis angle is inside the range of J1 ≥ +130° or J1 ≤ -140°, the operating range of the J2-axis is limited to -90° ≤ J2 ≤ +130°.
*3: Make sure to leave enough space open for cable connections between devices.
*4: Specify a thread engagement length of 10 to 9 mm.

Specifications

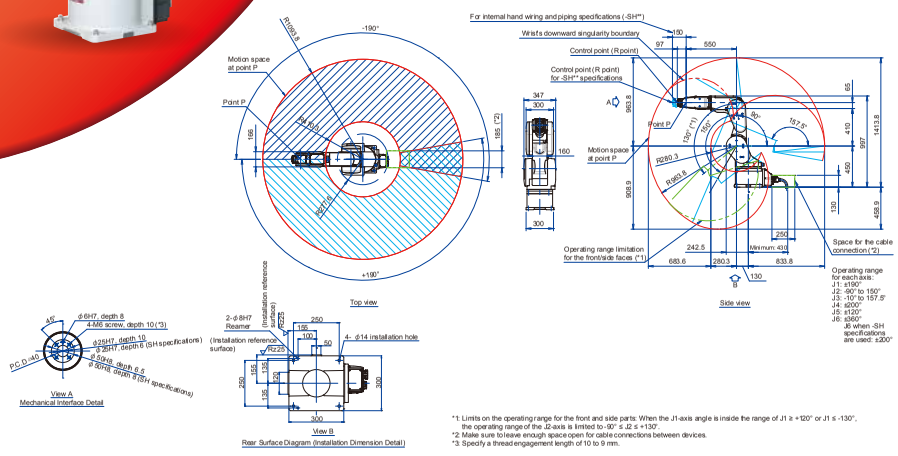
Type		Unit	RV-13F(M)(C)	RV-13FL(M)(C)
Machine class			Standard/ Oil mist/ Clean	
Protection degree			IP40 (standard)/ IP67 (oil mist) *1/ ISOclass3 *7	
Installation			Floor type, ceiling type, (wall-mounted type *2)	
Structure			Vertical, multiple-joint type	
Degrees of freedom			6	
Drive system			AC servo motor	
Position detection method			Absolute encoder	
Maximum load capacity		kg	Maximum: 13 (Rated: 12) *8	
Arm length	NO1 arm	mm	410 + 550	565 + 690
Maximum reach radius		mm	1094	1388
Operating range	J1	deg	380(±190)	
	J2		240 (-90 to +150)	
	J3		167.5 (-10 to +157.5)	
	J4		400 (±200)	
	J5		240 (-120 to +120)	
	J6		720 (±360)	
Maximum speed	J1	deg/sec	290	234
	J2		234	164
	J3		312	219
	J4		375	375
	J5		375	375
	J6		720	720
Maximum composite speed *3		mm/sec	10450	9700
Cycle time *4		sec	0.53	0.68
Position repeatability		mm	±0.05	
Ambient temperature		°C	0 to 40	
Mass		kg	120	130
Tolerable moment	J4	Nm	19.3	
	J5		19.3	
	J6		11	
Tolerable amount of inertia	J4	kgm²	0.47	
	J5		0.47	
	J6		0.14	
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)) *5	
Tool pneumatic pipes			Primary: φ6 x 2 Secondary: φ4 x 8, φ4 x 4 (With wrist attached)	
Machine cable			7m (connector on both ends)	
Connected controller			CR750, CR751	

*1: Please contact Mitsubishi Electric dealer since the environmental resistance may not be secured depending on the characteristics of oil you use.
*2: The wall-mounted specification is a custom specification where the operating range of the J1-axis is limited.
*3: This is the value at the surface of the mechanical interface when all axes are composited.
*4: The cycle time is based on back-and-forth movement over a vertical distance of 25 mm and horizontal distance of 300 mm when the load is 5 kg.
*5: Can also be used as a spare line (0.13 sq. mm, 4-pair cable) for conventional models. Provided up to the inside of the forearm.
*6: Select either controller according to your application.
*7: 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.
*8: The maximum load capacity indicates the maximum payload when the mechanical interface is facing downward (±10° to the perpendicular).

Vertical 20kg type

RV-20F

External Dimensions/Operating Range Diagram



*1: Limits on the operating range for the front and side parts: When the J1-axis angle is inside the range of J1 ≥ +120° or J1 ≤ -130°, the operating range of the J2-axis is limited to -90° ≤ J2 ≤ +130°.
*2: Make sure to leave enough space open for cable connections between devices.
*3 Specify a thread engagement length of 10 to 9 mm.

Specifications

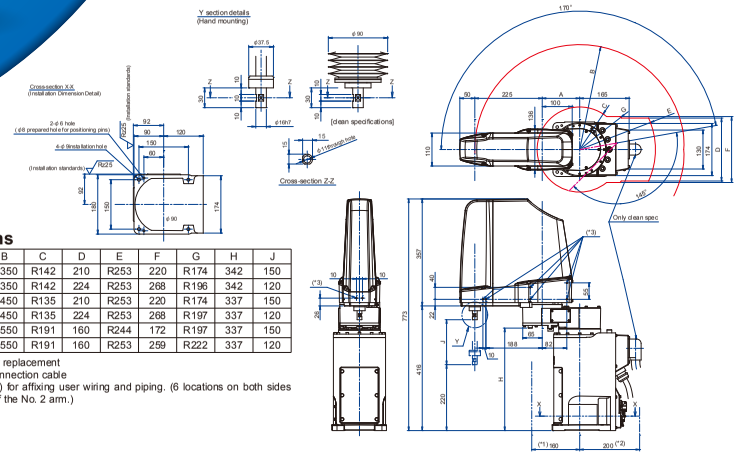
Type		Unit	RV-20F(M)(C)
Machine class			Standard/ Oil mist/ Clean
Protection degree			IP40 (standard)/ IP67 (oil mist) *1/ ISOclass3 *7
Installation			Floor type, ceiling type, (wall-mounted type *2)
Structure			Vertical, multiple-joint type
Degrees of freedom			6
Drive system			AC servo motor
Position detection method			Absolute encoder
Maximum load capacity		kg	Maximum: 20 (Rated: 15) *8
Arm length	NO1 arm	mm	410 + 550
Maximum reach radius		mm	1094
Operating range	J1	deg	380 (±190)
	J2		240 (-90 to +150)
	J3		167.5 (-10 to +157.5)
	J4		400 (±200)
	J5		240 (-120 to +120)
	J6		720 (±360)
Maximum speed	J1	deg/sec	110
	J2		110
	J3		110
	J4		124
	J5		125
	J6		360
Maximum composite speed *3		mm/sec	4200
Cycle time *4		sec	0.70
Position repeatability		mm	±0.05
Ambient temperature		°C	0 to 40
Mass		kg	120
Tolerable moment	J4	Nm	49.0
	J5		49.0
	J6		11
Tolerable amount of inertia	J4	kgm²	1.40
	J5		1.40
	J6		0.14
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)) *5
Tool pneumatic pipes			Primary: φ6 x 2 Secondary: φ4 x 8, φ4 x 4 (With wrist attached)
Machine cable			7m (connector on both ends)
Connected controller			CR750, CR751

*1: Please contact Mitsubishi Electric dealer since the environmental resistance may not be secured depending on the characteristics of oil you use.
*2: The wall-mounted specification is a custom specification where the operating range of the J1-axis is limited.
*3: This is the value at the surface of the mechanical interface when all axes are composited.
*4: The cycle time is based on back-and-forth movement over a vertical distance of 25 mm and horizontal distance of 300 mm when the load is 5 kg.
*5: Can also be used as a spare line (0.13 sq. mm, 4-pair cable) for conventional models. Provided up to the inside of the forearm.
*6: Select either controller according to your application.
*7: 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.
*8: The maximum load capacity indicates the maximum payload when the mechanical interface is facing downward (±10° to the perpendicular).

Horizontal 3kg type

RH-3FH35
RH-3FH45
RH-3FH55

External Dimensions/Operating Range Diagram



Variable dimensions

Robot series	A	B	C	D	E	F	G	H	J
RH-3FH3515	125	R350	R142	210	R253	220	R174	342	150
RH-3FH3512C	125	R350	R142	224	R253	268	R196	342	120
RH-3FH4515	225	R450	R135	210	R253	220	R174	337	150
RH-3FH4512C	225	R450	R135	224	R253	268	R197	337	120
RH-3FH5515	325	R550	R191	160	R244	172	R197	337	150
RH-3FH5512C	325	R550	R191	160	R253	259	R222	337	120

*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.)

Specifications

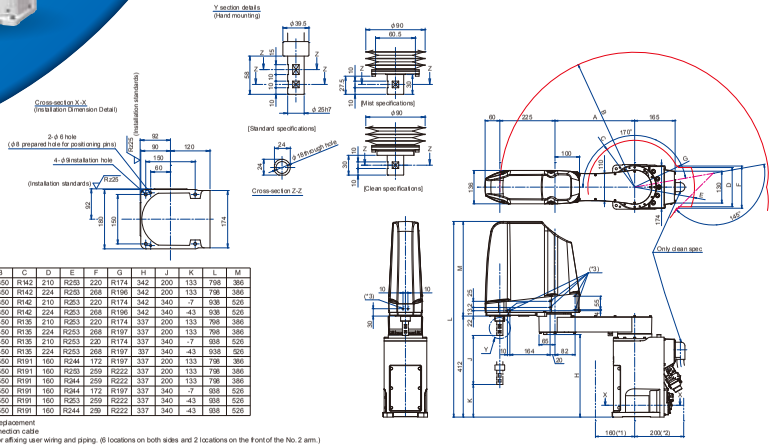
Type		Unit	RH-3FH3515/12C	RH-3FH4515/12C	RH-3FH5515/12C
Machine class			Standard/ Clean		
Protection degree *1			IP20/ ISOclass3 *6		
Installation			Floor type		
Structure			Horizontal, multiple-joint type		
Degrees of freedom			4		
Drive system			AC servo motor		
Position detection method			Absolute encoder		
Maximum load capacity		kg	Maximum 3 (rating 1)		
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	150 (Clean specification : 120) *1		
	J4 (θ)	deg	720 (±360)		
Maximum speed	J1	deg/sec	420		
	J2		720		
	J3 (Z)	mm/sec	1100		
	J4 (θ)	deg/sec	3000		
Maximum composite speed *2		mm/sec	6800	7500	8300
Cycle time *3			0.41	0.46	0.51
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	29	29	32
Tolerable amount of inertia	Rating	kgm²	0.005		
	Maximum		0.06		
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: ϕ 6 x 2 Secondary: ϕ 4 x 8		
Machine cable			5m (connector on both ends)		
Connected controller *5			CR750, CR751		

*1: The range for vertical movement listed in the environmental resistance specifications (C: Clean specifications) for the RH-3FH is narrower than for the standard model. Keep this in mind when working with the RH-3FH. The environment-resistant specifications are 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.
*6: 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 ø8-mm coupler for suctioning is provided at the back of the base.

Horizontal 6kg type

RH-6FH35
RH-6FH45
RH-6FH55

External Dimensions/Operating Range Diagram



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.)

Specifications

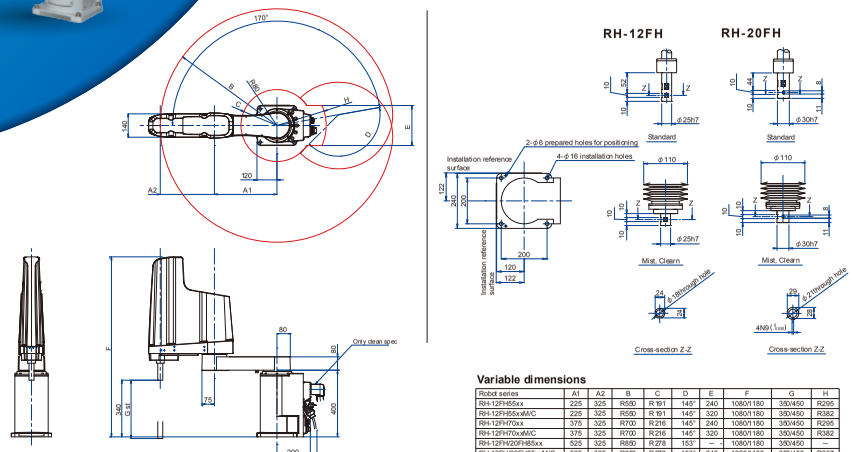
Type		Unit	RH-6FH35XX/M/C	RH-6FH45XX/M/C	RH-6FH55XX/M/C
Machine class			Standard/ oil mist/ Clean		
Protection degree *1			IP20 *6/ IP65 *7/ ISO3 *8		
Installation			Floor type		
Structure			Horizontal, multiple-joint type		
Degrees of freedom			4		
Drive system			AC servo motor		
Position detection 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	kgm²	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: ϕ 6 x 2 Secondary: ϕ 4 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.

Horizontal 12/20kg type

RH-12FH55 RH-20FH85 RH-12FH70 RH-20FH100 RH-12FH85

External Dimensions/Operating Range Diagram



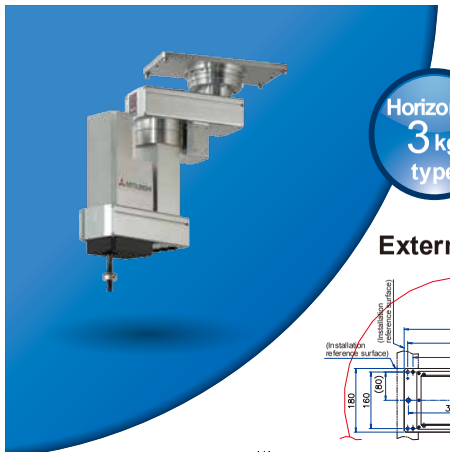
Variable dimensions

Robot series	A1	A2	B	C	D	E	F	G	H
RH-12FH55xx	225	325	R550	R191	145°	240	1080/1180	380/450	R295
RH-12FH55xxM/C	225	325	R550	R191	145°	320	1080/1180	380/450	R382
RH-12FH70xx	375	325	R700	R216	145°	240	1080/1180	380/450	R295
RH-12FH70xxM/C	375	325	R700	R216	145°	320	1080/1180	380/450	R382
RH-12FH20FH85xx	525	325	R880	R278	153°	–	1080/1180	380/450	–
RH-12FH20FH85xxM/C	525	325	R880	R278	153°	240	1080/1180	380/450	R367
RH-20FH100xx	525	475	R1000	R238	153°	240	1080/1180	380/450	R295
RH-20FH100xxM/C	525	475	R1000	R238	153°	320	1080/1180	380/450	R382

Specifications

Type		Unit	RH-12FH55XX/M/C	RH-12FH70XX/M/C	RH-12FH85XX/M/C	RH-20FH85XX/M/C	RH-20FH100XX/M/C
Machine class			Standard/ oil mist/ Clean			Standard/ oil mist/ Clean	
Protection degree *1			IP20/ IP65 *6/ ISO3 *7			IP20/ IP65 *6/ ISO3 *7	
Installation			Floor type			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 12 (rating 3)			Maximum 20 (rating 5)	
Arm length	NO1 arm	mm	225	375	525	525	525
	NO2 arm		325			325	475
Maximum reach radius		mm	550	700	850	850	1000
Operating range	J1	deg	340 (±170)			340 (±170)	
	J2		290 (±145)		306 (±153)	306 (±153)	
	J3 (Z)	mm	xx = 35 : 350/ xx = 45 : 450			xx = 35 : 350/ xx = 45 : 450	
	J4 (θ)	deg	720 (±360)			720 (±360)	
Maximum speed	J1	deg/sec	420		280	280	
	J2		450			450	
	J3 (Z)	mm/sec	2800			2400	
	J4 (θ)	deg/sec	2400			1700	
Maximum composite speed *2		mm/sec	11435	12535	11350	11372	13283
Cycle time *3			0.30	0.30	0.30	0.30	0.36
Position repeatability	Y-X composite	mm	±0.012	±0.015	±0.015	±0.015	±0.02
	J3 (Z)		±0.01			±0.01	
	J4 (θ)	deg	±0.005			±0.005	
Ambient temperature			0 to 40				
Mass		kg	65	67	69	75	77
Tolerable amount of inertia	Rating	kgm²	0.025			0.065	
	Maximum		0.3			1.05	
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: ϕ6 x 8				
Machine cable			5m (connector on both ends)				
Connected controller *5			CR750, CR751				

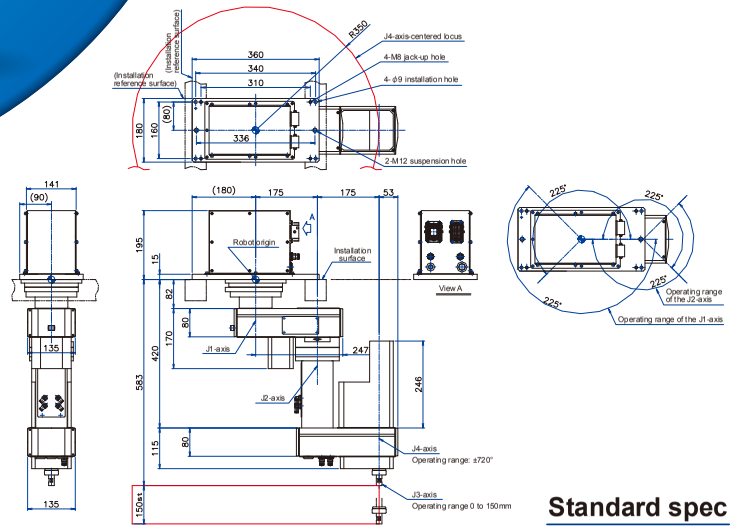
*1: The environment-resistant specifications (C: Clean specification, M: Mist specification) are factory-set custom specifications.
*2: The value assumes composition of J1, J2, and J4.
*3: Value for a maximum load capacity of 2 kg. The cycle time may increase if specific requirements apply such as high 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: 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.
*7: 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.



Horizontal 3kg type

RH-3FHR

External Dimensions/Operating Range Diagram

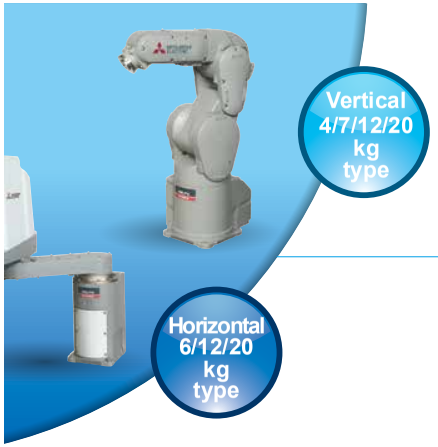


Specifications

Type		Unit	RH-3FHR3515	RH-3FHR3512C *1	RH-3FHR3512W *1
Machine class			Standard	Standard	Standard
Protection degree			IP20	ISOclass5 *5	IP65 *6
Installation			Ceiling type		
Structure			Horizontal, multiple-joint type		
Degrees of freedom			4		
Drive system			AC servo motor (J1, J2 and J4: with no brake, J3: with brake)		
Position detection method			Absolute encoder		
Maximum load capacity (rating)		kg	3 (1)		
Arm length	No. 1 arm	mm	175		
	No. 2 arm		175		
Maximum reach radius (No. 1 + No. 2)		mm	350		
Operating range	J1	deg	450 (±225)		
	J2		450 (±225)		
	J3 (Z)	mm	150 (0 to 150)		
	J4 (θ)	deg	1440 (±720)		
Maximum speed	J1	deg/sec	672		
	J2		708		
	J3 (Z)	mm/s	1500		
	J4 (θ)	deg/sec	3146		
Maximum composite speed *2		mm/sec	6267		
Cycle time *3		sec	0.32		
Position repeatability	X-Y composite	mm	±0.01		
	J3 (Z)		±0.01		
	J4 (θ)	deg	±0.01		
Ambient temperature		°C	0 to 40		
Mass		kg	Approx. 24		
Tool wiring			Hand: 8 input points / 0 output points, 8 spare lines (8 output points by options)		
Tool pneumatic pipes			Primary: ϕ6 x 2 (Secondary: ϕ4 x 8)		
Machine cable			5m (connector on both ends)		
Connected controller			CR751 / CR750 *4		

*1: The environmental resistance specifications of RH-3FHR (C: Clean specification, W: Waterproof specification) are factory-set custom specifications.
*2: The value assumes composition of J1, J2, and J4.
*3: Based on a load capacity of 1 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: Select either controller according to your application.
CR750-D/CR-751-Q: Standalone type, CR750-Q/CR751-Q: iQ Platform compatible type.
*5: 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.
*6: Direct jet to the bellows is excluded.

Standard spec



The environment-resistant specifications

(For medicinal products and foods)

The resistance to corrosion due to chemical cleaning is enhanced, and this improves detergency and cleanliness.
These types of robots are applicable to the production environments including conveying or processing medicinal products and foods.

- **Enhanced resistance to acid and alkaline cleaning liquids**
  - Since special coating (compliant to FDA *1) and special sealing are applied to these types of robots, they can be used in an environment sterilized with hydrogen peroxide gas and withstand wipe cleaning with hydrogen peroxide water.
  - Stainless materials are used to enhance the corrosion resistance.
- **NSF H1 *2 -certified grease for food machinery**
  The grease for food machinery is used to improve cleanliness.
- **Surface shape that prevents foreign matter from getting into and remaining inside**
  Specially-shaped bolts and the smooth surface facilitate daily cleaning.

*1: Food and Drug Administration
*2: Sanitation guideline of NSF (National Sanitation Foundation) in the United States

Models

Vertical, multiple-joint type	Type	Chemical-resistant	H1 grease for food machinery
RV-4F series	RV-4FM RV-4FLM	-SE01	-SE02
RV-7F series	RV-7FM RV-7FLM RV-7FLLM		
RV-13F series	RV-13FM RV-13FLM		
RV-20F series	RV-20FM		

Horizontal, multiple-joint type	Type	Chemical-resistant	H1 grease for food machinery
RH-6FH series	RH-6FH35XXM RH-6FH45XXM RH-6FH55XXM	-SE01	-SE02
RH-12FH series	RH-12FH55XXM RH-12FH70XXM RH-12FH85XXM		
RH-20FH series	RH-20FH85XXM RH-20FH100XXM		

For the specifications of each model, refer to the specifications of each standard model. Note that these models have the following differences from the standard models.
The protection degree of all the models is IP65.
These models are 2-3 kg heavier than the standard models. For details, refer to each specification sheet.

Specifications

A NSF H1-certified grease is applied (Compliant to FDA)

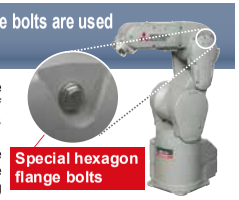
H1 grease for food machinery is applied to joint oil seals.
(Oil seals exposed to the external air)

B Stainless materials are used for robot tips

The tool flange of a robot tip is changed from a plated one to the one using stainless materials, and this enhances the corrosion resistance.

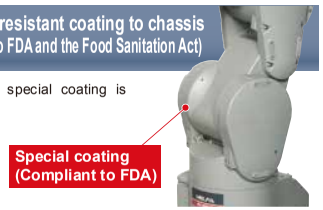
C Special hexagon flange bolts are used (Cover-fixing bolts)

Liquid does not remain in the special bolts that are made of stainless-steel, and this improves detergency.
Grooving is performed to the bolts to enable easy cleaning the area around the cover-fixing bolts.



D Chemical-resistant coating to chassis (Compliant to FDA and the Food Sanitation Act)

Chemical-resistant special coating is applied to the arm.



E Seals exposed to the external air are resistant to chemicals

Highly chemical-resistant rubbers are used for oil seals and packing, the seals exposed to the external environment, and this improves the detergency at food and pharmaceutical factories.

F The chemical resistance of bellows is improved (RH-F series only)

Fluorine resin is used for bellows, and this enhances the chemical resistance and improves the detergency at food and pharmaceutical factories.

Correspondence table for environmental resistance specifications (for medicinal products and foods)

Specifications	Item	Chemical-resistant -SE01 *3	H1 grease for food machinery -SE02
A	H1 grease is applied to the seals exposed to the external air	○	○
B	Stainless materials are used for robot tips	○	○
C	Special hexagon flange bolts are used	○	-
D	Chemical-resistant coating to chassis	○	-
E	Chemical-resistant seals	○	-
F	The chemical resistance of bellows is improved	○	-

*3: This model can be used in an environment sterilized with hydrogen peroxide gas (Concentration: 120ppm) and withstand wipe cleaning with hydrogen peroxide water (Concentration: 6%).

RV - 13 F L M - 1D 1 - SE01

- Robot structure (Horizontal, multiple-joint type)
- Maximum load capacity *4
- Series *4
- Arm length *4
- Special device No. SE01: Chemical-resistant SE02: H1 grease for food machinery
- 1: CE/KC specification
- Controller type *4
- Environment specification M: Oilmist specifications

RH - 20 FH 100 45 M - 1D 1 - SE01

- Robot structure (Horizontal, multiple-joint type)
- Maximum load capacity *4
- Series *4
- Arm length *4
- Vertical stroke *4
- Special device No. SE01: Chemical-resistant SE02: H1 grease for food machinery
- 1: CE/KC specification
- Controller type *4
- Environment specification M: Oilmist specifications

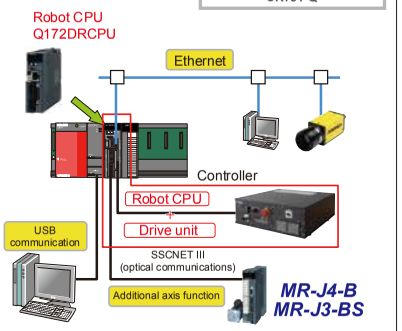
*4: For the notations, refer to the standard models. (Refer page 4)

Controller

FQ series

Controller configuration

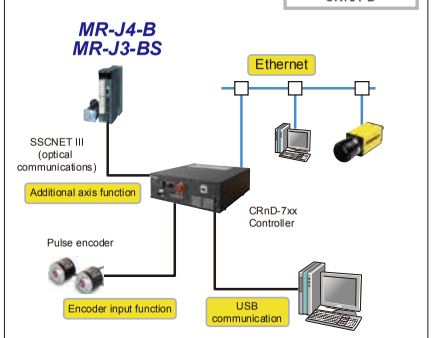
MELFA Controller Q Type (iQ Platform compatible)
CR750-Q
CR751-Q



FD series

Controller configuration

MELFA Controller D Type (Standalone)
CR750-D
CR751-D

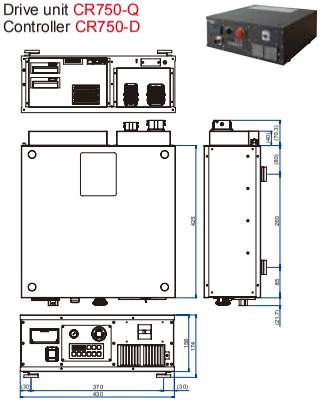


Specifications

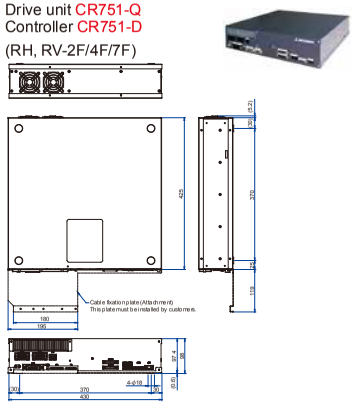
Type		Unit	CR750-Q / CR750-D	CR751-Q / CR751-D
Robot CPU			FQ Q172DRCPU	
Path control method			PTP control and CP control	
Number of axes controlled			Maximum 6 axes	
Robot language			MELFA-BASIC IV/V	
Position teaching method			Teaching method, MDI method	
Memory capacity	Number of teaching points	points	FQ 13,000 / FD 39,000	
	Number of steps	step	FQ 26,000 / FD 78,000	
	Number of programs	Unit	FQ 256 / FD 512	
External input/output *5	General-purpose I/O	points	FQ 8192 input points/8192 output points with the multiple CPU common device / FD 0 input/0 output (Up to 256/256 when options are used)	
	Dedicated I/O		FQ Assigned to multiple CPU common device. / FD Assigned to general-purpose I/O.	
	Hand open/close		8 input / 8 output	
	Emergency stop input		1 (redundant)	
	Door switch input		1 (redundant)	
	Enabling device input		1 (redundant)	
	Emergency stop output		1 (redundant)	
	Mode output		1 (redundant)	
	Robot error output		1 (redundant)	
	Synchronization of additional axes		1 (redundant)	
Interface	RS-422	ports	1 (Teaching pendant: dedicated T/B)	
	Ethernet		FQ 1 (dedicated teaching pendant port) 10BASE-T / FD 1 (dedicated teaching pendant port), 1 (for customer) 10BASE-T/100BASE-TX	
	USB		FQ 1 (USB port of programmable controller CPU unit can be used.) / FD 1 (Ver. 2.0 device functions only, mini B terminal)	
	Additional-axis interface	channels	1 (SSCNET III)	
	Extension slot *1	slots	FQ — / FD 2	
	Encoder input	channels	FQ Q173DPX (Sold separately) / FD 2	
Ambient temperature		°C	FQ 0 to 40 (drive unit)/0 to 55 (Robot CPU) / FD 0 to 40	
Relative humidity		%RH	45 to 85	
Power supply *5	Input voltage range *2	V	RV-2F/4F, RH-3FH/6FH: Single-phase AC 180 V to 253 V RV-7, 7FLL/13F/20F, RH-12FH/20FH: Three-phase AC 180 V to 253 V or Single-phase AC 207 V to 253 V	
	Power capacity *3	KVA	RV-2F, RH-3FH : 0.5 RV-4F, RH-6FH : 1.0 RH-12FH/20FH : 1.5 RV-7F : 2.0 RV-7FLL/13F/20F : 3.0	
External dimensions (including legs)		mm	430 (W) x 425 (D) x 174 (H)	430 (W) x 425 (D) x 98 (H) / 430 (W) x 425 (D) x 174 (H) *6
Weight		kg	Approx. 18	Approx. 12 / Approx. 18 *6
Structure [protective specification]			Self-contained floor type/open structure (Vertical and horizontal position can be placed) [IP20]	
Grounding *4		Ω	100 or less (class D grounding)	

*1: For installing option interface.
*2: The rate of power-supply voltage fluctuation is within 10%.
*3: The power capacity indicates the rating for normal operation. Take note that the power capacity does not include the currentbeing input when the power is turned on. The power capacity is only a rough guide and whether or not operation can be guaranteed depends on the input power-supply voltage.
*4: Grounding works are the customer's responsibility.
*5: For CR751, crimp or solder wiring for connection to user wiring connectors for emergency stop input/output, door switch input, etc. and power supply connectors. The optional terminal block replacement tool available separately can also be used to connect wiring.
*6: For RV-7FLL/13F/20F

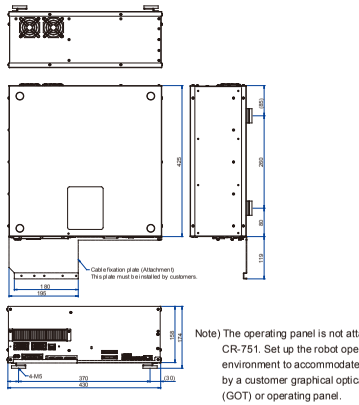
Drive unit CR750-Q
Controller CR750-D



Drive unit CR751-Q
Controller CR751-D
(RH, RV-2F/4F/7F)



(RV-7FLL/13F/20F)

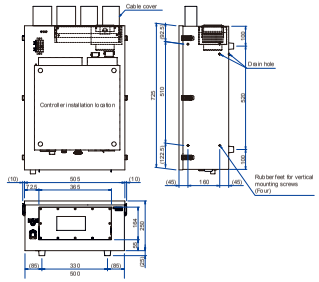


Note) The operating panel is not attached to the CR-751. Set up the robot operating environment to accommodate operation by a customer graphical optical terminal (GOT) or operating panel.
Automatic and other operation modes can be enabled from the teaching pendant.

Controller protection box (IP54)
CR750-MB/CR751-MB

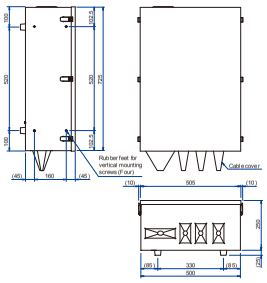
CR750-MB

The controller protection box is used to protect the controller from oil mist and other usage environments. (For CR750)
The front panel of the protection box has a mode switch and teaching box connector. It also contains a display window for viewing the controller operation panel.



CR751-MB

The controller protection box is used to protect the controller from oil mist and other usage environments. (For CR751)



Multiple CPU environment

Unit	Type
Base	High-speed standard base between multiple CPU • Q35DB: 5 slots • Q38DB: 8 slots • Q312DB: 12 slots
Power supply	• Q61P • Q62P • Q63P • Q64PN
Programmable controller CPU	Universal model • Q03UD (E/V) CPU • Q04UD (E/V) HCPU • Q06UD (E/V) HCPU • Q10UD (E) HCPU • Q13UD (E/V) HCPU • Q20UD (E) HCPU • Q26UD (E/V) HCPU • Q100UD (E) HCPU

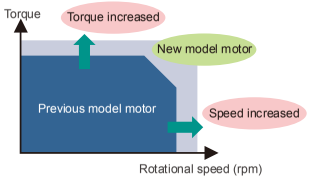
Functions

Increase through put

Improved control performance

Produced the fastest operating performance in its class using high-performance motors and unique driver control technology developed by Mitsubishi Electric.

- Enabled high torque output at high rotational speed, shortening acceleration/deceleration time.
- Shortened positioning time for improved device throughput.
- Continuous operability improved
- Improved speed for the vertical movements that are so essential to horizontal multi-joint robot operation. 2400 mm/s, [RH-6FH: Twice as fast as the conventional speed]



High-speed execution of programs

Enables execution up to 1.2 times faster than with the SQ/SD series.
Numerical operation and conditional branch processing speeds increased by up to twice as fast, leading to shortened takt times.

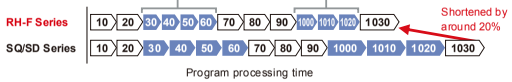
Sample program

```
10  JOVRD 100
20  MOV P100
30  M1=M_IN (10)
40  IF M1=1 THEN GOTO 1000
50  IF M1=2 THEN GOTO 2000
60  IF M1=3 THEN GOTO 3000
70  MOV P999
80  ERROR 9000
90  END
1000  PL=P1*POFF*PSHIFT
1010  PUP=PL
1020  PUP.Z=PUP.Z+MZ
1030  MOV PUP
      ·
      ·
      ·
```

Allows numerical operation and conditional branch processing times to be shortened dramatically. (The shortening rate may vary depending on operating conditions.)

Processing speed increased by 20%

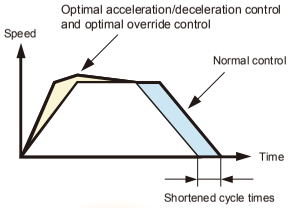
Note) Shortening effect depends on the contents of program instructions and processing.



Robot programs can be executed 1.2 times faster than before if compiled in advance and processed using an intermediate language.
Takt times can be shortened by up to 3 times as much for longer lines. (Compared to previous models)

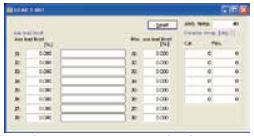
Optimal acceleration/deceleration control and optimal override control

- Optimal acceleration/deceleration times and speeds set automatically based on robot operating position, posture, and load conditions.
- Load conditions are set, enabling acceleration/deceleration times and speeds to be changed automatically according to whether a workpiece is present or not.
- This enables the maximum operating speed to be produced for each task
- Time needed to shorten cycle times reduced.

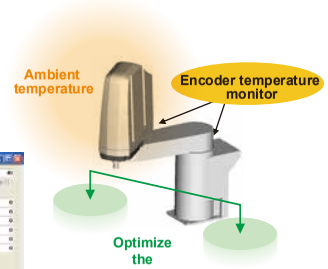


Improved continuous operatability

Overload detection levels optimized based on the ambient temperature settings for the robot (set in the parameters). This helps improve continuous operability using load levels calculated based on actual environmental conditions for the robot axes.
The encoder temperature is monitored such that the machine is shut down due to error if the temperature exceeds the tolerable limit.



Encoder temperature monitoring screen



Improved tooling performance

Compatuability with internal Ethernet cable tools

Internal installation of wiring and piping for connecting to vision sensors enabled.

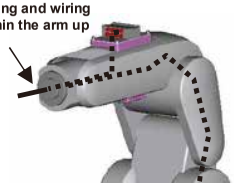
- Hand: 8 input points/8 output points
- Ethernet cable for the vision sensor

· Attachment of the vision sensor to the wrist facilitates wiring.

Internal routing of hand wiring and wiring channels

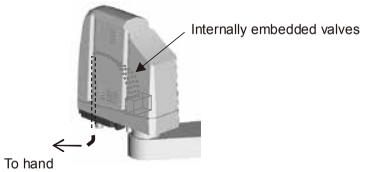
Internal routing of cables and air hoses is enabled through the internal channels that lead up to the end of the robot arm.
Such internal routing increases the areas of the work envelope that the robot can reach without twisting and entangling cables and hoses.
This prevents interference with cables around devices and reduces the risk of wiring disconnection.

Internal routing of wiring and wiring channels enabled within the arm up to the J6 axis tip.



Note: Specify a model with Internal wiring (a model ending in '-SHxx').
The supported Internal wiring types may vary by model.

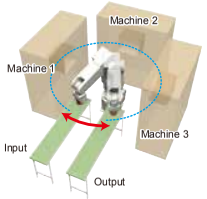
Note) The sections of wiring that can be routed internally may differ depending on the model.

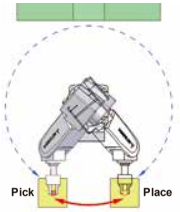


Space saving

Expanded pivotal operating range

Improved flexibility for robot layout design considerations.
Enabling more effective use of access space around the entire perimeter including to the rear.
Shortened movement distances, enabling takt times to be shortened.

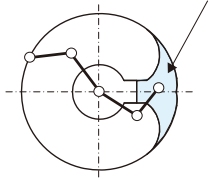




Movable stopper for the J1 axis

RV-2FQ/2FD pivot operation

Expanded J1 axis pivotal operating range to allow access to back of robot



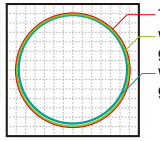
Rear access of RH-FQ/FD

Improved accuracy

Active gain control

- Optimal motor control tuning set automatically based on robot operating position, posture, and load conditions.
- Improves tracking accuracy for the target trajectory.

· Active gain control is a control method that allows the position gain to be changed in real time.
· This is effective for standard operations and tooling work requiring high accuracy.



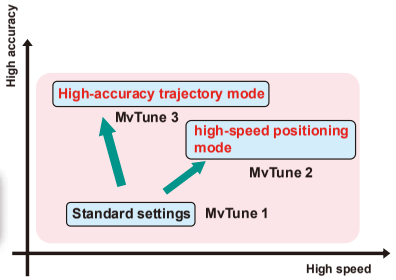
Monitor the robot posture and load conditions
Automatic tuning

Operating mode setting function

- Trajectory priority mode/speed priority operation can be set in programs to match customer system requirements.
- Optimal motor control tuning set automatically based on robot operating position, posture, and load conditions.
- Improves tracking accuracy for the target trajectory.

· This is effective for standard operations and tooling work requiring high accuracy.

●Improve trajectory accuracy
●Improve vibration-damping performance

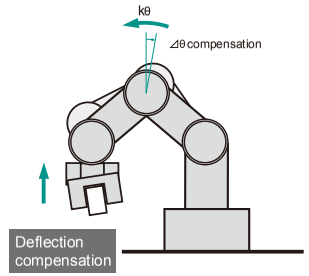


Deflection compensation function

- Compensates for deflection in the robot arm occurring due to gravity.
- Calculates the amount of compensation needed based on the operating position, posture, and load conditions of the robot and compensates for any deflection automatically.
- Compensates not only for static deflection due to gravitational pull but also for dynamic deflection due to the inertial force present during operation.

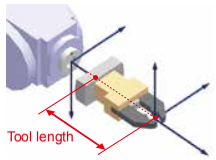
· Effective for work transporting workpieces to cassettes with low pitch and palletizing work.

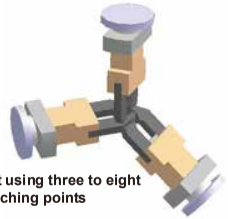
●Improve palletization accuracy
●Improve trajectory accuracy



Simplified tool length setting

Tool settings for the tool coordinate system can be set by attaching the tool and using three to eight of the same teaching points.
Enables settings to be made for the actual tool including errors introduced when the tool was made and other data without needing to calculate values from the tool diagram.





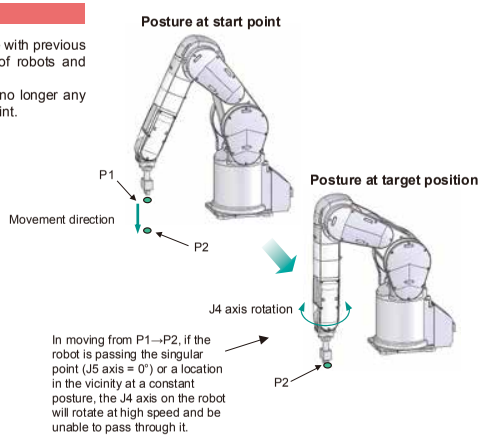
Set using three to eight teaching points

Adaptation to operation

Function for passing through the singular point

- The robot can be made to pass through the singular point, unlike with previous robot models. This allows for greater flexibility in the layout of robots and surrounding areas.
- Teaching operations can be performed more easily as there is no longer any need to cancel operations due to the presence of the singular point.

What a singular point is:
There is an unlimited number of angles at which the J4 and J6 axes can be set such that the angle of the J5 axis is 0° when linear interpolation operations are performed using position data from a joint coordinate system. This point is the singular point and is the point at which the robot cannot be operated at an assigned position and posture under normal conditions. The position at which this occurs is referred to as a singular point.

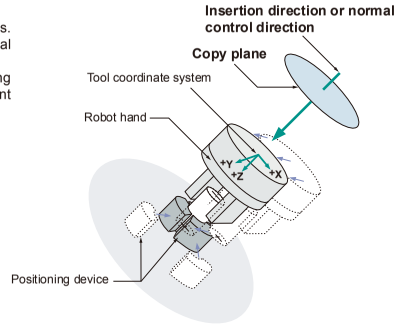


Orthogonal compliance control

- This function reduces the rigidity of the robot arm and tracks external forces. The robot itself is equipped with a compliance function, which makes special hands and sensors unnecessary.
- This allows the amount of force generated through interference during chucking and workpiece insertion to be reduced and external movement copying forces to be controlled.

· The compliance direction can be set arbitrarily using the robot coordinate system, the tool coordinate system, etc.
· This is useful in protecting against workpiece interference and cutting down on stoppage.

● Reduce tooling costs
● Shorten line stop times
● Shorten startup times



Improved user friendliness

Simple automatic operation from the teaching box

- Enables the robot to be controlled from the robot control screen using the same functions as on the operating panel of the robot controller.
- Monitoring screens can be set up individually to match the needs of user debugging conditions.

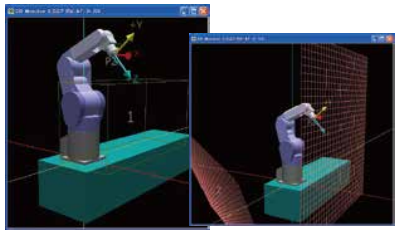
· Enabled for R32B/R33TB and R56TB/R57TB.

Robot control screen (R56TB)

Enables automatic operation of servo power on/off, startup, shutdown, reset, program selection, and other operations.

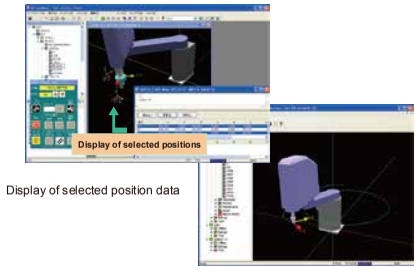
Enhanced RT ToolBox 2 visual functions

Enhanced RT ToolBox2 (PC software) graphic display function allowing setting parameters to be displayed visually. Visual confirmation using this function helps to proactively prevent setting errors.



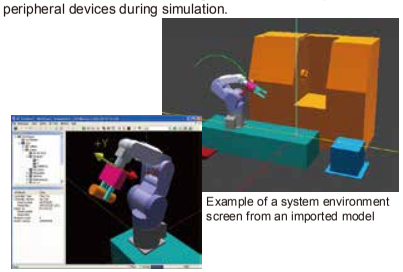
Display of user-defined regions/freedom-limited planes

Display of teaching positions and trajectories of end points helps to facilitate confirmation tasks during programming or simulations.



Display of trajectories

Hands can be created as combinations of basic diagrams on the Hand Editing screen and then attached to the robot. Standard 3D polygonal models (applicable 3D data file formats: STL, OBJ) can be imported into the program, allowing operators to confirm the relationship among the hands, workpieces, and peripheral devices during simulation.



Example of a system environment screen from an imported model

Attachment of a hand created in RT ToolBox2

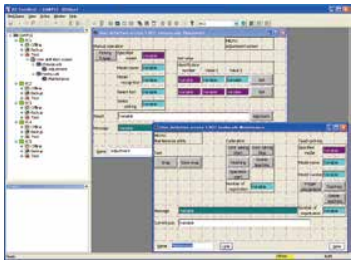
Up to 80000 records of data including current position, speed, axial loading, and sensor information can be obtained in every operating cycle of the robot and displayed in a graph. Execution rows and I/O signals are recorded and used for analyzing the robot status, and this improves the debug efficiency.
The obtained data can be saved as an image (Bitmap) or in the CSV format.

Oscillograph function (an example of the real-time monitoring of positions and current)

User-defined screen creation tools

Screens can be created anew, imported, or exported from "User-defined Screen Editing" in the project tree. Buttons, lamps, robot information, labels, and ruled lines can be arranged into layouts and assigned to robot variables.

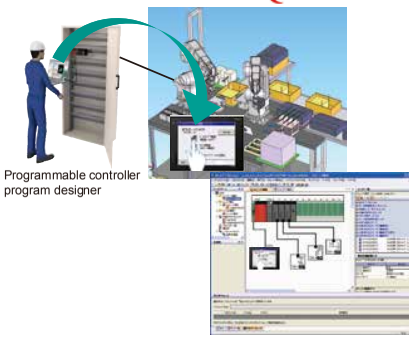
Data created here is exported and loaded into the R56/57TB.
Can be used as a user screen.



Linked to iQ Works

- Program management simplified
  Enables batch management of programs and data in blocks from the programmable controller to the servo, display device, and robot.
- Device model selection simplified
  All Mitsubishi device models are listed in the Navigator, enabling its use as a device model selection tool.
  Ver. 1.24A and later is equipped with robot CPU selection capability and comes packaged with RT ToolBox2 (mini ver.).

MELSOFT iQ Works



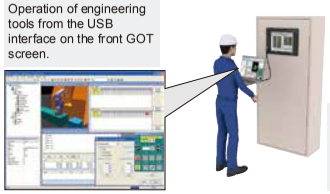
Programmable controller program designer

MELSOFT Navigator

GOT connection function

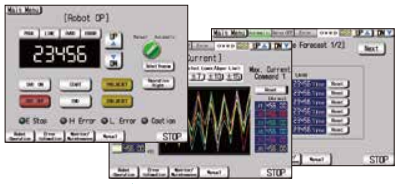
- The robot can be controlled directly from a Mitsubishi GOT 1000.
- Enables robot controller statuses to be uploaded and operations to be controlled directly from the GOT. Allows robot startup/shutdown, status/alarm monitoring, and other tasks to be completed from the GOT easily and quickly.
- Use of the transparent function enables editing of programs and parameters from the USB interface on the front GOT screen, improving user friendliness.

Operation of engineering tools from the USB interface on the front GOT screen.



The personal computer and the GOT are connected with a USB cable or RS232 cable

[For Q type /D type controllers]



· Ethernet
· Serial signals
etc.

Example GOT screen

[For Q type /D type controllers]

●Simplified control panel created using a GOT
●No need for ladder circuits with the GOT connection

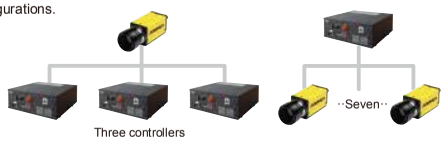
* You can download a sample image from the Mitsubishi FA site.
(Sample data corresponds to the GT16, 640×480 or more)

Connection to peripheral devices

Vision sensor

- Simple settings
  The robot and camera can be calibrated through a simple process using vision sensor setting tools.
- Simple connection
  Simple connection between the robot and camera using Ethernet.
- Simple control
  Simple control using vision control commands in the robot programs.
- Three robots connected to a single vision sensor/Seven vision sensors connected to a single robot
  → Enables costs to be reduced even for complicated system configurations.

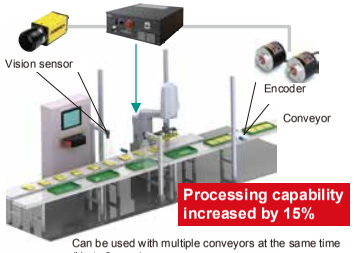
● Reduce cycle time
● Reduce system costs



Tracking

- Transport, alignment, and installation work, etc. can be performed while robots are tracked with the workpiece on the conveyor without stopping the conveyor. Processing capability improved by up to 15% compared to that for SQ/SD series robots.
- Different variations can be selected, including vision tracking in combination with a vision sensor, tracking in combination with an opto-electric sensor, etc.
- Programs can be created easily in robot language (MELFA BASIC IV, V).
- Standard interface function. (D type only.) (Separate encoder and vision sensor required.)

● No need for a positioning device
● Reduce cycle time
● Reduce system costs

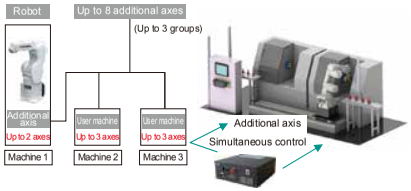


Can be used with multiple conveyors at the same time (Up to 8 max.).

Additional axis function

- The layout can be set up to include the robot traveling axis and turntable as well as user machines separate from the robot such as loaders and positioning devices.
- Up to 8 additional axes can be controlled by the controller.
- Additional axes and user machines can be operated from the robot program and teaching pendant without any additional motion control hardware. The same JOG operation as for the robot can be used. Robot language can be used for control operations.
- The robot controller has plug-and-play compatibility with the MELSERVO (MR-J4-B, MR-J3-BS) servos.
- Standard interface function (Separate servo amplifier and servo motor required.)

● No need for a dedicated control device



Compatible with MR-J4-B (J3-compatible mode)*

*Applicable software: Ver. R3g/S3g or later.

User interfaces

The various network options available allow connection to a variety of devices used throughout the world.

Standard equipment: Ethernet
USB
SSCNET III

Option: CC-Link
Profibus
DeviceNet
Network base card (EtherNet/IP, PROFINET IO)

Safety features

Security features

Security features were added to protect programs and parameters. Read/write protection prevents parameters from being overwritten and programs from being changed inadvertently. Sensitive data can be protected using password protection.

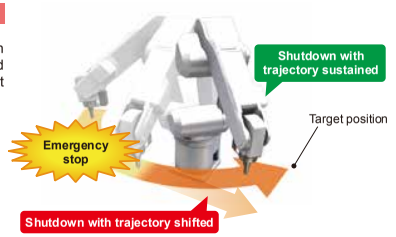
- Passwords can be set to protect created programs.
- The viewing and copying of data from the teaching pendant and RT ToolBox2 can be disabled.
- Writing operations for parameters can be disabled.

	Protected and restricted functions
Program-related	Reading and writing of programs Program deletion and copying Renaming and initialization of programs
Parameter-related	Writing of parameters
RT Tool Box2	Data backup and restore

Sustained tracking during emergency stop

The robot trajectory can be sustained even when the machine is shut down using an emergency stop. This allows interference with peripheral devices and other objects to be reduced or even fully prevented using the inertia of the robot arm to let it coast to a stop.

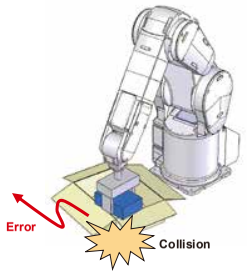
* Use of this function does not guarantee that the trajectory will be sustained. The trajectory may be shifted out of line depending on the timing at which the emergency stop is activated.



Collision detection function

- This function detects if the arm collides with an obstacle while teaching or operating, and helps reduce damage to the robot arm and tools.
- The collision detection function can be used to protect the workpiece from becoming damaged due to interference between the workpiece and affected objects.
- The detection level can be changed according to the protection targets.
- The collision detection function can be programmed to generate an alarm or perform a specific escape move or both.
  Ex.) An error is output due to the robot stopping suddenly, an error is output after escape movements are made, etc.

● Reduce tooling costs
● Shorten line stop times
● Reduce maintenance costs



Complies with safety standards

Complies with the latest ISO-10218-1 (2011) standards for Robots and robotic devices - Safety requirements.
Meets the requirements for PL d of ISO13849-1 Category 3.

Safety circuits (emergency stop circuits) can easily be installed for the customer's entire system, not just for the robot itself.
There are robots with special specifications that comply with various safety standards. Contact a Mitsubishi Electric dealer or sales agent for further details if interested.

Applicable standards

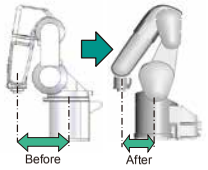
- **CE: European Conformity**
  (European safety standards)
  · Compliant with the EMC Directive, 2004/108/EC
  · Compliant with the Machinery Directive, 2006/42/EC
- **KCC: Korean Communications Commission**
  (Korean safety certification)
  · Complies with the revised Korea Radio Act (Article 58 Section 2)

Expanded J4 axis operating range

● Expanding the J4 axis operating range enables the posture to be changed continuously during assembly and transport operations. It also eliminates the need for the robot to move in the opposite direction partway through an operation.

Compact installation with operation performed near the robot base

● Use of a flap-style arm contributes to a slimming of customer equipment, enabling operations to be completed in even closer proximity to the robot.

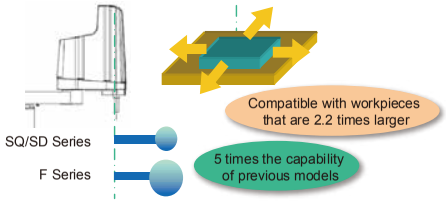


Changes in operating posture can be made even more quickly!!

● Changes in operating posture, which occur frequently during assembly, can be completed at rapid speed, increasing the speed of the axis close at hand as well as that of the base axis. Enables changes to be made to the operating posture at high speed.

Enhanced wrist axis

● Tolerable J4 axis inertia dramatically increased. Applies easily to multiple hands, offset hands, etc.
[5 times that of previous models (RH-20FH)]



Enhanced wrist (RH-20FH)

Features of IQ Platform Controllers

iQ Platform

Improved responsivity through high-speed communications

Increases the speed of data communications between CPUs and dramatically reduces I/O processing times using a high-speed standard base between multiple CPUs.

High-speed communications

Measurement example: Transfer of 16-word data (With data matching check)
CC-Link: 262ms
Between multiple CPUs: 63 ms (Approx. 4×)

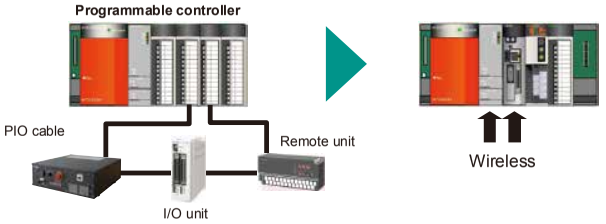
Large amounts of data

The number of device points between the programmable controller and robot was increased to 8192 input points and 8192 output points. This allows the system to handle larger programs, more complicated control, and other objects that require a lot of I/O points.

Number of I/O points: 8192/8192
Remote I/O: 256/256
CC-Link (4 stations, 1×): 126/126
CC-Link (4 stations, 8×): 894/894

Reduced wiring and number of units used

System costs can be reduced with the use of wireless systems and deletion of I/O units and network units.



Direct communication between CPU units

Enables shared memory to be read from and written to between multiple robot CPUs.
Speeds for data communications between robots increase, enabling more detailed control, such as with an interference prevention function or coordinated control, and cutting down on wasted time.

No need for special programmable controller programs as shared memory is used.

Direct communication between CPUs

Direct control between I/O units

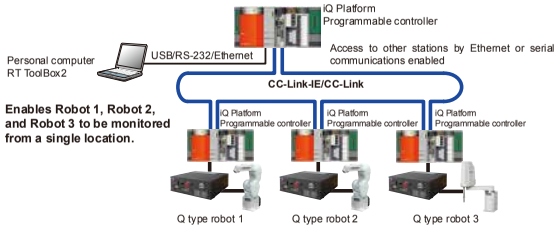
Enables data to be read and written directly between the CPU unit and I/O unit.
Responsivity improved and interlock times and cycle times shortened using high-speed I/O communications to peripheral devices.

No need for programmable controller programs for signal input/output
Improved responsivity without any delay due to scanning time

Direct control between CPUs and I/O units

Batch management of multiple robots

Enables access to robots in the programmable controller network from a PC connected to the main CPU. Leads to a shortening of rise times and improved maintainability for robots on the production line.



Shared memory expansion

Enhanced efficiency of monitoring and maintenance operations onsite using a single GOT (display device) as the Human Machine Interface (HMI).

Enables the robot to be controlled from the GOT even without a teaching box.
Current robot position data, error information, and other items can be displayed easily on the GOT.

Internal robot information

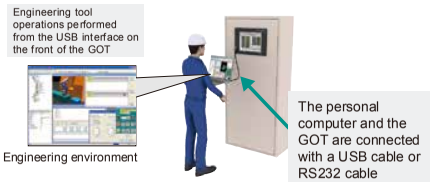
- Error, variable, and program information
- Robot status (Current speed, current position, etc.)
- Maintenance information (Remaining battery capacity, grease life, etc.)
- Servo data (Load factor, current values, etc.)

Operation panel screen | Jog/hand operation screen | Current position monitor screen

Current value and load factor monitor screen | Maintenance forecast screen | Manual/video display menu

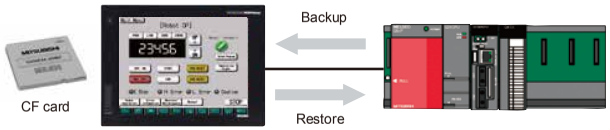
GOT connection (transparent function) (For GOT1000 Series)

Programs and parameters can be edited from the USB interface on the front of the GOT using a transparent function for improved operability.



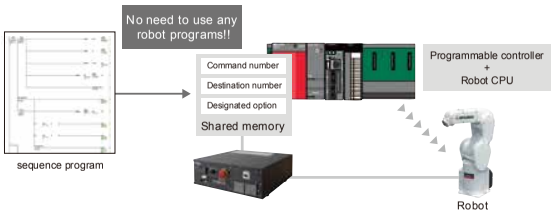
GOT backup/restore functions (Supported on GT14, GT15 and GT16)

Robot data on the GOT can be backed up to and restored from a CF card or USB memory stick. With no need for a PC.
This helps prevent data from being lost due to the empty battery / battery or robot malfunction.
Data can be saved after periodic maintenance tasks are performed or when unexpected errors occur. Dramatically improves serviceability.



Direct execution function for programmable controllers

Robots can be controlled easily using programmable controller language. System operation can be controlled using a single programmable controller. This enables the operation of the programmable controller to handle making changes to system specifications and troubleshooting directly.



[Details of supported control operations]

Details	
Operation	· Joint-interpolated motion · Linear-interpolated motion
Motion control	· Designated override · Designated acceleration/ deceleration settings · Designated speed · Tool settings · Designated auxiliary motion · Opening/closing of hand

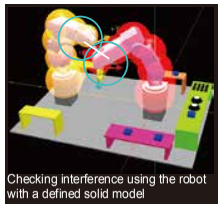
Collision Avoidance

iQ Platform

For automatic prevention of collisions between robots

The software constantly monitors robots motion, predicts collisions before they occur, and immediately stops the robots. This avoids damage to the robot during both the JOG operations and automatic mode operations. Also, this enables the number of interlocks needed to prevent collisions between robots to be reduced. (Alarm shutdown)

[Q type controllers only]



Checking interference using the robot with a defined solid model

Decreases downtime during startup operation

Reduces the number of recovery man-hours required after collisions due to teaching operation errors or failure to set interlocks

Coordinated control

iQ Platform

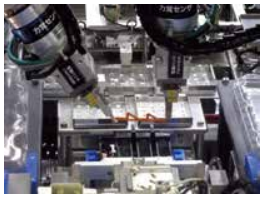
Coordinated control between multiple robots

Enables coordinated control between multiple robots through CPU connection between the robots. Easy to operate and use under normal operation through individual robot operation.

Coordinated transport

Enables transport of lengthy or heavy objects using multiple small-sized robots instead of larger ones.

[Q type controllers only]

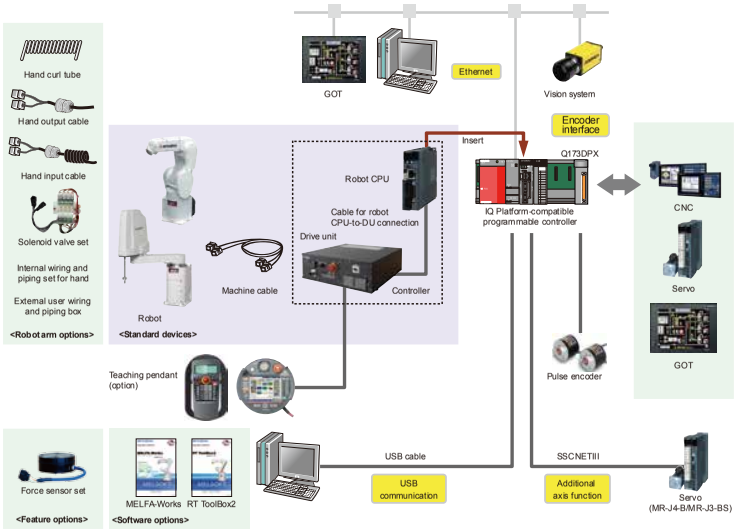


Enables installation work to be completed while gripper positions between robots are maintained.

System Configuration

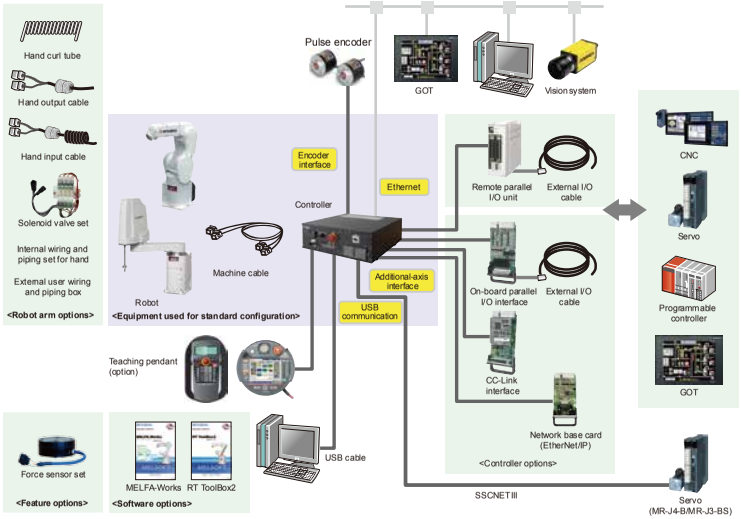
FQseries

System Configuration iQ Platform



FDseries

System Configuration



Configurations Options

Configurations options For details, refer to the specifications sheets.

Classification	Name	Type	RV 2F	RV 4F 4FL	RV 7F 7FL	RV 7FLL	RV 13F 13FL 20F	RH 3FH	RH 6FH	RH 12FH 20FH	RH 3FHR	Functional specifications
Robot arm	Solenoid valve set	1E-VD0□ (Sink) 1E-VD0□E (Source)	○	–	–	–	–	–	–	–	–	1 to 2 valves, with solenoid valve output cable. □ indicates the number of solenoid valves (1 or 2 valves) Output: ϕ4
		1F-VD0□-02 (Sink) 1F-VD0□E-02 (Source)	–	○	○	○	–	–	–	–	–	1 to 4 valves, with solenoid valve output cable. □ indicates the number of solenoid valves (1, 2, 3, or 4 valves) Output: ϕ4
		1F-VD0□-03 (Sink) 1F-VD0□E-03 (Source)	–	–	–	–	○	–	–	–	–	1 to 4 valves, with solenoid valve output cable. □ indicates the number of solenoid valves (1, 2, 3, or 4 valves) Output: ϕ6
		1F-VD0□-01 (Sink) 1F-VD0□E-01 (Source)	–	–	–	–	–	○	○	–	–	1 to 4 valves, with solenoid valve output cable. □ indicates the number of solenoid valves (1, 2, 3, or 4 valves) Output: ϕ4
		1S-VD0□-01 (Sink) 1S-VD0□E-01 (Source)	–	–	–	–	–	–	–	○	–	1 to 4 valves, with solenoid valve output cable. □ indicates the number of solenoid valves (1, 2, 3, or 4 valves) Output: ϕ6
		1S-VD04-05 (Sink) 1S-VD04E-05 (Source)	–	–	–	–	–	–	–	–	○	4 valves, with solenoid valve output cable. Output: ϕ4 (Standard)
		1S-VD04W-05 (Sink) 1S-VD04WE-05 (Source)	–	–	–	–	–	–	–	–	○	4 valves, with solenoid valve output cable. Output: ϕ4 (water proof/clean)
	Hand output cable	1E-GR35S	○	–	–	–	–	–	–	–	–	Straight cable for 2-solenoid valve systems, total length of 300 mm, with a robot connector on one side and unterminated on the other side
		1F-GR35S-02	–	○	○	○	○	–	–	–	–	Straight cable for 4-solenoid valve systems, total length of 300 mm, with a robot connector on one side and unterminated on the other side
		1F-GR60S-01	–	–	–	–	–	○	○	○	–	Straight cable for 4-solenoid valve systems, total length of 1050 mm, with a robot connector on one side and unterminated on the other side, equipped with a splash-proof grommet
		1S-GR35S-02	–	–	–	–	–	–	–	–	○	Straight cable for 4-solenoid valve systems, total length of 450 mm, with a robot connector on one side and unterminated on the other side
	Hand input cable	1S-HC30C-11	○	–	–	–	–	–	–	–	–	4-point type, with a robot connector on one side and unterminated on the other side
		1F-HC35S-02	–	○	○	○	○	–	–	–	–	8-point type, total length of 1000 mm , with a robot connector on one side and unterminated on the other side
		1F-HC35C-01	–	–	–	–	–	○	○	–	–	8-point type, total length of 1650 mm (includes a 350-mm-long curled section), with a robot connector on one side and unterminated on the other side, equipped with a splash-proof grommet
		1F-HC35C-02	–	–	–	–	–	–	–	○	–	8-point type, total length of 1800 mm (includes a 350-mm-long curled section), with a robot connector on one side and unterminated on the other side, equipped with a splash-proof grommet
		1S-HC00S-01	–	–	–	–	–	–	–	–	○	4-point type, total length of 1210 mm , with a robot connector on one side and unterminated on the other side
	Hand (curl) tube	1E-ST040□C	○	○	○	○	–	–	–	–	–	ϕ4: 1 to 4 valves (L = 300 mm) □ indicates the number of solenoid valves (2, 4, 6, 8). 2 or 4 valves for RV-2F.
		1E-ST0408C-300	–	–	–	–	–	○	○	–	–	Compatibility with ϕ4-4-solenoid valve systems (L = 300 mm)
		1N-ST060□C-01	–	–	–	–	○	–	–	○	–	ϕ6: 1 to 4 valves (L = 600 mm) □ indicates the number of solenoid valves (2, 4, 6, 8).
	Hand tube	1S-ST0304S	–	–	–	–	–	–	–	–	○	ϕ3: 2 valves (Maximum usable length: 400mm)
	External wiring set 1 for the forearm	1F-HB01S-01	–	○	○	○	○	–	–	–	–	Used for the forearm. External wiring box used for connecting the hand input cable, the Ethernet cable, and the electrical hand and force sensor cable.
	External wiring set 2 for the forearm	1F-HB02S-01	–	○	○	○	○	–	–	–	–	Used for the forearm. External wiring box used for connecting the force sensor, the electrical hand, and the Ethernet cable.
	External wiring set 1 for the base	1F-HA01S-01	–	○	○	○	○	–	–	–	–	Used for the base. External wiring box used for connecting the communications output for the electrical hand, the electrical hand and force sensor cable, and the Ethernet cable. There are hand input connection available.
	External wiring set 2 for the base	1F-HA02S-01	–	○	○	○	○	–	–	–	–	Used for the base. External wiring box used for connecting the communications output for the electrical hand, the electrical hand, the force sensor cable, and the Ethernet cable. No hand input connection available.
	Internal wiring and piping set for hand	1F-HS604S-01	–	–	–	–	–	–	–	○	–	Wiring and piping set for internal mounting in the tip axis (Compatible with 8 input points for hand systems + ϕ6-2 solenoid valve systems) For 350mm Z-axis stroke
		1F-HS604S-02	–	–	–	–	–	–	–	○	–	Wiring and piping set for internal mounting in the tip axis (Compatible with 8 input points for hand systems + ϕ6-2 solenoid valve systems) For 450mm Z-axis stroke
		1F-HS408S-01	–	–	–	–	–	–	○	–	–	Wiring and piping set for internal mounting in the tip axis (Compatible with 8 input points for hand systems + ϕ4-4 solenoid valve systems) For 200mm Z-axis stroke
		1F-HS408S-02	–	–	–	–	–	–	○	–	–	Wiring and piping set for internal mounting in the tip axis (Compatible with 8 input points for hand systems + ϕ4-4 solenoid valve systems) For 340mm Z-axis stroke
		1F-HS304S-01	–	–	–	–	–	○	–	–	–	Wiring and piping set for internal mounting in the tip axis (Compatible with 4 input points for hand systems + ϕ3-2solenoid valve systems)
	External user wiring and piping box	1F-UT-BOX	–	–	–	–	–	○	○	–	–	Box for external wiring of user wiring (hand I/O, hand tube)
		1F-UT-BOX-01	–	–	–	–	–	–	–	○	–	Box for external wiring of user wiring (hand I/O, hand tube)
	Machine cable (replacement for shorter 2m type) (*1)	1S-02UCBL-01	–	○	○	○	○	–	○	○	○	2m long cables for securement purposes (2-wire set with power supply and signal)
		1F-02UCBL-01	–	–	–	–	–	○	–	–	–	2m long cables for securement purposes (2-wire set with power supply and signal)
	Machine cable, for extension/fixed CR-750	1S-□□CBL-11	○	–	–	–	–	–	–	–	–	Exchange type, extended length 5m, 10m, 15m (2wires set with power and signal wires) □□ indicates the length of cables (5, 10, 15m)
		1S-□□CBL-01	–	○	○	○	○	–	○	○	○	Extention type, extended length 5m , 10m, 15m (2wires set with power and signal wires) □□ indicates the length of cables (5, 10, 15m)
		1S-□□CBL-03	–	–	–	–	–	○	–	–	–	Extention type, extended length 5m , 10m, 15m (2wires set with power and signal wires) □□ indicates the length of cables (5, 10, 15m)
	Machine cable, for extension/fixed CR-751	1F-□□UCBL-11	○	–	–	–	–	–	–	–	–	Exchange type, extended length 5m, 10m, 15m (2wires set with power and signal wires) □□ indicates the length of cables (5, 10, 15m)
		1F-□□UCBL-02	–	○	○	○	○	○	○	○	○	Exchange type, extended length 10m, 15m, 20m (2wires set with power and signal wires) □□ indicates the length of cables (10, 15, 20m)
	Machine cable, for extension/flexible CR-750	1S-□□LCBL-11	○	–	–	–	–	–	–	–	–	Exchange type, extended length 5m, 10m, 15m (2wires set with power and signal wires) □□ indicates the length of cables (5, 10, 15m)
		1S-□□LCBL-01	–	○	○	○	○	–	○	○	○	Extention type, extended length 5m, 10m, 15m (2wires set with power and signal wires) □□ indicates the length of cables (5, 10, 15m)
		1S-□□LCBL-03	–	–	–	–	–	○	–	–	–	Extention type, extended length 5m , 10m, 15m (2wires set with power and signal wires) □□ indicates the length of cables (5, 10, 15m)
	Machine cable, for extension/flexible CR-751	1F-□□LUCBL-11	○	–	–	–	–	–	–	–	–	Exchange type, extended length 5m, 10m, 15m (2wires set with power and signal wires) □□ indicates the length of cables (5, 10, 15m)
		1F-□□LUCBL-02	–	○	○	○	○	○	○	○	○	Exchange type, extended length 10m, 15m, 20m (2wires set with power and signal wires) □□ indicates the length of cables (10, 15, 20m)
	Stopper for changing the J1-axis operating range	1S-DH-11J1	○	–	–	–	–	–	–	–	–	Stopper for making changes, installed by customer
		1F-DH-05J1	–	–	–	○	○	–	–	–	–	Stopper for making changes, installed by customer (Compatible with the RV-7FLL.)
		1F-DH-04	–	–	○	–	–	–	–	–	–	Stopper for making changes, installed by customer
		1F-DH-03	–	○	–	–	–	–	–	–	–	Stopper for making changes, installed by customer
		1F-DH-02	–	–	–	–	–	–	–	○	–	Stopper for making changes, installed by customer
		1S-DH-01	–	–	–	–	–	○	○	–	–	Stopper for making changes, installed by customer
		1S-DH-05J1	–	–	–	–	–	–	–	–	○	Stopper for making changes, installed by customer
	Stopper for changing the J2-axis operating range	1S-DH-11J2	○	–	–	–	–	–	–	–	–	Stopper for making changes, installed by customer
		1S-DH-05J2	–	–	–	–	–	–	–	–	○	Stopper for making changes, installed by customer
	Stopper for changing the J3-axis operating range	1S-DH-11J3	○	–	–	–	–	–	–	–	–	Stopper for making changes, installed by customer

Note 1) This is a special specification for shipping. Inquire for delivery and prices.

Classification	Name	Type	CR750		CR751		Functional specifications
			Q type	D type	Q type	D type	
Controller	Standard teaching pendant (7m, 15m)	R32TB(-**)	○	○	–	–	7 m: Standard, 15 m: Custom ("-15" is included in the model name) For controller CR-750-*
	High-function teaching pendant (7 m, 15 m)	R56TB(-**)	○	○	–	–	7 m: Standard, 15 m: Custom ("-15" is included in the model name) For controller CR-750-*
	Standard teaching pendant (7m, 15m)	R33TB(-**)	–	–	○	○	7 m: Standard, 15 m: Custom ("-15" is included in the model name) For controller CR-751-*
	High-function teaching pendant (7 m, 15 m)	R57TB(-**)	–	–	○	○	7 m: Standard, 15 m: Custom ("-15" is included in the model name) For controller CR-751-*
	Conversion cable for the teaching box	2F32CON03M	–	–	○	○	Conversion cable used to connect the R32TB to the CR-751 controller. Cable length: 3 m.
	On-board Parallel I/O interface (Sink type) (Source type)	2A-RZ361 2A-RZ371	–	○	–	○	32 output points/ 32 input points
	Remote Parallel I/O cable (5m, 15m)	2A-CBL**	–	○	–	○	CBL05: 5 m, CBL15: 15 m, not terminated at one end. For 2A-RZ361/371.
	On-board Parallel I/O interface (Installed internally) (Sink type) (Source type)	2D-TZ368 2D-TZ378	–	○	–	○	32 output points/ 32 input points
	Remote Parallel I/O cable (5m, 15m)	2D-CBL**	–	○	–	○	CBL05: 5 m, CBL15: 15 m, not terminated at one end. For 2D-TZ368/378.
	CC-Link interface	2D-TZ576	–	○	–	○	CC-Link Intelligent device station, Ver. 2.0, 1 to 4 stations
	Network base card	2D-TZ535	–	○	–	○	Communications interface for attaching to Anybus-CompactCom modules manufactured by HMS Accepts EtherNet/IP and PROFINET IO modules (*1)
	Force sensor set	4F-FS001-W200	○	○	○	○	Set of devices required for the force control function including a force sensor and interface unit
	Terminal block replacement tool for the user wiring	2F-CNUSR01M	○	○	○	○	Terminal block replacement tool for the wiring for the external input/output, such as emergency input/output, door switch input, and enabling device input
	Controller protection box	CR750-MB	○	○	–	–	With a built-in CR750-D/Q for improved dust-proofing to IP54 (dedicated CR750)
		CR751-MB	–	–	○	○	With a built-in CR751-D/Q for improved dust-proofing to IP54 (dedicated CR751)
	Personal computer support software	3D-11C-WINE	○	○	○	○	With simulation function (CD-ROM)
	Personal computer support software -mini	3D-12C-WINE	○	○	○	○	Simple version (CD-ROM)
	Simulator (MELFA-Works)	3F-21D-WINE	○	○	○	○	Layout study/Takt time study/Program debug. Add-in software for Solidworks® (*2)

*1: Customer need to prepare the EtherNet/IP(HMS) module (AB6314-B) and PROFINET IO (AB6489-B) themselves.
*2: SolidWorks® is a registered trademark of SolidWorks Corporation (USA).

Configurations options (-SE01) The following options are dedicated for the environmentally-resistant models (Chemical-resistant specification: -SE01). For other models, refer to the options for the standard models.

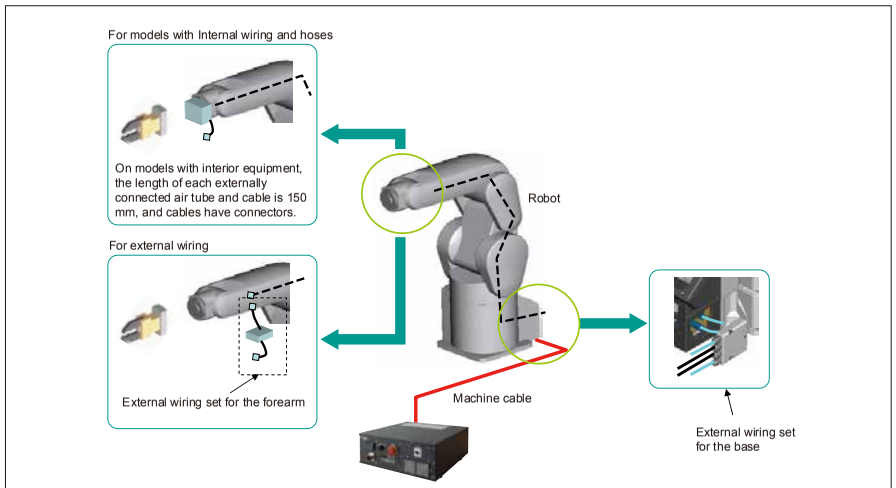
Classification	Name	Type	RV				RH		Functional specifications
			4F 4FL	7F 7FL	7FLL	13F 13FL 20F	6FH	12FH 20FH	
			SE01	SE01	SE01	SE01	SE01	SE01	
Robot arm	Solenoid valve set	1F-VD0□-04(Sink) 1F-VD0□E-04 (Source)	○	○	○	–	–	–	1 to 4 valves, with solenoid valve output cable. □ indicates the number of solenoid valves (1, 2, 3, or 4 valves) Output: ϕ4
		1F-VD0□-05 (Sink) 1F-VD0□E-05 (Source)	–	–	–	○	–	–	1 to 4 valves, with solenoid valve output cable. □ indicates the number of solenoid valves (1, 2, 3, or 4 valves) Output: ϕ6
	External wiring set 1 for the forearm	1F-HB01S-01	○	○	○	–	–	–	Used for the forearm. External wiring box used for connecting the hand input cable, the Ethernet cable, and the electrical hand and force sensor cable.
	External wiring set 2 for the forearm	1F-HB02S-01	○	○	○	–	–	–	Used for the forearm. External wiring box used for connecting the force sensor, the electrical hand, and the Ethernet cable.
	External wiring set 1 for the base	1F-HA01S-01	○	○	○	–	–	–	Used for the base. External wiring box used for connecting the communications output for the electrical hand, the electrical hand and force sensor cable, and the Ethernet cable. There are hand input connection available.
	External wiring set 2 for the base	1F-HA02S-01	○	○	○	–	–	–	Used for the base. External wiring box used for connecting the communications output for the electrical hand, the electrical hand, the force sensor cable, and the Ethernet cable. No hand input connection available.
	External user wiring and piping box	1F-UT-BOX-04	–	–	–	–	○	–	Box for external wiring of user wiring (hand I/O, hand tube)
		1F-UT-BOX-03	–	–	–	–	–	○	Box for external wiring of user wiring (hand I/O, hand tube)
	Machine cable, for extension/fixed CR-751	1F-□□UCBL-03	○	○	○	○	○	○	Exchange type, extended length 10m, 15m, 20m (2wires set with power and signal wires) □□ indicates the length of cables (10, 15, 20m)
	Machine cable, for extension/flexible CR-751	1F-□□LUCBL-03	○	○	○	○	○	○	Exchange type, extended length 10m, 15m, 20m (2wires set with power and signal wires) □□ indicates the length of cables (10, 15, 20m)
	Stopper for changing the J1-axis operating range	1F-DH-06	○	–	–	–	–	–	Stopper for making changes, installed by customer
		1F-DH-07	–	○	–	–	–	–	Stopper for making changes, installed by customer
		1F-DH-08	–	–	○	○	–	–	Stopper for making changes, installed by customer
		1F-DH-09	–	–	–	–	○	–	Stopper for making changes, installed by customer
		1F-DH-10	–	–	–	–	–	○	Stopper for making changes, installed by customer

Options

RV-4F/RV-7F/13F/20F Series Tooling device configuration

Hand configuration	Wiring format	Robot specifications	Required device		Comments
			External wiring set for the forearm	External wiring set for the base (*3)	
• Air-hand + Hand input signal	Interior equipment	-SH01	— (*1)	—	Air hoses: Up to 2 systems (4 mm diameter x 4); 8 input signals
	Exterior equipment	Standard	— (*2)	—	Air hoses: Up to 4 systems (4 mm diameter x 8) are possible.
• Air-hand + Hand input signal • Vision sensor	Interior equipment	-SH05	— (*1)	(1F-HA01S-01)	Air hoses: Up to 1 systems (4 mm diameter x 2); 8 input signals
	Exterior equipment	Standard	1F-HB01S-01 (*2)	1F-HA01S-01	Air hoses: Up to 4 systems (4 mm diameter x 8) are possible.
• Air-hand + Hand input signal • Force sensor	Interior equipment	-SH04	— (*1)	(1F-HA01S-01)	Air hoses: Up to 1 systems (4 mm diameter x 2); 8 input signals
	Exterior equipment	Standard	1F-HB01S-01 (*2)	1F-HA01S-01	Air hoses: Up to 4 systems (4 mm diameter x 8) are possible.
• Air-hand + Hand input signal • Vision sensor • Force sensor	Interior equipment (Air hoses are part of exterior equipment)	-SH02	— (*1)	(1F-HA01S-01)	Air hoses are exterior equipment: 4 systems (4 mm diameter x 8)
	End the connection	Standard	1F-HB01S-01	1F-HA01S-01	Air hoses: Up to 4 systems (4 mm diameter x 8) are possible.

*1: Users must provide the solenoid valves for Internal wiring model air-hands.
*2: Users must provide solenoid valves and hoses/input cables as needed for External wiring model air-hands.
*3: The external wiring set for the base is provided for models with Internal wiring and hoses.

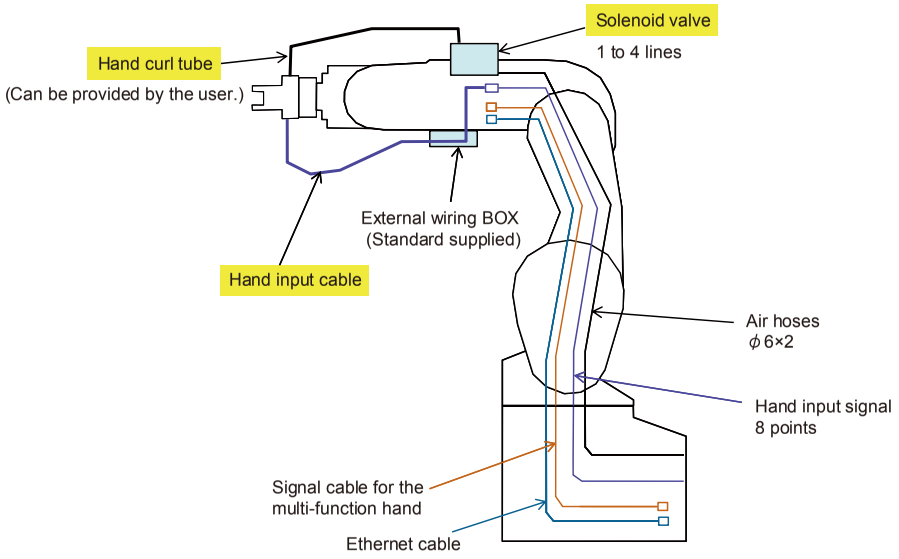


▶ Models with Internal wiring and hoses

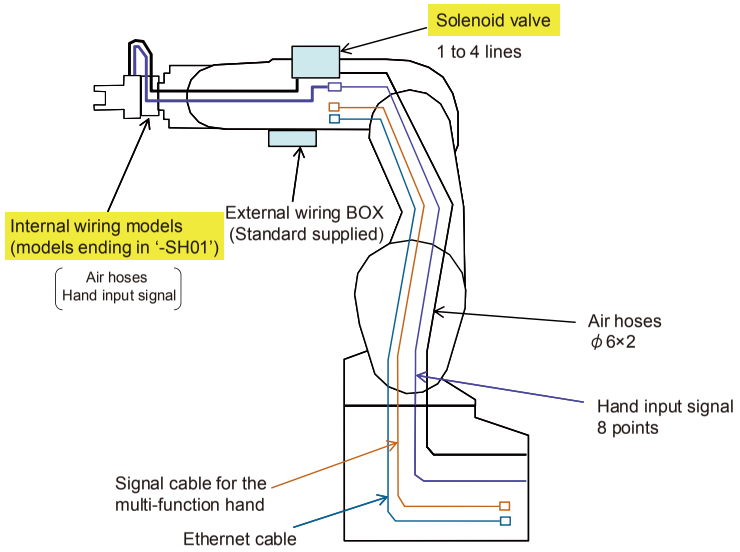
Devices supporting interior hoses	Model (special device number)			
	-SH01	-SH02	-SH04	-SH05
Air 4 mm diameter (×4/×2)	○ (×4)	—	○ (×2)	○ (×2)
Hand inputs (×8)	○	○	○	○
Ethernet (Vision sensor)	—	○	—	○
Force sensor	—	○	○	—

Options

RV series Tooling (air-hand) : External wiring



RV series Tooling (air-hand) : Internal wiring



RT ToolBox2

Type: 3D-11C-WINE

Software for program creation and total engineering support.

This PC software supports everything from system startup to debugging, simulation, maintenance and operation. This includes programming and editing, operational checking before robots are installed, measureing process tact time, debugging during robot startup, monitoring robot operation after startup, and trouble shooting.

Windows®-compatible

- Easy operation on Windows®.
- Compatible with Windows® 2000, Windows® XP, Windows® Vista, and Windows® 7 (32-bit Ver. 1.8 or later, 64-bit Ver. 2.0 or later).

*Windows is registered trademarks of Microsoft Corporation in the United States and other countries.

Enhanced simulation functions

- This function is compatible with all models that connect to CRn-500 series and CRn-700 controllers.
- Robots can be operated and tact time calculated using a personal computer. (Not available for the mini version.)
- Robot movements, operating status, input signals, and servo status can be monitored.

Support for all processes, from programming and startup to maintenance

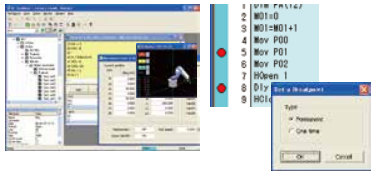
- Programming can be completed using the MELFA-BASIC IV/V and Movemaster languages (vary depending on the model).
- Robot movement and operating status, input signals, and servo status can be monitored.

Advanced maintenance functions

- The software has a maintenance function that notifies the operaters greasing periods, battery life cycles as well as position recovery support function when trouble occurs, etc. and is effective for preventative maintenance, shortening of recovery time.

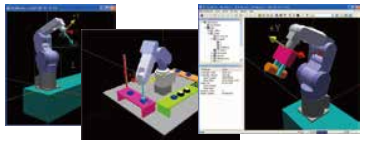
■Program editing and debugging functions

Creation of programs in MELFA-BASIC IV/V and the Movemaster languages. *1 Improvement of work operations by a multi-window format and the various editing functions. This is helpful for use in checking operations such as the execution of program steps, setting of breakpoint settings, and other tasks.



■3D viewer

Graphical representation of a work along with the dimensions, color and other specified details of the work area to be gripped.



*1: MELFA-BASIC is a programming language that further expands upon and develops the commands needed for robot control. In MELFA-BASIC IV/V, the expansion of the command as well as parallel processing or structuring that were difficult to realize in BASIC language can make it possible to operate MELFA easily.

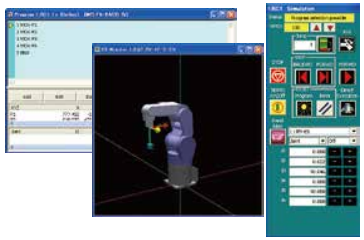
<Example of a Pick & Place program>

```
Mov Psafe          'Move the evasion point
Mov Pget,-50       'Move the workpiece
                    extraction position up
Mvs Pget           'Move the workpiece
                    extraction position
Dly 0.2            'Wait 0.2-sec. on standby
Hclose 1           'Close the hand
Dly 0.2            'Wait 0.2-sec. on standby
Mvs Pget,-50       'Move the workpiece
                    extraction position up
Wait M_In(12)=1    'Wait for a signal
Mov Pput,-80       'Move the workpiece
                    position up
Mvs Pput           'Move the workpiece
                    position
Dly 0.2            'Wait 0.2-sec. on standby
Hopen 1            'Close the hand
.....
```

Classification	Main functions
Operation-related	Joint, linear, and circular interpolation, optimal acceleration/deceleration control, compliance control, collision detection, and singular point passage
Input/output	Bit/byte/word signals, interrupt control
Numerical operations	Numerical operations, pose (position), character strings, logic operations
Additional functions	Multi-tasking, tracking, and vision sensor functions

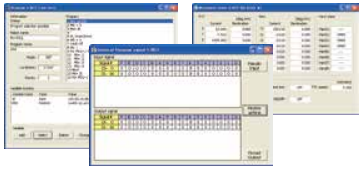
■Simulation functions

Offline robot motion and tact time check for designated parts of a program.



■Monitor functions

This is used to monitor program execution status and variables, input signals, etc.



■Maintenance functions

These functions include maintenance forecast, position recovery support, parameter management, etc.

Options

MELFA-Works

Type: 3F-21D-WINE

3D robot simulator offering powerful support for system design and preliminary layout.

What is MELFA-Works?

MELFA-Works is an add-in tool (*1) for SolidWorks(*2) used for robot simulation in production systems on PC's converting processing paths of workpieces into robot position data. Adding MELFA-Works into...on the robot simulation functions.

*1) An add-in tool is a software program that adds certain functions to application software packages.
*2) SolidWorks® is a registered trademark of SolidWorks Corp, (USA).

Features

Automatic robot program creation function

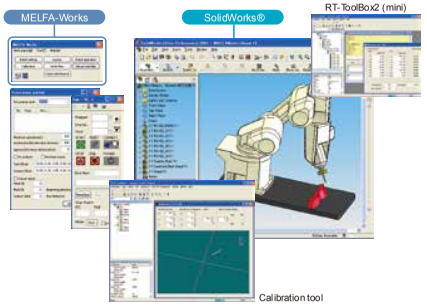
The teaching position data and robot operation programs necessary for operating robots can be generated automatically by simple loading of 3D CAD data (*3) for the applicable works into SolidWorks® and then setting of processing conditions and areas using MELFA-Works.

*3) Formats that can be loaded into SolidWorks®

- IGES
- STEP
- ParasolidR
- SAT (ACISR)
- Pro/ENGINEERR
- CGR (CATIARgraphics)
- Unigraphics
- PAR (Solid Edge TM)
- IPT (Autodesk Inventor)
- DWG
- DXFTM
- STL
- VRML
- VDA-FS
- Machanical Desktop
- CADKEYR
- Viewpoint
- RealityWave
- HOOPS
- HCG (Highly compressed graphics)

Note) Check the SolidWorks website and other published documents for the latest specifications.

■ Example Screens for MELFA-Works



List of functions

Loading of part data from peripheral devices and rearrangement

Part data created in Solidworks® can be loaded.
The positions of loaded parts can be rearranged relative to the CAD origin and other parts.
Part positions can also be changed via numerical input.

Installation of hands

Hands designed/created in SolidWorks® can be installed on robots. An ATC (Auto Tool Changer) can also be specified for each hand.

Handling of work

Simulations of hand signal control can be created using a robot program to handle workpieces.

CAD link

Operation data needed to perform sealing and other operations requiring many teaching steps are easily created. All you need is to select the target area to be processed from 3D CAD data. Since operation data is created from 3D CAD source data, complex three-dimensional curves can be recreated with ease.
This leads to significant reduction in teaching time.

Offline teaching

The robot posture can be set up on the screen in advance.

Creation of robot programs (template)

Workflow processes can be created using a combination of the offline teaching and CAD link functions and then converted into robot programs. (MELFA-BASIC IV, V format)

Assignment of robot programs

Robot programs can be used as is without any modifications.
A different robot program can also be specified for each task slot.

Simulation of robot operations

Robot programs, including I/O signals, can be simulated.This means that movements of the actual system can be recreated directly and accurately. The following two methods are provided to simulate I/O signals of your robot controller.
(1) Create simple definitions of operations associated with I/O signals.
(2) Link I/O signals with GX Simulator.

Display of the robot movement path

Robot movement path can be displayed in the application / the workspace as.

Interference checks

Interference between the robot and peripheral devices can be checked. A target of interference check can be specified by a simple mouse click it on the screen. Information explaining the condition of interference that occurred (such as the contacted part, program line that was being executed when the interference occured, and corresponding robot position) can be saved to a logfile.

Saving of video data

Simulated movements can be saved to video files (AVI format).

Measurement of cycle times

The cycle time of robot movement can be measured using an easy-to-use function resembling a stopwatch. It realizes the cycle time measurement of a specified part in a program.

Robot program debugging functions

The following functions are provided to support the debug of robot programs.
- Step operation : A specified program can be executed step by step.
- Breakpoint : Breakpoints can be set in a specified program.
- Direct execution : Desired robot commands can be executed.

Jog function

The robot shown in SolidWorks® can be jogged just like a real robot.

Traveling axis

A traveling axis can be installed to a robot to verify the operation of the system equipped with this.

Calibration

Point sequence data of CAD coordinates created by the CAD link function can be corrected to robot coordinate data.
Operation programs and point sequence data can also be transferred to robots.
To provide greater convenience for operators who perform calibration frequently on site, the calibration tool is provided as an application independent of MELFA-Works.
Accordingly, the calibration tool can be operated effectively on a notebook computer in which SolidWorks® software is not installed

Force sensor set

Type: 4F-FS001-W200

Allows copy and fitting work to be completed in the same way a person would while the force applied to the hand is monitored.
Enables necessary work such as fine force adjustments and force detection to be completed.

Improved production stability

Enables parts to be inserted or attached without being damaged while absorbing shifts in position due to part variations and emulating the slight amounts of external force applied. Improved operating stability gained through position latches and retry processes when work operations fail. Log data can be used to manage quality control and analyze causes of work errors and other issues.

Allows assembly of more complicated configurations

Force detection during contact allows operating directions and applied force to be changed and interrupts to be executed under trigger conditions combining position and force information.

Simple control

Simple programs can be created using specialized robot language.

Simple operation

Work conditions can be checked and adjusted by viewing position and force data from the teaching box and graphs on RT ToolBox2.

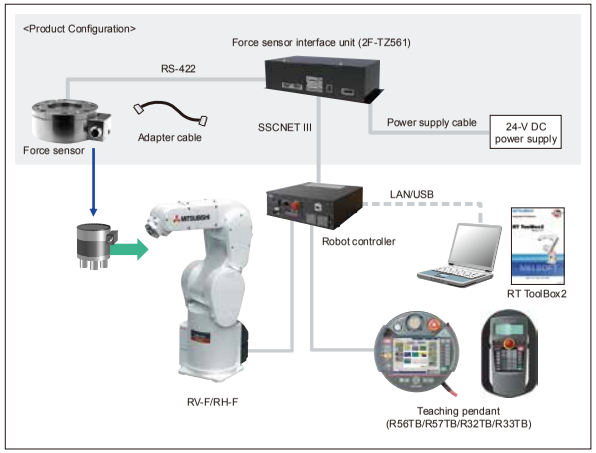
Product features

Item		Features
Force control	Force control	Function for controlling robots while applying a specified force
	Stiffness control	Function for controlling the stiffness of robot appendages
	Gain changes	Function for changing control characteristics while the robot is running
Force detection	Execution of interrupts	Interrupts can be executed (MO triggers) under trigger conditions combining position and force information.
	Data latch	Function for acquiring force sensor and robot positions while contact made
	Data reference	Function for display force sensor data and maintaining maximum values
Force log	Synchronous data	Function for acquiring force sensor information synchronized to position infromation as log data and displaying it in graph form
	Start/stop trigger	Allows logging start/stop commands to be specified in robot programs
	FTP transmission	Function for transferring acquired log files to the FTP server
Teaching box	Force sense control	Enables/disables force sensor control and sets control conditions while jogging.
	Force sense monitor	Displays sensor data and the force sense control setting status.
	Teaching position search	Function for searching for the contact position.
	Parameter setting screen	Parameter setting screen dedicated for the force sense function. (For R56B/R57TB)

Product Configuration

Name	Qty.
Force sensor	Qty. 1
Force sensor interface unit	Qty. 1
Sensor adapter	Qty. 1
Adapter cable	Qty. 1
24V DC power supply	Qty. 1
24V DC power supply cable	1m
Serial cable between the unit and sensor	5m
SSCNET III cable	10m

System Configuration



Force Sensor Specifications

Item		Unit	Specification Value
Rated load	Fx, Fy, Fz	N	200
	Mx, My, Mz	Nm	4
Max. static load	Fx, Fy, Fz	N	1000
	Mx, My, Mz	Nm	6
Breaking load	Fx, Fy, Fz	N	10000
	Mx, My, Mz	Nm	300
Minimum control force	Fx, Fy, Fz	N	0.3
	Mx, My, Mz	Nm	0.03
Consumption current		mA	200
Weight (sensor unit)		g	200
External dimensions		mm	ϕ80 x 3.25
Protective structure		-	IP30

Force Sense Interface Unit Specifications

Item		Unit	Specification Value
Interface	RS-422	ch	1 (For sensor connection)
	SSCNET III	ch	1 (For robot controller and additional axis ampconnection)
Power supply	Input voltage	Vdc	24±5%
	Power consumption	W	25
External dimensions		mm	225(W) x 111(D) x 48(H)
Weight		kg	Approx. 0.8
Construction		-	IP20 (Panel installation, opentype)

Options

In-Sight (Manufactured by COGNEX: For Mitsubishi Electric FA devices)

The In-Sight software developed exclusively for use with Mitsubishi Electric FA devices with enhanced linking to In-Sight, the vision system produced by COGNEX Corporation, offers better compatibility with FA devices, allowing it to be utilized more easily as a more user-friendly vision system.

Simplified settings using Easy Builder

Easy Builder allows connection to vision systems, setting of job (vision programs) settings, and calibration between the robot and vision system to be completed easily and quickly.

Simplified connection using Ethernet

Up to three robots and seven vision systems can be connected together to the same system by Ethernet connection. Vision system information can be shared between multiple robots.

Simplified control using robot language

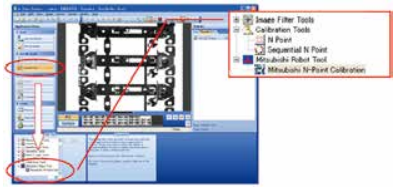
The included dedicated vision system commands enable vision system startup, job selection, and control of data receiving and other operations to be completed quickly and easily using a single command without any need for protocols.

Simplified job editing

Jobs (Vision recognition programs) are created from the job editing screen. Jobs can be edited using condition settings and other data, eliminating the need for specialized knowledge of vision control commands and other programming instructions.

Simplified calibration

The calibration wizard allows settings used in converting workpiece positions recognized by the vision system into robot coordinate system coordinates easily and quickly.



Robot controller specifications

Item	Specifications
Software	Robot controller: CR750 Series CRnQ-700 Series: R1 ver. or later CRnD-700 Series: S1 ver. or later RT ToolBox2: Ver. 1.0 or later recommended
Adapted robot controller	CR7xx/ CRnQ-7xx/ CRnD-7xx
Connected robot	All models
Number of robots connected to the vision system	Number of cameras used per robot controller: Up to 7 max. Number of robots that can be connected to a vision system: Up to 3 max.
Robot program language	MELFA-BASIC V comes with dedicated vision sensor commands

Model name -□□□		Entry	In-Sight Series					
			Standard		High resolution	Color		
		100	110	140	143	110C	140C	143C
Performance and magnification	Average performance data setting that for the standard version to 1 (*2)	1×	2×	5×	4×	2×	5×	4×
Camera	Resolution	640×480	640×480	640×480	1600×1200	640×480	640×480	1600×1200
	CCD sensor size	1/3 in.	1/3 in.	1/3 in.	1/1.8 in.	1/3 in.	1/3 in.	1/1.8 in.
	Color	×	×	×	×	○	○	○

Simplified control using robot language

MELFA BASIC V comes with dedicated vision system control commands and status variables. These control commands and status variables enable the vision system to be controlled using simple programs.

Instruction word	Details
NVOpen	Connect to the vision system and log on.
NVPst	Start up the specified vision program and receive the transmitted results.
NVRun	Start up the specified vision program.
NVIn	Receive the transmitted results of the vision program specified by the NVRUN command.
NVClose	End the connection to the vision system.
NVLoad	Ready the specified vision program to enable it for startup.
NVTrg	Transmit a request to the vision system for the image and acquire the encoder values after the specified length of time.

Separate MELFA-Vision software is available for customers using In-Sight5000 series or In-Sight Micro series products. The use of job programs corresponding to work tasks performed regularly enables even customers who are new to vision systems to easily understand and use them without problems.

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