

Mitsubishi Industrial Robot

CR750-D/CR751-D Controller

RH-6/12/20FHM-D-SE Series Standard Specifications Manual





Safety Precautions

Always read the following precautions and the separate "Safety Manual" before starting use of the robot to learn the required measures to be taken.

All teaching work must be carried out by an operator who has received special training. (This also applies to maintenance work with the power source turned ON.)

Enforcement of safety training

CAUTION

For teaching work, prepare a work plan related to the methods and procedures of operating the robot, and to the measures to be taken when an error occurs or when restarting. Carry out work following this plan. (This also applies to maintenance work with the power source turned ON.)

Preparation of work plan

⚠ WARNING

Prepare a device that allows operation to be stopped immediately during teaching work. (This also applies to maintenance work with the power source turned ON.)

Setting of emergency stop switch

⚠ CAUTION

During teaching work, place a sign indicating that teaching work is in progress on the start switch, etc. (This also applies to maintenance work with the power source turned ON.)

Indication of teaching work in progress

∕!\ DANGER

Provide a fence or enclosure during operation to prevent contact of the operator and robot.

Installation of safety fence

⚠ CAUTION

Establish a set signaling method to the related operators for starting work, and follow this method.

Signaling of operation start

⚠ CAUTION

As a principle turn the power OFF during maintenance work. Place a sign indicating that maintenance work is in progress on the start switch, etc. Indication of maintenance work in progress

⚠ CAUTION

Before starting work, inspect the robot, emergency stop switch and other related devices, etc., and confirm that there are no errors. Inspection before starting work

The points of the precautions given in the separate "Safety Manual" are given below. Refer to the actual "Safety Manual" for details.

♠ DANGER	When automatic operation of the robot is performed using multiple control
	devices (GOT, programmable controller, push-button switch), the interlocking of
	operation rights of the devices, etc. must be designed by the customer.

CAUTION

Use the robot within the environment given in the specifications. Failure to do so could lead to a drop or reliability or faults. (Temperature, humidity, atmosphere, noise environment, etc.)

Transport the robot with the designated transportation posture. Transporting the robot in a non-designated posture could lead to personal injuries or faults from dropping.

CAUTION Always use the robot installed on a secure table. Use in an instable posture could lead to positional deviation and vibration.

CAUTION Wire the cable as far away from noise sources as possible. If placed near a noise source, positional deviation or malfunction could occur.

Do not apply excessive force on the connector or excessively bend the cable. Failure to observe this could lead to contact defects or wire breakage.

Make sure that the workpiece weight, including the hand, does not exceed the rated load or tolerable torque. Exceeding these values could lead to alarms or faults.

Securely install the hand and tool, and securely grasp the workpiece. Failure to observe this could lead to personal injuries or damage if the object comes off or flies off during operation.

WARNING

Securely ground the robot and controller. Failure to observe this could lead to malfunctioning by noise or to electric shock accidents.

CAUTION Indicate the operation state during robot operation. Failure to indicate the state could lead to operators approaching the robot or to incorrect operation.

WARNING
When carrying out teaching work in the robot's movement range, always secure the priority right for the robot control. Failure to observe this could lead to personal injuries or damage if the robot is started with external commands.

∠ CAUTION

CAUTION Keep the jog speed as low as possible, and always watch the robot. Failure to do so could lead to interference with the workpiece or peripheral devices.

After editing the program, always confirm the operation with step operation before starting automatic operation. Failure to do so could lead to interference with peripheral devices because of programming mistakes, etc.

Make sure that if the safety fence entrance door is opened during automatic operation, the door is locked or that the robot will automatically stop. Failure to do so could lead to personal injuries.

Never carry out modifications based on personal judgments, or use non-designated maintenance parts.

Failure to observe this could lead to faults or failures.

⚠ WARNING

When the robot arm has to be moved by hand from an external area, do not place hands or fingers in the openings. Failure to observe this could lead to hands or fingers catching depending on the posture.

⚠ CAUTION

Do not stop the robot or apply emergency stop by turning the robot controller's main power OFF. If the robot controller main power is turned OFF during automatic operation, the robot accuracy could be adversely affected. Moreover, it may interfere with the peripheral device by drop or move by inertia of the arm.

⚠ CAUTION

Do not turn off the main power to the robot controller while rewriting the internal information of the robot controller such as the program or parameters. If the main power to the robot controller is turned off while in automatic operation or rewriting the program or parameters, the internal information of the robot controller may be damaged.

⚠ DANGER

Do not connect the Handy GOT when using the GOT direct connection function of this product. Failure to observe this may result in property damage or bodily injury because the Handy GOT can automatically operate the robot regardless of whether the operation rights are enabled or not.

⚠ DANGER

Do not remove the SSCNET III cable while power is supplied to the controller. Do not look directly at light emitted from the tip of SSCNET III connectors or SSCNET III cables. Eye discomfort may be felt if exposed to the light. (Reference: SSCNET III employs a Class 1 or equivalent light source as specified in JIS C 6802 and IEC60825-1 (domestic standards in Japan).)

⚠ DANGER

Attach the cap to the SSCNET III connector after disconnecting the SSCNET III cable. If the cap is not attached, dirt or dust may adhere to the connector pins, resulting in deterioration connector properties, and leading to malfunction.

A CAUTION

Make sure there are no mistakes in the wiring. Connecting differently to the way specified in the manual can result in errors, such as the emergency stop not being released. In order to prevent errors occurring, please be sure to check that all functions (such as the teaching box emergency stop, customer emergency stop, and door switch) are working properly after the wiring setup is completed.

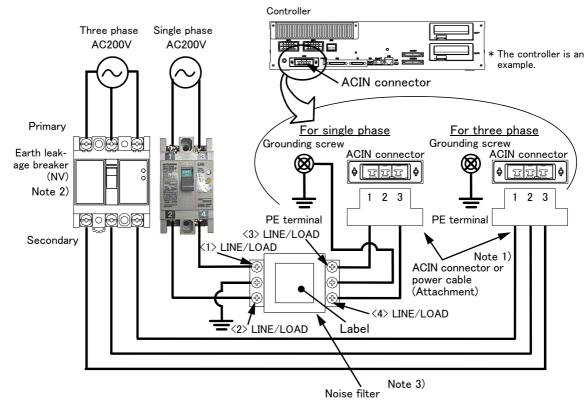
A CAUTION

Use the network equipments (personal computer, USB hub, LAN hub, etc) confirmed by manufacturer. The thing unsuitable for the FA environment (related with conformity, temperature or noise) exists in the equipments connected to USB. When using network equipment, measures against the noise, such as measures against EMI and the addition of the ferrite core, may be necessary. Please fully confirm the operation by customer. Guarantee and maintenance of the equipment on the market (usual office automation equipment) cannot be performed.

Notes of the basic component are shown.

⚠ CAUTION

Please install the earth leakage breaker in the primary side supply power supply of the controller of CR751-D or CR751-Q because of leakage protection.



- Note 1) Crimping swage is recommended for connecting the attachment ACIN connector (soldering is also possible)
 Recommendation compression tools: 234171-1(Tyco Electronics)
- Note 2) The earth leakage breaker is the customer preparation. Always use the cover below.

 Recommendation: For single primary power supply NV30FAU-2P-10A-AC100-240V-30mA, (Cover: TCS-05FA2)

 For three primary power supply NV30FAU-3P-10A-AC100-240V-30mA, (Cover: TCS-05FA3)
- Note 3) If necessary, as shown in the figure, connects the noise filter between ACIN terminal blocks and primary power supply.

 (Recommended noise filter: SUP-EL20-ER6 *OKAYA ELECTRIC INDUSTRIES)
 - Please prepare the following: Leakage current breaker (with the terminal cover), cable for connecting the primary power supply (AWG #14 (2mm² or above), cables to ground the primary power supply (AWG #12 (3.5mm² or above).
 - The secondary power cable (with the ACIN connector) for single phase or three phase power is supplied with the product to match the specifications. When you build a cable suitable for your environment using the ACIN connector and the ACIN terminal supplied, prepare a secondary power cable (AWG #14 (2mm²) or above).
 - 2) Confirm that the primary power matches the specifications.
 - 3) Confirm that the primary power is OFF and that the earth leakage breaker power switch is OFF.
 - 4) Connect the secondary power cable.
 - a) When using the supplied power cable with the ACIN connector

Refer to the figure above and connect the cable from the secondary side of the earth leakage breaker.

b) When building a power cable using the ACIN connector and the ACIN terminals supplied

Connect the ACIN terminals with the secondary power cable (prepared by customers), and insert the ACIN terminals to the ACIN connector pins with the following numbers. Crimping caulking is recommended to connect the ACIN terminals.

For single phase: 1 and 3 For three phase: 1, 2, and 3

Refer to the figure above and connect the cable from the secondary side of the earth leakage breaker.

- 5) Connect this ACIN connector to the ACIN connector on the front of the controller.
- 6) Connect the grounding cable to the PE terminal. (M4 screw)
- 7) Connect the primary power cable to the primary side terminal of the earth leakage breaker.



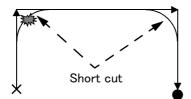
Be careful of interference with peripheral equipment.

Especially don't give a shock to the shaft (J3 axis). When you install the hand, be careful not to knock at the shaft end by the hammer etc. The shaft may be damaged.

Take care also of the following items.

(1)The robot's locus of movement may change with specified speed.

Especially as for the corner section, short cut distance may change. Therefore, when beginning automatic operation, moves at low speed at first, and you should gather speed slowly with being careful of interference with peripheral equipment.



Arch movement (example)

(2)It can be confirmed whether the specified position exist in the defined area by using the instruction command "Zone". It can utilize as one of the methods for collision evasion. Refer to the "detailed description of the instructions manual/function, and operation" of the separate volume for the details of the instruction command.

■Revision history

Date of print	Specifications No.	Details of revisions
2014-08-20	BFP-A3319	• First print.
2014-12-17	BFP-A3319-A	 Allowance value of the offset amount were added to "2.2.2 Mass capacity". The models of the CE Marking specification were added. The description of how to change the operating range moved into "INSTRUCTION MANUAL/ROBOT ARM SETUP & MAINTENANCE". Correction of errors in the Specifications discussion materials. (Network vision senso 4D-2CG5***-PKG was deleted.) The corporate logo mark of illustrations in this manual was changed. "6.4 EMC installation guideline" was added.
2015-02-10	BFP-A3319-B	 The special hexagon flange bolts are also used for SE1502 model. The description in case the ethernet cable is used as a backup wiring for data communication was added.
2015-11-17	BFP-A3319-C	 "Declaration of Incorporation" and "EC-Statement of Compliance" were updated. Transportation precaution of the lithium battery was modified. List of parts and manufacturer of parallel I/O unit was corrected. Note1) in "Table3-6: Function of the key switch interface" was corrected.
2015-12-14	BFP-A3319-D	Circuit diagrams in "3.6.1 Connection of the external emergency stop" and "6.1.7 Examples of safety measures" were modified.

■ Introduction

This series offers small-size industrial robots developed using Mitsubishi's latest technology. They are especially designed to handle and assemble mechanical parts. They are Mitsubishi's answer to the customer's need to achieve a compact manufacturing facility capable of highly flexible production, as necessitated by the diffusion of high-density product groups and the shorter product life cycles that have become common-place in recent years.

In order to support transportation and processing in food and pharmaceutical plants, we offer a product lineup with multiple-resistant specifications with improved corrosion resistance or washability of the robot arm. The products with chemical-resistant specifications (SExx01) and food machinery grade H1 grease specifications (SExx02) are available.

However, to comply with the target application, a work system having a well-balanced robot arm, peripheral devices or robot and hand section must be structured.

When creating these standard specifications, we have edited them so that the Mitsubishi robot's characteristics and specifications can be easily understood by users considering the implementation of robots. However, if there are any unclear points, please contact your nearest Mitsubishi branch or dealer.

Mitsubishi hopes that you will consider these standard specifications and use our robots.

Note that in this specification document the specifications related to the robot arm is described Page 13, "2 Robot arm", the specifications related to the controllerPage 84, "3 Controller", and software functions and a command list Page 162, "4 Software" separately.

This document has indicated the specification of the following types robot.

```
*RH-6FHM-D-SE series
*RH-12FHM-D-SE series
*RH-20FHM-D-SE series
```

· About CE Marking in the automization system

The Guidelines of the measures against EMC in the automization system manufactured by the customer is shown in Page 186, "6.4 EMC installation guideline".

Please refer to it and carry out the measures against EMC of the automization system of the customer.

- No part of this manual may be reproduced by any means or in any form, without prior consent from Mitsubishi.
- The contents of this manual are subject to change without notice.
- The specifications values are based on Mitsubishi standard testing methods.
- The information contained in this document has been written to be accurate as much as possible.
 Please interpret that items not described in this document "cannot be performed." or "alarm may occur".
- Please contact your nearest dealer if you find any doubtful, wrong or skipped point.
- This specifications is original.
- Microsoft, Windows, Windows XP, Windows Vista, Windows 7, Windows 8, Windows 8.1 are either registered trademarks or trademarks of Microsoft Corporation in the United States and/or other countries.
- The official name of Windows® is Microsoft®Windows®Operating System.
- Windows®XP、Windows Vista®、Windows® 7、Windows® 8、Windows® 8.1 are either product names of Microsoft Corporation in the United States.
- Ethernet is registered trademarks or trademarks of Xerox Corporation in the United States.
- All other company names and production names in this document are the trademarks or registered trademarks of their respective owners.

Contents

	Page
1 General configuration	1-1
1.1 Structural equipment	1-1
1.1.1 Standard structural equipment	
1.1.2 Special specifications	1-1
1.1.3 Options	1-1
1.1.4 Maintenance parts	1-1
1.2 Model type name of robot	1-2
1.2.1 How to identify the robot model	1-2
1.2.2 Combination of the robot arm and the controller	1-3
(1) CR750 controller	1-3
(2) CR751 controller	1-4
1.3 CE marking specifications	1-5
(1) CR750 controller	1-5
(2) CR751 controller	1-5
1.4 Contents of the structural equipment	1-6
1.4.1 Robot arm	
1.4.2 Controller	1-8
(1) CR750controller	1-8
(2) CR751 controller	1-9
1.5 Contents of the Option equipment and special specification	1–10
2 Robot arm	2-13
2.1 Standard specifications	2-13
2.1.1 Basic specifications	
(1) RH-6FH series	
(2) RH-12FH series	
(3) RH-20FH series	2-17
2.1.2 The counter-force applied to the installation surface	2 –18
2.2 Definition of specifications	2-19
2.2.1 Pose repeatability	
2.2.2 Mass capacity	
2.2.3 Relationships Among Mass Capacity, Speed, and Acceleration/Deceleration Speed	2-22
(1) Setting Load Capacity and Size (Hand Conditions)	
2.2.4 Vibrations at the Tip of the Arm during Low-Speed Operation of the Robot	2-22
2.2.5 Vibration of shaft (J3 axis) position and arm end	2-23
(1) Relationship Between Mass Capacity and Speed	2-23
(2) Relationship Between Height of Shaft (J3 Axis) and Acceleration/Deceleration Speed	2-24
(3) Relation between offset length and the maximum speed	2-26
(4) Time to reach the position repeatability	2-27
2.2.6 Collision detection	2–2 8
2.2.7 Protection specifications	
(1) Types of protection specifications	
(2) About using the robot in the sterilization environment	
(3) About the cleanliness	2–30
2.3 Names of each part of the robot	2-31
2.4 Outside dimensions • Operating range diagram	2-32
2.4.1 Outside dimensions • Operating range diagram (RH-6FH series)	2-32
2.4.2 Outside dimensions • Operating range diagram (RH-12FH series)	2 –38
2.4.3 Outside dimensions • Operating range diagram (RH-20FH series)	
2.4.4 Mechanical interface and Installation surface	
(1) Mechanical interface and Installation surface of RH-6FH series	
(2) Mechanical interface and Installation surface of RH-12FH series	
(3) Mechanical interface and Installation surface of RH-20FH series	
2.4.5 Outside dimensions of machine cables	
(1) Connection with the CR750 controller	
(2) Connection with the CR751 controller	2-51

Contents

	Page
2.5 Tooling	
2.5.1 Wiring and piping for hand	2-52
2.5.2 Internal air piping	
2.5.3 Internal wiring for the hand output cable	
2.5.4 Internal wiring for the hand input cable	
2.5.5 Ethernet cable	
2.5.6 About the Installation of Tooling Wiring and Piping (Examples of Wiring and Piping)	
(1) RH-6FH series	
(2) RH-12FH/20FH series	
(3) Example of wiring and piping <1>	
(4) Wiring and piping example <2>	
2.5.7 Wiring and piping system diagram for hand	
2.5.8 Electrical specifications of hand input/output	
2.5.9 Air supply circuit example for the hand	
2.6 Shipping special specifications, options, and maintenance parts	
2.6.1 Shipping special specifications	
2.7 Options	
(1) Machine cable extension	
(2) Stopper for changing the operating range	
(3) Solenoid valve set	
(4) Hand input cable(5) Hand output cable	
(6) Hand curl tube	
(7) Internal Wiring/Piping set for hand	
(8) External Wiring/Piping box	
2.8 About Overhaul	
2.9 Maintenance parts	
3 Controller	3–84
3.1.2 Protection specifications and operating supply	
3.2 Names of each part	
3.2.1 Controller	
(1) CR750 controller	
(2) CR751 controller	
3.3 Outside dimensions/Installation dimensions	
3.3.1 Outside dimensions	
(1) CR750 controller	
(2) CR751 controller	
3.3.2 Installation dimensions	
(1) CR750 controller	
(2) CR751 controller	
3.4 External input/output	
3.4.1 Types	
3.5 Dedicated input/output	
3.6 Emergency stop input and output etc.	
3.6.1 Connection of the external emergency stop	
(1) CR750 controller	
(2) CR751 controller	
3.6.2 Special stop input (SKIP)	
(1) CR750 controller	
(2) CR751 controller	
3.6.3 Door switch function	
J.U.4 LITADHITE UCVICE TUTICUOTI	۱۱۱ - ۱۱۱ -

Contents

	Page
(1) When door is opening	3-111
(2) When door is closing	
(3) Automatic Operation/Jog Operation/Brake Release and Necessary Switch Settings	3-112
3.7 Mode changeover switch input	
(1) Specification of the key switch interface	
(2) Connection of the mode changeover switch input	3-114
3.8 Additional Axis Function	3-115
3.8.1 Wiring of the Additional Axis Interface	
(1) CR750 controller	
(2) CR751 controller	
3.9 Magnet contactor control connector output (AXMC) for addition axes	
(1) CR750 controller	
(2) CR751 controller	3–120
3.10 Options	
(1) Teaching pendant (T/B)	
(2) Parallel I/O interface	
(3) External I/O cable	
(4) Parallel I/O unit	
(5) External I/O cable	
(6) CC-Link interface	
(7) Controller protection box(8) MELSOFT RT ToolBox2/RT ToolBox2 mini	
(9) Instruction Manual (bookbinding)	
3.11 Maintenance parts	3-161
4 Software	<i>I</i> -162
4.1 List of commands	
4.2 List of parameters	4-165
5 Instruction Manual	5-167
5.1 The details of each instruction manuals	
5.1 The details of each instruction manuals	5-167
6 Safety	6-168
6.1 Safety	
6.1.1 Self-diagnosis stop functions	
6.1.2 External input/output signals that can be used for safety protection measures	
6.1.3 Precautions for using robot	
6.1.4 Safety measures for automatic operation	
6.1.5 Safety measures for teaching	
6.1.6 Safety measures for maintenance and inspections, etc.	6-170
6.1.7 Examples of safety measures	6-171
(1) CR750 controller	6-171
(2) CR751 controller	
(3) External emergency stop connection [supplementary explanation]	6-181
6.2 Working environment	6-184
6.3 Precautions for handling	6-184
6.4 EMC installation guideline	6-186
6.4.1 Outlines	
6.4.2 EMC directive	
6.4.3 EMC measures	
6.4.4 Component parts for EMC measures	
(1) Ferrite core	
(2) Line noise filter	6-187
7Appendix	
Appendix 1 : Specifications discussion material (RH-6FH series) Appe	
Appendix 2 : Specifications discussion material (RH-12FH series)	ndix-189

Contents				
Appendix 3 : Specifications discussion material (RH-20FH series)	Page Appendix-190			

1 General configuration

1.1 Structural equipment

Structural equipment consists of the following types.

1.1.1 Standard structural equipment

The following items are enclosed as a standard.

- (1) Robot arm
- (2) Controller
- (3) Machine cable
- (4) Robot arm installation bolts
- (5) Safety manual, CD-ROM (Instruction manual)
- (6) Guarantee card

1.1.2 Special specifications

For the special specifications, some standard configuration equipment and specifications have to be changed before factory shipping. Confirm the delivery date and specify the special specifications at the order.

1.1.3 Options

User can install options after their delivery.

1.1.4 Maintenance parts

Materials and parts for the maintenance use.

1.2 Model type name of robot

(a)

This robot has arranged the type name corresponding to load mass, arm length, and environment specification. Details are shown below, please select the robot suitable for the customer's use.

1.2.1 How to identify the robot model

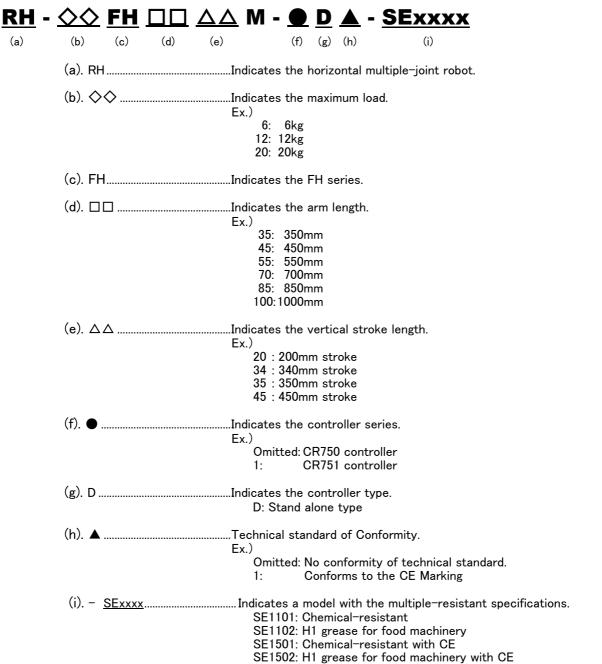


Table 1-1: Multiple-resistant correspondence table

	Table 1 1 : Martiple Teological Control Contro					
Specification	Item	Chemical-resistant specifications (SExx01)	Food machinery grade H1 grease specifications (SExx02)			
Α	Application of NSF H1 certified grease	0	0			
В	Use of stainless steel at the end of the robot	0	0			
С	Adoption of special hexagon flange bolts	0	O (- Note1))			
D	Chemical-resistant body coating	0	-			
E	Use of a chemical-resistant sealing material	0	-			
F	Improved chemical resistance of the bellows material	0	-			

Note1) Not apply for SE1102.

1.2.2 Combination of the robot arm and the controller

(1) CR750 controller

Table 1-2: Combination of the robot arm and the CR750 controller

Protection specification	Robot arm (Floor installation type)	Arm length (mm)	J3-axis stroke (mm)	Controller ^{Note1)}
RH-6FH series				
Chemical-resistant specifications	RH-6FH3520M-D-SE1101	350		
(SE1101)	RH-6FH4520M-D-SE1101	450	200	
	RH-6FH5520M-D-SE1101	550		CR750-06HD-1-SE1101
	RH-6FH3534M-D-SE1101	350		CR/30-00HD-1-3E1101
	RH-6FH4534M-D-SE1101	450	340	
	RH-6FH5534M-D-SE1101	550		
Food machinery grade H1 grease	RH-6FH3520M-D-SE1102	350		
specifications (SE1102)	RH-6FH4520M-D-SE1102	450	200	
	RH-6FH5520M-D-SE1102	550		CR750-06HD-1-SE1102
	RH-6FH3534M-D-SE1102	350		GR/50-00HD-1-5E1102
	RH-6FH4534M-D-SE1102	450	340	
	RH-6FH5534M-D-SE1102	550		
RH-12FH series	*	-1		
Chemical-resistant specifications	RH-12FH5535M-D-SE1101	550		- CR750-12HD-1-SE1101
(SE1101)	RH-12FH7035M-D-SE1101	700	350	
	RH-12FH8535M-D-SE1101	850		
	RH-12FH5545M-D-SE1101	550		
	RH-12FH7045M-D-SE1101	700	450	
	RH-12FH8545M-D-SE1101	850		
Food machinery grade H1 grease	RH-12FH5535M-D-SE1102	550		
specifications (SE1102)	RH-12FH7035M-D-SE1102	700	350	
	RH-12FH8535M-D-SE1102	850		OD750 10UD 1 051100
	RH-12FH5545M-D-SE1102	550		CR750-12HD-1-SE1102
	RH-12FH7045M-D-SE1102	700	450	
	RH-12FH8545M-D-SE1102	850		
RH-20FH series		1	ı.	<u> </u>
Chemical-resistant specifications	RH-20FH8535M-D-SE1101	850	250	
(SE1101)	RH-20FH10035M-D-SE1101	1000	350	CR750-20HD-1-SE1101
	RH-20FH8545M-D-SE1101	850	450	CK/30-20HD-1-3E1101
	RH-20FH10045M-D-SE1101	1000	450	
Food machinery grade H1 grease	RH-20FH8535M-D-SE1102	850	250	
specifications (SE1102)	RH-20FH10035M-D-SE1102	1000	50 450 CR750-2	OD750 00UD 1 051100
	RH-20FH8545M-D-SE1102	850		CR750-20HD-1-SE1102
	RH-20FH10045M-D-SE1102	1000		

Note1) The controller is not chemical-resistant. For installing the controller, avoid places where adhesion of chemicals may occur.

(2) CR751 controller

Table 1-3: Combination of the robot arm and the CR751 controller

Protection specification	Robot arm (Floor installation type)	Arm length (mm)	J3-axis stroke (mm)	Controller Note1)
RH-6FH series				•
Chemical-resistant specifications	RH-6FH3520M-1D-SE1101	350		
(SE1101)	RH-6FH4520M-1D-SE1101	450	200	
	RH-6FH5520M-1D-SE1101	550		CR751-06HD-0-SE1101
	RH-6FH3534M-1D-SE1101	350		CR/31-00HD-0-3E1101
	RH-6FH4534M-1D-SE1101	450	340	
	RH-6FH5534M-1D-SE1101	550		
Food machinery grade H1 grease	RH-6FH3520M-1D-SE1102	350		
specifications (SE1102)	RH-6FH4520M-1D-SE1102	450	200	
	RH-6FH5520M-1D-SE1102	550		CR751-06HD-0-SE1102
	RH-6FH3534M-1D-SE1102	350		CR/31-00HD-0-3E1102
	RH-6FH4534M-1D-SE1102	450	340	
	RH-6FH5534M-1D-SE1102	550		
RH-12FH series	=			
Chemical-resistant specifications	RH-12FH5535M-1D-SE1101	550		
(SE1101)	RH-12FH7035M-1D-SE1101	700	350	
	RH-12FH8535M-1D-SE1101	850		CR751-12HD-0-SE1101
	RH-12FH5545M-1D-SE1101	550		OR/31-12HD-0-3E1101
	RH-12FH7045M-1D-SE1101	700	450	
	RH-12FH8545M-1D-SE1101	850		
Food machinery grade H1 grease	RH-12FH5535M-1D-SE1102	550		
specifications (SE1102)	RH-12FH7035M-1D-SE1102	700	350	
	RH-12FH8535M-1D-SE1102	850		CR751-12HD-0-SE1102
	RH-12FH5545M-1D-SE1102	550		OR/31-12HD-0-3E1102
	RH-12FH7045M-1D-SE1102	700	450	
	RH-12FH8545M-1D-SE1102	850		
RH-20FH series		•		
Chemical-resistant specifications	RH-20FH8535M-1D-SE1101	850	350	
(SE1101)	RH-20FH10035M-1D-SE1101	1000	330	CR751-20HD-0-SE1101
	RH-20FH8545M-1D-SE1101	850	450	ON/31 ZUID-U-SEITUI
	RH-20FH10045M-1D-SE1101	1000	450	
Food machinery grade H1 grease	RH-20FH8535M-1D-SE1102	850	350	
specifications (SE1102)	RH-20FH10035M-1D-SE1102	1000		CD751_20UD_0_CE1102
	RH-20FH8545M-1D-SE1102	850		CR751-20HD-0-SE1102
	RH-20FH10045M-1D-SE1102	1000	400	

Note1) The controller is not chemical-resistant. For installing the controller, avoid places where adhesion of chemicals may occur.

1.3 CE marking specifications

The robot shown in the Table 1-4 or Table 1-5 are the CE Marking specification.

(1) CR750 controller

Table 1-4: Robot models with CE marking specifications

Robot type Note1)	Controller	External signal logic	Language setting	
RH-6FHxxyyM-D1-SE1501	CR750-06HD1-1-SE1501			
RH-6FHxxyyM-D1-SE1502	CR750-06HD1-1-SE1502	C	Frailink (FNO)	
RH-12FHxxyyM-D1-SE1501	CR750-12HD1-1-SE1501			
RH-12FHxxyyM-D1-SE1502	CR750-12HD1-1-SE1502	Source type	English (ENG)	
RH-20FHxxyyM-D1-SE1501	CR750-20HD1-1-SE1501			
RH-20FHxxyyM-D1-SE1502	CR750-20HD1-1-SE1502			

Note1) The "xx" indicate the arm length, "yy"indicate J3-axis stroke.

(2) CR751 controller

Table 1-5: Robot models with CE marking specifications

Robot type Note1)	Controller	External signal logic	Language setting	
RH-6FHxxyyM-1D1-SE1501	CR751-06HD1-0-SE1501			
RH-6FHxxyyM-1D1-SE1502	CR751-06HD1-0-SE1502		English (ENG)	
RH-12FHxxyyM-1D1-SE1501	CR751-12HD1-0-SE1501	Source type		
RH-12FHxxyyM-1D1-SE1502	CR751-12HD1-0-SE1502	Source type	English (ENG)	
RH-20FHxxyyM-1D1-SE1501	CR751-20HD1-0-SE1501			
RH-20FHxxyyM-1D1-SE1502	CR751-20HD1-0-SE1502			

Note1) The "xx" indicate the arm length, "yy"indicate J3-axis stroke.

1.4 Contents of the structural equipment

1.4.1 Robot arm

The list of structural equipment is shown in below.

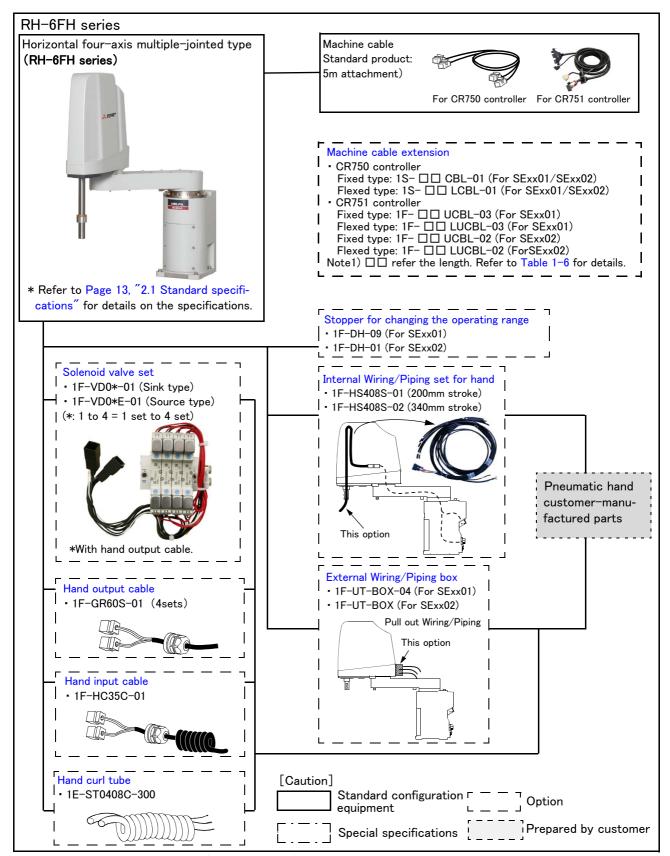


Fig.1-1: Structural equipment (RH-6FH series)

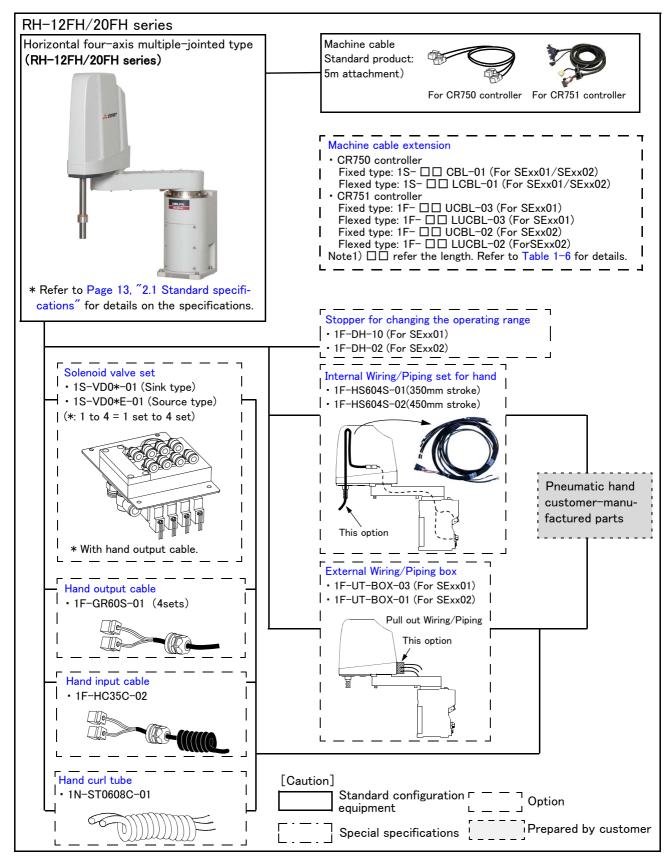


Fig.1-2: Structural equipment (RH-12FH/20FH series)

1.4.2 Controller

The devices shown below can be installed on the controller.

The controllers that can be connected differ depending on the specification of the robot. (Refer to Page 2, "1.2 Model type name of robot".)

(1) CR750controller

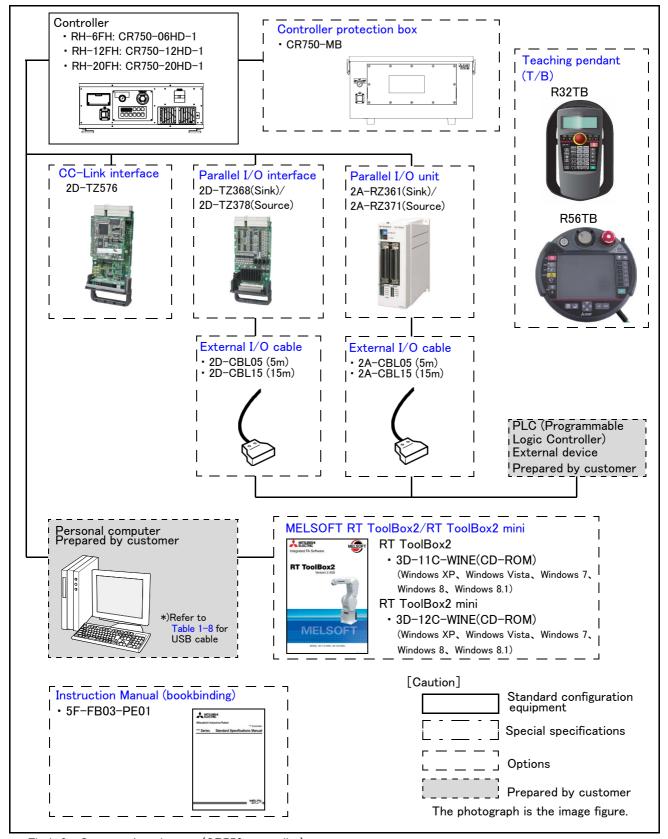


Fig.1-3: Structural equipment (CR750 controller)

(2) CR751 controller

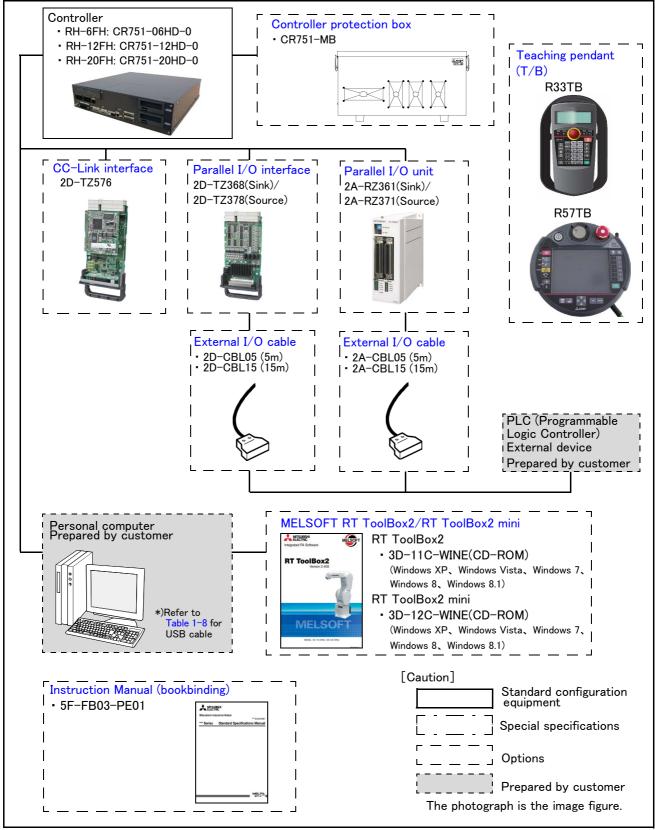


Fig.1-4: Structural equipment (CR751 controller)

1.5 Contents of the Option equipment and special specification

A list of all Optional equipment and special specifications are shown below.

Table 1-6 : The list of the robot arm option equipment and special specification

Item	Туре	Specifications	Classification Note1) CR750 CR751		Description		
Stopper for changing the operating range	1F-DH-09	The stopper parts for J1 axis	0	0	This must be installed by the customer. For SExx01 (Chemical-resistant specifications) of the RH-6FH series.		
	1F-DH-10	The stopper parts for J1 axis	0	0	This must be installed by the customer. For SExx01 (Chemical-resistant specifications) of the RH-12FH/20FH series.		
	1F-DH-01	The stopper parts for J1 axis	0	0	This must be installed by the customer. For SExx02 (Food machinery grade H1 grease specifications) of the RH-6FH series.		
	1F-DH-02	The stopper parts for J1 axis	0	0	This must be installed by the customer. For SExx02 (Food machinery grade H1 grease specifications) of the RH-12FH/20FH series.		
Extended machine cable (extension type)	1S- □□ CBL-01	For fixing (Set of power and signal) Extension type	0	-	" \(\sum \) " in type shows the length of the cables as follows.		
	1S- □□ LCBL-01	For flexing (Set of power and signal) Extension type	0	-	05=5m, 10=10m, 15=15m For SExx01 (Chemical-resistant specifications)/SExx02(Food machinery grade H1 grease specifications).		
Extended machine cable (direct type)	1F- □□ UCBL-03	For fixing (Set of power and signal) Extension type	-	0	" \(\sum \) " in type shows the length of the cables as follows.		
	1F- □□ LUCBL-03	For flexing (Set of power and signal) Extension type	-	0	10=10m, 15=15m, 20=20m For SExx01 (Chemical-resistant specifications).		
	1F- □□ UCBL-02	For fixing (Set of power and signal) Extension type	-	0	" □□ " in type shows the length of the cables as follows. 10=10m, 15=15m, 20=20m		
	1F- □□ LUCBL-02	For flexing (Set of power and signal) Extension type	-	0	For SExx02 (Food machinery grade H1 grease specifications).		
Solenoid valve set	1F-VD01-01/VD01E-01	1 set (Sink type)/(Source type)	0	0	The solenoid-valve set for the hand of		
	1F-VD02-01/VD02E-01	2 set (Sink type)/(Source type)	0	0	the customer setup. For RH-6FH series.		
	1F-VD03-01/VD03E-01	3 set (Sink type)/(Source type)	0	0			
	1F-VD04-01/VD04E-01	4 set (Sink type)/(Source type)	0	0	1		
	1S-VD01-01/VD01E-01	1 set (Sink type)/(Source type)	0	0	The solenoid-valve set for the hand of		
	1S-VD02-01/VD02E-01	2 set (Sink type)/(Source type)	0	0	the customer setup. For RH-12FH/20FH series.		
	1S-VD03-01/VD03E-01	3 set (Sink type)/(Source type)	0	0			
	1S-VD04-01/VD04E-01	4 set (Sink type)/(Source type)	0	0			
Hand input cable	1F-HC35C-01	Robot side: connector. Hand side: wire.	0	0	The cable is connected to the sensor by the customer. Attaches the cable clamp (drip proof type) For RH-6FH series		
	1F-HC35C-02	Robot side: connector. Hand side: wire.	0	0	The cable is connected to the sensor by the customer. Attaches the cable clamp (drip proof type) For RH-12FH/20FH series		
Hand output cable	1F-GR60S-01	Robot side: connector. Hand side: wire	0	0	This cable can be used for the solenoid valve prepared by the customer.		
Hand curl tube	1E-ST0408C-300	For solenoid valve 4set.:Φ4x8	0	0	Curl type air tube For RH-6FH series		
	1N-ST0608C-01	For solenoid valve 4set.:Φ6x8	0	0	Curl type air tube For RH-12FH/20FH series		

Item	Туре	Specifications	Classification Note1) CR750 CR751		Description
External Wiring/Piping box	1F-UT-BOX-04	For solenoid valve 4set.:Φ4x8		0	Box which pulls out the Wire/Piping (Hand I/O cable, Hand curl tube) For SExx01 (Chemical-resistant specifications) of the RH-6FH series.
	1F-UT-BOX-03	For solenoid valve 4set.:Φ6x8	0		Box which pulls out the Wire/Piping (Hand I/O cable, Hand curl tube) For SExx01 (Chemical-resistant specifications) of the RH-12FH/20FH series.
	0 0		Box which pulls out the Wire/Piping (Hand I/O cable, Hand curl tube) For SExx02 (Food machinery grade H1 grease specifications) of the RH-6FH series.		
	1F-UT-BOX-01	For solenoid valve 4set.:Φ6x8	0		Box which pulls out the Wire/Piping (Hand I/O cable, Hand curl tube) For SExx02 (Food machinery grade H1 grease specifications) of the RH-12FH/20FH series.
Internal Wiring/Piping set for hand	1F-HS408S-01	Hand input cable (eight signal lines and two power lines), ϕ 4 eight hoses	0	0	Wiring/Piping to pass in the shaft For RH-6FH series (200mm stroke)
	1F-HS408S-02	Hand input cable (eight signal lines and two power lines), ϕ 4 eight hoses	0	0	Wiring/Piping to pass in the shaft For RH-6FH series (340mm stroke)
	1F-HS604S-01	Hand input cable (eight signal lines and two power lines), ϕ 6 four hoses	0		Wiring/Piping to pass in the shaft For RH-12FH/20FH series (350mm stroke)
	1F-HS604S-02	Hand input cable (eight signal lines and two power lines), ϕ 6 four hoses	0	0	Wiring/Piping to pass in the shaft For RH-12FH/20FH series (450mm stroke)

Note1) O: option, \square : special specifications.

Table 1-7: The list of the controller option equipment and special specification

Item	Туре	Specifications	Classif Not CR750	:e1)	Description	
Simple teaching pendant	R32TB	Cable length 7m	0	-	With 3-position enable switch	
	R32TB-15	Cable length 15m	0	-	IP65	
	R33TB	Cable length 7m	_	0		
	R33TB-15	Cable length 15m	_	0		
Highly efficient teaching	R56TB	Cable length 7m	0	-		
pendant	R56TB-15	Cable length 15m	0	-		
	R57TB	Cable length 7m	_	0		
	R57TB-15	Cable length 15m	-	0		
Parallel I/O Interface	2D-TZ378(Source type)	DO: 32 point DI: 32 point Insulated type output signal (0.1A/24V /point) Insulated type input signal (9mA/ 24V /point)	0	0	The card type external input-and-output. Interface. Install to the slot of controller.	
External I/O cable	2D-CBL05	5m	0	0	Use to connect the external peripheral	
(For Parallel I/O Interface)	2D-CBL15	15m	0	0	device to the parallel input/output interface.	
Parallel I/O Unit	2A-RZ371(Source type)	DO: 32 point/ DI: 32 point Insulated type output signal (0.1A/24V /point) Insulated type input signal (7mA/ 24V /point)	0	0	The unit for expansion the external input/output. Electrical isolated Type (100mA/Point)	
External I/O cable (For Parallel I/O Unit)	2A-CBL05	5m	0	0	Use to connect the external peripheral	
(For Parallel I/O Unit)	2A-CBL15	15m	0	0	device to the parallel input/output unit	
CC-Link interface	2D-TZ576	Only Intelligent device station, Local station	0	0	For MELSEC PLC with CC-Link connection.	
Controller protection box	CR750-MB	IP54	0	-	The controller protection box is used to	
	CR751-MB		- 0		protect the controller from an oil mist of other operating environment.	
RT ToolBox2 (Personal computer Support software)	3D-11C-WINE	CD-ROM	0	0	Windows XP、Windows Vista、Windows 7、Windows 8、Windows 8.1 (With the simulation function)	

Item	Туре	Specifications	Classification Note1)		Description	
			CR750	CR751		
RT ToolBox2 mini (Personal computer Sup- port software mini)	3D-12C-WINE	CD-ROM	0		Windows XP、Windows Vista、Windows 7、Windows 8、Windows 8.1	
Instruction Manual		RH-6FH/12FH/20FH-D series multiple-resistant specification	0	0		

Note1) O : option, \square : special specifications.

[Reference]: The recommendation products of the USB cable are shown below

Table 1-8: Recommendation article of the USB cable

Name	Type name	Supplier
USB cable	KU-AMB530	SANWA SUPPLY INC.
(USB A type-USB mini B type)	USB-M53	ELECOM CO., LTD.
	GT09-C30USB-5P	MITSUBISHI ELECTRIC SYSTEM & SERVICE CO., LTD.
	MR-J3USBCBL3M	MITSUBISHI ELECTRIC CO., LTD.
USB adapter (USB B type-USB mini B type)	AD-USBBFTM5M	ELECOM CO., LTD.



Caution Be careful to the USB cable to apply neither the static electricity nor the noise. Otherwise, it becomes the cause of malfunction.



Caution Use the network equipments (personal computer, USB hub, LAN hub, etc) confirmed by manufacturer. The thing unsuitable for the FA environment (related with conformity, temperature or noise) exists in the equipments connected to USB. When using network equipment, measures against the noise, such as measures against EMI and the addition of the ferrite core, may be necessary. Please fully confirm the operation by customer. Guarantee and maintenance of the equipment on the market (usual office automation equipment) cannot be performed.

2 Robot arm

2.1 Standard specifications

2.1.1 Basic specifications

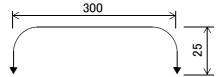
(1) RH-6FH series

Table 2-1: Standard specifications of robot arm

Table 2-1 : Standa	rd specific	ations c	of robot arm					
Item		Unit	Specifications					
Type ^{Note1)}			RH-6FH3520M/3534M-SExx01 RH-6FH3520M/3534M-SExx02	RH-6FH4520M/4534M-SExx01 RH-6FH4520M/4534M-SExx02	RH-6FH5520M/5534M-SExx01 RH-6FH5520M/5534M-SExx02			
Environment			SExx01: Chemical-resistant specifications SExx02: Food machinery grade H1 grease specifications					
Installation posture			On floor					
Degree of freedom				4				
Structure				Horizontal, multiple-joint type				
Drive system				AC servo motor				
Position detection method	od			Absolute encoder				
Motor capacity	J1	W		750				
	J2	W		400				
	J3 (Z)	W		200				
	J4 (<i>θ</i> axis)	W		100				
Brake				J1, J2, J4: no brake, J3: with brake				
Arm length	No. 1 arm	mm	125	225	325			
	No. 2 arm	mm		225				
Max.reach radius(No. 1+	No. 2)	mm	350	450	550			
Operating range	J1	deg		±170				
	J2	deg		±145				
	J3 (Z)	mm	RH-6FH**20M-SE**: 200 (+133 to +333) RH-6FH**34M-SE**: 340 (-43 to +297)					
	J4 (<i>θ</i> axis)	deg	±360					
Speed of motion Note2)	J1	deg/s	400					
Speed of Motion	J2	deg/s	670					
	J3 (Z)	mm/s		2,400				
	J4 (θ axis)	deg/s	2,500					
Maximum horizontal com		mm/s	6,900 7,600 8,300					
Cycle time Note4)		sec		0.29				
Oycle time	Rating		3					
Load	Maximum	kg (N)	6					
Z axis pressing force	Maximum	N		165				
Note5)	Waxiiiuiii	IV	100					
Allowable inertia	Rating	kg·m²		0.01				
	Maximum	Ng III		0.12				
Pose repeatability Note6)	X-Y direction	mm	±0.010	±0.010	±0.012			
	J3 (Z)	mm		±0.010				
	J4 (<i>θ</i> axis)	deg		±0.004				
Ambient temperature No	te7)	°C	0 to 40					
Mass		k	3	36	37			
Tool wiring			 Input 8 points/Output 8 points, (total 20 cores) Dedicated signal cable for multifunctional hand (Two cores + Power cable two cores) Ethernet cable one cable (100BASE-TX, eight cores) Note8) 					
Tool pneumatic pipes			Primary: ϕ 6 x two hoses, Secondary: ϕ 4 x eight hoses Note9)					
Supply pressure		MPa		$0.5 \pm 10\%$				
Protection specification	Note10) Note11)		Chemical-resistant specifications (SExx01)/Food machinery grade H1 grease specifications (SExx02): IP65 Note12)					
Painting color			Chemical-resistant specifications (SExx01): Gray (Coating agent's color) Food machinery grade H1 grease specifications (SExx02): Light gray (Equivalent to Munsell: 0.6B7.6/0.2)					

Note1) Chemical-resistant specifications (SExx01) and food machinery grade H1 grease specifications (SExx02) are listed together. SExx01 at the end of the model indicates chemical-resistant specifications, and SExx02 indicates H1 grease specifications. The type in which operating range of J3 axis (Z) is 200mm and 340mm are shown together.

- Note3) At the maximum speed on the X-Y flat surface in the robot's control point, it is obtained with each speed of J1, J2, and J4. The control point is the position offset by the rated inertia from the flange.
- Note4) The value of the following movement which applied MvTune2 (high-speed movement mode) with the carrying mass of
 - · The cycle time may increase with the case where the positioning accuracy of the work etc. is necessary, or by the moving position.



- Note5) This is the downwards pressing force that occurs at the end of the load when the maximum load is on board and the J1, J2 and J4 axis are in their resting state. Please operate at this level or below. When pressing for long periods of time, an excess load error may occur. Please operate in a manner that does not cause errors.
- Note6) The pose repeatability details are given in Page 19, "2.2.1 Pose repeatability".
- Note7) Sets the robot's operating environmental temperature as parameter OLTMX. Corresponding to the environment, the continuous control action performance and the overload-protection function are optimized. (Refers to "Optimizing the overload level" described in "Chapter 5 Functions set with parameters" of separate instruction manual/ Detailed explanations of functions and operations for details.)
- Note8) The 8-wire cable designated for LAN wiring can also be used for backup wiring.
- Note9) The ϕ 4 secondary piping can be obtained with the electromagnetic valve (option). Details regarding the electromagnetic netic valve (optional) are shown on Page 69, "(3) Solenoid valve set".
- Note10) The protection specification details are given in Page 28, "2.2.7 Protection specifications".
- Note11) The controller is not chemical-resistant. For installing the controller, avoid places where adhesion of chemicals may occur.
- Note12) Direct jet flow to the bellows section is not included.

(2) RH-12FH series

Table 2-2: Standard specifications of robot arm

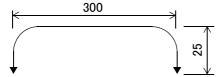
Item		Unit	Specifications				
Type ^{Note1)}			RH-12FH5535M/5545M-SExx01 RH-12FH5535M/5545M-SExx02	RH-12FH7035M/7045M-SExx01 RH-12FH7035M/7045M-SExx02	RH-12FH8535M/8545M-SExx01 RH-12FH8535M/8545M-SExx02		
Environment			SExx01: Chemical-resistant specifications SExx02: Food machinery grade H1 grease specifications				
Installation posture				On floor			
Degree of freedom				4			
Structure				Horizontal, multiple-joint type			
Drive system				AC servo motor			
Position detection metho	od			Absolute encoder			
Motor capacity	J1	W		750			
	J2	W		750			
	J3 (Z)	W		400			
	J4 (<i>θ</i> axis)	W		200			
Brake	II.			J1, J2, J4: no brake, J3: with brake	•		
Arm length	No. 1 arm	mm	225	375	525		
-	No. 2 arm	mm		325	1		
Max.reach radius(No. 1+ I	1	mm	550	700	850		
Operating range	J1	deg	333	±170	000		
Operating range	J2	deg	+		±153		
	J3 (Z)	mm	±145 ±153 RH-12FH**35M: 350 (-10 ~ +340) RH-12FH**45M: 450 (-110 ~ +340)				
	J4 (θ axis)	deg					
Speed of motion Note2)	J1	deg/s	4	280			
opoda or modern	J2	deg/s	450				
	J3 (Z)	mm/s	2,800				
	J4 (θ axis)	deg/s	2,400				
Maximum horizontal com Note3)		mm/s	11,435	11,350			
Cycle time Note4)		sec		0.30			
•	Rating		3				
Load	Maximum	kg (N)	12				
Z axis pressing force Note5)	Maximum	N	200				
Allowable	Rating		0.025				
inertia	Maximum	kg·m ²		0.3			
Pose repeatability Note6)	X-Y direction	mm	±0.012		0.015		
	J3 (Z)	mm		±0.010			
	J4 (θ axis)	deg		±0.005			
Ambient temperature Not	l .	°C		0 to 40			
Mass		kg	65	67	69		
Tool wiring			Input 8 points/Output 8 points, (total 20 cores) Dedicated signal cable for multifunctional hand (Two cores + Power cable two cores) Ethernet cable one cable (100BASE-TX, eight cores) Note8)				
Tool pneumatic pipes		Primary: φ6 x two hoses, Secondary: φ6 x eight hoses Note9)					
Supply pressure MPa		MPa	0.5±10%				
Protection specification Note10 Note11)		Chemical-resistant specifications (SExx01)/Food machinery grade H1 grease specifications (SExx02): IP65 Note12)					
Painting color			Chemical-resistant specifications (SExx01): Gray (Coating agent's color) Food machinery grade H1 grease specifications (SExx02): Light gray (Equivalent to Munsell: 0.6B7.6/0.2)				

Note1) Chemical-resistant specifications (SExx01) and food machinery grade H1 grease specifications (SExx02) are listed together. SExx01 at the end of the model indicates chemical-resistant specifications, and SExx02 indicates H1 grease specifications. The type in which operating range of J3 axis (Z) is 350mm and 450mm are shown together.

Note2) The maximum speed is the value which applied MvTune2 (high-speed movement mode).

Note3) At the maximum speed on the X-Y flat surface in the robot's control point, it is obtained with each speed of J1, J2, and J4. The control point is the position offset by the rated inertia from the flange.

- Note4) The value of the following movement which applied MvTune2 (high-speed movement mode) with the carrying mass of
 - · The cycle time may increase with the case where the positioning accuracy of the work etc. is necessary, or by the moving position.



- Note5) This is the downwards pressing force that occurs at the end of the load when the maximum load is on board and the J1, J2 and J4 axis are in their resting state. Please operate at this level or below. When pressing for long periods of time, an excess load error may occur. Please operate in a manner that does not cause errors.
- Note6) The pose repeatability details are given in Page 19, "2.2.1 Pose repeatability".
- Note7) Sets the robot's operating environmental temperature as parameter OLTMX. Corresponding to the environment, the continuous control action performance and the overload-protection function are optimized. (Refers to "Optimizing the overload level" described in "Chapter 5 Functions set with parameters" of separate instruction manual/ Detailed explanations of functions and operations for details.)
- Note8) The 8-wire cable designated for LAN wiring can also be used for backup wiring.
- Note9) The ϕ 6 secondary piping can be obtained with the electromagnetic valve (option). Details regarding the electromagnetic valve (option). netic valve (optional) are shown on Page 69, "(3) Solenoid valve set".
- Note10) The protection specification details are given in Page 28, "2.2.7 Protection specifications".
- Note11) The controller is not chemical-resistant. For installing the controller, avoid places where adhesion of chemicals may occur.
- Note12) Direct jet flow to the bellows section is not included.

(3) RH-20FH series

Table 2-3: Standard specifications of robot arm

Item		Unit	Specifications					
Type ^{Note1)}			RH-20FH8535M/8545M-SExx01 RH-20FH8535M/8545M-SExx02	RH-20FH10035M/10045M-SExx01 RH-20FH10035M/10045M-SExx02				
Environment			SExx01: Chemical-resistant specifications SExx02: Food machinery grade H1 grease specifications					
Installation posture			On floor					
Degree of freedom			4	4				
Structure			Horizontal, mult	tiple-joint type				
Drive system			AC serve	o motor				
Position detection method	od		Absolute	encoder				
Motor capacity	J1	W	75	0				
	J2	W	75	0				
	J3 (Z)	W	40	0				
	J4 (<i>θ</i> axis)	W	20	0				
Brake			J1, J2, J4: no brak	ke, J3: with brake				
Arm length	No. 1 arm	mm	52	5				
	No. 2 arm	mm	325	475				
Max.reach radius(No. 1+ I	No. 2)	mm	850	1,000				
Operating range	J1	deg	±1	70				
	J2	deg	±1	53				
	J3 (Z)	mm	RH-20FH**35M: 350 (-10 ~ +340) RH-20FH**45M: 450 (-110 ~ +340)					
	J4 (<i>θ</i> axis)	deg	±360					
Speed of motion Note2)	J1	deg/s	280					
	J2	deg/s	450					
	J3 (Z)	mm/s	2,400					
	J4 (<i>θ</i> axis)	deg/s	1,700					
Maximum horizontal com Note3)	posite speed	mm/s	11,372	13,283				
Cycle time Note4)		sec	0.30	0.36				
Land	Rating	kg	5					
Load	Maximum	(N)	20					
Z axis pressing force Note5)	Maximum	N	230					
Allowable	Rating	kg·m²	0.00					
inertia	Maximum	Kg · m	1.05 ^N	Note6)				
Pose repeatability Note7)	X-Y direction	mm	±0.015	±0.020				
	J3 (Z)	mm	±0.0	010				
	J4 (<i>θ</i> axis)	deg	±0.0	005				
Ambient temperature Not	:e8)	°C	0 to	40				
Mass		kg	75	77				
Tool wiring			 Input 8 points/Output 8 points, (total 20 cores) Dedicated signal cable for multifunctional hand (Two cores + Power cable two cores) Ethernet cable one cable (100BASE-TX, eight cores) Note9) 					
Tool pneumatic pipes			Primary: ϕ 6 x two hoses, Secondary: ϕ 6 x eight hoses Note10)					
Supply pressure		MPa	0.5±10%					
Protection specification ^I	Note11) Note12)		Chemical-resistant specifications (SExx01)/Food machinery grade H1 grease specifications (SExx02): IP65 Note13)					
Painting color			Chemical-resistant specifications (SExx01): Gray (Co Food machinery grade H1 grease specifications (SExx	pating agent's color) x02): Light gray (Equivalent to Munsell: 0.6B7.6/0.2				

Note1) Chemical-resistant specifications (SExx01) and food machinery grade H1 grease specifications (SExx02) are listed together. SExx01 at the end of the model indicates chemical-resistant specifications, and SExx02 indicates H1 grease specifications. The type in which operating range of J3 axis (Z) is 350mm and 450mm are shown together.

Note3) At the maximum speed on the X-Y flat surface in the robot's control point, it is obtained with each speed of J1, J2, and J4. The control point is the position offset by the rated inertia from the flange.

Note2) The maximum speed is the value which applied MvTune2 (high-speed movement mode).

- Note4) The value of the following movement which applied MvTune2 (high-speed movement mode) with the carrying mass of
 - · The cycle time may increase with the case where the positioning accuracy of the work etc. is necessary, or by the moving position.



- Note5) This is the downwards pressing force that occurs at the end of the load when the maximum load is on board and the J1, J2 and J4 axis are in their resting state. Please operate at this level or below. When pressing for long periods of time, an excess load error may occur. Please operate in a manner that does not cause errors.
- Note6) When offset hand is used, the adjustment of moving speed and acceleration/deceleration speeds may be the Required. Refers to it, because the details is shown in Page 20, "2.2.2 Mass capacity".
- Note7) The pose repeatability details are given in Page 19, "2.2.1 Pose repeatability".
- Note8) Sets the robot's operating environmental temperature as parameter OLTMX. Corresponding to the environment, the continuous control action performance and the overload-protection function are optimized. (Refers to "Optimizing the overload level" described in "Chapter 5 Functions set with parameters" of separate instruction manual/ Detailed explanations of functions and operations for details.)
- Note9) The 8-wire cable designated for LAN wiring can also be used for backup wiring.
- Note 10) The ϕ 6 secondary piping can be obtained with the electromagnetic valve (option). Details regarding the electromagnetic valve (option). netic valve (optional) are shown on Page 69, "(3) Solenoid valve set".
- Note11) The protection specification details are given in Page 28, "2.2.7 Protection specifications".
- Note12) The controller is not chemical-resistant. For installing the controller, avoid places where adhesion of chemicals may occur.
- Note13) Direct jet flow to the bellows section is not included.

2.1.2 The counter-force applied to the installation surface

The counter-force applied to the installation surface for the strength design of the robot installation surface is shown.

Table 2-4: Value of each counter-force

Item	Unit	Value
RH-6FH series		
Falls moment: M _L	N•m	1,640
Torsion moment: M _T	N•m	710
Horizontal translation force: F _H	N	1,653
Vertical translation force: F _V	N	2,318
RH-12FH/20FH series		
Falls moment: M _L	N•m	3,190
Torsion moment: M _T	N•m	1,840
Horizontal translation force: F _H	N	2,240
Vertical translation force: F _V	N	2,500

2.2 Definition of specifications

The accuracy of pose repeatability mentioned in catalogs and in the specification manual is defined as follows.

2.2.1 Pose repeatability

For this robot, the pose repeatability is given in accordance with JIS B 8432 (Pose repeatability). Note that the value is based on 100 measurements (although 30 measurements are required according to JIS).

[Caution] The specified "pose repeatability" is not guaranteed to be satisfied under the following conditions.

- [1] Operation pattern factors
 - 1) When an operation that approaches from different directions and orientations are included in relation to the teaching position during repeated operations
 - 2) When the speed at teaching and the speed at execution are different
- [2] Load fluctuation factor
 - 1) When work is present/absent in repeated operations
- [3] Disturbance factor during operation
 - 1) Even if approaching from the same direction and orientation to the teaching position, when the power is turned OFF or a stop operation is performed halfway
- [4] Temperature factors
 - 1) When the operating environment temperature changes
 - 2) When accuracy is required before and after a warm-up operation
- [5] Factors due to differences in accuracy definition
 - 1) When accuracy is required between a position set by a numeric value in the robot's internal coordinate system and a position within the actual space
 - 2) When accuracy is required between a position generated by the pallet function and a position within the actual space

2.2.2 Mass capacity

The robot's mass capacity is expressed solely in terms of mass, but even for tools and works of similar mass, eccentric loads will have some restrictions When designing the tooling or when selecting a robot, consider the following issues.

- (1) The tooling should have the value less or equal than the smaller of the allowable moment of inertia found in Page 13, "2.1.1 Basic specifications".
- (2) Fig. 2-1 to Fig. 2-3 shows the distribution dimensions for the center of gravity in the case where the volume of the load is relatively small. Use this figure as a reference when designing the tooling. Please use the robot in the allowable moment of inertia of maximum moment of inertia shown in Fig. 2-1 to Fig. 2-3.
- [Caution] The mass capacity is greatly influenced by the operating speed of the robot and the motion posture. Even if you are within the allowable range mentioned previously, a vibration, an overload or generate an overcurrnt alarm could occur. In such cases, please reduce acceleration and deceleration (Accel command) speeds and movement speed (Ovrd command). Although the standard value to reduce is 50% for each command, please adjust corresponding to the movement posture. Refer to separate "Instruction Manual/Detailed Explanation of Functions and Operations" for details of each command.

Moreover, if hand/workpiece parameters are not set exactly, the similar phenomenon will be easier to occur.

[Caution] Refer to Page 22, "2.2.3 Relationships Among Mass Capacity, Speed, and Acceleration/Deceleration Speed", and set the values of the mass, magnitude, and distance to the centroid of a tool and a workpiece to parameters.

If parameters are not set exactly, the lifetime of reduction gears, a belt, etc. is affected.

[Caution] The overhang amount of the load, such as the mass capacity and the allowable moment of inertia defined in this section, are dynamic limit values determined by the capacity of the motor that drives axes or the capacity of the speed reducer. Therefore, it does not guarantee the accuracy on all areas of tooling. Guaranteed accuracy is measured from the center point of the mechanical interface surface. Please note that if the point of operation is kept away from the mechanical interface surface by long and low-rigid tooling, the positioning accuracy may deteriorate or may cause vibration.

Note that the allowable offset value (Z direction) from the lower edge of the shaft to the position of center of gravity is 100 mm.

[Caution] Even within the allowable range previously mentioned, an overload alarm may be generated if an ascending operation continues at a micro-low speed. In such a case, it is necessary to increase the ascending speed.

[Caution] This robot will restrict speed automatically by internal controls when the load center-of-gravity position separates from the shaft center. Refer to Page 22, "2.2.3 Relationships Among Mass Capacity, Speed, and Acceleration/Deceleration Speed" in detail.

The allowance distance (allowance offset amount) from the center of the shaft to the gravity center of loading weight are shown below.

RH-6FH: less than 140mm, RH-12FH: less than 240mm, RH-20FH: less than 320mm.

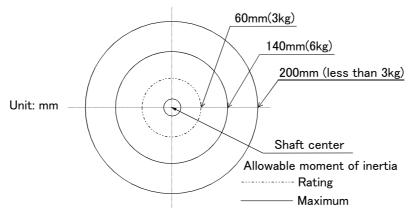


Fig.2-1: Position of center of gravity for loads (for loads with comparatively small volume): RH-6FH series

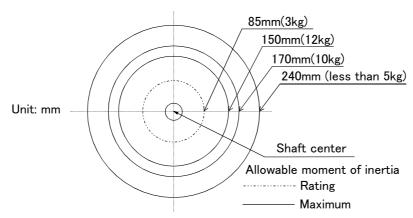


Fig.2-2: Position of center of gravity for loads (for loads with comparatively small volume): RH-12FH series

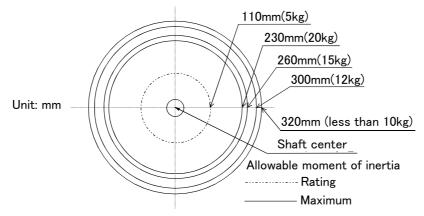


Fig.2-3: Position of center of gravity for loads (for loads with comparatively small volume): RH-20FH series

2.2.3 Relationships Among Mass Capacity, Speed, and Acceleration/Deceleration Speed

This robot automatically sets the optimum acceleration and deceleration speeds and maximum speed, according to the load capacity and size that have been set, and operates using these automatically set speeds.

To achieve that, it is necessary to correctly set the actual load data (mass and size of hand and work) to be used. However, vibration, overheating and errors such as excessive margin of error and overload may occur, depending on the robot operation pattern or ambient temperature.

In this case, reduce the speed and the acceleration and deceleration rate before continuing to use. This is done by accessing the robot program and adjusting the speed settings (Ovrd) and the acceleration and deceleration settings (Accel).

If a setting is performed in such a way that it falls below the mounted load, the life span of the mechanism elements used in the robot may be shortened. In the case of a work requiring a high degree of accuracy, set up the load correctly and use the robot by lowering the ratios of the acceleration and deceleration speeds.

(1) Setting Load Capacity and Size (Hand Conditions)

Set up the capacity and size of the hand with the "HNDDAT*" parameter (optimum acceleration/deceleration setting parameter), and set up the capacity and size of the work with the "WRKDAT*" parameter. Numbers 0 to 8 can be used for the asterisk (*) part. Designate the "HNDDAT*" and "WRKDAT*" parameters to be used using the "LoadSet" command in a program.

For more details, refer to the separate "Instruction Manual/Detailed Explanation of Functions and Operations." It is the same meaning as "LoadSet 0.0" if not using the "LoadSet".

<Factory default settings>

		Hand mass kg	size X mm	size Y mm	size Z mm	center-of-gravity position X mm	center-of-gravity position Y mm	center-of-gravity position Z mm
R	H-6FH serie:	S						
	HNDDAT*	6.0	99.0	99.0	76.0	0.0	0.0	38.0
	WRKDAT*	0.0	0.0	0.0	0.0	0.0	0.0	0.0
R	H-12FH serie	es						
	HNDDAT*	12.0	165.0	165.0	64.0	0.0	0.0	16.0
	WRKDAT*	0.0	0.0	0.0	0.0	0.0	0.0	0.0
R	H-20FH serie	es						
	HNDDAT*	20.0	165.0	165.0	109.0	0.0	0.0	37.0
	WRKDAT*	0.0	0.0	0.0	0.0	0.0	0.0	0.0

Note) The position of the center of gravity is located at the center of the surface at the bottom of the shaft. Set the X, Y and Z center of gravity positions for the tool coordinate directions (the Z center of gravity position will be a plus for downward directions).

2.2.4 Vibrations at the Tip of the Arm during Low-Speed Operation of the Robot

Vibrations at the tip of the arm may increase substantially during the low-speed operation of the robot, depending on the combination of robot operation, hand mass and hand inertia. This problem occurs when the vibration count specific to the robot arm and the vibration count of the arm driving force are coming close to each other. These vibrations at the tip of the arm can be reduced by taking the following measures:

- 1) Change the robot's operating speed by using the Ovrd command.
- 2) Change and move the teaching points of the robot.
- 3) Change the hand mass and hand inertia.

2.2.5 Vibration of shaft (J3 axis) position and arm end

Vibrations at the tip of the arm may increase substantially during operation under the shaft position near the low end or the high end of the robot, depending on the combination of hand mass and hand inertia. This problem occurs according to that inertia, because the distance from the shaft support section to the shaft end becomes long. When this vibration affects the robot's operations, please change operating speed etc. like the above Page 22, "2.2.4 Vibrations at the Tip of the Arm during Low-Speed Operation of the Robot".

(1) Relationship Between Mass Capacity and Speed

A function to optimize the maximum speed of each axis according to the setting value of the load capacity will be activated (Refer to Fig. 2-4).

However, this function does not work with the following load mass:

RH-6FH/12FH series: 3kg or less RH-20FH series: 5kg or less

When the setting of the load mass is changed to following, the maximum speed is compensated according to the load mass:

RH-6FH/12FH series: 3kg or heavier RH-20FH series: 5kg or heavier

[CAUTION] Depending on the operation pattern, the speed and/or acceleration/deceleration at the front edge may not be parallel with the speed and the rate of change of acceleration/deceleration specified in a program.

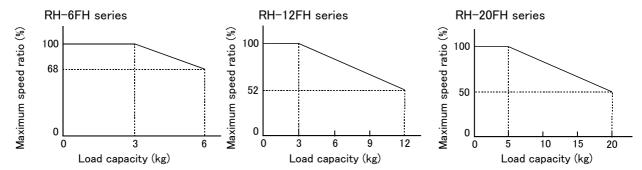


Fig.2-4: Automatic compensation of speed

(2) Relationship Between Height of Shaft (J3 Axis) and Acceleration/Deceleration Speed

A function to optimize the acceleration/deceleration speed according to the height of the shaft (Refer to Fig. 2-5, Fig. 2-6) will be activated. This function is invalid if the shaft (axis J3) operates at a position above P3 in Fig. 2-5. Acceleration/deceleration is compensated for at a position below P3 in Fig. 2-5 if the position of the center of gravity of the load is located at the front edge of the shaft.

This function contains both a standard acceleration and deceleration pattern and a high acceleration and deceleration pattern, both of which can be selected in the parameters. The original settings are set to the standard acceleration and deceleration pattern, which enables operation while keeping vibration at the shaft tip (including residual vibration) to a minimum. Users are also able to select the high acceleration and deceleration pattern and operate the robot at high speed. When doing so, users should make sure that additional vibration will not have a negative impact on work carried out by the robot. Where necessary the pattern should be changed, allowing the robot to be used in the most effective way.

The relevant parameter names and their set values are shown below. For more details about parameters and how to change them, please refer to the separate "Instruction Manual/Detailed Explanation of Functions and Operations".

Parameter name......MAPMODE (acceleration and deceleration optimization pattern selected)
Set value and function......0: Standard acceleration and deceleration pattern (original setting)

1: High acceleration and deceleration pattern

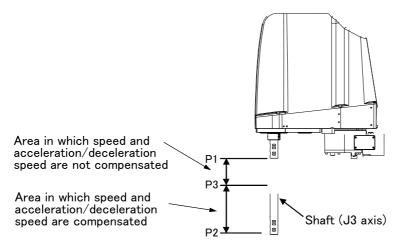


Fig.2-5: Area in which acceleration/deceleration speed is compensated

Table 2-5: Area in which acceleration/deceleration speed is compensated

Type	J3 axis stroke (mm)			Compensation area
Туре	Stroke length	P1(Upper end)	P2(Lower end)	(P2 to P3)
RH-6FH series Note1)	340	333	-7	−7 to 133
RH-12FH/20FH series	350	340	-10	-10 to 240
	450	340	-110	-110 to 155

Note1) When stroke of J3 axis is 200mm this function is not operate.

RH-6FH series <u>J3 axis (Z) stroke 340mm</u> (Standard Acceleration/deceleration speed) J3 axis (Z) stroke 340mm (High acceleration and deceleration rate) Acceleration/deceleration speed ratio(%) Acceleration/deceleration speed ratio(%) 100 50 50 34 0 - 333 0 133 73 -7 133 73 -7 [′]333 Shaft position (mm) Shaft position (mm) RH-12FH series J3 axis (Z) stroke 350/450mm J3 axis (Z) stroke 350/450mm (Standard Acceleration/deceleration speed) (Standard Acceleration/deceleration speed) Acceleration/deceleration speed ratio(%) Acceleration/decelera-65 61 58 tion speed ratio(%) 65 38 20 0 40 0 240 140 -110 -10 240 140 -110 Shaft position (mm) Shaft position (mm) RH-20FH series <u>J3 axis (Z) stroke 350/450mm</u> J3 axis (Z) stroke 350/450mm (Standard Acceleration/deceleration speed) (Standard Acceleration/deceleration speed) 100 Acceleration/deceleration speed ratio(%) 100 Acceleration/deceleration speed ratio(%) 50 41 30 50 37 20 0 <u>-</u> 340 0340 155 70 155 70 0 0

Fig.2-6: Automatic compensation of acceleration/deceleration speed

Shaft position (mm)

Shaft position (mm)

(3) Relation between offset length and the maximum speed

A function to optimize the maximum speed of each axis according to the offset length will be activated. (Refer to Fig. 2-7)

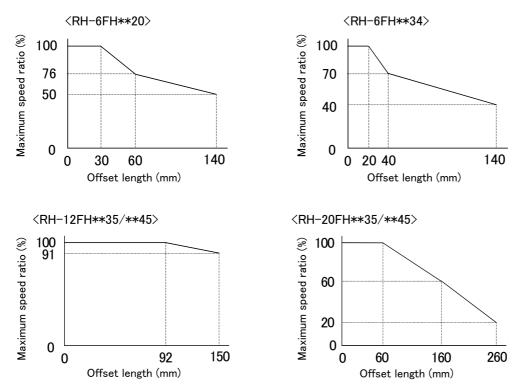


Fig.2-7: Relationship of the offset length and maximum velocity

[Supplementary explanation 1]: The setting which shortens execution time

The execution time can be improved by using the following methods.

- 1) Perform continuous path operation using the Cnt command.
- 2) Control the optimum acceleration/deceleration using the Oadl command.
- 3) Control the optimum speed using the Spd command.
- 4) Setting a larger value in the optimum acceleration/deceleration adjustment rate parameter: JADL. (Maximum 100)

The moving time can be shortened by setting a larger value in the optimum acceleration/deceleration adjustment rate parameter (JADL). In this robot, the acceleration/deceleration speed is initialized to allow continuous moving with a short wait time (setting of B in the Fig. 2-8).

This setting is suited for continuous operations that have a short tact time, such as palletizing work.

Conversely, if quick moves (short moving time) are required, such as L/UL work on machined parts, the acceleration/deceleration speed can be increased by initial setting (setting of A in the Fig. 2-8).

However, please note that some setting values of acceleration/deceleration speed tend to cause overload and overheat errors. In such a case, extend the wait time, reduce the acceleration/deceleration speed, or decrease the moving speed.

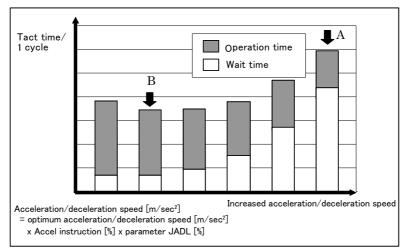


Fig.2-8: Relationship between Acceleration/deceleration Speed and Tact Time (Conceptual Drawing)

(4) Time to reach the position repeatability

When using this robot, the time to reach the position repeatability may be prolonged due to the effect of residual vibration at the time of stopping. If this happens, take the following measures:

- 1) Change the operation position of the Z axis to the location near the top as much as possible.
- 2) Increase the operation speed prior to stopping.
- 3) When positioning the work near the bottom edge of the Z axis, if no effectiveness is achieved in step "2)" above, perform operation ① (robot path: $O \to A \to C$). In the case of operation ② (robot path: $O \to B \to C$), residual vibration may occur. (Refer to Fig. 2-9.)

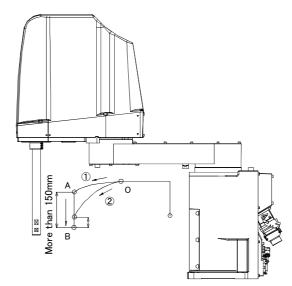


Fig.2-9: Recommended path when positioning at the bottom edge of the Z axis

2.2.6 Collision detection

This series have the "collision detection function" which detects the abnormalities by the collision of the robot arm, and the initial setting has set this function as the enable to suppress damage to the minimum.

Although the enable/disable of this function can be changed by parameter: COL and command: ColChk, you should use in valid condition of this function for protection of the robot and of the peripheral equipment.

The abnormalities are detected by the robot's kinetics model, presuming torque necessary for movement at any time. Therefore, the setting parameter (HNDDAT*, WRKDAT*) of the hand and the work piece conditions should be right. And, it may be detected as the collision in movement as speed and motor torque are changed rapidly. (for example, the movement near the place of the origin by linear interpolation, the reversal movement, the cold condition, the operation after long term stoppage)

In such a case, by adjusting the value of the setting parameter (COLLVL, COLLVLJG) of the collision detection level according to actual use environment, the sensitivity of collision detection can be optimized and the damage risk can be reduced further. And, in the operation after the low temperature or long term stoppage, please operate by accustoming at low speed (warm-up), or use the warm-up operation mode.

Refer to the separate instruction manual "Detailed explanations of functions and operations" for details of related parameter.

Table 2-6: Factory-shipments condition

	JOG operation	Automatic
RH-6FH/12FH/20FH series	Valid	Invalid

2.2.7 Protection specifications

(1) Types of protection specifications

The robot arm has protection specifications that comply with the IEC Standards. The protection specifications and applicable fields are shown in Table 2-7.

Table 2-7: Protection specifications and applicable fields

Туре	Protection specifications (IEC Standards value)	Classification	Applicable field
RH-6FHxx20M/xx34M-SExx01 RH-12FHxx35M/xx45M-SExx01 RH-20FHxx35M/xx45M-SExx01	Robot arm: IP65 (Direct jet flow to the bellows section is not included.)	Chemical-resistant specifications (SExx01)	Transportation and processing of medicine and food. Worksites that require chemical sterilization/ cleaning of the robot arm.
RH-6FHxx20M/xx34M-SExx02 RH-12FHxx35M/xx45M-SExx02 RH-20FHxx35M/xx45M-SExx02		Food machinery grade H1 grease specifications (SExx02)	Transportation and processing of food. Worksites that require cleaning of the robot arm by wiping.



CAUTION Do not use the controller in the sterilization/cleaning environment shown in Table 2-7. Avoid places where adhesion of chemicals may occur.

The IEC IP symbols define the degree of protection against solids and fluids, and do not indicate a protective structure against the entry of chemicals.

The IEC standard is described by the following "Information" The robots with food machinery grade H1 grease specifications (SExx02) may be corroded with rust due to liquids such as chemicals, water, or oil.

[Information]

• The IEC IP65

Protection against water infiltration as specified in IP65 indicates a protective structure that is not harmfully affected when 12.5 ± 5% liters of water is supplied from a test device at a position approx. 3m away in various directions and a water pressure of 30kPa at the nozzle section. The water is filled one minute per 1m2 of test device surface area for a total of three minutes.

(2) About using the robot in the sterilization environment

The multiple-resistant specification robot has protection methods that conform to IEC's IP65 standards. (Direct jet flow to the bellows section is not included.)

It has protection structure designed to prevent harmful effects caused by splashing water coming from various directions, as the robot is operating. (Direct jet flow to the bellows section is not included.)

Recommended usage conditions.

- 1) Robots with multiple-resistant specifications are supposed to be used in applications such as transportation/processing systems in pharmaceutical and food plants.
- 2) In our company, chemical resistance of the robots is confirmed by the sterilization environment test with hydrogen peroxide gas*1) (for chemical-resistant specifications (SExx01) only). The robot arm may be adversely affected when used in the sterilization environment other than the above, or in direct contact with water or other liquids in excess of the amount indicated in the protection specifications. If you have any specific requests for surface treatment, materials, etc., contact your dealer.
- 3) Take measures to protect the robot arm against the sterilization environment other than the above or direct contact with water, oil, or cut chips in excess of the amount indicated in the protection specifications.
- 4) The packing gets deteriorated with the passage of time and must be replaced as required. Replace the packing while removing/installing the cover. Failure to replace the packing permits chemicals, water or oil to enter the interior of the robot, possibly causing it to become inoperable. Packing required and liquid gasket used therewith are available from dealer.

Although the robot with food machinery grade H1 grease specifications (SExx02) may become rusty from water splashes, the operating performance of the robot is not disturbed.

The warranty is invalid for any faults that occur when the robot is used under the following conditions. Also, if the cover and/or other parts are damaged by interferences caused by the peripheral devices and the robot, the protection specification (seal performance, etc.) may be degraded. Therefore, please pay extra attention when handling the robot.

Refer to Page 184, "6.2 Working environment".

- 1) In surroundings that generate inflammable gases or corrosive gasses $^{*2)}$.
- 2) Atmosphere of the mist containing polish liquid etc.
- 3) Atmosphere in which the water, the oil, and the dust exceeding protection specification fall on the robot arm directly.

^{*1) &}lt;Sterilization environment test> 6-h exposure in the environment of 120-ppm concentration of hydrogen peroxide gas X 14 times

^{*2)} Chemical resistance of the robots is confirmed by the sterilization environment test with hydrogen peroxide gas*1) for the models with chemical-resistant specifications (SExx01).

(3) About the cleanliness

■ Precautions for use

1) The ventilation duct is attached to the robot arm rear (refer to Fig. 2–10). As the Z axis moves up and down the volume of the bellows varies, and air is sucked in and released out of the robot's ventilation duct opening. Be sure to locate the ventilation duct's opening in a position that will not affect the robot's clean-liness.

Furthermore, whilst it is only a small amount, in external air flows into the robot through the ventilation duct's opening, and therefore the following two points should be considered when deciding where to locate the ventilation duct's opening.

- The opening should be facing downwards
- The opening should not be located in the vicinity of dust/dirt, chemical ambience, or liquids, etc.

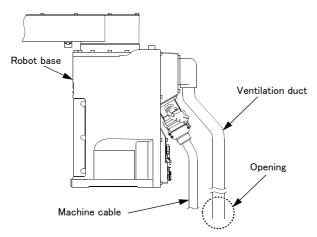


Fig.2-10: Installation of Ventilation Duct

2) When using the optional electromagnetic valve set, we recommend using the primary piping's spare piping (ϕ 6 air hose) to release the exhaust fumes.

Please take care as leaking exhaust fumes inside the robot may have an impact on the robot's cleanliness.

2.3 Names of each part of the robot



Fig.2-11: Names of each part of the robot

2.4 Outside dimensions • Operating range diagram

2.4.1 Outside dimensions • Operating range diagram (RH-6FH series)

<u>Note</u>

- *1) Indicates the space necessary to replace the battery.
- *2) Indicates screw holes (M4 depth 6mm) for fixing user wiring/piping. Six places on both-sides of No.2 arm, Two places on front surface.
- *3) The duct (\$\phi\$ 25, length: 3m) attached to the clean specification. Be careful for the hand etc. not to interfere and arrange the
- *4) The distance to a minimum bendable radius of the machine cable for CR750/751 controller.
- *5) Indicates the space necessary to connect the machine cable for CR750/751 controller.

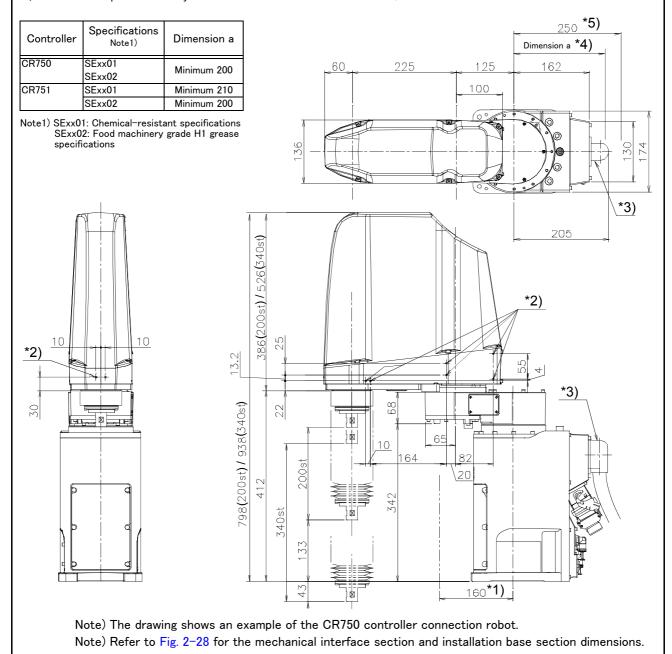


Fig.2-12: Outside dimensions of RH-6FH35xxM-SE

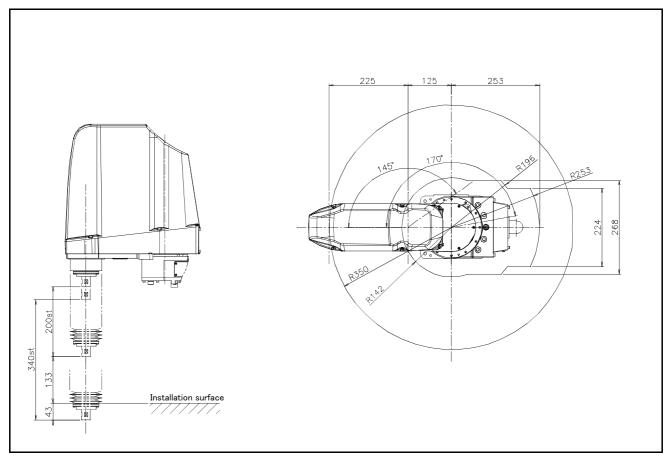


Fig.2-13: Operating range diagram of RH-6FH35xxM-SE

<u>Note</u>

- *1) Indicates the space necessary to replace the battery.
- *2) Indicates screw holes (M4 depth 6mm) for fixing user wiring/piping. Six places on both-sides of No.2 arm, Two places on
- *3) The duct (\$\phi\$ 25, length: 3m) attached to the clean specification. Be careful for the hand etc. not to interfere and arrange the
- *4) The distance to a minimum bendable radius of the machine cable for CR750/751 controller.
- *5) Indicates the space necessary to connect the machine cable for CR750/751 controller.

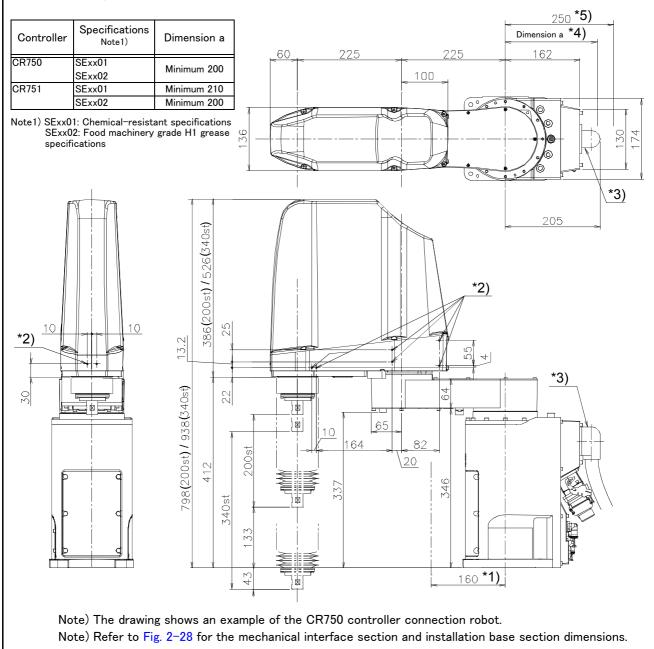


Fig.2-14: Outside dimensions of RH-6FH45xxM-SE

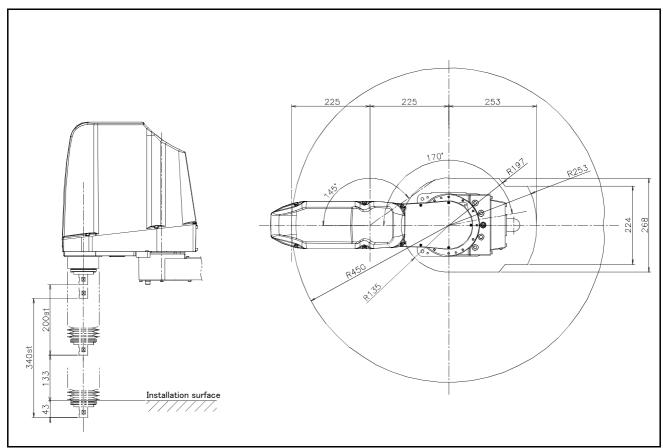


Fig.2-15: Operating range diagram of RH-6FH45xxM-SE

<u>Note</u>

- *1) Indicates the space necessary to replace the battery.
- *2) Indicates screw holes (M4 depth 6mm) for fixing user wiring/piping. Six places on both-sides of No.2 arm, Two places on
- *3) The duct (\$\phi\$ 25, length: 3m) attached to the clean specification. Be careful for the hand etc. not to interfere and arrange
- *4) The distance to a minimum bendable radius of the machine cable for CR750/751 controller.
- *5) Indicates the space necessary to connect the machine cable for CR750/751 controller.

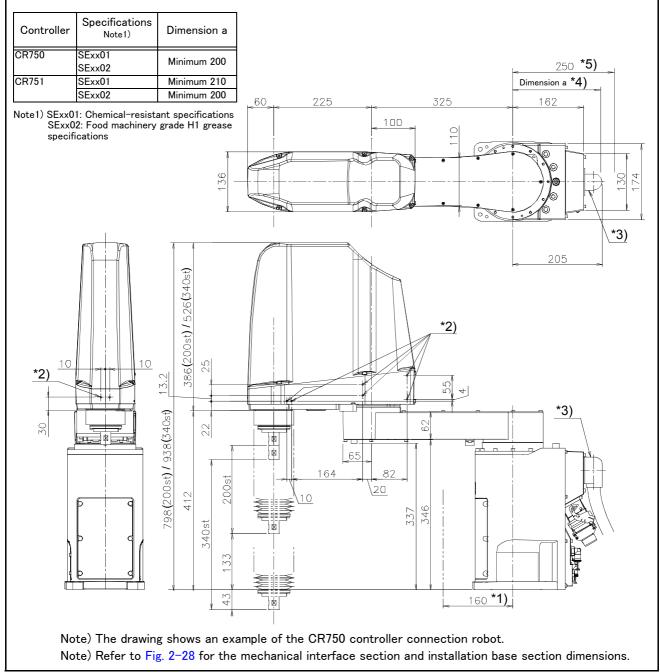


Fig.2-16: Outside dimensions of RH-6FH55xxM-SE

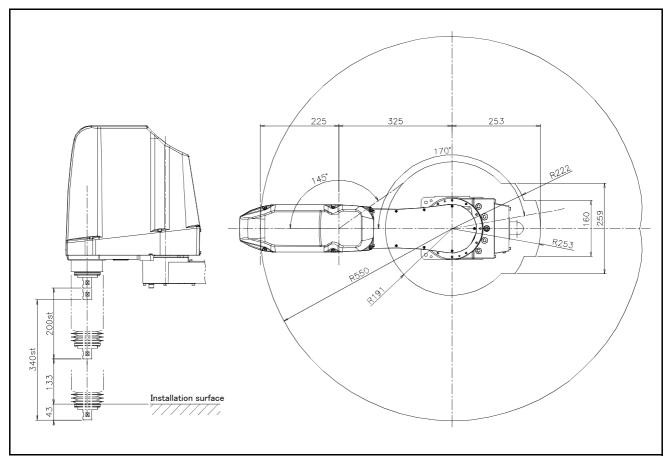


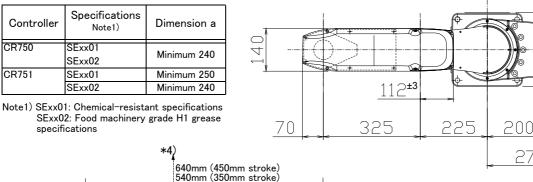
Fig.2-17 : Operating range diagram of RH-6FH55xxM-SE

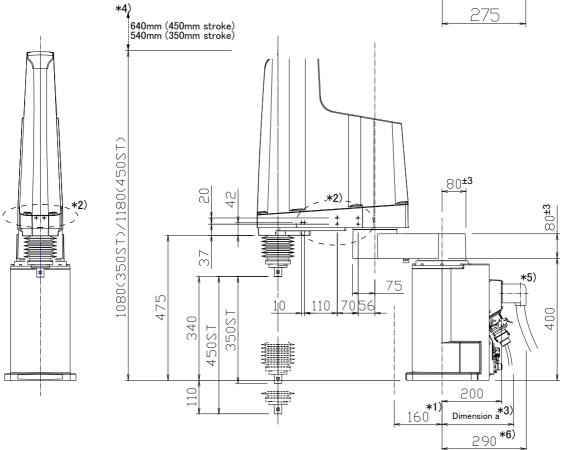
4

2.4.2 Outside dimensions • Operating range diagram (RH-12FH series)

Note

- *1) Indicates the space necessary to replace the battery.
- *2) Indicates screw holes for fixing user wiring/piping. (Refer to Fig. 2-32)
- *3) The distance to a minimum bendable radius of the machine cable for CR750/751 controller.
- *4) Required space to installing/removing the cover.
- *5) The duct (\$\phi\$ 50, length: 2m) attached to the clean specification. Be careful for the hand etc. not to interfere and arrange
- *6) Indicates the space necessary to connect the machine cable for CR750/751 controller.





Note) The drawing shows an example of the CR750 controller connection robot.

Note) Refer to Fig. 2-29 for the mechanical interface section and installation base section dimensions.

Fig.2-18: Outside dimensions of RH-12FH55xxM-SE

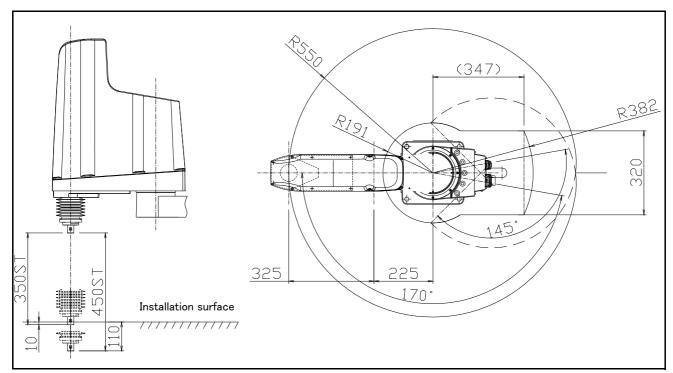
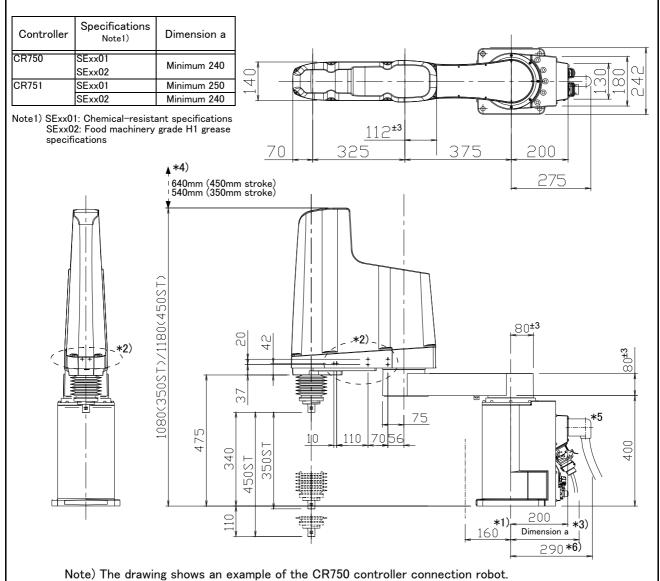


Fig.2-19 : Operating range diagram of RH-12FH55xxM-SE

Note

- *1) Indicates the space necessary to replace the battery.
- *2) Indicates screw holes for fixing user wiring/piping. (Refer to Fig. 2-32)
- *3) The distance to a minimum bendable radius of the machine cable for CR750/751 controller.
- *4) Required space to installing/removing the cover.
- *5) The duct (\$\phi\$ 50, length: 2m) attached to the clean specification. Be careful for the hand etc. not to interfere and arrange the
- *6) Indicates the space necessary to connect the machine cable for CR750/751 controller.



Note) Refer to Fig. 2-29 for the mechanical interface section and installation base section dimensions.

Fig.2-20: Outside dimensions of RH-12FH70xxM-SE

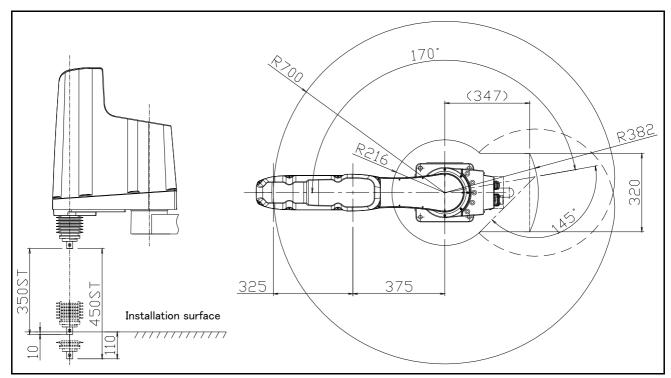
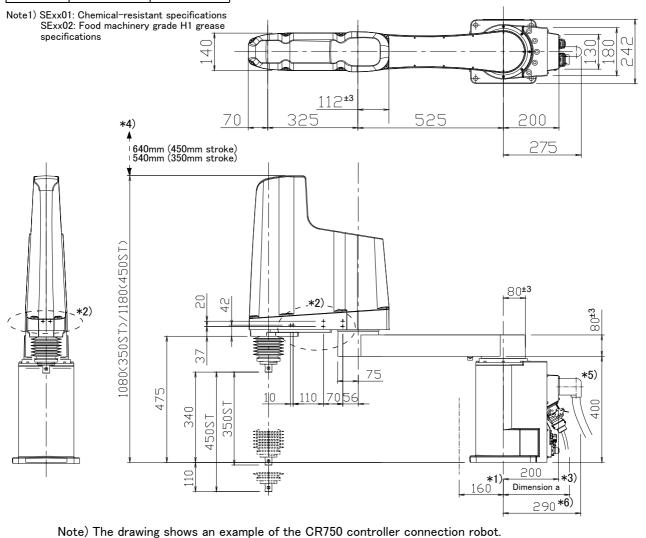


Fig.2-21: Operating range diagram of RH-12FH70xxM-SE

Note

- *1) Indicates the space necessary to replace the battery.
- *2) Indicates screw holes for fixing user wiring/piping. (Refer to Fig. 2-32)
- *3) The distance to a minimum bendable radius of the machine cable for CR750/751 controller.
- *4) Required space to installing/removing the cover.
- *5) The duct (ϕ 50, length: 2m) attached to the clean specification. Be careful for the hand etc. not to interfere and arrange the duct.
- *6) Indicates the space necessary to connect the machine cable for CR750/751 controller.

Controller	Specifications Note1)	Dimension a
CR750	SExx01 SExx02	Minimum 240
CR751	SExx01	Minimum 250
	SExx02	Minimum 240



Note) Refer to Fig. 2-29 for the mechanical interface section and installation base section dimensions.

Fig.2-22: Outside dimensions of RH-12FH85xxM-SE

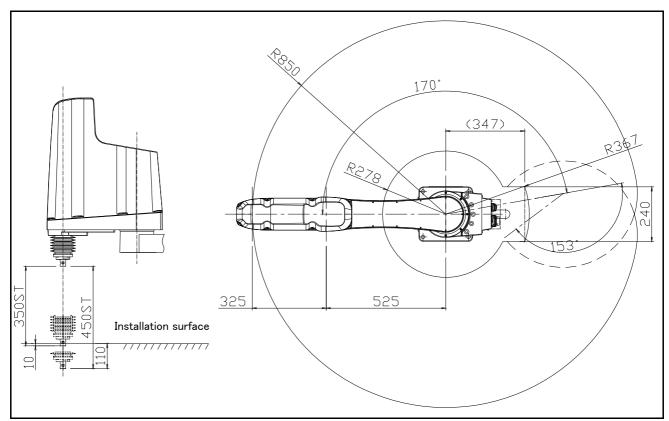
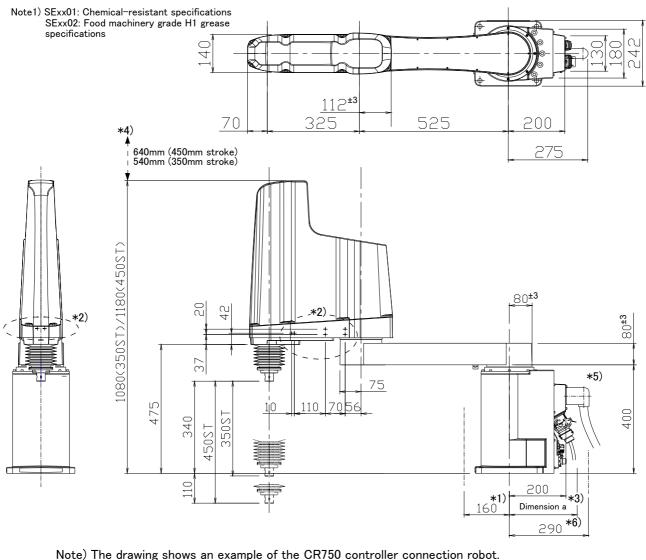


Fig.2-23 : Operating range diagram of RH-12FH85xxM-SE

2.4.3 Outside dimensions • Operating range diagram (RH-20FH series)

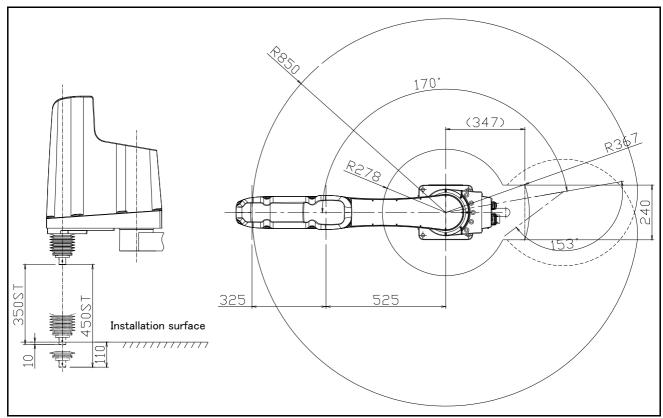
- *1) Indicates the space necessary to replace the battery.
- *2) Indicates screw holes for fixing user wiring/piping. (Refer to Fig. 2-32)
- *3) The distance to a minimum bendable radius of the machine cable for CR750/751 controller.
- *4) Required space to installing/removing the cover.
- *5) The duct (\$\phi\$ 50, length: 2m) attached to the clean specification. Be careful for the hand etc. not to interfere and arrange the
- *6) Indicates the space necessary to connect the machine cable for CR750/751 controller.

Controller	Specifications Note1)	Dimension a
CR750	SExx01 SExx02	Minimum 240
CR751	SExx01	Minimum 250
	SExx02	Minimum 240



Note) Refer to Fig. 2-30 for the mechanical interface section and installation base section dimensions.

Fig.2-24: Outside dimensions of RH-20FH85xxM-SE

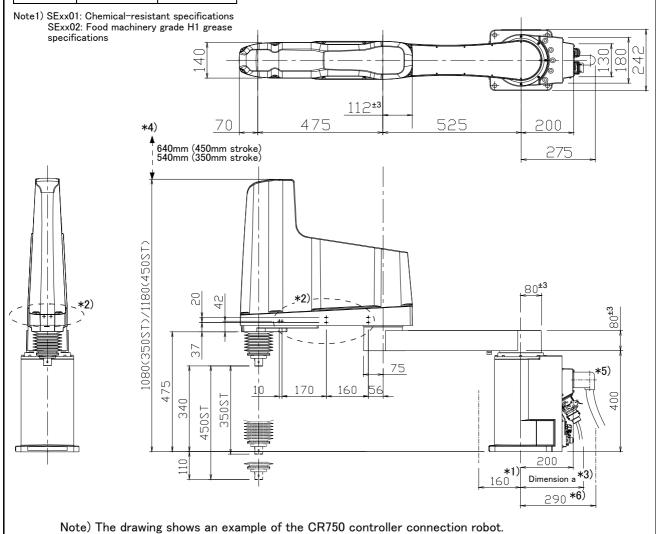


 $\label{eq:fig.2-25} \textit{Fig.2-25}: \textit{Operating range diagram of RH-20FH85xxM-SE}$

Note

- *1) Indicates the space necessary to replace the battery.
- *2) Indicates screw holes for fixing user wiring/piping. (Refer to Fig. 2-32)
- *3) The distance to a minimum bendable radius of the machine cable for CR750/751 controller.
- *4) Required space to installing/removing the cover.
- *5) The duct (\$\phi\$ 50, length: 2m) attached to the clean specification. Be careful for the hand etc. not to interfere and arrange the duct.
- *6) Indicates the space necessary to connect the machine cable for CR750/751 controller.

Controller	Specifications Note1)	Dimension a	
CR750	SExx01 SExx02	Minimum 240	
CR751	SExx01	Minimum 250	
	SExx02	Minimum 240	



Note) Refer to Fig. 2-30 for the mechanical interface section and installation base section dimensions.

Fig.2-26: Outside dimensions of RH-20FH100xxM-SE

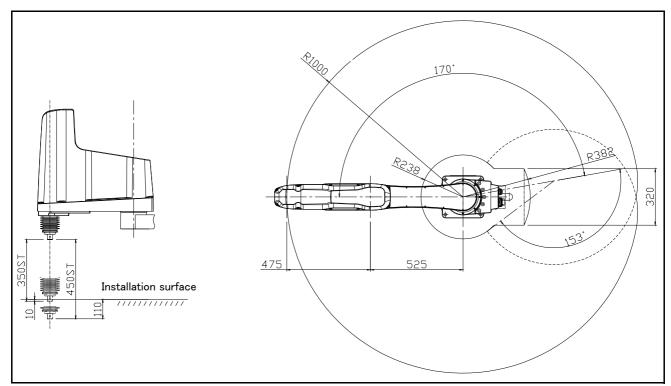


Fig.2-27 : Operating range diagram of RH-20FH100xxM-SE

2.4.4 Mechanical interface and Installation surface

(1) Mechanical interface and Installation surface of RH-6FH series

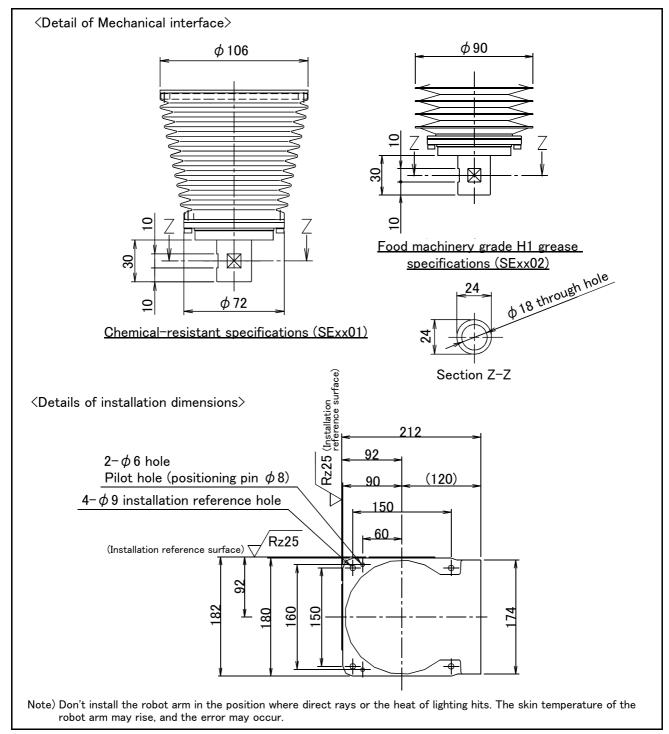


Fig.2-28: Mechanical interface and Installation surface (RH-6FH series)

(2) Mechanical interface and Installation surface of RH-12FH series

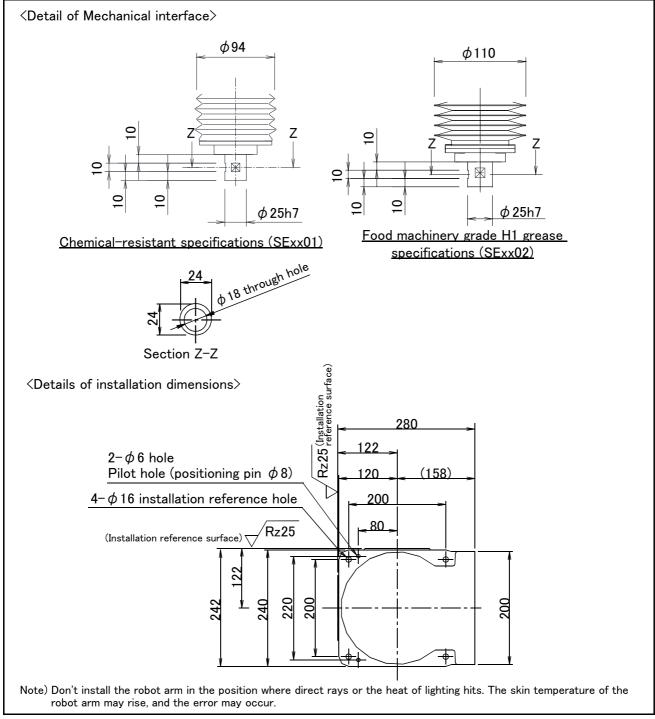


Fig.2-29: Mechanical interface and Installation surface of RH-12FH series

(3) Mechanical interface and Installation surface of RH-20FH series

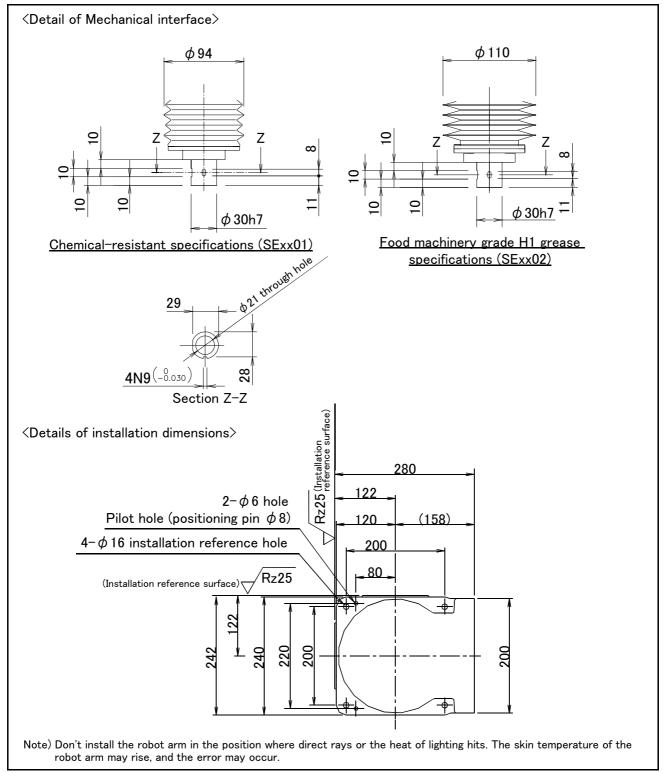
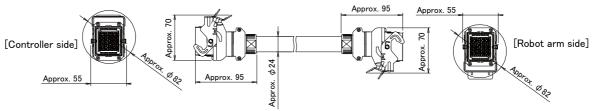


Fig.2-30: Mechanical interface and Installation surface of RH-20FH series

2.4.5 Outside dimensions of machine cables

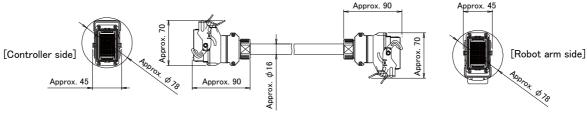
(1) Connection with the CR750 controller

1) Power cable



Note) If using an optional machine cable extension, refer to Page 63, "(1) Machine cable extension" in a diameter of the cable.

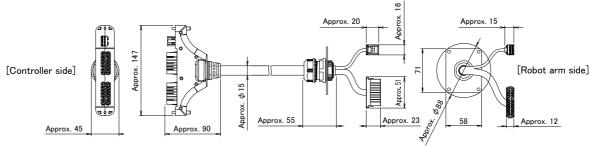
2) Signal cable



Note) If using an optional machine cable extension, refer to Page 63, "(1) Machine cable extension" in a diameter of the cable.

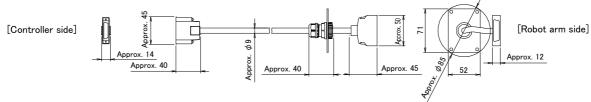
(2) Connection with the CR751 controller

1) Power cable



Note) If using an optional machine cable extension, refer to Page 63, "(1) Machine cable extension" in a diameter of the cable.

2) Signal cable



Note) If using an optional machine cable extension, refer to Page 63, "(1) Machine cable extension" in a diameter of the cable.

2.5 Tooling

2.5.1 Wiring and piping for hand

Shows the wiring and piping configuration for a standard-equipped hand.

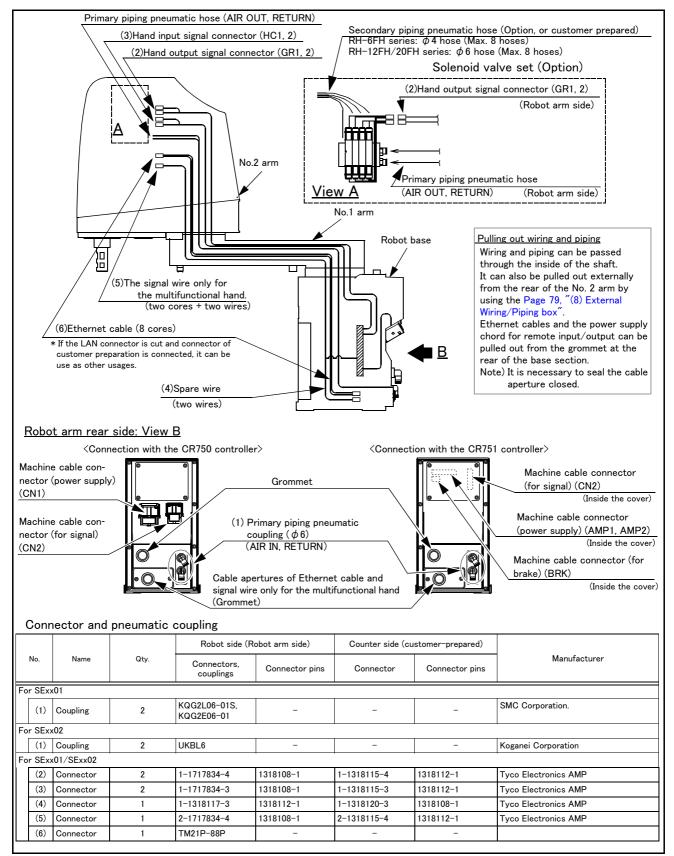


Fig.2-31: Wiring and piping for hand

2.5.2 Internal air piping

- •The robot has two ϕ 6 urethane hoses from the pneumatic entrance on the base section to the No.2 arm. One hose is the primary piping for the pneumatic equipment, and the other pipe is used for air exhaust.
- The pneumatic inlet in the base section has a ϕ 6 pneumatic coupling bridge.
- The solenoid valve set (optional) can be installed to the side on No.2 arm.
- Refer to Page 69, "(3) Solenoid valve set" for details on the electronic valve set (optional).

2.5.3 Internal wiring for the hand output cable

 The hand output primary cable extends from the connector PCB of the base section to the back side of the No.2 arm. (AWG#24(0.2mm²): 10 cables) The cable terminals have connector bridges for eight hand outputs. The connector names are GR1 and GR2.

To pull the wiring out of the arm, following separate options are required.

- Hand output cable......1F-GR60S-01
- External wiring and piping boxFor SExx01: 1F-UT-BOX-04 (RH-6FH series)

1F-UT-BOX-03 (RH-12FH/20FH series)

For SExx02: 1F-UT-BOX (RH-6FH series)

1F-UT-BOX-01 (RH-12FH/20FH series)

2.5.4 Internal wiring for the hand input cable

- The hand input cable extends from the connector PCB of the base section to the No.2 arm.
 (AWG#24(0.2mm²): 10 cables) The cable terminals have connector bridges for eight hand inputs. The connector names are HC1 and HC2.
- 2) The hand check signal of the pneumatic hand is input by connecting this connector.

To extend the wiring to the outside of the arm, following separate options are required.

Hand input cable......1F-HC35C-01 (RH-6FH series)

1F-HC35C-02 (RH-12FH/20FH series)

• External wiring and piping boxFor SExx01: 1F-UT-BOX-04 (RH-6FH series)

1F-UT-BOX-03 (RH-12FH/20FH series)

For SExx02: 1F-UT-BOX (RH-6FH series)

1F-UT-BOX-01 (RH-12FH/20FH series)

2.5.5 Ethernet cable

Ethernet cables are installed from the robot's base section up to the No. 2 arm section, and can be used. Similar to on our previous models, these cables can also be used for backup wiring. For further details please refer to the separate "Instruction Manual/Robot Arm Setup".

Example of use for backup wiring.

- When connecting previously used tools to the robot
- Folding back the hand output cable when attaching the electromagnetic valve to the robot's exterior.
- When attaching 8 devices or more to the hand section such as sensors, (8 input and 8 output dedicated points are available for hand signals.). In this case connect the signals (of the sensors, etc.) to parallel input/output signals.

When shipped from the factory, both ends are LAN connectors.

When using it as backup wiring, cut the LAN connectors off and use with user supplied connectors.

When using it as backup wiring for data communication, the shield wire must be grounded. If the shield wire is not grounded, it may cause a communication abnormality by noise superposed on the cable.

Table 2-8: Ethernet cable specification

Item	Specification		
Communication speed	100BASE-TX		
Size	AWG #26 (0.13mm ²) x four pair (total eight cores)		
Externality of insulator	Approx. 0.98 mm		

2.5.6 About the Installation of Tooling Wiring and Piping (Examples of Wiring and Piping)

The customer is required to provide tooling wiring, piping and metal fixtures.

Screw holes are provided on the robot arm for the installation of tooling wiring, piping and metal fixtures. (Refer to the Fig. 2–32 to Fig. 2–33.)

The length of wiring and piping and the installation position on the robot must be adjusted according to the work to be done by the robot. Please use the following example as reference.

<Pre>cautions>

- · A hand input cable and a hand curl cable are available as optional accessories for your convenience.
- · After performing wiring and piping to the robot, operate the robot at low speed to make sure that each part does not interfere with the robot arm and the peripheral devices.
- Confirm that there is no interference also with bellows of the shaft section.
- · Please be aware that dust may be generated from friction if wires and pipes come into contact with the robot arm.
- ·If you install metal fixtures and a solenoid valve using the screw holes on the No.2 arm portion, add the mass of the metal fixtures and the solenoid valve to mass of a hand then set the HNDDAT parameter. Moreover, Fix the parts, such as a solenoid valve, firmly to prevent the parts getting shaky during operation of a robot.

(1) RH-6FH series

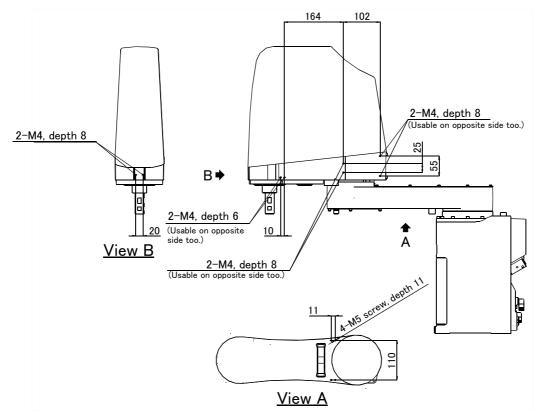


Fig.2-32: Location of screw holes for fixing wiring/piping (RH-6FH)

(2) RH-12FH/20FH series

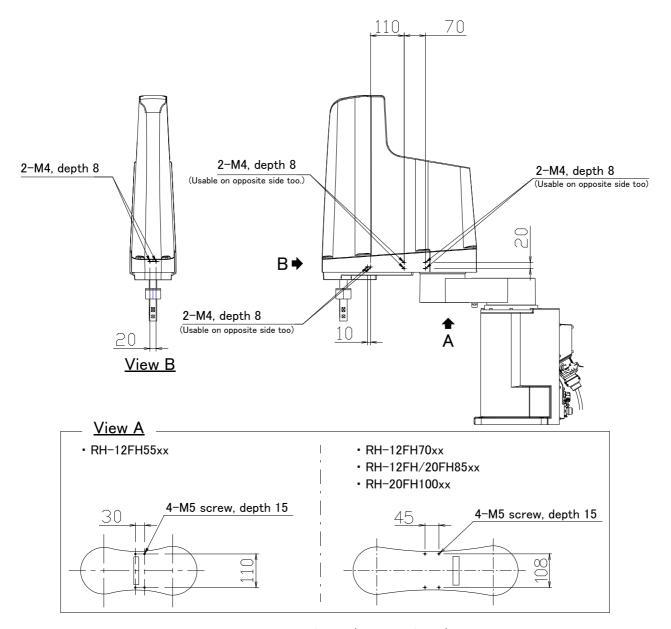


Fig.2-33: Location of screw holes for fixing wiring/piping (RH-12FH/20FH)

(3) Example of wiring and piping <1>

By feeding wiring and piping through the inside of the shaft, the wiring and piping to the hand becomes compact.

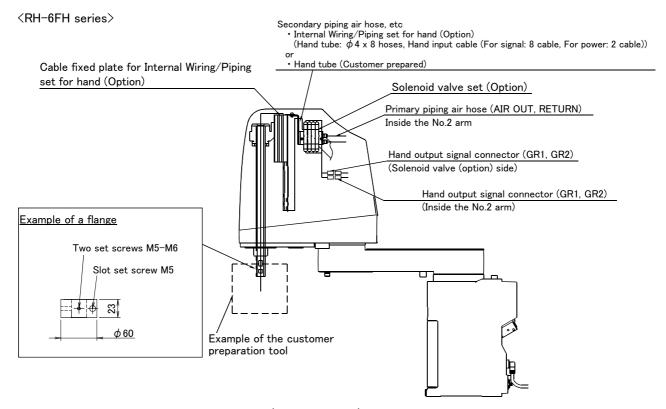


Fig.2-34: Example of wiring and piping <1> (RH-6FH series)

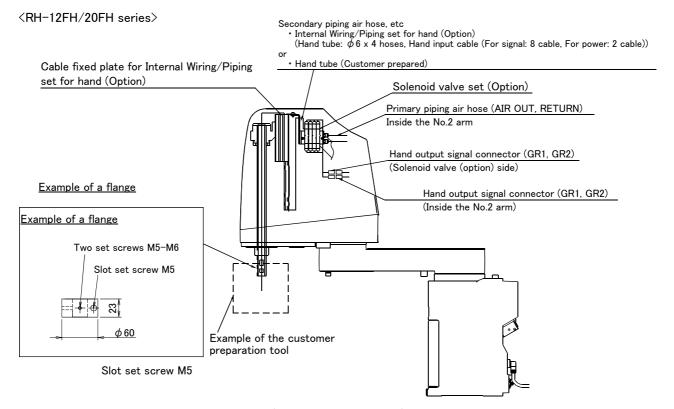


Fig.2-35: Example of wiring and piping <1> (RH-12FH/20FH series)

(4) Wiring and piping example <2>

This is an effective method in cases where the wiring and piping is often changed, or when the hand rotation is minimal (within $\pm 90^{\circ}$), etc.

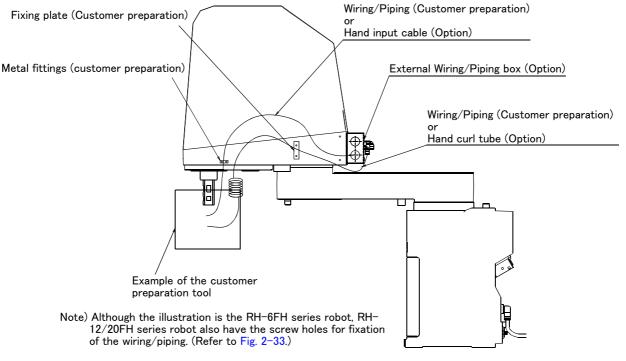


Fig.2-36: Example of wiring and piping <2>

(5) Precautions for the shaft through hole

The through hole of the top part of the tip shaft are taped at shipment.

Perform the following actions as necessary in order to ensure that the robot keeps sufficiently protective performance during the operation:

- 1) When the through hole of the shaft is not used
 - \cdot Keep the top part of the tip shaft taped while the robot is in use.
- 2) When the through hole of the shaft is used for wiring.
 - Remove the rubber cap on top of the tip shaft and perform the necessary wiring. Once the wiring is completed, seal the bottom part of the tip shaft using liquid seal in order to avoid accumulation of dust and entry of chemicals.
 - •Perform the wiring in such a way that the wires around the area below the tip shaft will not get into contact with other parts while the robot is operating.

2.5.7 Wiring and piping system diagram for hand

Shows the wiring and piping configuration for a standard-equipped hand.

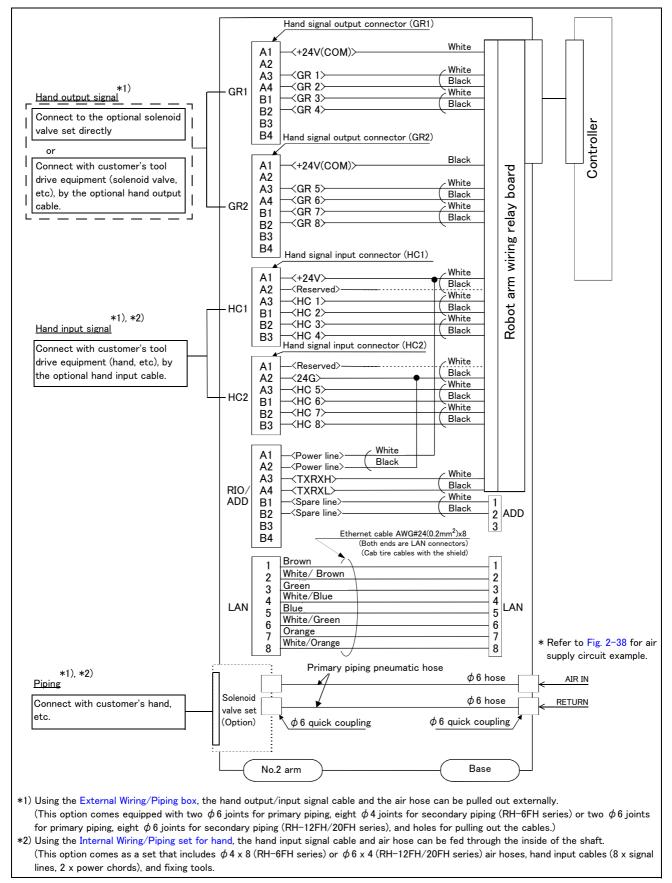


Fig.2-37: Wiring and piping system diagram for hand and example the solenoid valve installation

2.5.8 Electrical specifications of hand input/output

Table 2-9: Electrical specifications of input circuit

Item		Specifications	Internal circuit
Туре		DC input	⟨Sink type⟩
No. of input point	No. of input points 8		+24V ♀
Insulation method	Insulation method Photo-coupler insulation		+24V
Rated input volta	ge	24VDC	
Rated input curre	nt	approx. 7mA	→ ↓ [820
Working voltage r	ange	DC10.2 to 26.4V (ripple rate within 5%)	HCn*
ON voltage/ON o	urrent	8VDC or more/2mA or more	3.3K 24G
OFF voltage/OFF	current	4VDC or less/1mA or less	
Input resistance		Approx. 3.3kΩ	<source type=""/>
Response time OFF-ON		10ms or less (DC24V)	+24V
ON-OFF		10ms or less (DC24V)	+24V
			3.3K HCn* 820 24G
			* HCn = HC1 to HC8

Table 2-10: Electrical specifications of output circuit

Item		Specification	Internal circuit
Туре		Transistor output	⟨Sink type⟩
No. of output points		8	+24V(COM)
Insulation method		Photo coupler insulation	(Initial power supply)
Rated load voltage		DC24V	T⋈
Rated load voltage rang	ge ge	DC21.6 to 26.4VDC	
Max. current load		0.1A/ 1 point (100%)	GRn*
Current leak with power	r OFF	0.1mA or less	1 \$_,
Maximum voltage drop v	with power ON	DC0.9V(TYP.)	
Response time	OFF-ON	2ms or less (hardware response time)	1
	ON-OFF	2ms or less (resistance load) (hardware response time)	Protection of over-current
Protects	•	Protects the over-current (0.9A)]
			24G
			<source type=""/>
			Protection of over-current GRn* 24G * GRn = GR1 to GR8

2.5.9 Air supply circuit example for the hand

An example of pneumatic supply circuitry for the hand is shown below.

- (1) Place diodes parallel to the solenoid coil.
- (2) When the factory pneumatic pressure drops, as a result of the hand clamp strength weakening, there can be damage to the work. To prevent it, install a pressure switch to the source of the air as shown in Fig. 2–38 and use the circuit described so that the robot stops when pressure drops. Use a hand with a spring-pressure clamp, or a mechanical lock-type hand, that can be used in cases where the pressure switch becomes damaged.
- (3) The optional hand and solenoid valve are of an oilless type. If they are used, don't use any lubricator.
- (4) Supply clean air to the vacuum generation valve .
- (5) If the air supply temperature (primary piping) used for the tool etc. is lower than ambient air temperature, the dew condensation may occur on the coupling or the hose surface.

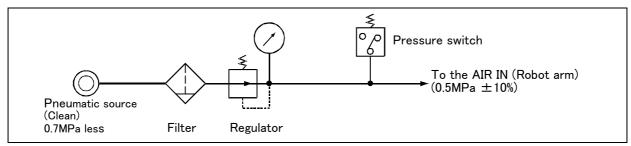


Fig.2-38: Air supply circuit example for the hand

2.6 Shipping special specifications, options, and maintenance parts

2.6.1 Shipping special specifications

■ What are sipping special specifications?

Shipping special specifications are changed before shipping from the factory. Consequently, it is necessary to confirm the delivery date by the customer.

To make changes to the specifications after shipment, service work must be performed at the work site or the robot must be returned for service.

■ How to order

- (1) Confirm beforehand when the factory special specifications can be shipped, because they may not be immediately available.
- (2) Specify, before shipping from our company.
- (3) Specified method ····· Specify the part name, model, and robot model type.

2.7 Options

■ What are options?

There are a variety of options for the robot designed to make the setting up process easier for customer needs. customer installation is required for the options. Options come in two types: "set options" and "single options".

- 1. Set optionsA combination of single options and parts that together, from a set for serving some purpose.
- 2. Single optionsThat are configured from the fewest number of required units of a part.

 Please choose customer's purpose additionally.

(1) Machine cable extension

■ Order type:

CR750 controller.......Fixed type: 1S-□□ CBL-01 (For SExx01/SExx02)

● CR751 controller.....Fixed type: 1F- □□ UCBL-03 (For SExx01)

Flexed type: $1F-\Box\Box$ LUCBL-03 (For SExx01) Fixed type: $1F-\Box\Box$ UCBL-02 (For SExx02) Flexed type: $1F-\Box\Box$ LUCBL-02 (For SExx02)

Note) \square refer the length.

Outline

<CR750 controller>

<CR751 controller>



The distance between the robot controller and the robot arm is extensible by this option.

A fixed type and flexible type are available.

The fix and flexible types are both configured of the motor signal cable and motor power cable.

The extension method is discriminated as follows depending on a controller.

• The cables for CR750 controller:

Adds to the machine cable (5m) attached in the standards.

• The cables for CR751 controller:

Exchanges with the machine cable (5m) attached in the standards.

■ Configuration

Table 2-11: Configuration equipment and types

	Part name	Type ^{Note1)}	Q	ty.	Mass(kg)	Remarks	
	i ai c name	Туре	Fixed	Flexed	Note2)	rtemarte	
0 controll	ler						
or SExx01	/SExx02						
Fixed	Set of signal and power cables	1S- □□ CBL-01	1 set	-	6.7(5m)	5m, 10m, or 15m each	
	Motor signal cable		(1 cable)	_	12(10m) 17(15m)		
	Motor power cable		(1 cable)	_	17(13111)		
Flexed	Set of signal and power cables	1S- □□ LCBL-01	_	1 set	7(5m)	5m, 10m, or 15m each	
	Motor signal cable		_	(1 cable)	13(10m) 17(15m)		
	Motor power cable		_	(1 cable)	17(13111)		
Nylon cla	amp	NK-14N	_	2 pcs.	-	for motor signal cable	
Nylon cla	amp	NK-18N	_	2 pcs.	-	for motor power cable	
Silicon ru	ubber		_	4 pcs.	-		
1 controll	ler			,			
or SExx01							
Fixed	Set of signal and power cables	1F- 🗆 🗆 UCBL-03	1 set	_	6.7(10m)	10m, 15m, or 20m eacl	
	Motor signal cable		(1 cable)	_	12(15m) 17(20m)		
	Motor power cable		(1 cable)	_	17(2011)		
Flexed	Set of signal and power cables	1F- 🗆 LUCBL-03	_	1 set	7(10m)	10m, 15m, or 20m each	
	Motor signal cable		_	(1 cable)	13(15m) 17(20m)		
	Motor power cable		_	(1 cable)	17(2011)		
Nylon cla	amp	NK-14N	_	2 pcs.	-	for motor signal cable	
Nylon cla	amp	NK-18N	-	2 pcs.	-	for motor power cable	
Silicon ru	ubber		-	4 pcs.	-		

Part name		Type ^{Note1)}	Q:	Qty.				Remarks
		туре	Fixed Flexed		Note2)	Hemains		
or SExx02								
Fixed	Set of signal and power cables	1F- □□ UCBL-02	1 set	_	6.7(10m)	10m, 15m, or 20m each		
Motor signal cable			(1 cable)	_	12(15m) 17(20m)			
	Motor power cable		(1 cable)	_	17(2011)			
Flexed	Set of signal and power cables	1F- 🗆 🗆 LUCBL-02	-	1 set	7(10m)	10m, 15m, or 20m each		
	Motor signal cable		-	(1 cable)	13(15m) 17(20m)			
	Motor power cable		-	(1 cable)	17(2011)			
Nylon clamp		NK-14N	_	2 pcs.	-	for motor signal cable		
Nylon clamp		NK-18N	-	2 pcs.	_	for motor power cable		
Silicon rubber			-	4 pcs.	-			

Note1) The numbers in the boxes $\square \square$ refer the length.

Note2) Mass indicates one set.

■ Specifications

The specifications for the fixed type cables are the same as those for standard cables. Shows usage conditions for flexed type cables in Table 2-12.

Table 2-12 : Conditions for the flexed type cables

Ite	em	Specifications		
Cable		1S- 🗆 🗆 LCBL-01	1F-	
Minimum flexed radius		100mm or more		
Cableveyor, etc., occupa	ation rate	50% or less		
Maximum movement spe	eed	2,000mm/s or less		
Guidance of life count		7.5 million times (With silicone grease coating)		
Environmental proof		IP54	IP54 (except for the area approximately 500 mm from the end of the connector on the controller side)	
Cable configuration	Motor signal cable	ϕ 6 x 5, ϕ 8.5 x 1, and ϕ 1.7 x 1	ϕ 6 x 7 and ϕ 1.7 x 1	
	Motor power cable	ϕ 8.9 x 3 and ϕ 6.5 x 6	φ 6.5 x 8 and φ 8.9 x 2	

[Caution] The guidance of life count may greatly differ according to the usage state items related to Table 2–12 and to the amount of silicon grease applied in the cableveyor.

Recommendation grease: G-501 (Supplier: Shin-Etsu Chemical Co., Ltd.)

* The above-mentioned grease is not the food machinery grade H1 grease.

[Caution] The cleanliness of this option is not under warranty.

[Caution] When a cableveyor is used, partitions are required to avoid overlapping or riding up of the cables. Also, adjust the cable length to eliminate tension or excessive looseness, and fix it securely.

■ Cable configuration

The configuration of the flexible cable is shown in Table 2–13. Refer to this table when selecting the cableveyor.

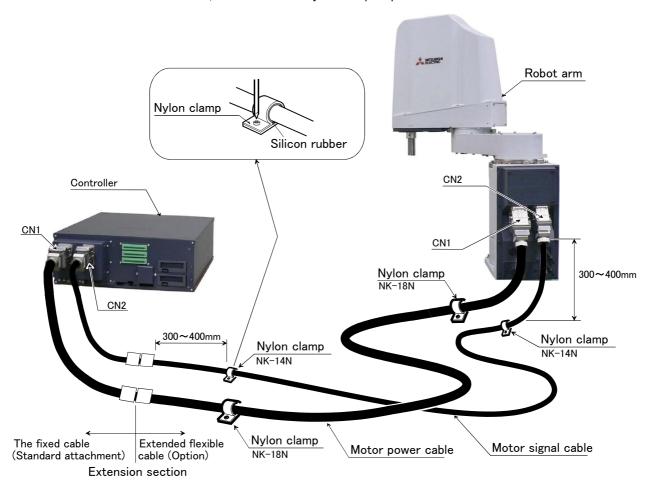
Table 2-13 : Cable configuration (Flexed type)

Item		Motor sign	al cable		Motor pow	ver cable
R750 controller				<u> </u>		
No. of cores	AWG#24 (0.2mm ²)-4P	AW0 (0.2mm	G#24 n ²)-7P	AWG#18 (0.75mm ²)	AWG#16 (1.25mm ²)-4C	AWG#18 (0.75mm ²)-4C
Finish dimensions	Approx. φ6mm	Approx. <i>φ</i> 8.5mm		Approx. <i>φ</i> 1.7mm	Approx. <i>φ</i> 8.9mm	Approx. φ6.5mm
No.of cables used	5 cables	1 cable		1 cable	3 cable	6 cable
No. in total		7 cables			9 cables	
R751 controller				1		
No. of cores	AWG#24 (0.2mm ²)-4	AWG#24 (0.2mm ²)-4P		AWG#18 (0.75mm ²)	AWG#16 (1.25mm ²)-4C	AWG#18 (0.75mm ²)-3C
Finish dimensions	Approx. φ6n	6mm		orox. φ1.7mm	Approx. <i>φ</i> 8.9mm	Approx. <i>φ</i> 6.5mm
No.of cables used	7 cables	;		1 cable	2 cable	8 cable
No. in total		8 cab	vles		10 ca	bles

■ Fixing the flexible cable

<CR750 controller>

- (1) Connect the connector to the robot arm.
 The connection method to a robot arm is the same as a standard machine cable. Please refer to the separate "Instruction Manual/ROBOT ARM SETUP & MAINTENANCE" and connect.
- (2) Wind the silicon rubber around the cable at a position 300 to 400 mm from the side of robot arm and extension section as shown below, and fix with the nylon clamp to protect the cable from external stress.



CAUTION

Cover the extension terminal area with the cover etc. so that it may not be easily touched to the latch lever.

The bend size of cables are as follows.

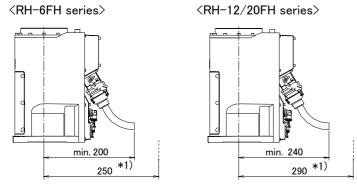
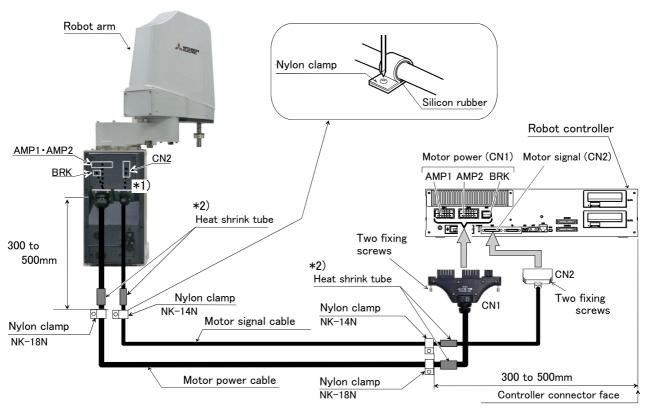


Fig.2-39: Fixing the flexible cable (CR750 controller)

*1) The connection space for a machine cable.

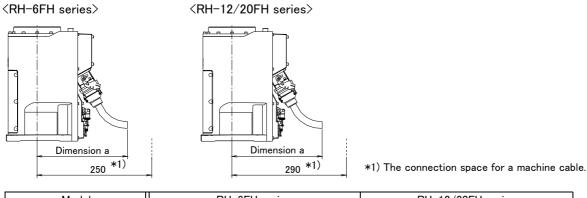
<CR751 controller>

- (1) Connect the connector to the robot arm.
 - The connection method to a robot arm is the same as a standard machine cable. Please refer to the separate "Instruction Manual/ROBOT ARM SETUP & MAINTENANCE" and connect.
- (2) For protection of wires from external stress, refer to following. Wrap the cable with the supplied silicon rubber and fix the cable with nylon clamps in the area between the heat shrink tubes on the robot and the controller sides (flexible cable area).



- *1) Connect the robot arm side connector to the connector which is inside the CONBOX cover.
- *2) The flexible cable area is the area between the heat shrink tubes on the robot and the controller sides.

The bend size of cables are as follows.



Model	RH-6FI	H series	RH-12/20FH series		
Specification ^{Note1)}	SExx01 SExx02		SExx01 SExx02		
Dimension a	Min. 210	Min. 200	Min. 250	Min. 240	

Note1) SExx01: Chemical-resistant specifications. SExx02: Food machinery grade H1 grease specifications.

Fig.2-40: Fixing the flexible cable (CR751 controller)

(2) Stopper for changing the operating range

■ Order type: RH-6FH seriesJ1 axis: 1F-DH-09 (For SExx01)

1F-DH-01 (For SExx02)

RH-12FH/20FH seriesJ1 axis: 1F-DH-10 (For SExx01)

1F-DH-02 (For SExx02)

Outline



The operating range of J1 axis is limited by the robot arm's mechanical stopper and the controller parameters.

If the axis could interfere with the peripheral devices, etc., and the operating range need to be limited, use this.

■ Configuration

Table 2-14: Configuration devices

Part name	Туре	Qty.	Mass(kg)	Remarks
RH-6FH series				
Stopper for changing the operat-	1F-DH-09	1 set	0.05	For SExx01. Hexagon socket head bolt (M10 x 20): 2 bolts
ing range	1F-DH-01	1 set	0.05	For SExx02. Hexagon socket head bolt (M10 x 20): 2 bolts
RH-12FH/20FH series				
Stopper for changing the operat-	1F-DH-10	1 set	0.05	For SExx01. Hexagon socket head bolt (M12 x 20): 2 bolts
ing range	1F-DH-02	1 set	0.05	For SExx02. Hexagon socket head bolt (M12 x 20): 2 bolts

■ Specifications

Table 2-15 : Specifications

	Axis	Standard	Changeable angle
J1	+/- side	+/- 170 deg	+/- 130 deg, +/- 150 deg

- (1) The changeable angle shown in Table 2-15 indicates the operation range by the software.

 The limit by the mechanical stopper is positioned 3 degrees outward from that angle, so take care when designing the layout.
- (2) The operating range is changed with robot arm settings (insertion of the pin) and parameter settings. Refer to the separate "Instruction Manual/ROBOT ARM SETUP & MAINTENANCE" and "Instruction Manual/Detailed Explanation of Functions and Operations" for details.
- (3) If the arm collides with mechanical stopper for operating range change at the automatic operation, replacement of the mechanical stopper is necessary.

(3) Solenoid valve set

■ Order type: RH-6FH seriesOne set: 1F-VD01-01(Sink type)/1F-VD01E-01(Source type)

Two sets: 1F-VD02-01(Sink type)/1F-VD02E-01(Source type)
Three sets: 1F-VD03-01(Sink type)/1F-VD03E-01(Source type)
Four sets: 1F-VD04-01(Sink type)/1F-VD04E-01(Source type)

RH-12FH/20FH series.....One set: 1S-VD01-01(Sink type)/1S-VD01E-01(Source type)

Two sets: $1S-VD02-01(Sink\ type)/1S-VD02E-01(Source\ type)$ Three sets: $1S-VD03-01(Sink\ type)/1S-VD03E-01(Source\ type)$ Four sets: $1S-VD04-01(Sink\ type)/1S-VD04E-01(Source\ type)$

■ Outline

<RH-6FH series> <RH-12FH/20FH series>





• 1F-VD0*-01 • 1F-VD0*E-01

1S-VD0*-011S-VD0*E-01

The solenoid valve set is an option that is used for controlling toolings when various toolings, such as the hand, are installed at the end of the arm.

Also, for easy installation of this electromaagnetic set onto the robot, it comes equipped with a manifold, couplings, connectors, among other things.

■ Configuration

Table 2-16: Configuration equipment

Part name	Туре	Q'ty	Mass(kg) Note1)	Remark
H-6FH series	<u>•</u>			
Solenoid valve set (1 sets)	1F-VD01-01/ 1F-VD01E-01	Either one pc.	1.0	
Solenoid valve set (2 sets)	1F-VD02-01/ 1F-VD02E-01	Either one pc.	1.0	Hand output cable is already connected. Refer to Page 75, "(5) Hand output cable".
Solenoid valve set (3 sets)	1F-VD03-01/ 1F-VD03E-01	Either one pc.	1.0	- M4 x 30 Two screws (Installation screws) 1F-VD0*-01: Sink type 1F-VD0*E-01: Source type.
Solenoid valve set (4 sets)	1F-VD04-01/ 1F-VD04E-01	Either one pc.	1.0	, , , , , , , , , , , , , , , , , , ,
H-12FH/20FH series		"		
Solenoid valve set (1 sets)	1S-VD01-01/ 1S-VD01E-01	Either one pc.	1.0	
Solenoid valve set (2 sets)	1S-VD02-01/ 1S-VD02E-01	Either one pc.	1.0	Hand output cable is already connected. Refer to Page 75, "(5) Hand output cable".
Solenoid valve set (3 sets)	1S-VD03-01/ 1S-VD03E-01	Either one pc.	1.0	M4 x 8 Two screws (Installation screws) 1S-VD0*-01: Sink type 1S-VD0*E-01: Source type.
Solenoid valve set (4 sets)	1S-VD04-01/ 1S-VD04E-01	Either one pc.	1.0	

Note1) Mass indicates one set.

■ Specifications

Table 2-17: Valve specifications

Item	Specifications				
Number of positions	2				
Port	5 Note1)				
Valve function	Double solenoid				
Operating fluid	Clean air ^{Note2)}				
Operating method	Internal pilot method				
Effective sectional area (CV value)	0.64mm ² (0.03)				
Oiling	Unnecessary				
Operating pressure range	0.1 to 0.7MPa				
Response time	22msec or less (at 0.5 MPa)				
Max. operating frequency	5Hz				
Ambient temperature	-10 to 50 °C (However, there must be no condensation.)				

Note1) Couplings of unused solenoid valves must be blocked with plugs. If they are not blocked, supplied air will blow out from the couplings, lowering the air pressure of the solenoid valves being used and making them nonfunctional.

Recommended plugs: KQ2P-04 plug (RH-6FH series) made by SMC

KQ2P-06 plug (RH-12FH/20FH series) made by SMC.

Note2)



CAUTION The air to be provided must be clean, i.e., filtered with a mist separator or air filter. Failing to do so may lead to malfunctions.

Table 2-18: Solenoid specifications

Item	Specifications
Method	Built-in fly-wheel diodes with surge protection
Coil rated voltage	DC24V ±10%
Power consumption	0.55W
Voltage protection circuit with power surge protection	Diode

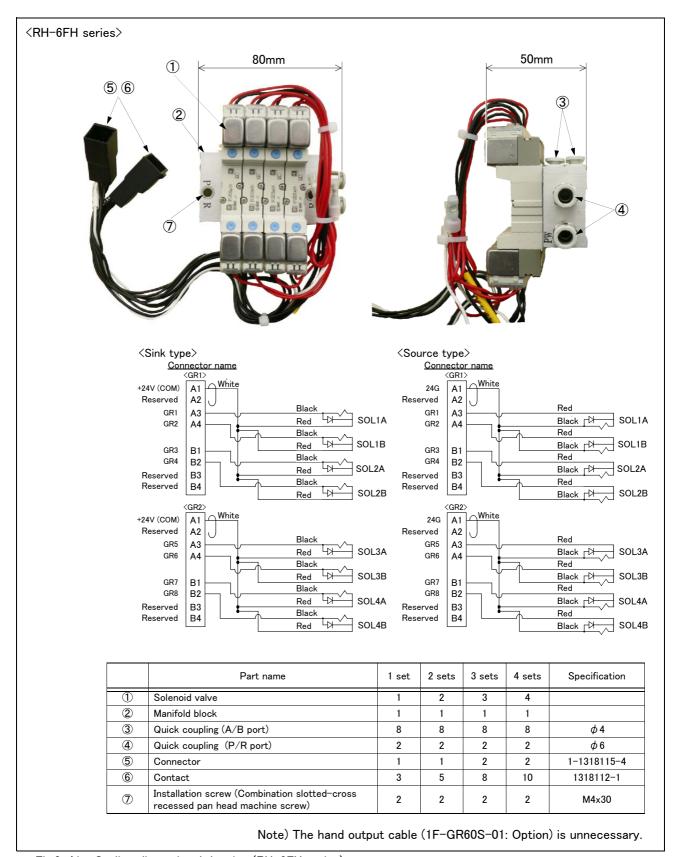


Fig.2-41: Outline dimensional drawing (RH-6FH series)

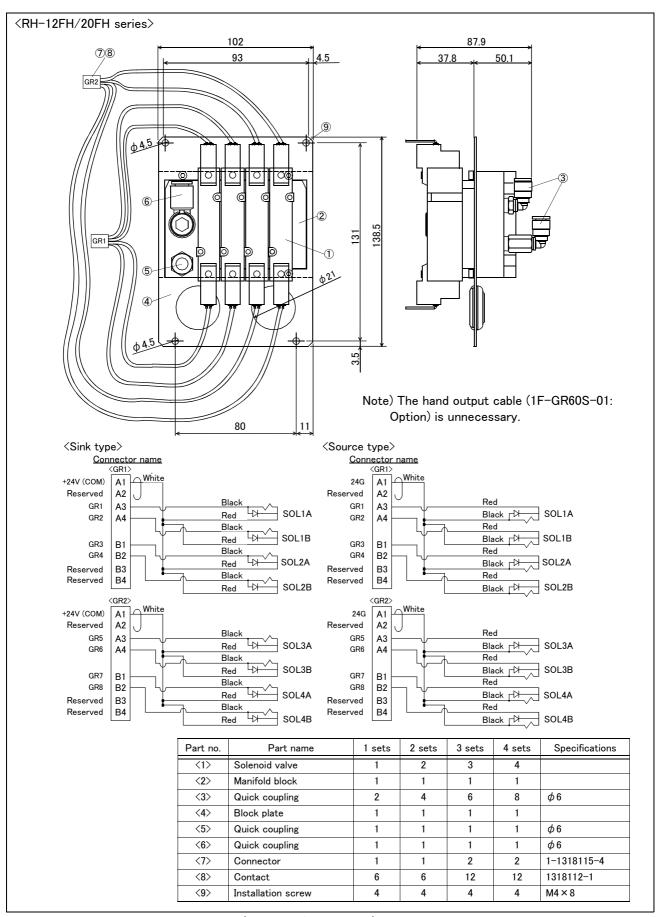


Fig.2-42: Outline dimensional drawing (RH-12FH/20FH series)

(4) Hand input cable

■ Order type: RH-6FH series1F-HC35C-01
RH-12FH/20FH series1F-HC35C-02

■ Outline



The hand input cable is used for customer-designed pneumatic hands.

It is necessary to use this to receive the hand's open/close confirmation signals and grasping confirmation signals, at the controller.

One end of the cable connects to the connector for hand input signals, which is in the wrist section of the hand. The other end of the cable connected to the sensor inside the hand customer designed.

To extend the wiring to the outside of the robot arm, optional external wiring and piping box is required. Refer to Page 79, "(8) External Wiring/Piping box" in detail.

■ Configuration

Table 2-19: Configuration equipment

Part name	Туре	Qty.	Mass (kg) Note1)	Remarks
RH-6FH series				
Hand input cable	1F-HC35C-01	1 cable	0.2	
RH-12FH/20FH series				
Hand input cable	1F-HC35C-02	1 cable	0.2	

Note1) Mass indicates one set.

■ Specifications

Table 2-20: Specifications

Item	Specifications	Remarks	
RH-6FH series			
Size x cable core	AWG#24 (0.2mm ²) × 12	One-sided connector, one-sided cable bridging	
Total length	1,650mm (Including the curl section, which is 350mm long)		
RH-12FH/20FH series			
Size x cable core	AWG#24 (0.2mm ²) × 12	One-sided connector, one-sided cable bridging	
Total length	1,800mm (Including the curl section, which is 350mm long)		

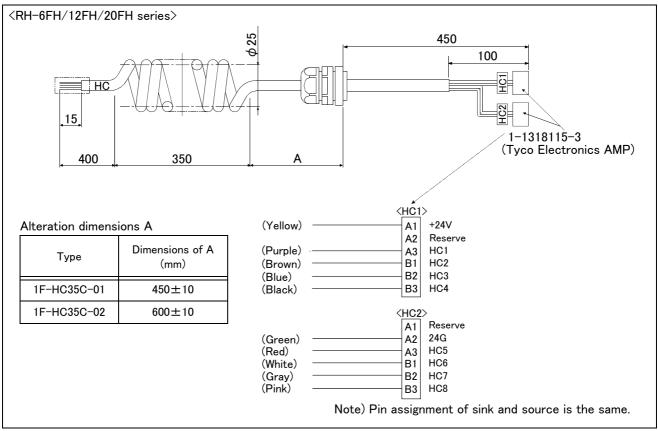


Fig.2-43: Outside dimensional drawing and pin assignment (RH-6FH/12FH/20FH series)

(5) Hand output cable

■ Order type: 1F-GR60S-01

Outline



The hand output cable (solenoid valve connection cable) is an option that is used when a solenoid valve other than one of the solenoid valve set options, is used. One end of the cable has a connector that connects to the input terminal inside the robot. The other end of the cable is connected.

To extend the wiring to the outside of the robot arm, optional external wiring and piping box is required. Refer to Page 79, "(8) External Wiring/Piping box" in detail.

■ Configuration

Table 2-21: Configuration equipment

Part name	Туре	Qty.	Mass (kg) Note1)	Remarks
Hand output cable	1F-GR60S-01	1 cable	0.3	

Note1) Mass indicates one set.

■ Specifications

Table 2-22: Specifications

Item	Specifications	Remarks
Size x Cable core	AWG#24(0.2mm ²) x 12 cores	One side connector and one side cable connection
Total length	1,050mm	

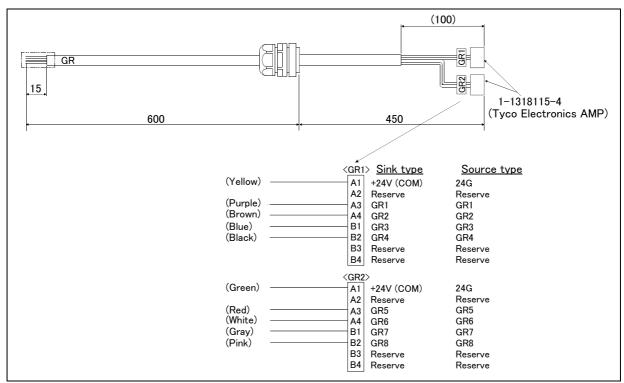


Fig.2-44: Outline dimensional drawing and pin assignment

(6) Hand curl tube

■ Order type: RH-6FH seriesFour sets: 1E-ST0408C-300 RH-12FH/20FH seriesFour sets: 1N-ST0608C-01

Outline



The hand curl tube is a curl tube for the pneumatic hand.

■ Configuration

Table 2-23: Configuration equipment

Part name	Туре	Qty.	Mass(kg) ^{Note1)}	Remarks	
RH-6FH series					
Hand curl tube (Four set: 8 pcs.)	1E-ST0408C-300	1 pc.	0.1	Φ4 tube, 8pcs	
RH-12FH/20FH series					
Hand curl tube (Four set: 8 pcs.)	1N-ST0608C-01	1 pc.	0.4	Φ6 tube, 8pcs	

Note1) Mass indicates one set.

■ Specifications

Table 2-24: Specifications

Item	Specifications				
Item	RH-6FH series	RH-12FH/20FH series			
Material	Urethane	Urethane			
Size	Outside diameter: Φ4 x Inside diameter Φ2.5	Outside diameter: Φ6 x Inside diameterΦ4			

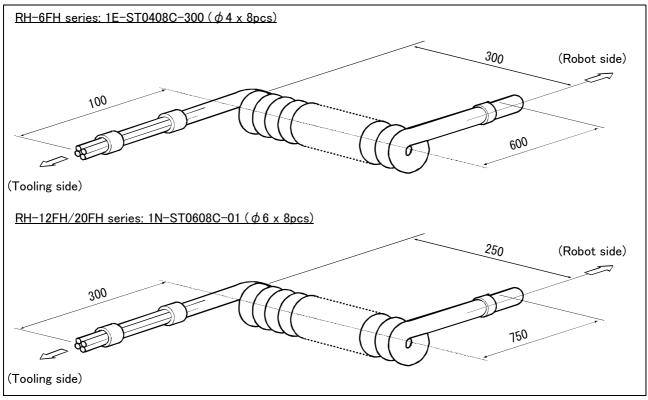
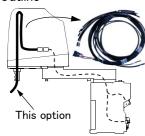


Fig.2-45: Outline dimensional drawing

(7) Internal Wiring/Piping set for hand

Order type: RH-6FH series, 200mm stroke	.1F-HS408S-01
RH-6FH series, 340mm stroke	.1F-HS408S-02
RH-12FH/20FH series, 350mm stroke	.1F-HS604S-01
RH-12FH/20FH series, 450mm stroke	1F-HS604S-02

■ Outline



This set, consisting of air hoses and cables, is for feeding air hoses and hand input signal cables from the No. 2 arm through to the shaft tip.

A plate is already attached to be fixed onto the No. 2 arm, and therefore it is easy to ensure the necessary space for wiring and piping.

This can be used together with the separately sold electromagnetic valve set option.

■ Configuration

Table 2-25 : Configuration equipment

Item	Туре	Qty.	Mass (Kg) Note1)	Remarks
RH-6FH series				
Internal Wiring/Piping set for hand (For 200mm stroke)	1F-HS408S-01	1	0.4	The air hose and the cable for hand input signals are contained. The grease (for application to shaft top) and the
Internal Wiring/Piping set for hand (For 340mm stroke)	1F-HS408S-02	1	0.4	union band (for fixation of the hose and the cable) are attached.
RH-12FH/20FH series				
Internal Wiring/Piping set for hand (For 350mm stroke)	1F-HS604S-01	1	0.4	The air hose and the cable for hand input signals are contained. The grease (for application to shaft top) and the
Internal Wiring/Piping set for hand (For 450mm stroke)	1F-HS604S-02	1	0.4	union band (for fixation of the hose and the cable) are attached.

Note1) Mass indicates one set.

■ Specification

Table 2-26: Specification

Item		Specif	ication		
		1F-HS408S-01 1F-HS604S-01 1F-HS604S-02 1F-HS604S-02		Remarks	
Air hose	hose		φ6 x 4pcs	Both ends are free.	
Hand input signal cable	Signal	AWG #26(0.13mm ²) × 8pcs		The robot arm side is connector (HC1, HC2), and	
Power		AWG #22(0.35mm ²) × 2pcs		one side is free.	
Useable length from the shaft end		380mm	420mm	The length from the shaft end which can be used of customer.	

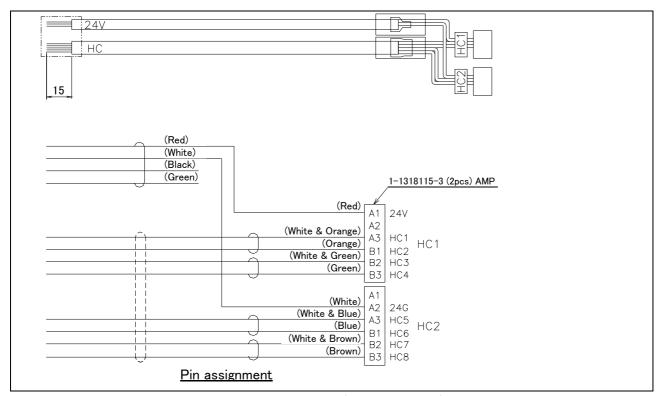
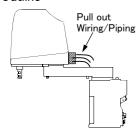


Fig.2-46: Outline dimension drawing and pin assignment (Hand input cable)

(8) External Wiring/Piping box

■ Outline



This is a very useful option when removing the air hoses and signal lines from the rear of the No. 2 arm, and pulling hand wiring and piping out to the robot's exterior. The joint for connects to the external hose is prepared, and the holes which fixes the signal cable to pull out with cable clamp are prepared. Optional hand output cables and hand input cables can be fixed here.

■ Configuration

Table 2-27: Configuration equipment

Part name	Туре	Qty.	Mass (Kg) Note1)	Remarks
H-6FH series				
External Wiring/Piping box	1F-UT-BOX-04	1	0.5	For SExx01 Attachments: • Eight Air hoses (\$\phi\$ 4, connect to solenoid valve) • Installation screw M4 x 12: 4 screws (Conical spring washer, Plain washer) • Simple spanner for resin nuts
	1F-UT-BOX	1	0.5	For SExx02 Attachments: • Eight Air hoses (\$\phi\$ 4, connect to solenoid valve) • Installation screw M4 x 12: 4 screws (Conical spring washer, Plain washer) • Simple spanner for resin nuts
H-12FH/20FH series				
External Wiring/Piping box	1F-UT-BOX-03	1	0.5	For SExx01 Attachments: • Eight Air hoses (\$\phi\$ 6, connect to solenoid valve) • Installation screw M4 x 12: 4 screws (Conical spring washer, Plain washer) • Simple spanner for resin nuts
	1F-UT-BOX-01	1	0.5	For SExx02 Attachments: • Eight Air hoses (∅ 6, connect to solenoid valve) • Installation screw M4 x 12: 4 screws (Conical spring washer, Plain washer) • Simple spanner for resin nuts

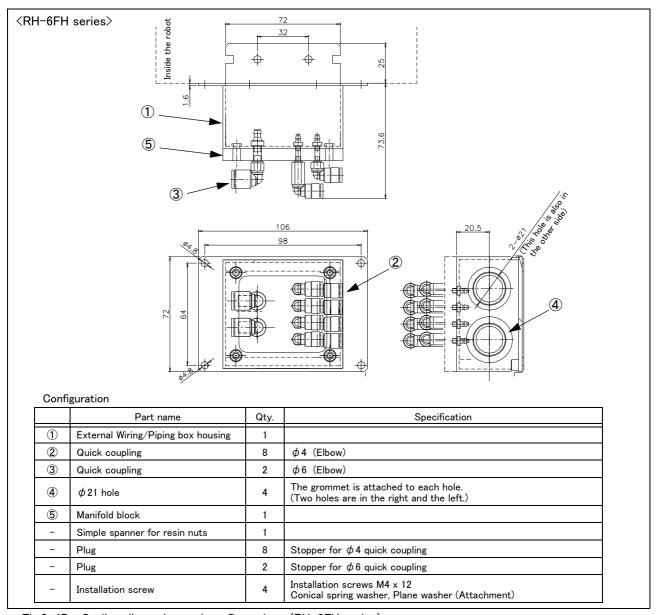
Note1) Mass indicates one set.

■ Specification

Table 2-28 : Specification

Item		Specification	Remarks
RH	-6FH series		
	Outline	106(W) x 73.6(D) x 72(H)	The coupling is included.
	The hole for wiring drawers	φ21 x 4 places	Fix the cable by cable clamp etc.
	Coupling	For ϕ 4 air hose x 8pcs	Installed previously
		For ϕ 6 air hose x 2pcs	
RH	-12FH/20FH series		
	Outline	100(W) x 91.9(D) x 70(H)	The coupling is included.
	The hole for wiring drawers	φ21 x 4 places	Fix the cable by cable clamp etc.
	Coupling	For ϕ 6 air hose x 8pcs	Installed previously

An outside dimension and a component are shown in Fig. 2-47 or Fig. 2-48.



 $\label{eq:Fig.2-47} \textit{Fig.2-47}: \textit{Outline dimension and configurations} \; (\textit{RH-6FH series})$

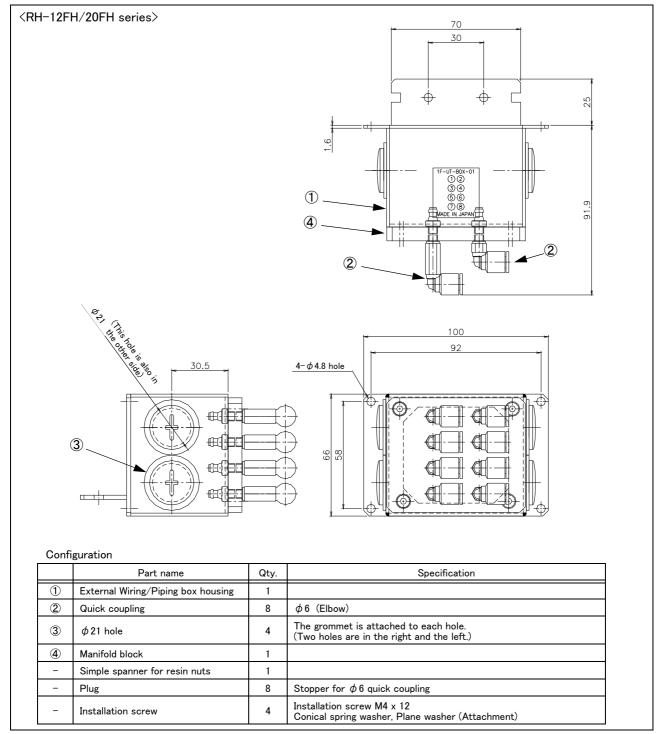


Fig.2-48: Outline dimension and configurations (RH-12FH/20FH series)

2.8 About Overhaul

Robots which have been in operation for an extended period of time can suffer from wear and other forms of deterioration. In regard to such robots, we define overhaul as an operation to replace parts running out of specified service life or other parts which have been damaged, so that the robots may be put back in shape for continued use. Overhaul interval for robots presumably varies with their operating conditions and thus with the degree of the equipment's wear and loss of performance. As a rule of thumb, however, it is recommended that overhaul be carried out before the total amount of servo-on time reaches the predetermined levels (24,000 hours for the robot arm and 36,000 hours for the controller). (See Fig. 2-49.) For specific information about parts to be replaced and timing of overhaul, contact your local service representative.

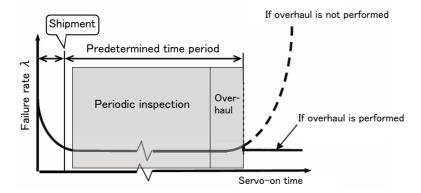


Fig.2-49: Periodic inspection/overhaul periods

2.9 Maintenance parts

The consumable parts used in the robot arm are shown in Table 2–29. Purchase these parts from the designated maker or dealer when required. Some Mitsubishi-designated parts differ from the maker's standard parts. Thus, confirm the part name, robot arm and controller serial No. and purchase the parts from the dealer.

Table 2-29: Consumable part list

No.	Part name	Type Note1)	Usage place	Qty.	Supplier				
Comm	Common parts between robot type								
1	Grease		Reduction gears of each axis	As needed					
2			Ball screw Ball spline	As needed	Mitsubishi Electric				
3	Lithium battery	ER6	Front section of the base	3					
RH-6F	H series		•						
4	Timing belt		J3 axis	1					
5			J4 axis motor side	1	Mitsubishi Electric				
6			J4 axis shaft side	1					
RH-12	FH series								
7	Timing belt		J3 axis	1					
8			J4 axis motor side	1	Mitsubishi Electric				
9			J4 axis shaft side	1					
RH-20	RH-20FH series								
10	Timing belt		J3 axis	1					
11			J4 axis motor side	1	Mitsubishi Electric				
12			J4 axis shaft side	1					

Note1) Confirm the robot arm serial No., and contact the dealer or service branch of Mitsubishi Electric Co., for the type.

3 Controller

3.1 Standard specifications

3.1.1 Basic specifications

Table 3-1: Specifications of controller

	Item	Unit	Specification	Remarks
Туре			CR750- □ HD-1 CR751- □ HD-0	" \(\text{ " in type name shows the load } \) (6kg: "06", 12kg: "12", 20kg: "20") of the robot arm.
Number of control axis			Simultaneously 4	and report urm.
Memory Programmed positions		point	39,000	
capacity	No. of steps	step	78,000	
	Number of program		512	
Robot langu	age		MELFA-BASIC IV, V	
Teaching me	ethod		Pose teaching method, MDI method Note1)	
External	Input and output	point	0/0	Max. 256/256 by option
input and output	Dedicated input/output		Assigned with general-purpose input/output	The signal number of "STOP" input signals is fixing.
	Hand open/close input/output	point	8/8	Built-in
	Emergency stop input	point	1	Dual line
	Door switch input	point	1	Dual line
	Enabling device input	point	1	Dual line
	Emergency stop output	point	1	Dual line
	Mode output	point	1	Dual line
	Robot error output	point	1	Dual line
	Addition axis synchronization		1	Dual line
		point		
	Mode changeover switch input	point	1	Dual line (CR751 controller only)
Interface	RS-422	port	1	Only for T/B
	Ethernet	port	1	10BASE-T/100BASE-Tx
	USB	port	1	Ver.2.0 FullSpeed Only device function
	Additional axis interface	Channel	1	SSCNET III (Connects with MR-J3-BS, MR-J4-B series)
	Tracking interface	Channel	2	
	Option slot	slot	2	For option interface
Power source	Input voltage range	V	RH-6FH series: Single phase AC180 to 253 RH-12FH/20FH series ^{Note2)} : Three phase AC180 to 253, or Single phase AC207 to 253	
	Power capacity	kVA	RH-6FH series: 1.0 RH-12/20FH series: 1.5	Does not include rush current. Note3)
	Power supply frequency	Hz	50/60	
Outline dimensions Note4)		mm	CR750 controller 430(W) x 425(D) x 174(H) CR751 controller 430(W) x 425(D) x 98(H)	Excluding protrusions
Mass		kg	CR750 controller RH-6FH series: Approx. 16 RV-12FH/20FH series: Approx. 18	
Construction	1		CR751 controller: Approx. 12 Self-contained floor type, Opened type. Installation vertically or horizontally	IP20 Note5)
Operating to	emperature range	°C	0 to 40	
Ambient hur		%RH	45 to 85	Without dew drops
Grounding	-	Ω	100 or less	100 Ω or less (class D grounding) ^{Note6)}

Item	Unit	Specification	Remarks
Paint color		Dark gray	Equivalent to Munsell: 3.5PB3.2/0.8

Note1) Pose teaching method: The method to register the current position of the robot arm.

MDI method: The method to register by inputting the numerical value Immediate.

Note2) Both the three phase power supply and the single phase power supply can use this product according to voltage conditions.

Note3) The power capacity is the rating value for normal operation. The power capacity does not include the rush current when the power is turned ON. The power capacity is a guideline and the actual operation is affected by the input power voltage. The power consumption in the specific operation pattern with the RH-6FH is approx. 0.3kW and RH-20FH is approx. 0.49kW. The short circuit breaker should use the following.

* Operate by the current leakage under the commercial frequency domain (50-60Hz). If sensitive to the high frequency ingredient, it will become the cause in which below the maximum leak current value carries out the trip. Note4) Refer to Page 91, "3.3.1 Outside dimensions" for details.

Note5) This controller is standard specification. (Refer to Page 85, "3.1.2 Protection specifications and operating supply".)

Note6) The robot must be grounded by the customer.

3.1.2 Protection specifications and operating supply

A protection method complying with the IEC Standard IP20 (Opened type) is adopted for the controller.

The IEC IP symbols refer only to the degree of protection between the solid and the fluids, and don't indicated that any special protection has been constructed for the prevention against oil and water.

The controller is not chemical-resistant. For installing the controller, avoid places where adhesion of chemicals may occur.

[Information]

• The IEC IP20

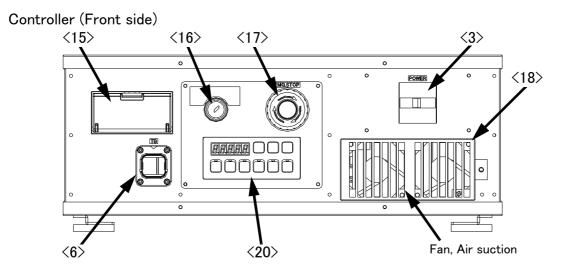
It indicates the protective structure that prevents an iron ball $12^{+0.05}_{0}$ mm diameter, which is being pressed with the power of 3.1 kg ± 10%, from going through the opening in the outer sheath of the supplied equipment.

Refer to the section Page 184, "6.2 Working environment" for details on the working environment.

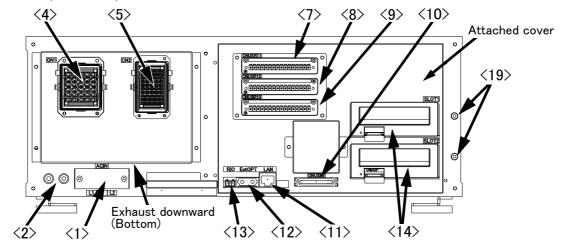
3.2 Names of each part

3.2.1 Controller

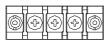
(1) CR750 controller



Controller (Rear side)



<1>: ACIN terminal



There are two types (Type A and B) of terminal. Refer to next page for details.

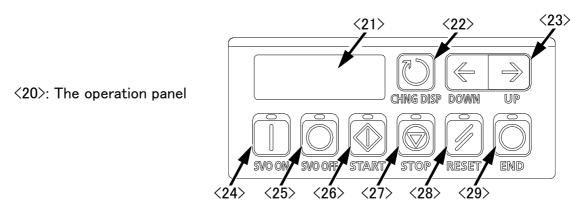


Fig.3-1: Names of controller parts (CR750)

<1> ACIN terminalThe terminal box for AC power source (single phase or three phase, AC200V) input. (Inner side of a cover)

There are two types of the terminal and the terminal differs depending on the model.

Model	Type of the terminal
RH-6FH series	Type A: For single phase L1 L2
	Connect the primary power supply to L1 and L2 terminal.
RH-12FH series RH-20FH series	Type B: For single phase/three phase L1 L2 L3
	When using the three phase primary power supply, connect to L1, L2, and L3 terminal. When using the single phase primary power supply, connect to L1 and L3 terminal.

Refer to a separate manual "INSTRUCTION MANUAL/Controller setup, basic operation, and maintenance" for how to connect a power cable.

- 42> PE terminalThe screw for grounding of the cable. (M4 screw x 2 place)
- <3> Power switch......This turns the control power ON/OFF. (With earth leakage breaker function)
- <4> Machine cable connector (motor signal) (CN1)

Connect with the CN1 connector of the robot arm.

- <5> Machine cable connector (motor power) (CN2)
 - Connect with the CN2 connector of the robot arm.
- <6> T/B connection connector (TB).....This is a dedicated connector for connecting the T/B. When not using T/B, connect the attached dummy connector.
- <7><8><9><10> CNUSR connector.....The connector for input/ output connection dedicated for robot. (a plug connector attached)

<7>: CNUSR11, <8>: CNUSR12, <9>: CNUSR13, <10>: CNUSR2
Refer to a separate manual "INSTRUCTION MANUAL/Controller setup, hasic operation, and maintenance" for the connection method and the

basic operation, and maintenance" for the connection method and the further description of pin assign.

- <11> LAN connector (LAN).....For LAN connection
- <12> ExtOPT connector (ExtOPT) Connect the cable for addition axis control.
- <14> Option slot (SLOT1, SLOT2)....... Install the interface optional. (Install the cover, when not using.)

AUTOMATICOperations from the controller or external equipment are valid. Operations for which the operation mode must be at the external device or T/B are not possible. (Exclude the start of automatic operation.)

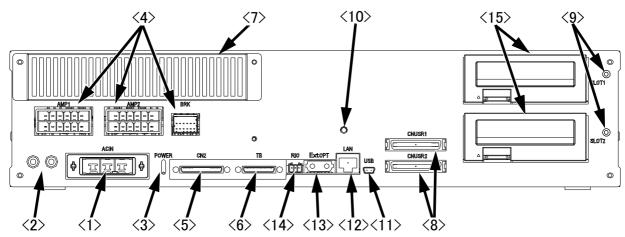
MANUALWhen the T/B is valid, only operations from the T/B are valid. Operations for which the

- operation mode must be at the external device or controller are not possible.
- <17> Emergency stop switch......This switch stops the robot in an emergency state. The servo turns OFF.
- <19> Grounding terminal The grounding terminal for connecting cables of option card. (M3 screw x 2 places)
- <20> Operation panel The operation panel for servo ON/OFF, START/STOP the program etc.
- <21> Display panel (STATUS.NUMBER) The alarm No., program No., override value (%), etc., are displayed.
- <23> UP/DOWN button......This scrolls up or down the details displayed on the "STATUS. NUMBER" display panel.

<24> SVO.ON button	. This turns ON the servo power. (The servo turns ON.)
<25> SVO.OFF button	. This turns OFF the servo power. (The servo turns OFF.)
<26> START button	. This executes the program and operates the robot. The program is run
	continuously.
<27> STOP button	This stops the robot immediately. The servo does not turn OFF.
<28> RESET button	This resets the error. This also resets the program's halted state and
	resets the program.
<29> END button	. This stops the program being executed at the last line or End statement.

(2) CR751 controller

Controller (Front side)



Controller (Rear side)

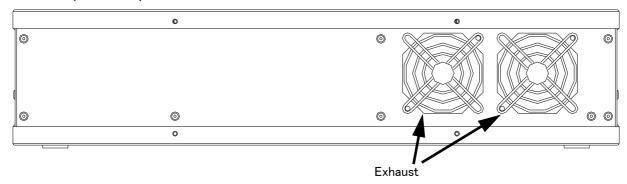


Fig.3-2: Names of controller parts (CR751)

<1> ACIN terminal	The connector for AC power source (single phase or single phase/three phase, AC200V) input. (a socket housing and a terminal are attached).
	Refer to a separate manual "INSTRUCTION MANUAL/Controller setup,
	basic operation, and maintenance" for how to connect a power cable.
(0) DE	·
	The screw for grounding of the cable. (M4 screw x 2 place)
<3> POWER lamp	Lamp of control power source
<4> Machine cable connector (motor po	ower)
	AMP1, AMP2: Motor power, BRK: Motor brake
<5> Machine cable connector (motor si	gnal)
	CN2: Motor signal
<6>T/B connection connector (TB)	.This is a dedicated connector for connecting the R33TB. When not using T/
	B, connect the attached dummy plug.
<7>Filter cover	There is an air filter and buttery inside this cover.
<8>CNUSR connector	.The connector for input/ output connection dedicated for robot.
(CNUSR1、CNUSR2)	(a plug connector attached)
	Refer to a separate manual "INSTRUCTION MANUAL/Controller setup,
	basic operation, and maintenance" for the connection method and
	thefurther description of pin assign.
<9>Grounding terminal	The grounding terminal for connecting cables of option card. (M3 screw x 2
	places)
<10>Power supply charge lamp (CRAR)	GE)

The lamp is to ensure safe timing (prevent electric shocks) when removing the cover (users are not normally required to remove the cover). This lamp is illuminated (red) when electrical energy accumulates on the controller's power supply circuit board due to the robot's servo being ON.

After turning the control power OFF and allowing a few minutes to pass, the lamp will go out.

<11>USB connecting connector (USB).. For USB connection

<12>LAN connector (LAN).....For LAN connection

<13>ExtOPT connector (ExtOPT)......Connect the cable for addition axis control.

 $\verb|\label{localization}| $$<14>RIO connector (RIO).....Connect the extension parallel input/output unit.$

<15>Option slotInstall the interface optional. (Install the cover, when not using.)

(SLOT1, SLOT2)



Use the network equipments (personal computer, USB hub, LAN hub, etc) confirmed by manufacturer. The thing unsuitable for the FA environment (related with conformity, temperature or noise) exists in the equipments connected to USB. When using network equipment, measures against the noise, such as measures against EMI and the addition of the ferrite core, may be necessary. Please fully confirm the operation by customer. Guarantee and maintenance of the equipment on the market (usual office automation equipment) cannot be performed.

3.3 Outside dimensions/Installation dimensions

3.3.1 Outside dimensions

(1) CR750 controller

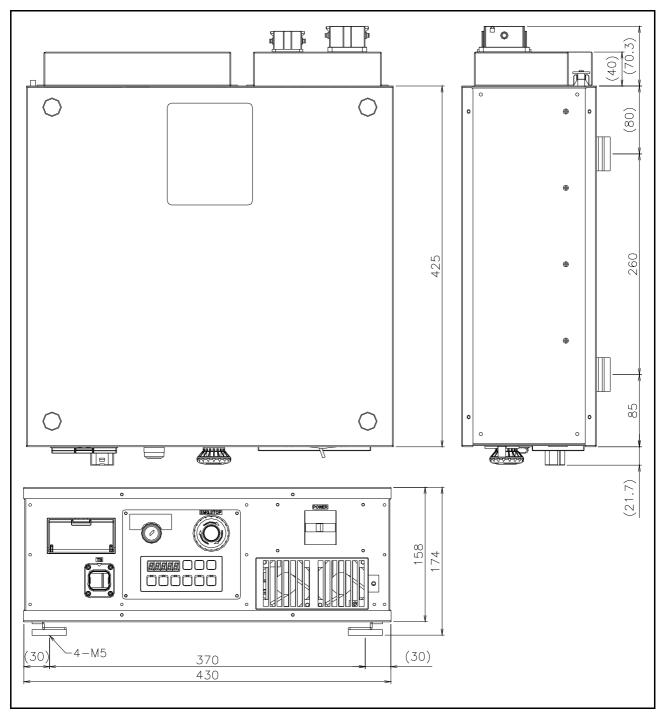


Fig.3-3: Outside dimensions of controller (CR750)

(2) CR751 controller

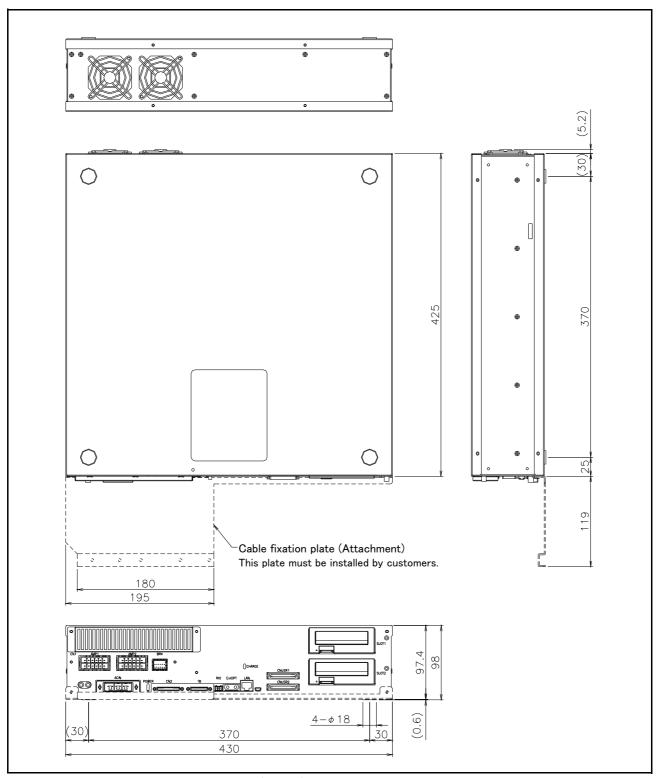
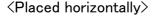
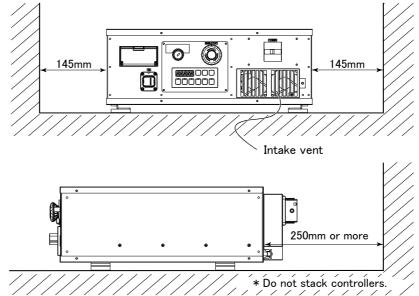


Fig.3-4: Outside dimensions of controller (CR751)

3.3.2 Installation dimensions

(1) CR750 controller





<Placed vertically>

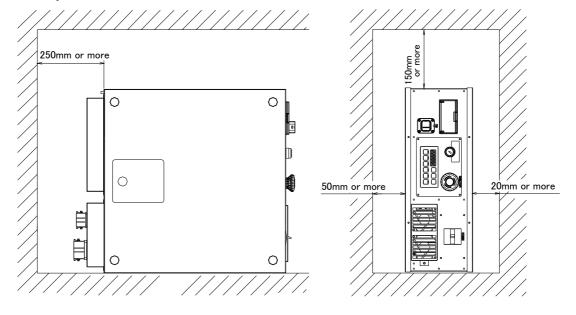


Fig.3-5: Installation of controller (CR750)

⚠CAUTION

Fixing installation section sure for prevention from the fall, when using the controller placing vertically. The reference figure of the metal plate for fixing is shown in Fig. 3-6. You should install the metal plate for fixation to the controller with M4 x 8 or the shorter screw. The screw projection length inside the controller (side board thickness is 1.2 mm) surely makes 6.8 mm or less.

ACAUTION

When storing the controller in a cabinet, etc., take special care to the heat radiating properties and ventilation properties so that the ambient temperature remains within the specification values. And, don't install the controller in the position where direct rays or the heat of lighting hits. The skin temperature of the controller may rise, and the error may occur.

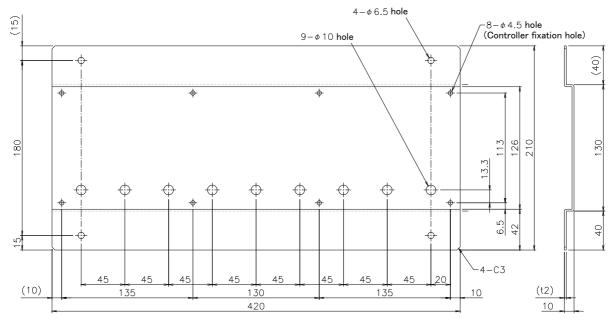
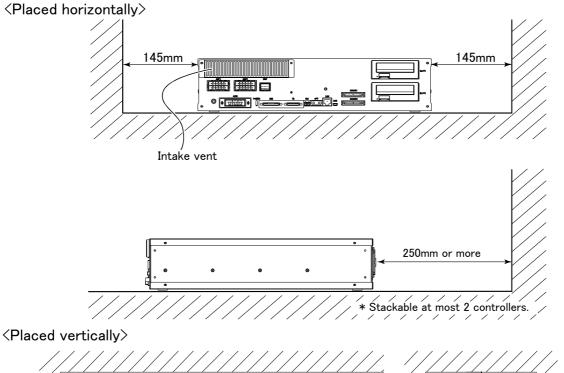


Fig.3-6: Metal plate for fixation to placing vertically (Reference for CR750)

(2) CR751 controller



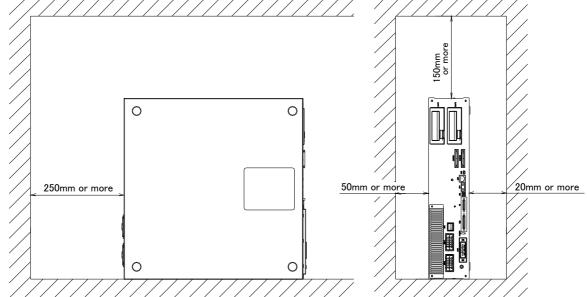


Fig.3-7: Installation of controller (CR751)

CAUTION

Fixing installation section sure for prevention from the fall, when using the controller placing vertically. The reference figure of the metal plate for fixing is shown in Fig. 3-8. You should install the metal plate for fixation to the controller with M4 x 8 or the shorter screw. The screw projection length inside the controller (side board thickness is 1.2mm) surely makes 6.8mm or less.

!\CAUTION

When storing the controller in a cabinet, etc., take special care to the heat radiating properties and ventilation properties so that the ambient temperature remains within the specification values. And, don't install the controller in the position where direct rays or the heat of lighting hits. The skin temperature of the controller may rise, and the error may occur.

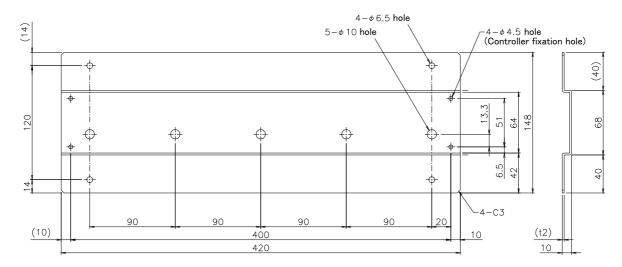


Fig.3-8: Metal plate for fixation to placing vertically (Reference for CR751)

3.4 External input/output

3.4.1 Types

•		
	(1) Dedicated input/output	.These inputs and outputs carry out the robot remote operation and
		status display.
	(2) General-purpose input/output	These are inputs and outputs that the customer can program for peripheral device control.
	(3) Hand input/output	. These are inputs and outputs related to the hand that the customer
		can program.
	(4)Emergency stop/Door switch input	. The wiring for the safe security of the emergency stop etc. is shown in
		on Page 101, "3.6 Emergency stop input and output etc." and on Page
		171. "6.1.7 Examples of safety measures".

⟨For Reference⟩

Linking our GOT1000 Series (GT15) display equipment to the robot controller over the Ethernet permits you to control robot controller's input/output from a GOT (graphic operation terminal).

3.5 Dedicated input/output

Show the main function of dedicated input/output in the Table 3-2. Refer to attached instruction manual "Detailed explanations of functions and operations" in the product for the other functions. Each parameter indicated with the parameter name is used by designated the signal No., assigned in the order of input signal No. and output signal No.

Table 3-2: Dedicated input/output list

Parameter	Input		Note1)		Output
name	Name	Function	Level	Name	Function
TEACHMD	None			Teaching mode output signal	Outputs that the teaching mode is entered.
ATTOPMD		None		Automatic mode output signal	Outputs that the automatic mode is entered.
ATEXTMD		None		Remote mode output signal	Outputs that the remote mode is entered.
RCREADY		None		Controller power ON complete signal	Outputs that external input signals can be received.
AUTOENA	Automatic opera- tion enabled input signal	Allows automatic operation.	L	Automatic operation enabled output signal	Outputs the automatic operation enabled state.
START	Start input signal	Starts all slots.	Е	Operating output sig- nal	Outputs that the slot is operating.
STOP	Stop input signal Stops all slots. The input signal No. is fixed to 0. Note) Use the emergency stop input for stop inputs related to safety.		L	Wait output signal	Outputs that the slot is temporarily stopped.
STOP2	Stop input signal The program during operation is stopped. Unlike the STOP parameter, change of the signal number is possible. Notes) Specification is the same as the STOP parameter.		L	Wait output signal	Outputs that the slot is temporarily stopped. Notes) Specification is the same as the STOP parameter.
SLOTINIT	Program reset input signal	Resets the wait state.	Е	Program selection enabled output signal	Outputs that the slot is in the program selection enabled state.
ERRRESET	Error reset input signal	Resets the error state.	E	Error occurring out- put signal	Outputs that an error has occurred.
CYCLE	Cycle stop input signal	Carries out cycle stop.	E	In cycle stop operation output signal	Outputs that the cycle stop is operating.
SRVOFF	Servo ON enabled input signal	Turns the servo OFF for all mechanisms.	L	Servo ON enabled output signal	Outputs servo-on disable status. (Echo back)
SRVON	Servo ON input signal	Turns the servo ON for all mechanisms.	Е	In servo ON output signal	Outputs the servo ON state.
IOENA	Operation rights input signal	Requests the operation rights for the external signal control.	L	Operation rights output signal	Outputs the operation rights valid state for the external signal control.
MELOCK	Machine lock input signal	Sets/resets the machine lock state for all mechanisms.	Е	In machine lock output signal	Outputs the machine lock state.
SAFEPOS	Evasion point return return input signal Requests the evasion point return operation.		Е	In evasion point return output signal	Outputs that the evasion point return is taking place.
OUTRESET	General-purpose output signal reset signal.		Е		None
EMGERR	None			Emergency stop output signal	Outputs that an emergency stop has occurred.
S1START : S32START	Start input Starts each slot.		E	In operation output	Outputs the operating state for each slot.

Parameter		Input	Note1)		Output
name	Name	Function	Level	Name	Function
S1STOP : S32STOP	Stop input Stops each slot.		L	In wait output	Outputs that each slot is temporarily stopped.
PRGSEL	Program selection input signal Designates the setting value for the program No. with numeric value input signals.		E		None
OVRDSEL	Override selection input signal Designates the setting value for the override with the numeric value input signals.		E		None
IODATA Note2)	Numeric value input (start No., end No.)	Used to designate the program name, override value., mechanism value.	L	Numeric value output (start No., end No.)	Used to output the program name, override value., mechanism No.
PRGOUT	Program No. out- put request	Requests output of the program name.	E	Program No. output signal	Outputs that the program name is being output to the numeric value output signal.
LINEOUT	Line No. output request	Requests output of the line No.	E	Line No. output signal	Outputs that the line No. is being output to the numeric value output signal.
OVRDOUT	Override value output request	· · · · · · · · · · · · · · · · · · ·		Override value out- put signal	Outputs that the override value is being output to the numeric value output signal.
ERROUT	Error No. output request	Requests the error No. output.	Е	Error No. output sig- nal	Outputs that the error No. is being output to the numeric value output signal.
JOGENA	Jog valid input sig- nal	Validates jog operation with the external signals	E	Jog valid output sig- nal	Outputs that the jog operation with external signals is valid.
JOGM	Jog mode input 2- bit	Designates the jog mode.	L	Jog mode output 2- bit	Outputs the current jog mode.
JOG+	Jog feed + side for 8-axes	Requests the + side jog operation.	L	None	
JOG-	Jog feed - side for 8-axes	Requests the - side jog operation.	L	None	
HNDCNTL1 : HNDCNTL3	None			Mechanism 1 hand output signal status : : Mechanism 3 hand output signal status	Mechanism 1: Outputs the status of general-purpose outputs 900 to 907. Mechanism 2: Outputs the status of general-purpose outputs 910 to 917. Mechanism 3: Outputs the status of general-purpose outputs 920 to 927.
HNDSTS1 : HNDSTS3	None			Mechanism 1 hand input signal status : Mechanism 3 hand input signal status	Mechanism 1: Outputs the status of hand inputs 900 to 907. Mechanism 2: Outputs the status of hand inputs 910 to 917. Mechanism 3: Outputs the status of hand inputs 920 to 927.
HNDERR1 : HNDERR3	Mechanism 1 hand error input signal : Mechanism 3 hand error input signal Requests the hand error occur- rence.		L	Mechanism 1 hand error output signal : : Mechanism 3 hand error output signal	Outputs that a hand error is occurring.

Parameter	Input _{No}		Note1)	Note1) Output		
name	Name	Function	Level	Name	Function	
AIRERR1 : AIRERR3	Pneumatic pressure error 1 input signal : Pneumatic pressure error 3 input signal	Request the pneumatic pressure error occurrence.	L	Pneumatic pressure error 1 output signal. : Pneumatic pressure error 3 output signal.	Outputs that a pneumatic pressure error is occurring.	
M1PTEXC : M3PTEXC	None		L	Maintenance parts replacement time warning signal	Outputs that the maintenance parts have reached the replacement time.	
USERAREA Note3)	None			User-designated area 8-points	Outputs that the robot is in the user-designated area.	

Note1) The level indicates the signal level.

- L: Level signal → The designated function is validated when the signal is ON, and is invalidated when the signal is OFF.
- E: Edge signal → The designated function is validated when the signal changes from the OFF to ON state, and the function maintains the original state even when the signal then turns OFF.
- Note2) Four elements are set in the order of input signal start No., end No., output signal start No. and end No.
- Note3) Up to eight points can be set successively in order of start output signal No. and end output signal No.

3.6 Emergency stop input and output etc.

Do wiring of the external emergency stop, the special stop input, the door switch, and the enabling device from the "special input/output" terminal connector.

Table 3-3: Special input/output terminal

Item	Name	Function		
Input	Emergency stop	Applies the emergency stop. Dual emergency line		
Input	Special stop input	Applies the stop. (Refer to Page 109, "3.6.2 Special stop input (SKIP)")		
Input	Door switch	Servo-off. Dual line, normal close (Page 111, "3.6.3 Door switch function")		
Input	Enabling device	Servo-off. Dual line, normal close (Page 111, "3.6.4 Enabling device function")		
Output	Robot error output	Contactor is opening during error occurrence.		
Output	Emergency stop output	The point of contact opens under occurrence of emergency stop of external input signal, emergency stop of OP, emergency stop of T/B.		
Output Mode output MANUAL mode: contactor is opening, AUTOMATIC mode:		MANUAL mode: contactor is opening, AUTOMATIC mode: contactor is closing.		
Output	Magnet contactor control connector output for addition axes	When an additional axis is used, the servo ON/OFF status of the additional axis can be synchronized with the robot arm. (Page 119, "3.9 Magnet contactor control connector output (AXMC) for addition axes")		

^{*}At the time of the power supply OFF, the output point of contact is always open.

[Note] The contact capacity of each input/output terminal is DC24V/10mA - 100mA. Don't connect the equipment except for this range. The use exceeding contact capacity causes failure. In the customer's system, do not ground the + side of 24V power supply prepared by customer for connect to the controller. (related with emergency stop and parallel input/output) If it connects with the controller under the condition that the + side is grounded, it will lead to failure of controller.

Pin number assignment of each terminal and the circuit diagram are shown in Fig. 3-10 (CR750) or Fig. 3-14 (CR751).

3.6.1 Connection of the external emergency stop

The external emergency stop input and door switch input and enabling device input are opened at shipment as shown in Fig. 3-10 (CR750) or Fig. 3-14 (CR751).

Connect the external emergency stop switch and door switch with the following procedure.

And, the example of the connection and notes of the emergency stop are described in Page 171, "6.1.7 Examples of safety measures" Refer to it together

- [Caution] The emergency stop circuit is duplicated inside the controller. The emergency stop switch uses a double contact-type switch, so please be sure to fix both of the contacts to the connector pins as shown below in order to ensure the wiring is duplicated. An error will continue to occur in the event that only one of the pins is connected.
- 1) Please prepare the emergency stop switch, door switch and enabling device.
 - a) External emergency switch
 - · CR750 controller..........CNUSR11 connector "between 3 and 4" and CNUSR12 Connector "between 3 and 4".
 - · CR751 controller..........CNUSR1 connector "between 2 and 27" and "between 7 and 32".
 - b) Door switch
 - CR750 controller..........CNUSR11 connector "between 7 and 8" and CNUSR12 connector "between 7 and 8".
 - · CR751 controller...........CNUSR1 connector "between 4 and 29" and "between 9 and 34".
 - c) Enabling device
 - · CR750 controller..........CNUSR11 connector "between 9 and 10" and CNUSR12 connector "between 9 and 10".
 - CR751 controller...........CNUSR1 connector "between 5 and 30" and "between 10 and 35".
- [Caution] Be sure to use a shield cable for the emergency stop wiring cable. And when operating in an environment that is easily affected by noise, be sure to fix the attached ferrite core (model number: E04SR301334, manufacturer: Seiwa Electric Mfg. Co., Ltd.). Be sure to place the ferrite core more than 30 cm from the connecting terminal section.

ACAUTION

Make sure there are no mistakes in the wiring. Connecting differently to the way specified in the manual can result in errors, such as the emergency stop not being released. In order to prevent errors occurring, please be sure to check that all functions (such as the teaching box emergency stop, customer emergency stop, and door switch) are working properly after the wiring setup is completed.

ACAUTION

You should always connect doubly connection of the emergency stop, the door switch, and the enabling switch. In connection of only one side, if the relay of customer use should break down, it may not function correctly.

And, the output contacts from the robot controller (robot error output, emergency stop output, mode output, addition axis contactor control output) are dual contacts (synchronizes). You should connect surely by dual line with the customer's equipment as well as connection of the emergency stop and the door switch.

ACAUTION

Please make sure to wire the multiple emergency stop switches so that they each function independently. Check and make sure that the emergency stop doesn't only function under an AND condition (when multiple emergency stop switches are ON at the same time).

(1) CR750 controller

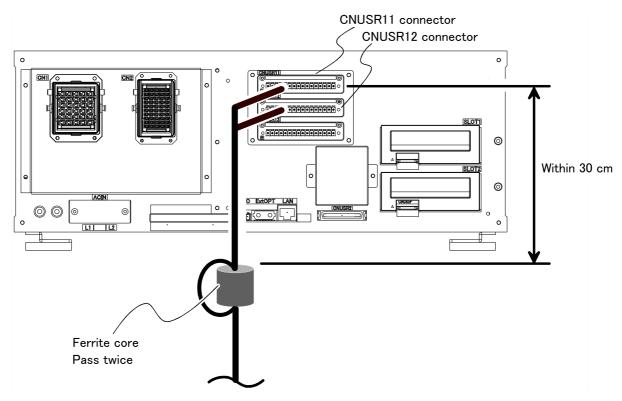
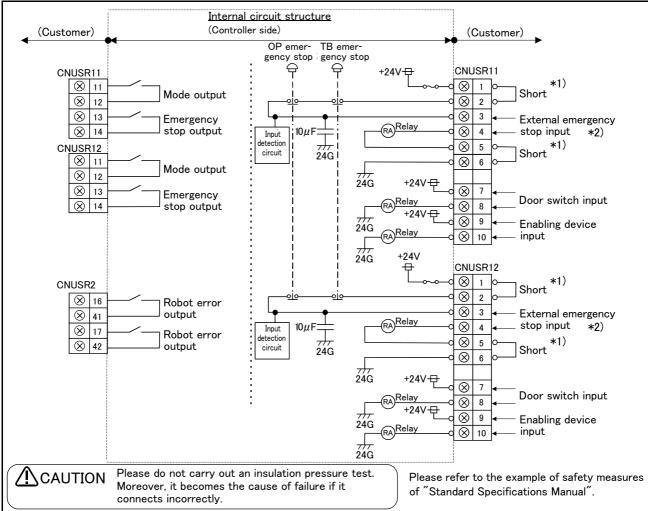


Fig.3-9: Emergency stop cable connection (CR750)



^{*1)} This terminal is opened at factory shipping (unconnected). If power supply inside the controller is used, short-circuit the terminal.

(Do not use the terminal for other purposes such as monitoring the test pulse outputs, or a false detection may occur.)

[Note] In the customer's system, do not ground the + side of 24V power supply prepared by customer for connect to the controller. (related with emergency stop and parallel input/output) If it connects with the controller under the condition that the + side is grounded, it will lead to failure of controller.

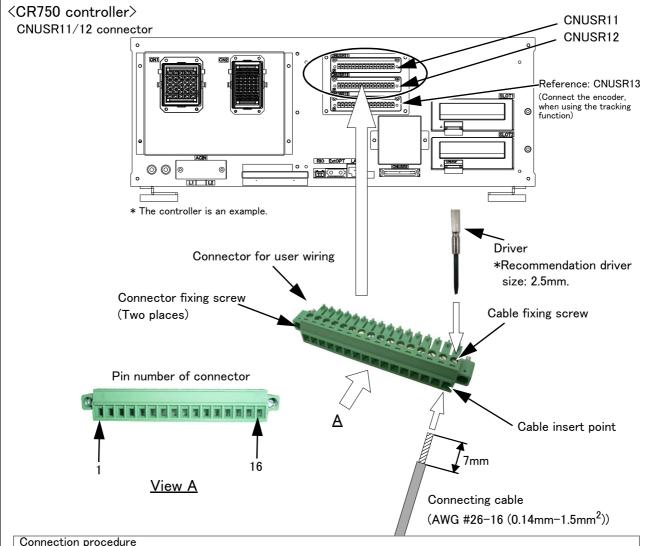
Fig.3-10: External emergency stop connection (CR750)



Place the emergency stop switch in an easily operable position, and be sure to wire it to the emergency stop correctly by referencing Page 171, "6.1.7 Examples of safety

This is a necessary measure in order to ensure safe operation so that the robot can be stopped immediately by pressing the emergency stop switch in the event that the robot malfunctions.

^{*2)} This terminal can be used only for the external emergency stop input to the controller. The terminal cannot be used for the output signal of OP emergency stop or TB emergency stop because the controller's internal circuit contains the input detection circuit and a capacitor.



Connection procedure

Insert the connection cable into the appropriate pin of the user wiring connector that accompanies the product. Fix it securely with a screw and connect the connector to the CNUSR11/CNUSR12 connector at the back of the controller.

Please use an AWG #26 to 16 (0.14 to 1.5mm²) connector cable.

- 1) Prepare the user wiring connector that accompanies the product.
- 2) Loosen the cable fixing screw at the point where the cable is to be inserted. Please use a screwdriver head with a width of 2.5mm to loosen the screw.
- 3) Peel the insulation of the connecting cable to 7mm, and insert it into the cable slot of the corresponding con-
- 4) Be sure to fix the inserted cable securely by fastening a cable fixing screw. (tightening torque of 0.22 to 0.25Nm)
- 5) After the necessary cables save been fixed, connect the connector to the connector (CNUSR11/12) that corresponds with the controller. Connect so that the cable fixing screw is comes on top, and make sure to fix securely by fastening connector fixing screws in two places. A screwdriver head with a width of 2.5mm should be used to fix screws (tightening torque of 0.22 to 0.25Nm).

This concludes the connection procedure.

Fig.3-11: Method of wiring for external emergency stop connection (CR750 (CNUSR11/12))



Makes sure that there is no mistake when connecting to the target connectors. Connecting incorrectly will result in the robot breaking down or malfunctioning. The connector on the controller side that connects to the user wiring connector is CNUSR11 or CNUSR12. Be careful not to connect to CNUSR13 as the robot will not operate properly.

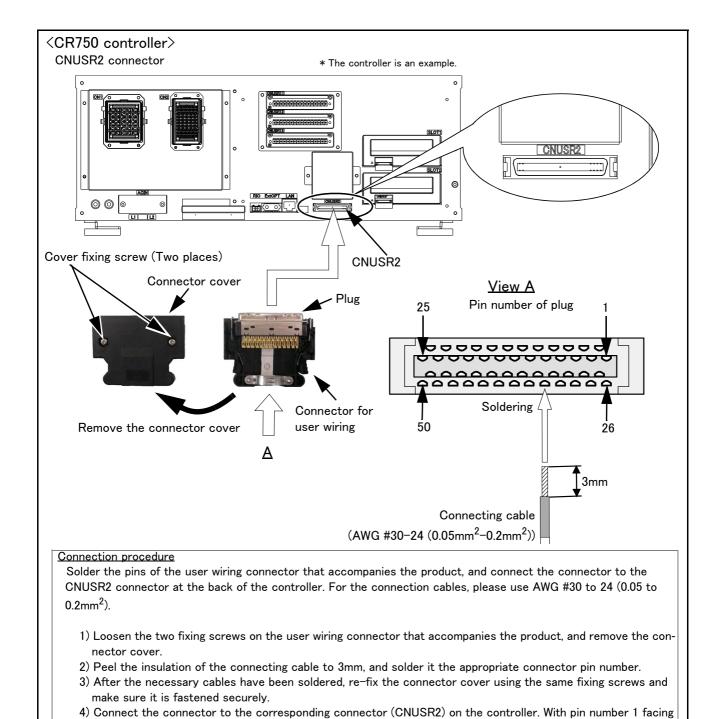


Fig.3-12: Method of wiring for external emergency stop connection (CR750 (CNUSR2))

to the upper right, insert firmly until you hear the connector's latch click in to place.



This concludes the connection procedure.

When soldering please take care to only connect to the specified pin number. Connecting to a different pin number or short-circuiting with another pin will result in the robot breaking down or malfunctioning.

(2) CR751 controller

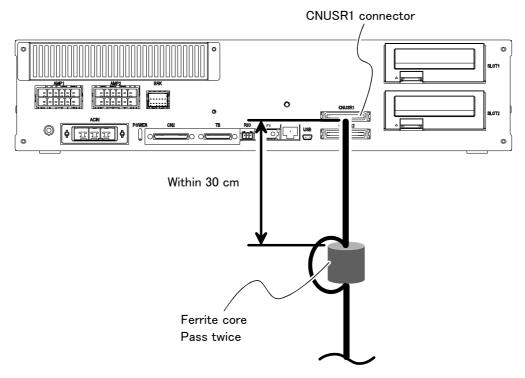
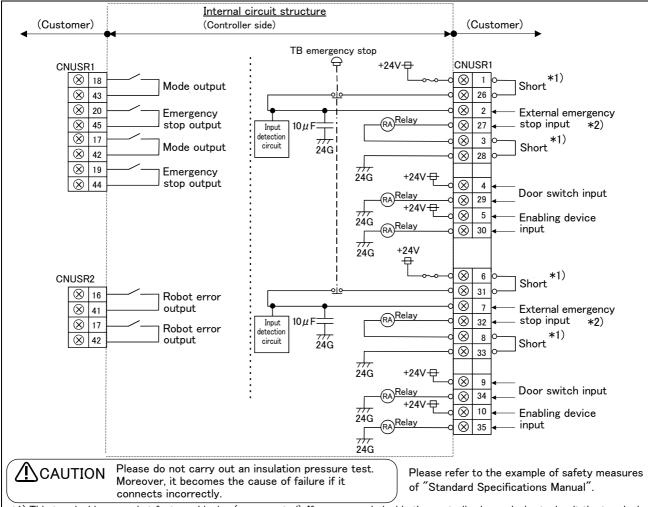


Fig.3-13 : Emergency stop cable connection (CR751)



*1) This terminal is opened at factory shipping (unconnected). If power supply inside the controller is used, short-circuit the terminal.

(Do not use the terminal for other purposes such as monitoring the test pulse outputs, or a false detection may occur.)

[Note] In the customer's system, do not ground the + side of 24V power supply prepared by customer for connect to the controller. (related with emergency stop and parallel input/output) If it connects with the controller under the condition that the + side is grounded, it will lead to failure of controller.

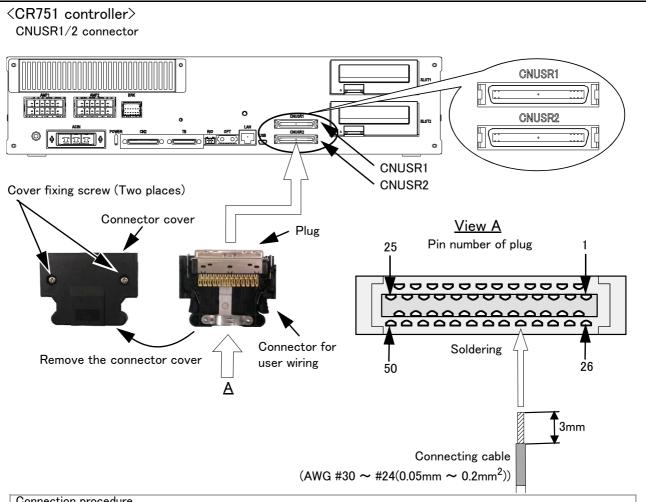
Fig.3-14: External emergency stop connection (CR751)



Place the emergency stop switch in an easily operable position, and be sure to wire it to the emergency stop correctly by referencing Page 171, "6.1.7 Examples of safety measures".

This is a necessary measure in order to ensure safe operation so that the robot can be stopped immediately by pressing the emergency stop switch in the event that the robot malfunctions.

^{*2)} This terminal can be used only for the external emergency stop input to the controller. The terminal cannot be used for the output signal of OP emergency stop or TB emergency stop because the controller's internal circuit contains the input detection circuit and a capacitor.



Connection procedure

Solder the user wiring connector that accompanies the product to the corresponding pin, and connect it to the CNUSR1 or CNUSR2 connector at the back of the controller. For the connection cable, please use AWG #30 to 24 $(0.05 \text{ to } 0.2 \text{mm}^2).$

- 1) Loosen the 2 fixing screws on the user wiring connector that accompanies the product, and remove the con-
- 2) Peel the insulation of the connecting cable to 3mm, and solder it the appropriate connector pin number.
- 3) After the necessary cable has been soldered, re-fix the connector cover sing the same fixing screws and make sure it is fastened securely.
- 4) Connect the connector to the corresponding connector (CNUSR1 or CNUSR2) on the controller. With pin number 1 facing to the upper right, insert firmly until you hear the connector's latch click in to place.

This concludes the connection procedure.

Fig.3-15: Method of wiring for external emergency stop connection (CR751 (CNUSR1/2))



When soldering please take care to only connect to the specified pin number.

Connecting to a different pin number or short-circuiting with another pin will result in the robot breaking down or malfunctioning.

The connectors on the controller side are CNUSR1 (upper side) and CNUSR2 (lower side). Makes sure that there is no mistake when connecting to the target connectors. Connecting incorrectly will result in the robot breaking down or malfunctioning.

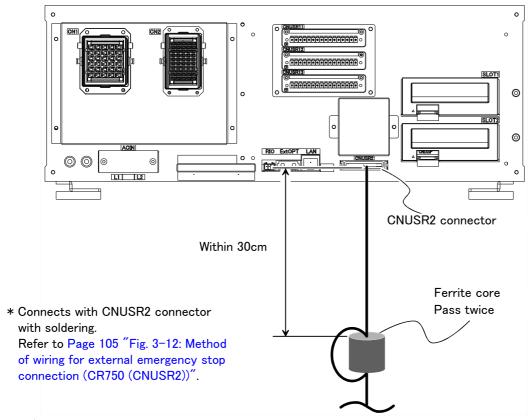
3.6.2 Special stop input (SKIP)

The skip is the input signal to stop the robot. The pin 9, 34 of the CNUSR2 connector shown in Fig. 3-16 (CR750) or Fig. 3-17 (CR751).

Table 3-4: Special stop input electric specification

Item		Specifications	Internal circuit
Туре		DC input	
No. of input poi	nt	1	
Insulation meth	od	Photo-coupler insulation	
Rated input vol	tage	DC24V	,
Rated input cur	rent	Approx. 11mA	9 +24V(COM)
Working voltage range		DC 21.6 ~ 26.4V (Ripple rate within 5%)	330 34
ON voltage/ON	current	DC 8V or more / 2mA or more	2.2k Input
OFF voltage/O	FF current	DC 4V or less / 1mA or less	2.20
Input resistance		Approx. 2.2 k Ω	
Response	OFF → ON	1ms or less	
time	ON → OFF	1ms or less	
Common method		1 point per common	
External wire connection method		Connector	

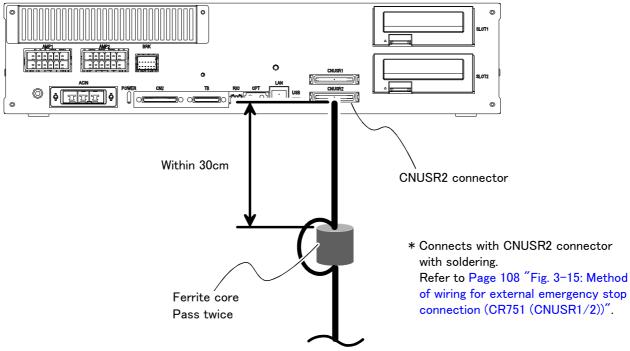
(1) CR750 controller



Note) In the customer's system, do not ground the + side of 24V power supply prepared by customer for connect to the controller. (related with emergency stop and parallel input/output) If it connects with the controller under the condition that the + side is grounded, it will lead to failure of controller.

Fig.3-16: Connection of the special-stop-input (CR750)

(2) CR751 controller



Note) In the customer's system, do not ground the + side of 24V power supply prepared by customer for connect to the controller. (related with emergency stop and parallel input/output) If it connects with the controller under the condition that the + side is grounded, it will lead to failure of controller.

Fig.3-17: Connection of the special-stop-input (CR751)

3.6.3 Door switch function

This function retrieves the status of the switch installed on the door of the safety fence, etc., and stops the robot when the door is opened. This differs from an emergency stop in that the servo turns OFF when the door is opened and an error does not occur. Follow the wiring example shown in Page 103 "Fig. 3–10: External emergency stop connection (CR750)" or Page 107 "Fig. 3–14: External emergency stop connection (CR751)", and Page 171, "6.1.7 Examples of safety measures". Those figure explains the wire is contact closes when the door is closed. Details of this function according to the robot status are shown below.

*During automatic operationWhen the door is opened, the servo turns OFF and the robot stops. An error occurs. The process of the restoration: Close the door, reset the alarm, turn on the servo, and restart

*During teaching......Even when the door is opened, the servo can be turned ON and the robot moved using the teaching pendant.

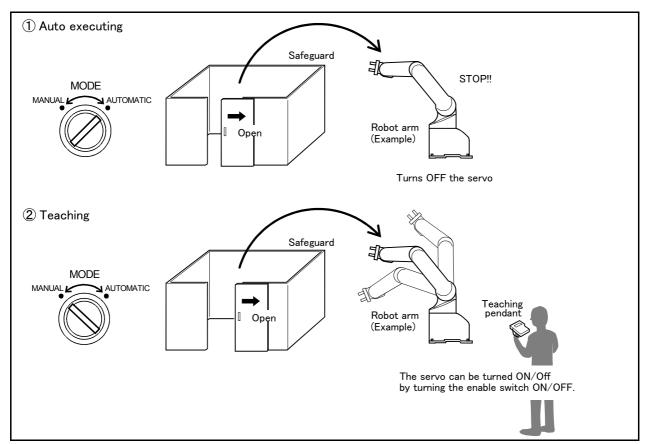


Fig.3-18: Door switch function

3.6.4 Enabling device function

When the abnormalities occur in teaching operations etc., the robot's servo power can be immediately cut only by switch operation of the enabling device*

(servo-off), and the safety increases. To use the robot safely, please be sure to connect the enabling device.

(1) When door is opening

Please do teaching by two-person operations. One person has T/B, the other has enabling device. Turn on the servo power, in the condition that both of switches are pushed. (Enable switch of T/B and enabling device) Then the jog operation will be available. You can off the servo power only by releasing the switch of the enabling device. And, care that the servo-on and releasing the brake cannot be done in the condition that the switch of the enabling device is released.

(2) When door is closing

You can turn on the servo power by operation of only T/B. In this case perform jog operation outside the safeguard sure.

^{*1)} Recommendation products: HE1G-L20MB (IDEC)

(3) Automatic Operation/Jog Operation/Brake Release and Necessary Switch Settings
The following is a description of various operations performed on the robot and switch settings that are required.

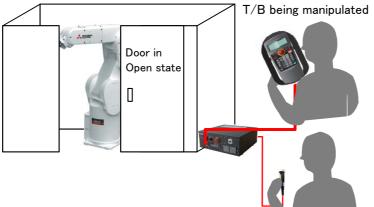
Table 3-5: Various operations and necessary switch settings

		Related switch settings Note1)					
No	Operation	Mode of controller	T/B enable/ disable	T/B enable switch	Enabling device input terminal	Door switch input terminal	Description
1	Jog operation	Manual	Enable	ON	Close(ON)	_	If the enabling device input is set to Close (On), the state of door switch input does not matter.
2	Jog operation Note2)	Manual	Enable	ON	Open(OFF)	Close (Door Close)	If the enabling device input is set to Open (Off), door switch input must be in a state of Close
3	Brake release Note3)	Manual	Enable	ON	Close(ON)	_	Irrespective of the state of door switch input, enabling device input must be in a state of Close (On).
4	Automatic operation	Automatic	Disable	_	_	Close (Door Close)	Door switch input must always be in a state of Close (Door Close).

Note1) "-" in the table indicates that the state of switch concerned does not matter.

Refer to the following for operation of each switch.

- Mode of CR750 controller: Page 86, "3.2 Names of each part"
 Mode of CR751 controller: Page 113, "3.7 Mode changeover switch input"
 T/B enable/disable: Page 122, "(1) Teaching pendant (T/B)"
 T/B enable switch: Page 122, "(1) Teaching pendant (T/B)"
 Enabling device input terminal: Page 171, "6.1.7 Examples of safety measures"
 Door switch input terminal: Page 171, "6.1.7 Examples of safety measures"
- Note2) Jog operation, if door switch input is set for Close (Door Close), must be performed outside the safety barrier.
- Note3) It is imperative that brake release operation be carried out by two persons. One person turns on the enabling device ("Close" on the enabling device input terminal) while the other manipulates the T/B. Brake release can be effected only when both of the enabling switch device and the T/B enable switch are placed in intermediate position (lightly gripped position). At this point, the state of door switch input does not matter.



Enabling device being manipulated

ACAUTION

Upon the release of brake, the robot arm may fall under its own weight depending on the axis which has been released. For added safety, provide support or take other precaution to prevent the falling of the arm.

Fig.3-19: Brake release operation

3.7 Mode changeover switch input

Connect the key switch of customer prepared and change the right of robot's operation by switch operation. The key switch can be installed in the operation panel of customer preparation.

<Right of operation (mode)>

AUTOMATIC......The operation from external equipment becomes available. Operation which needs the right of operation from T/B cannot be performed. It is necessary to set the parameter for the rights of operation to connection with external equipment. Refer to the separate volume, "Instruction Manual/Detailed Explanation of Functions and Operations" for detail.

MANUALWhen T/B is available, only the operation from T/B becomes available. Operation which needs the right of operation from external equipment cannot be performed.

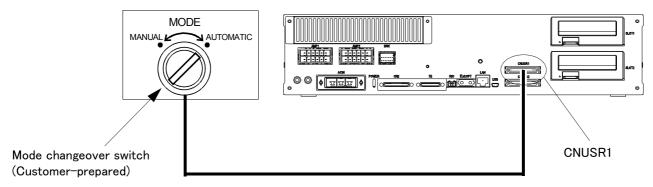


Fig.3-20: Mode changeover switch image figure (CR751)

(1) Specification of the key switch interface

The function and specification of the key switch interface are shown below.

Table 3-6: Function of the key switch interface

Pin number and	Pin number and Function (Connector: CNUSR1)		ode ^{Note1)}
Pin number Function		MANUAL	AUTOMATIC
49	49 1st line KEY input		
24	Power supply +24V of pin number 49	Open	Close
50	2nd line KEY input		
25	Power supply +24V of pin number 50	Open	Close

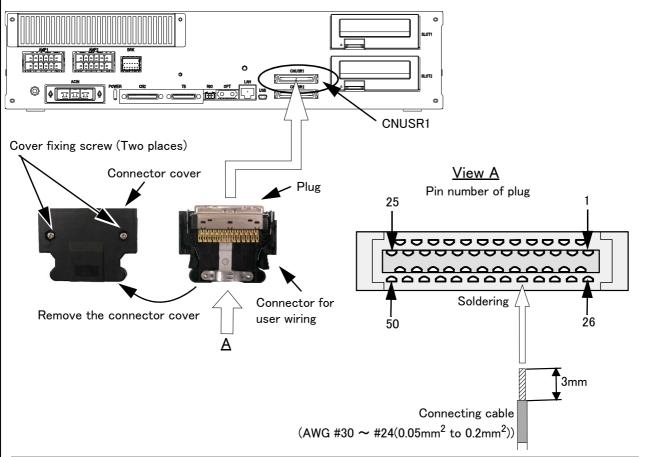
Note1) The mode changes by both opening or both closing between 49-24 pin and between 50-25 pin. When input states differ between two lines, error H0044 (OP Mode key line is faulty) will occur.

[Note] In the customer's system, do not ground the + side of 24V power supply prepared by customer for connect to the controller. (related with emergency stop and parallel input/output) If it connects with the controller under the condition that the + side is grounded, it will lead to failure of controller.

Table 3-7: Specification of the mode changeover switch input

Item	Specification	Remarks
Rated voltage	DC24V	Supply from the controller.
Current rating	Approx. 10mA	Select the switch or button which operates normally in 24V/10mA.
Input resistance	Approx. 2.2kΩ	
Response time (OFF->ON)	Approx. 15ms	Example: The response time the program starts, after pushing the run button.
Common method	1 point per common	
Connection method	Connector	
Conformity electric wire size	AWG#24 to #18	0.2 to 0.75mm ²
Maker/Type	-	Maker: PHOENIX CONTACT/ Type: FKC2.5/4-STF-5.0B

(2) Connection of the mode changeover switch input



Connection procedure

Solder the user wiring connector that accompanies the product to the corresponding pin, and connect it to the CNUSR1 connector at the back of the controller. For the connection cable, please use AWG #30 to 24 (0.05 to 0.2mm^2).

- 1) Loosen the 2 fixing screws on the user wiring connector that accompanies the product, and remove the connector cover.
- 2) Peel the insulation of the connecting cable to 3mm, and solder it the appropriate connector pin number.
- 3) After the necessary cable has been soldered, re-fix the connector cover sing the same fixing screws and make sure it is fastened securely.
- 4) Connect the connector to the corresponding connector (CNUSR1) on the controller. With pin number 1 facing to the upper right, insert firmly until you hear the connector's latch click in to place.

This concludes the connection procedure.

Fig.3-21: Connection of the mode changeover switch input (CR751)

3.8 Additional Axis Function

This controller is equipped with an additional axis interface for controlling an additional axis when a traveling axis or rotary table is added to the robot. A maximum of eight axes of servo motors can be controlled at the same time by connecting a general-purpose servo amplifier (MR-J3-B, MR-J4-B series) that supports Mitsubishi's SSCNET III. Refer to the separate "Additional axis interface Instruction Manual" for details on the additional axis function.

3.8.1 Wiring of the Additional Axis Interface

Table 3-8 shows the connectors for additional axes inside the controller. Fig. 3-22 (CR750) and Fig. 3-23 (CR751) shows a connection example (configuration example).

Table 3-8: Dedicated connectors inside the controller

Name	Connector name	Details
Connector for additional axes	ExtOpt	The connector for connecting the general-purpose servo amplifier.

(1) CR750 controller

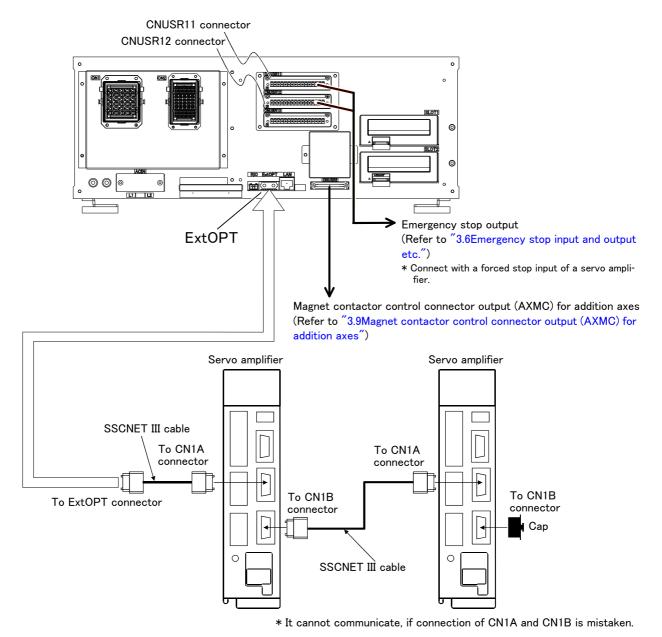
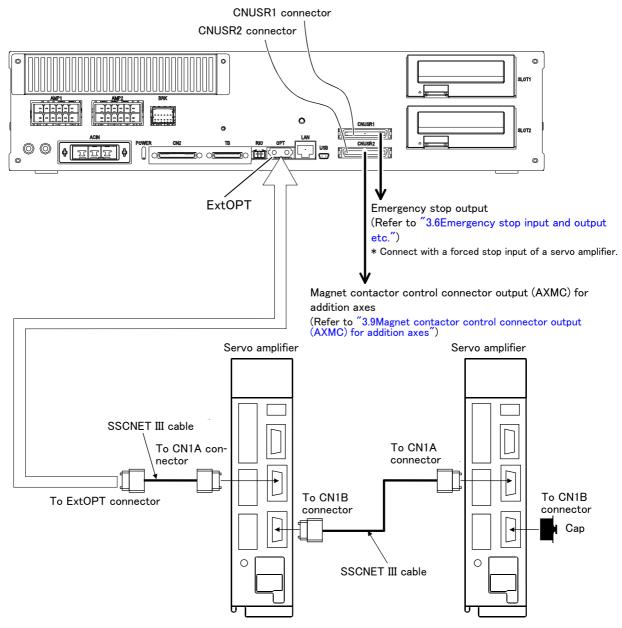


Fig.3-22: Example of addition axis connection (CR750)

(2) CR751 controller



* It cannot communicate, if connection of CN1A and CN1B is mistaken.

Fig.3-23: Example of addition axis connection (CR751)

- (3) Example of the installation of the noise filter
- 1) EMC filter (recommended)

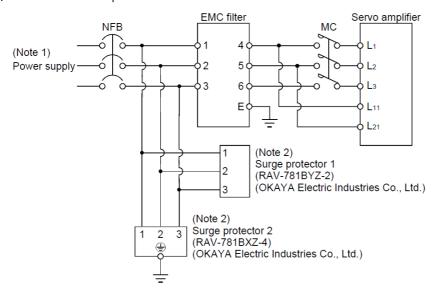
Please install the recommendation filter shown below according to the example of connection.

1) Combination with the servo amplifier

Servo amplifier	Recommended filter (Soshin Electric)		Mass [kg]/[lb])	
Servo ampilier	Model	Leakage current [mA]	Mass [kg]([lb])	
MR-J3-10B to MR-J3-100B MR-J3-10B1 to MR-J3-40B1	(Note) HF3010A-UN	5	3 (6.61)	
MR-J3-250B • MR-J3-350B	(Note) HF3030A-UN		5.5 (12.13)	
MR-J3-500B • MR-J3-700B	(Note) HF3040A-UN	1.5	6.0 (13.23)	
MR-J3-11KB to MR-J3-22KB	(Note) HF3100A-UN	6.5	15 (33.07)	
MR-J3-60B4 • MR-J3-100B4	TF3005C-TX		6(12.22)	
MR-J3-200B4 to MR-J3-700B4	TF3020C-TX		6(13.23)	
MR-J3-11KB4	TF3030C-TX	5.5	7.5(16.54)	
MR-J3-15KB4	TF3040C-TX		10.5(07.50)	
MR-J3-22KB4	TF3060C-TX		12.5(27.56)	

Note. A surge protector is separately required to use any of these EMC filters.

2) Connection example



Note1) For 1-phase 200V to 230VAC power supply, connect the power supply to L1, L2 and leave L3 open. There is no L3 for 1-phase 100 to 120 VAC power supply.

Note2) The example is when a surge protector is connected.

Fig.3-24: Example of EMC noise filter installation

2) Line noise filter

This filter is effective in suppressing noises radiated from the power supply side and output side of the servo amplifier and also in suppressing high-frequency leakage current (zero-phase current) especially within 0.5MHz to 5MHz band.

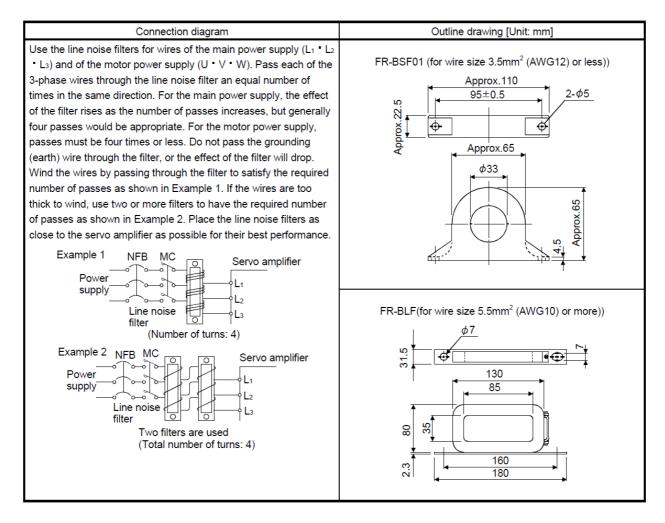


Fig.3-25: Example of noise filter installation

3.9 Magnet contactor control connector output (AXMC) for addition axes

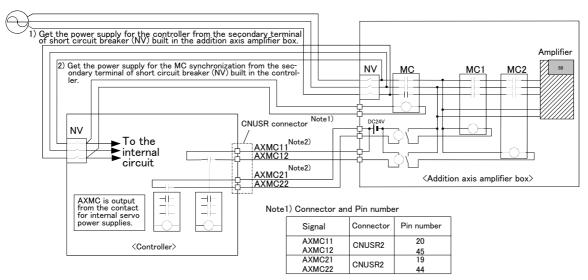
When an additional axis is used, the servo ON/OFF status of the additional axis can be synchronized with the servo ON/OFF status of the robot itself by using the output contact (AXMC) provided on the rear or inside of the controller and configuring a circuit so that the power to the servo amplifier for the additional axis can be turned off when this output is open.

An example circuit is shown Fig. 3-26. An image of how to connect the controller connector are shown Fig. 3-27 and Fig. 3-28.

When you are using an additional axis, please perform appropriate circuit connections by referring to these draw-

Refer to the separate "Additional axis interface Instruction Manual" for details on the additional axis function.

Note1) you use the addition axis function as a user mechanism who became independent of the robot arm, please do not connect this output signal. Servo-on of the user mechanism may be unable.



Note2) This output is opened, if the robot turns off the servo by occurrence of alarm etc. <Electric specification>
 DC24V/10mA to 100mA

[Note] In the customer's system, do not ground the + side of 24V power supply prepared by customer for connect to the controller. (related with emergency stop and parallel input/output) If it connects with the controller under the condition that the + side is grounded, it will lead to failure of controller.

Fig.3-26: Example of circuit for addition axes of Magnet contactor control output

(1) CR750 controller

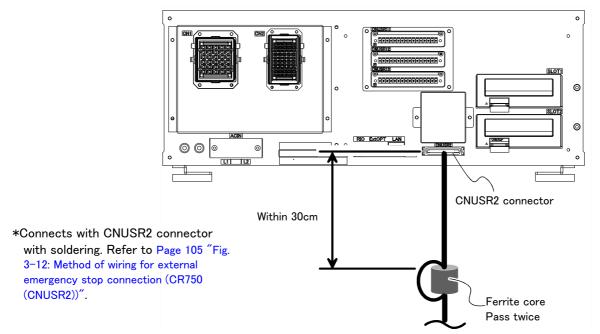


Fig.3-27: AXMC terminal connector (CR750)

(2) CR751 controller

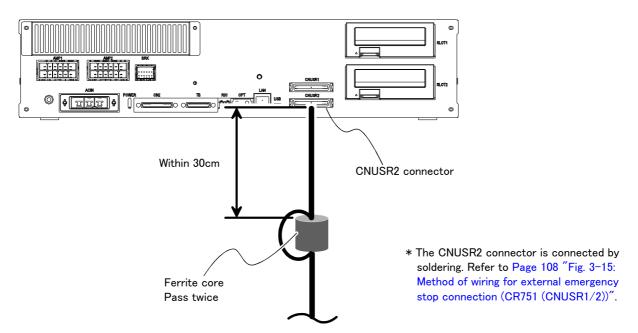


Fig.3-28: AXMC terminal connector (CR751)

3.10 Options

■ What are options?

There are a variety of options for the robot designed to make the setting up process easier for user needs. User installation is required for the options.

Options come in two types: "set options" and "single options".

1.	Set optionsA combination of single options and parts that together, form a set for serving
	some purpose.

2. Single options......That are configured from the fewest number of required units of a part. Please choose user's purpose additionally.

(1) Teaching pendant (T/B)

■ Order type: CR750 controller......
■ R32TB: Cable length 7m
■ R32TB-15: Cable length 15m
CR751 controller.....
■ R33TB: Cable length 7m
■ R33TB-15: Cable length 15m

Outline



This is used to create, edit and control the program, teach the operation position and for jog feed, etc.

For safety proposes, a 3-position enable switch is mounted.*1)

■ Configuration

Table 3-9: Configuration device

	Part name Type		Qty. Mass (kg) Note1)		Remarks			
CR	CR750 controller							
	Teaching pendant	R32TB	Fight	1.7	Cable length is 7m. Hand strap is attached.			
		R32TB-15	Either one pc.	2.8	Cable length is 15m. Hand strap is attached.			
CR	CR751 controller							
	Teaching pendant	R33TB	Fither and no	1.7	Cable length is 7m. Hand strap is attached.			
	R33TB-15 Either one pc.		Either one pc.	2.8	Cable length is 15m. Hand strap is attached.			

Note1) Mass indicates one set.

Specifications

Table 3-10: Specifications

Items	Specifications	Remarks		
Outline dimensions	imensions 195(W) x 292(H) x 106(D) (refer to outline drawing)			
Body color	Dark gray			
Mass	Approx. 0.9kg (only arm, excluding cable)			
Connection method	Connection method Connection with controller and connector.			
Interface	RS-422			
Display method	LCD method: 24 characters x 8 lines, LCD illumination: with backlight	At 8x8 font		
Operation section	36 keys			

In ISO/10218 (1992) and JIS-B8433 (1993), this is defined as an "enable device". These standards specify that the robot operation using the teaching pendant is enabled only when the "enable device" is at a specified position. With the Mitsubishi Electric industrial robot, the above "enable device" is configured of an "Enable/Disable switch" and "Enable switch".

The 3-position enable switch has three statuses. The following modes are entered according to the switch state.

- a) "Not pressed"The robot does not operate. *)
- b) "Pressed lightly".....The robot can be operated and teaching is possible.
- c) "Pressed with force"The robot does not operate. $^{*)}$

^{*1) &}lt;3-position enable switch>

^{*)} Operations, such as program editing and status display, other than robot operation are possible.

Safety is secured as the servo power is turned OFF simultaneously with the input of the emergency stop.

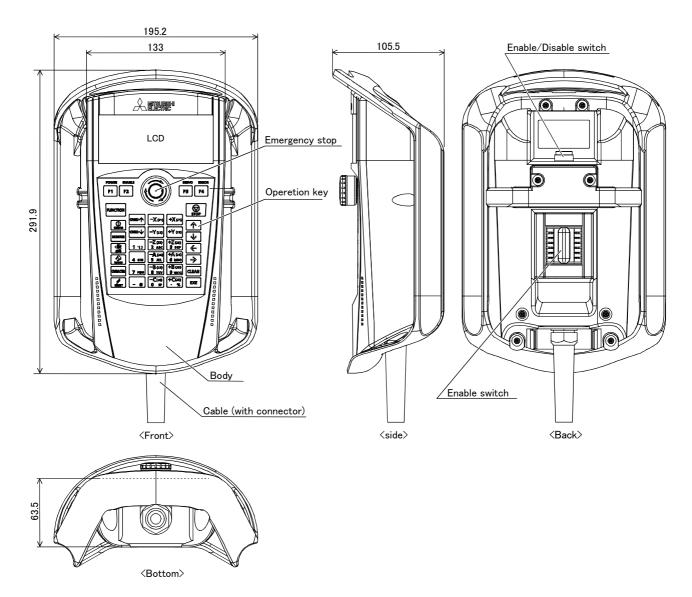


Fig.3-29: Outside dimensions of teaching pendant

■ Installation method

The teaching pendant is connected to the $\ensuremath{\mathsf{T/B}}$ connector on the front of the controller.

■ Key layout and main functions

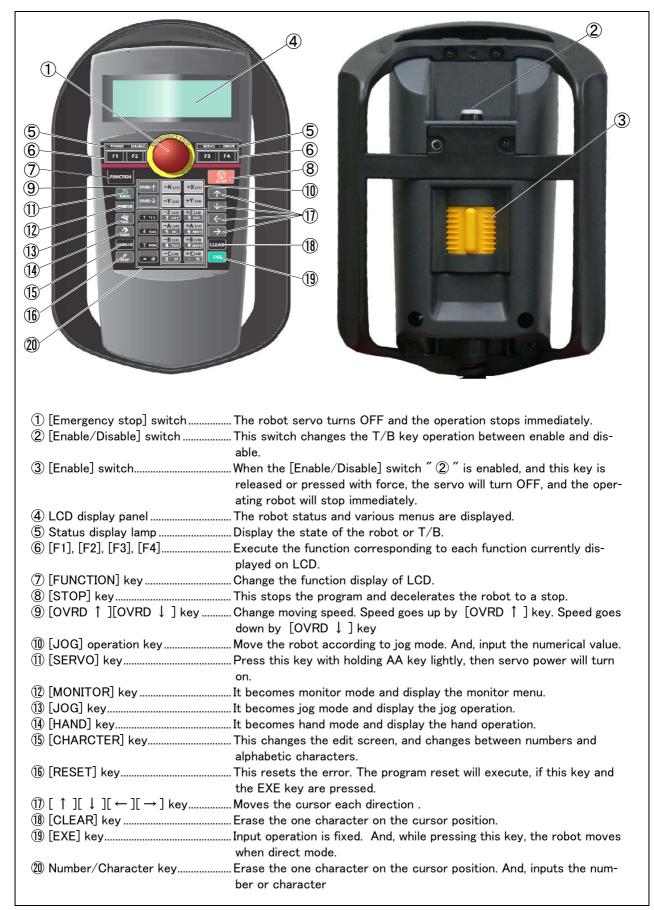


Fig.3-30: Teaching pendant key layout and main functions

(2) Parallel I/O interface

■ Order type : ● 2D-TZ368 (Sink type)/2D-TZ378 (Source type)

Outline



This is used to expand the external inputs and outputs

• The connecting cable with external equipment is not attached. Since we are preparing the external input-and-output cable (2D-CBL05 or 2D-CBL15) as the option, please use. Notes)Although the combined use with the parallel input-and-output unit (2A-RZ361/2A-RZ371) of another option is also possible, please use the setup of the station number by the different number separately. The station number is automatically determined by the position of the option slot which installed this interface. (station number 0 to 1)

■ Configuration

Table 3-11: Configuration device

Part name	Туре	Qty.	Mass (kg) Note1)	Remarks
Parallel I/O interface		Either		Input/output 32 points/32 points
	2D-TZ378	one pc.		2D-TZ368 is sink type. 2D-TZ378 is source type.

Note1) Mass indicates one set.

■ Specifications

Table 3-12: Electrical specifications of input circuits

Item		Specification		Internal circuit
Туре	Туре			<sink type=""></sink>
Number of input po	ints	32		.+24V/+12V
Insulation method		Photo coupler insulation		(COM)
Rated input voltage)	DC12V	DC24V	
Rated input current	t	Approx. 3mA	Approx.9mA	□
Working voltage rar	Working voltage range		d be less than 5%)	2.7K
ON voltage/ON cui	rrent	DC8V or more/2mA or more		
OFF voltage/ OFF	current	DC4V or less/1mA or less		<pre> <source type=""/> </pre>
Input resistance		Approx. 2.7k Ω		2.7K Input
Response time	OFF-ON	10ms or less(DC24V)		7,07,000
ON-OFF		10ms or less(DC24V)		
Common method		32 points per common		—
External cable connection method		Connector		

Specification Internal circuit Item Transistor output <Sink type> Type No. of output points +24V/+12V Insulation method Photo-coupler insulation DC12V/DC24V Rated load voltage Output DC10.2 ~ 30V (peak voltage DC30V) Rated load voltage range Max. load current 0.1A/point (100%) Leakage current at OFF Within 0.1mA 24G/12G DC0.9V(TYP.) Note1) Max. voltage drop at ON OFF-ON 10ms or less(Resistance load) (hardware response time) Respons <Source type> e time ON-OFF 10ms or less(Resistance load) (hardware response time) +24V/+12V Fuse rating Fuse 1.6A(one per common) Replacement possible (max. 3) Common method 16 points per common (common terminal: 2points) External wire connection Connector method 24G/12G DC12/24V(DC10.2 ~ 30V) External Voltage power 60mA(TYP.DC24V per common)(base drive current) Current supply

Table 3-13: Electrical specifications for the output circuits

Note1) The maximum voltage drop value at signal ON.

Refer to it for the equipment connected to the output circuit.



Caution The protection fuse of the output circuit prevents the failure at the time of the load short circuit and incorrect connection. The load connected of the customer should be careful not to exceed maximum rating current. The internal transistor may be damaged if maximum rating current is exceeded.

Installation method

The expansion parallel input/output interface is installed in the controller. Refer to separate "Instruction Manual/ Controller setup, basic operation, and maintenance" for details on the installing method.

If it installs in the option SLOT of the controller, the station number will be assigned automatically.

SLOT1: station number 0 (0 to 31)

SLOT2: station number 1 (32 to 63)



Caution If it uses together with parallel input-and-output unit 2A-RZ361/2A-RZ371, please do not overlap with the station number of the parallel input-and-output interface.

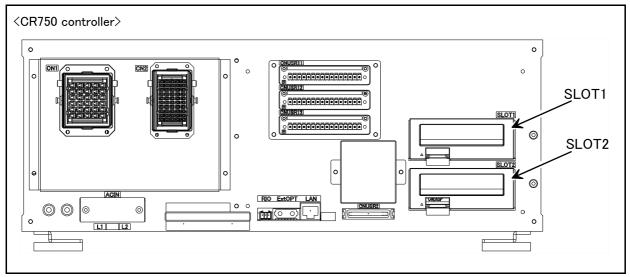


Fig.3-31: Parallel I/O interface installation position (CR750)

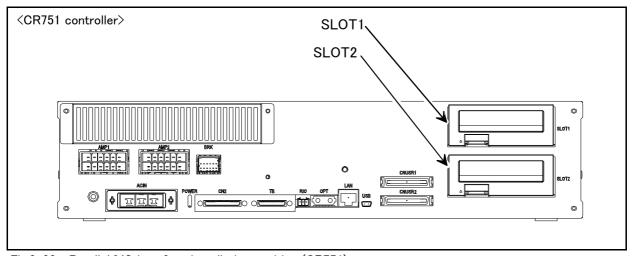


Fig.3-32 : Parallel I/O interface installation position (CR751)

■ Pin layout of connector

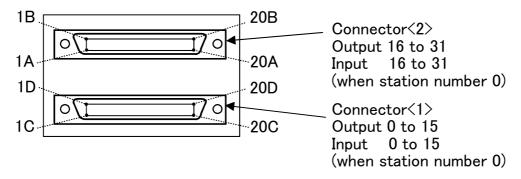


Fig.3-33: Pin layout of connector

■ Connector pin No. and signal assignment

The station number is fixed by the slot to install and the allocation range of the general-purpose input-and-output signal is fixed.

Table 3-14: The slot number and the station number

Slot number	Station	Range of the general-purpos	se input-and-output signal
Slot number	number	Connector <1>	Connector <2>
SLOT1	0	Input: 0 to 15 Output: 0 to 15	Input : 16 to 31 Output : 16 to 31
SLOT2	1	Input : 32 to 47 Output : 32 to 47	Input: 48 to 63 Output: 48 to 63

The connector pin number of the parallel input-and-output interface installed in SLOT1 and signal number allocation are shown in Table 3-15 and Table 3-16. If it installs in other slots, please interpret and utilize.

Table 3-15 : Connector<1> pin assignment list and external I/O cable (2D-CBL**) color(SLOT1)

Pin		Function name		Pin		Function name		
No.	Line color	General-purpose	Dedicated/power supply, No. Line color common		Line color	General-purpose	Dedicated/power supply, common	
1C	Orange/Red a		24G/12G: For pins 5D-	1D	Orange/Black a		+24V/+12V(COM): For	
			20D				pins 5D-20D	
2C	Gray/Red a		COM : For pins	2D	Gray/Black a		Reserved	
			5C-20C ^{Note1)}					
3C	White/Red a		Reserved	3D	White/Black a		Reserved	
4C	Yellow/Red a		Reserved	4D	Yellow/Black a		Reserved	
5C	Pink/Red a	General-purpose input 15		5D	Pink/Black a	General-purpose output 15		
6C	Orange/Red b	General-purpose input 14		6D	Orange/Black b	General-purpose output 14		
7C	Gray/Red b	General-purpose input 13		7D	Gray/Black b	General-purpose output 13		
8C	White/Red b	General-purpose input 12		8D	White/Black b	General-purpose output 12		
9C	Yellow/Red b	General-purpose input 11		9D	Yellow/Black b	General-purpose output 11		
10C	Pink/Red b	General-purpose input 10		10D	Pink/Black b	General-purpose output 10		
11C	Orange/Red c	General-purpose input 9		11D	Orange/Black c	General-purpose output 9		
12C	Gray/Red c	General-purpose input 8		12D	Gray/Black c	General-purpose output 8		
13C	White/Red c	General-purpose input 7		13D	White/Black c	General-purpose output 7		
14C	Yellow/Red c	General-purpose input 6		14D	Yellow/Black c	General-purpose output 6		
15C	Pink/Red c	General-purpose input 5	Operation rights input	15D	Pink/Black c	General-purpose output 5		
			signal ^{Note2)}					
16C	Orange/Red d	General-purpose input 4	Servo ON input signal Note2)	16D	Orange/Black d	General-purpose output 4		
17C	Gray/Red d	General-purpose input 3	Start input ^{Note2)}	17D	Gray/Black d	General-purpose output 3	Operation rights output signal Note2)	
18C	White/Red d	General-purpose input 2	Error reset input signal Note2)	18D	White/Black d	General-purpose output 2	Error occurring output signal Note2)	
19C	Yellow/Red d	General-purpose input 1	Servo OFF input signal Note2)	19D	Yellow/Black d		In servo ON output signal ^{Note2)}	
20C	Pink/Red d	General-purpose input 0	Stop input ^{Note3)}	20D	Pink/Black d	General-purpose output 0	Operating output Note2)	

Note1) Sink type: $\pm 24V/\pm 12V(COM)$, Source type: $\pm 24G/12G$ Note2) The dedicated signal is assigned at shipping. It can change with the parameter.

Note3) The dedicated input signal (STOP) is assigned at shipping. The signal number is fixing.

Table 3-16 : Connector<2> pin assignment list and external I/O cable (2D-CBL**) color(SLOT1)

Pin	Line color	Function name		Pin		Function name	
No.		General-purpose	Dedicated/power supply, common	No.	Line color	General-purpose	Dedicated/power supply, common
1A	Orange/Red a		24G/12G: For pins 5B-	1B	Orange/Black a		+24V/+12V(COM): For
			20B				pins 5B-20B
2A	Gray/Red a		COM: For pins 5A-	2B	Gray/Black a		Reserved
			20A ^{Note1)}				
3A	White/Red a		Reserved	3B	White/Black a		Reserved
4A	Yellow/Red a		Reserved	4B	Yellow/Black a		Reserved
5A	Pink/Red a	General-purpose input 31		5B	Pink/Black a	General-purpose output 31	
6A	Orange/Red b	General-purpose input 30		6B	Orange/Black b	General-purpose output 30	
7A	Gray/Red b	General-purpose input 29		7B	Gray/Black b	General-purpose output 29	
8A	White/Red b	General-purpose input 28		8B	White/Black b	General-purpose output 28	
9A	Yellow/Red b	General-purpose input 27		9B	Yellow/Black b	General-purpose output 27	
10A	Pink/Red b	General-purpose input 26		10B	Pink/Black b	General-purpose output 26	
11A	Orange/Red c	General-purpose input 25		11B	Orange/Black c	General-purpose output 25	
12A	Gray/Red c	General-purpose input 24		12B	Gray/Black c	General-purpose output 24	
13A	White/Red c	General-purpose input 23		13B	White/Black c	General-purpose output 23	
14A	Yellow/Red c	General-purpose input 22		14B	Yellow/Black c	General-purpose output 22	
15A	Pink/Red c	General-purpose input 21		15B	Pink/Black c	General-purpose output 21	
16A	Orange/Red d	General-purpose input 20		16B	Orange/Black d	General-purpose output 20	
17A	Gray/Red d	General-purpose input 29		17B	Gray/Black d	General-purpose output 19	
18A	White/Red d	General-purpose input 18		18B	White/Black d	General-purpose output 18	
19A	Yellow/Red d	General-purpose input 17		19B	Yellow/Black d	General-purpose output 17	
20A	Pink/Red d	General-purpose input 16		20B	Pink/Black d	General-purpose output 16	

Note1) Sink type: +24V/+12V(COM), Source type: 24G/12G

<Reference> The example of connection with our PLC

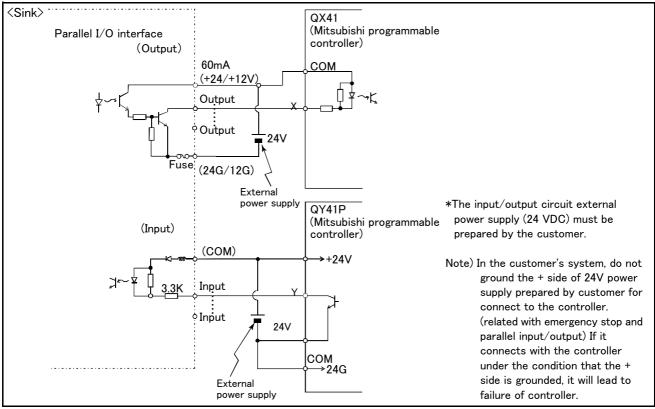


Table 3-17: Connection with a Mitsubishi PLC (Example of sink type)

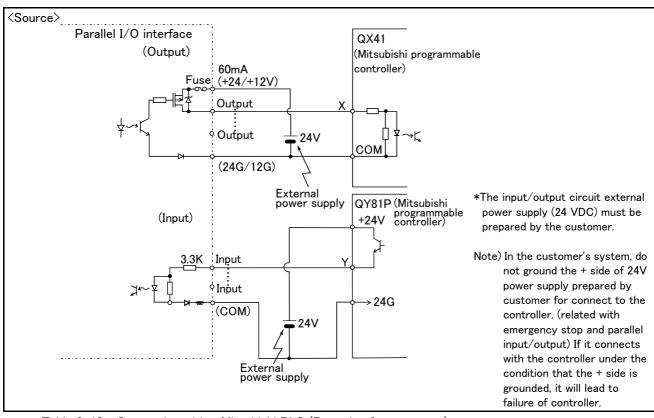


Table 3-18: Connection with a Mitsubishi PLC (Example of source type)

(3) External I/O cable

■ Order type : ● 2D-CBL □□ Note) The numbers in the boxes □□ refer to the length. (05: 5m, 15: 15m)

Outline



This is the dedicated cable used to connect an external peripheral device to the connector on the parallel I/O interface. For parallel I/O unit is another option 2A-CBL.**. One end matches the connector on the parallel input/output unit, and the other end is free. Connect the peripheral device's input/output signal using the free end. One cable correspond to the input 16 points and output 16 points.

Two cables are needed to connection of (input 32 points and output 32 points) with built-in standard.

■ Configuration

Table 3-19: Configuration device

Part name	Туре	Qty.	Mass (kg) ^{Note1)}	Remarks
External I/O cable	2D-CBL □□	1 pc.	0.7(5m) 1.84(15m)	5m or 15m

Note1) Mass indicates one set.

■ Specifications

Table 3-20: Specifications

Items	Specifications			
Number of cables x cable size	AWG #28 x 20P (40 pairs)			
Total length	5m, 15m			

■ Connector pin numbers and cable colors

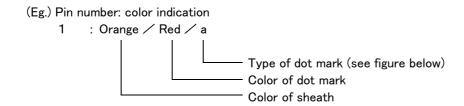
Table 3-21: Connector pin numbers and cable colors

Pin no.	Cable colors	Pin no.	Cable colors	Pin no.	Cable colors	Pin no.	Cable colors
1A/C	Orange/Red a	11A/C	Orange/Red c	1B/D	Orange/Black a	11B/D	Orange/Black c
2A/C	Gray/Red a	12A/C	Gray/Red c	2B/D	Gray/Black a	12B/D	Gray/Black c
3A/C	White/Red a	13A/C	White/Red c	3B/D	White/Black a	13B/D	White/Black c
4A/C	Yellow/Red a	14A/C	Yellow/Red c	4B/D	Yellow/Black a	14B/D	Yellow/Black c
5A/C	Pink/Red a	15A/C	Pink/Red c	5B/D	Pink/Black a	15B/D	Pink/Black c
6A/C	Orange/Red b	16A/C	Orange/Red d	6B/D	Orange/Black b	16B/D	Orange/Black d
7A/C	Gray/Red b	17A/C	Gray/Red d	7B/D	Gray/Black b	17B/D	Gray/Black d
8A/C	White/Red b	18A/C	White/Red d	8B/D	White/Black b	18B/D	White/Black d
9A/C	Yellow/Red b	19A/C	Yellow/Red d	9B/D	Yellow/Black b	19B/D	Yellow/Black d
10A/C	Pink/Red b	20A/C	Pink/Red d	10B/D	Pink/Black b	20B/D	Pink/Black d

Notes) Pin number of connector<1> are 1C, 2C,20C, 1D, 2D,20D, connector<2> are 1A, 2A,20A, 1B, 2B,20B.

■ Connections and outside dimensions

The sheath of each signal cable (40 lines) is color indicated and marked with dots. Refer to the cable color specifications in "Table 3-32: Connector pin numbers and cable colors" when making the connections.



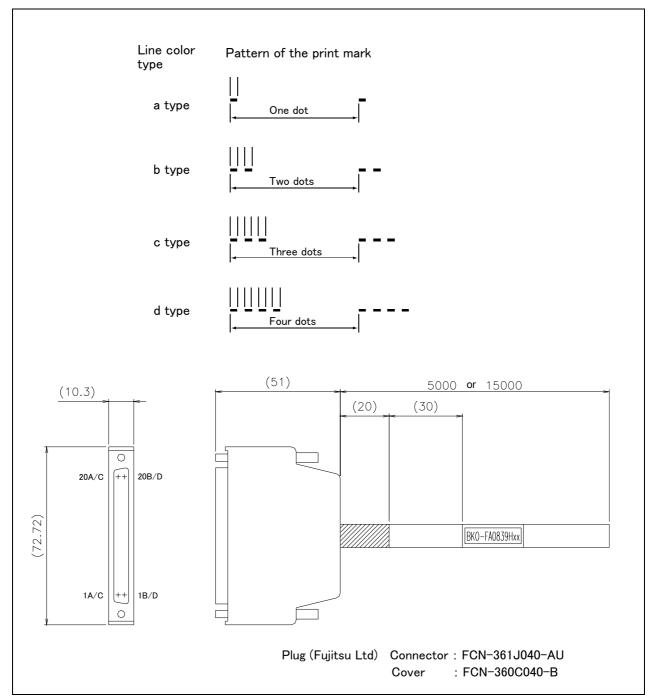


Fig.3-34: Connections and outside dimensions

(4) Parallel I/O unit

■ Order type: 2A-RZ361(Sink type)

2A-RZ371(Source type)

Outline



This is used to expand the external inputs and outputs. One one equal with this unit is built into the control unit among controllers the standard.

- The connection cable is not included. Prepare the optional external input/output cable (2A-CBL05 or 2A-CBL15).
- Use 2A-RZ361 if the external input/output signal logic is of the sink type and 2A-RZ371 for source type signal logic.

Notes) Although the combined use with the parallel I/O interface (2D-TZ368) of another option is also possible, please use the setup of the station number by the different number separately. The station number is automatically fixed by the position of the option slot which installed the parallel I/O interface in 0-1.

■ Configuration

Table 3-22: Configuration device

Part name	Туре	Qty.	Mass (kg) Note1)	Remarks
Parallel I/O unit	2A-RZ361	Either one	0.7	Input/output 32 points/32 points
	2A-RZ371	pc.	0.7	2A-RZ361 is the sink type. 2A-RZ371 is the source type.
Robot I/O link connection connector	NETcable-1	2 sets	_	Connector with pins. The cable must be prepared and wired by the customer.
Power connection connector	DCcable-2	1 set	-	Connector with pins. The cable must be prepared and wired by the customer.
Terminator	R-TM	1 pc.	_	100Ω(1/4W)

Note1) Mass indicates one set.

■ Specifications

- 1) The parallel I/O interface (2D-TZ368) of another option, and the a maximum of eight pieces in all. (One station occupies one unit.)
- 2) The power supply (24V) must be prepared by the customer and connected with the power connection cable (DCcable-2)

A separate 24V power supply is required for the input/output circuit wiring.

Table 3-23: Electrical specifications of input circuits

Item		Specification		Internal circuit
Туре		DC input		⟨Sink type⟩
Number of input poin	nts	32		+24V/+12V
Insulation method		Photo coupler insula	tion	(COM)
Rated input voltage		12VDC	24VDC	
Rated input current		Approx 3mA	Approx 7mA	│
Working voltage rang	ge	10.2 to 26.4VDC(Ripple factor should be less than 5%.)		Input
ON voltage/ON curr	ent	8VDC or more/ 2mA	or more	3.3K
OFF voltage/ OFF of	urrent	4VDC or less/ 1mA	or less	<pre></pre>
Input resistance		Approx. 3.3kΩ		
Response time	OFF-ON	10ms or less (24VD0	0)	3.3K Input
	ON-OFF	10ms or less (24VDC	0)	
Common method		8 points per commor	1	ヿ゠゚゚゚
External cable connection method		Connector		
				24G/12G

Item Specification Internal circuit Type Transistor output <Sink type> No. of output points Insulation method Photo-coupler insulation +24V/+12V 12VDC/24VDC Rated load voltage Output 10.2 to 30VDC(peak voltage 30VDC) Rated load voltage range Max. load current 0.1A/point (100%) Leakage current at OFF 0.1mA or less 24G/12G 0.9VDC(TYP.) Note1) Max. voltage drop at ON Fuse 2ms or less OFF-ON (hardware response time) Response time <Source type> 2ms or less ON-OFF (Resistance load) (hardware response time) Fuse +24V/+12V Fuse rating Fuse 3.2A (one per common) Replacement not possible Output Common method 8 points per common (common terminal: 4 points) External wire connection Connector method 24G/12G 12VDC/24VDC(10.2 to 30VDC) Voltage External power supply Current 60mA (TYP. 24VDC per common) (base drive current)

Table 3-24: Electrical specifications for the output circuits

Note1) The maximum voltage drop value at signal ON.

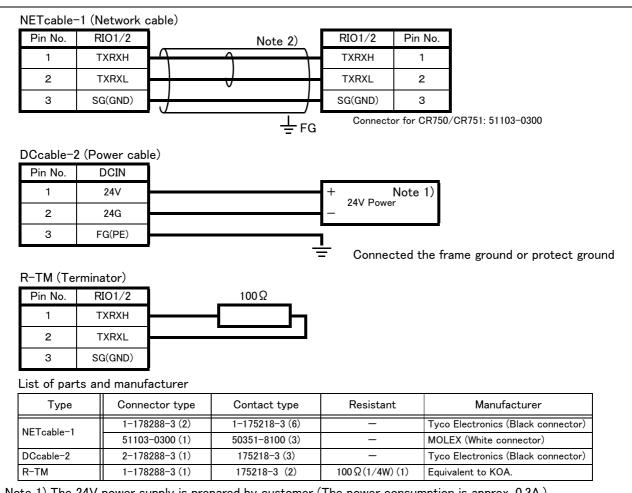
Refer to it for the equipment connected to the output circuit.



The output circuit protective fuses prevent failure in case of load short-circuit and improper connections. Please do not connect loads that cause the current to exceed the maximum rated current. If the maximum rated current is exceeded, the internal transistors may be damaged.



Inputs the power supply for control (DCcable-2) then inputs the controller's power supply.



Note 1) The 24V power supply is prepared by customer (The power consumption is approx. 0.3A.)

In the customer's system, do not ground the + side of 24V power supply prepared by customer for connect to the controller. (related with emergency stop and parallel input/output) If it connects with the controller under the condition that the + side is grounded, it will lead to failure of controller.

Note 2) The cable for general purpose can be used to the network cable. However, use the twisted shield cable of AWG#22(0.3mm²) or more.

Fig.3-35: Specifications for the connection cable

■ Installation method

The expansion parallel input/output unit is installed outside of the controller. Connect with the network connection cable (NETcable-1) from the RIO connector in the rear/into of the controller. (Terminator is connected at the time of shipment)

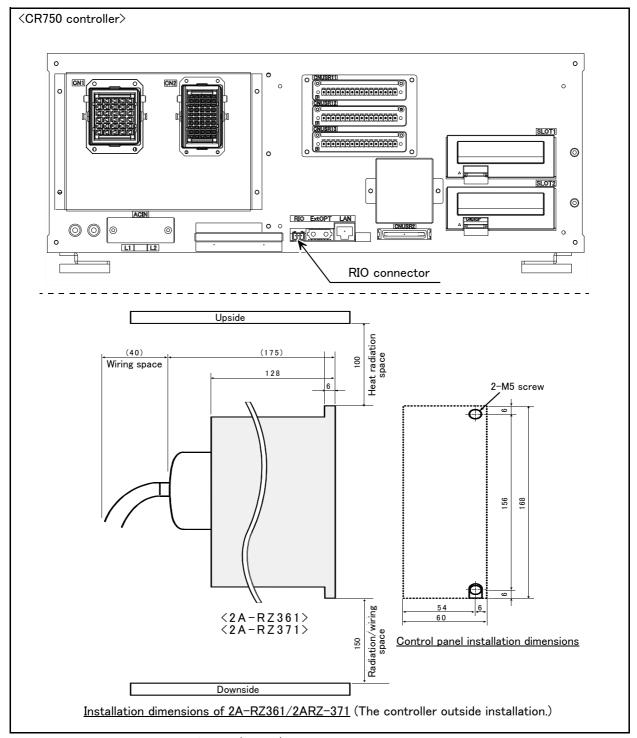


Fig.3-36: Installing the parallel I/O unit (CR750)

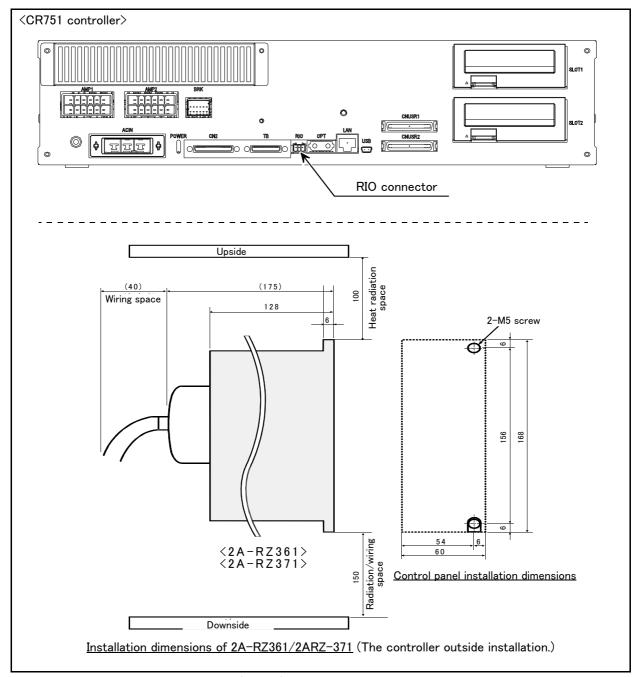


Fig.3-37: Installing the parallel I/O unit (CR751)

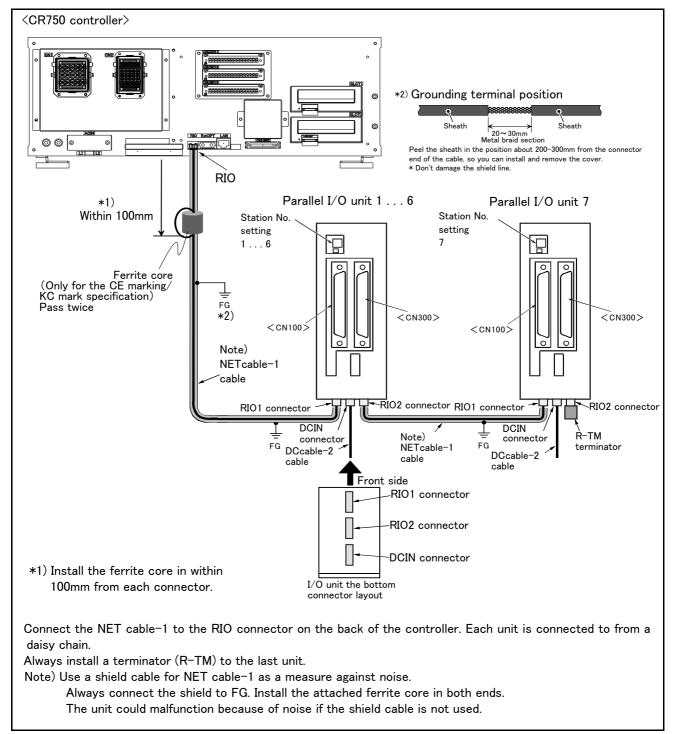


Fig.3-38: Connection method of expansion parallel I/O unit (CR750)

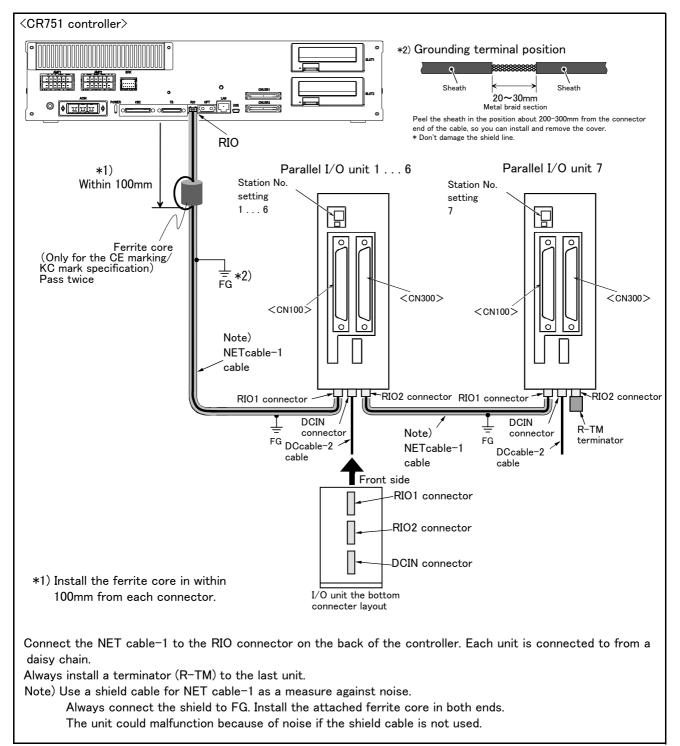
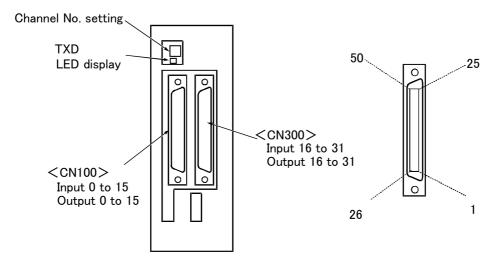


Fig.3-39: Connection method of expansion parallel I/O unit (CR751)

■ Pin arrangement of the connector



*2A-RZ361/2 A-RZ371 are 32/32 input-and-output units. (One-station occupancy)

Fig.3-40 : Pin arrangement of the parallel I/O unit

■ Assignment of pin number and signal

The assignment range of the general-purpose input-and-output signal is fixed by the setup of the station number.

Table 3-25: Assignment of pin number and signal

Unit Number	Station number	CN100	CN300
1st set	0	Input : 0 to 15 Output : 0 to 15	Input : 16 to 31 Output : 16 to 31
2nd set	1	Input : 32 to 47 Output : 32 to 47	Input: 48 to 63 Output: 48 to 63
3rd set	2	Input : 64 to 79 Output : 64 to 79	Input: 80 to 95 Output: 80 to 95
4th set	3	Input : 96 to 111 Output : 96 to 111	Input : 112 to 127 Output : 112 to 127
5th set	4	Input : 128 to 143 Output : 128 to 143	Input : 144 to 159 Output : 144 to 159
6th set	5	Input : 160 to 175 Output : 160 to 175	Input : 176 to 191 Output : 176 to 191
7th set	6	Input : 192 to 207 Output : 192 to 207	Input : 208 to 223 Output : 208 to 223
8th set	7	Input : 224 to 239 Output : 224 to 239	Input : 240 to 255 Output : 240 to 255

The connector pin number of the parallel I/O unit of the station number 0 and signal number assignment are shown in Table 3-26 and Table 3-27. If it is set as other station number, please interpret and utilize.

■ Parallel I/O interface (First expansion unit)

Table 3-26 : Connector CN100pin No. and signal assignment list (2A-CBL □□)

	20.00	Function name		Pin	,	Function name	
Pin No.	Line color	General-purpose	Dedicated/power supply, common	No.	Line color	General-purpose	Dedicated/power supply, common
1	Orange/Red A		FG	26	Orange/Blue A		FG
2	Gray/Red A		0V:For pins 4-7, 10-13	27	Gray/Blue A		0V:For pins 29-32, 35-38
3	White/Red A		12V/24V:For pins 4-7	28	White/Blue A		12V/24V:For pins 29-32
4	Yellow/Red A	General-purpose output 0	Operating output Note1)	29	Yellow/Blue A	General-purpose output 4	
5	Pink/Red A	General-purpose output 1	In servo ON output signal Note1)	30	Pink/Blue A	General-purpose output 5	
6	Orange/Red B	General-purpose output 2	Error occurring output signal Note1)	31	Orange/Blue B	General-purpose output 6	
7	Gray/Red B	General-purpose output 3	Operation rights output sig- nal Note1)	32	Gray/Blue B	General-purpose output 7	
8	White/Red B		0V:For pins 4-7, 10-13	33	White/Blue B		0V:For pins 29-32, 35-38
9	Yellow/Red B		12V/24V:For pins 10-13	34	Yellow/Blue B		12V/24V:For pins 35-38
10	Pink/Red B	General-purpose output 8		35	Pink/Blue B	General-purpose output 12	
11	Orange/Red C	General-purpose output 9		36	Orange/Blue C	General-purpose output 13	
12	Gray/Red C	General-purpose output 10		37	Gray/Blue C	General-purpose output 14	
13	White/Red C	General-purpose output 11		38	White/Blue C	General-purpose output 15	
14	Yellow/Red C		COM0:For pins 15-22 Note2)	39	Yellow/Blue C		COM1:For pins 40-47 Note2)
15	Pink/Red C	General-purpose input 0	Stop input ^{Note3)}	40	Pink/Blue C	General-purpose input 8	
16	Orange/Red D	General-purpose input 1	Servo OFF input signal Note1)	41	Orange/Blue D	General-purpose input 9	
17	Gray/Red D	General-purpose input 2	Error reset input signal Note1)	42	Gray/Blue D	General-purpose input 10	
18	White/Red D	General-purpose input 3	Start input Note1)	43	White/Blue D	General-purpose input 11	
19	Yellow/Red D	General-purpose input 4	Servo ON input signal Note1)	44	Yellow/Blue D	General-purpose input 12	
20	Pink/Red D	General-purpose input 5	Operation rights input sig- nal ^{Note1)}	45	Pink/Blue D	General-purpose input 13	
21	Orange/Red E	General-purpose input 6		46	Orange/Blue E	General-purpose input 14	
22	Gray/Red E	General-purpose input 7		47	Gray/Blue E	General-purpose input 15	
23	White/Red E		Reserved	48	White/Blue E		Reserved
24	Yellow/Red E		Reserved	49	Yellow/Blue E		Reserved
25	Pink/Red E		Reserved	50	Pink/Blue E		Reserved

Note1) The dedicated signal is assigned at shipping. It can change with the parameter. Note2) Sink type: 12V/24V(COM), Source type: 0V(COM)

Note3) The dedicated input signal (STOP) is assigned at shipping. The signal number is fixing.

<u>Table 3-27 : Connector CN300pin</u> No. and signal assignment list (2A-CBL □ □)

Tabl	able 3-27: Connector CN300pin No. and signal assignn				list (ZA ODI	- 		
Pin		Function name				Function name		
No.	Line color	General-purpose	Dedicated/power supply, common	Pin No.	Line color	General-purpose	Dedicated/power supply, common	
1	Orange/Red A		FG	26	Orange/Blue A		FG	
2	Gray/Red A		0V:For pins 4−7, 10−13	27	Gray/Blue A		0V:For pins 29-32, 35-38	
3	White/Red A		12V/24V:For pins 4-7	28	White/Blue A		12V/24V:For pins 29-32	
4	Yellow/Red A	General-purpose output 16		29	Yellow/Blue A	General-purpose output 20		
5	Pink/Red A	General-purpose output 17		30	Pink/Blue A	General-purpose output 21		
6	Orange/Red B	General-purpose output 18		31	Orange/Blue B	General-purpose output 22		
7	Gray/Red B	General-purpose output 19		32	Gray/Blue B	General-purpose output 23		
8	White/Red B		0V:For pins 4−7, 10−13	33	White/Blue B		0V:For pins 29-32, 35-38	
9	Yellow/Red B		12V/24V:For pins 10-13	34	Yellow/Blue B		12V/24V:For pins 35-38	
10	Pink/Red B	General-purpose output 24		35	Pink/Blue B	General-purpose output 28		
11	Orange/Red C	General-purpose output 25		36	Orange/Blue C	General-purpose output 29		
12	Gray/Red C	General-purpose output 26		37	Gray/Blue C	General-purpose output 30		
13	White/Red C	General-purpose output 27		38	White/Blue C	General-purpose output 31		
14	Yellow/Red C		COM0:For pins 15-22 ^{Note1)}	39	Yellow/Blue C		COM1:For pins 40-47 Note1)	
15	Pink/Red C	General-purpose input 16		40	Pink/Blue C	General-purpose input 24		
16	Orange/Red D	General-purpose input 17		41	Orange/Blue D	General-purpose input 25		
17	Gray/Red D	General-purpose input 18		42	Gray/Blue D	General-purpose input 26		
18	White/Red D	General-purpose input 19		43	White/Blue D	General-purpose input 27		
19	Yellow/Red D	General-purpose input 20		44	Yellow/Blue D	General-purpose input 28		
20	Pink/Red D	General-purpose input 21		45	Pink/Blue D	General-purpose input 29		
21	Orange/Red E	General-purpose input 22		46	Orange/Blue E	General-purpose input 30		
22	Gray/Red E	General-purpose input 23		47	Gray/Blue E	General-purpose input 31		
23	White/Red E		Reserved	48	White/Blue E		Reserved	
24	Yellow/Red E		Reserved	49	Yellow/Blue E		Reserved	
25	Pink/Red E		Reserved	50	Pink/Blue E		Reserved	

Note1) Sink type:12V/24V(COM),Source type:0V(COM)

<Reference> The example of connection with our PLC

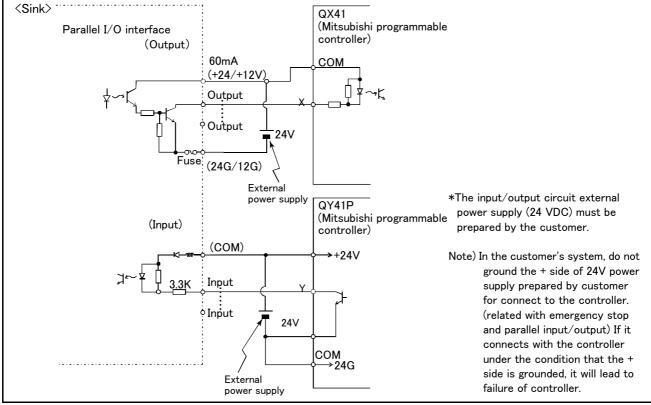


Table 3-28: Connection with a Mitsubishi PLC (Example of sink type)

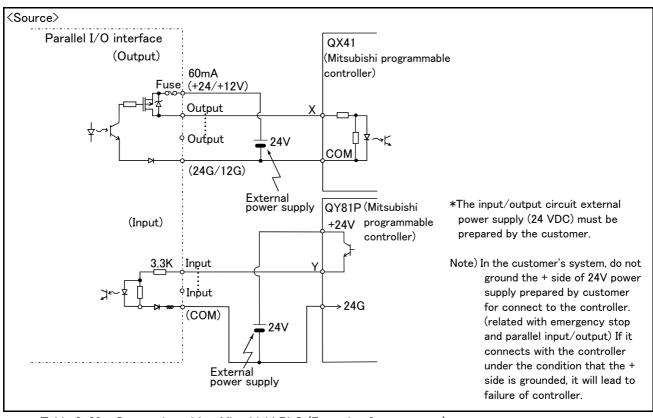


Table 3-29: Connection with a Mitsubishi PLC (Example of source type)

(5) External I/O cable

■ Order type: 2A-CBL □□ Note) The numbers in the boxes □□ refer to the length. (05: 5m、15: 15m)

Outline



This is the dedicated cable used to connect an external peripheral device to the connector on the parallel input/output unit.

One end matches the connector on the parallel input/output unit, and the other end is free. Connect the peripheral device's input/output signal using the free end.

One cable correspond to the input 16 points and output 16 points.

Two cables are needed to connection of (input 32 points and output 32 points) with built-in standard.

■ Configuration

Table 3-30: Configuration device

Part name	Туре	Qty.	Mass(kg) ^{Note1)}	Remarks
External I/O cable	2A-CBL □□	1pc.	0.7(5m) 1.84(15m)	5m or 15m

Note1) Mass indicates one set.

■ Specifications

Table 3-31: Specifications

Items	Specifications			
Number of cables x cable size	50 pairs x AWG #28			
Total length	5m or 15m			

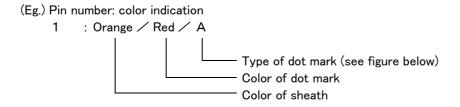
■ Connector pin numbers and cable colors

Table 3-32: Connector pin numbers and cable colors

Pin no.	Cable colors	Pin no.	Cable colors	Pin no.	Cable colors	Pin no.	Cable colors	Pin no.	Cable colors
1	Orange/Red A	11	Orange/Red C	21	Orange/Red E	31	Orange/Blue B	41	Orange/Blue D
2	Gray/Red A	12	Gray/Red C	22	Gray/Red E	32	Gray/Blue B	42	Gray/Blue D
3	White/Red A	13	White/Red C	23	White/Red E	33	White/Blue B	43	White/Blue D
4	Yellow/Red A	14	Yellow/Red C	24	Yellow/Red E	34	Yellow/Blue B	44	Yellow/Blue D
5	Pink/Red A	15	Pink/Red C	25	Pink/Red E	35	Pink/Blue B	45	Pink/Blue D
6	Orange/Red B	16	Orange/Red D	26	Orange/Blue A	36	Orange/Blue C	46	Orange/Blue E
7	Gray/Red B	17	Gray/Red D	27	Gray/Blue A	37	Gray/Blue C	47	Gray/Blue E
8	White/Red B	18	White/Red D	28	White/Blue A	38	White/Blue C	48	White/Blue E
9	Yellow/Red B	19	Yellow/Red D	29	Yellow/Blue A	39	Yellow/Blue C	49	Yellow/Blue E
10	Pink/Red B	20	Pink/Red D	30	Pink/Blue A	40	Pink/Blue C	50	Pink/Blue E

■ Connections and outside dimensions

The sheath of each signal cable (50 lines) is color indicated and marked with dots. Refer to the cable color specifications in "Table 3-32: Connector pin numbers and cable colors" when making the connections.



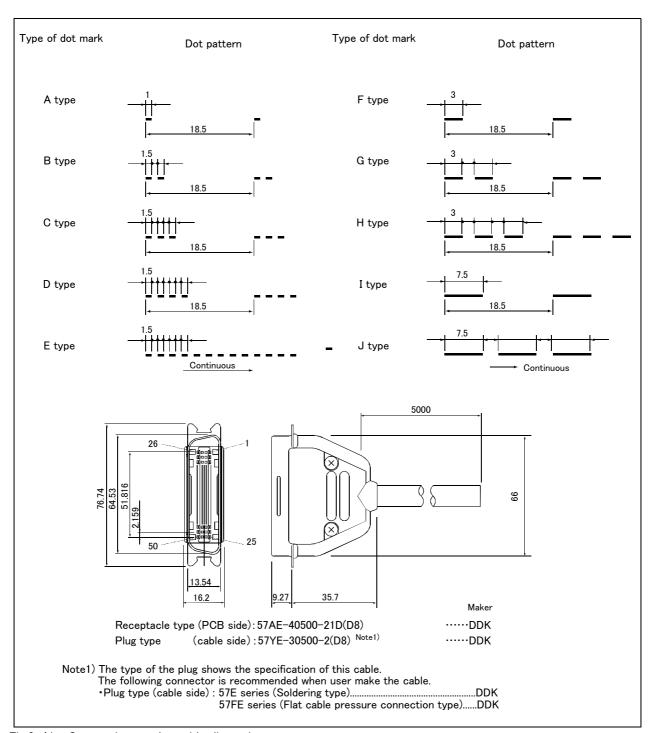


Fig.3-41: Connections and outside dimensions

(6) CC-Link interface

■ Order type: ● 2D-TZ576

■ Outline



The CC-Link interface is the optioninterface to not only add bit data to the robot controller. but also to add CC-Link field network function that allows cyclic transmission of word data.

■ Configuration

Table 3-33: Configuration device

Part name	Туре	Qty.	Mass(kg) ^{Note1)}	Remarks
CC-Link interface	TZ576	1	0.6	
Manual	BFP-A8701	1	-	
Ferrite core	E04SR301334	2	-	
Cable clamp	AL4	2	-	Be sure to install this for noise countermeasure.
	AL5	2	-	

Note1) Mass indicates one set.

Table 3-34: Procured by the customer

Part name	Туре	Qty.	Remarks	
	QJ61BT11(Q series)			
	QJ61BT11N(Q series)			
	AJ61QBT11(QnA series)			
Master station	A1SJ61QBT11(QnAS series)	1	FX series products are not supported.	
	AJ61BT11(A series)			
	A1SJ61BT11(AnS series)			
	A80BD-J61BT11(personal computer board)			
Communication cable	-	1	Shielded 3-core twisted cable This cable may be manufactured by the customer.	
Terminal resistor	-	1	110 Ω or 130 Ω is recommended.	

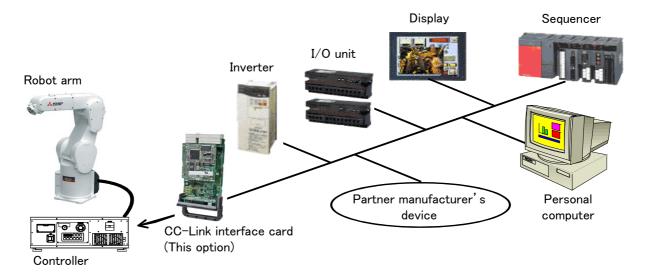


Fig.3-42: Example of CC-Link Product Configuration

■ Specifications

Table 3-35 : Specifications

Item			Specif	ications		Remarks	
Communication function			Bit data	and word da	ata can be tr	ansmitted.	Word data are used by the registers.
Station type			Int	elligent devi	ice station ^N	ote1)	
Support sta	ation			Local	station		No master station function
The version	n correspondin	g to CC-Link		V	er.2		The extended cyclic setup is possible.
Mountable	option slot			Slo	t 1, 2		
Number of	mountable CC	-Link interface cards			1		Multiple CC-Link interface cards cannot be inserted.
Number of	stations			1 to 64	stations		When four stations are occupied, continuous station numbers are used. The station numbers are set by a DIP switch.
Transmissio	on speed		101	M/5M/2.5M	/625K/156K	bps	This is set by the rotary SW.
Station nun	nber			1 t	:o 64		When two or more stations are occupied,
Number of	occupied stati	ons		1/2	2/3/4		continuous station numbers are used.
Extended c	yclic setup			1/2	2/4/8		
Maximum lii	nk point	Remote I/O (RX, RY).		Each 8	96 points		The two last cannot be used.
		Remote register (RWr, RWw)		Each 12	8 register		16 bits/register
Extended c	yclic setup	-	1 fold setup	2 fold setup	3 fold setup	4 fold setup	
Link point per set	When one station is	Remote I/O (RX, RY).	32 point	32 point	64 point	128 point	
	occupied	Remote register (RWw)	4 word	8 word	16 word	32 word	
		Remote register (RWr)	4 word	8 word	16 word	32 word	
	When two stations is	Remote I/O (RX, RY).	64 point	96 point	192 point	384 point	
	occupied	Remote register (RWw)	8 word	16 word	32 word	64 word	
		Remote register (RWr)	8 word	16 word	32 word	64 word	
	When three stations is	Remote I/O (RX, RY).	96 point	160 point	320 point	640 point	
	occupied	Remote register (RWw)	12 word	24 word	48 word	96 word	
		Remote register (RWr)	12 word	24 word	48 word	96 word	
	When four stations is	Remote I/O (RX, RY).	128 point	224 point	448 point	896 point	
	occupied	Remote register (RWw)	16 word	32 word	64 word	128 word	
Remote register (RWr)		16 word	32 word	64 word	128 word		
Number of the maximum occupancy station		occupancy station		4 st	ations		
The I/O first number of the robot controller.			nber corresponder to the set	6000 conding to the cup of the pa CFIX."			

Note1) The CC-Link interface supports neither the transient transmission function nor the FX series.

■ Functions

(1) Communication function

• The number of usable points is 896 points maximum for bit control and 128 points maximum for word control.

(2) Easy setup

- The CC-Link interface card can be set by a rotary switch or DIP switch.
- •No separate space is required to mount the CC-Link interface card as it is embedded in the robot controller (can only be mounted into slot 2).
- Easy wiring since only four terminals need to be connected.
- Dedicated commands have been added to MELFA-BASIC V (robot programming language); thus, no complex interface programming is required.

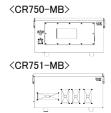
(3) High-speed response

- •The link scan time when connecting 64 stations is approximately 7.2 ms, achieving superior high-speed response performance.
- A transmission speed can be selected from 10M, 5M, 2.5M, 625K and 156K bps according to the transmission distance.

(7) Controller protection box

■ Order type: CR750 controller......CR750-MB CR751 controller.....CR751-MB

■ Outline



By putting the controller in this box, the controller can be protected from oil mist environment.

Use this option, when the controller is installed where environment is oil mist such as machine shop etc.

This option is not chemical-resistant. For installing the option, avoid places where adhesion of chemicals may occur.

■ Configuration

Table 3-36: Configuration equipment and types

Part name	Туре	Qty.	Mass (Kg) ^{Note1)}	Remarks
CR750 controller			<u> </u>	
Controller protection box	CR750-MB	1		
Internal power cable		3		For connection between the power supply relay terminal and controller inside this box
Internal earth cable		1		For connection between the grounding terminal and controller inside this box
Label for serial number		1	22	
Transparent seal		1		
Cable tie	T50L	4		
Screw for fixing of the controller mounting plate	M4x8	4		
Instruction Manual	BFP-A8896	1	-	
CR751 controller			•	
Controller protection box	CR751-MB	1		
Internal power cable		2		For connection between the power supply relay terminal and controller inside this box
Internal earth cable		1		For connection between the grounding terminal and controller inside this box
Label for serial number		1	21	
Transparent seal		1		
Cable tie	T50L	4		
Screw for fixing of the controller mounting plate	M4x8	4		
Instruction Manual	BFP-A8997	1	-	

Note1) Mass indicates one set.

■ Specifications

Table 3-37 : Specifications

Item	Unit	Specifications	Remarks
CR750 controller	•		•
Outside dimension	mm	500(W) × 725(D) × 250(H)	Excluding protrusions
Mass	Kg	22	
Construction		Self-contained floor type	IP54
Grounding	Ω	100 or less (class D grounding)	
Paint color		Dark gray	Equivalent to Munsell: 3.5PB3.2/0.8
CR751 controller			
Outside dimension	mm	500(W) × 725(D) × 250(H)	Excluding protrusions
Mass	Kg	21	
Construction		Self-contained floor type	IP54
Grounding	Ω	100 or less (class D grounding)	
Paint color		Dark gray	Equivalent to Munsell: 3.5PB3.2/0.8

- (1) The robot must be grounded by the customer.
- (2) The cable for primary power supply connection and the grounding cable are customer preparations.

■ Outside dimension

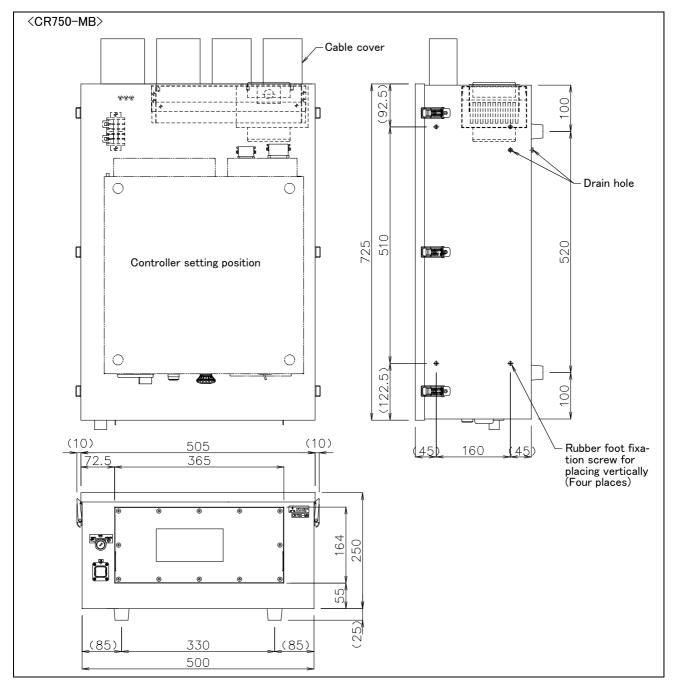


Fig.3-43: Outside dimension of CR750-MB

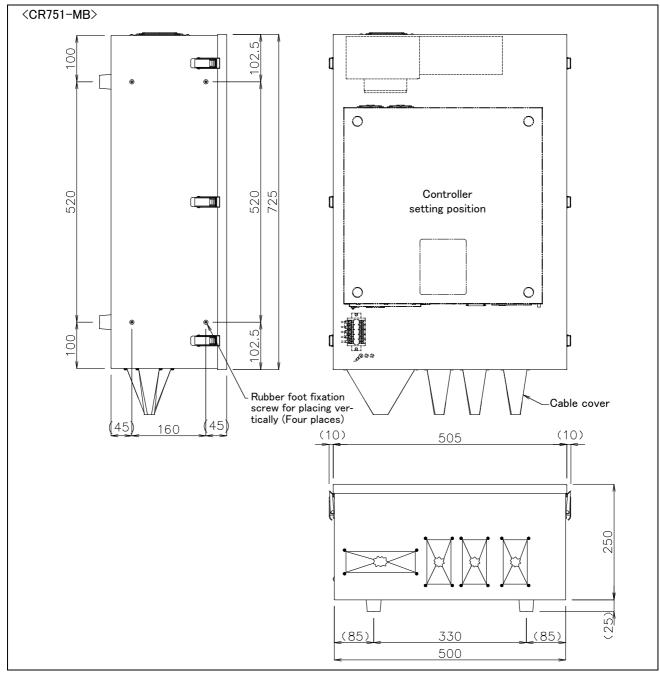


Fig.3-44 : Outside dimension of CR751-MB

■ Names of each part

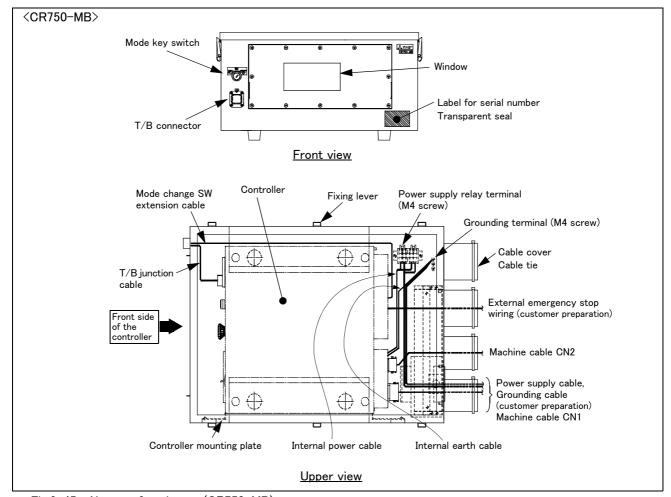


Fig.3-45: Names of each part (CR750-MB)

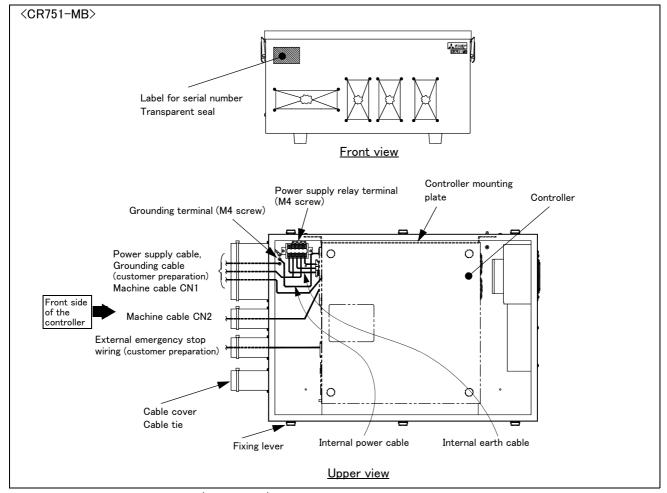
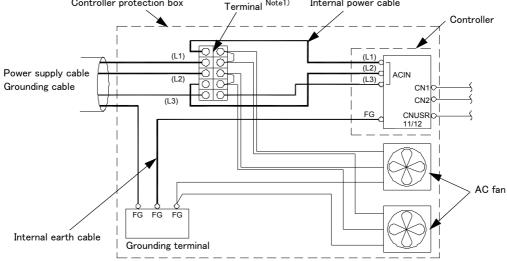


Fig.3-46: Names of each part (CR751-MB)

■ Wiring system diagram

<CR750-MB> Single phase: RH-6FH series Controller protection box Internal power cable Terminal Controller (L1) Power supply cable (L2) Grounding cable CN1 CN2 FG CNUSR 11/12 AC fan FG FG FG Internal earth cable Grounding terminal Single phase/Three phase: RH-12FH/20FH series Controller protection box Terminal Note1) Internal power cable Controller



Note1) When using the controller for the three phases with the single-phase power supply, connect the primary power supply to L1 and L2 electric terminal of the protection box so that the power supply may be supplied to the heat-exchanger AC fan of the protection box.

Connects with L1 and L3 electric terminal to the ACIN terminal block of the controller. Refer to the separate manual "Controller setup, basic operation, and maintenance" for detail of connecting the power cable and the grounding cable.

Fig.3-47: Wiring system diagram (CR750-MB)

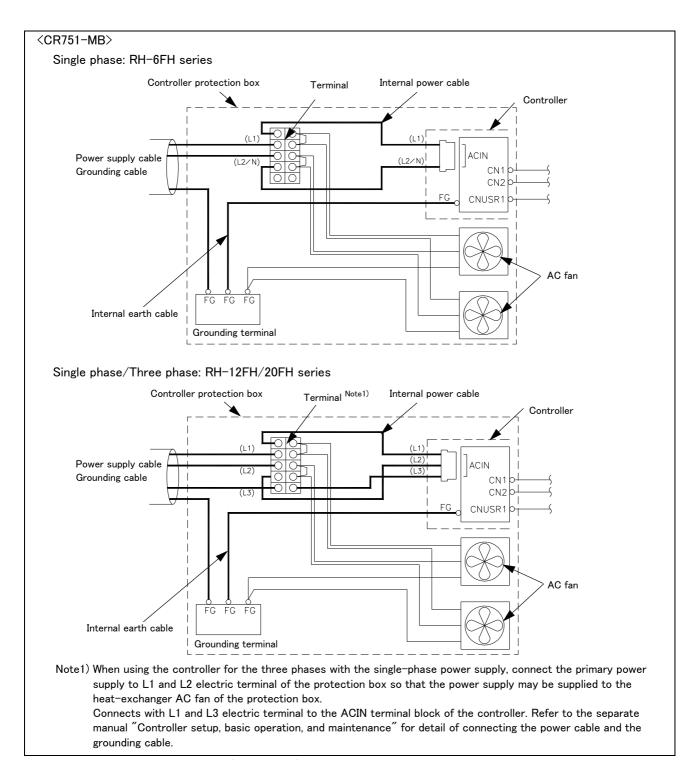


Fig.3-48: Wiring system diagram (CR751-MB)

■ Installation dimensions

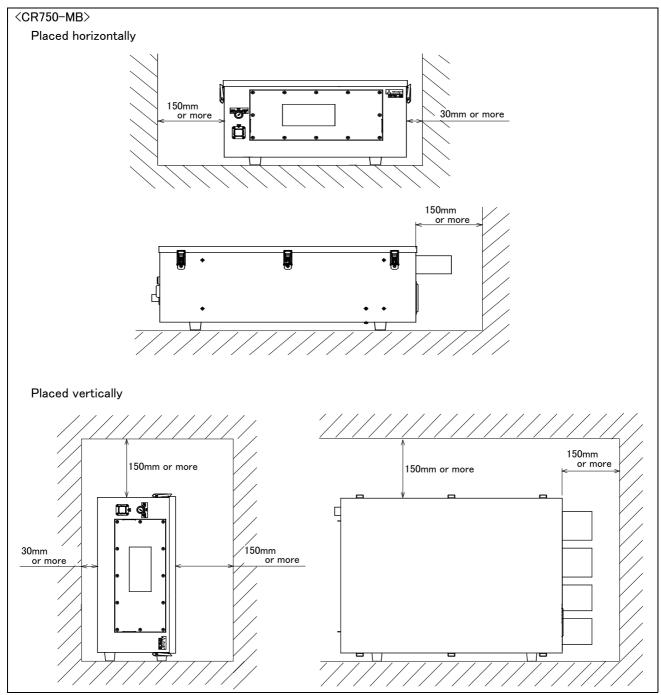


Fig.3-49: Installation dimensions (CR750-MB)

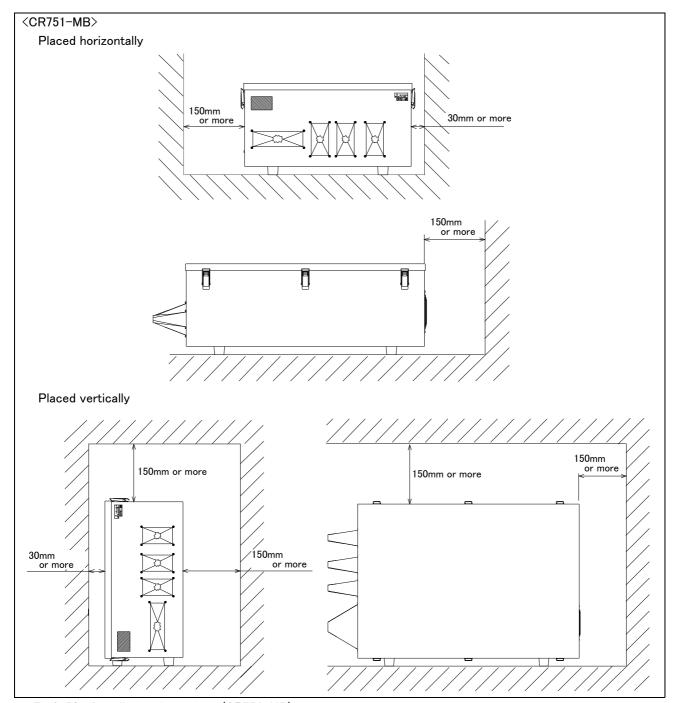


Fig.3-50: Installation dimensions (CR751-MB)

(8) MELSOFT RT ToolBox2/RT ToolBox2 mini

■ Order type : ● MELSOFT RT ToolBox2

*For windows CD-ROM : 3D-11C-WINE

MELSOFT RT ToolBox2 mini

*For windows CD-ROM : 3D-12C-WINE

Outline



This is handy software that fully uses the personal computer functions. It can be used in various stages from the robot specifications study (tact study, etc.) to the design support (creation and editing of programs), start up support (execution, control and debugging of program), and maintenance.

The "personal computer support software" which supports these function fully, and the "personal computer support software mini" which does not have the simulation function are available.

■ Configuration

Table 3-38: Product configuration

Part name	Туре	Medium	Mass (kg) Note1)	Remarks
RT ToolBox2	3D-11C-WINE	CD-ROM	0.2	
RT ToolBox2 mini	3D-12C-WINE	CD-ROM	0.2	

Note1) Mass indicates one set.

■ Features

(1) Simple operation with guidance method and menu method

The Windows standard is used for windows operation, so the controller initialization and startup operations can be carried out easily by following the instructions given on the screen. Even a beginner can easily carry out the series of operations from program creation to execution.

(2) Increased work efficiency with ample support functions

The work efficiency is greatly improved with the multi-window method that carries out multiple steps and displays in parallel. The renumbering function, and copy, search, syntax check and step execution are especially sufficient, and are extremely useful when editing or debugging the program.

With the simulation function support, the program can be debugged and the tact checked before starting the machine at the site. This allows the on-site startup work efficiently to be greatly improved.

- (3) The maintenance forecast function increases the efficiency of maintenance work. Analyze the load condition while the robot is actually operating. Based on this analysis, calculate the time for maintenance, such as lubrication and belt replacement. By utilizing this information, the line stop time as well as the maintenance costs can be reduced.
- (4) The position recovery support function increases the recovery efficiency in the event of origin position displacement. This function compensates the origin settings and position data by just reproducing several previous teaching points when hand and/or arm displacement occurs, when replacing the motor and the belts, or when reloading the robot. This function can reduce the time required for recovery.

■ Functions

Table 3-39 : Functions

Function Compatible model		Functional existence ^{Note1)}		Details	
		0	0	Personal computer running Windows XP, Windows Vista, Windows 7, Windows 8, or Windows 8.1. Note2)	
functions Multiple editing screen Command input, comm Position data editing File operation (writing Search and replace fur Copy, cut, paste, insert statement, position conv Line No. automatic ger Batch syntax check Command template Position conversion ba		File operation (writing to controller, floppy disk, personal computer) Search and replace function (using characters, line Nos., labels) Copy, cut, paste, insert (per character, line), undo (per command statement, position conversion) Line No. automatic generation, renumbering Batch syntax check Command template Position conversion batch editing Position variable template			
	Control func- tions	0	0	Program file control (list, copy, movement, delete, content comparison, name change, protect)	
	Debugging functions	0	0	Direct editing of program in controller Confirmation of robot program operation (step execution, direct execution)	
Simulation function		0	×	Off-line simulation of robot program operation using CG (compute graphics) Tact time calculation	
tions O O ti		0	Robot operation monitor (robot operation state, stop signal, error monitor, program monitor (execution program, variables), general-purpose input/output signals (forced output possible), dedicated input/output signals, operation confirmation (operation range, current position, hand, etc.) Operation monitor (working time statistics, production information, robot version) Servo monitor (load)		
Maintenance function		0	0	Parameter setting Batch, divided backup	
				RT ToolBox2 mini (3D-12C-WINE) RT ToolBox2 (3D-11C-WINE)	

Note1) The functions included with the RT ToolBox2 and the RT ToolBox2 mini are shown below.

O : Function provided ×: Function not provided

Note2) Recommend corresponding to CE Marking, an FCC standard, and a VCCI standard.

(9) Instruction Manual (bookbinding)

■ Order type: ● 5F-FB03-PE01.....RH-6FH/12FH/20FH-D series multiple-resistant specification

Outline



This is a printed version of the CD-ROM (instruction manual) supplied with this product.

■ Configuration

Table 3-40: Product configuration

Name	Туре	Mass (Kg) Note1)	Specifications	
struction Manual	5F-FB03-PE01	2.6	The instructions manual set of RH-6/12/20FH-D series multiple-resistant specification robot	
Safety Manual	BFP-A8006	-	Items relating to safety in handling the robot	
Standard Specifications	BFP-A3319	-	Specification of the robot arm and controller	
Robot Arm Setup & Maintenance	BFP-A3321	-	Installation method of the robot arm, jog operation, and maintenance and inspection procedures	
Controller Setup, Basic Operation and Maintenance	BFP-A8867	-	Installation method of the controller, basic operation, and maintenance and inspection procedures	
Detailed Explanation of Functions and Operations	BFP-A8869	-	Functions of the controller and T/B, operation method, and explanation of MELFA-BASIC V	
Troubleshooting	BFP-A8871	-	Causes of errors occurred and their countermeasures	
Additional axis function	BFP-A8663	-	Function of the additional axis, operation method.	
Tracking Function Manual	BFP-A8664	-	Function of the Tracking, operation method.	
GOT Direct Connection Extended Function	BFP-A8849	-	Explains of data configuration of shared memory, monitoring, and operating procedures, between the GOT and controller.	

Note1) Mass indicates one set.

3.11 Maintenance parts

The consumable parts used in the controller are shown in Table 3–41. Purchase these parts from your dealer when required. Some Mitsubishi-designated parts differ from the maker's standard parts. Thus, confirm the part name, robot arm and controller serial No. and purchase the parts from your dealer.

Table 3-41: Controller consumable parts list

No.	Name	Type Note1)	Qty.	Usage place	Supplier
1	Lithium battery	Q6BAT	1	CR750 controller: Inside of the interface cover CR751 controller: Inside of the filter cover	Mitsubishi Electric
2	Filter	CR750 controller: BKOFA0773H42 CR751 controller: BKOFA0773H41	1	Inside the filter cover	

Note1) Confirm the robot arm serial No., and contact the dealer or service branch of Mitsubishi Electric Co., for the type.

4 Software

4.1 List of commands

The available new functions in MELFA-BASIC V are given in Table 4-1.

Table 4-1 : List of MELFA-BASIC V commands

Туре	Class	Function	Input format (example)
	Joint interpolation	Moves to the designated position with joint interpolation.	Mov P1
	Linear interpolation	Moves to the designated position with linear interpolation.	Mvs P1
	Circular interpolation	Moves along a designated arc (start point \rightarrow passing point \rightarrow start point (end point)) with 3-dimensional circular interpolation (360 degrees).	Mvc P1,P2,P1
		Moves along a designated arc (start point \rightarrow passing point \rightarrow end point) with 3-dimensional circular interpolation.	Mvr P1,P2,P3
		Moves along the arc on the opposite side of a designated arc (start point \rightarrow reference point \rightarrow end point) with 3-dimensional circular interpolation.	Mvr2 P1,P9,P3
		Moves along a set arc (start point \rightarrow end point) with 3-dimensional circular interpolation.	Mvr3 P1,P9,P3
	Speed designation	Designates the speed for various interpolation operations with a percentage (0.1% unit).	Ovrd 100
		Designate the speed for joint interpolation operation with a percentage (0.1% unit).	JOvrd 100
		Designates the speed for linear and circular interpolation with a numerical value (mm/s unit).	Spd 123.5
<u>_</u>		Designates the acceleration/deceleration time as a percentage in respect to the predetermined maximum acceleration/deceleration. (1% unit)	Accel 50,80
Position and operation control		Automatically adjusts the acceleration/deceleration according to the parameter setting value.	Oadl ON
ation		Sets the hand and work conditions for automatic adjustment of the acceleration/deceleration.	Loadset 1,1
per	Operation	Adds a process unconditionally to the operation.	Wth
Ор		Adds a process conditionally to the operation.	WthIf
an		Designates smooth operation.	Cnt 1,100,200
.uo		Performance of movement is upgraded corresponding to the application.	MvTune 4
sit		Designates the positioning completion conditions with a No. of pulses.	Fine 200
Po		Designates the positioning completion conditions with a distance in a straight line	Fine 1, P
		Designates the positioning completion conditions with a joint interpolation.	Fine 0.5, J, 2
		Turns the servo power ON/OFF for all axes.	Servo OFF
		Limits the operation of each axis so that the designated torque is not exceeded.	Torq 4,10
	Position control	Designates the base conversion data.	Base P1
		Designates the tool conversion data.	Tool P1
	Float control	The robot arm rigidity is lowered and softened. (XYZ coordinate system)	Cmp Pos ,&B00000011
		The robot arm rigidity is lowered and softened. (JOINT coordinate system)	Cmp Jnt ,&B00000011
		The robot arm rigidity is lowered and softened. (TOOL coordinate system)	Cmp Tool ,&B00000011
		The robot arm rigidity is returned to the normal state.	Cmp Off
		The robot arm rigidity is designated.	CmpG 1.0,1.0,1.0,1.0,1.0,1.0,1.0,1.0
	Pallet	Defines the pallet.	Def Plt 1,P1,P2,P3,P4,5,3,1
		Operates the pallet grid point position.	Plt 1,M1
	Singular point pas- sage	Move to a specified position using linear interpolation passing through a singular point.	Mvs P1 Type 0,2

Туре	Class	Function	Input format (example)
	Branching	Branches unconditionally to the designated place.	GoTo 120
		Branches according to the designated conditions.	If M1=1 Then GoTo *L100
			Else GoTo 20
			End If
		Repeats until the designated end conditions are satisfied.	For M1=1 TO 10
		Describe while the decimant of an divine are existed	Next M1 While M1<10
		Repeats while the designated conditions are satisfied.	While MICIO
			WEnd
		Branches corresponding to the designated expression value.	On M1 GoTo *La1, *Lb2, *Lc3
		Executes program block corresponding to the designated expression	Select
		value	Case 1
			Break
			Case 2
			0430 2
			Break
_			End Select
Program control		Moves the program process to the next line.	Skip
con	Collision detection	Set to enable/disable the collision detection.	ColChk ON/OFF
an an		Set the detection level of the collision detection.	ColLvl 100,80,,,,,
ogra	Subroutine	Executes the designated subroutine. (Within program)	GoSub *L200
٩		Returns from the subroutine.	Return
		Executes the designated program.	CallP "P10",M1,P1
		Defines the program argument executed with the CALLP command.	FPrm M10,P10
		Executes the subroutine corresponding to the designated expression	On M1 GoSub *La1, *Lb2, *Lc3
	T4	value.	Def Act 1, M1=1 GoTo *L100
	Interrupt	Defines the interrupt conditions and process. Enables/disables the interrupt.	Act 1=1
		Defines the start line of the program to be executed when an interrupt is	ACL I-I
		generated from the communication line.	On Com(1) GoSub *L100
		Enables the interrupt from the communication line.	Com(1) On
		Disables the interrupt from the communication line.	Com(1) Off
		Stops the interrupt from the communication line.	Com(1) Stop
	Wait	Designates the wait time, and the output signal pulse output time. (0.01s	DI. O F
		unit)	Dly 0.5
		Waits until the variable becomes the designated value.	Wait M_In(1)=1
	Stop	Stops the program execution.	Hlt
		Generates an error. During program execution, continue, stop or servo	Error 9000
	F .	OFF can be designated.	
	End	Ends the program execution.	End
Hand	Hand open	Opens the designated hand.	HOpen 1
	Hand close	Closes the designated hand.	HClose 1
out	Assignment	Defines the input/output variables.	Def IO PORT1=BIT,0
outk	Input	Retrieves the general-purpose input signal.	M1=M_In(1)
ut/c	Output	Calls out the general-purpose output signal.	M_Out(1) =0
Input/output			w_Out(1) =0
	Mechanism designa-	Acquires the mechanism with the designated mechanism No.	GetM 1
tion	tion	Releases the mechanism with the designated mechanism No.	RelM 1
ecn	Selection	Selects the designated program for the designated slot.	XLoad 2,"P102"
ě	Start/stop	Carries out parallel execution of the designated program.	XRun 3,"100",0
<u>e</u>		Stops parallel execution of the designated program.	XStp 3
Parallel execution		Returns the designated program's execution line to the head and enters	XRst 3
		the program selection enabled state.	74.00

Туре	Class	Function	Input format (example)
	Definition	Defines the integer type or real number type variable.	Def Inte KAISUU
		Defines the character string variable.	Def Char MESSAGE
		efines the layout variable. (Up to 3-dimensional possible)	Dim PDATA(2,3)
		Defines the joint variable.	Def Jnt TAIHI
		Defines the position variable.	Def Pos TORU
		Defines the function.	Def FN TASU(A,B)=A+B
Others	Clear	Clears the general-purpose output signal, variables in program, variables	Clr 1
₹		between programs, etc.	
	File	Opens a file.	Open "COM1:" AS #1
		Closes a file.	Close #1
		Inputs data from a file.	Input# 1,M1
		Outputs data to a file.	Print# 1,M1
	Comment	Describes a comment.	Rem "ABC"
	Label	Indicates the branching destination.	*SUB1

4.2 List of parameters

Show the main parameter in the Table 4-2.

Table 4-2 : List of parameters

Parameter		Details
Standard tool coordinates.	MEXTL	Set the default value for the tool data. Unit: mm or deg.
Standard base coordinates	MEXBS	Set the relation of the world coordinate system and robot coordinate system. Unit: mm or deg.
XYZ operation range	MEPAR	Designate the overrun limit value for the world coordinate system.
JOINT operation range	MEJAR	Set the overrun limit value for each joint axis.
Free plane limit		This is the overrun limit set with the free plane. Create a plane with the three coordinates x1, y1, z1 to x3, y3, z3, and set the outer side of the plane as the outside operation range (error). The following three types of parameters are used.
	SFC1P : SFC8P	Eight types of free plane limits can be set in SFC1P to SFC8P. There are nine elements, set in the order of x1, y1, z1, x2, y2, z2, x3, y3, z3.
	SFC1ME : SFC8ME	Designate which mechanism to use eight types of set free plane limits. The mechanism No. to use is set with 1 to 3.
	SFC1AT : SFC8AT	Set the validity of the eight types of set free plane limits. (Valid 1/Valid 2/invalid = 1/-1/0)
User-defined area		An area (cube) defined with two XYZ coordinate points can be designated and that area set as the outside operation range. Furthermore, a signal can be output when the axis enters that area. Up to 32 types of area can be designated.
	AREA1CS : AREA32CS	Specify the coordinate system of the user definition area *. 0: Base coordinate system (conventional compatibility) 1: Robot coordinate system
	AREA1P1 : AREA32P1	Designated the 1st point of the area. There are eight elements, set in the order of x, y, z, a, b, c, L1, L2. (L1 and L2 are the additional axes.)
	AREA1P2 : AREA32P2	Designated the 2nd point of the area. There are eight elements, set in the order of x, y, z, a, b, c, L1, L2. (L1 and L2 are the additional axes.)
	AREA1ME : AREA32ME	Designate which mechanism to use the 32 types of set area. The mechanism No. to use is set with 1 to 3.
	AREA1AT : AREA32AT	Designate the area check type. (Invalid/zone/interference = 0/1/2) Zone: The dedicated output signal USRAREA turns ON. Interference: An error occurs
Automatic return setting	RETPATH	Set to restart the program after returning to the interrupt position when resuming operation after an interruption.
Buzzer ON/OFF	BZR	Designate whether to the turn buzzer ON or OFF.
Jog setting	JOGJSP	Designate the joint jog and step operation speed. (Set dimension H/L amount, max. override.)
	JOGPSP	Designate the linear jog and step operation speed. (Set dimension H/L amount, max. override.)
Jog speed limit value	JOGSPMX	Limit the operation speed during the teaching mode. Max. 250[mm/s]
Hand type	HANDTYPE	Set the hand type of the single/double solenoid, and the signal No. (Single/double = S/D) Set the signal No. after the hand type. Example) D900
Stop input B contact designation	INB	Change the dedicated input (stop) to either of normal open or normal close.

Parameter		Details
User-designated origin USERORG		Designate the user-designated origin position.
Program selection memory	SLOTON	Select the program selected previously when initializing the slot. The non-selected state will be entered when not set.
Communication setting	CBAU232	Set the baud rate.
	CLEN232	Set the character length.
	CPRTY232	Set the parity.
	CSTOP232	Set the stop bit.
	CTERM232	Set the end code.
Slot table	SLT1 : SLT32	Make settings (program name, operation type, order of priority, etc.) for each slot during slot initialization.
No. of multi-tasks	TASKMAX	Designate the No. of programs to be executed simultaneously. (Max. 32)
Select the function of singular point adjacent alarm	MESNGLS W	Designate the valid/invalid of the singular point adjacent alarm. (Invalid/Valid = 0/1) When this parameter is set up "VALID", this warning sound is buzzing even if parameter: BZR (buzzer ON/OFF) is set up "OFF".
Display language.	LNG	Change the language to display on the LCD display of teaching pendant.

5 Instruction Manual

5.1 The details of each instruction manuals

The contents and purposes of the documents enclosed with this product are shown below. Use these documents according to the application.

Instruction manuals enclosed in dashed lines in the list below are for optional products.

For special specifications, a separate instruction manual describing the special section may be enclosed.

Safety Manual

Explains the common precautions and safety measures to be taken for robot handling, system design and manufacture to ensure safety of the operators involved with the robot.

Standard **Specifications**

Explains the product's standard specifications, factory-set special specifications, option configuration and maintenance parts, etc. Precautions for safety and technology, when incorporating the robot, are also explained.

Robot Arm Setup & Maintenance

Explains the procedures required to operate the robot arm (unpacking, transportation, installation, confirmation of operation), and the maintenance and inspection procedures.

Controller Setup, Basic Operation and Maintenance

Explains the procedures required to operate the controller (unpacking, transportation, installation, confirmation of operation), basic operation from creating the program to automatic operation, and the maintenance and inspection procedures.

Detailed Explanation of Functions and Operations

Explains details on the functions and operations such as each function and operation, commands used in the program, connection with the external input/output device, and parameters, etc.

Troubleshooting

Explains the causes and remedies to be taken when an error occurs. Explanations are given for each error No.

Additional axis function

Explains the specifications, functions and operations of the additional axis control.

Tracking Function Manual

Explains the control function and specifications of conveyor tracking

Extended Function Instruction Manual

Explains the detailed description of data configuration of shared memory, monitoring, and operating procedures, about the PLC(CR750-Q/CR751-Q controller) and the GOT(CR750-D/CR751-D controller).

6 Safety

6.1 Safety

Measures to be taken regarding safety of the industrial robot are specified in the "Labor Safety and Sanitation Rules". Always follow these rules when using the robot to ensure safety.

6.1.1 Self-diagnosis stop functions

This robot has the self-diagnosis stop functions shown in Table 6-1 and the stop functions shown in Table 6-2 for safe use.

Table 6-1 : Self-diagnosis stop functions

No.	Function		Details	Remarks	
1	Overload protection function		Activates when the total servo current time exceeds the specified value.	The drive circuit is shut off. The robot stops, and an alarm displays.	
2	Overcurrent function	diagnosis	Activates when an overcurrent flows to the motor circuit.	The drive circuit is shut off. The robot stops, and an alarm displays.	
3	Encoder disconnection diagnosis function		Activates when the encoder cable is disconnected.	The drive circuit is shut off. The robot stops, and an alarm displays.	
4	Deflection over diagnosis function		Activates when an error occurs between the command value and actual position, and the error exceeds the specified amount.	The drive circuit is shut off. The robot stops, and an alarm displays.	
5	AC power voltage drop diagnosis function		Activates when the AC power voltage drops below the specified value.	The drive circuit is shut off. The robot stops, and an alarm displays.	
6	CPU error detection function		Activates when an error occurs in the CPU.	The drive circuit is shut off. The robot stops, and an alarm displays.	
7	Overrun prevention	Software limit detection	This is the limit provided by the software to enable operation only in the operation range.	The drive circuit is shut off. The robot stops, and an alarm displays.	
	function	Mechanical stopper	This is the mechanical stopper provided outside the software.	The robot mechanically stops, and function 1 or 2 activates.	

Table 6-2: List of stop functions

Stop function	Operation panel Note1)	Teaching pendant	External input	Details
Emergency stop	0	0	0	This is the stop with the highest degree of emergency. The servo power is shut off, and the mechanical brakes (all axes) activate to stop the robot. To recover, reset the alarm, and turn the servo ON with the servo ON command.
Stop	0	0	0	This is a stop operation with a high degree of emergency. The robot immediately decelerates and stops. Note that the servo power is not shut off. Use this when using the collision evasion sensor, etc.

Note1) Only CR750 controller has operation panel.

6.1.2 External input/output signals that can be used for safety protection measures

Table 6-3: External input/output signals that can be used for safety protection measures

	Signal	Connection point	Parameter	Functions	Usage method
	External emer- gency stop Note1)	Connector (CR750 controller: CNSUSR11/12) (CR751 controller:	-	This servo power is shut off, and the robot stops immediately.	Externally installed emergency stop switch. Door switch on safety protection fence. Stopping at high-level error occurrence.
	Door switch	CNSUSR1)	-		The door switch of the safe protection fence
±.	Enabling device input		-		Enabling device. The safety switch during teaching work
Input	Stop	Parallel I/O unit or interface	STOP	The program execution is stopped, and the robot stops. The servo power is not shut off.	The robot is stopped when a peripheral device fault occurs. The servo power is not shut off.
	Servo OFF		SRVOFF	The servo power can be shut off.	The robot is stopped when a peripheral device fault occurs. The servo power is not shut off.
	Automatic operation enable		AUTOENA	Disables automatic operation when inactive.	Door switch on safety protection fence
	Emergency stop output	Connector (CR750 controller: CNSUSR11/12) (CR751 controller: CNSUSR1)	-	Outputs the input signal of external emergency stop or emergency stop switch of T/B turned on.	Display and warn the pilot lamp, the input signal of external emergency stop or the emergency stop switch of T/B turned on.
Output	In servo ON	Parallel I/O unit or interface	SRVON	The servo power ON/OFF state is output.	The servo power ON/OFF state is shown and alerted with the display lamps.
Ou	Waiting		STOP	Outputs that the robot is temporarily stopped.	The temporary stop state is shown and alerted with the display lamps.
	In alarm	Connector (CR750/CR751 controller: CNUSR2)	ERRRESET -	Outputs when an alarm occurs in the robot.	The alarm state is shown and alerted with the display lamps.

Note1) The external emergency stop input is prepared as a normal close for safety proposes. Thus, if the emergency stop input circuit is opened when the robot is started up, the robot will not operate. Refer to Page 171, "6.1.7 Examples of safety measures" for details.

And, refer to Page 112, "(3) Automatic Operation/Jog Operation/Brake Release and Necessary Switch Settings" for the function of the door switch input and the enabling device input.

6.1.3 Precautions for using robot

The safety measures for using the robot are specified in the "Labor Safety and Sanitation Rules". An outline of the rules is given below.

(1) Robot installation

- Secure sufficient work space required to safely perform work such as teaching and maintenance related to the robot.
- Install the controller outside the robot's motion space. (If a safety fence is provided, install outside the fence.)
- Install the controller where the entire robot operation can be viewed.
- Install display lamps, etc., to indicate the robot's operation state.
- Securely fix the robot arm onto the fixing table with the designated bolts.

(2) Prevention of contact with operator

- · Install a safety fence or enclosure so that the operator cannot easily enter the robot's motion space.
- Install an interlock function that will stop the robot if the safety fence or enclosure door is opened.

(3) Work procedures

- · Create and observe work procedures for the robot teaching, operation, inspection and emergencies.
- Create hand signals to be followed when several operators are working together.
- Create displays such as "Teaching in Progress" and "Inspection in Progress" to be put up when an operator is
 in the robot's motion space so that other operators will not operate the operation panel (controller, control
 panel).

(4) Training

• Train the operators about the operations, maintenance and safety required for the robot work.

- Only trained and registered operators must operate the robot.
 Participation in the "Special training for industrial robots" sponsored by the Labor Safety and Sanitation Committee, etc., is recommended for safety training.
- (5) Daily inspection and periodic inspection
 - · Always inspect the robot before starting daily operations and confirm that there are no abnormalities.
 - Set the periodic inspection standards in view of the robot's ambient environment and operation frequency, and perform periodic inspections.
 - Make records when periodic inspections and repairs have been done, and store the records for three or more vears.

6.1.4 Safety measures for automatic operation

- (1) Install safety fences so that operators will not enter the operation area during operation and indicate that automatic operation is in progress with lamps, etc.
- (2) Create signals to be given when starting operation, assign a person to give the signal, and make sure that the operator follows the signals.

6.1.5 Safety measures for teaching

Observe the following measures when teaching, etc., in the robot's operation range.

- (1) Specify and follow items such as procedures related to teaching work, etc.
- (2) Take measures so that operation can be stopped immediately in case of trouble, and measures so that operation can be restarted.
- (3) Take measures with the robot start switch, etc., to indicate that teaching work is being done.
- (4) Always inspect that stop functions such as the emergency stop device before starting the work.
- (5) Immediately stop the work when trouble occurs, and correct the trouble.
- (6) Take measures so that the work supervisor can immediately stop the robot operation when trouble occurs.
- (7) The teaching operator must have completed special training regarding safety. (Training regarding industrial robots and work methods, etc.)
- (8) Create signals to be used when several operators are working together.

6.1.6 Safety measures for maintenance and inspections, etc.

Turn the power OFF and take measures to prevent operators other than the relevant operator from pressing the start switch when performing inspections, repairs, adjustments, cleaning or oiling.

If operation is required, take measures to prevent hazards caused by unintentional or mistaken operations.

- (1) Specify and follow items such as procedures related to maintenance work, etc.
- (2) Take measures so that operation can be stopped immediately in case of trouble, and measures so that operation can be restarted.
- (3) Take measures with the robot start switch, etc., to indicate that work is being done.
- (4) Take measures so that the work supervisor can immediately stop the robot operation when trouble occurs.
- (5) The operator must have completed special training regarding safety. (Training regarding industrial robots and work methods, etc.)
- (6) Create signals to be used when several operators are working together.

6.1.7 Examples of safety measures

Two emergency-stop input circuits are prepared on the user wiring terminal block of the controller. Create a circuit as shown below for safety measures. In addition, the figure shows the normal state which is not in the emergency stop state.

[Caution] Since we have omitted the information in part because of explanation, there is the section different from the product. Also refer to Page 181, "(3) External emergency stop connection [supplementary explanation]".

- [Note] In the emergency-stop related wiring by the customer, if the coil (is not the contact points) of the relay prepared by the customer is connected to the controller, please be sure to implement the measure against the noise by the customer in the coil section. And, please also take the lifetime of noise suppression parts into consideration.
 - · Electric specification of the emergency-stop-related output terminal: 100mA/24V or less
 - In the customer's system, do not ground the + side of 24V power supply prepared by customer for connect to the controller. (related with emergency stop and parallel input/output) If it connects with the controller under the condition that the + side is grounded, it will lead to failure of controller.

(1) CR750 controller

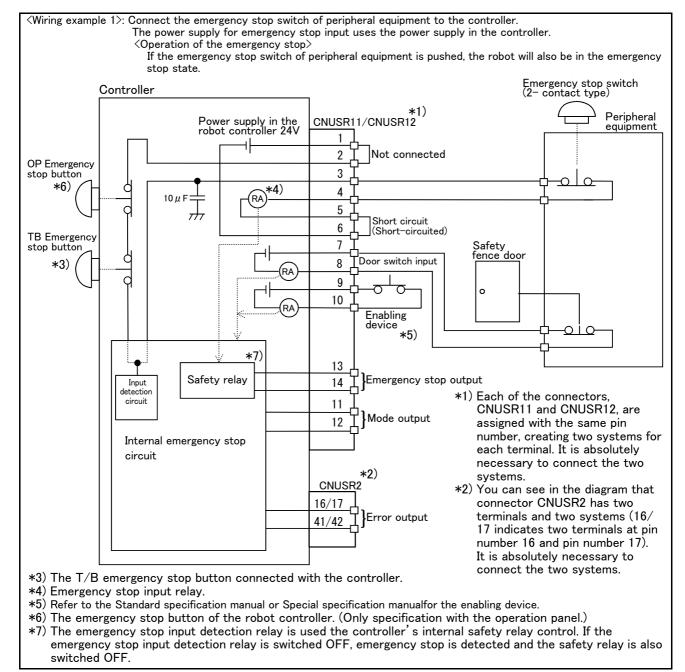


Fig.6-1: Example of safety measures (CR750 wiring example 1)

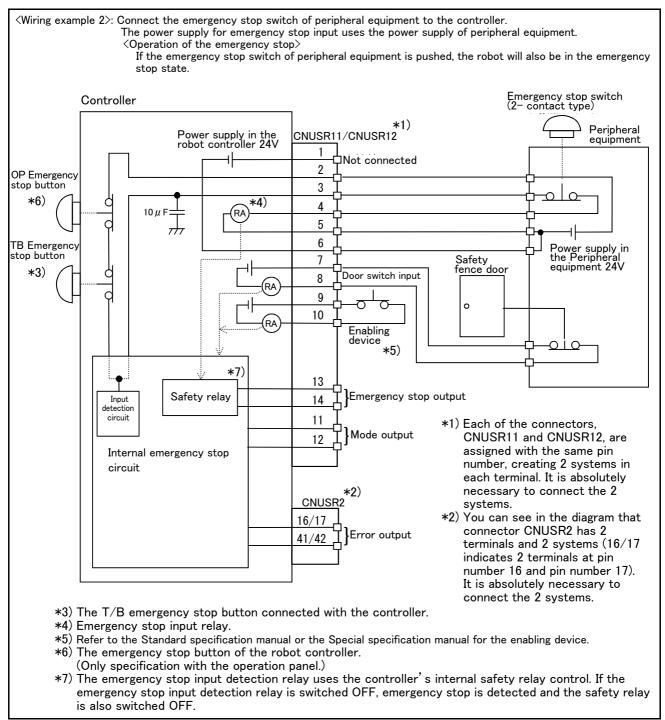


Fig.6-2: Example of safety measures (CR750 wiring example 2)

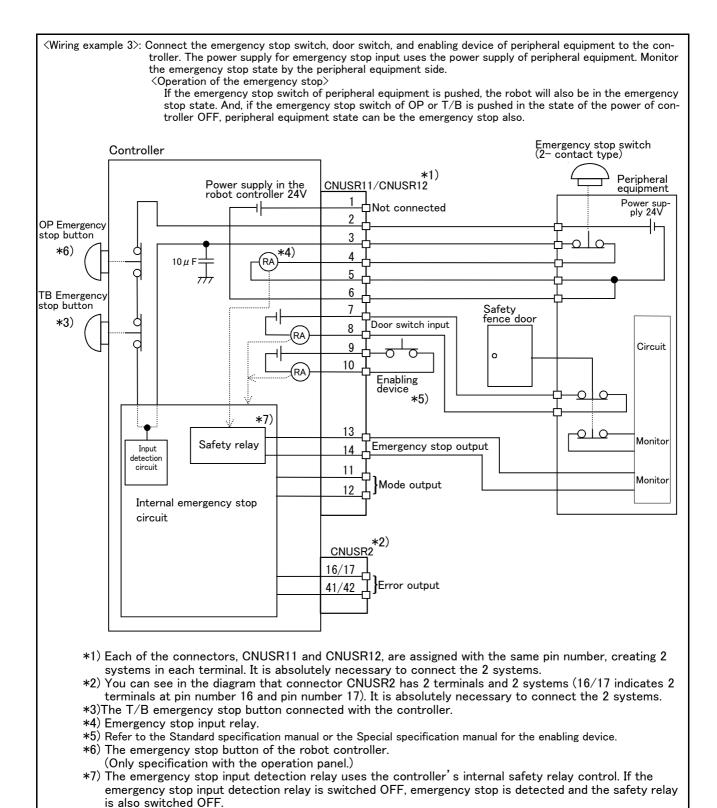


Fig.6-3: Example of safety measures (CR750 wiring example 3)

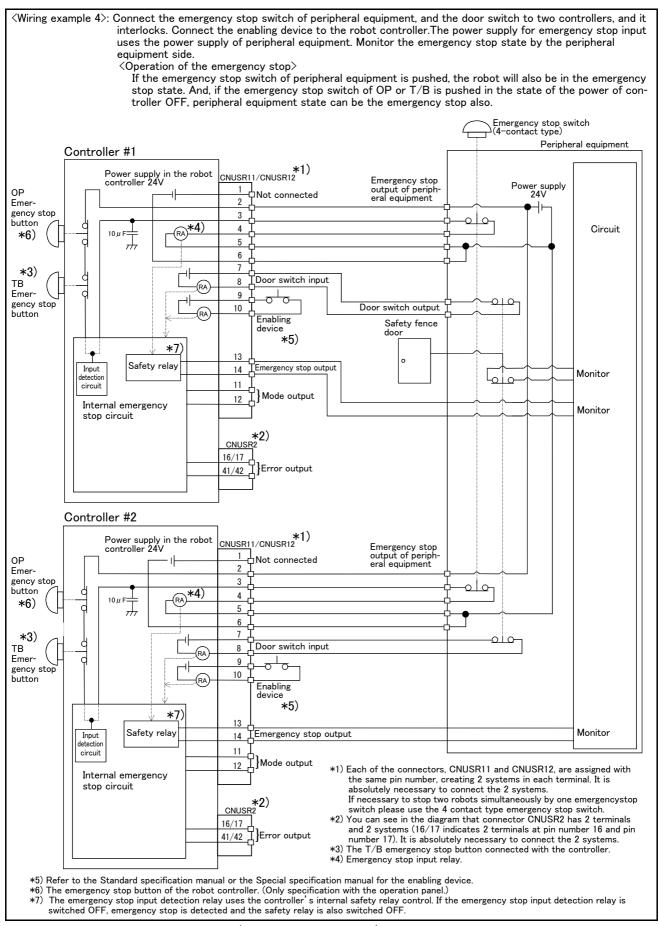
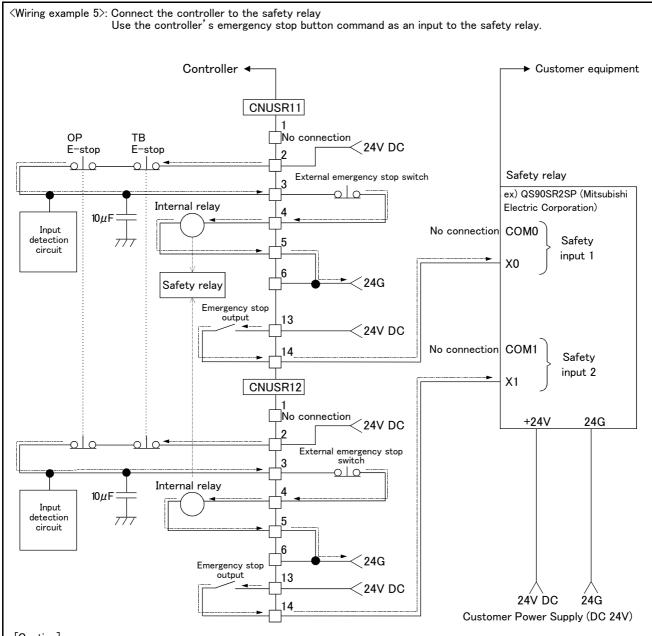


Fig.6-4: Example of safety measures (CR750 wiring example 4)



- [Caution]
 - 1) This product has category 3 functionality and therefore the robot's whole unit cannot be set to category 4.
 - 2) The controller's internal circuit has polarity. Please adhere to the polarity as detailed in the wiring examples, particularly for emergency stop button output when using user equipment. Connect the positive side of the user equipment (24V DC) to the terminal 2 of CNUSR11/12, then connect the emergency stop button (or contact points) in the user equipment to across the terminals 3 and 4 of CNUSR11/12, and ultimately connect the negative side (24G).
 - 3) When installing a safety relay to use it as an input point of the controller's emergency stop button command, use a safety relay that is activated by an input from one of the two systems (i.e. QS90SR2SP (Manufacture: Mitsubishi Electric Corporation)).
 - 4) The emergency stop input detection relay (internal relay) uses the controller's internal safety relay control. If the emergency stop input detection relay is switched OFF, emergency stop is detected and the safety relay is also switched OFF.
 - 5) When connecting emergency stop button output to an external safety relay, please take note of the polarity and make sure that the electrical current flows in the same direction as indicated by the dotted arrows in the two places in the diagram. If the polarity is setup incorrectly, this function will not operate correctly. Please connect the terminal 13 of CNUSR11/12 to 24V.

Fig.6-5: Example of safety measures (CR750 wiring example 5)

(2) CR751 controller

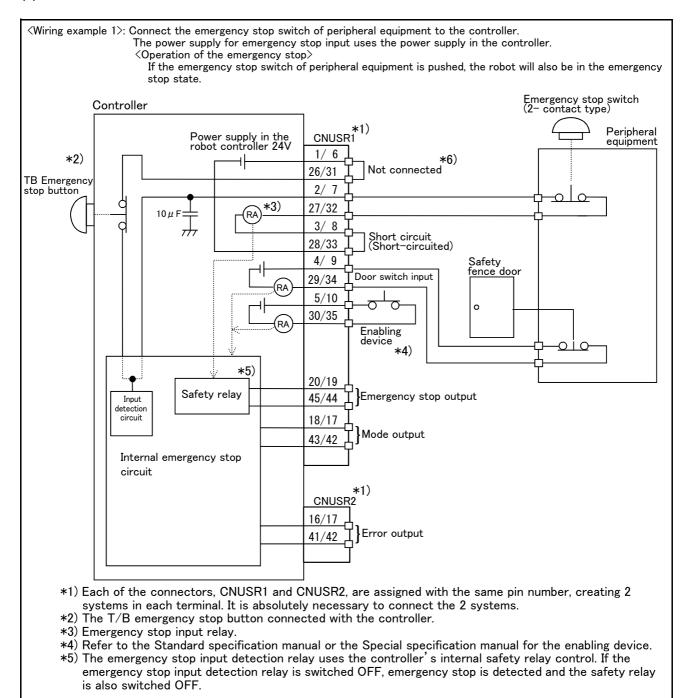
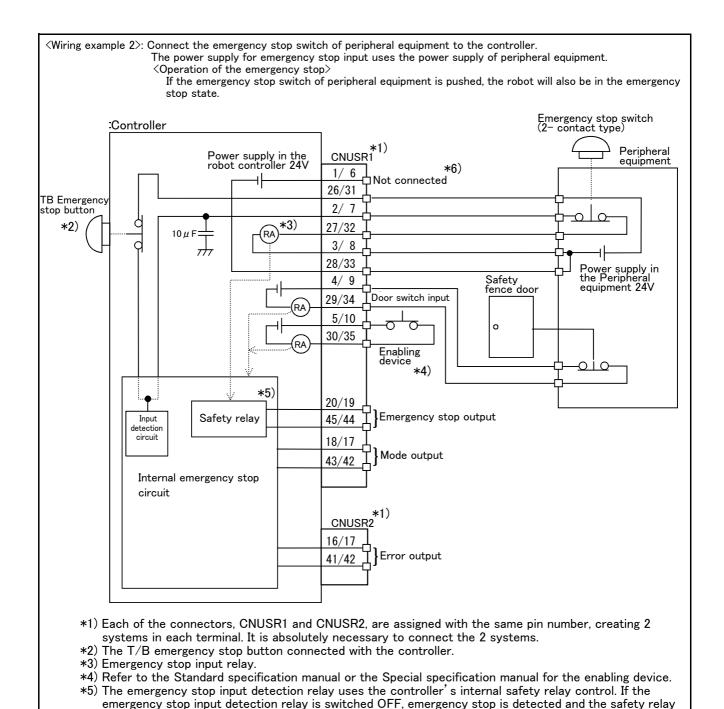


Fig.6-6: Example of safety measures (CR751 wiring example 1)



*6) Connect the 24V power supply to 26/31 terminals.

Fig.6-7: Example of safety measures (CR751 wiring example 2)

is also switched OFF.

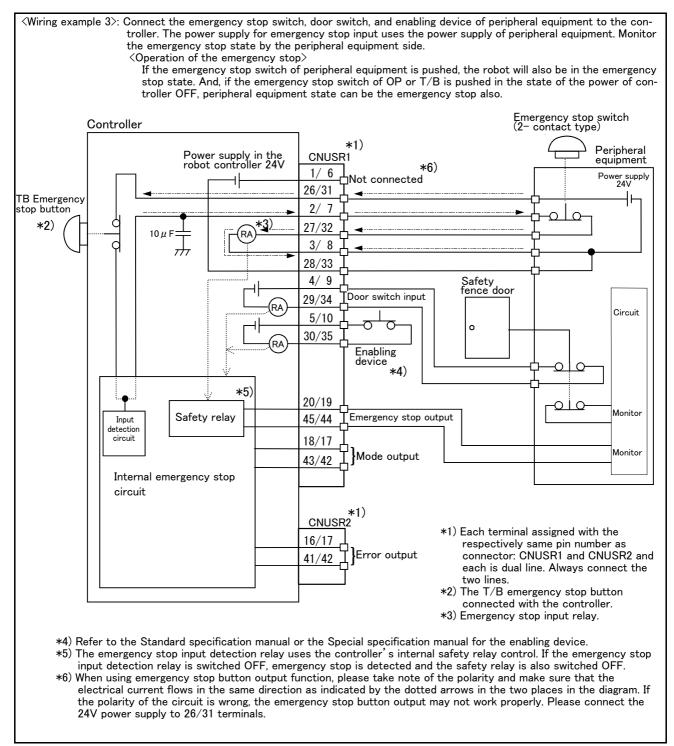


Fig.6-8: Example of safety measures (CR751 wiring example 3)

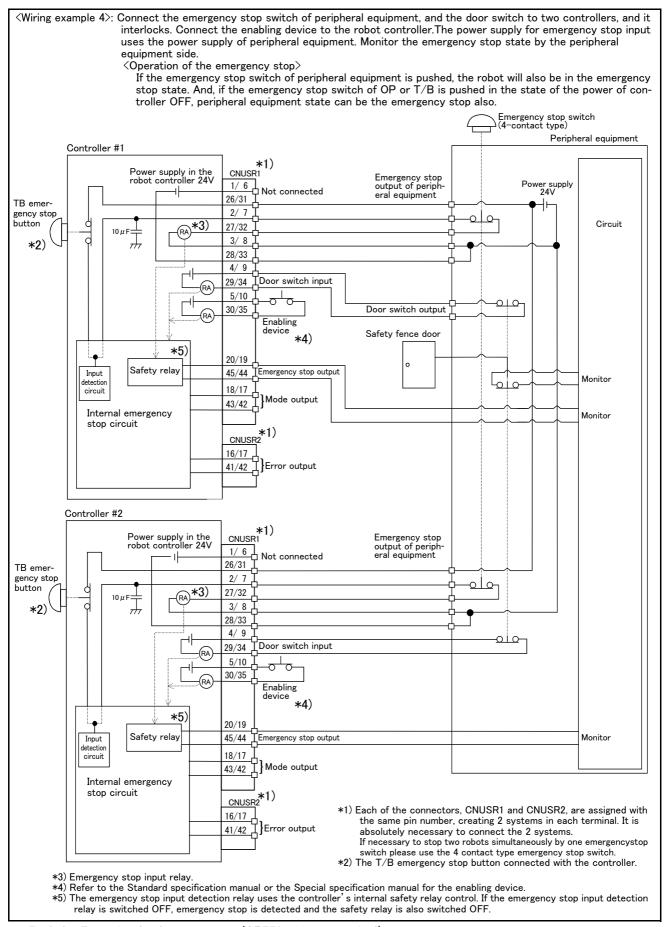
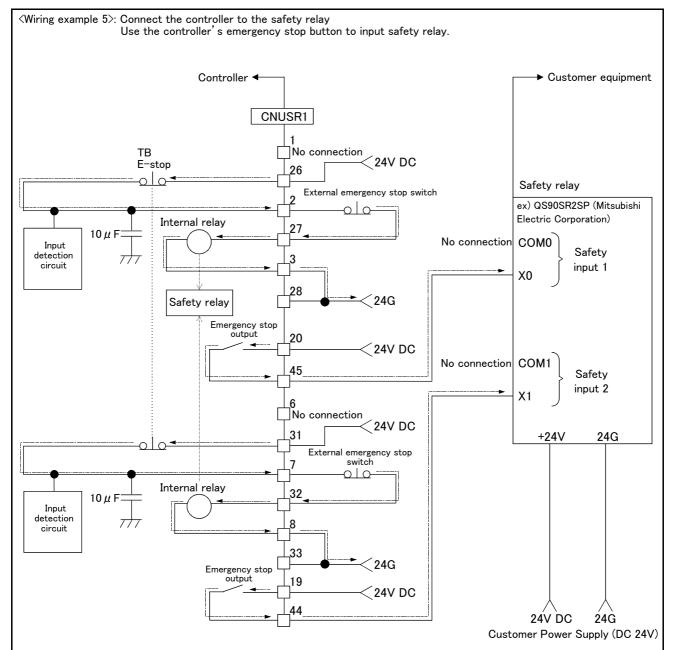


Fig.6-9: Example of safety measures (CR751 wiring example 4)



[Caution]

- 1) This product has category 3 functionality and therefore the robot's whole unit cannot be set to category 4.
- 2) The controller's internal circuit has polarity. Please adhere to the polarity as detailed in the wiring examples, particularly for emergency stop button output when using user equipment. Connect the positive side of the user equipment (24V DC) to the two terminals 26/31, then connect the emergency stop button (or contact points) in the user equipment to the 2-27 and 7-32 terminals, and ultimately connect to the negative side (24G).
- 3) Setup a safety relay on the user equipment, and when using to input the emergency stop button on the controller, please only use a safety relay that functions when connecting the input to the one end of the 2 systems (i.e. QS90SR2SP (Manufacture: Mitsubishi Electric Corporation)).
- 4) The emergency stop input detection relay (internal relay) uses the controller's internal safety relay control. If the emergency stop input detection relay is switched OFF, emergency stop is detected and the safety relay is also switched OFF.
- 5) When connecting emergency stop button output to an exterior safety relay, please take note of the polarity and make sure that the electrical current flows in the same direction as indicated by the dotted arrows in the two places in the diagram. If the polarity is setup incorrectly this function will not operate correctly. Please connect 20/19 terminal to 24V.

Fig.6-10: Example of safety measures (CR751 wiring example 5)

- (3) External emergency stop connection [supplementary explanation]
 - (1) Use a 2-contact type switch for all switches.
 - (2) Install a limit switch on the safety fence's door. With a constantly open contact (normal open), wire to the door switch input terminal so that the switch turns ON (is conducted) when the door is closed, and turns OFF (is opened) when the door is open.
 - (3) Use a manual-return type of normal close which have two lines for the emergency stop button.
 - (4) Classify the faults into minor faults (faults that are easily restored and that do not have a great effect) and major faults (faults that cause the entire system to stop immediately, and that require care in restoration), and wire accordingly.

[Caution] The emergency stop input (terminal block) on the user wiring in the controller can be used for safety measures as shown in figure above. Note that there are limits to the No. of switch contacts, capacity and cable length, so refer to the following and install.

• Switch contact.....Prepare a 2-contact type.*1)

utilize.

 Switch contact capacity...... Use a normal open contact that operates with a switch contact capacity of approx. 1mA to 100mA/24V. *1)

If you connect the relay etc., rated current of the coil should use the relay which is 100mA/24V or less. (Refer to Fig. 6-12, Fig. 6-11)

The size of the wire that fits to use is shown below.

- CR750 controller...... CNUSR11/12/13 connector: AWG #26 to #16 (0.14mm² to 1.5mm²)
- CR750 controller...... CNUSR2 connector: AWG #30 to #24 (0.05mm² to 0.2mm²)
- CR751 controller...... CNUSR1/2 connector: AWG #30 to #24 (0.05mm² to 0.2mm²)

Electric specification of the emergency stop related output circuit is 100mA/24V or less. Don't connect the equipment except for this range.

^{*1)} The minimum load electric current of the switch is more than 5mA/24V.

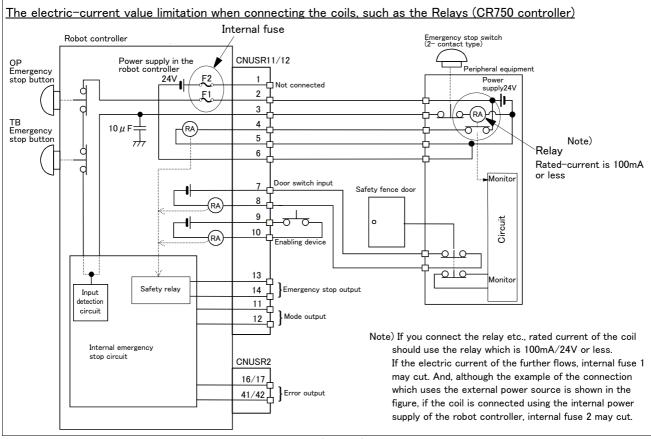


Fig.6-11: Limitations when connecting the relay etc. (CR750)

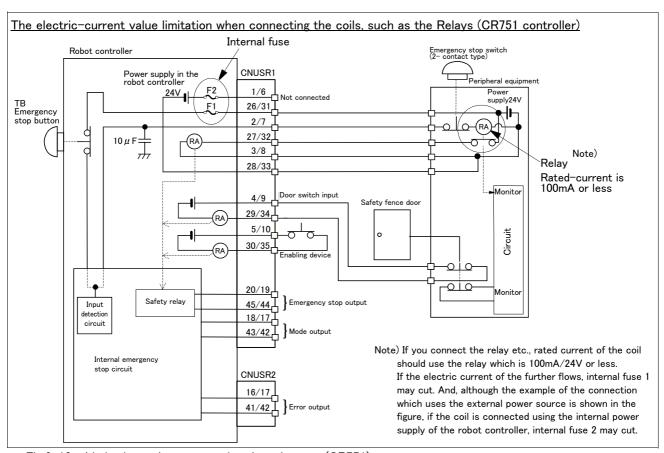


Fig.6-12: Limitations when connecting the relay etc. (CR751)

[Supplementary explanation regarding emergency stop circuit]

The controller's internal circuit is as shown in the below diagram. Be sure to build a circuit that properly shuts off the emergency stop detection relay when the emergency stop button is pressed.

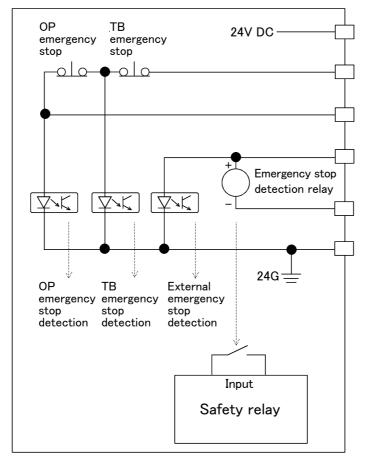


Fig.6-13: Internal circuit of controller



Be sure to perform wiring correctly. If there are mistakes in the wiring, the robot may not stop when the emergency stop button is pressed and there will be a risk of damage or personal injury occurring.

After wiring, be sure to press each of the installed emergency stop switches and check whether the emergency stop circuit works properly.



Be sure to duplicate connection of the emergency stop, door switch and enabling switch. If not duplicated, these functions may fail due to a broken relay used by customer, etc.

6.2 Working environment

Avoid installation in the following places as the equipment's life and operation will be affected by the ambient environment conditions. When using in the following conditions, the customer must pay special attention to the preventive measures.

(1) Power supply

- Where the voltage fluctuation will exceed the input voltage range.
- Where a momentary power failure exceeding 20ms may occur.
- Where the power capacity cannot be sufficiently secured.



Please use the controller with an input power supply voltage fluctuation rate of 10% or less. In the case of 200 VAC input, for example, if the controller is used with 180 VAC during the day and 220 VAC during the night, turn the servo off once and then on again. If this is not performed, an excessive regeneration or overvoltage error may occur.

(2) Noise

• Where a surge voltage exceeding 1000V, 1 μ s may be applied on the primary voltage. Near large inverters, high output frequency oscillator, large contactors and welding machines. Static noise may enter the lines when this product is used near radios or televisions. Keep the robot away from these items.

(3) Temperature and humidity

- Where the atmospheric temperature exceeds 40 degree, lower than 0 degree.
- Where the relative humidity exceeds 85%, lower than 45%, and where dew may condense.
- · Where the robot will be subject to direct sunlight or near heat generating sources such as heaters.

(4) Vibration

• Where excessive vibration or impact may be applied. (Use in an environment of 34m/s^2 or less during transportation and 5m/s^2 or less during operation.)

(5) Installation environment

- · Where strong electric fields or magnetic fields are generated.
- Where the installation surface is rough. (Avoid installing the robot on a bumpy or inclined floor.)
- · Where there is heavy powder dust and oil mist present.

6.3 Precautions for handling

- (1) This robot has brakes on J3 axes. The precision of the robot may drop, looseness may occur and the reduction gears may be damaged if the robot is moved with force with the brakes applied.
- (2) Avoid moving the robot arm by hand. When unavoidable, gradually move the arm. If moved suddenly, the accuracy may drop due to an excessive backlash, or the backed up data may be destroyed.
- (3) Note that depending on the posture, even when within the movement range, the shaft section could interfere with the base section. Take care to prevent interference during jog. *1)
- (4) The robot arm consists of precision parts such as bearing. Lubricants such as grease are also applied on the moving parts to keep the mechanical accuracy. In a cold start under low temperature or in the first start after being stored for one month or longer, lubricants may not be spread enough. Such condition may lower the positioning accuracy, cause servo and overload alarms, and early wearing of the moving parts. To avoid such situation, perform warm-up operation of the machine at a low speed (at about 20% of normal operation speed). Move the robot arm from the lower to the upper limit of the movable range with the 30 degree joint angle or more for about 10 minutes. After that, speed up the operation gradually.
 - Please use the warm-up operation. (About the details of the warm-up operation, refer to "INSTRUCTION MANUAL/Detailed explanations of functions and operations".)
- (5) When the air hoses and cables are used inside the shaft (J3 axis), the grease for cable protection may ooze out or abrasion powders may be generated from the tip of the shaft while the robot is moving. However, movements and performance of the robot are not affected. Wipe off the grease or powders as required.

^{*1)} Jog operation refers to operating the robot manually using the teaching pendant.

- (6) In the environment where hygiene management is required, clean the robot arm before use. Chemical-resistant specifications (SExx01) corresponds to the sterilization and cleaning by chemicals. And Food machinery grade H1 grease specifications (SExx02) corresponds to wiping. (Refer to Page 28, "2.2.7 Protection specifications" in detail.)
- (7) The robot arm and controller must be grounded with $100\,\Omega$ or less (class D grounding) to secure the noise resistance and to prevent electric shocks.
- (8) The items described in these specifications are conditions for carrying out the periodic maintenance and inspections described in the instruction manual.
- (9) When using the robot arm on a mobile axis or elevating table, the machine cables enclosed as standard configuration may break due to the fixed installation specifications. In this case, use "the machine cable extension (for flexed)" factory shipment special specifications or options.
- (10) If this robot interferes with the workpiece or peripheral devices during operation, the position may deviate, etc. Take care to prevent interference with the workpiece or peripheral devices during operation.
- (11) Do not attach a tape or a label to the robot arm and the controller. If a tape or a label with strong adhesive power, such as a packaging tape, is attached to the coated surfaces of the robot arm and controller, the coated surface may be damaged when such tape or label is peeled off.
- (12) If the robot is operated with a heavy load and at a high speed, the surface of the robot arm gets very hot. It would not result in burns, however, it may cause secondary accidents if touched carelessly.
- (13) Do not shut down the input power supply to stop the robot. If the power supply is frequently shut down during a heavy load or high-speed operation, the speed reducer may be damaged, backlash may occur, and the program data may be destroyed.
- (14) During the robot's automatic operation, a break is applied to the robot arm when the input power supply is shut down by a power failure, for instance. When a break is applied, the arm may deviate from the operation path predetermined by automatic operation and, as a result, it may interfere with the mechanical stopper depending on the operation at shutdown. In such a case, take an appropriate measure in advance to prevent any dangerous situation from occurring due to the interference between the arm and peripheral devices. Example) Installing a UPS (uninterruptible power supply unit) to the primary power source in order to reduce interference.
- (15) Do not conduct an insulated voltage test. If conducted by mistake, it may result in a breakdown.
- (16) Fretting may occur on the axis which moving angle or moving distance move minutely, or not moves. Fretting is that the required oil film becomes hard to be formed if the moving angle is small, and wear occurs. The axis which not moved is moving slightly by vibration etc. To make no fretting recommends to move these axes about once every day the 30 degree or more, or the 20mm or more.
- (17) The United Nations' Recommendations on the Transport of Dangerous Goods must be observed for trans-border transportation of lithium batteries by air, sea, and land. The lithium batteries (ER6, Q6BAT) used in Mitsubishi industrial robots contain lithium and fall under the definition.
 When the lithium batteries are shipped for storage, etc., they will be classified as Class 9: Miscellaneous dangerous substances and articles. Please contact your transportation company and must provide appropriate transport safety measures as the customer's consignor.
- (18) If the air supply temperature (primary piping) used for the tool etc. is lower than ambient air temperature, the dew condensation may occur on the coupling or the hose surface.
- (19) Collision detection function is valid condition for both of automatic and jog operation at shipping. So, the robot stops immediately if the robot's tool or arm interferes with a peripheral device, minimizing damage. Therefore, please use in the valid condition.
- (20) When fumigants that contain halogen materials such as fluorine, chlorine, bromine, and iodine are used for disinfecting and protecting wooden packaging from insects, they cause malfunction when entering our products. Please take necessary precautions to ensure that remaining materials from fumigant do not enter our products, or treat packaging with methods other than fumigation (heat method). Additionally, disinfect and protect wood from insects before packing products.

6.4 EMC installation guideline

6.4.1 Outlines

The EMC directive is coerced from January 1, 1996, and it is necessary to attach the CE mark which shows that the product is in conformity to directive.

Since the industrial robot is the component of the automation system, it considers that the EMC directive is not the target product of the direct. However, because it is one of the main components, introduces the method and components of the measures for conforming the automation system to the EMC directive.

And also we are carrying out the qualification test about the conformity of the EMC directive under the environment based on the contents of this document. However, the noise level is changed by the kind of equipment to be used, the layout, the construction of the controlling board, the course of wiring, etc. Therefore, please confirm by the customer eventually.

6.4.2 EMC directive

The Mitsubishi Electric industrial robot follows the European EMC directive. This technical standard regulates the following two items.

- (1) Emission (EMI: Electromagnetic Interference)......The capacity not to generate the disturbance noise which has a bad influence outside.
- (2) Immunity (EMS: Electromagnetic Susceptibility)......The capacity which does not malfunction for the disturbance noise from the outside.

Each contents are shown below.

Item	Name	Contents	Testing technical- standard number
Emission (EMI)	Radiative noise disturbance	The electromagnetic noise etc. which are emitted to environs.	EN61000-6-2 : 2005 EN61000-6-4 : 2007
	Electrical-conduction noise disturbance	The electromagnetism noise etc. which flow out of the power-supply line.	EN62061:2005(Annex E)
Immunity	Electrostatic discharge immunity test	The noise from the electrified human body.	
(EMS)	Radiated, radio-frequency, electromagnetic field immunity test susceptibility test	The electromagnetism noise from the transceiver, the broadcasting station, etc.	
	Electrical fast transient burst immunity test	The relay noise or the electromagnetism noise etc. which are caused in power-supply ON/OFF.	
	Immunity to conducted distrurbances induced radio-frequency fields	The electromagnetism noise etc. which flow in through the power source wire and the grounding wire.	
	Power frequency magnetic field immunity test	The electromagnetism noise with a power supply frequency of 50/60 Hz etc.	
	Voltage dips, short interruptions and voltage variations immunity test	The noise in the variation of the source voltage of the power dispatching, etc.	
	Surge immunity test	The electromagnetism noise by the thunderbolt, etc.	

6.4.3 EMC measures

There are mainly following items in the EMC measures.

- (1) Store into the sealed metal board.
- (2) Grounding all the conductor that have floated electrically (makes the impedance low).
- (3) Wiring so that the power source wire and signal wire are separated.
- (4) Use the shield cable for the cable which wired outside of the metal board.
- (5) Install the noise filter.

To suppress the noise emitted out of the board, be careful of the following item.

- (1) Ensure grounding of the equipment.
- (2) Use the shield cable.
- (3) Separate the metal board electrically. Narrows the distance/hole.

The strength of electromagnetic noise emitted to environment is changed a lot by the shielding efficiency of cable and the distance of metal board, so it should be careful.

6.4.4 Component parts for EMC measures

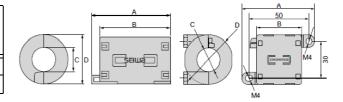
(1) Ferrite core

The ferrite core is mounted by the plastics case as one. It can attach by the one-touch, without cutting the cable. This has the effect in the common-mode noise. The measures against the noise are made not influential in the quality of the signal.

There are the following as an example.

Maker: SEIWA ELECTRIC MFG. Co.,Ltd.

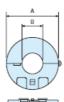
T	Out	side dim	Diameter of the		
Туре	Α	В	С	D	adaptation cable [max] (mm)
E04SR401938	61	38	19	40	19.0
E04SR301334	39	34	13	30	13.0



Maker: TAKACHI ELECTRONICS ENCLOSURE CO., LTD.

T	Out	side dim	Diameter of the		
Туре	Α	В	С	D	adaptation cable [max] (mm)
TFT-274015S	43.8	27.4	20.7	-	φ 26.5

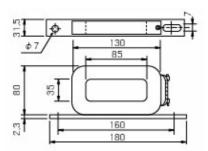






(2) Line noise filter

Type: FR-BLF (Mitsubishi Electric Corp.)



	omer informa	tion								
	pany name	<u> </u>				Name				
Address						Telephone				
Purcl	hased model									
	Item			Туре		Arm length	1	Stroke	Controller	
Chen	nical-resistant		RH-6FH	I□□△△ M−D−SEx	v01	7 till folige	•	ou one	☐ CR750-06HI	
	ifications (SExx0)1)		□□ΔΔ M-1D-SE		- □ 350 □ 450	□ 55	0 🗆 200 🗆 340	☐ CR751-06HI	
Food	machinery grade H	11grease		I□□△△ M−D−SEx					☐ CR750-06HI	
	fications (SExx02)	_	RH-6FH	□□△△ M-1D-SE	xx02	- □ 350 □ 450	□ 55	0 200 340	☐ CR751-06HI	
Shipr	oing special s	necific	ations			II.				
	В оросии о		em			Standard specification	on	Special shippin	ng specifications	
Robot	+ a			ifiti						
RODO	t arm	ľ	CE Markin	g specification		conforming with EM ctive.	iC	□ Not provided □ -8	510	
Optic	ns (Installabl	e after	shipme	nt)				1		
	Item	1		Туре		Pro	vision,	and specifications when	provided.	
arm	J1 axis operatin	g range	change	1F-DH-09		For SExx01: Not	provi	ded Provided	·	
ot a				1F-DH-01		For SExx02: Not	provi	ded 🛘 Provided		
Robot	Machine cable e	xtension	า	1S- □□ CBL-01	Fixed type (For CR750, SExx01/02): ☐ Not provide ☐ 5m ☐			□ 5m □ 10m □ 1		
_				1S- 🗆 🗆 LCBL-01		Flexed type (For CR750, SExx01/02): ☐ Not provide ☐ 5m ☐ 10m ☐				
				1F- □□ UCBL-03		Fixed type (For CR751, SExx01): ☐ Not provide ☐ 10m ☐ 15m ☐ 20i				
				1F- 🗆 🗆 LUCBL-0	• • • • • • • • • • • • • • • • • • • •					
				1F- 🗆 🗆 UCBL-02		Fixed type (For CR7	51, SE	xx02): Not provide	10m □ 15m □ 20r	
				1F- 🗆 🗆 LUCBL-02	2	Flexed type (For CR	751, SI	Exx02) 🗌 Not provide 🗆	10m	
	Solenoid valve set		1F-VD0 □ -01 1F-VD0 □ E-01	□ Not provide 1F-VD0 □ -01 1F-VD0 □ E-0	(Sink t I (Soui	zype): ☐ 1set ☐ 2set [rce type): ☐ 1set ☐ 2s	☐ 3set ☐ 4set et ☐ 3set ☐ 4set			
-	Hand input cable	e		1F-HC35C-01		□ Not provided □ Provided				
	Hand output cal	ole		1F-GR60S-01		□ Not provided □ Provided				
	Hand curl tube			1E-ST0408C-300		□ Not provided □ Provided				
	External Wiring/	Piping b	ox	1F-UT-BOX-04		For SExx01: ☐ Not provided ☐ Provided				
				1F-UT-BOX		For SExx02: ☐ Not provided ☐ Provided				
ľ	Internal Wiring/Piping for hand		r hand	1F-HS408S-01		☐ Not provided [] Prov	vided (For 200mm stroke)	
				1F-HS408S-02		□ Not provided □ Provided (For 340mm stroke)				
troller	Simple teaching Highly efficient	pendant	t	R32TB- □ □ R33TB- □ □				CR750 controller): ☐ 7m CR751 controller): ☐ 7m		
L			pendant	R56TB- □ □ R57TB- □ □		Rt	57TB (0	CR750 controller): ☐ 7m CR751 controller): ☐ 7m	□ 15m	
	Parallel I/O inte			2D-TZ368/ 2D-TZ378			2D-T	Z368(Sink type)/ ☐ -1pc Z378(Source type)/ ☐ -	1рс. □ -2рс.	
	External I/O cal (For parallel I/O		ce)	2D−CBL □□ (2D−TZ368/TZ378)		☐ Not provided [_ 5m−	()pc. □ 15m-()p	С.	
	Parallel I/O unit	I/O unit		2A-RZ361/ 2A-RZ371		☐ Not provided		-RZ361(Sink type)/(-RZ371(Source type)/(unit) unit	
	External I/O cal (For Parallel I/C			2A-CBL □□ (2A-RZ361/RZ371)] 5m−		c	
	CC-Link interfa	ce		2D-TZ576		☐ Not provided [∃ Pro\	vided		
L	Controller protection box		×	CR750-MB		For CR750 controll	er: 🔲	Not provided	ed	
-	Controller protection box					For CR751 controller: Not provided Provided				
-				CR751-MB				Not provided LI Provid	ed	
	RT ToolBox2			CR751-MB 3D-11C-WINE				Not provided ☐ Providows XP/Vista/7/8/8.1 E		
		ini				☐ Not provided ☐] Wind		nglish CD-R	

) pcs. ☐ Backup batteries Q6BAT (

Atmosphere ☐ Chemicals (Contact your dealer.) ☐ Water ☐ Other(

Work description ☐ Material handling ☐ Assembly ☐ Machining L/UL ☐ Sealing ☐ Testing and inspection ☐ Other (

Maintenance parts

Workpiece mass

■ Robot selection check list

)g

Hand mass

(

)g

☐ Backup batteries ER6 (

Remarks:

) pcs.

☐ Grease (

) cans

7Appendix Appendix 2: Specifications discussion material (RH-12FH series) ■ Customer information Company name Address Telephone Purchased model Item Arm length Controller Stroke RH-12FH □□△△ M-D-SExx01 ☐ CR750-12HD-1 Chemical-resistant □ 550 □ 700 □ 850 □ 350 □ 450 specifications (SExx01) RH-12FH □□△△ M-1D-SExx01 ☐ CR751-12HD-0 RH-12FH □□△△ M-D-SExx02 Food machinery grade H1 ☐ CR750-12HD-1 □ 350 □ 450 □ 550 □ 700 □ 850 grease specifications (SExx02) RH-12FH □□△△ M-1D-SExx02 ☐ CR751-12HD-0 ■ Shipping special specifications Standard specification Special shipping specifications CE Marking specification Not conforming with EMC □ Not provided □ -S15 Robot arm directive. Options (Installable after shipment) Туре Provision, and specifications when provided. J1 axis operating range change 1F-DH-10 For SExx01: ☐ Not provided ☐ Provided

()g (Remarks:

0	tomer inform	1				Name					
	npany name										
	ress					Telepho	ne				
urc	hased mode	l									
Item Bu co		Type	0.1	Arm le		Str		Controller			
	mical-resistant cifications (SEx)	ر01)		FH 🗆 🗆 🛆 A M-D-SExx			☐ 1000 ☐ 1000	□ 350	☐ 450	☐ CR750-20HD	
	•			FH□□△△ M-1D-SEx			☐ 1000 ☐ 1000	□ 350	☐ 450	☐ CR751-20HD	
	d machinery grad se specifications			FH □□△△ M-D-SExx FH □□△△ M-1D-SEx			□ 1000 □ 1000	□ 350 □ 350	□ 450 □ 450	☐ CR750-20HD	
_				FH LLAA M-1D-3EX	XUZ	□ 630	□ 1000	□ 330	□ 450	☐ CR751-20HD	
riip	ping special				T _			_			
		Ite	m			andard spec				g specifications	
	ot arm			ing specification	Not c direct	onforming w	th EMC	□ Not prov	rided □ −S	15	
)pti	ons (Installat	ole after	shipm	ent)							
	iter			Туре					tions when p	rovided.	
arm	J1 axis operati	ing range c	hange	1F-DH-10				☐ Provide			
Robot a				1F-DH-02	For	SExx02: 🗆 l	Not provided	☐ Provide	ed		
S _o	Machine cable	extension		1S- 🗆 CBL-01	+				-	5m 🗆 10m 🗆 15m	
				1S- 🗆 LCBL-01	+				-	5m 🗆 10m 🗆 15n	
				1F- 🗆 UCBL-03	Fixe	d type (For C	R751, SExx0	1):	ovide 🗌 10m	□ 15m □ 20m	
				1F- 🗆 LUCBL-03	Flex	ed type (For	CR751, SExx	01): 🗌 Not p	rovide 🛮 10ı	m □ 15m □ 20m	
				1F- 🗆 UCBL-02	Fixe	Fixed type (For CR751, SExx02): ☐ Not provide ☐ 10m ☐ 15m ☐ 20m					
				1F- 🗆 LUCBL-02	Flex	Flexed type (For CR751, SExx02) Not provide 10m 15m 20m					
	Solenoid valve set		1S-VD0 □ -01 1S-VD0 □ E-01	1	☐ Not provide 1S-VD0 ☐ -01 (Sink type): ☐ 1set ☐ 2set ☐ 3set ☐ 4set 1S-VD0 ☐ E-01 (Source type): ☐ 1set ☐ 2set ☐ 3set ☐ 4set						
	Hand input cable Hand output cable Hand curl tube			1F-HC35C-02		lot provided	☐ Provide	d			
				1F-GR60S-01		□ Not provided □ Provided					
				1N-ST0608C-01	□ Not provided □ Provided						
	External Wiring/Piping box		х	1F-UT-BOX-03	For SExx01: ☐ Not provided ☐ Provided						
		•		1F-UT-BOX-01	For SExx02: ☐ Not provided ☐ Provided						
	Internal Wiring	/Piping for	hand	1F-HS604S-01	☐ Not provided ☐ Provided (For 350mm stroke)						
				1F-HS604S-02		□ Not provided □ Provided (For 450mm stroke)					
ontroller	Simple teachin	g pendant		R32TB- □ □ R33TB- □ □	□N	□ Not provided R32TB (CR750): □ 7m □ 15m R33TB (CR751): □ 7m □ 15m					
Con	Highly efficient dant	t teaching _l	oen-	R56TB- □□ R57TB- □□	☐ Not provided R56TB (CR750): ☐ 7m ☐ 15m R57TB (CR751): ☐ 7m ☐ 15m						
	Parallel I/O int	Parallel I/O interface		2D-TZ368/ 2D-TZ378		□ Not provided 2D-TZ368(Sink type)/ □ -1pc. □ -2pc. 2D-TZ378(Source type)/ □ -1pc. □ -2pc.					
	External I/O c (For parallel I/		e)	2D−CBL □ □ (2D−TZ368/TZ378)		lot provided	□ 5m-()pc. ☐ 15n	n-()pc.		
	Parallel I/O un	iit		2A-RZ361/ 2A-RZ371		lot provided		Z361(Sink ty _l Z371(Source		t unit	
	External I/O c (For Parallel I/			2A-CBL □□ (2A-RZ361/RZ371)		lot provided	□ 5m-()pc. ☐ 15n	n-()pc.		
	CC-Link interf			2D-TZ576		lot provided					
	Controller prot	tection box		CR750-MB	+	50 : □ Not _I					
				CR751-MB	+	51 : □ Not ¡					
	RT ToolBox2			3D-11C-WINE					1/8/8.1 Englis		
	RT ToolBox2 r			3D-12C-WINE	_				//8/8.1 Englis	sh CD-ROM	
	Instructions m			5F-FB03-PE01		lot provided	☐ Provide	d () sets			
1ain	tenance par										
Ма	intenance par	ts □ Ba	ckup ba	tteries ER6 () pcs.	□Ва	ckup batteri	es Q6BAT	() pcs.	☐ Grease (() cans	
	ot selection o	check lis	t								
Robo	ot selection (oricon no	-								
				; ☐ Assembly ☐ Mac	hining	L/UL □ Se	aling 🗆 Te	sting and ins	pection 🗆 C	Other ()	



EC-Statement of Compliance

No. E6 15 02 25554 053

Holder of Certificate: Mitsubishi Electric Corporation

Tokyo BILD., 2-7-3 Marunouchi,

Chiyoda-ku Tokyo

100-8310 JAPAN

Name of Object:

Industrial, Scientific and Medical

equipment

Industrial Robot

Model(s):

F series

(See Attachment for Nomenclature)

Description of

Object:

Rated Voltage:

230 VAC

Rated Power:

1.7 kW

Protection Class: 1

Tested according to:

EN 61000-6-4/A1:2011

EN 61000-6-2:2005

This EC-Statement of Compliance is issued according to the Directive 2004/108/EC relating to electromagnetic compatibility. It confirms that the listed apparatus complies with such aspects of the essential requirements of the EMC directive as specified by the manufacturer or his authorized representative in the European Community and applies only to the sample and its technical documentation submitted to TÜV SÜD Product Service GmbH for testing and certification. See also notes overleaf.

Technical report no.:

73552066

Date, 2015-02-10 (Johann Roidt)



TÜV SÜD Product Service GmbH is Notified Body to the Directive 2004/108/EC of the European Parliament and of the council with the identification number 0123.

Page 1 of 8

Statement No.

E6 15 02 25554 053



Product Service

A: Model name of **F** series Robot description is shown as follows. A1:RH-3FH,RH6FH,RH-2FH series 1.7kW

RH-x FH xx xx x - x x x-Sxx

(1) (2) (3) (4) (5) (6) (7) (8) (9) (10) (11)

(1)RH: Horizontal Robot

(2) Maximum Payload specification:

3 : 3kg **2** : 2kg

6 : 6kg

(3) **F** : **F** series robot

(4)**H** :4 joints

(5) Robot Arm length(No1 and No2 arm) specification:

35 : 350 mm arm **15** : 150 mm arm

45 : 450 mm arm **55** : 550 mm arm

(6) Z stroke length specification:

12 : 120 mm arm **25** : 250 mm arm

15 : 150 mm arm 20 : 200 mm arm 34 : 340 mm arm

(7) Dimension and Ambient specification:

M : Oil mist model(IP65)C : Clean room model(ISO5)

[none] : Basic model(IP54)

(8) Type of Robot controller cabinet

[none] :CR750 controller

1 :CR751 controller

(9)Robot controller type:

Stand alone typeiQ platform type

(10)Standard:

0: normal type

1:CE marking model

2:CE marking and UL model

(11)Optional Specification:

1 :normal type

SM :added cabinet box over Robot controller for oil mist resist

Sxx :Mechanical option

Statement No.

E6 15 02 25554 053



A2:RH-12FH,RH-20FHseries 1.7kW

RH-x FH xx xx x - x x x-Sxx

(1) (2) (3) (4) (5) (6) (7) (8) (9) (10) (11)

(1)RH: Horizontal Robot

(2) Maximum Payload specification:

12 : 12kg 20 : 20kg

: F series robot (3) **F**

(4)**H** :4 joints

(5) Robot Arm length(No1 and No2 arm) specification:

: 550 mm arm 55 70 : 700 mm arm 85 ; 850 mm arm 100 : 1000 mm arm

(6) Z stroke length specification:

35 : 350 mm arm : 450 mm arm 45

(7) Dimension and Ambient specification:

: Oil mist model(IP65) : Clean room model(ISO3) C : Special spec. For EU(IP54) Ν

[none]: Basic model(IP20)

(8) Type of Robot controller cabinet

[none] :CR750 controller :CR751 controller 1 (9)Robot controller type:

:Stand alone type :iQ platform type Q

(10)Standard:

0: normal type

1:CE marking model

2:CE marking and UL model

(11)Optional Specification:

1 :normal type

:added cabinet box over Robot controller for oil mist resist SM

Statement No.

E6 15 02 25554 053



Product Service

A3:RV-2Fseries 1.7kW

RV-x F x x - x x x-Sxx

(1) (2) (3) (4)(5) (6)(7) (8) (9)

(1) RV: Vertical Robot

(2) Maximum Payload specification:

2 : 2kg

: F series robot (3) **F**

(4)Robot Joint type

:All axes have brake units.

[none] :J4 axis doesn't have brake unit.

(5)Robot Arm length

: Long Arm model [none] : normal model

(6) Type of Robot controller cabinet

[none] :CR750 controller :CR751 controller

(7)Robot controller type:

:Stand alone type :iQ platform type

(8)Standard:

0: normal type

1:CE marking model

2:CE marking and UL model

(9)Optional Specification:

1 :normal type

:added cabinet box over Robot controller for oil mist resist SM

CERTIFICATE

Attachment

Statement No.

E6 15 02 25554 053



Product Service

A4:RV-4F,7Fseries 1.7kW

RV - x F x x x - x x x - Sxx

(1) (2) (3) (4)(5) (6)

(10)(7) (8) (9)

(1)RV: Vertical Robot

(2) Maximum Payload specification:

: 4kg 7 : 7kg

: F series robot (3) **F**

(4) Robot axes:

: 5 axes model [none]: normal model

(5) Robot arm length:

: Long arm model [none]: normal model

(6) Dimension and Ambient specification:

: Oil mist model(IP67) M : Clean room model(ISO3) C

[none] : Basic model(IP40)

(7) Type of Robot controller cabinet

:CR750 controller [none] :CR751 controller (8)Robot controller type:

:Stand alone type D

:iQ platform type Q

(9)Standard:

0: normal type 1:CE marking model

2:CE marking and UL model

(10)Optional Specification:

:normal type 1

:added cabinet box over Robot controller for oil mist resist SM

:Internal tube and wires are extended to J6 axis. SH

ZERTIFIKAT + CERTIFICATE

Attachment

Statement No.

E6 15 02 25554 053



Product Service

A5:RV-13F,20F,7FLLseries 1.7kW

RV-x F x x - x x x - Sxx

(1) (2) (3) (4) (5) (6) (7) (8) (9)

(1) RV: Vertical Robot

(2) Maximum Payload specification:

13

: 13kg

20

: 20kg

7

: 7kg

(3) F

: F series robot

(4) Robot arm length:

: Long arm model

LL

: Long reach(1503mm) model (for onlyRV-7FLL series)

[none]: normal model

(5) Dimension and Ambient specification:

M

: Oil mist model(IP67)

C

: Clean room model(ISO3)

[none] : Basic model(IP40)

(6) Type of Robot controller cabinet

[none]

:CR750 controller

:CR751 controller

(7)Robot controller type:

D

:Stand alone type

Q

:iQ platform type

(8)Standard:

0: normal type

1:CE marking model

2:CE marking and UL model

(9)Optional Specification:

1

:normal type

SM

:added cabinet box over Robot controller for oil mist resist

SH Sxx :Internal tube and wires are extended to J6 axis. :Mechanical option

Statement No.

E6 15 02 25554 053



Product Service

A6:RH-1FHR,RH-3FHR series 1.7kW

RH-x F HR xx xx x - x x x - Sxx

(1) (2) (3) (4) (5) (6) (7) (8) (9) (10) (11)

: 750 mm arm

(1)RH: Horizontal Robot

(2) Maximum Payload specification:

: 1kg

3 : 3kg

55

; **F** series robot (3) **F**

:4 joints ,reverse mount model (4)**HR**

(5) Robot Arm length(No1 and No2 arm) specification:

75 : 350 mm arm

: 550 mm arm

(6) Z stroke length specification:

: 120 mm arm 12 : 150 mm arm 15

(7) Dimension and Ambient specification:

W : Water proof model : Oil mist model M

: Clean room model(ISO5)

[none] : Basic model(IP54)

(8) Type of Robot controller cabinet

[none] :CR750 controller :CR751 controller (9)Robot controller type:

:Stand alone type D Q :iQ platform type

(10)Standard:

0: normal type

1:CE marking model

2:CE marking and UL model

(11)Optional Specification:

:normal type 1

:added cabinet box over Robot controller for oil mist resist SM

Statement No.

E6 15 02 25554 053



Product Service

B: Model name of **F** series Robot controller description is shown as follows.

CR750- $xx \times x \times x - x - x - Sxx$

(2) (3) (4) (5) (6) (7) (1)

(1)CR750: CR750 controller

CR751: CR751 controller (2) Maximum Payload specification:

01 : 1kg

03 : 3kg

06 : 6kg

12 : 12kg

20 : 20kg

02

: 2kg

04 : 4kg

07 : 7kg

13 : 13kg

(3) Robot type

Н : Horizontal robot

: Horizontal robot(reverse mount) HR

V : Vertical robot

VJ : 5 axes Vertical robot

: for only RV-7FLL series VL

(4)Robot controller type

:stand alone D

Q :iQ platform type

(5)Standard

:CE marking model

:CE marking and UL model

(6)Operation Panel

:No panel type [none]

:Panel type

(7)Power input connector type

[none] :normal type

:Added cable with a connector and a terminal P2

:Added cable with a connector and a terminal block Р3

(8)Optional Specification

[none] :normal

:Added Cabinet box over robot controller for oil mist resist SM



EC DECLARATION OF CONFORMITY (According to EMC Directive) EC DECLARATION OF INCORPORATION (According to Machinery Directive)

We.

Manufacturer:

MITSUBISHI ELECTRIC Corporation Nagoya Works

Address

1-14 Yada-Minami 5-Chome Higashi-Ku, Nagoya 461-8670, Japan

(Place of Declare):

Declare under our sole responsibility that the Product

Description:

Industrial Robot

Type of Model:

F series

Notice:

Details of Serial number are as per attached Nomenclature.

Restrictive use:

For industrial environment only

Conforms with the essential requirements of the EMC Directive 2004/108/EC and the Machinery Directive 2006/42/EC, based on the following specifications applied:

EU Harmonized Standar	EU Harmonized Standards					
EMC(2004/108/EC)	MC(2004/108/EC) EN 61000-6-4:2007+A1:2011 EN61000-6-2:2005					
Machinery (2006/42/EC)	Type A:Fundamental safety standards EN ISO12100-1:2003 EN ISO12100-2:2003 EN 1050:1997	N/A				
	Type B:Group safety standards B1:Safety aspects EN60204-1:2006, ISO 13857:2008, ISO 13854:1996 IEC61326-3-1:2008					
	ISO13849-1:2006 (Category 3 and Performance level "d") Type C:Machine Safety standard					
E * 2	ISO10218-1:2011					

and therefore complies with the essential requirements and provisions of the EMC Directive and the Machinery Directive.

< Partly completed Machinery>

This product meets the specification and/or the performance by correct installing. So it must not be used until being installed into the final machinery of the customer.

Issue Date (Date of Declaration):

Feb 23 20/5-

The identity and signature of the person empowered to bind the manufacturer or his authorized representative.

(signature

[Tomoyuki Kobayashi]

Senior Manager

Robot Manufacturing Department

MITSUBISHI ELECTRIC Corporation Nagoya

Works

Authorized representative in Europe

(The person-authorized compiles the relevant

Technical documentation)

(signature)

[Hartmut Putz]

FA Product Marketing Director FA Group Gother St. 8 40880 Ratingen ,Germany MITSUBISHI Electric Europe B.V Germany

Page 1 of 9

BFP-A5735-18-G

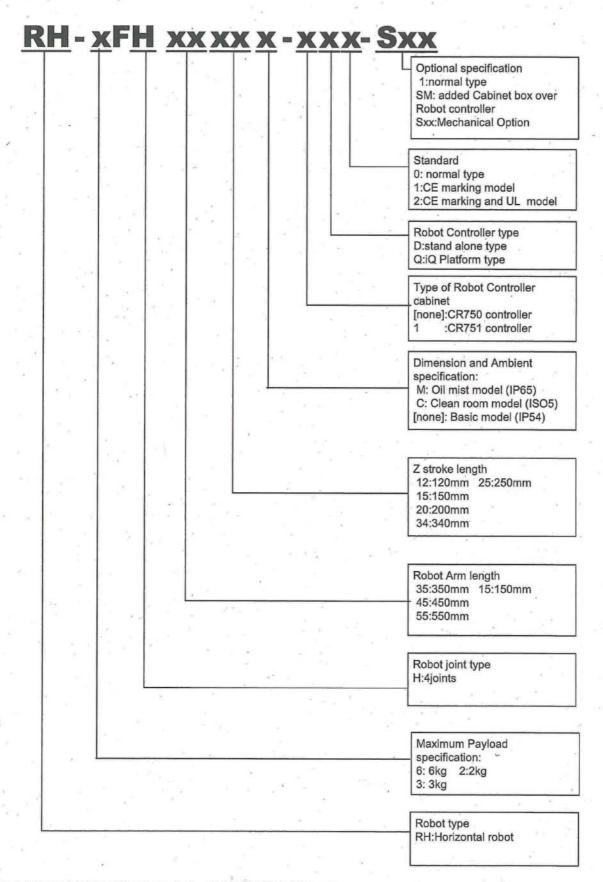


Fig.1-1 Nomenclature of F series robot of RH-6FH,3FH ,2FH series

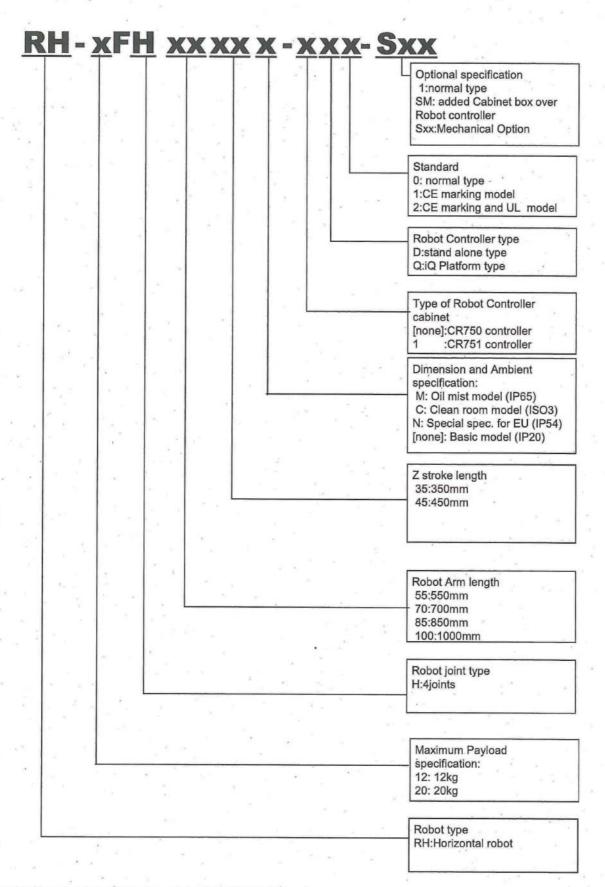


Fig.1-2 Nomenclature of F series robot of RH-12FH,20FH series

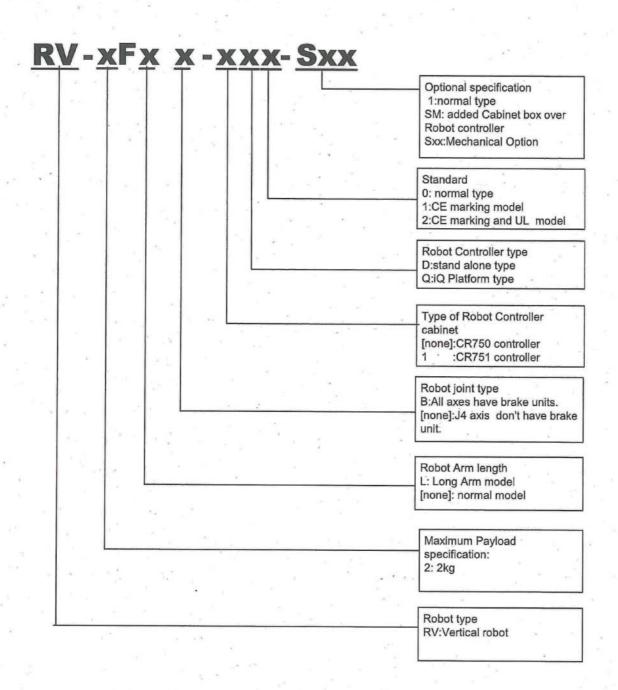


Fig.1-3 Nomenclature of F series robot of RV-2F series

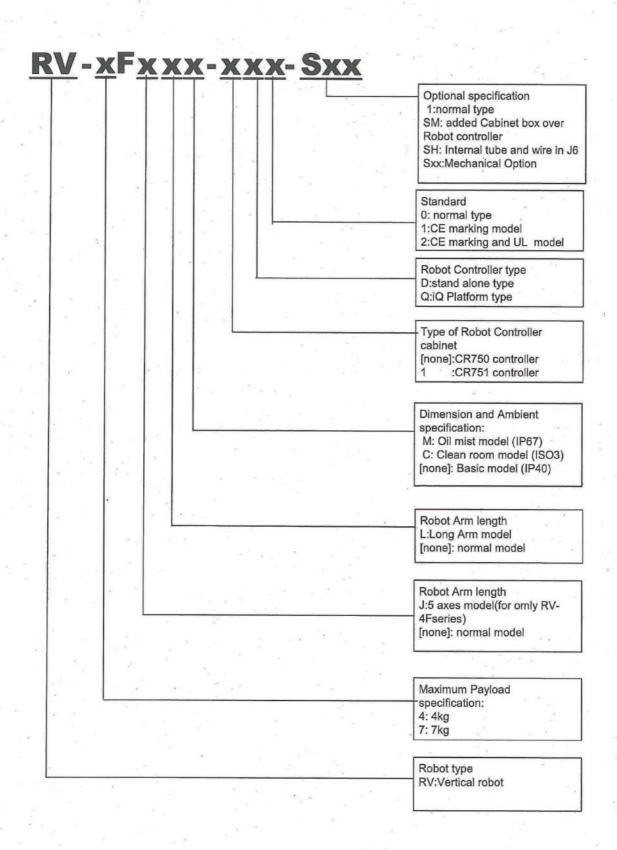


Fig.1-4 Nomenclature of F series robot of RV-4F,7F series

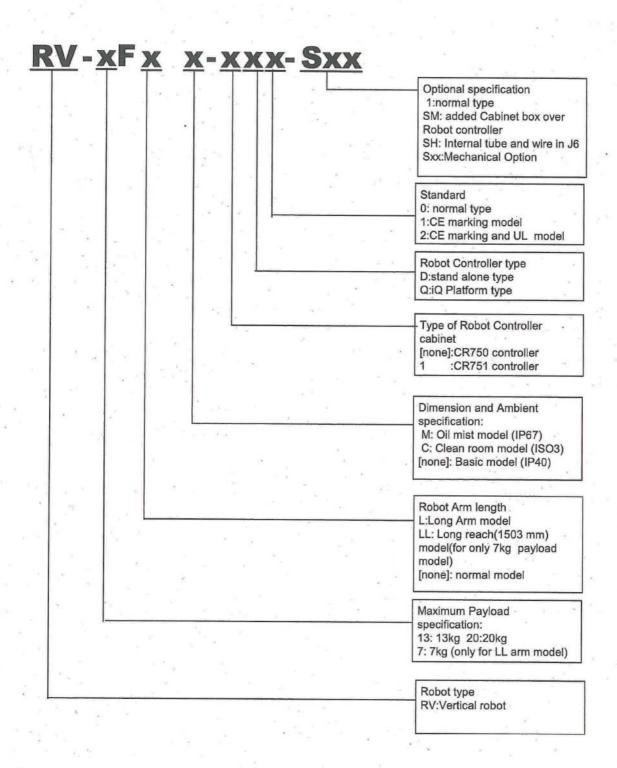


Fig.1-5 Nomenclature of F series robot of RV-13F,20F,7FLL series

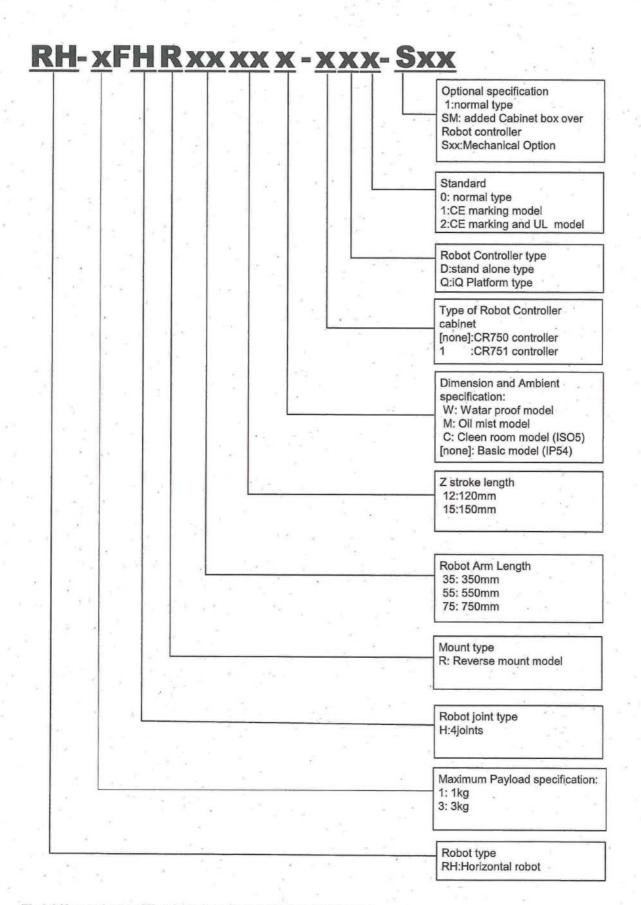


Fig.1-6 Nomenclature of F series robot of RH-1FHR, RH-3FHR series

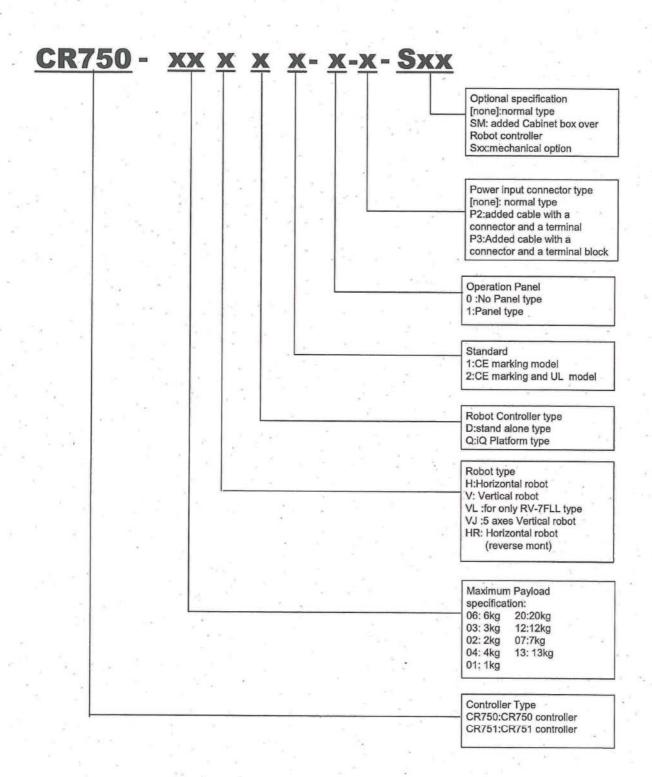


Fig.2-1 Nomenclature of F series robot controller

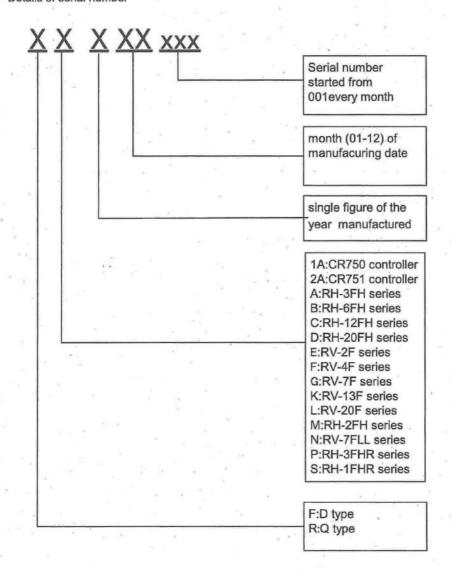


Fig.3.1 Nomenclature of serial number about F series Robot and robot controller

Revision history

Date	Specifications No.	Details of revisions	Rev.
April 16,2012		First print	*
May 25, 2012		Q type are added.	Α
Oct 1, 2012	Fig.1-2,1-3,1-4 added	RH-12/20FH-D series,RV-2F-D series,RV-4F/7F-D series are added.	В
Nov 1,2012	P1 P3-P7	Form is changed. RH-12/20FH-Q series,RV-2F-Q series,RV-4F/7F-Q series are added "Details of serial No." is added	С
Apr 15, 2013	P2,P6,P7,P8	RH-2FH series,RV-13F,20FH,7FLL series are added	D
Mar 12,2014	P1 P5	Standards are updated. "J"option added (RV-4FJseries added)	E
Apr 24, 2014	P1	Standards are updated.	
Jul 9 2014	P7	RH-3FHR series and RH-1FHR series are added.	1
Feb.3,2015	P1 P4	Standards are updated. Nomenclature of RV-2F series update(added RV-2FL series added)	G

MITSUBISHI ELECTRIC CORPORATION HEAD OFFICE: TOKYO BUILDING, 2-7-3, MARUNOUCHI, CHIYODA-KU, TOKYO 100-8310, JAPAN NAGOYA WORKS: 5-1-14, YADA-MINAMI, HIGASHI-KU NAGOYA 461-8670, JAPAN

Authorised representative:
MITSUBISHI ELECTRIC EUROPE B.V. GERMANY
Gothaer Str. 8, 40880 Ratingen / P.O. Box 1548, 40835 Ratingen, Germany