

**NACHI**

Standard specifications

**MC20-01/03 [AX20/FD11]  
MC10L-01/03 [AX20/FD11]  
MC12S-01/03 [AX20/FD11]**

22nd edition



**NACHI-FUJIKOSHI CORP.**

1707, SMCEN-017-022,001



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## 1. Outline

NACHI ROBOT has used mechatronic techniques, cultivated throughout the last few decades, to supply robots suited multi-purpose for industries utilizing welding, spray painting and the material handling techniques.

The MC robot is a 6 axes robot that has characteristics like listed as below.

- Simple structure
- High speed
- High accuracy
- Suitable for material handling applications

Installation \ Arm type Load weight	Standard arm 20 kg (Max.22Kg)	Long arm 10 kg	Short arm 12 kg
Floor mount Inverted mount	MC20-01 MC20-03	MC10L-01 MC10L-03	MC12S-01 MC12S-03 (*1)
Wall mount	×	×	

\*1; If wall mount is selected, wall mount option (OP-S7-010) is necessary.

### ■ Characteristic

1. This robot is designed so that the size of the motion range is similar to that of one worker. Therefore, it becomes possible to make a compact robot cell. And, this robot is also suitable for a loading application for randomly workpieces.
2. The wide motion range lightens the limitation of the actual motion range. And examining applicability becomes easier than before.
3. The wrist and the main body become “Dust-proof / Drip-proof performance (IP65 corresponding)”, and the application that can be applied has extended.
4. The motion range suitable for the weight of the workpieces or tools can be selected. Because of this, it becomes possible to use a heavier workpiece, double hand, etc.

## 2. Basic specifications

Item		Specifications		
Robot model		MC20-01 MC20-03 <sup>*8</sup>	MC10L-01 MC10L-03 <sup>*7</sup>	MC12S-01 MC12S-03 <sup>*9</sup>
Construction		Articulated		
Number of axis		6		
Drive system		AC servo motor		
Max. working envelope	Axis 1	$\pm 3.14$ rad ( $\pm 180^\circ$ ) <sup>*4</sup>		
	Axis 2	$+1.05 \sim -2.53$ rad ( $+60 \sim -145^\circ$ ) <sup>*4</sup>		
	Axis 3	$+4.22 \sim -2.84$ rad ( $+242 \sim -163^\circ$ )	$+4.22 \sim -2.69$ rad <sup>*4</sup> ( $+242 \sim -154^\circ$ )	
	Axis 4	$\pm 3.14$ rad ( $\pm 180^\circ$ ) <sup>*4</sup>		
	Axis 5	$\pm 2.42$ rad ( $\pm 139^\circ$ ) <sup>*4</sup>		
	Axis 6	$\pm 6.28$ rad ( $\pm 360^\circ$ ) <sup>*4</sup>		
Max. speed	Axis 1	2.96 rad/s (170 °/s)	2.62 rad/s (150 °/s)	3.49 rad/s (200 °/s)
	Axis 2	2.96 rad/s (170 °/s)		
	Axis 3	2.96 rad/s (170 °/s)		
	Axis 4	6.28 rad/s (360 °/s)		6.46 rad/s (370 °/s)
	Axis 5	6.28 rad/s (360 °/s)		6.46 rad/s (370 °/s)
	Axis 6	10.5 rad/s (600 °/s)		12.2 rad/s (700 °/s)
Max. pay load <sup>*1</sup>		20 kg (Max. 22 kg)	10 kg	12 kg
Allowable static load torque	Axis 4	49 N·m	24.5 N·m	28 N·m
	Axis 5	49 N·m	24.5 N·m	28 N·m
	Axis 6	23.5 N·m	12 N·m	13 N·m
Allowable moment of inertia <sup>*2</sup>	Axis 4	1.6 kg·m <sup>2</sup>	1.6 kg·m <sup>2</sup>	1.3 kg·m <sup>2</sup>
	Axis 5	1.6 kg·m <sup>2</sup>	1.6 kg·m <sup>2</sup>	1.3 kg·m <sup>2</sup>
	Axis 6	0.8 kg·m <sup>2</sup>	0.7 kg·m <sup>2</sup>	0.47 kg·m <sup>2</sup>
Position repeatability <sup>*3</sup>		$\pm 0.06$ mm		
Maximum air pressure		Not more than 0.49 MPa (5.0 kgf / cm <sup>2</sup> )		
Installation		Floor mount, Inverted mount		Floor mount, Inverted mount, Wall mount <sup>*4</sup>
Ambient conditions		Temperature: 0 to 45 °C <sup>*5</sup> Humidity: 20 to 85%RH (No dew condensation allowed) Vibration to the installation face: Not more than 0.5G (4.9 m/s <sup>2</sup> )		
Dust-proof / Drip-proof performance <sup>*6</sup>		IP65 equivalent (dust and drain proof-type)		
Robot mass		220 kg	225 kg	210 kg (Wall mount <sup>*4</sup> , 330 Kg)

1 [rad] = 180 /  $\pi$  [°], 1 [N·m] = 1 / 9.8 [kgf·m]

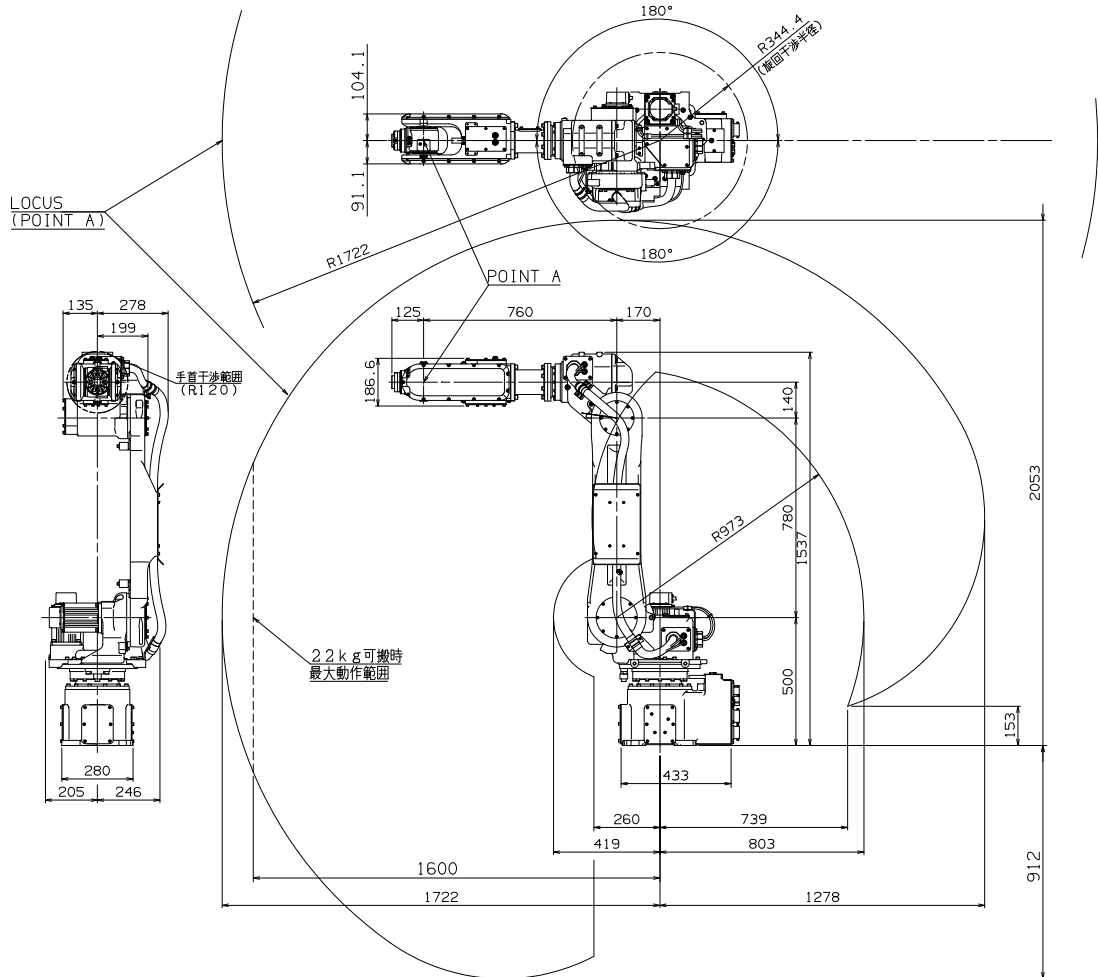
- On controller display, axis 1 to 6 is displayed J1 to J6 for each.

- The specification and externals described in this specifications might change without a previous notice for the improvement.

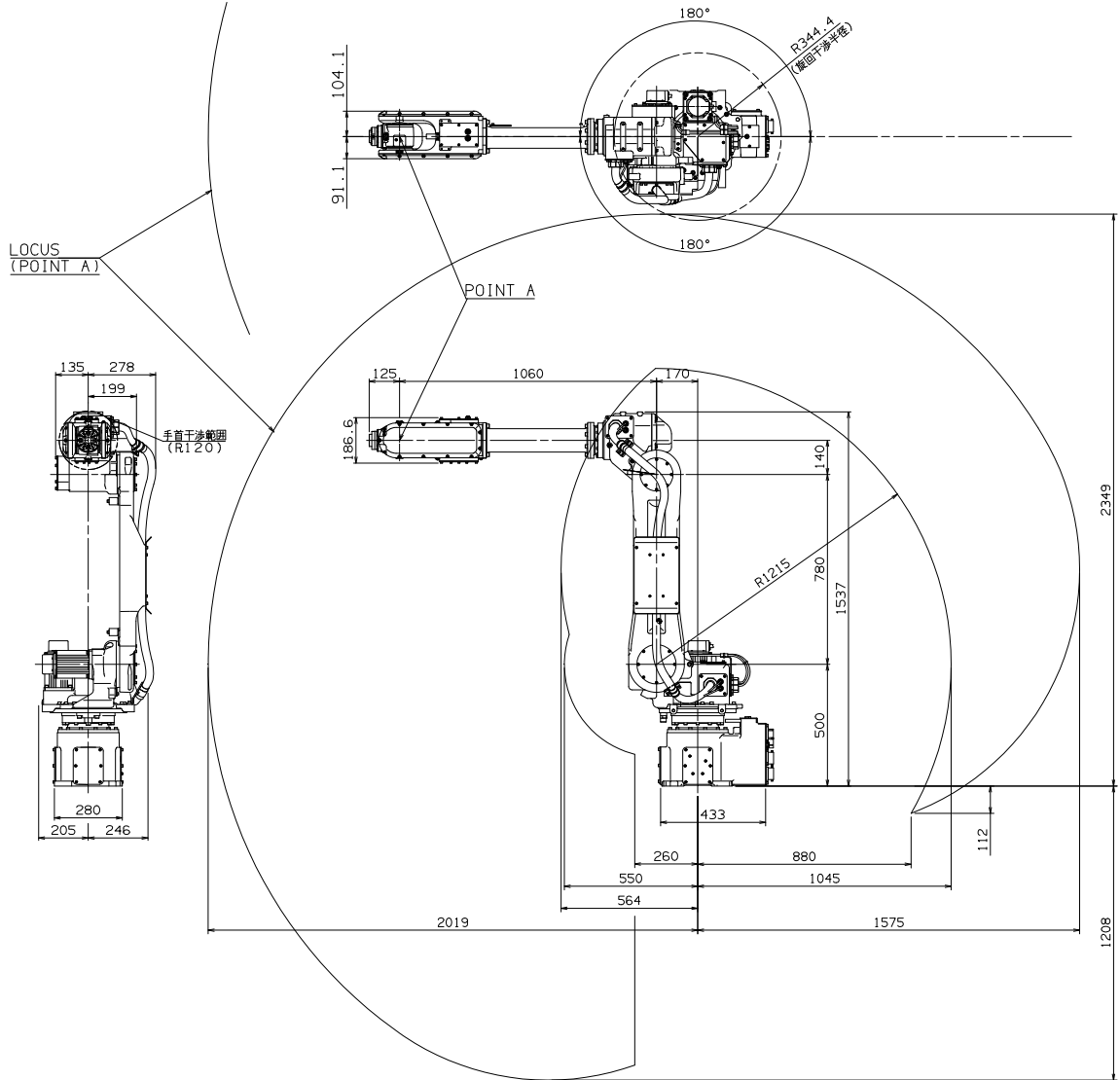
\*1: Operating range is limited according to the payload weight. \*2: The Allowable moment of inertia of a wrist changes with load conditions of a wrist. \*3: This value conforms to "JIS B 8432" standard. \*4: If wall mount is selected, wall mount option (OP-S7-010) is necessary. Working envelope and robot mass is different from those of floor mount and inverted mount. Please refer to "3 Robot dimensions and working envelope" for detail. \*5: Permitted height is not higher than 1,000m above sea level. If used in higher place, permitted temperature is affected by height. \*6: Liquid such as organic compound, acidity, alkalinity, chlorine or gasoline cutting fluid which deteriorates the seal material are not available to use. \*7\*8\*9: MC20-03 has Ethernet cable in arm, based on MC20-01. (Same as MC10L-03 based on MC10S-01, MC12S-03 based on MC12S-01).

### 3. Robot dimensions and working envelope

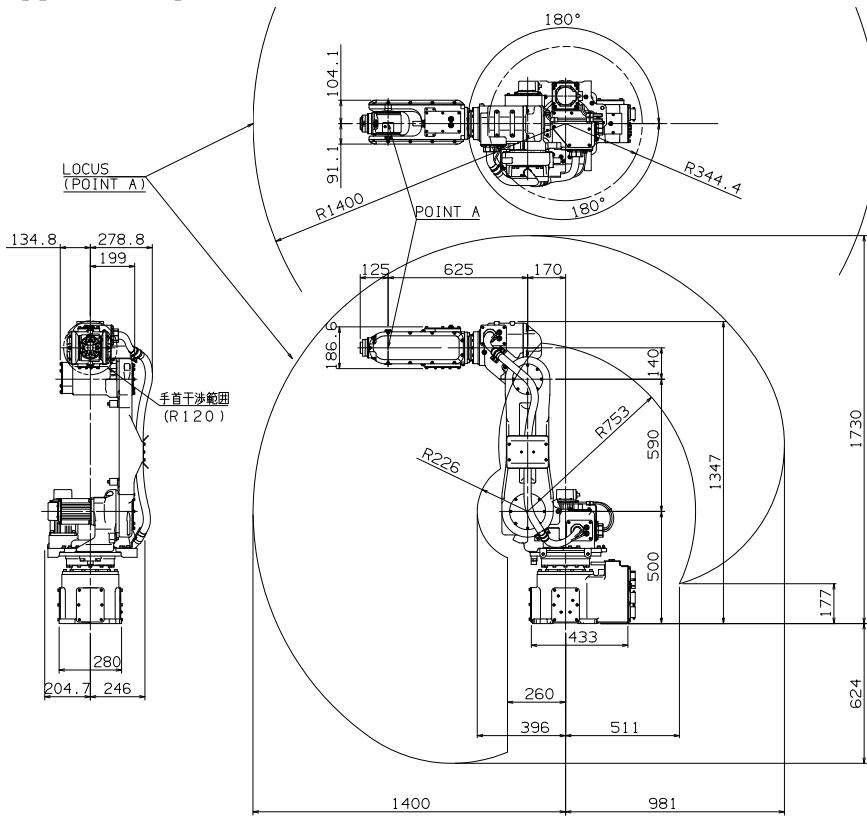
[MC20-01] [MC20-03]



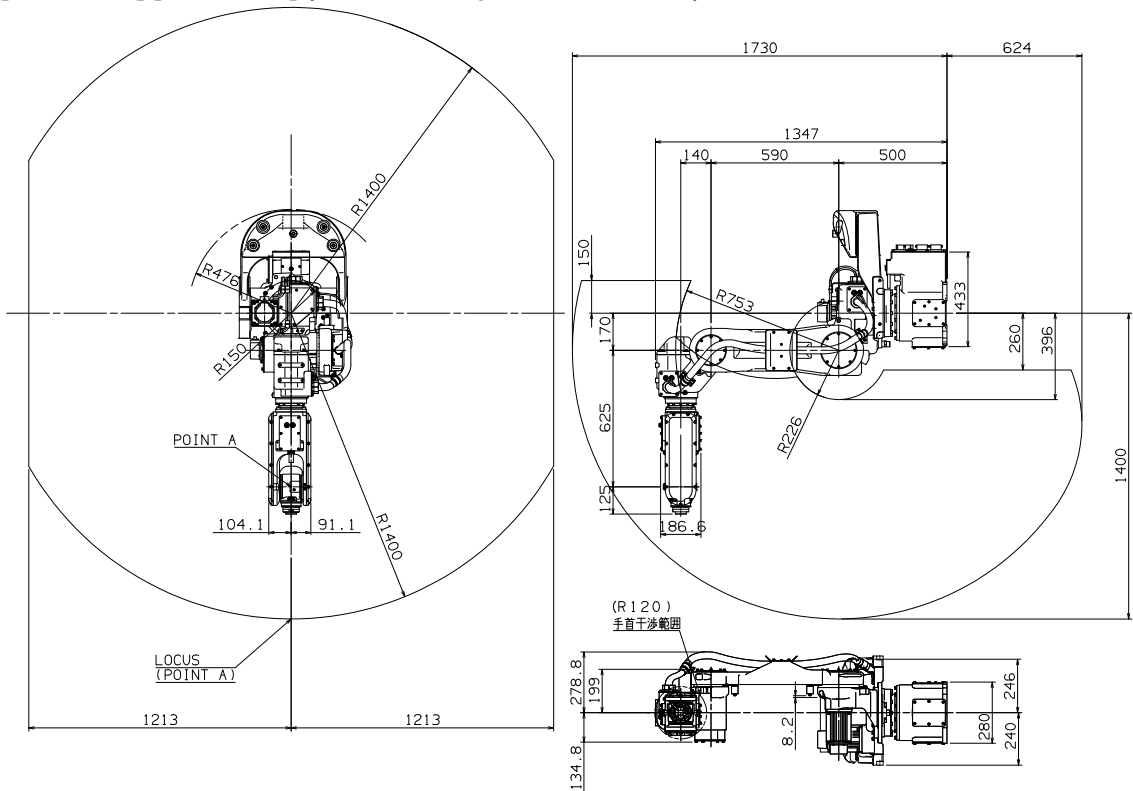
[MC10L-01] [MC10L-03]



[MC12S-01] [MC12S-03]




[MC12S-01] [MC12S-03] (wall mount option: OP-S7-010)



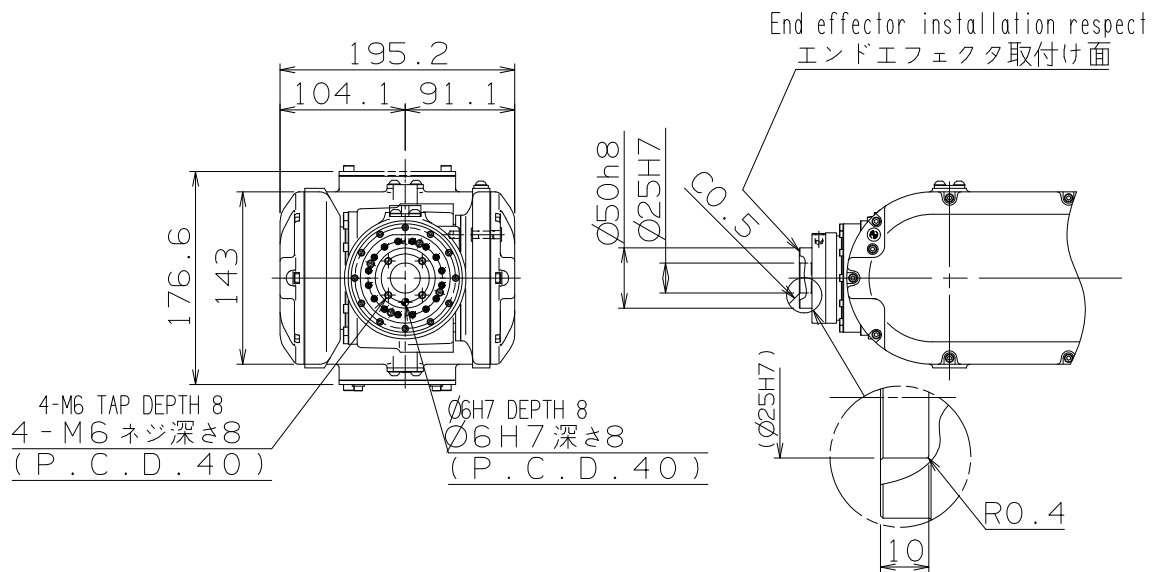
## 4. Detail of load mounting plate

### ■ Wrist

For the end effector fixing bolts, use the mounting P.C.D. shown in following figure.

 <b>CAUTION</b>	Don't screw in installation bolts (M6) over thread tap depth. Installation bolts over thread tap depth may damage the wrist.
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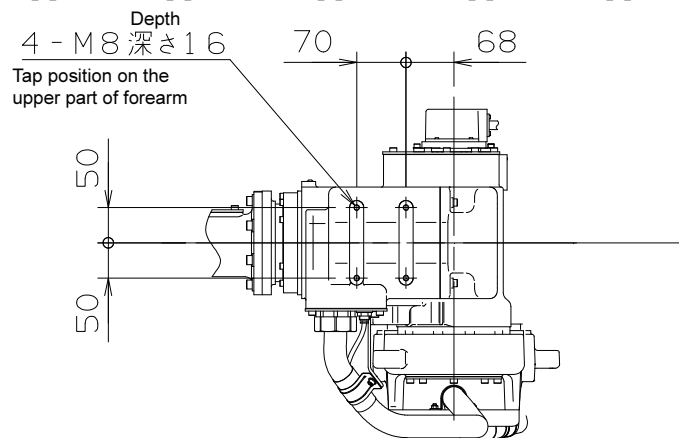
**[MC20-01] [MC20-03] [MC10L-01] [MC10L-03] [MC2S-01] [MC2S-03]**



### ■ Upper part of forearm

Ancillary equipment can be mounted to the upper part of robot forearm.

**[MC20-01] [MC20-03] [MC10L-01] [MC10L-03] [MC2S-01] [MC2S-03]**






## 5. Installation Procedure

The installation location and the installation procedure of the robot are critical factors to maintain robot functions. The ambient conditions of installation location not only have influence on the life of mechanical sections of the robot, but also get involved in safety issues. Consequently, strictly observe the environmental conditions shown below. Furthermore, utmost care should be exerted for the installation procedure and the foundation for the robot in order to maintain the robot performance. Strictly observe the installation procedure for the robot provided below.

### Installation

To install the robot, give it first priority to thoroughly consider safety of workers and take safety measures. The following describes precautions for this purpose.

### Safety measures against entry in the robot operating area

 <b>WARNING</b>	While the robot is in operation, workers are in danger of coming in contact with the robot. To avoid that, install a <b>guard fence</b> so as to keep the worker away from the robot. Not doing so will cause the workers or other persons to accidentally enter the operating area, thus resulting in accidents.
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#### ■ Installation location and ambient conditions

Conditions (temperature, humidity, height and vibration) are written in “2. Basic Specifications”. Further ambient conditions listed below must be observed.

- (1) Location with the drainage structure so that swivel base is not flooded, when the liquid such as water or cutting fluid is splashed on the robot body
- (2) Location with no flammable or corrosive fluid or gas.
- (3) Type D grounding (the grounding resistance is 100Ω or less) is necessary.

#### ■ Installation procedure

While robot moves, large reaction force is applied to the swiveling base from all directions. Consequently, the robot should be installed in such a manner that the foundation endures reaction force caused by accelerating or decelerating the speed to lock the robot, not to mention that it endures static loads.

Repair uneven spots, cracks, and others on the floor, and then install the robot by following to the table below. If thickness of floor concrete is less than needed level, an independent foundation should be constructed. Inspect the foundation prior to the robot installation, and then construct the foundation, if necessary.

Robot Model	All
Thickness of floor concrete	Not less than 150 mm
Installation parts *1	4 bolts of M16 X 45 (JIS: Strength class 12.9) 4 plain washers of not less than 4.5 mm in thickness and HRC35 in hardness
Tightening torque *2	287 ± 30 N·m
Allowable repeated tensile *3	Approximately 10,512 N



\*1 : Installation parts are not accessory of robot.

\*2 : Apply a coating of lubricating oil to the threaded parts of bolts, and then tighten bolts by using torque wrench to the specified tightening torque.

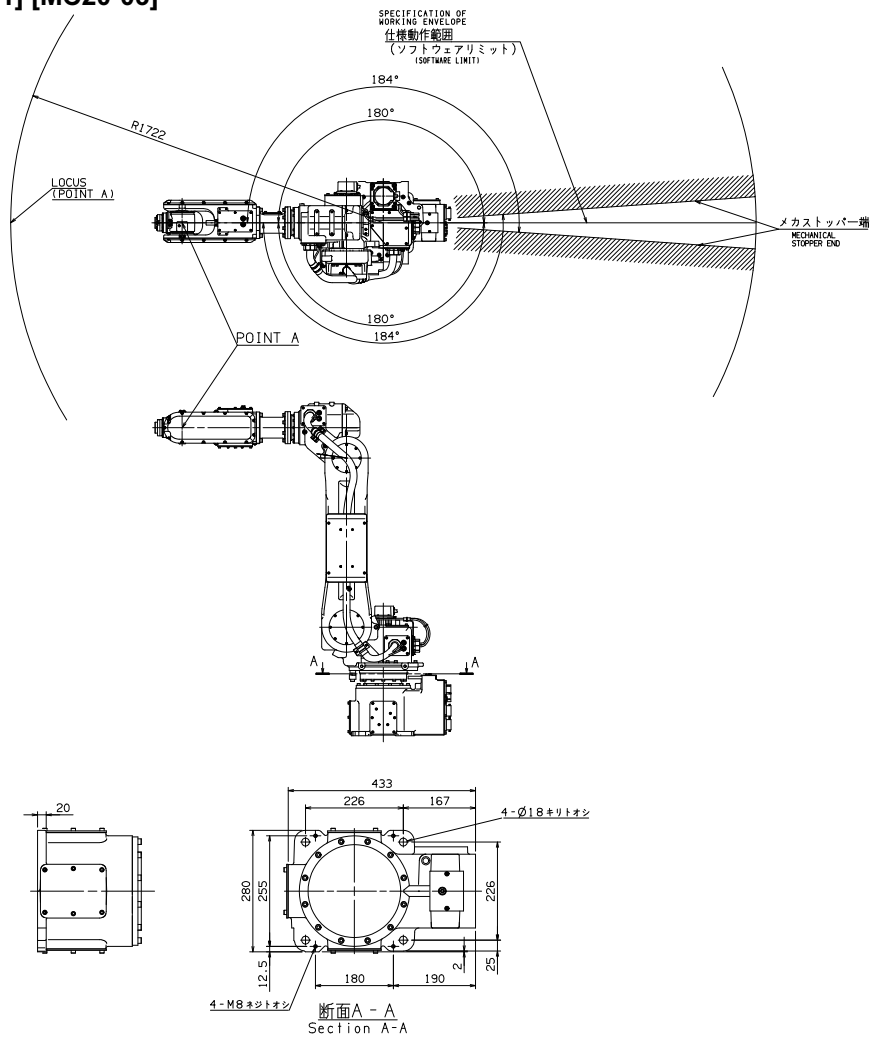
\*3 : This tensile is per installation bolt when robot is installed with all bolts written in table above.

■ Installation space

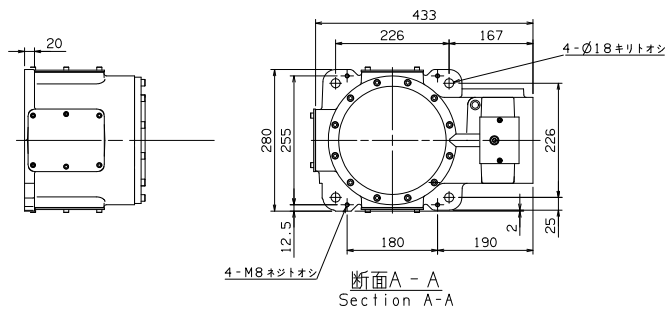
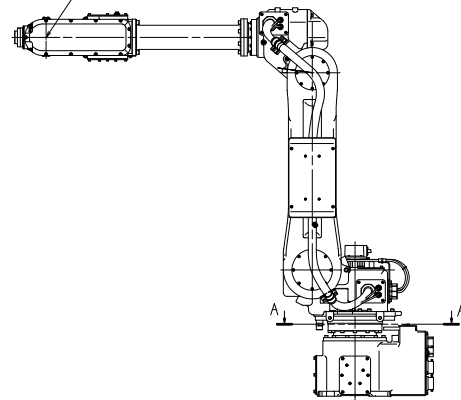
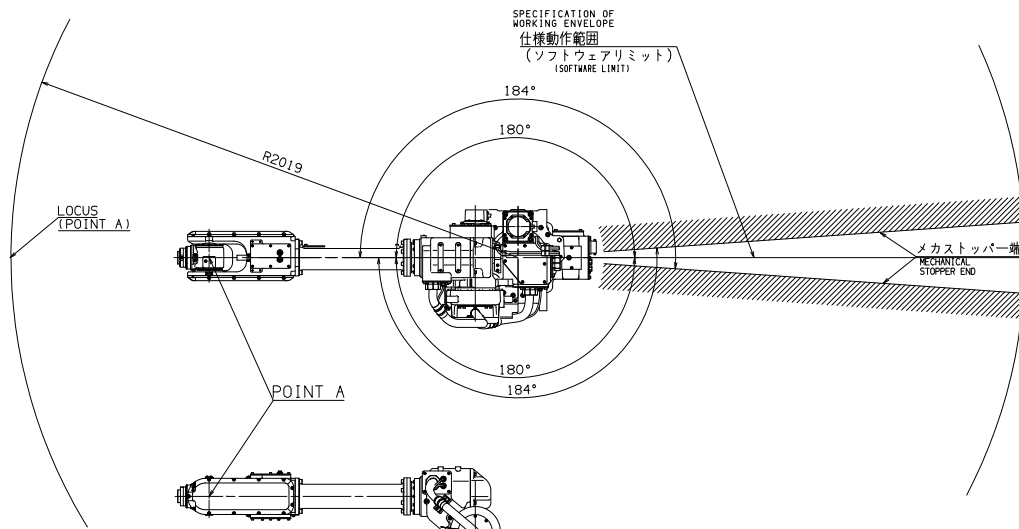
To install the robot, fix the swiveling base of the robot.

 WARNING	A mechanical stopper is mounted 4 degrees over the axis 1 working envelope (software limit). When installing a guard fence (safety fence), please make sure to consider the motion range, wrist posture, and the shape of the end effector.
 WARNING	To operate safely, range of the motion can be restricted in axis 1, axis 2 and axis 3 (Option). Because the option parts are always necessary to restrict the motion range, do not move the standard parts (mechanical stopper block etc.) alone.

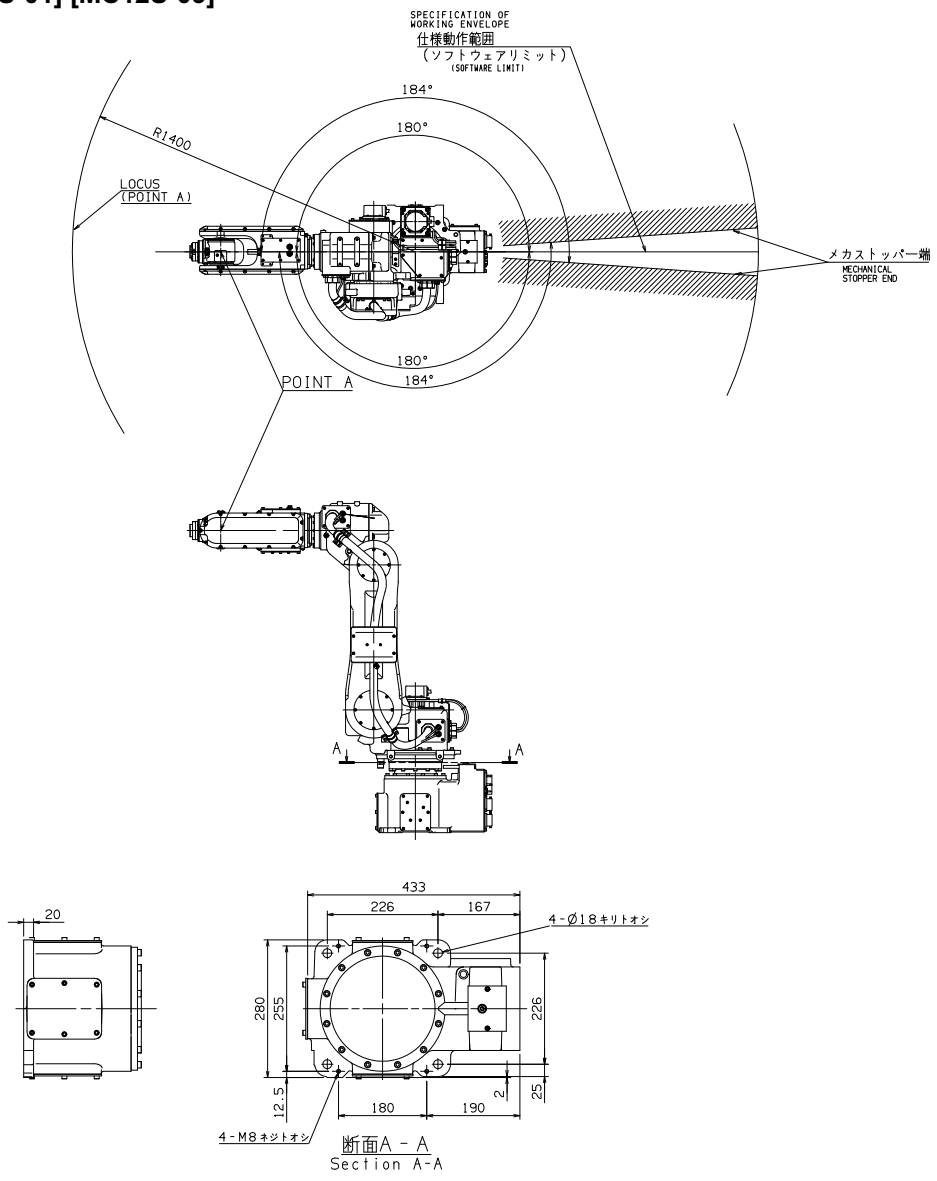
[MC20-01] [MC20-03]



[MC10L-01] [MC10L-03]



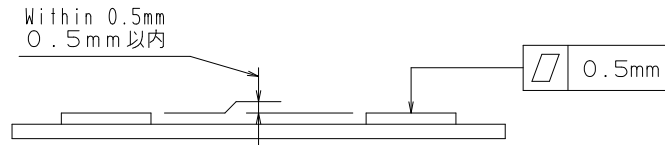
[MC12S-01] [MC12S-03]



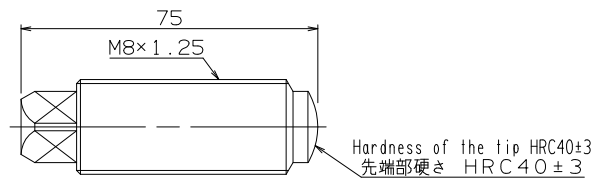
■ Accuracy of installation surface

When installing robot, strictly observe precautions listed below to cause no deformation in the swivel base.

- (1) Make the deviation from the flatness of the 4 plates on the robot installation surface fall within 0.5 mm.
- (2) Make the deviation in height between the 4 places of each base plate installation surface and the robot installation surface fall in the range of 0.5 mm ( $\pm 0.25$  mm).

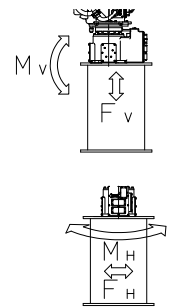


- (3) If the two precautions above cannot be observed, use jack bolts to bring the four places into even contact with the installation surface.




■ Maximum Robot Generative Force

Robot type	Maximum vertical generative force FV	Maximum horizontal generative force FH	Maximum Vertical generative moment MV	Maximum horizontal generative moment MH
All	8,300 N	6,000 N	9,400 N·m	8,100 N·m



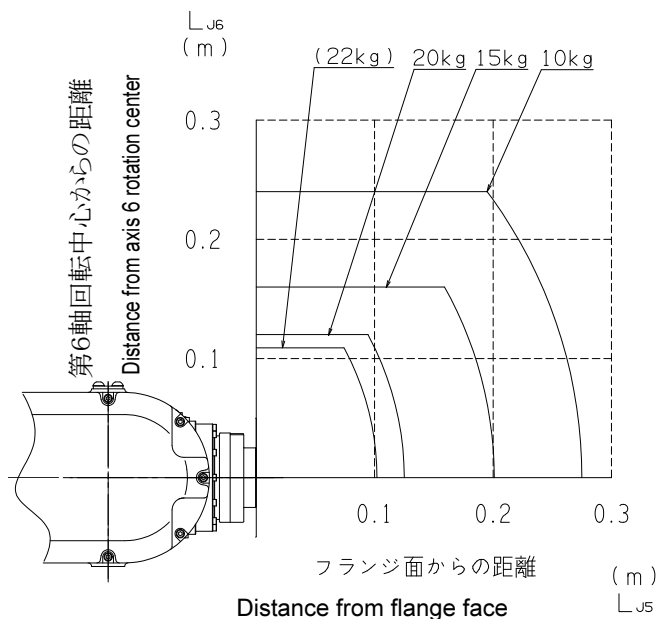
## 6. Allowable load

 <b>CAUTION</b>	<p>Load fixed on the tip of wrist is regulated by “allowable payload mass”, “allowable static load torque”, and “allowable moment of inertia”. Strictly keep the wrist load within each allowable value. If wrist load exceeds the allowable value, this robot is out of guarantee.</p> <p>Refer to the table of “2 Basic specifications” and following figures for the detail of each specification.</p>
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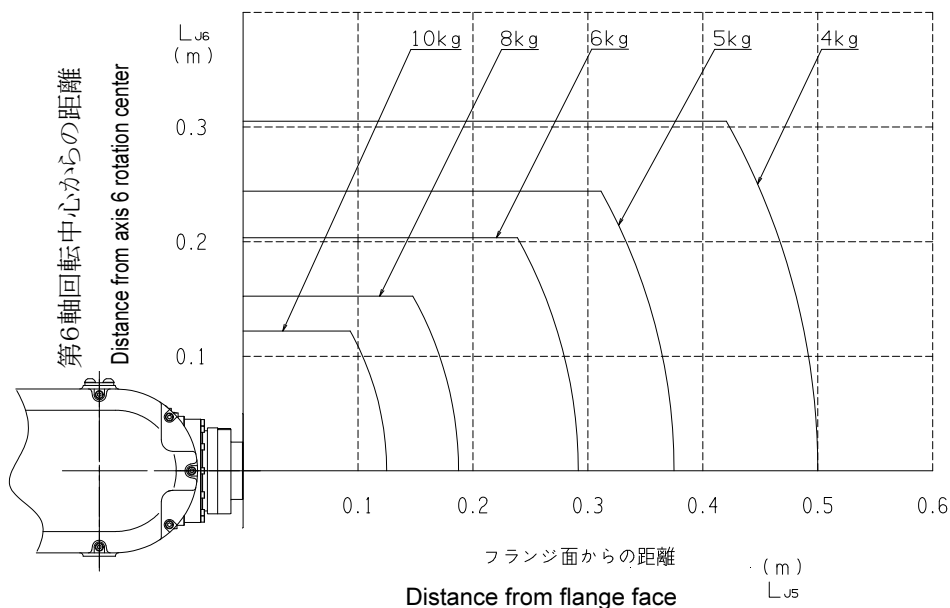
### ■ Torque map for the wrist load

C.O.G. of wrist load should exist inside the range shown below.

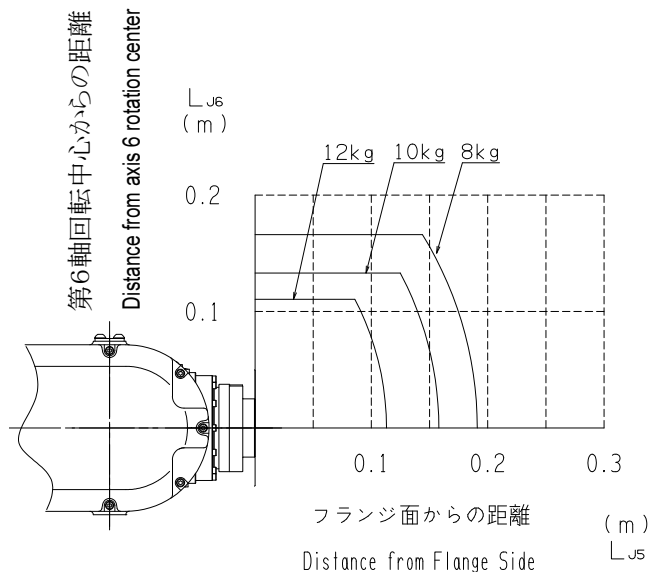
[MC20-01]  
[MC20-03]



[MC10L-01]  
[MC10L-03]



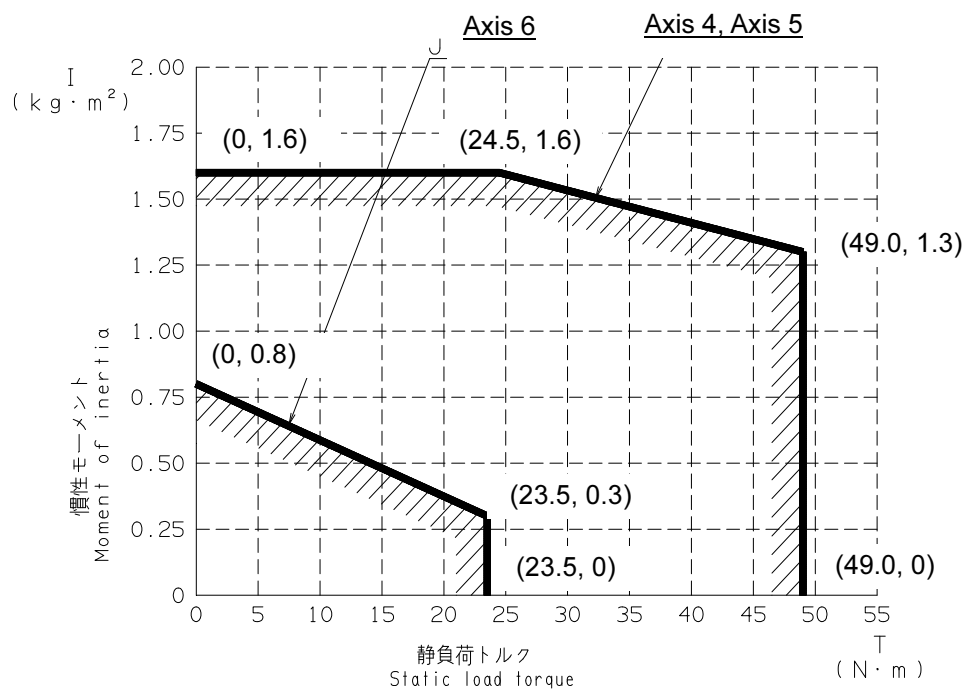
[MC12S-01]  
[MC12S-03]



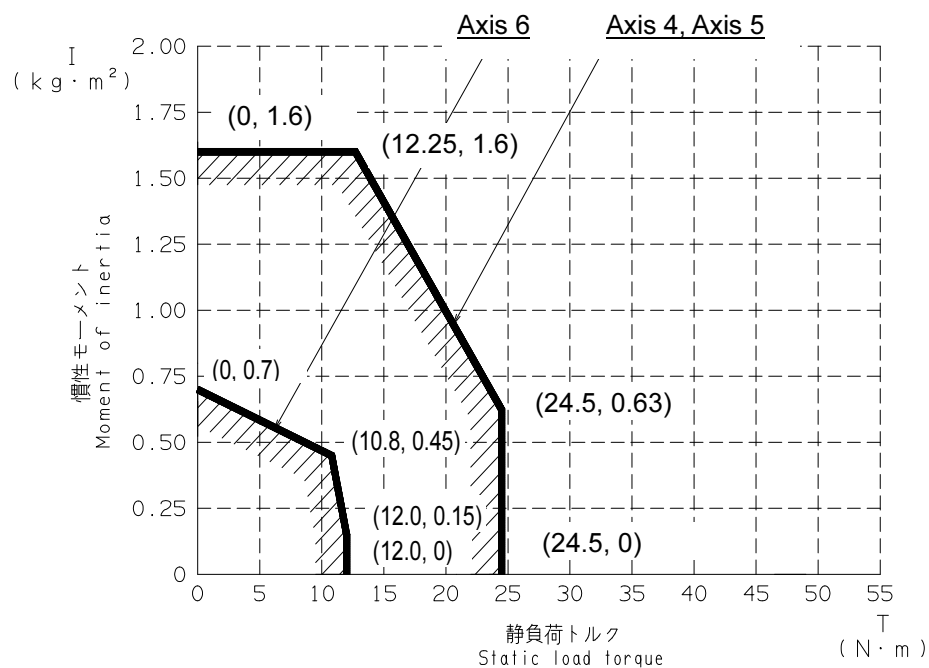
■ Inertia map for the wrist load

Static load torque and moment of inertia of wrist load should exist inside the range shown below.

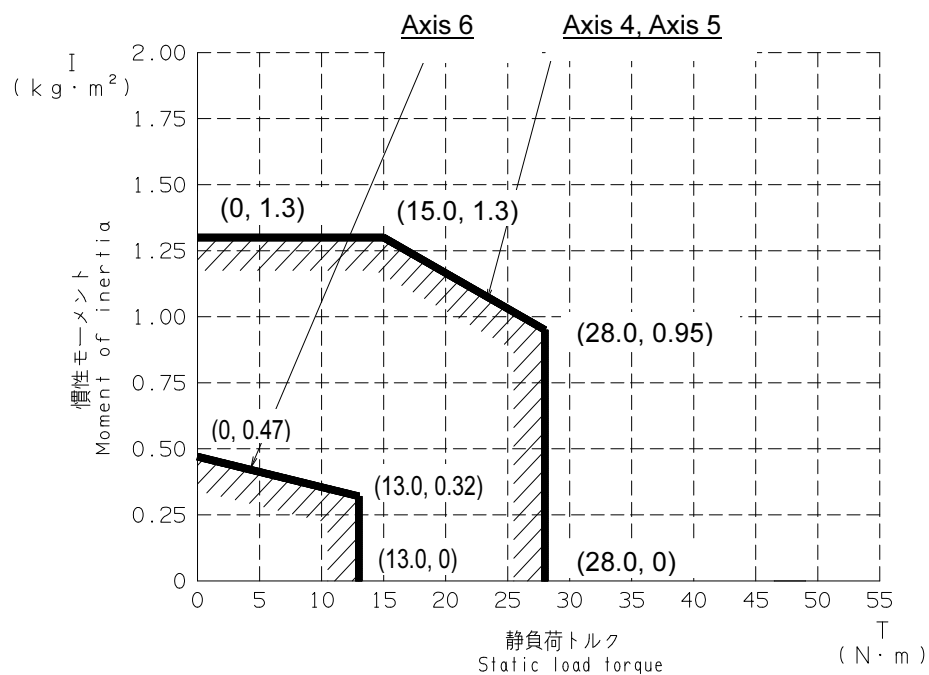
[MC20-01]  
[MC20-03]



[MC10L-01]  
[MC10L-03]

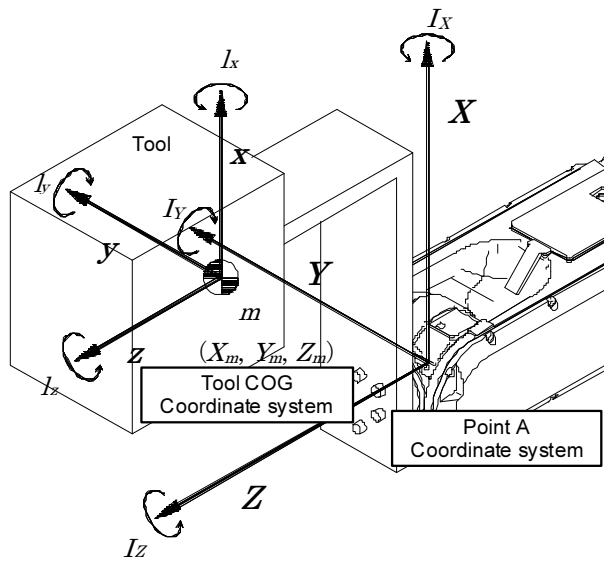


[MC12S-01]  
[MC12S-03]





■ How to calculate inertia moment of wrist axes



Point A coordinate system

Origin is Point A (intersection point of axis 6, 4 rotation center and axis 5 rotation center) and its X, Y and Z direction are defined as

- X: Perpendicular coordinate with Y, Z
- Y: Axis 5 rotation center when wrist is in reference position
- Z: Axis 6 and 4 rotation center when wrist is in reference position

Tool COG coordinate system

Origin is COG of bol, and parallel to pointA coordinate system

- x: Parallel to X
- y: Parallel to Y
- z: Parallel to Z

Inertia moment

- $I_x$ : Around X on point A coordinate system
- $I_y$ : Around Y on point A coordinate system
- $I_z$ : Around Z on point A coordinate system
- $I_x$ : Around x on tool COG coordinate system
- $I_y$ : Around y on tool COG coordinate system
- $I_z$ : Around z on tool COG coordinate system

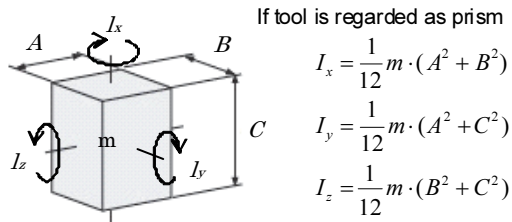
m: Tool mass

( $X_m, Y_m, Z_m$ ) : COG of tool on point A coordinate system

**1** Calculate inertia moment defined on tool COG coordinate system ( $xyz$ ).  
If tool is regarded as prism, it is calculated as right formula.

**2** Calculate inertia moment defined on point A coordinate system ( $XYZ$ ), then calculate inertia moment around robot wrist joint (axis 4, 5 and 6).  
  
This result must not be larger than "Allowable moment of inertia" written in robot specification sheet.

Inertia moment example on tool COG coordinate system



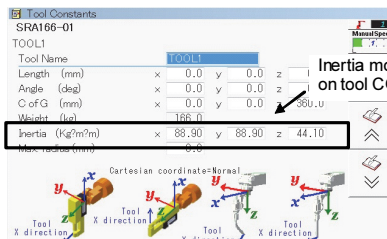
If tool is regarded as prism

$$I_x = \frac{1}{12} m \cdot (A^2 + B^2)$$

$$I_y = \frac{1}{12} m \cdot (A^2 + C^2)$$

$$I_z = \frac{1}{12} m \cdot (B^2 + C^2)$$

These values ( $I_x, I_y, I_z$ ) are registered to controller.



Inertia moment on tool COG coordinate system

This is different from "allowable moment of inertia" written in robot specification sheet.

Inertia moment on point A coordinate system ( $XYZ$ ) is

$$I_X = m \cdot (Y_m^2 + Z_m^2) + I_x$$

$$I_Y = m \cdot (X_m^2 + Z_m^2) + I_y$$

$$I_Z = m \cdot (X_m^2 + Y_m^2) + I_z$$

Axis 4 and 5 inertia moment is larger value of  $I_x$  and  $I_y$ , because this depends on axis 6 position.

Axis 6 inertia moment is  $I_z$  itself.

$$I_{J4} = I_{J5} = \max ( I_x , I_y )$$

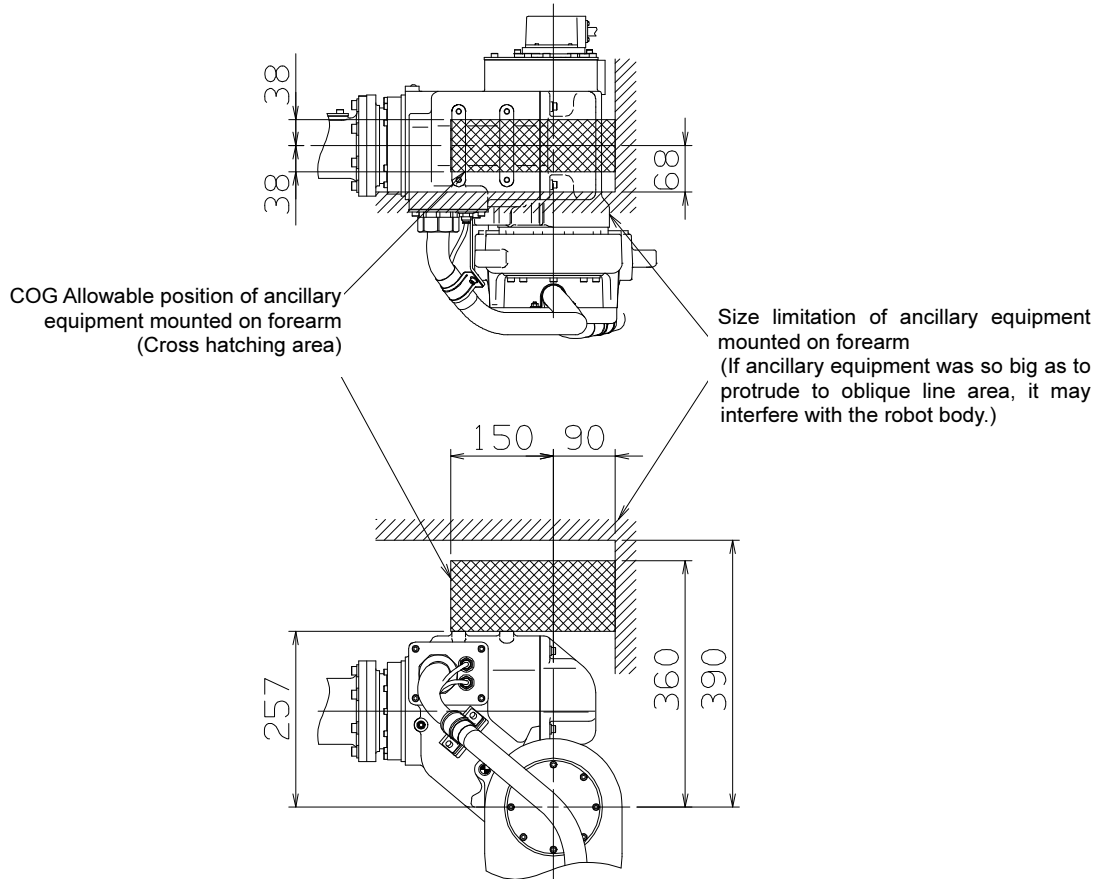
$$I_{J6} = I_z$$

■ **Load on the forearm**

Ancillary equipment can be mounted to the upper part of robot forearm.

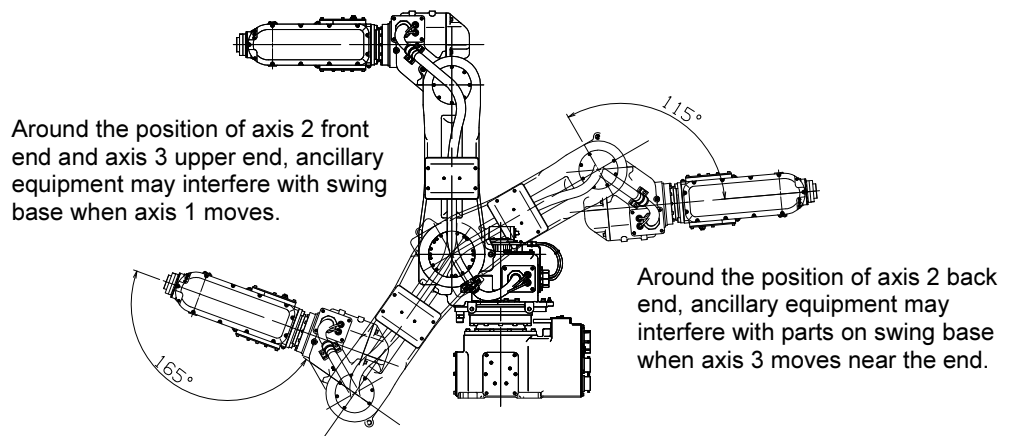
**[MC20-01] [MC20-03] [MC10L-01] [MC10L-03] [MC2S-01] [MC2S-03]** Maximum weight is 5kg

COG position and size limitation of ancillary equipment



**[MC12S-01] [MC12S-03]**

In case of MC12S-01/03, maximum working envelope near the front and the back end area of axis 2 can not be secured because of ancillary equipment mounted on forearm, regardless of its size, even when its size was smaller than above limitation.



## 7. Option specifications

○: Possible to correspond / -: Impossible to correspond

No	Item	Specifications	Parts No.	Robot type					
				MC20-01	MC20-03	MC10L-01	MC10L-03	MC12S-01	MC12S-03
1	Parts for installation *4	Chemical anchor specification (Installing plate with 4 base plates + chemical anchor bolts)	OP-F1-019	○	○	○	○	○	○
		Hammer drive anchor specification (Installing plate with 4 base plates + ore anchor bolts)	OP-F2-015	○	○	○	○	○	○
		Robot installation bolts and washers	OPJ-F1-0051	○	○	○	○	○	○
		Chemical anchor bolt set	OPJ-F1-0021	○	○	○	○	○	○
		Hammer drive anchor bolt set	OPJ-F2-0006	○	○	○	○	○	○
2	Axis 1 adjustable stopper *4	Restriction of axis 1 operation edge (± 3.14 ± 0.52 rad, every 0.17 rad)	OP-S5-015	○	○	○	○	○	○
3	Axis 2 adjustable stopper *4	Restriction of axis 2 operation edge (+ 2.62 ~ + 1.83, - 0.39 ~ - 1.04 rad, every 0.39 rad)	OP-A5-019	○	○	○	○	○	○
4	Axis 3 adjustable stopper *4	Restriction of axis 3 operation edge (+ 3.14 ~ + 2.35, - 1.43 ~ + 0.64 rad, every 0.39 rad)	OP-A6-016	○	○	○	○	○	○
5	Solenoid valve plate *1	For storage in wrist of solenoid valve *1	OP-H1-018	○	○	○	○	○	○
6	Solenoid valve inside arm *2	(table below)		○	-	○	-	○	-
7	Zeroing pin & Zeroing block *4	Zeroing pin & Zeroing block	OP-T2-047	○	○	○	○	○	○
8	Hanging jig	Jig for installation of inverted mount robot	OP-S7-007	○	○	○	○	○	○
9	Wall mount option	Necessary for wall mount specification	OP-S7-010	-	-	-	-	○	○
10	Hanging jig for wall mount	Jig for installation of wall mount robot (This is necessary when "wall mount option" is selected)	OP-S7-011	-	-	-	-	○	○
11	Assembly jig	Jig for assembling option parts	OP-TY-004	○	○	○	○	○	○
12	Name seal for inverted mount	Name seal for MC20-01/03 inverted mount	OP-N2-019	○	○	-	-	-	-
		Name seal for MC10L-01/03 inverted mount	OP-N2-022	-	-	○	○	-	-
		Name seal for MC12S-01/03 inverted mount	OP-N2-027	-	-	-	-	○	○
13	Encoder ID writing cable		MR20-OP03-A	○	○	○	○	○	○
14	Bypass cable unit *4		BCUNIT20-30	○	○	○	○	○	○
15	Water proof coolant Paint		(standard)	○	○	○	○	○	○
16	Axis 2 cover	Cover on axis 2 honeycombed structure	OP-C1-013	○	○	-	-	-	-

\*1; This is the unit of storage plate and cover. Solenoid valve and wires are not included.

Applicable solenoid valve size is two SY3000 (SMC) valves or one SY5000 (SMC) valve When solenoid valve is installed inside, exhaust air must be exhausted to the outside of the robot (not inside).

"Solenoid valve plate" and "Solenoid valve inside arm" can not be used at the same time.

\*2; Detail of "Solenoid valve inside arm" for [MC20-01] [MC10L-01] [MC12S-01]

	Specifications	Parts No.
1	2 Double solenoids + Application cable	CABLEMR-DD-A + OPJ-H1-0008
2	2 Double solenoids	CABLEMR-DD + OPJ-H1-0008
3	1 Double solenoid + Application cable	CABLEMR-D-A + OPJ-H1-0010
4	1 Double solenoid	CABLEMR-D + OPJ-H1-0010
5	2 Single solenoids + Application cable	CABLEMR-SS-A + OPJ-H1-0009
6	2 Single solenoids	CABLEMR-SS + OPJ-H1-0009
7	1 Single solenoid + Application cable	CABLEMR-S-A + OPJ-H1-0011
8	1 Single solenoid	CABLEMR-S + OPJ-H1-0011
9	1 Double solenoid + 1 Single solenoid + Application cable	CABLEMR-DS-A + OPJ-H1-0012
10	1 Double solenoid + 1 Single solenoid	CABLEMR-DS + OPJ-H1-0012

Single solenoid valve type SYJ3130-5GS [SMC]

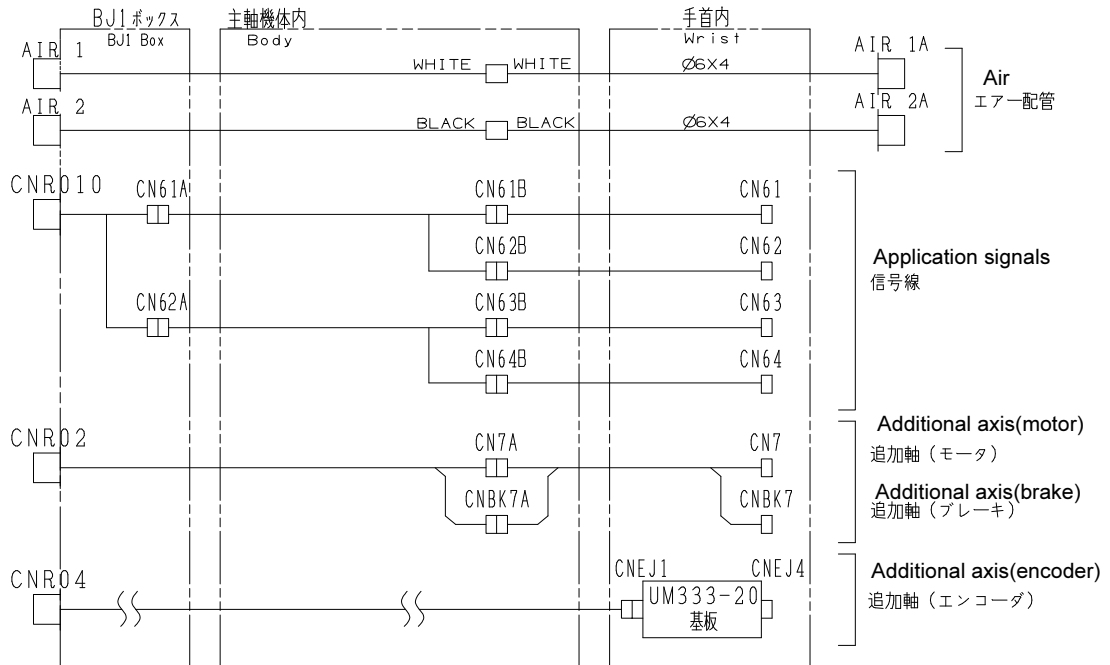
Double solenoid valve type SYJ3230-5GS [SMC]

\*3; Transporting jig is accessory as standard. If another transporting jig is needed to transport the robot, please order KP-ZJ-005 (although not written in above list) to Nachi service.

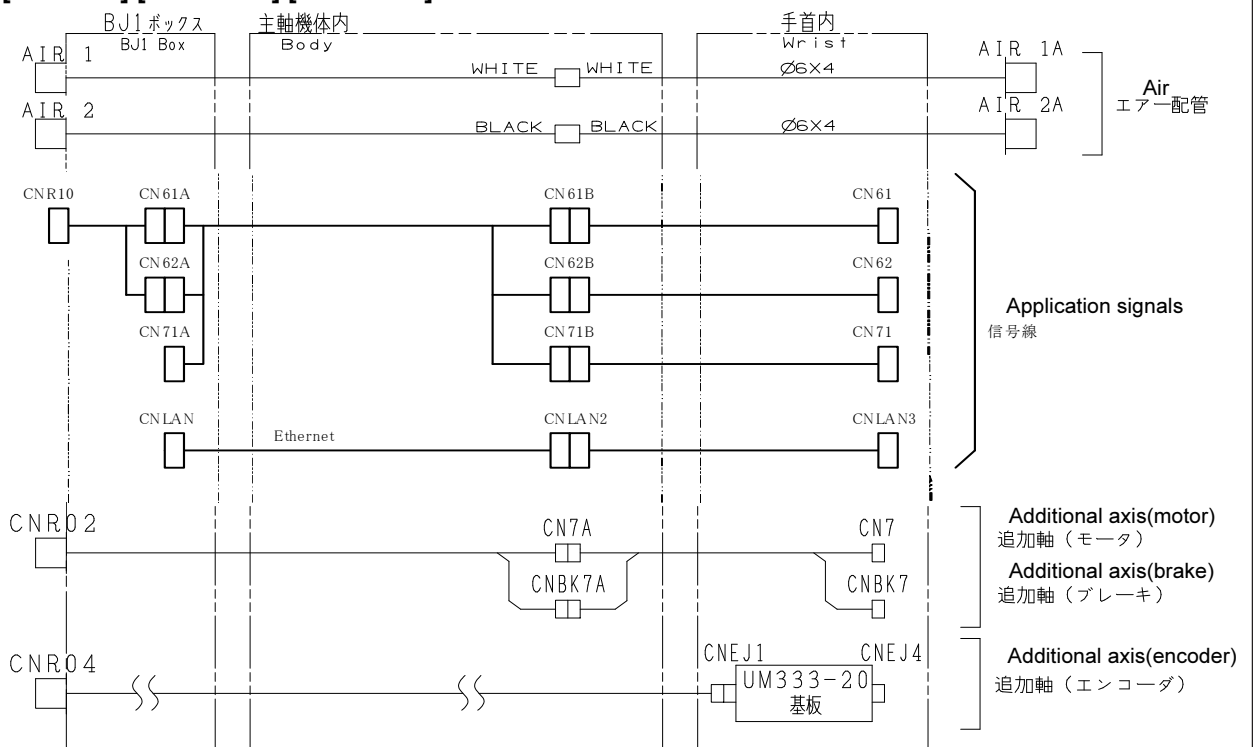
\*4; These parts are packed separately from the robot. (Not attached on the robot)

## 8. Application wiring and tubing diagram (standard)

### ■ Wiring and tubing system diagram [MC20-01] [MC10L-01] [MC12S-01]



### [MC20-03] [MC10L-03] [MC12S-03]



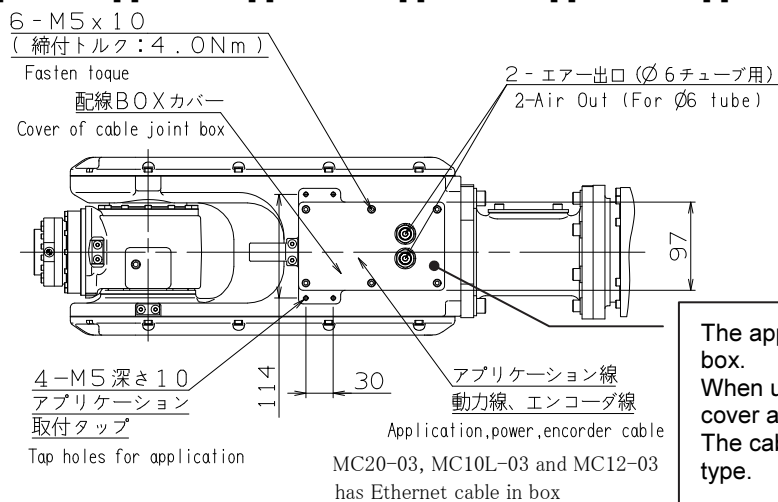
For additional axis encoder, it is necessary to use a bus-connection type encoder that is designated by NACHI. For more details, please contact our technical department.

■ Detailed diagram of the base frame

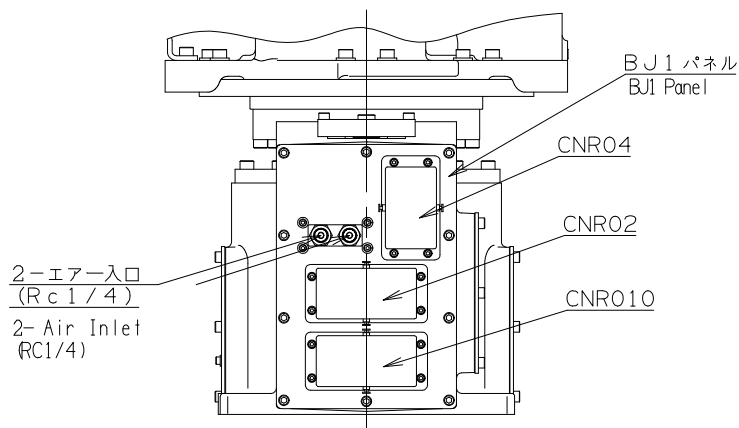
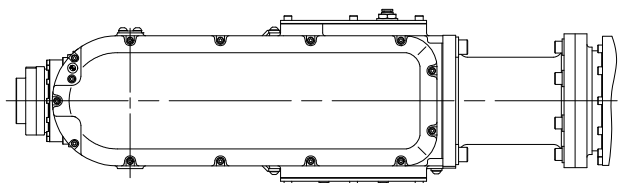


- When not using air, attach plugs to the air in/out holes so that water or oil can not get into the robot arm. (The plugs are attached when the robot is shipped)
- When attaching air valves or cable brackets etc., please use "Tap holes for application (4-M5)" shown in the figure. Tightening those things with the cover fixing bolts or making holes on the box cover itself may cause water leakage or oil leakage into the arm and the parts of the robot may be damaged.

[MC20-01] [MC20-03] [MC10L-01] [MC10L-03] [MC12S-01] [MC12S-03]

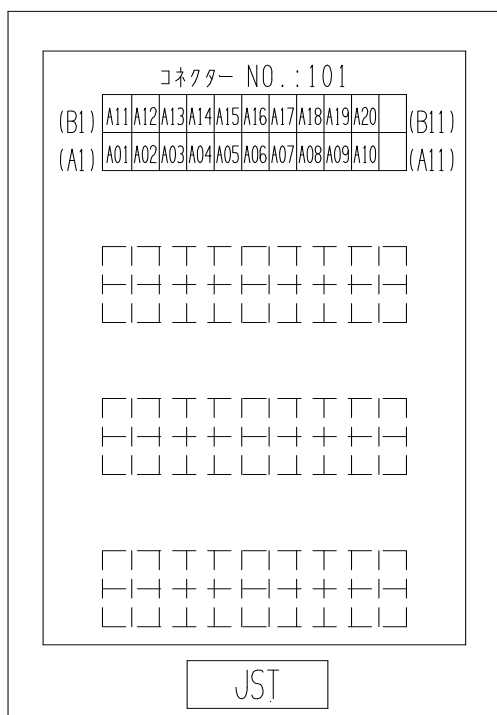


The application signal lines are in the box.  
When using those, make a hole on the cover and attach a cable clamp.  
The cable clamp must be waterproof type.



■ Detailed diagram of the connectors

BJ1 side (connector) [MC20-01] [MC20-03] [MC10L-01] [MC10L-03] [MC12S-01] [MC12S-03]



**Connector for application cable**

Wire-side shell: JFM-WSA-4-A (JST)  
or JFM-WSA-4-C (JST)

Guide plate A kit: FM-GPAK-4 (JST)

Receptacle housing: JFM2FDN-22V-K (JST)

Receptacle contact:

- (a) SJ2F-01GF-P1.0 (JST) (0.20 ~ 0.50 mm<sup>2</sup>)
- (b) SJ2F-21GF-P1.0 (JST) (0.30 ~ 0.75 mm<sup>2</sup>)

Manual crimp tool:

- for (a), YRS-8861
- for (b), YRF-1120

Cable diameter suitable for wire-side shell:

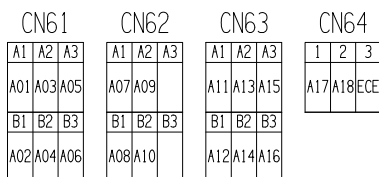
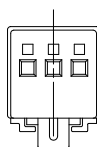
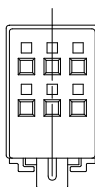
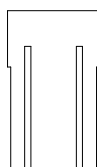
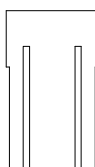
- JFM-WSA-4-A (JST)  $\phi 26.2 \sim \phi 28.0$
- JFM-WSA-4-C (JST)  $\phi 15.5 \sim \phi 16.5$

(Pin location shows the view from connecting side.)

BJ3 side (junction connector) [MC20-01] [MC10L-01] [MC12S-01]

CN61, CN62, CN63

CN64



**Connector form (CN61, CN62 and CN63)**

Housing: J21DF-06V-KX (JST)

**Partner connector**

Housing: J21DPM-06V-KX (JST)

Contact:

- (a) SJ2M-01GF-M1.0N (0.20 ~ 0.50 mm<sup>2</sup>)
- (b) SJ2M-21GF-M1.0N (0.30 ~ 0.75 mm<sup>2</sup>)
- (c) SJ2M-01GF-M1.0S (0.20 ~ 0.50 mm<sup>2</sup>)

Manual crimp tool: (one of a, b or c)

- for (a)(c), YRS-8861
- for (b), YRF-1120

**Connector form (CN64)**

Housing: J21SF-03V-KX (JST)

**Partner connector**

Housing: J21SPM-03V-KX (JST)

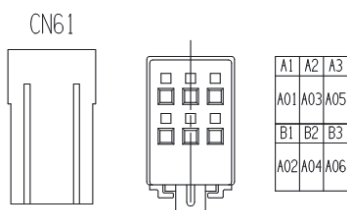
- (a) SJ2M-01GF-M1.0N (0.20 ~ 0.50 mm<sup>2</sup>)
- (b) SJ2M-21GF-M1.0N (0.30 ~ 0.75 mm<sup>2</sup>)
- (c) SJ2M-01GF-M1.0S (0.20 ~ 0.50 mm<sup>2</sup>)

Manual crimp tool: (one of a, b or c)

- for (a)(c), YRS-8861
- for (b), YRF-1120

(Pin location shows the view from connecting side.)

BJ3-side (Relay connectors) [MC20-03] [MC10L-03] [MC12S-03]



Connector type (CN61)

Housing J21DF-06V-KX (JST)

User-side connector

Housing J21DPM-06V-KX (JST)

Contact

a: SJ2M-01GF-M1.0N (0.20~0.50 mm<sup>2</sup>)

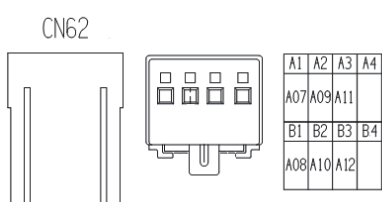
b: SJ2M-21GF-M1.0N (0.30~0.75 mm<sup>2</sup>)

c: SJ2M-01GF-M1.0S (0.20~0.50 mm<sup>2</sup>)

Manual crimp tool (use one among a, b, c)

a, c : YRS-8861

b : YRF-1120



Connector type (CN62)

Housing J21DF-08V-KX (JST)

User-side connector

Housing J21DPM-08V-KX (JST)

Contact

a: SJ2M-01GF-M1.0N (0.20~0.50 mm<sup>2</sup>)

b: SJ2M-21GF-M1.0N (0.30~0.75 mm<sup>2</sup>)

c: SJ2M-01GF-M1.0S (0.20~0.50 mm<sup>2</sup>)

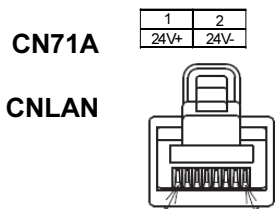
Manual crimp tool (use one among a, b, c)

a, c : YRS-8861

b : YRF-1120

(Pin location shows the view from connecting side.)

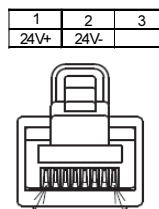
CN71A,71,LAN,LAN3 connectors BJ1·BJ3-side [MC20-03] [MC10L-03] [MC12S-03]



CN71A

CNLAN

Connector in wiring box BJ1



CN71

CNLAN3

Connector in wiring box BJ3

		CN71A	CN71
Connector	Housing	VLR-02V	J21SF-03V-KX
User-side connector	Housing	VLP-02V	J21SPM-03V-KX
	Contact	SVF-42T-P2.0 (0.3~1.25 mm <sup>2</sup> )	SJ2F-01GF-P1.0
	Retainer	VLS-02V	-
	Crimp tool	YC-590 (SV*-61T-P2.0) YC-592 (SV*-42T-P2.0)	YRS-8861

		CNLAN	CNLAN3
Connector	RJ45 plug connector	5-1479184-3	5-1479184-3
User-side connector	Hood	(any) RJ45 type connector	(any) RJ45 type connector

(Pin location shows the view from connecting side.)




Adequate contact and manual crimp tool should be used for each cable.

User-side connectors need to be prepared by customer.

## 9. Transport procedure

### Safety measures against transport

The following describes precautions for transporting the robot. Fully understand the precautions for safe transport work.

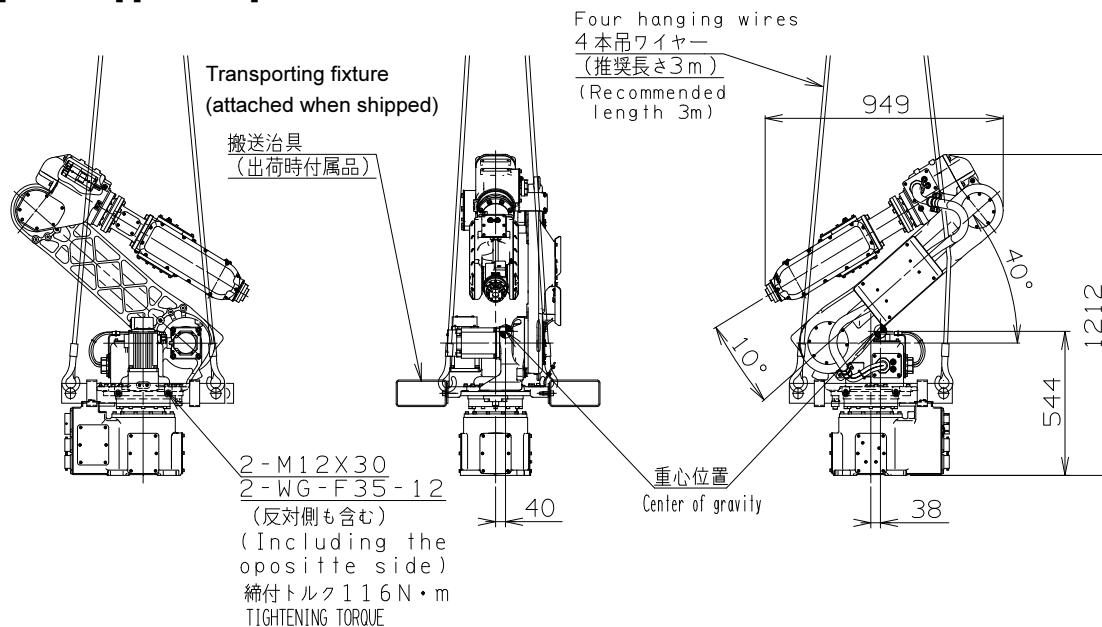
 <b>WARNING</b>	The robot must be transported by personnel who have licenses required for slinging work, crane operation, forklift truck operation, and others.
 <b>WARNING</b>	To lift the robot or the controller, follow the procedures specified in the Maintenance Manual. Following any procedures other than those specified will cause the robot to topple over or drop during transport, thus resulting in accidents.
 <b>CAUTION</b>	During transport or installation work of the robot, pay utmost care not to cause damage to wirings. Furthermore, after installing the robot, take protective measures such as using protective guards so that the wirings will not be damaged by workers or other persons, or forklift trucks or else.

To transport the robot, make it a rule to use a crane.

First, put the robot into the configuration shown below and mount the two carrier brackets dedicated to the transport of the robot to both sides of the robot frame. Then, lift the robot using four hanging wires. Fix these dedicated brackets with the two M12 X 30 bolts. The tightening torque is 116 N·m. Recommended length of the hanging wires is 3 m.

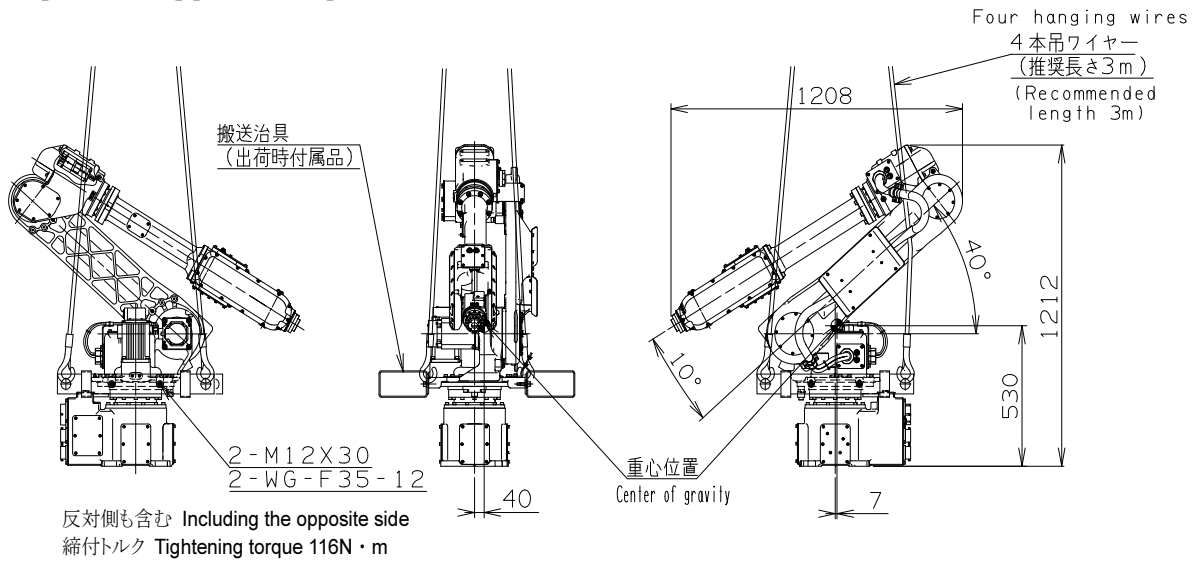
In case that wall mount option is selected, wall mount hanging jig (OP-S7-011) has to be used instead of the hanging jig (accessory when shipped) with using two M12x85 bolts and two M12x120 bolts.

### [MC20-01] [MC20-03]

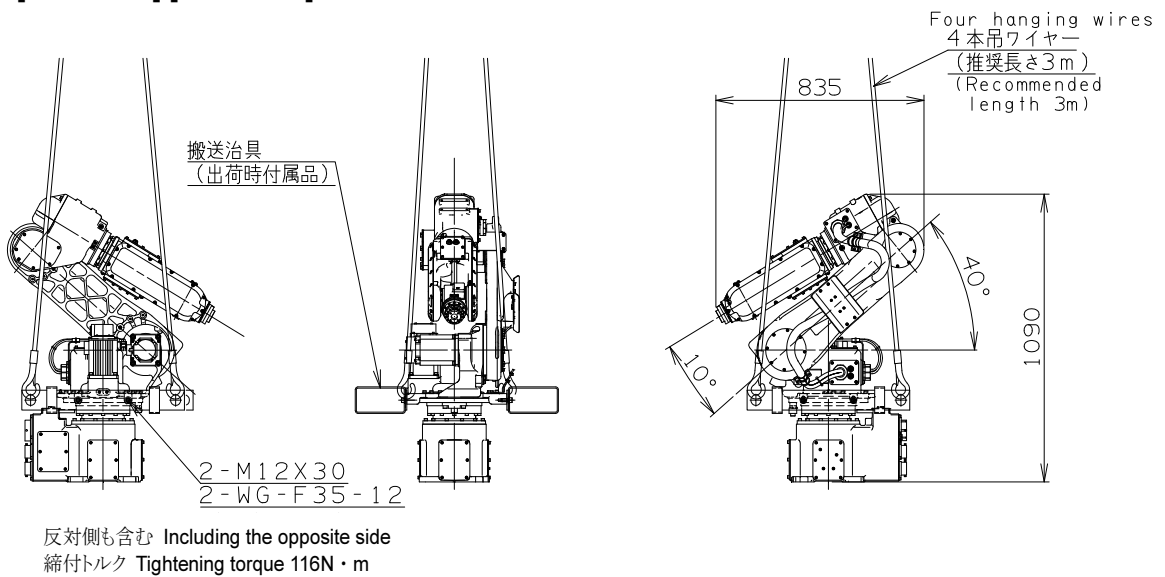




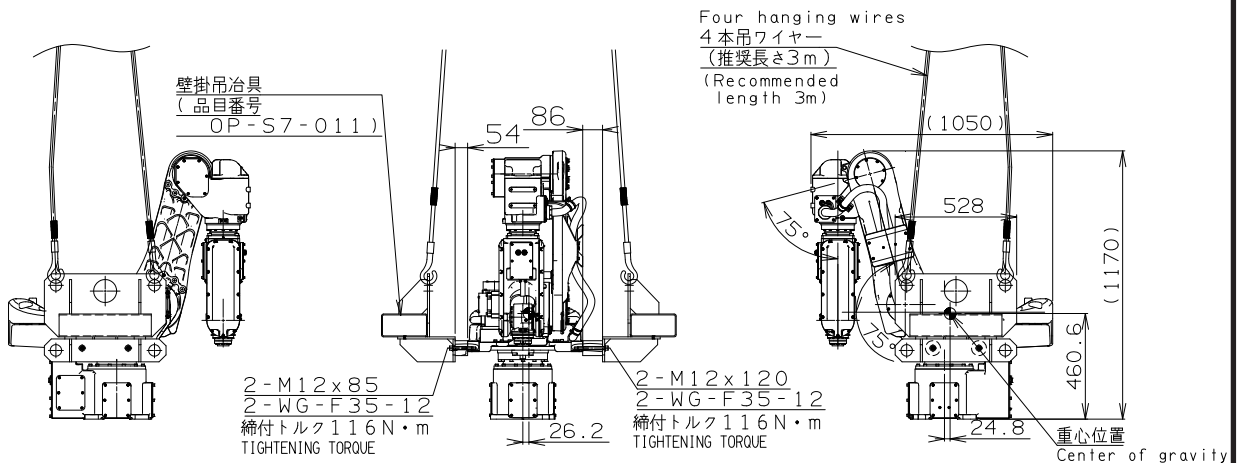
**[MC10L-01] [MC10L-03]**



**[MC12S-01] [MC12S-03]**



**[MC12S-01] [MC12S-03] (wall mount option: OP-S7-010)**



## 10. Installation (specification which contains a robot)

### 1. Delivery condition

Because the expense is different, which form to choose be sufficiently examined.

Style	Condition	Details
1	Delivery on the truck	Robot is delivered on the truck near the entrance of customer's plant.
2	Delivery after installation and test-run	Robot is installed and test-run done.
3	Delivery after installation and test-run with work piece	After style 2, teaching with work piece is done.

### 2. Operation and maintenance education

The special spot operation guide and the special spot preservation guide are the outside of the estimation. Also, there is schooling system in the Toyama factory, too.

Consult with each NACHI-FUJIKOSHI office for the details.

### 3. The type D grounding (the grounding resistance is 100Ω or less) is necessary.

## 11. Consuming power (Robot + Controller)

1.7 kVA (peak)

## 12. Paint color

Standard color	Controller cabinet	Munsell 10GY9/1
	Robot body	Munsell 10GY9/1

Water proof coolant paint option is useful for the circumstance such as that coolant splashes on robot body. Please refer to "7 Option specifications" for the type of this option.

## 13. Warranty

Elapse of 1 year after delivery.

The specifications and appearances in this document might change without a previous notice for the improvement.



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