

P-50iB/10L



Max. load capacity
at wrist: 10 kg



Max. reach:
1800 mm

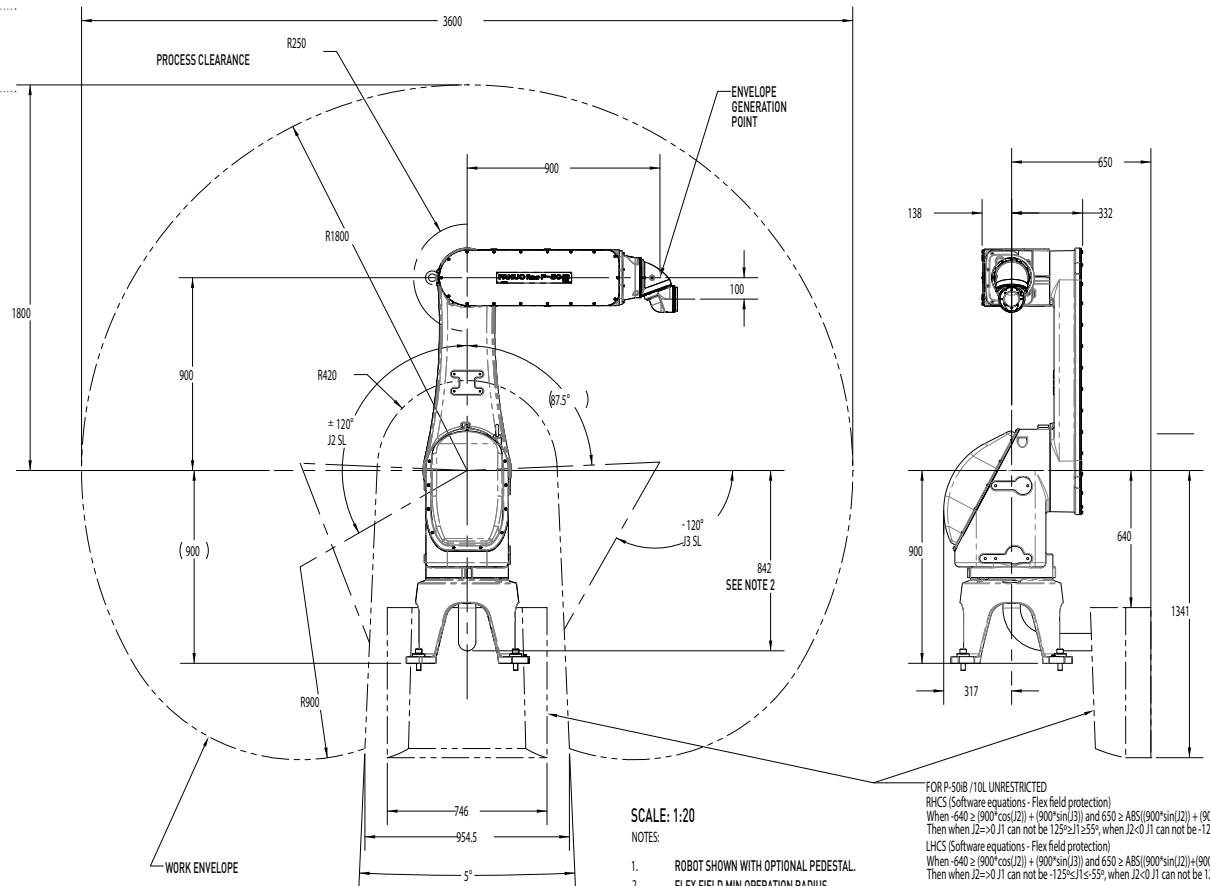
FANUC

Robot			Max. load capacity at wrist (kg)	Reach (mm)	Controlled axes	Repeatability (mm)	Mechanical weight (kg)	Motion range [°]						Maximum speed [°/s]						Allowable load moment at wrist (Nm) Allowable load inertia at wrist (kg m ²)			Input power source (VAC) (50-60 HZ)
Series	Version	Type						J1	J2	J3	J4	J5	J6	J1	J2	J3	J4	J5	J6	J4	J5	J6	
P-50	iB	10L	10	1800	6	± 0.05	110	320	240	404	1080	1080	1080	140	140	160	375	430	545	43.45 1.954	36.86 1.413	7.67 .233	200-300 +10/-15%

P-50iB/10L Paint robot



P-50iB/10L



SCALE: 1:20
NOTES:

- ROBOT SHOWN WITH OPTIONAL PEDESTAL.
- FLEX FIELD MIN OPERATION RADIUS MUST NOT BE VIOLATED.

FOR P-50iB/10L UNRESTRICTED
RHCS (Software equations - Flex field protection)
When $-640 \geq (900 \cdot \cos(J2)) + (900 \cdot \sin(J3))$ and $650 \geq ABS(900 \cdot \sin(J2)) + (900 \cdot \cos(J3))$
Then when $J2 > 0$ J1 can not be $125^\circ \leq J1 \leq 55^\circ$; when $J2 < 0$ J1 can not be $-125^\circ \leq J1 \leq 55^\circ$
LHCS (Software equations - Flex field protection)
When $-640 \geq (900 \cdot \cos(J2)) + (900 \cdot \sin(J3))$ and $650 \geq ABS(900 \cdot \sin(J2)) + (900 \cdot \cos(J3))$
Then when $J2 > 0$ J1 can not be $-125^\circ \leq J1 \leq 55^\circ$; when $J2 < 0$ J1 can not be $125^\circ \leq J1 \leq 55^\circ$

LH INNER ARM OFFSET
CONFIGURATION SHOWN