

P-50iB



Max. load capacity at wrist: 10 kg



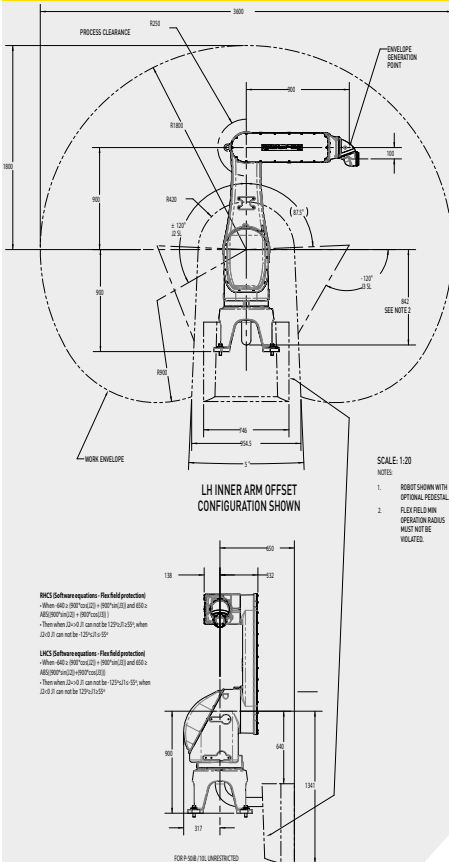
Max. reach: 1800 mm

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Design

The P-50iB is a highly flexible and advanced six-axis paint robot for a wide range of painting applications.

Working range P-50iB/10L

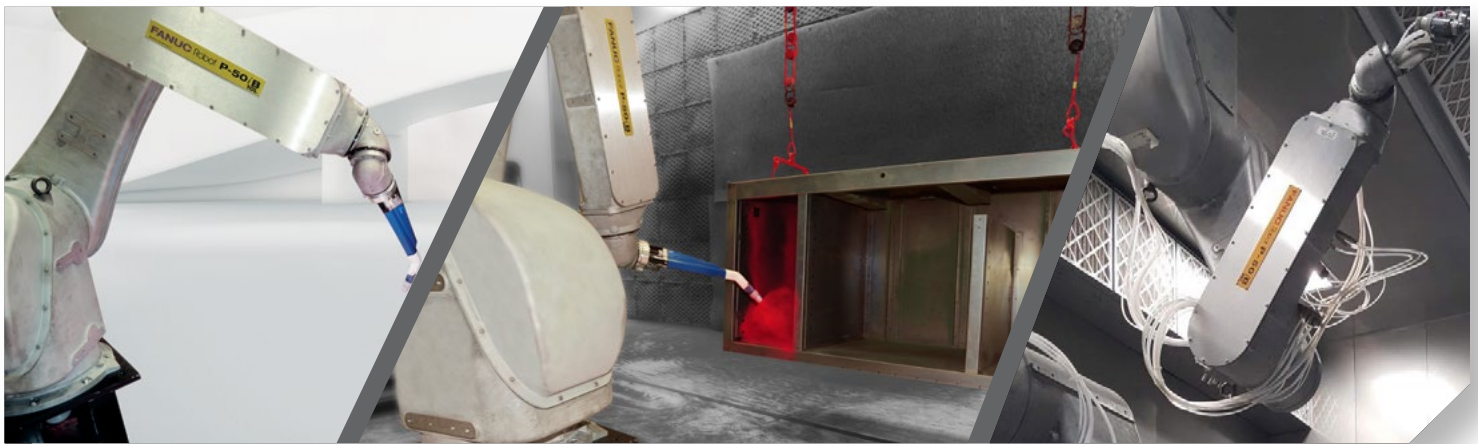


Features

- Ability to package process components in the outer arm in close proximity to the applicator for rapid, accurate, and consistent application performance
- Optional transducers and trigger valve are built into the inner arm for fast process control
- Flip-Over capability provides for a wide variety of work envelopes
- Balanced arm design provides excellent near reach and stroke
- New Mate Controller is compact but with same powerful processor as larger robots
- 140 degree hollow wrist to allow for tight process demands
- Dual Check Safety enables smaller booths and lower system costs

Options

- Floor, wall, angle, and ceiling mount configurations
- Easily configured left hand or right hand arm to maintain symmetry across the booth
- Designed for ease of maintenance and easy access to all critical components
- High arm and wrist payload design supports a variety of applications including rotary atomizers, conventional and electrostatic spray guns and multi-gun configurations



P-50iB/10L



Max. load capacity
at wrist: 10 kg



Max. reach:
1800 mm

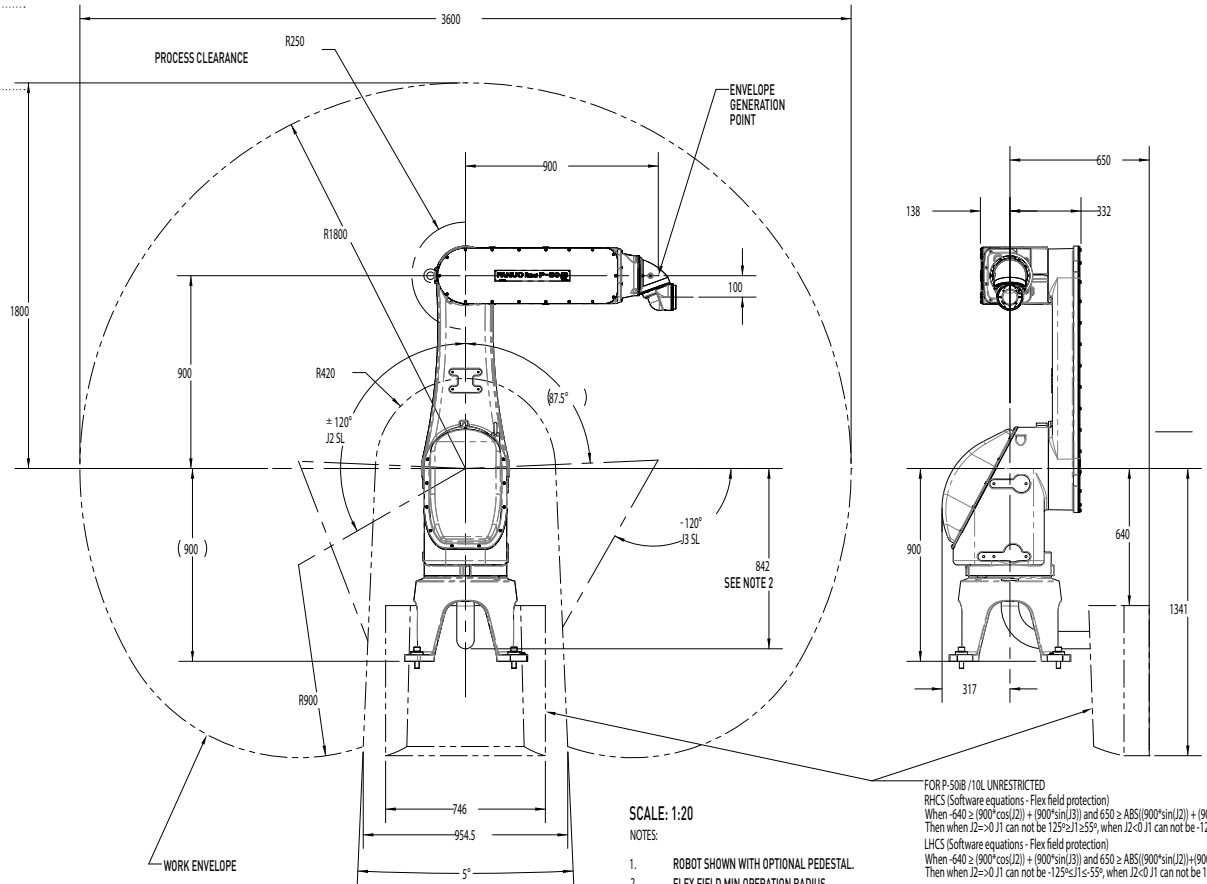
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Robot			Max. load capacity at wrist (kg)	Reach (mm)	Controlled axes	Repeatability (mm)	Mechanical weight (kg)	Motion range [°]						Maximum speed [°/s]						Allowable load moment at wrist (Nm) Allowable load inertia at wrist (kg m ²)			Input power 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	±0.2	364	±160	±120	+300 -120	±540	±540	±540	140	140	160	375	430	545	43.45 1.954	36.86 1.413	4.9 .025	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.
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FOR P-50B/10L UNRESTRICTED
 RHCS (Software equations - Flex field protection)
 When -640 ≥ (900*cos(J2)) + (900*sin(J3)) and 650 ≥ ABS(900*sin(J2)) + (900*cos(J3))
 Then when J2 ≥ 0 J1 can not be 125° ≤ J1 ≤ 55°; when J2 < 0 J1 can not be -125° ≤ J1 ≤ 55°
 LHCS (Software equations - Flex field protection)
 When -640 ≥ (900*cos(J2)) + (900*sin(J3)) and 650 ≥ ABS(900*sin(J2)) + (900*cos(J3))
 Then when J2 ≥ 0 J1 can not be -125° ≤ J1 ≤ 55°; when J2 < 0 J1 can not be 125° ≤ J1 ≤ 55°

LH INNER ARM OFFSET
CONFIGURATION SHOWN