

2.8 Robot Motion

Floor-mounting

Dimensions apply to
IRB 6400R/ 3.0-100

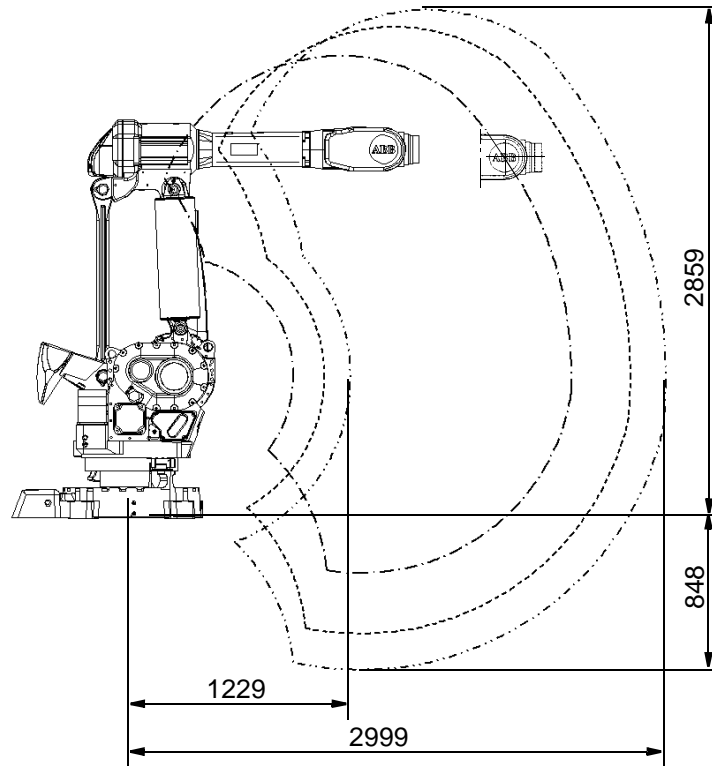


Figure 8 Working space of IRB 6400R (dimensions in mm).

Motion performance

The QuickMove™ concept means that a self-optimizing motion control is used. The robot automatically optimizes the servo parameters to achieve the best possible performance throughout the cycle – based on load properties, location in working area, velocity and direction of movement.

- No parameters have to be adjusted to achieve correct path, orientation and velocity.
- Maximum acceleration is always obtained (acceleration can be reduced, e.g. when handling fragile parts).
- The number of adjustments that have to be made to achieve the shortest possible cycle time is minimized.

The TrueMove™ concept means that the programmed path is followed – regardless of the speed or operating mode – even after an emergency stop, a safeguarded stop, a process stop, a program stop or a power failure.

The robot can, in a controlled way, pass through singular points, i.e. points where two axes coincide.

Technical specification

IRB 6400R /2.5-120, /2.5-150, /2.5-200, /2.8-150, /2.8-200 and /3.0-100

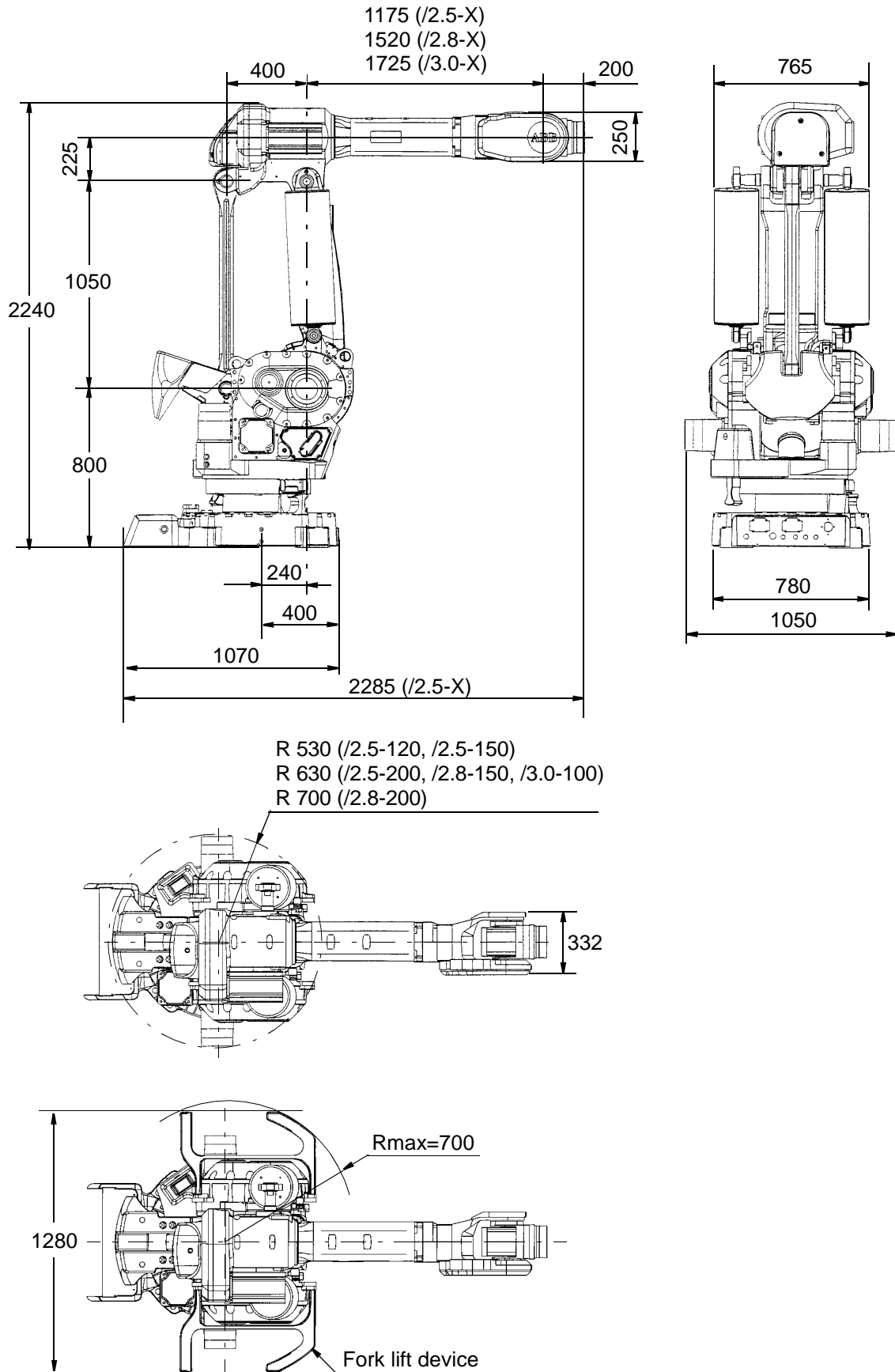


Figure 11 View of the manipulator from the side, rear and above (dimensions in mm).

Mounting the manipulator

Maximum load in relation to the base coordinate system.

	Endurance load in operation	Max. load at emergency stop
Force xy	±14000 N	±38000 N
Force z	22000 ±8000 N	22000 ±19000 N
Torque xy	±34000 Nm	±61000 Nm
Torque z	7000 Nm	±15000 Nm

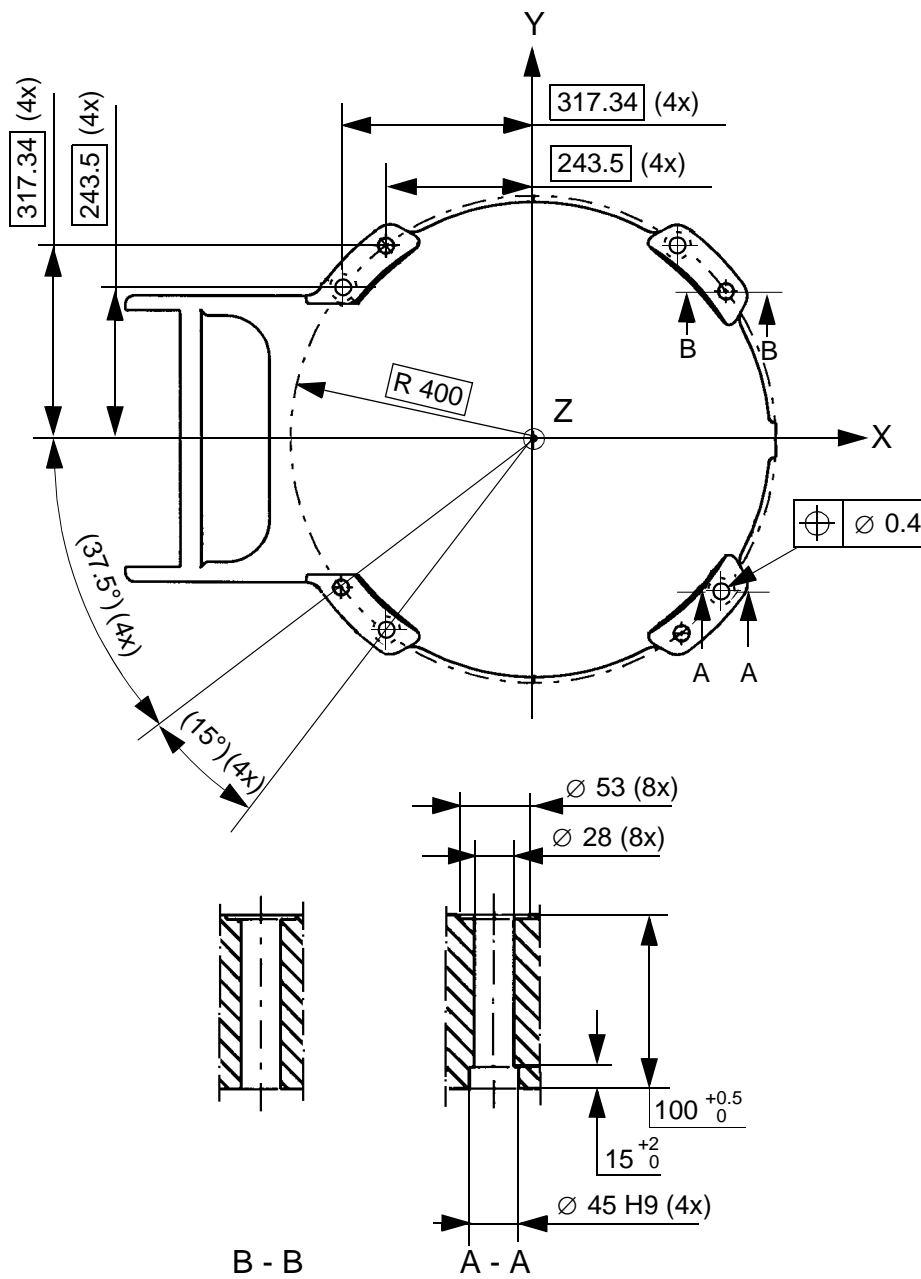


Figure 14 Hole configuration (dimensions in mm).