

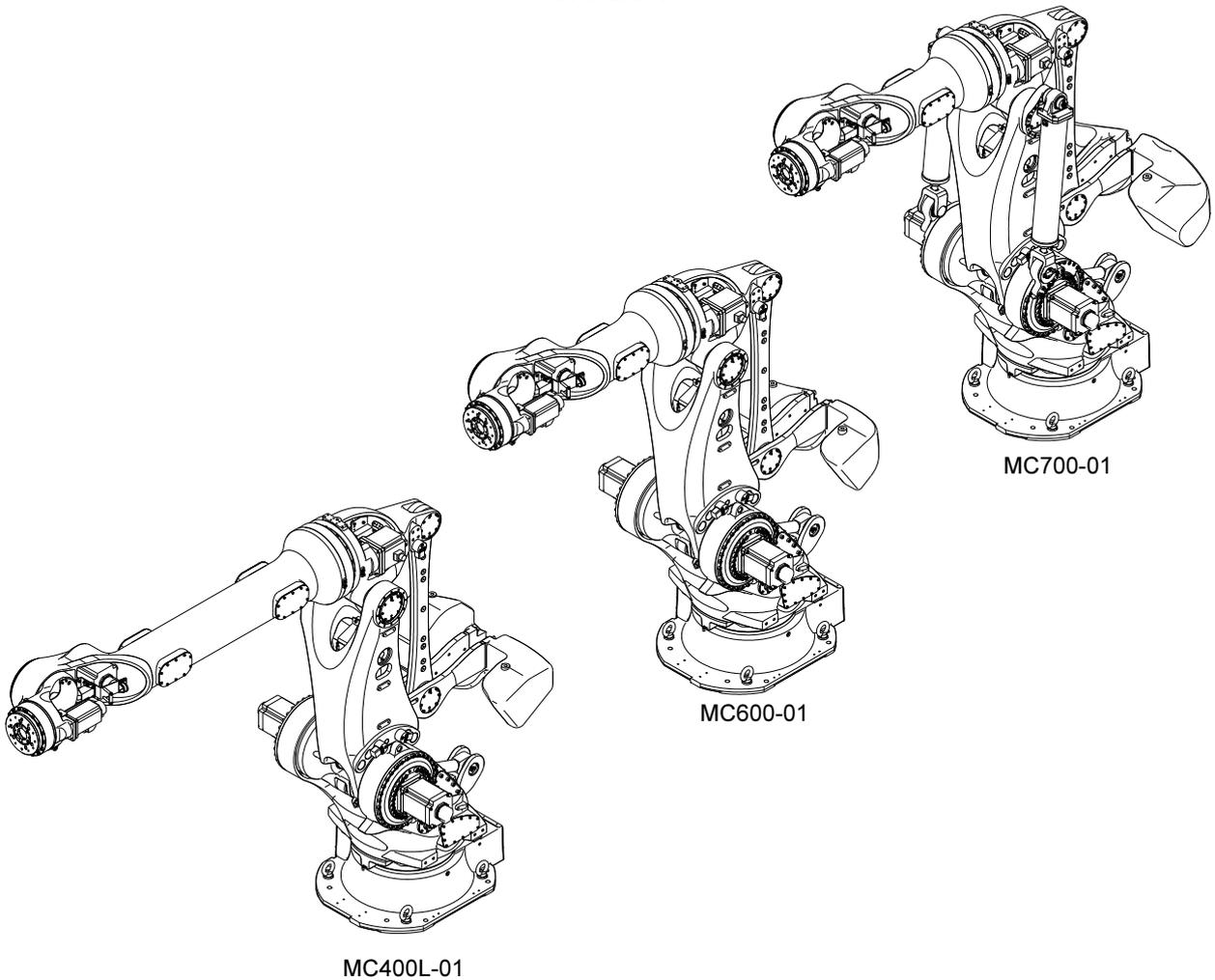
## Standard specifications

**MC400L-01 [FD11]**

**MC600-01 [FD11]**

**MC700-01 [FD11]**

5th edition



**NACHI-FUJIKOSHI CORP.**

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# 1. Outline

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

This is a robot of simple highly rigid structure which is optimal for material handling application. \*1

Max. payload	400 kg	600 kg	700 kg
Installation	MC400L-01	MC600-01	MC700-01
Floor mount	MC400L-01	MC600-01	MC700-01

## ■ Characteristics

1. Due to high wrist torque and high moment of inertia, this robot is suitable for handling of heavy payload.
2. Wide motion range makes easier applicability than before.
3. By installing the balance unit inside arm, swivel base becomes slim and interference radius gets substantially shorter than before.
4. Due to making higher maximum speed, cycle time is shortened. Also it is possible to get faster air-cut motion that is changing wrist attitude widely.
5. By hollow forearm and wrist, cables to end effector are installed inside arm. So it is possible to install robot in narrow space where used to be difficult to install it.

\*1: MC700 is used only for material handling application.

## 2. Basic specifications

Item		Specifications		
Robot model		MC400L-01	MC600-01	MC700-01
Construction		Articulated		
Number of axis		6		
Drive system		AC servo motor		
Max. working envelope	Axis 1	±3.14 rad (±180°)		
	Axis 2	-1.83 ~ +1.05rad (-105 ~ +60°)		
	Axis 3	-2.27 ~ +0.52rad (-130 ~ +30°)	-2.44 ~ +0.52rad (-140 ~ +30°)	
	Axis 4	±3.67 rad (±210°)		
	Axis 5	±2.09 rad (±120°)		
	Axis 6	MAX: ±6.28 rad (±360°) INITIAL SETTING: ±3.67 rad (±210°)*4		
Max. speed	Axis 1	1.57 rad/s (90°/s)	1.40 rad/s (80°/s)	
	Axis 2	1.57 rad/s (90°/s)	1.40 rad/s (80°/s)	
	Axis 3	1.57 rad/s (90°/s)	1.40 rad/s (80°/s)	
	Axis 4	1.92 rad/s (110°/s)	1.74 rad/s (100°/s)	
	Axis 5	1.92 rad/s (110°/s)	1.74 rad/s (100°/s)	
	Axis 6	3.14 rad/s (180°/s)	2.79 rad/s (160°/s)	
Max. pay load	Wrist	400 kg	600 kg	700 kg
	Forearm *1	50 kg at maximum		25 kg at maximum
Allowable static load torque	Axis 4	3450 N·m		
	Axis 5	3450 N·m		
	Axis 6	1725 N·m		
Allowable moment of inertia *2	Axis 4	600 kg·m <sup>2</sup>		
	Axis 5	600 kg·m <sup>2</sup>		
	Axis 6	400 kg·m <sup>2</sup>		
Position repeatability *3		±0.3 mm		
Installation		Floor mounting		
Ambient conditions		Temperature: 0 to 45 °C *5 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> )		
Robot mass		3,050 kg	2,850 kg	3,320 kg

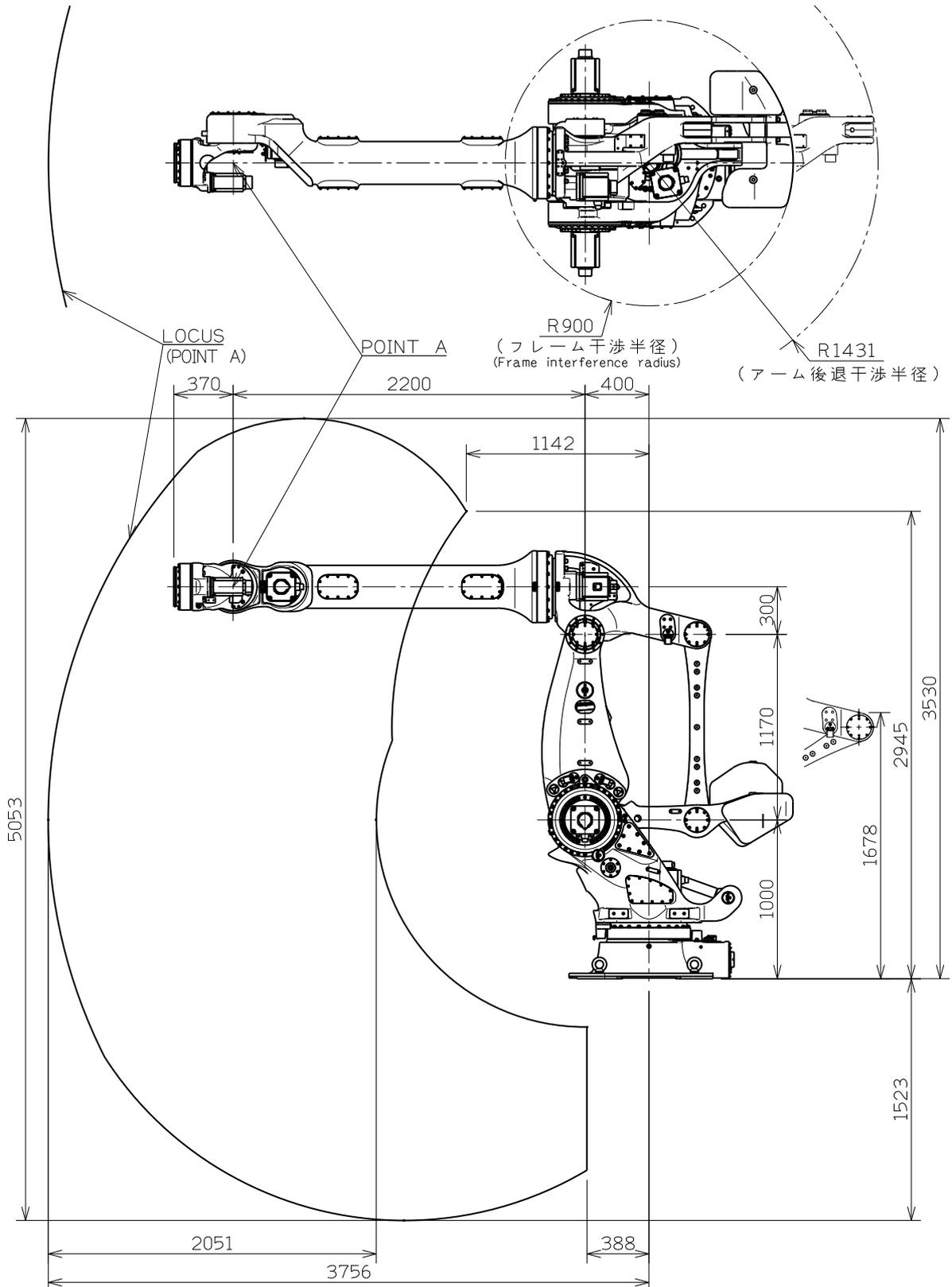
1[rad] = 180/π[°], 1[N·m] = 1/9.8[kgf·m]

- On controller display, axis 1 to 6 is displayed as J1 to J6 for each.
- The specification and externals described in this specification might change without a previous notice for the improvement.
- The explosion proof specification is not available.

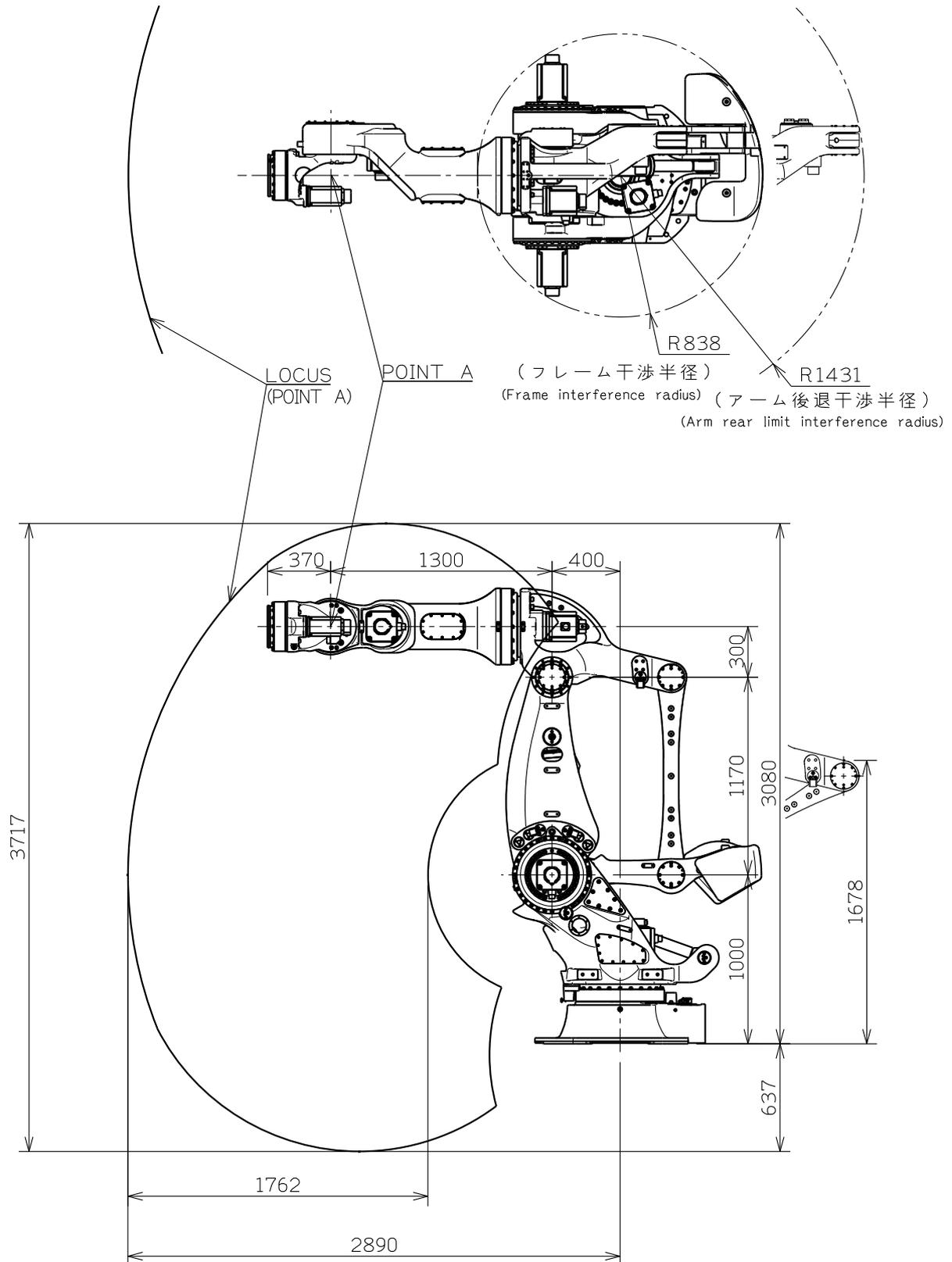
\*1: This value changes by placement and load conditions of a wrist. \*2: The Allowable moment of inertia of a wrist changes with load conditions of a wrist. \*3: This value conforms to "JIS B 8432". \*4: The initial setting of the software limit is ±210°. When installing the cables in the hollow hole part of the Axis 6, please use the robot in the range of ±210°. If the cables do not go through the hollow hole of the axis 6, it is possible to widen the motion range of the Axis 6 up to ±360° considering the condition. For details of how to change the software limit range, refer to the instruction manual "SETUP MANUAL"(Chapter 4). \*5: Permitted height is not higher than 1,000m above sea level. If used in higher place, permitted temperature is affected by height.

### 3. Robot dimensions and working envelope

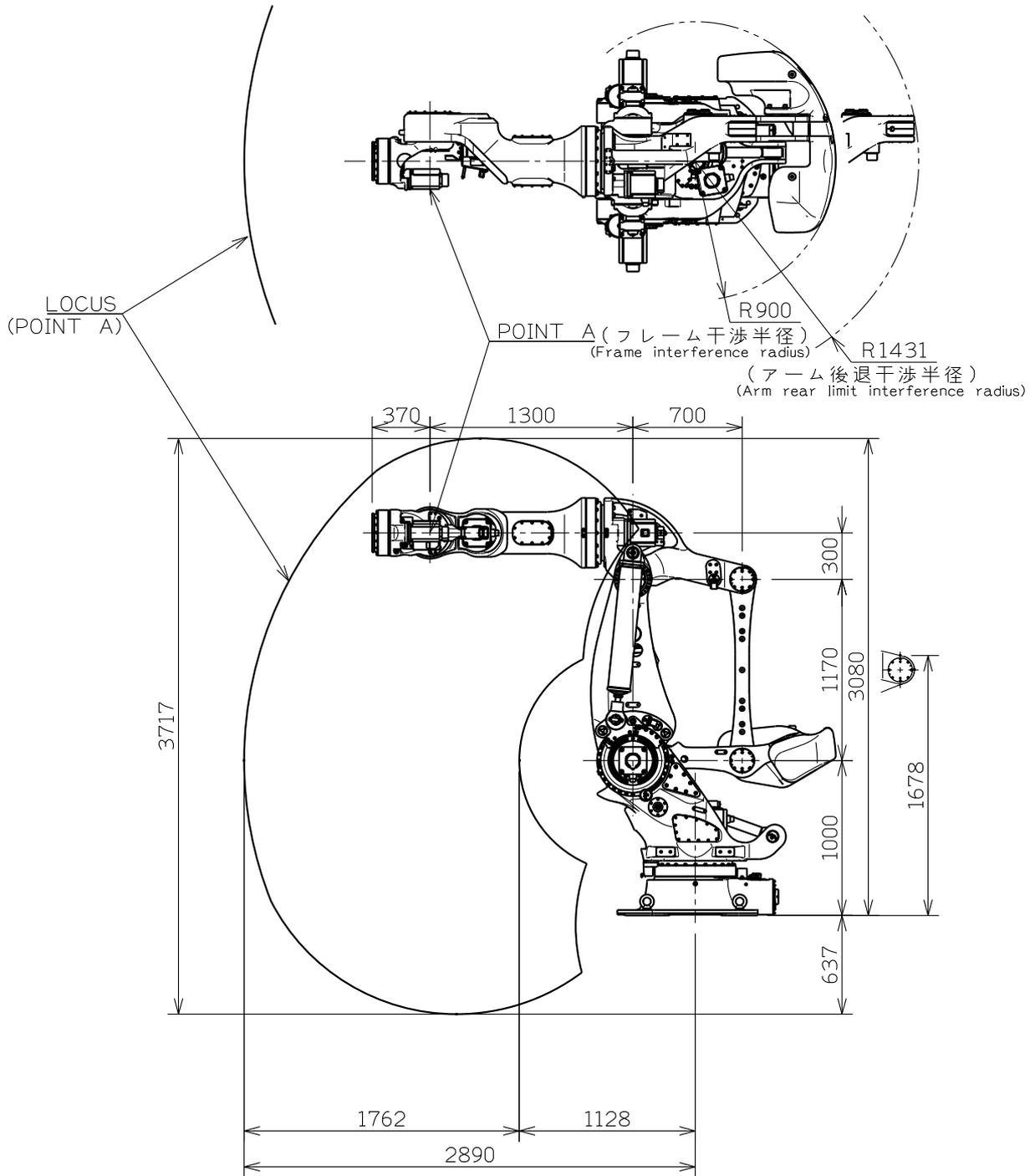
[MC400L-01]



[MC600-01]



[MC700-01]



## 4. Detail of load mounting plate

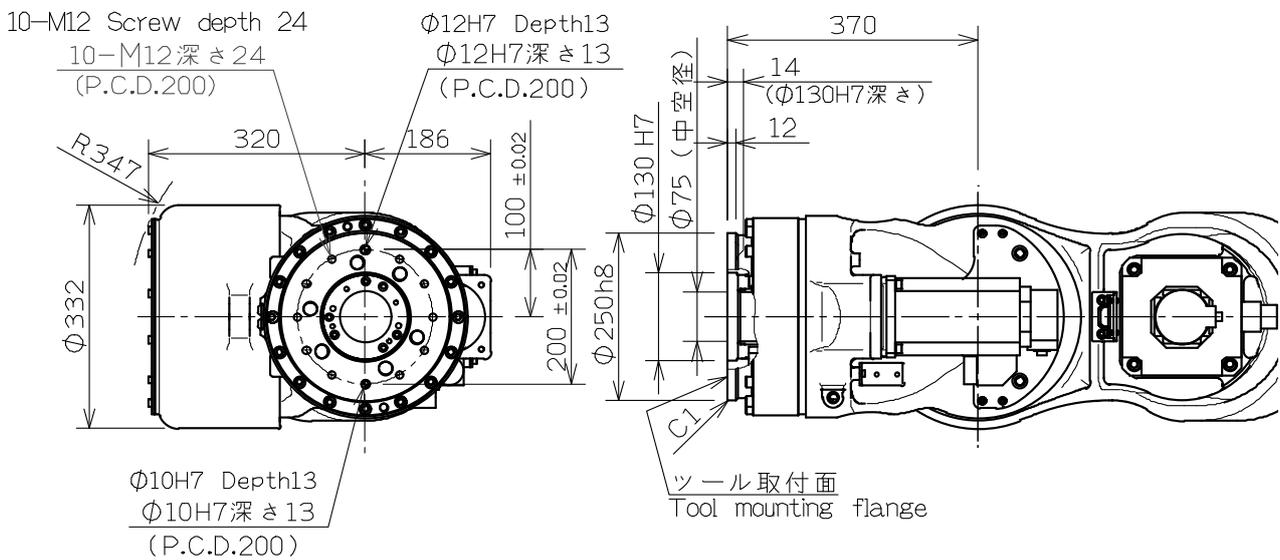
### ■ Wrist

For the end effector fixing bolts, use the mounting P.C.D. shown in the following figures.  
Another P.C.D. is prepared as option. Consult with each NACHI-FUJIKOSHI office for the details.

 <b>CAUTION</b>	Be sure to screw the M12 tool fixing bolts in the wrist not deeper than the screw depth in the mounting face. Screwing the bolts deeper than the screw depth may damage the wrist.
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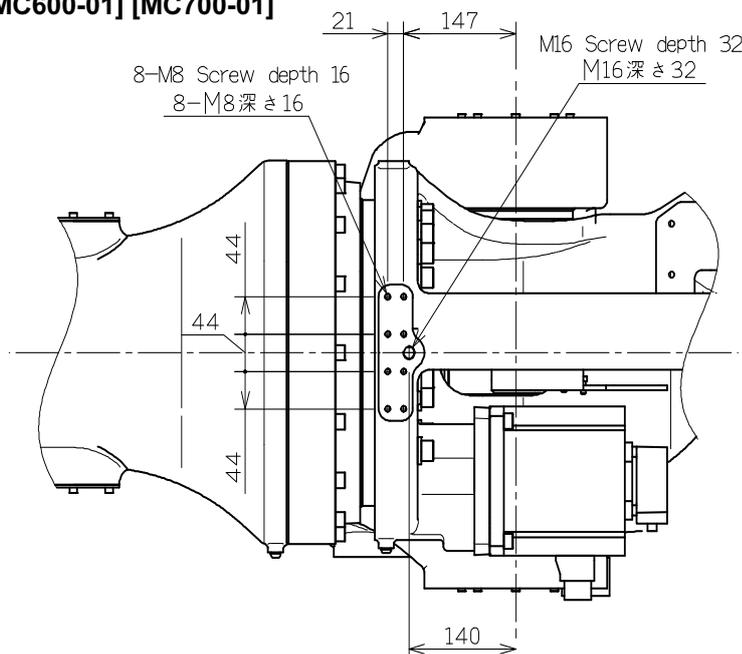
[MC400L-01] [MC600-01] [MC700-01]

Tightening torque of M10 Hex. socket head cap screw	
JIS: Strength class 10.9	96 N·m
JIS: Strength class 12.9	116 N·m



### ■ Upper part of forearm

[MC400L-01] [MC600-01] [MC700-01]



## 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 not only the static loads but also the reaction force caused by robot movement. 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	MC400L-01, MC600-01, MC700-01
Thickness of floor concrete	Not less than 160 mm
Installation parts *1	8 bolts of M20 (JIS: Strength class 12.9) not less than 65mm 8 plain washers of not less than 4.5 mm in thickness and HRC35 in hardness
Tightening torque *2	560 ± 30 N·m
Allowable repeated tensile *3	Approximately 56,000 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.

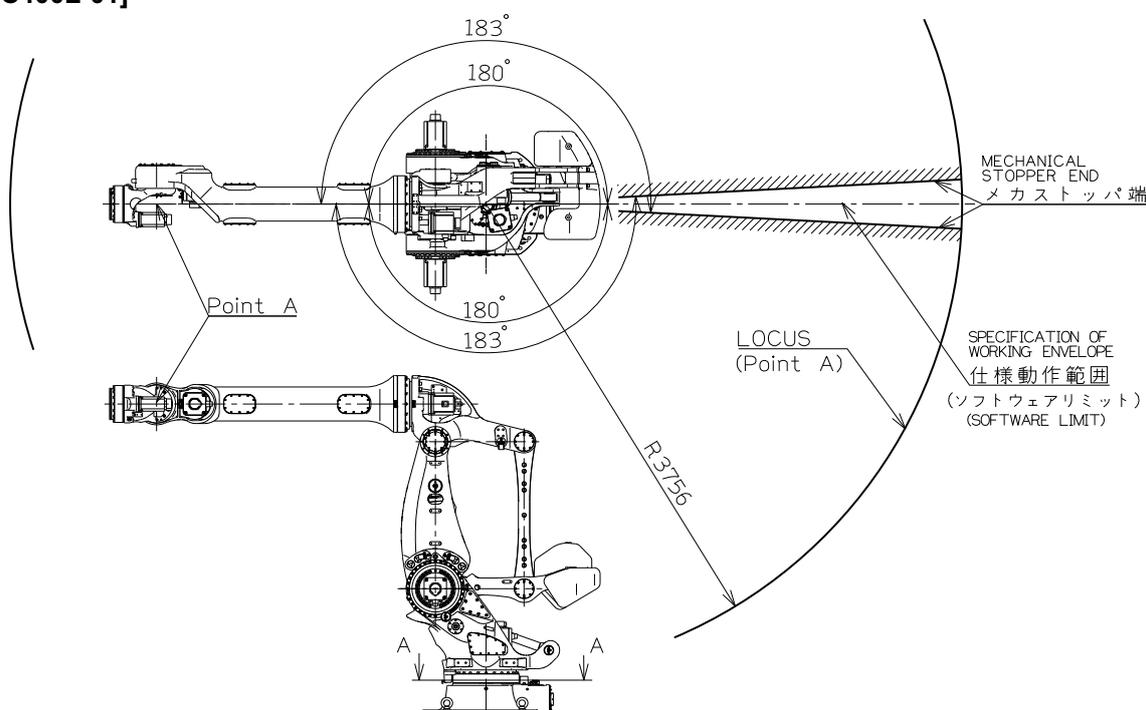
\*3 : This tensile is per installation bolt when robot is installed with all bolts written in table above.

■ Installation space

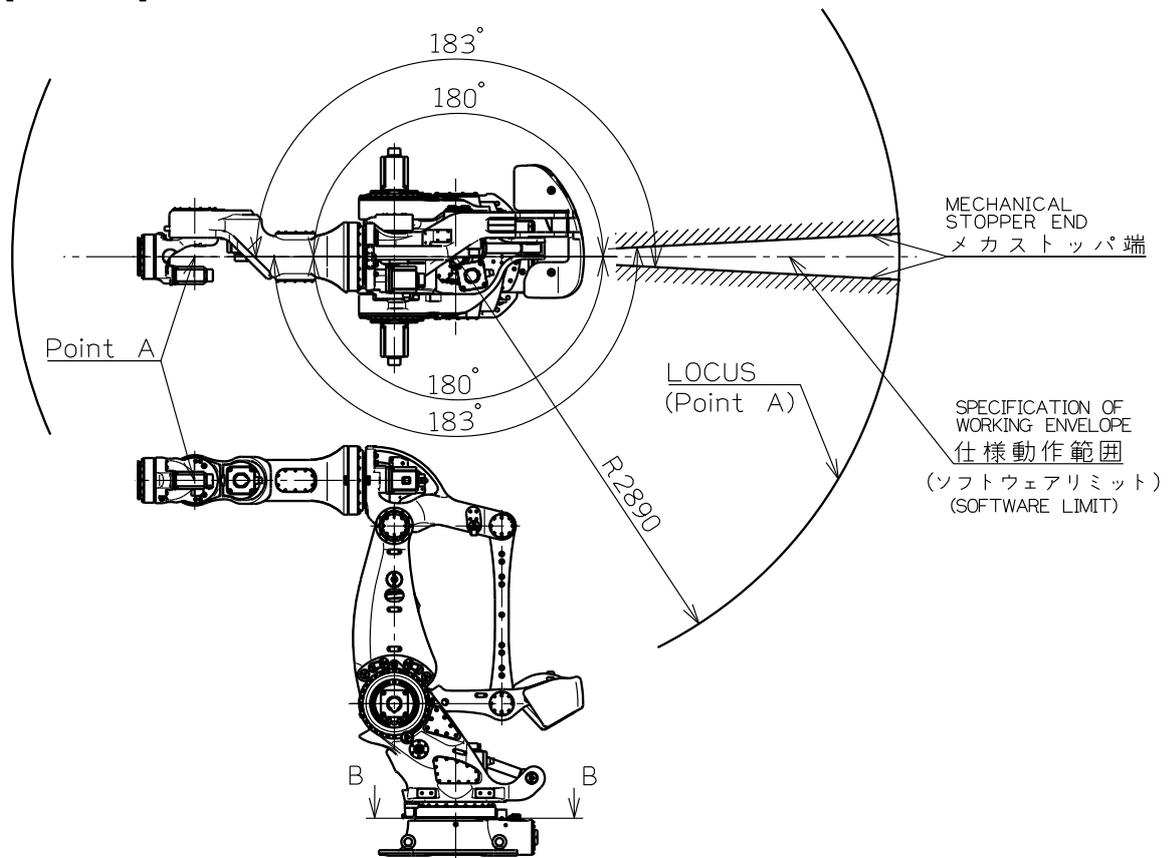
To install the robot, lock the swiveling base of the robot.

 WARNING	The mechanical stopper end is located in a position exceeding the specified working envelope (software limit) of axis 1 by 3°. To install the safety fence, with consideration given to the wrist configuration and the shape of end effector.
 WARNING	On axes 1, 2 and 3, the robot working envelope can be regulated for safety (optional function). Since optional parts should be installed to enable this function, do not independently move the standard parts (e.g. mechanical stopper).
 WARNING	If mechanical stopper collides and robot stops, it's possible that some parts are already damaged, for example, mechanical stopper is transformed or fixing bolts are broken. In this case, sufficient intensity and function can not be kept. Mechanical stopper and reduction gear of collided joint are needed to be replaced to the new one.

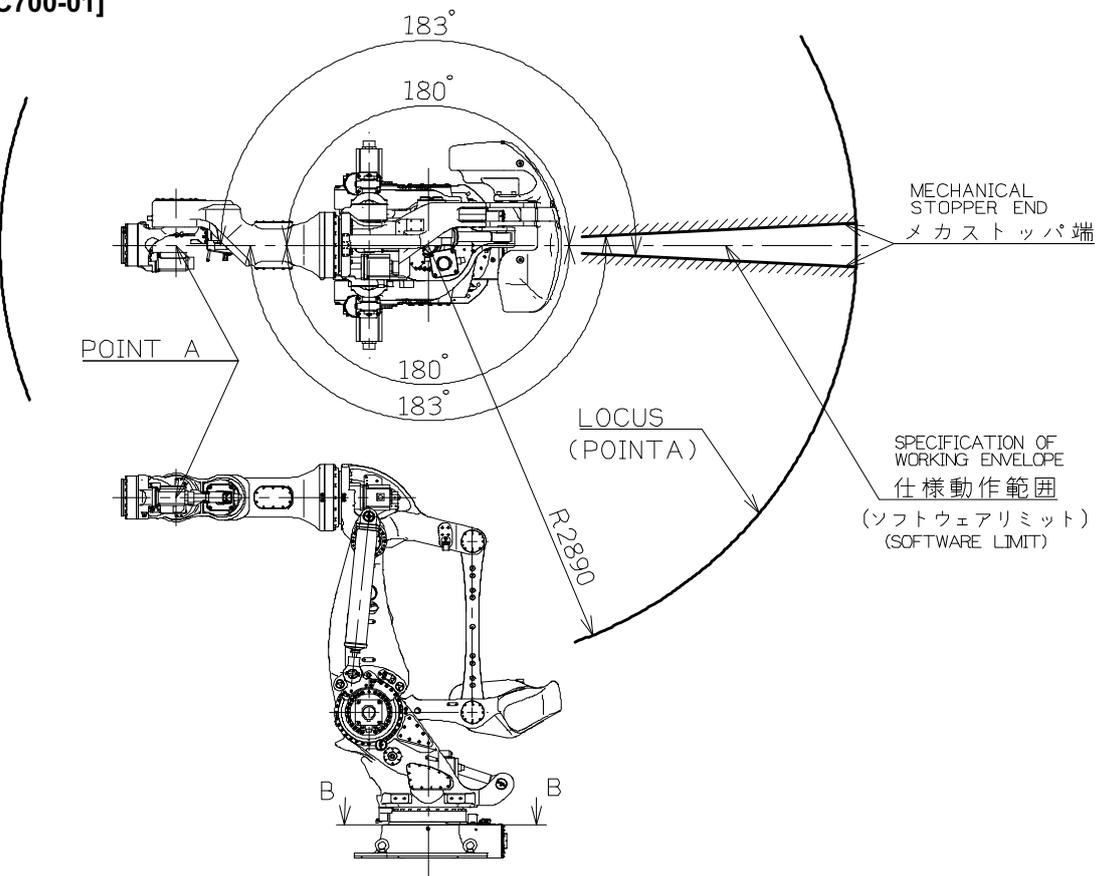
[MC400L-01]



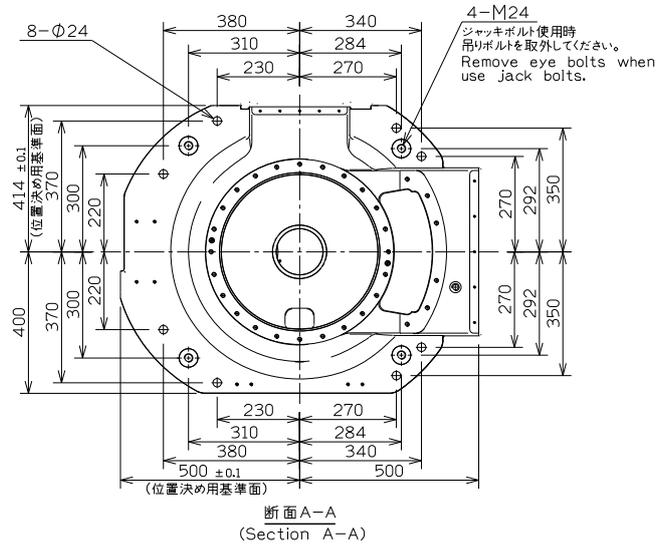
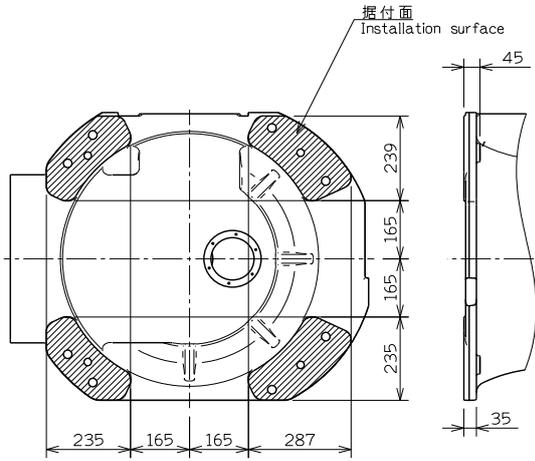
[MC600-01]



[MC700-01]



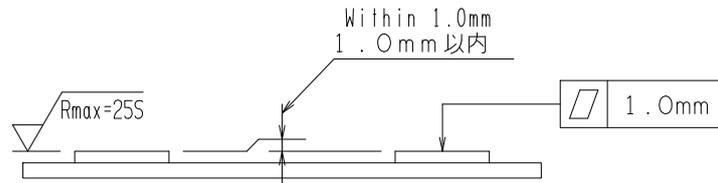
[MC400L-01] [MC600-01] [MC700-01]



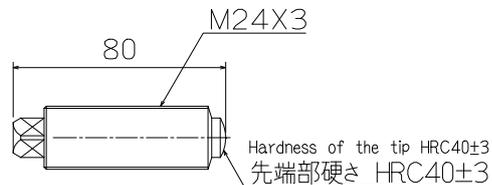
■ Accuracy of installation surface

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 1.0 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 1.0mm (±0.5mm).
- (3) The roughness of the surface of the base plate must be 25S or less in Rmax.



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

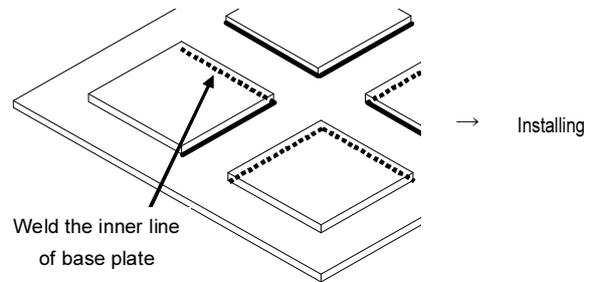
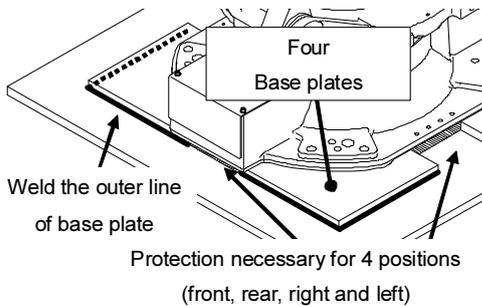


■ Welding of base plate

Protect the space (4 places of the front, back, left and right) on robot bottom and installed side by the cover etc. as follows when you weld with the base plate installed in the robot body by the welding spatter and the spark, etc. so that wiring in the robot should not receive damage. After welding the outer line, once remove the robot and weld the inner line.

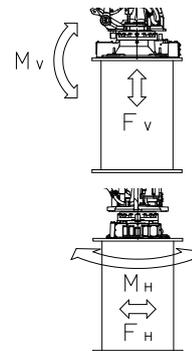
Temporary install the robot, and weld the outer line of base plate.

Once remove the robot and weld the inner line.



■ Maximum robot generative force

Robot model	Max. vertical generative force $F_v$	Max. horizontal generative force $F_H$	Max. vertical generative moment $M_v$	Max. horizontal generative moment $M_H$
MC400L-01 MC600-01	95,300 N	69,500 N	260,400 N·m	225,800 N·m
MC700-01	147,100 N	111,200 N	347,900 N·m	306,800 N·m



## 6. Allowable wrist load



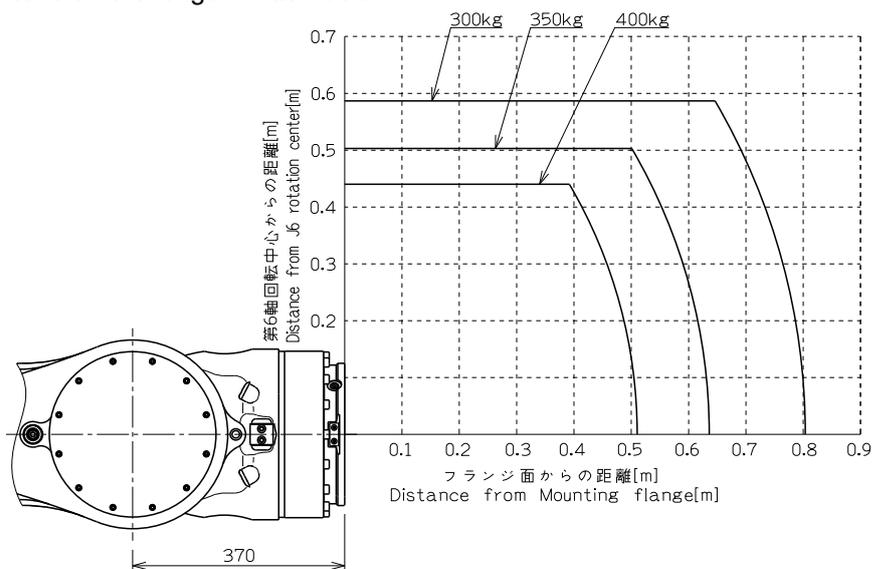
CAUTION

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. Refer to the table of “2. Basic specifications” and following figures for the detail of each specification.

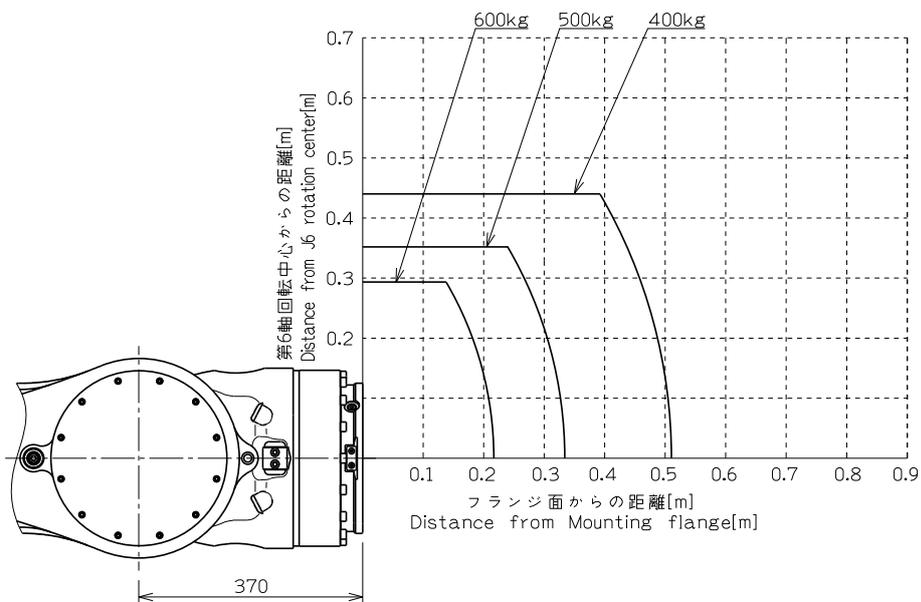
### ■ Torque map

Use the robot under condition that COG of wrist load falls on the rotation center of axis 6 and its direction is shorter than the length written below.

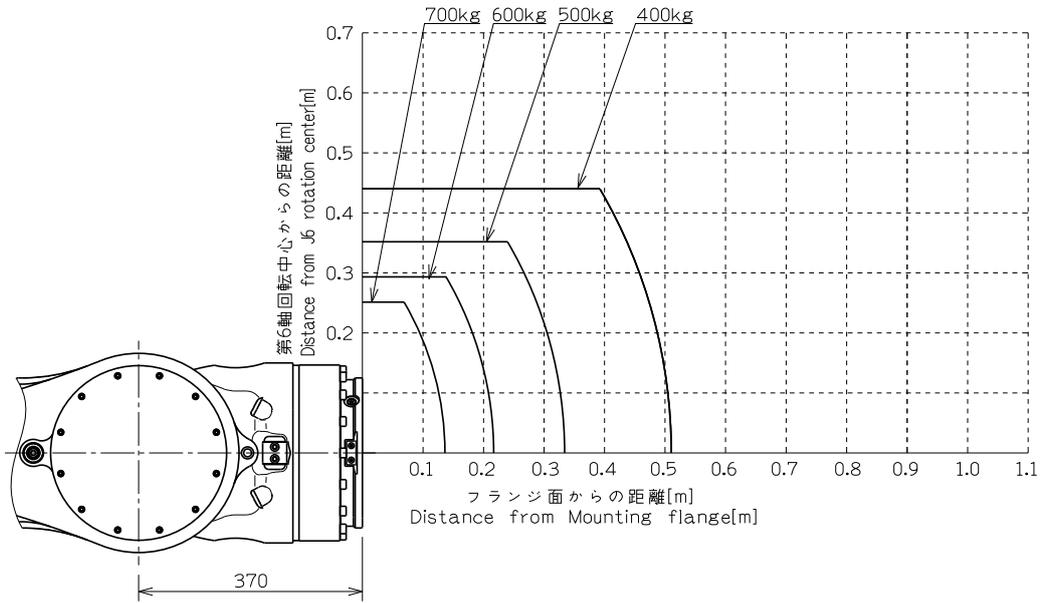
[MC400L-01]



[MC600-01]



[MC700-01]

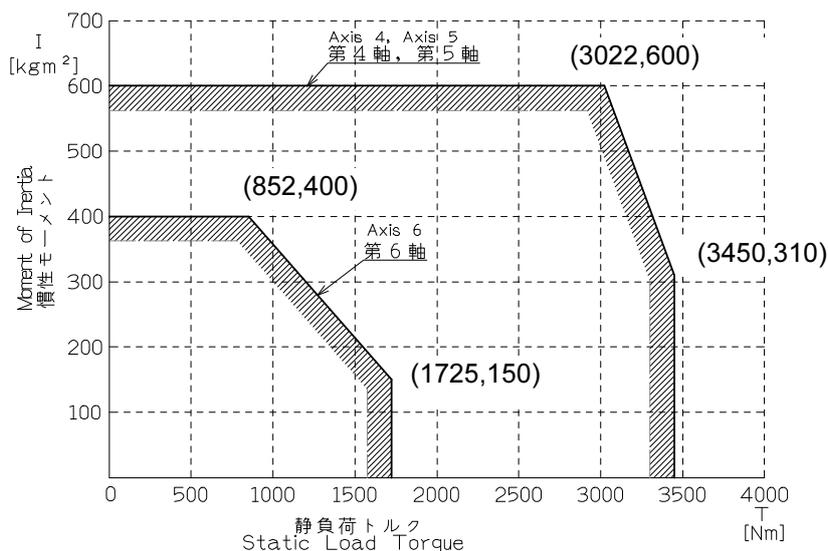


■ **Wrist load conditions**

Static load torque and moment of inertia of wrist load should exist inside the range shown below. Maximum speed may be limited even when inertia of wrist load does not exceed the permitted range.

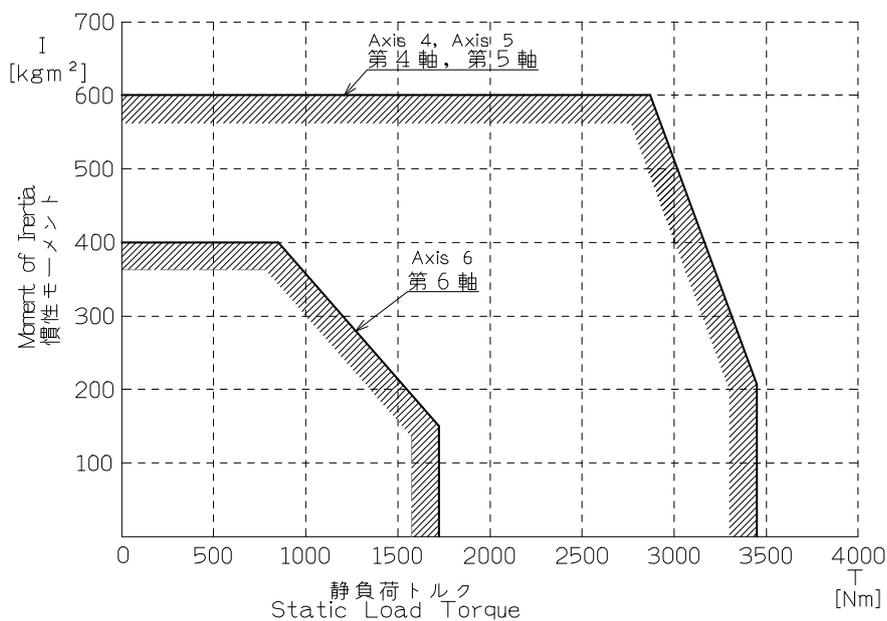
 <b>IMPORTANT</b>	If the real inertia is over the limit, maximum speed will be restrained by software to protect the robot.
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**[MC400L-01]**



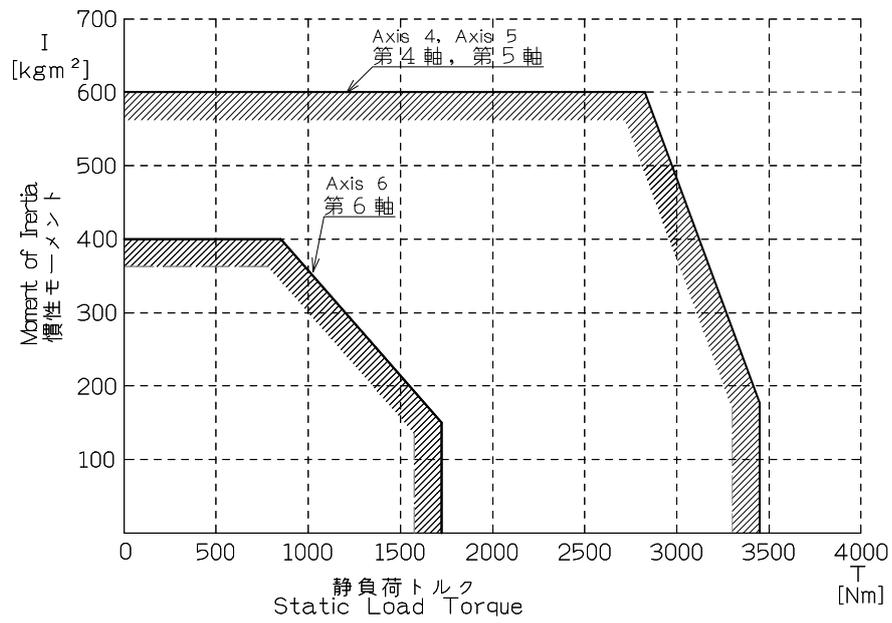
The robot operates at the most suitable speed considering the moment of inertia.

**[MC600-01]**



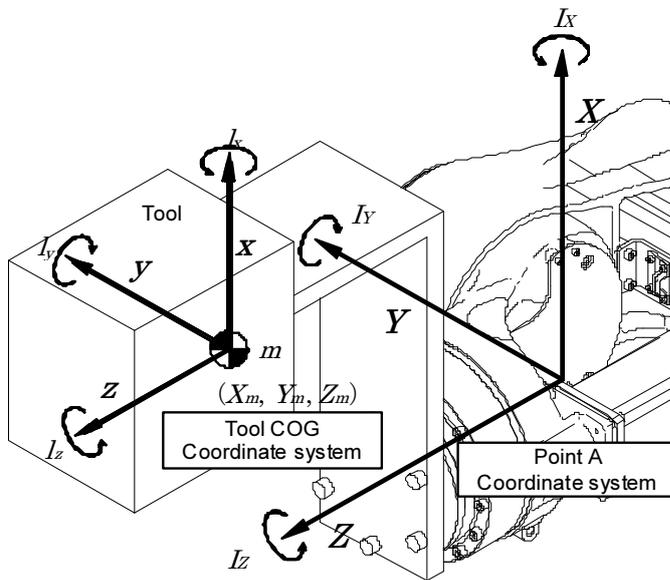
The robot operates at the most suitable speed considering the moment of inertia.

[MC700-01]



The robot operates at the most suitable speed considering the moment of inertia.

■ How to find the inertia moment of each axis



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 tool, and parallel to point A coordinate system

x: Parallel to X

y: Parallel to Y

z: Parallel to Z

Inertia moment

I<sub>x</sub>: Around X on point A coordinate system

I<sub>y</sub>: Around Y on point A coordinate system

I<sub>z</sub>: Around Z on point A coordinate system

I<sub>x</sub>: Around x on tool COG coordinate system

I<sub>y</sub>: Around y on tool COG coordinate system

I<sub>z</sub>: Around z on tool COG coordinate system

m: Tool mass

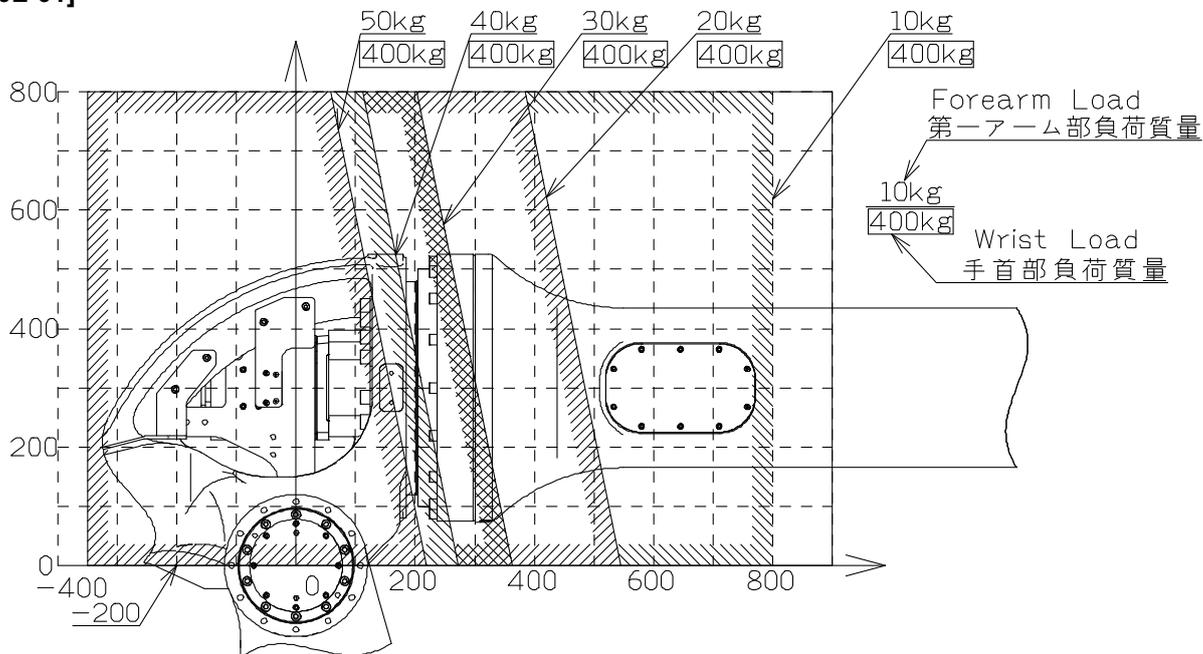
(X<sub>m</sub>, Y<sub>m</sub>, Z<sub>m</sub>): COG of tool on point A coordinate system

<p><b>1</b> Calculate inertia moment defined on tool COG coordinate system (xyz). If tool is regarded as prism, it is calculated as right formula.</p>	<p>Inertia moment example on tool COG coordinate system</p> <p>If tool is regarded as prism</p> $I_x = \frac{1}{12} m \cdot (A^2 + B^2)$ $I_y = \frac{1}{12} m \cdot (A^2 + C^2)$ $I_z = \frac{1}{12} m \cdot (B^2 + C^2)$ <p>These values (I<sub>x</sub>, I<sub>y</sub>, I<sub>z</sub>) are registered to controller.</p> <p>Inertia moment on tool COG coordinate system</p> <p>This is different from "allowable moment of inertia" written in robot specification sheet.</p>
<p><b>2</b> 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.</p>	<p>Inertia moment on point A coordinate system (XYZ) is</p> $I_X = m \cdot (Y_m^2 + Z_m^2) + I_x$ $I_Y = m \cdot (X_m^2 + Z_m^2) + I_y$ $I_Z = m \cdot (X_m^2 + Y_m^2) + I_z$ <p>Axis 4 and 5 inertia moment is larger value of I<sub>X</sub> and I<sub>Y</sub>, because this depends on axis 6 position. Axis 6 inertia moment is I<sub>Z</sub> itself.</p> $I_{J4} = I_{J5} = \max(I_X, I_Y)$ $I_{J6} = I_Z$

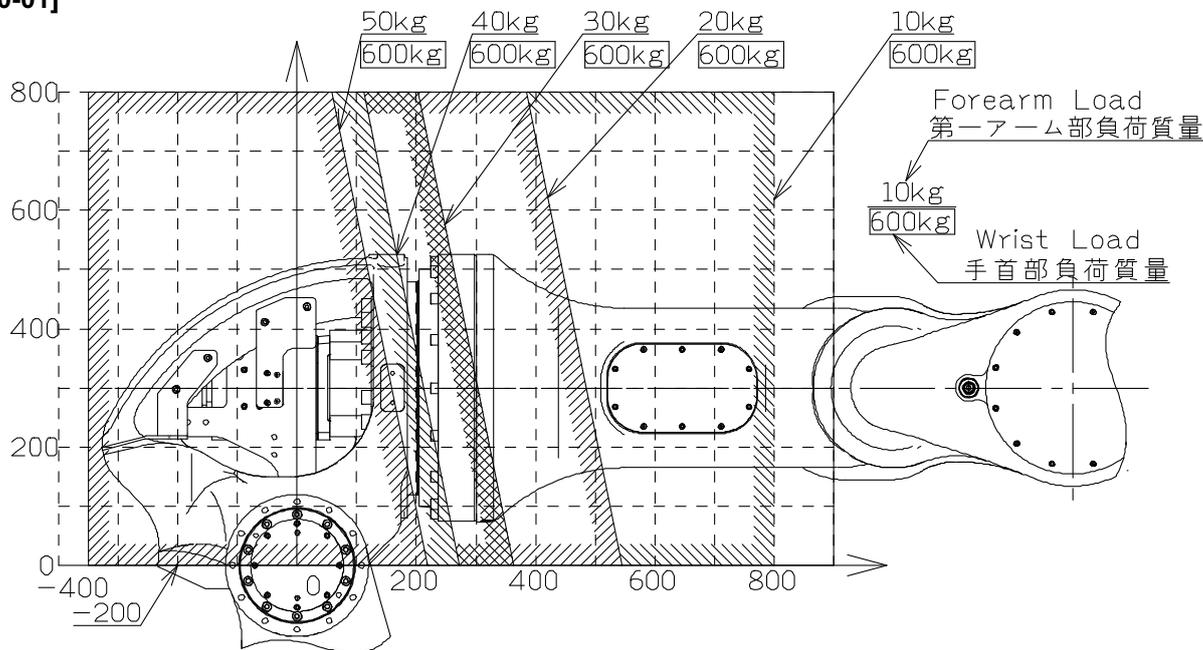
■ Allowable forearm load

Use the robot under condition that COG of the ancillary equipment on the forearm falls in the range shown below.

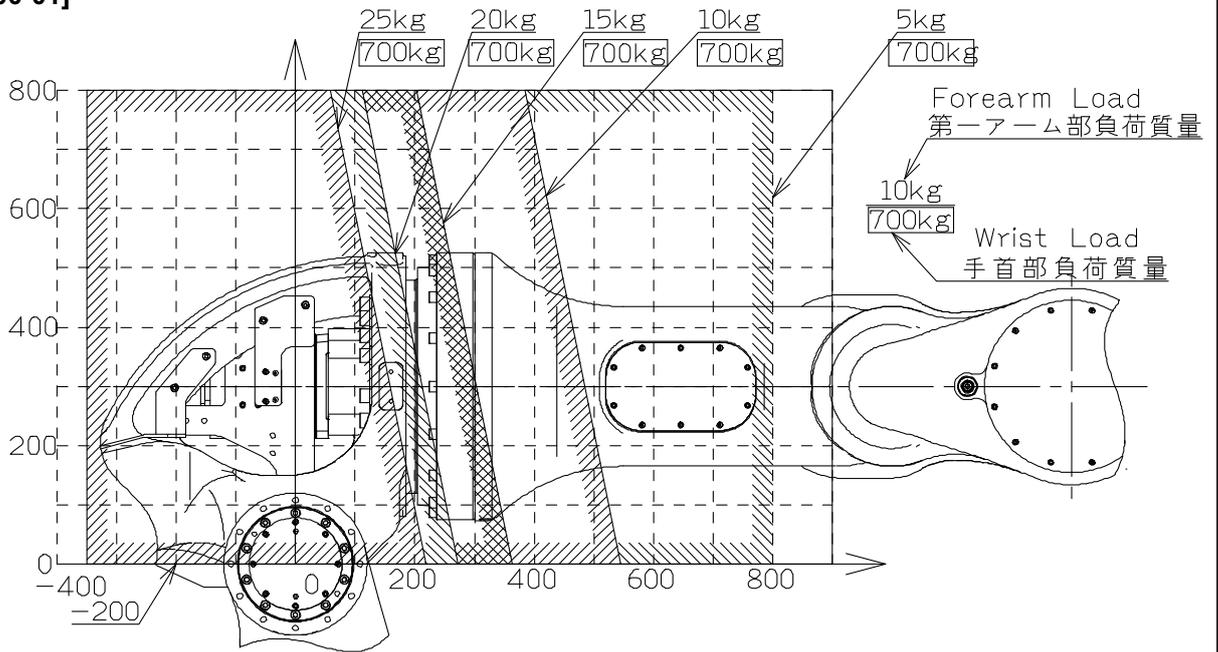
[MC400L-01]



[MC600-01]



[MC700-01]



## 7. Option specifications

### 7.1 Mechanical options

O: Possible to use / —: Impossible to use

No	Item	Specifications	Parts No.	Robot model		
				MC400L-01	MC600-01	MC700-01
1	Installation parts *1	Chemical anchor specification (Base plate welded)	OP-F1-037	○	○	○
		Hammer drive anchor specification (Base plate welded)	OP-F2-022	○	○	○
		Installation bolts & washers	OP-F1-036	○	○	○
2	Extension flange	Side routing flange fro cables (P.C.D.200)	OP-W3-015	○	○	○
3	Axis 1 adjustable stopper *1 (Including the adjustable LS dog)	Restriction of axis 1 operation edge Including adjustable limit switch dog (±2.61 rad ~ ±0, every 0.13 rad)	OP-S5-027	○	○	○
4	Axis 2 adjustable stopper	Restriction of axis 2 operation edge (by changing the position of the standard parts) (-0.26 rad, -0.52 rad from the upper limit, -0.26 rad, -0.52 rad from the lower limit)	Standard	○	○	○
5	Axis 3 adjustable stopper *1	Restriction of axis 3 operation edge (-0.26 rad, -0.52 rad from the upper limit, -0.26 rad, -0.52 rad from the lower limit)	OP-A6-030	○	○	○
6	Axis 2 adjustable LS dog	Axis 2 adjustable limit switch dog set	OP-S8-009	○	○	○
7	Axis 3 adjustable LS dog	Axis 3 adjustable limit switch dog set	OP-S4-015	○	○	○
8	Transfer jig	Fork bracket	OP-S2-046	○	○	○
9	Zeroing pin & block *1		OP-T2-090	○	○	○
10	Dual circuit limit switch (LS)	For axes 1, 2 and 3 (3pcs. of dual circuit LS)	Standard	○	○	○
11	Encoder connector protector	For axis 2 and 3	OP-P6-010	○	○	○
12	Scale sticker for zeroing position	For axis 4, 5 and 6	OP-N2-020	○	○	○
13	Gas balancer unit pressure gauge *1	Analog pressure gauge	KP-ZJ-013	○	○	○
		Digital pressure gauge	KP-ZJ-014	○	○	○
14	Gas balancer unit charging equipment *1 *2	Charging unit (W22, pitch14, Female)	KP-ZJ-015	○	○	○
		Charging unit (W23, pitch14, Male)	KP-ZJ-016	○	○	○
		Joint of Female->Male (W22)	KP-ZJ-019	○	○	○
		Axis 3 L shape joint for charging gas	KP-ZJ-066	○	○	○
15	Gas balancer support axis grease lubrication tool *1	Long nozzle for the Axis 2 support axis lubrication	KP-ZJ-069	○	○	○
		Lubrication tube for the Axis 3 support axis	KP-ZJ-067	○	○	○

\*1 : These parts are packed separately from the robot. (Not attached on the robot)

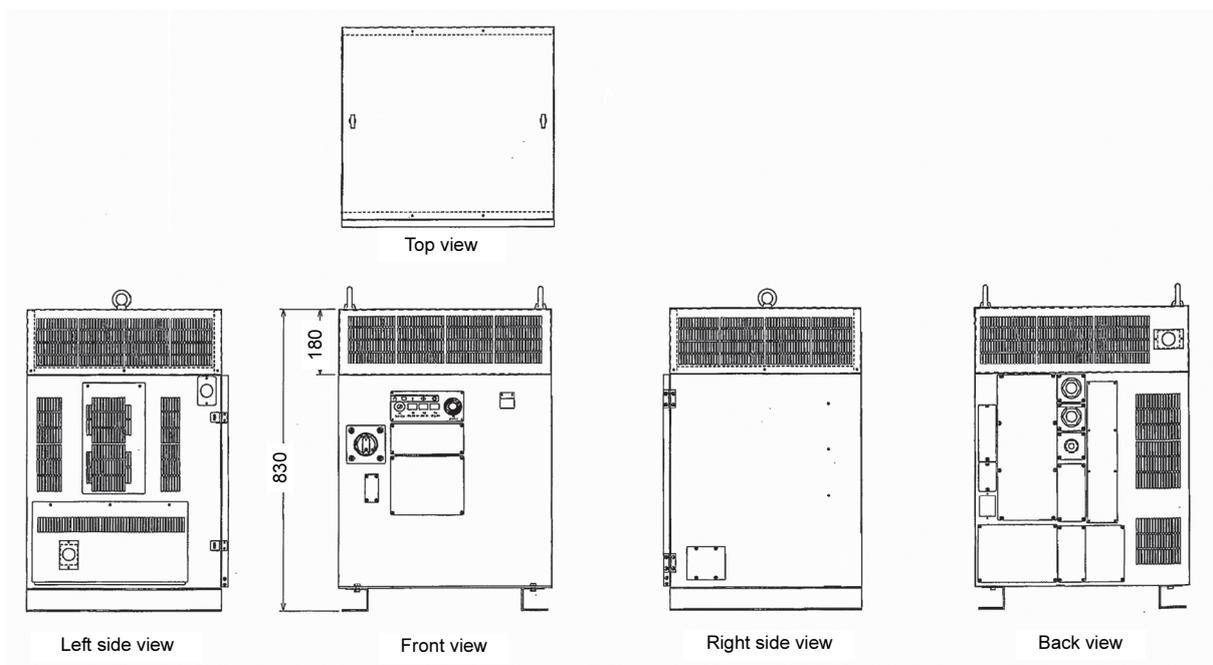
\*2 : If diameter of charging equipment (gas cylinder) is "W22, pitch14, Female, Right screw, Metal contacts", please prepare the charging equipment "KP-ZJ-015" and the joint "KP-ZJ-019".

## 7.2 Controller options

According to the application and moving pattern, "High capacity regenerative discharger option" is necessary. Please consult with each NACHI-FUJIKOSHI office for the detail of it.

○: Possible to use / - : Impossible to use

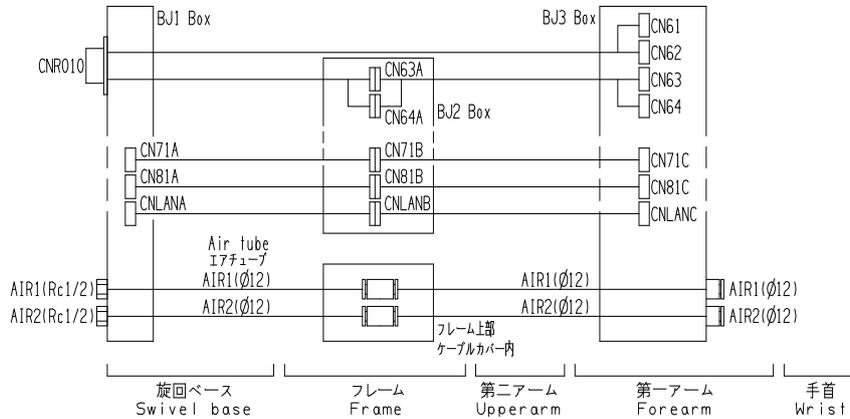
No	Item	Specifications	Parts No.	Robot model		
				MC400L-01	MC600-01	MC700-01
1	High capacity regenerative discharger option	High capacity regenerative discharger spec. (Controller size is same as standard.)	FD11-OP65-C	○	-	-
		High capacity regenerative discharger and high duty spec. (Controller size is bigger than standard. Please refer to the figure below.)	FD11-OP65-G	○	-	-



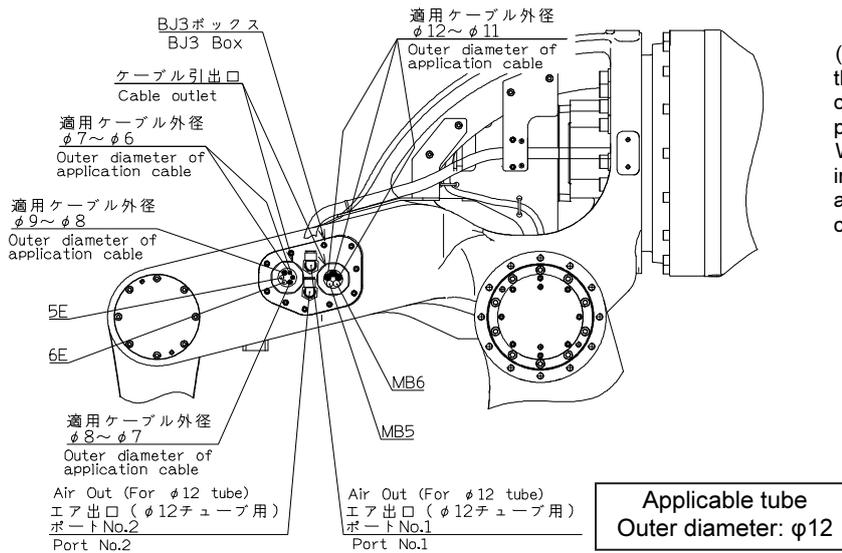
FD11-OP65-G (High capacity regenerative discharger and high duty spec) is installed on FD11 controller

## 8. Application wiring and piping diagram

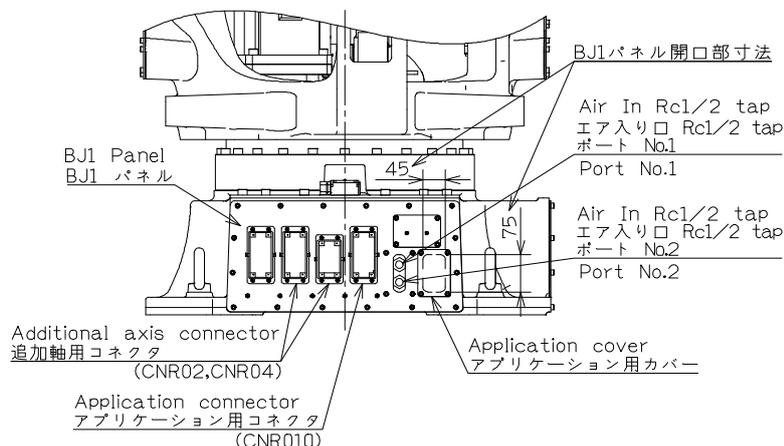
### ■ Standard specification [MC400L-01] [MC600-01] [MC700-01]



### ■ Upper part of forearm - Wiring and piping for application [MC400L-01] [MC600-01] [MC700-01]



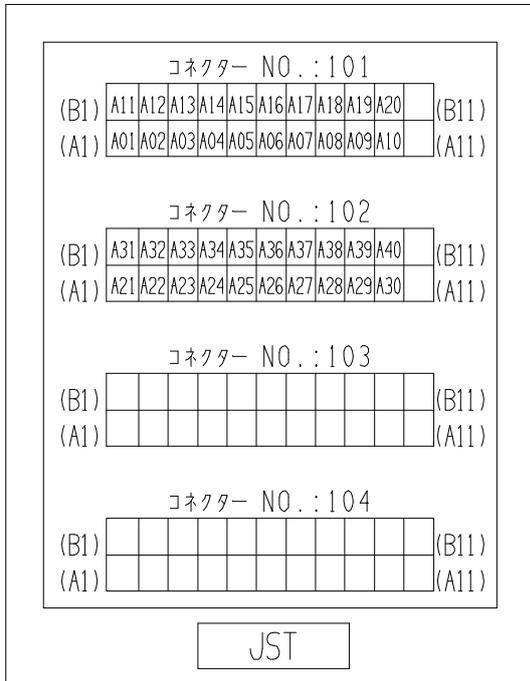
### ■ Base frame block - Wiring and piping for application [MC400L-01] [MC600-01] [MC700-01]



(NOTE) In wiring BOX (BJ1 BOX), there are connectors shown in the next pages. And, to use the DeviceNet / Ethernet connectors, it is necessary to manufacture the application cover.

■ Details of application connectors (standard) [MC400L-01] [MC600-01] [MC700-01]

BJ1 side (connector)

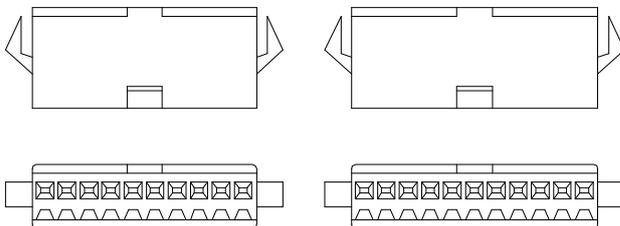


User-side Connectors

- Wire-side shell: JFM-WSA-4-A (JST)  
or JFM-WSA-4-C (JST)
- Guide plate A kit: JFM-GPAK-4 (JST)
- Receptacle housing: JFM2FDN-22V-K (JST)
- Receptacle contact:
  - a: SJ2F-01GF-P1.0 (JST) (0.20 ~ 0.50sq)
  - b: SJ2F-21GF-P1.0 (JST) (0.30 ~ 0.75sq)
- Manual crimp tool:
  - a: YRS-8861
  - b: YRF-1120
- Cable diameter suitable for wire-side shell:
  - JFM-WSA-4-A φ26.2~φ28.0
  - JFM-WSA-4-C φ15.5~φ16.5
- Application wiring specification
- Rated voltage Max. AC/DC 115 V
- Rated current rating Max. 1 A

(Shown pin assignment is a view from an insertion face of robot side connector.)

BJ3 side (connector)



CN61

1	2	3	4	5	6	7	8	9	10
A01	A02	A03	A04	A05	A06	A07	A08	A09	A10

CN62

1	2	3	4	5	6	7	8	9	10	11
A11	A12	A13	A14	A15	A16	A17	A18	A19	A20	ECE

CN63

1	2	3	4	5	6	7	8	9	10
A21	A22	A23	A24	A25	A26	A27	A28	A29	A30

CN64

1	2	3	4	5	6	7	8	9	10	11
A31	A32	A33	A34	A35	A36	A37	A38	A39	A40	ECE

Connector form (CN61, CN63)

Housing SMP-10V-BC (JST)

User-side Connectors

Housing SMR-10V-B (JST)

Contact SYM-001T-P0.6

(Applicable wire : AWG#22~28)

Pressure tool YRS-121

Connector form (CN62, CN64)

Housing SMP-11V-BC (JST)

User-side Connectors

Housing SMR-11V-B (JST)

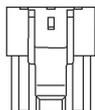
Contact SYM-001T-P0.6

(Applicable wire : AWG#22~28)

Manual crimp tool: YRS-121

■ Details of additional axis connectors (standard) [MC400L-01] [MC600-01] [MC700-01]

BJ3 side (joint connector)



3	W7	2	V7	1	U7
6	G	5	BA7	4	PB7

Connector form (CNMB7B)

Housing VLP-06V (JST)

User-side Connectors

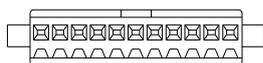
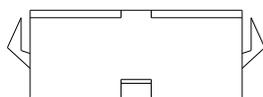
Housing VLR-06V (JST)

Retainer VLS-03V (JST)

Contact SVM-61T-P2.0

(Applicable wire: AWG#20~14)

Manual crimp tool: YC-590



1	2	3	4	5	6	7	8	9	10	11
				447	457	P5E7	M5E7	M3E7	P3E7	G

Connector form (CNE7B)

Housing SMP-11V-BC (JST)

User-side Connectors

Housing SMR-11V-B (JST)

Contact SYM-001T-P0.6

(Applicable wire: AWG#22~28)

Manual crimp tool: YRS-121

(Shown pin assignment is a view from an insertion face of robot side connector.)

■ Details of DeviceNet connectors (standard) [MC400L-01] [MC600-01] [MC700-01]

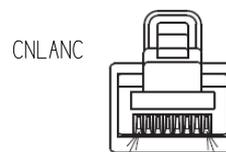


Connector  
in wiring box BJ1

Connector  
in wiring box BJ3

		CN81A	CN81C
Connector		231-635/010-DM	231-305/037/010-DM
User-side connector	Connector	231-305/037/010-DM	231-635/010-DM
	Crimp tool	231-131	
	Contact	CAN_L, CAN_H : 216-301 V-, V+ : 216-201 Drain : 216-201 Crimp tool : 206-204	

■ Details of Ethernet connectors (standard) [MC400L-01] [MC600-01] [MC700-01]

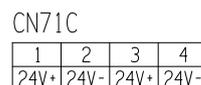


Connector  
in wiring box BJ1

Connector  
in wiring box BJ3

		CNLANA	CNLANC
Connector	RJ45 plug connector	5-569552-3	5-569552-3
User-side connector	Hood	RJ45 type connector	RJ45 type connector

■ Details of 24V power connectors (standard) [MC400L-01] [MC600-01] [MC700-01]



Connector  
in wiring box BJ1

Connector  
in wiring box BJ3

		CN71A	CN71C
Connector	Housing	VLR-04V	VLP-04V
User-side connector	Housing	VLP-04V	VLR-04V
	Contact	SVF-61T-P2.0 (0.5~2.0 mm <sup>2</sup> ) SVF-42T-P2.0 (0.3~1.25 mm <sup>2</sup> )	SVM-61T-P2.0 (0.5~2.0 mm <sup>2</sup> ) SVM-42T-P2.0 (0.3~1.25 mm <sup>2</sup> )
	Retainer	VLS-02V	
	Crimp tool	YC-590 (SV*-61T-P2.0) YC-592 (SV*-42T-P2.0)	

(Pin location shows the connector mounted on robot body and is the view from connecting side.)

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

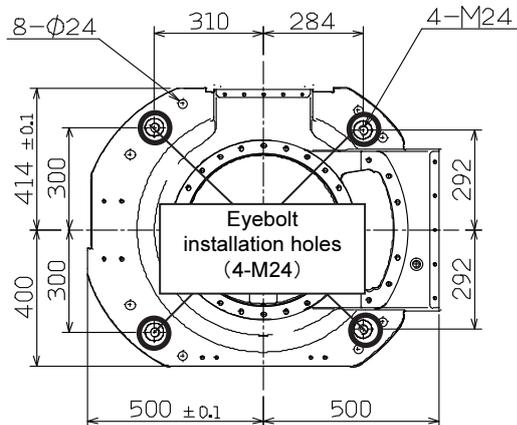
User-side connectors need to be prepared by customer.

## 9. Transport procedure

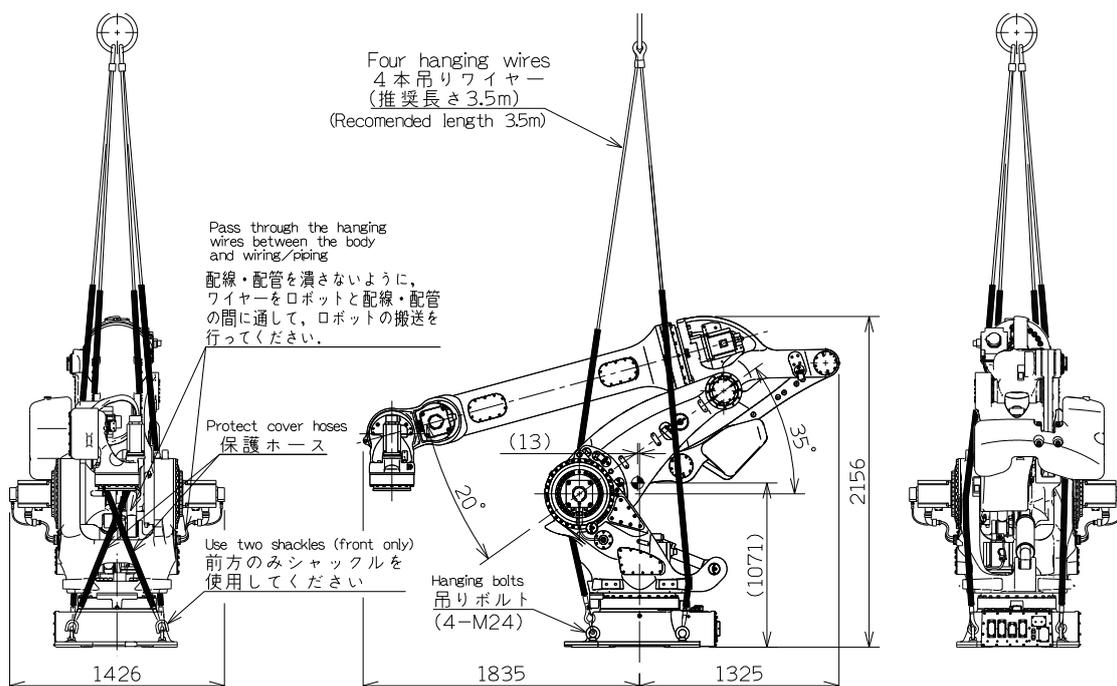
 <b>WARNING</b>	The robot must be transported by personnel who have licenses required for slinging work, crane operation, forklift truck operation, and others. The weight of the robot and controller is listed in the Operating Manual and the Maintenance Manual. Check for the weight, and then handle them according to procedures suitable for the weight.
 <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.
 <b>CAUTION</b>	If hanging wires push the encoder connectors or wiring/piping, they may be broken when hanging the robot. When hanging the robot, please pay attention not to make the wires touch the encoder connectors and wiring/piping.

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

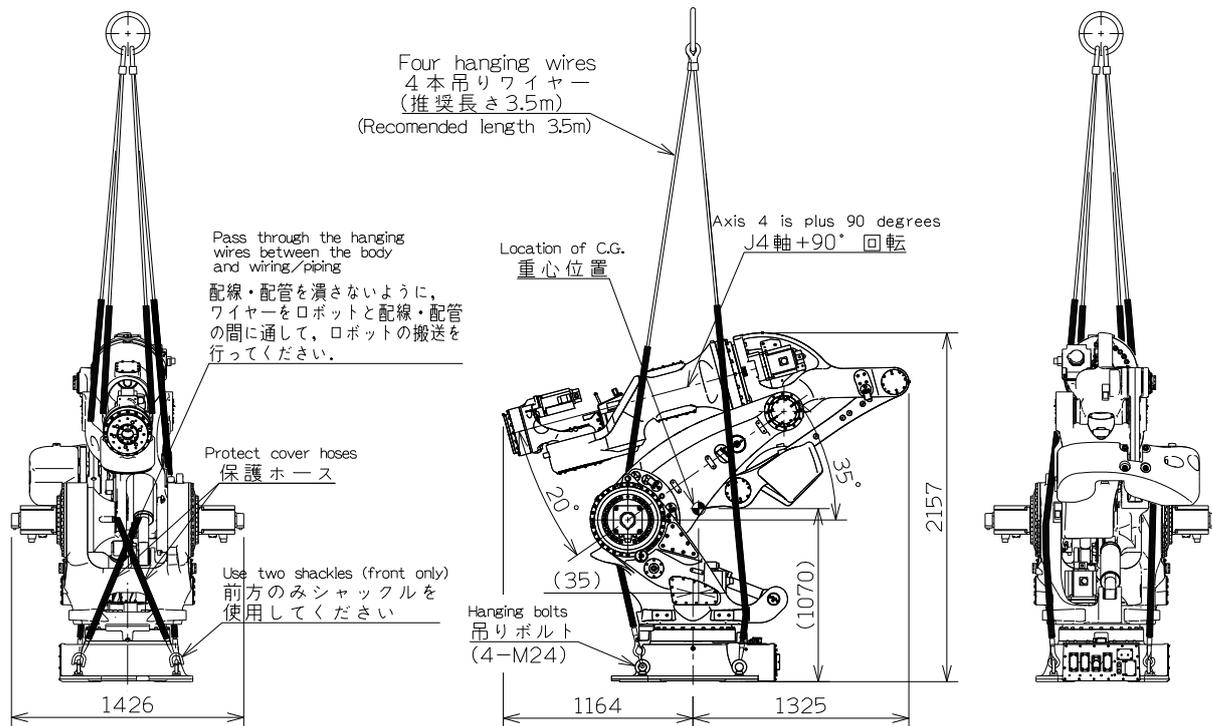
At first, put the robot into the configuration shown in figure below and mount the four M24 hanger bolts to the swivel base. Then, be sure to lift the robot using 4 hanging wires. It is recommended to use hanging wires of 3.5 m in length and protect areas that contact the robot, using rubber hoses to cover the wire ropes. For the areas to be covered with the rubber hoses refer to figure below.



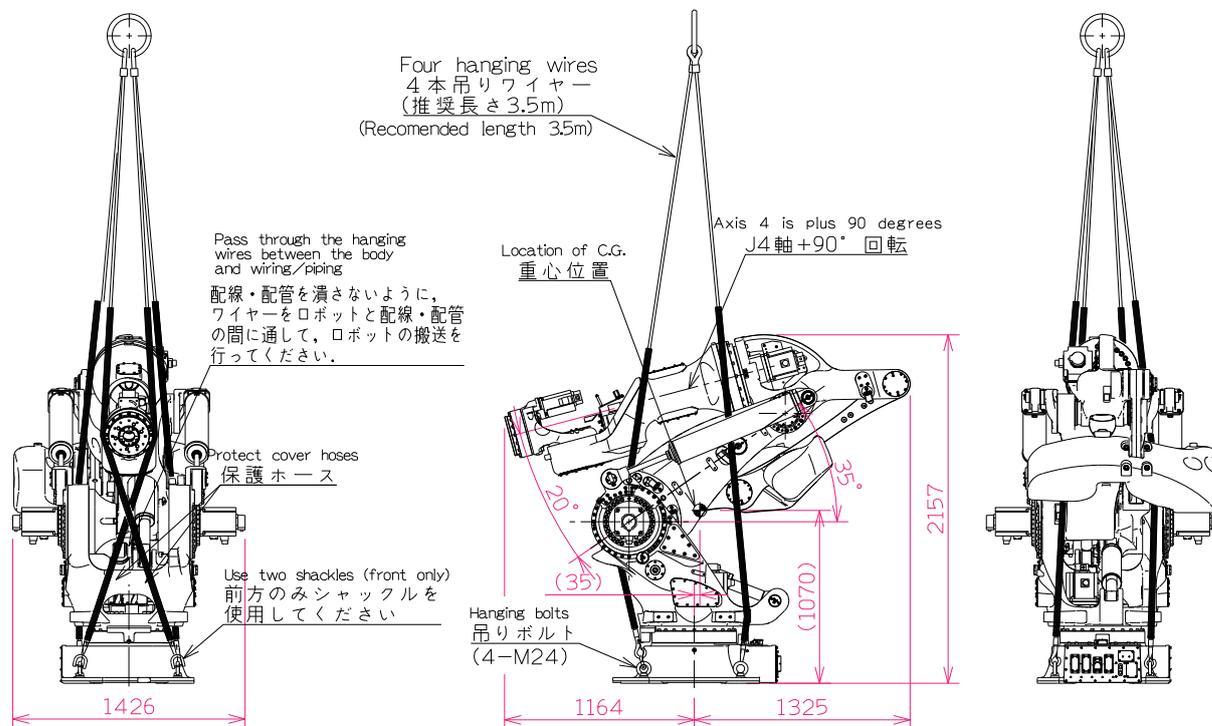
### [MC400L-01]



[MC600-01]



[MC700-01]



## 10. Delivery style (specification which contains a robot)

1. There are three styles as shown below.

	Style	Details
1	Delivery on the truck	Robot is delivered on the truck near the entrance of customer's plant. (Installation and test-run is not included)
2	Delivery after installation and test-run	Robot is installed and test-run is done. (Teaching with work piece is not included.)
3	Delivery after installation and teaching with work piece	After style 2, teaching with work piece is done.

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

2. Operation and maintenance education

The special spot operation guide and the special spot preservation guide are the outside of the estimation. Consult with each NACHI-FUJIKOSHI office for the details as for the schooling system.

## 11. Consuming power (Robot + Controller)

### [MC400L-01]

19.3 kVA at maximum, 5.8 kVA at average  
(may vary according to the application and motion pattern.)

### [MC600-01]

19.3 kVA at maximum, 5.8 kVA at average  
(may vary according to the application and motion pattern.)

### [MC700-01]

9.3 kVA at maximum, 4.2 kVA at average  
(may vary according to the application and motion pattern.)

## 12. Paint color

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

## 13. Warranty

Elapse of 1 year after delivery. (8 hours/day running)

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

<b>NACHI</b> NACHI-FUJIKOSHI CORP.		<a href="http://www.nachi-fujikoshi.co.jp/">http://www.nachi-fujikoshi.co.jp/</a>	
<b>Japan Main Office</b>	Phone: +81-3-5568-5245	Fax: +81-3-5568-5236	Shiodome Sumitomo Bldg. 17F, 1-9-2 Higashi-Shinbashi Minato-ku, TOKYO, 105-0021 JAPAN
<b>Nachi Robotic Systems Inc. (NRS)</b>		<a href="http://www.nachirobotics.com/">http://www.nachirobotics.com/</a>	
<b>North America Headquarters</b>	Phone: 248-305-6545	Fax: 248-305-6542	42775 W. 9 Mile Rd. Novi, Michigan 48375, U.S.A
<b>Indiana Service Center</b>	Phone: 248-305-6545	Fax: 248-305-6542	Greenwood, Indiana
<b>Ohio Service Center</b>	Phone: 248-305-6545	Fax: 248-305-6542	Cincinnati, Ohio
<b>South Carolina Service Center</b>	Phone: 248-305-6545	Fax: 248-305-6542	Greenville, South Carolina
<b>Canada Branch Office</b>	Phone: 905-760-9542	Fax: 905-760-9477	89 Courtland Ave., Unit No.2, Concord, Ontario, L4K 3T4, CANADA
<b>Mexico Branch Office</b>	Phone :+52-555312-6556	Fax:+52-55-5312-7248	Urbina No.54, Parque Industrial Naucalpan, Naucalpan de Juarez, Estado de Mexico C.P. 53489, MEXICO
<b>NACHI EUROPE GmbH</b>		<a href="http://www.nachi.de/">http://www.nachi.de/</a>	
<b>Central Office Germany</b>	Phone: +49-2151-65046-0	Fax: +49-2151-65046-90	Bischofstrasse 99, 47809, Krefeld, GERMANY
<b>U.K. branch</b>	Phone: +44-0121-423-5000	Fax: +44-0121-421-7520	Unit 3, 92, Kettles Wood Drive, Woodgate Business Park, Birmingham B32 3DB, U.K.
<b>Czech branch</b>	Phone: + 420-255-734-000	Fax: +420-255-734-001	Obchodni 132, 251 01 Cestlice, PRAGUE-EAST CZECH REPUBLIC
<b>Turkey branch</b>	Phone: + 90-(0)216-688-4457	Fax: +90-(0)216-688-4458	Ataturk Mah. Mustafa Kemal Cad. No:10/1A 34758 Atasehir / Istanbul - TURKEY
<b>NACHI AUSTRALIA PTY. LTD.</b>		<a href="http://www.nachi.com.au/">http://www.nachi.com.au/</a>	
<b>Robotic Division &amp; Victoria office</b>	Phone: +61-(0)3-9796-4144	Fax: +61-(0)3-9796-3899	38, Melverton Drive, Hallam, Victoria 3803, AUSTRALIA
<b>Sydney office</b>	Phone: +61-(0)2-9898-1511	Fax: +61-(0)2-9898-1678	Unit 1, 23-29 South Street, Rydalmere, N.S.W, 2116, AUSTRALIA
<b>Brisbane office</b>	Phone: +61-(0)7-3272-4714	Fax: +61-(0)7-3272-5324	7/96 Gardens Dr,Willawong,QLD 4110, AUSTRALIA
<b>NACHI SHANGHAI CO., LTD.</b>		<a href="http://www.nachi.com.cn/">http://www.nachi.com.cn/</a>	
<b>Shanghai office</b>	Phone: +86-(0)21-6915-2200	Fax: +86-(0)21-6915-2200	11F Royal Wealth Centre, No.7 Lane 98 Danba Road Putuo District, Shanghai 200062, China
<b>NACHI KOREA</b>		<a href="http://www.nachi-korea.co.kr/">http://www.nachi-korea.co.kr/</a>	
<b>Seoul office</b>	Phone: +82-(0)2-469-2254	Fax: +82-(0)2-469-2264	2F Dongsan Bldg. 276-4, Sungsu 2GA-3DONG, Sungdong-ku, Seoul 133-123, KOREA

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**Robot Division**

1-1-1, FUJIKOSHIHONMACHI, TOYAMA CITY, JAPAN 930-8511

Phone +81-76-423-5137

Fax +81-76-493-5252

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