QJAR

QJR6-3



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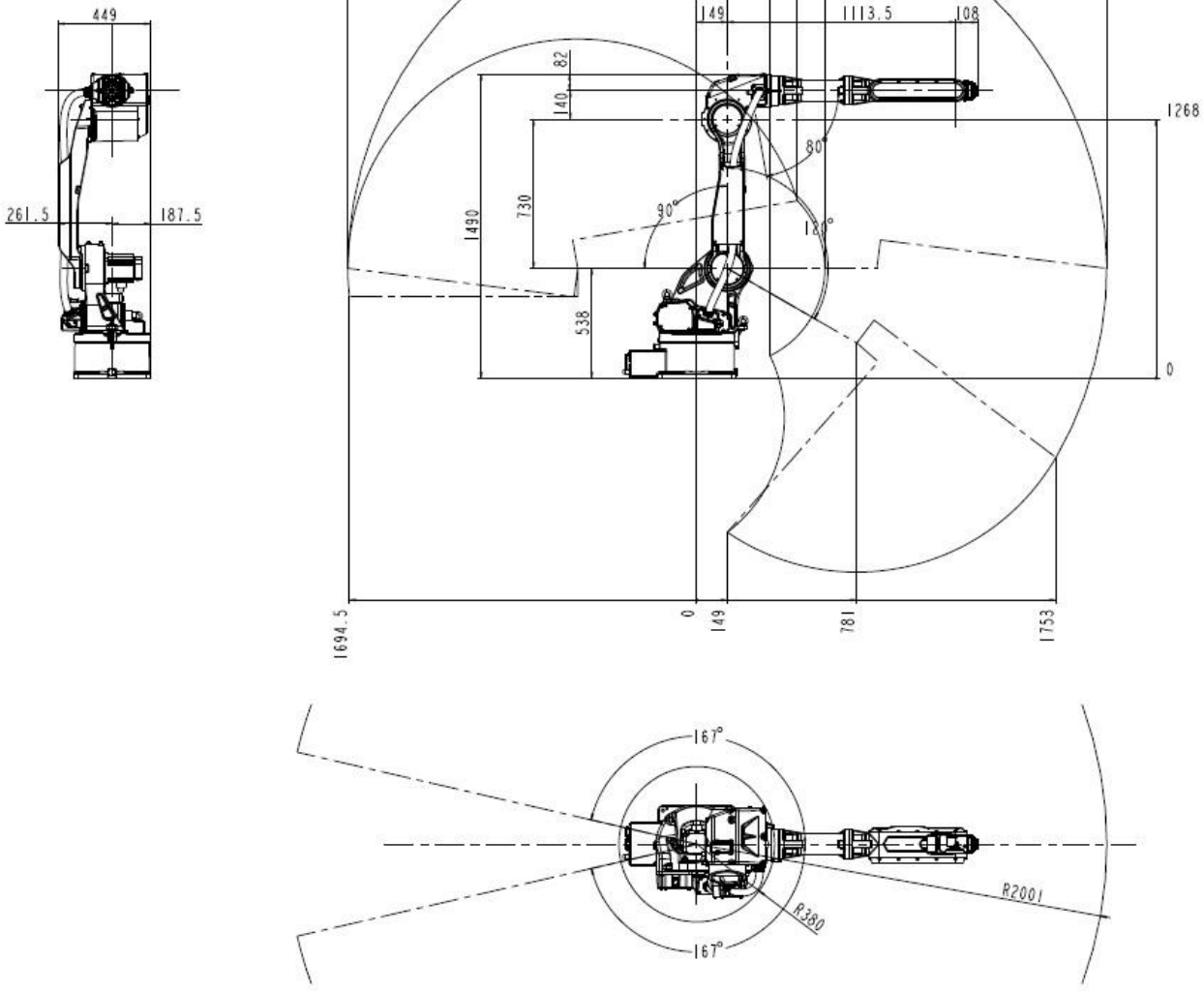
Specifications and Drawings of QJR6-3

QJR6-3 Robot basic specification table

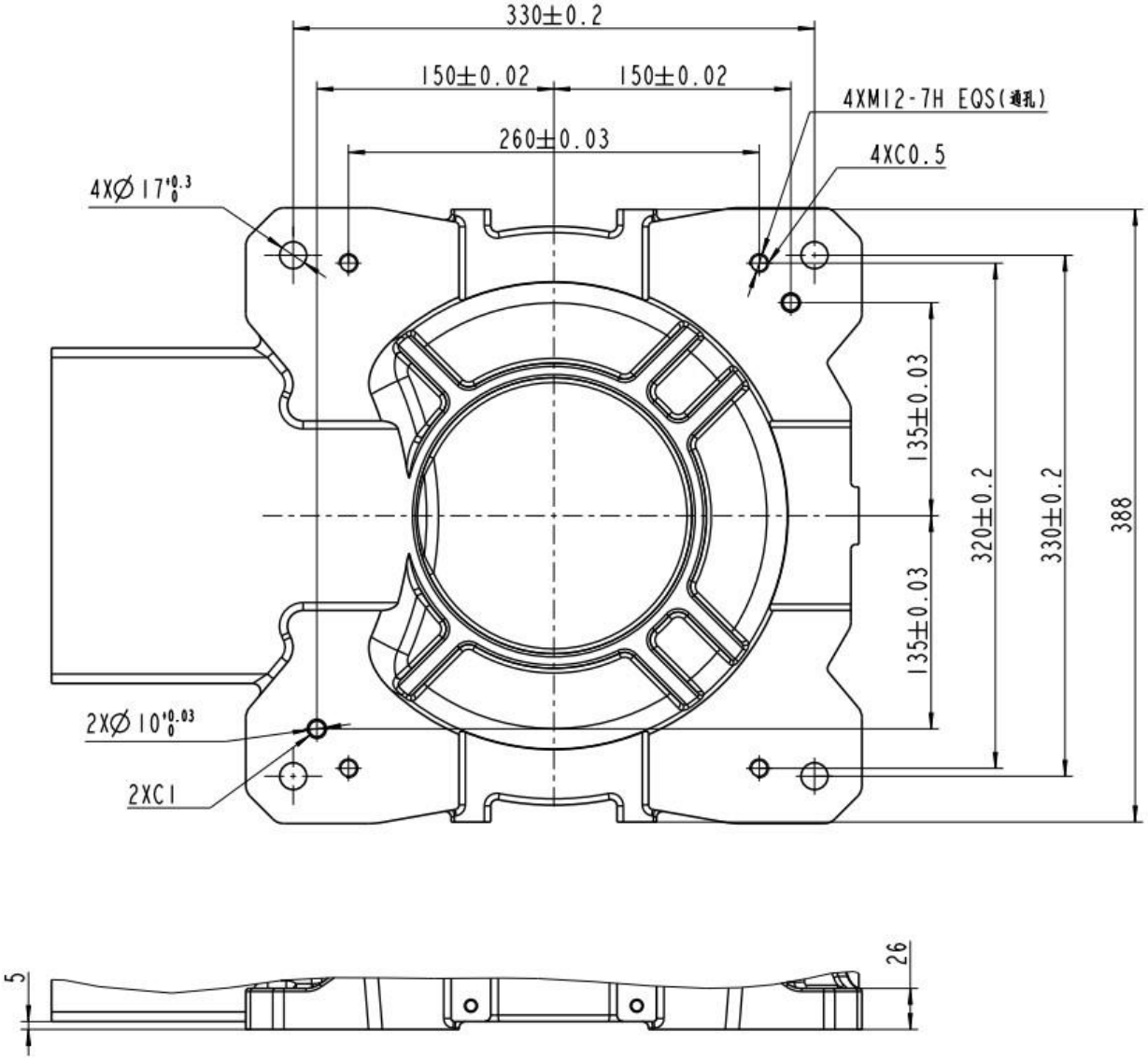
QJR6-3 Basic specification sheet			
Body shape		Vertical multiarticular	
Degrees of freedom		6	
The payload		6kg	
Arm span		2001mm	
Repeated positioning accuracy ^2		±0.05mm	
Mechanical limit range	1axis	±172°	
	2axis	+166°, -100°	
	3axis	+83°, -92°	
	4axis	±170°	
	5axis	±125°	
	6axis	±360°	
Maximum speed	1axis	3 rad/s	172.0 °/s
	2axis	3 rad/s	172.0 °/s
	3axis	3.5 rad/s	200.6 °/s
	4axis	7.5 rad/s	429.9 °/s
	5axis	7.8 rad/s	447.1 °/s
	6axis	10 rad/s	573.2 °/s
Maximum acceleration	1axis	12 rad/s2	687.9 °/s2
	2axis	10 rad/s2	573.2 °/s2
	3axis	22 rad/s2	1261.1 °/s2
	4axis	50 rad/s2	2866.2 °/s2
	5axis	50 rad/s2	2866.2 °/s2
	6axis	70 rad/s2	4012.7 °/s2
Allow the torque	4axis	8.81 N.m	
	5axis	8.81 N.m	
	6axis	3.14 N.m	
Inertia moment	4axis	0.2 kg.m2	
	5axis	0.2 kg.m2	
	6axis	0.03 kg.m2	
Body weight		225 kg	
Installation environment	temperature	0~45 ℃	
	humidity	20%~80% RH(No condensation)	
	vibration	<4.9m/s2 (0.5G)	

	other	Avoid flammable, corrosive gases and liquids; Avoid contact with water, oil, dust, etc. Keep away from electrical noise sources.
The power capacity		3.8kVA

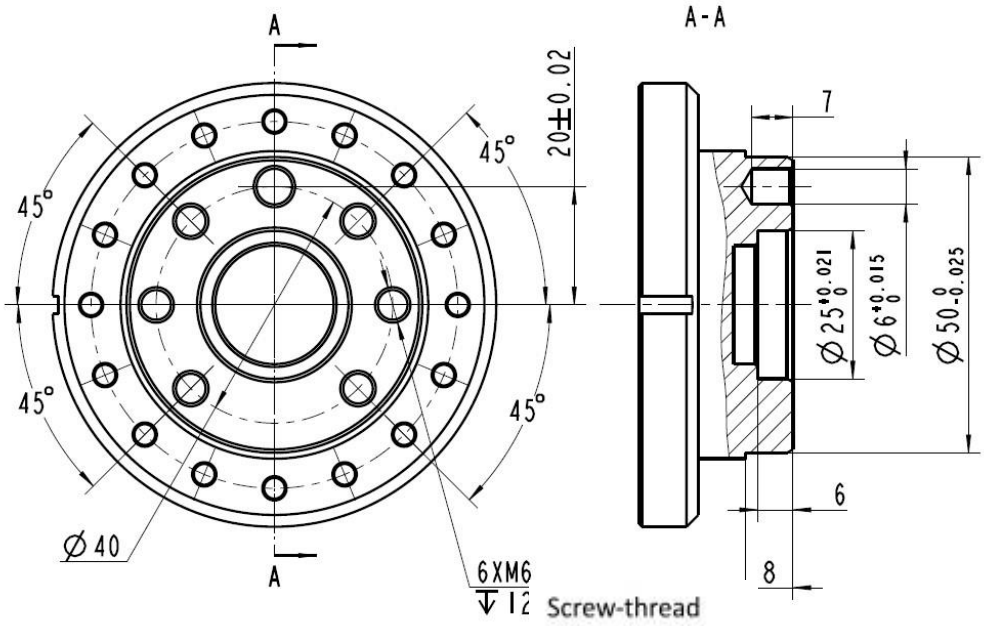
QJR6-3 Diagram of the robot's overall size and maximum motion range


449
261.5
187.5
1703
0
149
358
491
625
2001
149
1113.5
108
82
140
1268
80°
90°
180°
730
1490
538
0
1694.5
0
149
781
1753
167°
167°
R380
R2001

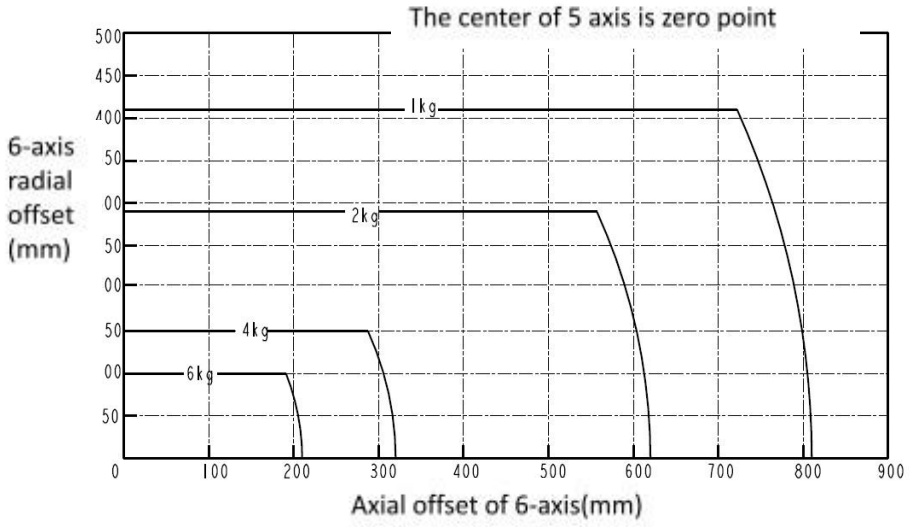
III. QJR6-3 Robot base mounting dimension drawing



IV. QJR6-3 Installation dimension drawing of robot end

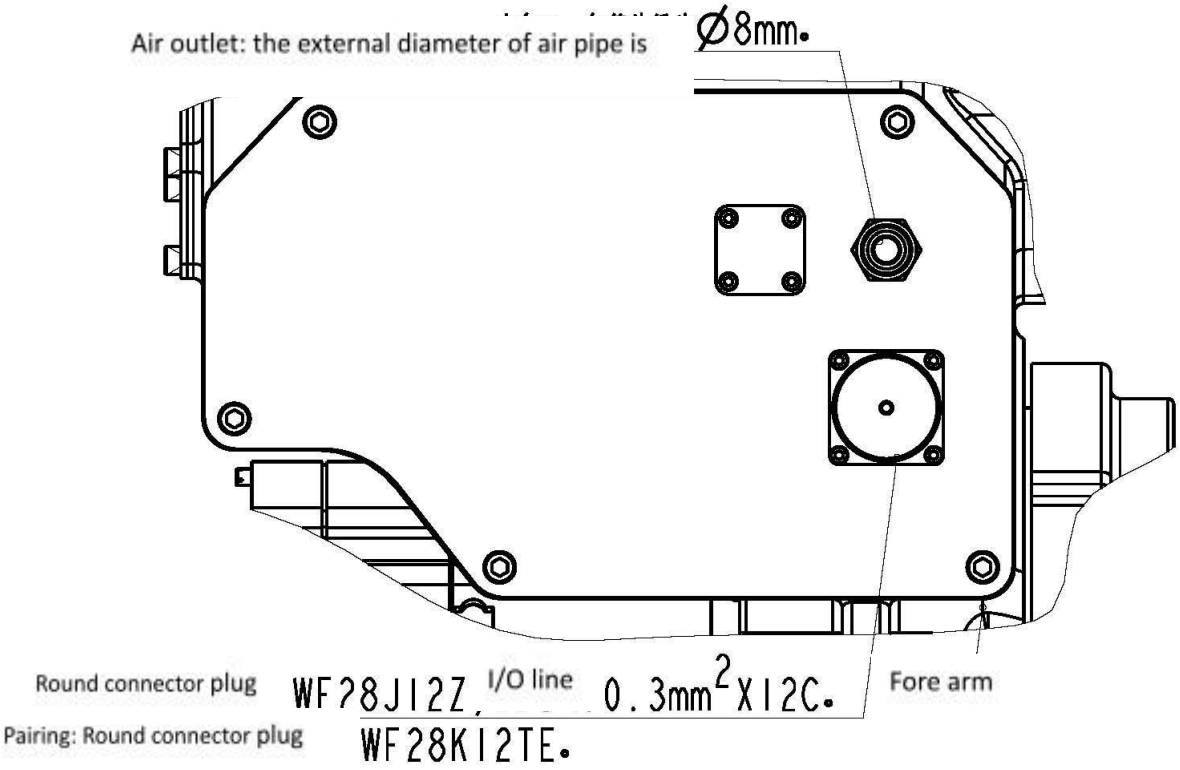


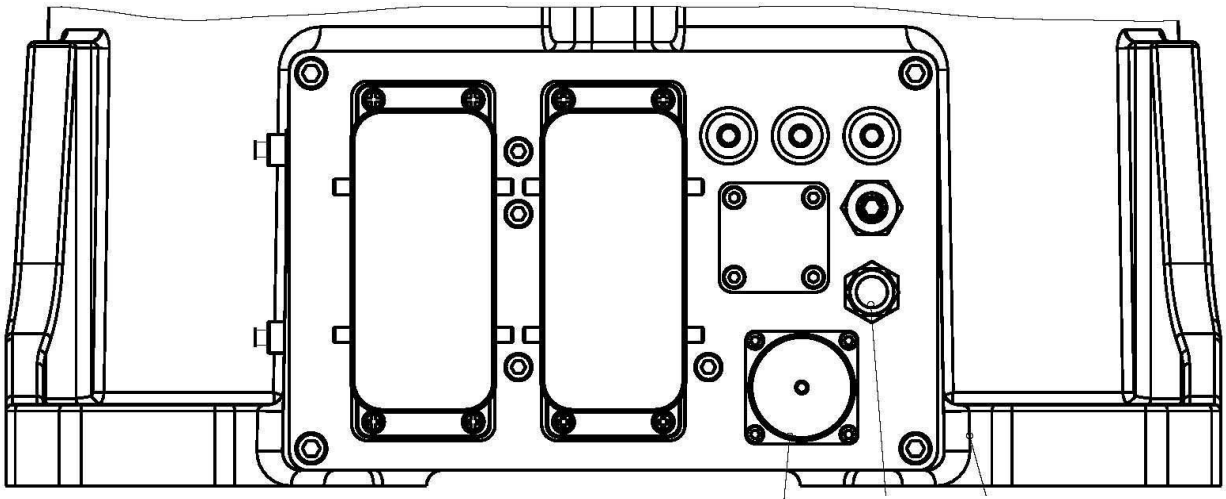
V. QJR6-3 Robot Load Chart



VI. Schematic diagram of robot reserved gas path and I / O interfaceposition

1. Non-welded condition:





Round connector plug **WF28JI2Z-3, I/O line:0.3mm²×12C**
Pairing: Round connector plug **WF28KI2TE-3**,
10A cold pressing female **YK1.5-20.4-1.OAU**
（1.OAU is optional according to the need）
explain:
The base and the fore arm position circular connector plug are connected in the same position

Base
Air outlet: the external diameter of air pipe is **φ8mm**

2. Welded condition

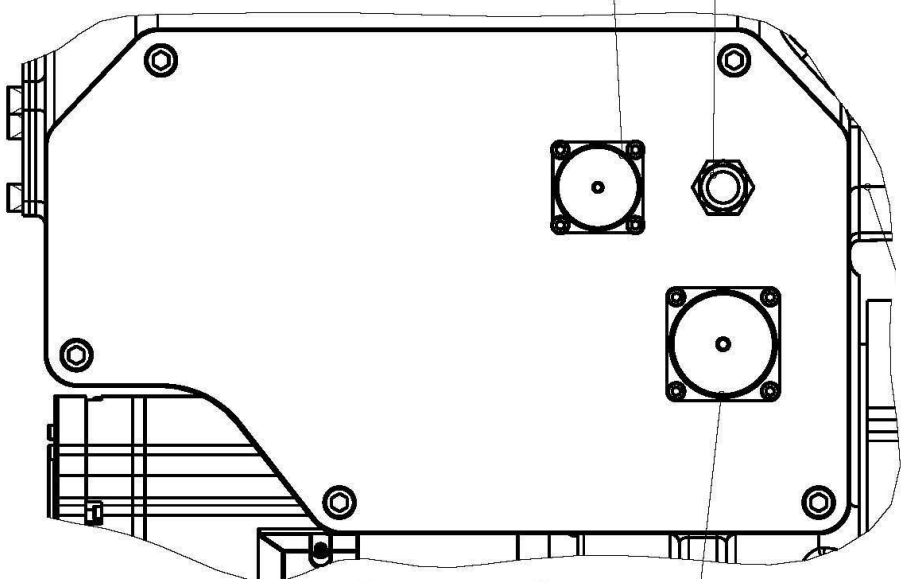
Anti collision line : 0.3mm²×4C

Round connector plug WFI6K4Z

撞线：0.3mm²X4C。

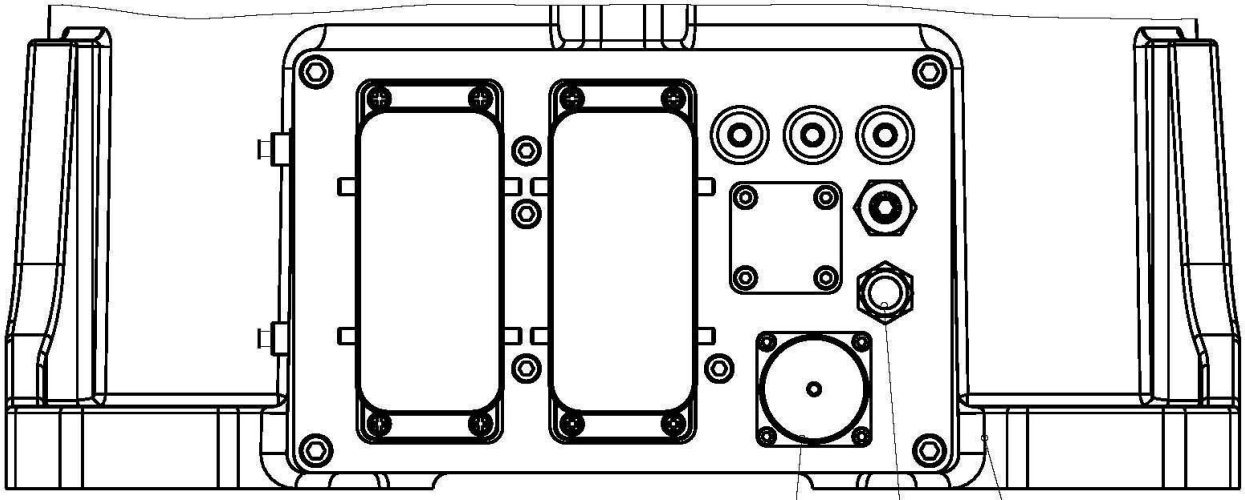
Air outlet: the diameter of air pipe is : φ8mm

Pairing: Round connector plug WFI6J4TE



Round connector plug WF28JI2Z I/O line 0.3mm²×12C.

Pairing : round connector plug WF28KI2TE



Round connector plug WF28JI2Z-3, I/O line : 0.3mm²×12C

Pairing: Round connector plug WF28KI2TE-3,

10A cold pressing female YK1.5-20.4-1.OAU

（1.OAU is optional according to the need）

explain:

The base and the fore arm position circular connector plug are connected in the same position.

Air inlet: the external diameter of air pipe is φ8mm

VII. QJR6-3 Configuration table of robot products

QJR6-3 Configuration table of robot products	
Motor	TAMAGAWA/Ruking
RV Reducer	Nabotesco/Domestic reducer
Harmonic reducer	Shimpo
Controller	QJAR
Drive	Tsino dynatron/Ruking

VIII. QJR6-3 Controller cabinet

QJR6-3 controller cabinet	
Control hardware	QJAR controller (version R5 IO board)
Control cabinet software	QJAR system
Power Supply	Three phase four wire AC380V (+ 10%, - 10%)
Rated power	6.2KW
Power capacity	3.8KVA
Size of control cabinet	580x600x960mm
Weight of control cabinet	130kg
ambient temperature	0-45℃
Maximum humidity	20%~80% RH (no condensation)
Protection level	IP21
operation panel	On the control cabinet

Programming unit	Color touch screen teaching box
Security	Emergency stop, automatic mode stop, remote mode stop
Input and output	Digital IO 7 input 13 output, analog 2 output