

RHCH Series

Part Number Configuration

RH 1 CH 2 3 1D1 4

Must select items 1–4.

1 Max Load Capacity

Symbol	Maximum Load Capacity
3	3kg
6	6kg

2 Arm Length

Symbol	Arm Length/Option
40	400mm (3kg only)
60	600mm (6kg only)
70	700mm (6kg only)

3 Vertical Stroke

Symbol	Vertical Stroke
18	180 mm stroke (3kg only)
20	200 mm stroke (6kg only)

4 Select only one from table below:

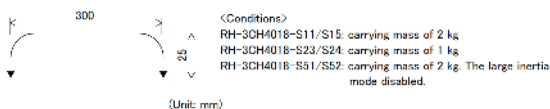
S	Compliance Specification
15	CE
24	CE with J3 bellows
52	CE with 5kg payload (3kg only)

RH3CH

Model Number	RH3CH4018S15	RH3CH4018S24	RH3CH4018S52	
Environment	Standard specification			
Protection Degree (*7)	IP20			
Mounting Position	Floor type			
Structure	Horizontal, multiple-joint type			
Degree of Freedom	4 axis			
Drive System	AC servo motor			
Position Detection Method	Absolute encoder			
Load Rating (kg) N	1			
Maximum Payload (Rated) kg (N)	3	3	5	
Motor Capacity (W)	J1	200		
	J2	100		
	J3	100		
	J4	100		
Brake	J1, J2, J4 axes: no brake; J3 axis: with brake		J1, J2 axes: no brake; J3, J4 axes: with brake	
Arm Length (mm)	N01 Arm	225		
	N02 Arm	175		
Maximum Reach Radius (N01+ N02) (mm)	400			
Operating Range (deg)	J1	264(±132)		
	J2	282(±141)		
	J3	180	130	180
	J4	720(±360)		
Maximum Speed (deg/sec) (*1)	J1	720		
	J2	720		
	J3 mm/sec	1100		
	J4	2600		
	J1+J2 mm/sec	7200		
Cycle Time (*3)	0.44			
Position Repeatability (mm) (*2)	X-Y Direction	±0.01		
	J3 (Z)	±0.01		
	J4 (Ø) Deg	±0.01		
Ambient Temperature (°C) (*8)	0 to 40			
Weight (kg)	14			
Allowable Inertia (kg • m ²) (*4)	Rating	0.005		
	Maximum	0.05; (0.075)		
J3(Z) Axis Pressing Force (N) (*5)	100			
Maximum Eccentricity (During the Large Inertia Mode (mm) (*6)	150 (10)			
Tool Wiring	15 points, D-SUB			
Tool Pneumatic Pipes	ø6 × 2, ø4 × 1			
Supply Pressure (MPa)	0.5 ±10%			
Machine Cable	5			
Connection Controller	CR751-D			

Notes:

- The maximum speed is the value which applied MvTune2 (high-speed movement mode).
- Pose repeatability details can be found in the product manual.
- The value with the movements and conditions below when the MvTune2 (high-speed movement mode) is applied.



- The values in parentheses are the values when the large inertia mode is enabled.
- When the maximum load is installed, the downward pushing force generated at the tip of the load is obtained with J1, J2, and J4 axes stopped. The force shown above is the maximum value. When the force is applied for a long time, an overload error will be generated.
- The values in parentheses are the values when the large inertia mode is enabled.
- The protection specification details can be found in the product manual.
- Sets the robot's operating environmental temperature as parameter OLTMX. Corresponding to the environment, the continuous control action performance and the overload-protection function are optimized. (Refers to product manual for details.)

RH6CH

Model Number	RH6CH6020S15		RH6CH6020S24		RH6CH7020S15		RH6CH7020S24		
Environment	Standard specification								
Protection Degree (*7)	IP20								
Mounting Position	Floor type								
Structure	Horizontal, multiple-joint type								
Degree of Freedom	4								
Drive System	AC servo motor								
Position Detection Method	Absolute encoder								
Load Rating kg (N)	2								
Maximum Payload (Rated) kg (N)	6								
Motor Capacity (W)	J1	200							
	J2	200							
	J3	100							
	J4	100							
Brake	J1, J2 axes: no brake; J3, J4 axes: with brake								
Arm Length (mm)	N01 Arm	325				425			
	N02 Arm	275							
Maximum Reach Radius (N01+ N02) (mm)	600				700				
Operating Range (deg)	J1	264 (±132)							
	J2	300 (±150)							
	J3	200		172		200		172	
	J4	720 (±360)							
Maximum Speed (deg/sec) (*1)	J1	420				360			
	J2	720							
	J3 mm/sec	1100							
	J4	2500							
Cycle Time (*3)	J1+J2 mm/sec	7800							
		0.41				0.43			
Position Repeatability (mm) (*2)	X-Y Direction	±0.02							
	J3 (Z)	±0.01							
	J4 (Ø) Deg	±0.01							
Ambient Temperature (°C) (*8)	0 to 40								
Weight (kg)	17				18				
Allowable Inertia (kg • m ²) (*4)	Rating	0.01							
	Maximum	0.12 (0.18)							
J3(Z) Axis Pressing Force (N) (*5)	100								
Maximum Eccentricity (During the Large Inertia Mode) (mm) (*6)	150 (10)								
Tool Wiring	15 points, D-SUB								
Tool Pneumatic Pipes	ø6 × 2, ø4 × 1								
Supply Pressure (MPa)	0.5 ±10%								
Machine Cable	5								
Connection Controller	CR751-D								

Notes:

- The maximum speed is the value which applied MvTune2 (high-speed movement mode).
- Pose repeatability details can be found in the product manual.
- The value with the movements and conditions below when the MvTune2 (high-speed movement mode) is applied.



- The values in parentheses are the values when the large inertia mode is enabled.
- When the maximum load is installed, the downward pushing force generated at the tip of the load is obtained with J1, J2, and J4 axes stopped. The force shown above is the maximum value. When the force is applied for a long time, an overload error will be generated.
- The values in parentheses are the values when the large inertia mode is enabled.
- The protection specification details can be found in the product manual.
- Sets the robot's operating environmental temperature as parameter OLTMX. Corresponding to the environment, the continuous control action performance and the overload-protection function are optimized. (Refers to "product manual for details.")