

Kawasaki Robot Lineup



Our Product Philosophy is “Simple and friendly”

With more than 50 years experience in industrial robotics, we have consolidated our "state-of-the-art" technologies into productivity enhancing flexible automation solutions that are simple and friendly. Our product lineup offers comprehensive functionality with operational ease of use.

Kawasaki began the manufacture and sales of industrial robots in 1969. Since that time, we have consistently produced high quality, cost effective industrial robots featuring state-of-the-art technology for both the domestic and overseas markets.

Our broad product portfolio services a wide range of applications across diverse industries; from the assembly of miniature components weighing only a few grams, to the material handling of castings weighing 1.500 kg. For optimum control of the manipulator, our high-performance lineup is supported by our continuous development of control technology to improve function and operation.

Our human and environmentally friendly robot systems provide a high level of skill and intelligence. We hope that you will benefit from our technology and experience in your future automation projects to increase production, lower costs and improve quality.



■ Small-to-medium payload robots
R series

■ Medium payload robots
CX series

■ Medium payload robots
Z series

■ Extra large payload robots
M series

■ Spot welding robots
B series

■ Arc welding robots
RA/BA series



■ Painting robots
Explosion-proof
K series

■ Palletizing robots
RD/CP/MD/ZD

■ Dual-arm SCARA Robot
duAro

■ Pick & Place robots
Y series

■ Clean robots
NT/NTS series

■ Medical & pharmaceutical robots
MS/MC series

Small-to-medium payload robots up to 80 kg

R series

Setting the benchmark in its class – higher speed and longer reach in a compact design.



RS020N

| | | RS003N | RS005N/005L | RS007N/007L | RS006L/010N | RS015X | RS010L/020N | RS030N/050N/080N |
|--------------------------|--------------------|--------------------------------|-------------|-------------|-------------|-------------|-------------|------------------|
| Application | | ●●●●●●●● | | ●●●●●●●●●● | | ●●●●●●●● | ●●●●●●●●●● | ●●●●●●●● |
| Degree of freedom (axes) | | 6 | | | | | | |
| Max. payload (kg) | | 3 | 5 | 7 | 6/10 | 15 | 10/20 | 30/50/80 |
| Max. reach (mm) | | 620 | 705/903 | 730/930 | 1.650/1.450 | 3.150 | 1.925/1.725 | 2.100 |
| Repeatability *1 (mm) | | ±0,02 | ±0,02/±0,03 | ±0,02/±0,03 | ±0,03 | ±0,06 | ±0,05/±0,04 | ±0,06 |
| Motion range (°) | Arm rotation (JT1) | ±160 | ±180 | ±180 | ±180 | ±180 | ±180 | ±180 |
| | Arm out-in (JT2) | +150 - -60 | +135 - -80 | ±135 | +145 - -105 | +140 - -105 | +155 - -105 | +140 - -105 |
| | Arm up-down (JT3) | +120 - -150 | +118 - -172 | ±155/±157 | +150 - -163 | +135 - -155 | +150 - -163 | +135 - -155 |
| | Wrist swivel (JT4) | ±360 | ±360 | ±200 | ±270 | ±360 | ±270 | ±360 |
| | Wrist bend (JT5) | ±135 | ±145 | ±125 | ±145 | ±145 | ±145 | ±145 |
| | Wrist twist (JT6) | ±360 | ±360 | ±360 | ±360 | ±360 | ±360 | ±360 |
| Max. speed (°/s) | Arm rotation (JT1) | 360 | 360/300 | 470/370 | 250 | 180 | 190 | 180 |
| | Arm out-in (JT2) | 250 | 360/300 | 380/310 | 250 | 180 | 205 | 180 |
| | Arm up-down (JT3) | 225 | 410/300 | 520/410 | 215 | 200 | 210 | 185/185/160 |
| | Wrist swivel (JT4) | 540 | 460 | 550 | 365 | 410 | 400 | 260/260/185 |
| | Wrist bend (JT5) | 225 | 460 | 550 | 380 | 360 | 360 | 260/260/165 |
| | Wrist twist (JT6) | 540 | 740 | 1.000 | 700 | 610 | 610 | 360/360/280 |
| Mass (kg) | | 20 | 34/37 | 35/36 | 150 | 545 | 230 | 555 |
| Installation | | Floor, Ceiling, Optional: Wall | | | | | | |
| Controller | | F60 | | | E01/F60 | E02 | E01 | E02 |

*1: conforms to ISO9283
Application: ● Assembly ● Dispensing ● Machine tending ● Material handling ● Material removal ● Palletizing ● Arc welding

Medium payload robots up to 210 kg

CX series

Kawasaki's latest technology delivers increased robot motion speed and installation flexibility.



CX210L

| | | CX110L | CX165L | CX210L |
|--------------------------|--------------------|-----------|-----------|-----------|
| Application | | | ●●●● | |
| Degree of freedom (axes) | | 6 | | |
| Max. payload (kg) | | 110 | 165 | 210 |
| Max. reach (mm) | | 2.699 | 2.699 | 2.699 |
| Repeatability *1 (mm) | | ±0,06 | ±0,06 | ±0,06 |
| Motion range (°) | Arm rotation (JT1) | ±160 | ±160 | ±160 |
| | Arm out-in (JT2) | +80 - -60 | +80 - -60 | +80 - -60 |
| | Arm up-down (JT3) | +95 - -75 | +95 - -75 | +95 - -75 |
| | Wrist swivel (JT4) | ±210 | ±210 | ±210 |
| | Wrist bend (JT5) | ±120 | ±120 | ±120 |
| | Wrist twist (JT6) | ±360 | ±360 | ±360 |
| Max. speed (°/s) | Arm rotation (JT1) | 140 | 130 | 125 |
| | Arm out-in (JT2) | 135 | 125 | 115 |
| | Arm up-down (JT3) | 135 | 125 | 115 |
| | Wrist swivel (JT4) | 200 | 180 | 155 |
| | Wrist bend (JT5) | 200 | 180 | 160 |
| | Wrist twist (JT6) | 300 | 280 | 220 |
| Mass (kg) | | 870 | 870 | 870 |
| Installation | | Floor | | |
| Controller | | E02 | | |

*1: conforms to ISO9283
Application: ● Assembly ● Material handling ● Palletizing ● Spot welding












Medium payload robots up to 300 kg

Z series

Robust low-maintenance design with wide work envelope provides application flexibility.



ZX165U

| | | ZX130S/130L/165U/200S/300S | ZH100U | ZT130S/165U/200S | ZT130Y/165X/165Y |
|--------------------------|--------------------|---|---|---|-------------------|
| Application | |     |    |     | |
| Degree of freedom (axes) | | 6 | | | |
| Max. payload (kg) | | 130/130/165/200/300 | 100 | 130/165/200 | 130/165/165 |
| Max. reach (mm) | | 2.651/2.951/2.651/2.651/2.501 | 1.634 | 3.230 | 3.130/2.830/3.130 |
| Repeatability *1 (mm) | | ±0,3 | ±0,3 | ±0,3 | ±0,3 |
| Motion range (°) | Arm rotation (JT1) | ±180 | ±160 | ±180 | ±180 |
| | Arm out-in (JT2) | +75 - -60 | +120 - -60 | +60 - -75 | +50 - -120 |
| | Arm up-down (JT3) | +250 - -120 | +75 - -90 | +165 - -95 | +150 - -65 |
| | Wrist swivel (JT4) | ±360 | ±360 | ±360 | ±360 |
| | Wrist bend (JT5) | ±130/±130/±130/±130/±130 | ±130 | ±130/±130/±120 | ±130 |
| | Wrist twist (JT6) | ±360 | ±360 | ±360 | ±360 |
| Max. speed (°/s) | Arm rotation (JT1) | 130/110/110/105/100 | 140 | 130/105/100 | 120/120/105 |
| | Arm out-in (JT2) | 130/110/110/110/85 | 100 | 130/105/100 | 110/110/105 |
| | Arm up-down (JT3) | 130/110/115/105/85 | 100 | 130/105/90 | 115/115/100 |
| | Wrist swivel (JT4) | 180/140/140/120/90 | 150 | 180/135/120 | 160/140/140 |
| | Wrist bend (JT5) | 180/135/155/120/90 | 150 | 180/135/115 | 180/155/155 |
| | Wrist twist (JT6) | 280/230/260/200/150 | 250 | 280/210/180 | 280/260/260 |
| Mass (kg) | | 1.350/1.400/1.350/1.400/1.400 | 750 | 1.550/1.550/1.600 | 1.665/1.650/1.665 |
| Installation | | Floor | | Shelf | |
| Controller | | E02 | | | |

*1: conforms to ISO9283
Application: ● Assembly ● Material handling ● Palletizing ● Spot welding

Extra large payload robots up to 1.500 kg

M series

Achieves high wrist torque and payload capacity without any counterweights for a wide motion range and compact footprint.



MG15HL

| | | MX350L | MX420L | MX500N | MX700N | MT400N | MG10HL | MG15HL |
|--------------------------|--------------------|------------|------------|------------|------------|------------|------------|--------------|
| Application | | ●● | | | | | | |
| Degree of freedom (axes) | | 6 | | | | | | |
| Max. payload (kg) | | 350 | 420 | 500 | 700 | 400 | 1.000 | 1.500 |
| Max. reach (mm) | | 3.018 | 2.778 | 2.540 | 2.540 | 3.503 | 4.005 | 4.005 |
| Repeatability *1 (mm) | | ±0,5 | ±0,5 | ±0,5 | ±0,5 | ±0,5 | ±0,1 | ±0,1 |
| Motion range (°) | Arm rotation (JT1) | ±180 | ±180 | ±180 | ±180 | ±180 | ±150 | ±150 |
| | Arm out-in (JT2) | +90 - -45 | +90 - -45 | +90 - -45 | +90 - -45 | +15 - -135 | +90 - -40 | +90 - -40 |
| | Arm up-down (JT3) | +20 - -115 | +20 - -125 | +20 - -130 | +20 - -130 | +106 - -30 | +30 - -110 | +30*2 - -110 |
| | Wrist swivel (JT4) | ±360 | ±360 | ±360 | ±360 | ±360 | ±360 | ±360 |
| | Wrist bend (JT5) | ±110 | ±110 | ±110 | ±110 | ±120 | ±120 | ±120 |
| | Wrist twist (JT6) | ±360 | ±360 | ±360 | ±360 | ±360 | ±360 | ±360 |
| Max. speed (°/s) | Arm rotation (JT1) | 80 | 80 | 80 | 65 | 80 | 65 | 65 |
| | Arm out-in (JT2) | 70 | 70 | 70 | 50 | 70 | 33.5 | 33.5 |
| | Arm up-down (JT3) | 70 | 70 | 70 | 45 | 70 | 37.5 | 37.5 |
| | Wrist swivel (JT4) | 80 | 80 | 80 | 50 | 70 | 65 | 36 |
| | Wrist bend (JT5) | 80 | 80 | 80 | 50 | 70 | 65 | 36 |
| | Wrist twist (JT6) | 120 | 120 | 120 | 95 | 130 | 80 | 80 |
| Mass (kg) | | 2.800 | 2.800 | 2.750 | 2.860 | 2.600 | 6.500 | 6.550 |
| Installation | | Floor | | | | Shelf | Floor | |
| Controller | | E04 | | | | E02 | E58 | |

*1: conforms to ISO9283 *2: depends on payload
Application: ● Machine tending ● Material handling

Spot welding robots

B series

High speed spot welding with greater spot control. Space saving design supports “high density” applications.



BX200L

| | | BX100S | BX100N | BX100L/165L/200L | BX130X/BX200X | BX165N | BX250L/300L | BT165L/BT200L |
|--------------------------|--------------------|------------|------------|------------------|----------------------|-----------|-------------|---------------|
| Application | | ● | | | | | | |
| Degree of freedom (axes) | | 6 | | | | | | |
| Max. payload (kg) | | 100 | 100 | 100/165/200 | 130/200 | 165 | 250/300 | 165/200 |
| Max. reach (mm) | | 1.634 | 2.200 | 2.597 | 2.991/3.412 | 2.325 | 2.812 | 3.151 |
| Repeatability *1 (mm) | | ±0,06 | ±0,06 | ±0,06 | ±0,06/±0,07 | ±0,06 | ±0,07 | ±0,08 |
| Motion range (°) | Arm rotation (JT1) | ±160 | ±160 | ±160 | ±160/±180 | ±160 | ±180 | ±160 |
| | Arm out-in (JT2) | +120 - -65 | +120 - -65 | +76 - -60 | +76 - -60 | +76 - -60 | +76 - -60 | +80 - -130 |
| | Arm up-down (JT3) | +90 - -81 | +90 - -77 | +90 - -75 | +90 - -75/+90 - -110 | +90 - -75 | +90 - -120 | +90 - -75 |
| | Wrist swivel (JT4) | ±210 | ±210 | ±210 | ±210 | ±210 | ±210 | ±210 |
| | Wrist bend (JT5) | ±125 | ±125 | ±125 | ±125 | ±125 | ±125 | ±125 |
| | Wrist twist (JT6) | ±210 | ±210 | ±210 | ±210 | ±210 | ±210 | ±210 |
| Max. speed (°/s) | Arm rotation (JT1) | 135 | 135 | 105/120/105 | 105/125 | 105 | 125 | 120/105 |
| | Arm out-in (JT2) | 125 | 110 | 130/110/90 | 90/102 | 130 | 120/102 | 110/85 |
| | Arm up-down (JT3) | 155 | 140 | 130/130/100 | 130/85 | 130 | 100/85 | 130/100 |
| | Wrist swivel (JT4) | 200 | 200 | 200/170/120 | 200/105 | 120 | 140/105 | 170/120 |
| | Wrist bend (JT5) | 160 | 200 | 160/170/120 | 160/120 | 160 | 140/110 | 170/120 |
| | Wrist twist (JT6) | 300 | 300 | 300/280/200 | 300/200 | 300 | 200/180 | 280/200 |
| Mass (kg) | | 720 | 740 | 890 | 920/1.450 | 875 | 1.460 | 1.100 |
| Installation | | Floor | | | | | | Shelf |
| Controller | | E02 | | | | | | |

*1: conforms to ISO9283
Application: ● Spot welding

Arc welding robots

BA/RA series

Kawasaki robots use the latest arc welding technology to rival the quality of a skilled human welder.



BA006N

| | | BA006N | BA006L | RA005L | RA006L | RA010N | RA010L | RA020N |
|--------------------------|--------------------|----------------|------------|-------------|-------------|-------------|-------------|-------------|
| Application | | ● | | | | | | |
| Degree of freedom (axes) | | 6 | | | | | | |
| Max. payload (kg) | | 6 | 6 | 5 | 6 | 10 | 10 | 20 |
| Max. reach (mm) | | 1.445 | 2.036 | 903 | 1.650 | 1.450 | 1.925 | 1.725 |
| Repeatability *1 (mm) | | ±0,06 | ±0,08 | ±0,03 | ±0,03 | ±0,03 | ±0,05 | ±0,04 |
| Motion range (°) | Arm rotation (JT1) | ±165 | ±165 | ±180 | ±180 | ±180 | ±180 | ±180 |
| | Arm out-in (JT2) | +150 - -90 | +150 - -90 | +135 - -80 | +145 - -105 | +145 - -105 | +155 - -105 | +155 - -105 |
| | Arm up-down (JT3) | +90 - -175 | +90 - -175 | +118 - -172 | +150 - -163 | +150 - -163 | +150 - -163 | +150 - -163 |
| | Wrist swivel (JT4) | ±180 | ±180 | ±360 | ±270 | ±270 | ±270 | ±270 |
| | Wrist bend (JT5) | ±135 | ±135 | ±145 | ±145 | ±145 | ±145 | ±145 |
| | Wrist twist (JT6) | ±360 | ±360 | ±360 | ±360 | ±360 | ±360 | ±360 |
| Max. speed (°/s) | Arm rotation (JT1) | 240 | 210 | 300 | 250 | 250 | 190 | 190 |
| | Arm out-in (JT2) | 240 | 210 | 300 | 250 | 250 | 205 | 205 |
| | Arm up-down (JT3) | 220 | 220 | 300 | 215 | 215 | 210 | 210 |
| | Wrist swivel (JT4) | 430 | 430 | 460 | 365 | 365 | 400 | 400 |
| | Wrist bend (JT5) | 430 | 430 | 460 | 380 | 380 | 360 | 360 |
| | Wrist twist (JT6) | 650 | 650 | 740 | 700 | 700 | 610 | 610 |
| Mass (kg) | | 150 | 160 | 37 | 150 | 150 | 230 | 230 |
| Installation | | Floor, Ceiling | | | | | | |
| Controller | | E01/F60 | | F60 | E01/F60 | | E01 | |

*1: conforms to ISO9283
Application: ● Arc welding

Painting robots

K series

The optimum wrist configuration and model can be selected according to the workpiece.
Servo controlled part positioning equipment available (explosion proof).



KJ264

| | | KF121 | KF192/193/194 | KF262/263/264 | KJ194/244/264 | KJ314 |
|--------------------------|--------------------|--|---------------------------|---------------------------|---------------------------|---------------------------|
| Application | | ● | | | | |
| Degree of freedom (axes) | | 6 | | | | 6/7 |
| Max. payload (kg) | | 5 | Wrist : 12 Upper Arm : 20 | Wrist : 12 Upper Arm : 20 | Wrist : 15 Upper Arm : 25 | Wrist : 15 Upper Arm : 25 |
| Max. reach (mm) | | 1.240 | 1.973/1.973/1.978 | 2.665/2.665/2.668 | 1.940/2.490/2.640 | 3.100 |
| Repeatability *1 (mm) | | ±0,2 | ±0,5 | ±0,5 | ±0,5 | ±0,5 |
| Motion range (°) | Arm rotation (JT1) | ±160 | ±150 | ±150*2 | ±120*2 | ±120 |
| | Arm out-in (JT2) | ±90 | +110 - -60 | +110 - -60 | +130 - -80 | +130 - -80 |
| | Arm up-down (JT3) | ±150 | +90 - -80 | +90 - -80 | +90 - -65 | +90 - -65 |
| | Wrist (JT4) | ±270 | ±360/±720/±720 | ±360/±720/±720 | ±720 | ±720 |
| | Wrist (JT5) | ±145 | ±360/±720/±720 | ±360/±720/±720 | ±720 | ±720 |
| | Wrist (JT6) | ±360 | ±360/±410/±410 | ±360/±410/±410 | ±410 | ±410 |
| | Arm (JT7) | - | - | - | - | ±90 |
| Wrist type | | RBR | BBR/3Rø40/3Rø70 | BBR/3Rø40/3Rø70 | 3Rø70 | 3Rø70 |
| Mass (kg) | | 140 | 690/720/750 | 720/740/770 | 530/540 | 720 |
| Explosion protection | | Combination of pressurized type and intrinsically safety type (II 2G Ex pxb ib II BT4) | | | | |
| Installation | | Floor, Wall | | | Floor, Shelf, Wall | Wall |
| Controller | | E47 | E45 | | | |

*1: conforms to ISO9283 *2: wall left side: +120-30, wall right side: +30-120
Application: ● Painting

Palletizing robots

Kawasaki's high-speed palletizing robots meet the demands for flexibility on reduced energy consumption.



CP700L

| | | RD080N | ZD130S | ZD250S | CP180L | CP300L | CP500L | CP700L |
|-------------------------------------|--------------------------|-------------|------------|------------|----------------|----------------|------------|------------|
| Application | | ● | | | | | | |
| Degree of freedom (axes) | | 5 | 4 | | | | | |
| Max. payload (kg) | | 80 | 130 | 250 | 180 | 300 | 500 | 700 |
| Max. reach (mm) | | 2.100 | 3.255 | 3.255 | 3.255 | 3.255 | 3.255 | 3.255 |
| Repeatability *2 (mm) | | ±0,06 | ±0,5 | ±0,5 | ±0,5 | ±0,5 | ±0,5 | ±0,5 |
| Motion range (°) | Arm rotation (JT1) | ±180 | ±180 | ±180 | ±160 | ±160 | ±160 | ±160 |
| | Arm out-in (JT2) | +140 - -105 | +90 - -50 | +90 - -50 | +95 - -46 | +95 - -46 | +95 - -46 | +95 - -46 |
| | Arm up-down (JT3) | +40 - -205 | +15 - -120 | +15 - -120 | +15 - -110 | +15 - -110 | +15 - -110 | +15 - -110 |
| | Wrist swivel (JT4) | ±360 | ±360 | ±360 | ±360 | ±360 | ±360 | ±360 |
| | Wrist compensation (JT5) | ±10 *3 | N/A | N/A | N/A | N/A | N/A | N/A |
| Max. speed (°/s) | Arm rotation (JT1) | 180 | 135 | 95 | 140 *4/130 | 115 *5/100 | 85 | 75 |
| | Arm out-in (JT2) | 180 | 110 | 90 | 125 *4/120 | 100 *5/90 | 80 | 65 |
| | Arm up-down (JT3) | 175 | 130 | 95 | 130 *4/125 | 100 *5/90 | 80 | 65 |
| | Wrist swivel (JT4) | 360 | 400 | 190 | 400 *4/330 | 250 *5/220 | 180 | 170 |
| Working area (mm) | Width | 1.100 | 1.800 | 1.800 | 1.800 | 1.800 | 1.800 | 1.800 |
| | Depth | 1.100 | 1.600 | 1.600 | 1.600 | 1.600 | 1.600 | 1.600 |
| | Height | 2.062 | 2.200 | 2.200 | 2.200 | 2.200 | 2.200 | 2.200 |
| Palletizing capacity *1(cycle/hour) | | 900 | 1.500 | 1.400 | 2.050 *4/1.800 | 1.700 *5/1.500 | 1.000 | 900 |
| Mass (kg) | | 540 | 1.350 | 1.350 | 1.600 | 1.600 | 1.650 | 1.650 |
| Controller | | E03 | E43 | | E03 | | | |

*1: Motion pattern (400mm up, 2,000mm horizontal, 400mm down in a to-and-fro motion) *2: conforms to ISO9283 *3: operating angle of the JT5 is ±10 degrees perpendicular to the ground. *4: in case of 130 kg payload and less *5: in case of 250 kg payload and less
Application: ● Palletizing

Dual-arm SCARA Robot

duAro

The duAro can fit into a single-person space. The coaxial dual-arm configuration makes coordinated movements possible.



DuAro 1

| duAro 1/duAro 2 | | | |
|--------------------------|-----------------------|---|-------------------|
| Application | | ● ● ● ● | |
| Degree of freedom (axes) | | 4 × (each arm) | |
| Vertical stroke | | 150 mm | 550 mm |
| Max. payload (kg) | | 2 (each arm) | 3 (each arm) |
| Repeatability (mm) | | ±0,05 | |
| Motion range (°) | Arm 1 (lower arm) | | Arm 2 (upper arm) |
| | Arm rotation (JT1) | | -170 - +170 |
| | Arm rotation (JT2) | | -140 - +500 |
| | Arm up-down (mm)(JT3) | | 0 - +550*1 |
| Wrist swivel (JT4) | -360 - +360*1 | | -360 - +360*1 |
| Mass (kg) | | 210 (integrated type), 100 (arm unit of separated type) | |
| Installation | | Floor | |
| Controller | | F61 | |

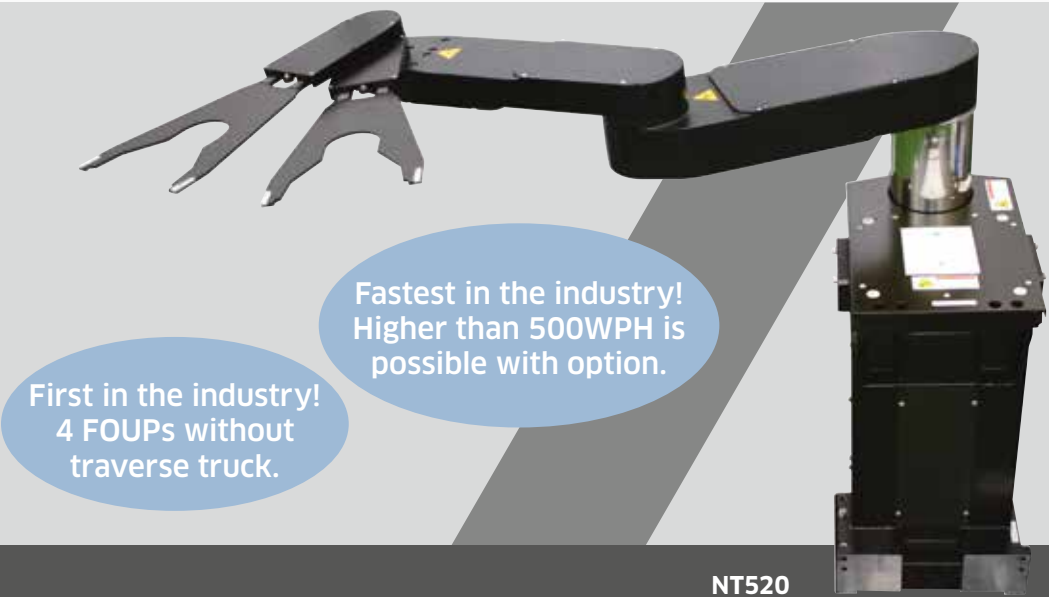
*1: Specification varies in case of other options or conversion
Application: ● Assembly ● Material handling ● Machine tending ● Dispensing

Clean robots

NT/NS series

Horizontal Articulated type

A wide range of horizontal articulated robots for semi-conductor manufacturing lines



NT520

Pick & Place robots

Y series

Ultra high-speed picking robot with renowned Kawasaki product quality and reliability.



YF003N

| | | YF002N | YF003N |
|----------------------------------|--------------------------|-------------------------------------|-----------------------------|
| Application | | ● ● | |
| Type | | Parallel link type | |
| Max. payload (kg) | | 2 | 3 |
| Degree of freedom (axes) | Standard | 4 | |
| | Option | - | 5 |
| Motion range (mm) | | ø600 × H200*3 | ø1.300 × H500*4 |
| Cycle time *1 (Payload) | | 0,3 s (0,5 kg) 0,36 s (2 kg) | 0,27 s (1 kg) 0,45 s (3 kg) |
| Positional repeatability *2 (mm) | | ± 0,04 | ± 0,1 |
| Angular repeatability (°) | | ± 0,1 | |
| Mass (kg) | | 60 | 145 |
| Installation | | Ceiling | |
| Environmental condition | Ambient Temperature (°C) | 10 - 40 | 0 - 45 |
| | Relative Humidity (%) | 35 - 85 (No dew, nor frost allowed) | |
| Degree of protection | Standard | IP 65 | |
| | Option | - | IP 67 |
| Controller | | E91 | |

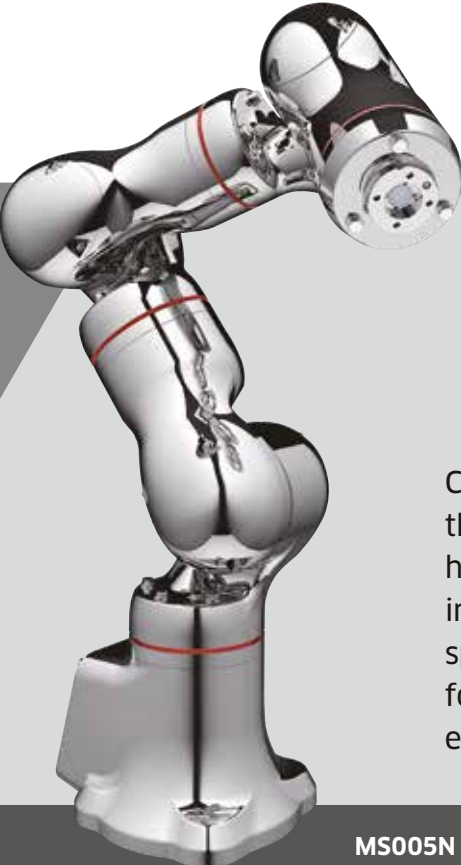
*1: Motion pattern (25mm up, 305mm horizontal, 25mm down in a to-and-fro motion)
*2: conforms to ISO9283
*3: Motion range is changing at H=150
*4 Motion range is changing at H=300
Application: ● Assembly ● Material handling

Medical & Pharmaceutical robots

MC004N
MS005N
MC004V

| | | MC004N/004V | MS005N |
|--------------------------|--------------------|----------------|------------|
| Degree of freedom (axes) | | 6 | 7 |
| Max. payload (kg) | | 4 | 5 |
| Max. reach (mm) | | 505,8 | 660 |
| Repeatability *1 (mm) | | ±0,05 | ±0,1 |
| Motion range (°) | Arm rotation (JT1) | ±180 | ±180 |
| | Arm out-in (JT2) | +135 - -95 | +135 - -90 |
| | Arm up-down (JT3) | +60 - -155 | ±120 |
| | Wrist swivel (JT4) | ±270 | ±180 |
| | Wrist bend (JT5) | ±120 | ±115 |
| | Wrist twist (JT6) | ±270 | ±180 |
| | Arm rotation (JT7) | - | ±180 |
| Max. speed (°/s) | Arm rotation (JT1) | 200 | 130 |
| | Arm out-in (JT2) | 180 | 130 |
| | Arm up-down (JT3) | 225 | 215 |
| | Wrist swivel (JT4) | 700 | 300 |
| | Wrist bend (JT5) | 500 | 300 |
| | Wrist twist (JT6) | 350 | 480 |
| | Arm rotation (JT7) | - | 215 |
| Mass (kg) | | 25 | 50 |
| Installation | | Floor, ceiling | Floor |
| Controller | | F60 | |

*1: conforms to ISO9283



MS005N

Clean robots that meet the healthcare industry's specifications for processing equipment.

Kawasaki Robotics Options: Individual Additions for Your Robots

Safety Modules, Software Solutions, External Axes and more: Kawasaki Robotics offers an extensive range of application-specific options for our robots and controllers – allowing you to precisely adapt each Kawasaki robot to your individual needs and to maximize its performance.

Selection of Hardware Options

Cubic-S

The Kawasaki Robotics Cubic-S safety module enables you to individually define and precisely limit the available working space. With Cubic-S, extremely space-saving application cells are easily possible. The robot is not able to exceed the given work area limits at any time. This ensures the safety of employees and the system itself at all times – without additional, expensive safety technology.

Cubic-S offers a total of eight individual functions, including Motion Area Monitoring Function, Axis Monitoring Function, Speed Monitoring Function and Emergency Stop Function. It is compatible with light barriers of many kinds and provides a multitude of inputs and interfaces.



Bus-Modules

A variety of bus-modules for Kawasaki Robotics controllers allow for maximum adaptability and fast communication between controllers and sensors/actuators of all types. The available bus-modules are:

DeviceNet (Slave/Master), PROFIBUS (Slave/Master), Interbus (Slave), EtherNet/IP (Slave/Master), Modbus-TCP – Server (Slave), CANopen (Slave), PROFINET IO (Slave/Master), ControlNet (Slave), EtherCAT (Slave) and CC-Link (Slave).



Conveyor Tracking

This optional module allows the tracking of up to four external conveyor belts in linear or circular shape and the immediate calculation into the robot movement – the position of each conveyor belt is not relevant. Up to 16 robots can be operated on a single conveyor.



Arm-ID Board

The Arm-ID Board comes with an IO interface board and provides additional in- and outputs. These IOs are located on the Robot Arm and can be used to control grippers or any other peripheral devices.





Additional Input/Output Boards

Available:

- Analog Input Board (E-Controller)
- Analog Output Board, PNP, with 32 additional Digital IOs
- Analog Output Board, NPN, with 32 additional Digital IOs
- Analog In- and Output Board (F-Controller)
- Additional Digital IO Board with 32 Digital IOs, NPN (E-Controller)
- Additional Digital IO Board with 32 Digital IOs, PNP (E-Controller)
- Additional Digital IO Board with 32 Digital IOs, PNP & NPN (F-Controller)

External Axis

The system can be extended through the use of external axes, such as positioners. By using an external axis, the robot system will be more efficient and flexible.

Arm Power/Signal Harness

While the standard version of the arm power and signal cables for Kawasaki robots in the EU is 10 meters, they can be exchanged at your request for 5-40 m cables – available in 5 m steps. Specialized/custom lengths are available as well.

Sensor Harness

Harnesses for setting up a signal connection of grippers to the Arm-ID Board.

Brake Release Box

The brake release box makes it possible to release the individual brakes of a robot. Brake release buttons are a standard option for all E4x controllers.

External Operator Panel

The external control panel is equipped with an Emergency Off Switch, a Teach/Repeat Switch and an optional Fast Check Switch.

Filter Option for Controller/Transformer

Additional filters can be installed to protect the inside of the controller and transformer from dust and other coarse particles in especially challenging work environments.

IP54 Option for F60 Controller

This option upgrades the F-Controller to protection class IP54. The front and back as well as the bottom of the controller unit are provided with additional elements and the controller is effectively sealed off from its environment.

Remote IO Unit, PNP & NPN

The external box provides additional inputs and outputs. The digital version offers 32 Digital IOs while the analogue version offers 4 inputs and 4 outputs. A maximum of six boxes, 4 digital and 2 analogue, can be connected to one controller. The boxes offer a variety of mounting options such as brackets on all sides or top-hat rail mounting. The unit is configurable as NPN and PNP – including 2AW or 2AH boards.

IO-Connector Harness

The IO-Connector harness allows to access the IOs of the F-Controller via a D-SUB-connector.

IO-Connector Interface Module

The IO-connector interface is a terminal block which can be connected to the IO-connector harness.

Teach Pendant Light Harness Options

It is possible to exchange the Teach Pendant Light Harness from its original 10m to a different length. Available in 5m, 15m, 20m, 25m and 30m

Cable Reel for Teach Pendant Light

To keep the workspace safe and clean, a cable reel for the Teach Pendant is available in two variants: 10 m or 15 m

Pedestal

Our space-saving, sturdy and light-weight pedestals are available for the models BX200L, BX300L, RS020N and MG15HL. Their hollow design elevates the robot, increases its effective workspace and allows for the easy storage of cables within the pedestal.

Selection of Software Options

Collision Detection

This option allows the monitoring of motor current values according to selectable thresholds. Different values can be defined for manual and automatic operation of each robot. This option can reduce the damage caused by collisions significantly.

Spin Control Function

Available for robots and external axes (such as positioners), the spin control function allows for the endless rotation of axis 6 in \pm range. It can be reset at the end of the process via command – no separate retraction of axis 6 is required.

Changing Servo System Gain

This option allows the soft switching of the control parameters of individual axes. The robot will move back to its original position as soon as the external disturbance is no longer present.

Soft Absorber

The Soft Absorber option makes the soft switching of the control parameters of individual axes possible, within individually definable limits, such as direction and path. If the external disturbance is no longer present, the robot stops at the current position.

K-IDE

K-IDE is an intuitive programming interface for Kawasaki robots, enabling the precise development of programs for numerous applications and systems. The easy to use editor, the clearly arranged project management, the automatic synchronization between software and robots and many other functions make K-IDE the perfect tool for programming.

K-Roset

K-Roset enables simple 3D simulations and offline programming of Kawasaki robots – ensuring maximum planning reliability for your automation. The tool directly accesses the kinematic models and controller software of the Kawasaki robots.

K-Logic

K-Logic is a software-based PLC (programmable logic controller) with several logical functions.

K-Ladder

Additional programming software for K-Logic. Requires an installation of K-Logic.

K-Sparc

K-Sparc is a palletizing software for Kawasaki robots – makes it possible to create individual packing patterns on pallets. Requires both K-Roset and a separate license.

K-Vision

K-Vision offers a flexible vision system for numerous applications. It enables the easy connection of cameras to Kawasaki robots for implementing position detection and inspection processes within the robot application. This way, you are able to considerably increase both effectiveness and flexibility in automation.

Open AS

Open AS provides an easy-to-use development environment for the convenient creation of user interfaces, applications and the flexible integration of sensors/signals.

Learn more about our options!

Talk to us!



Kawasaki Robotics Options: Adapt each robot to your individual needs

Color LCD teach pendant for the E and F series controllers

The teach pendant has a significantly lighter body with an optimized weight balance that reduces the burden of teaching work. The operator can now switch on the motors and activate the cycle start all from the teach pendant. In addition, new features such as the easy-to-navigate screen and switch layout allow for a more convenient control system. Two information windows can be displayed simultaneously on the monitor screen, providing access to different type of information (e.g. positional information and signal information).



The explosion-proof teach pendant features a color LCD with a large-sized touch screen that allows for teaching, editing, and monitoring of information such as current position and IO signals in the painting area. It is possible to customize the interface panel according to user preference. The back-light provides a clear view of the screen in dark locations.



Controller

Combines high performance, unprecedented reliability, a host of integrated features and simple operation all in a compact design. The enhanced CPU capacity allows for more accurate trajectory control and faster application program execution.



F-Controller



E9X-Controller



E0X-Controller

| | | F-Controller | E9X-Controller | E0X-Controller |
|--|--------------------|--|--|--|
| Features | | Smallest Controller in its class. Compact design for small arm robots. High performance, 19 inch rack compatible, electrical regeneration function and safety system Cubic-S. (Option) | Compact design for medium robot arms, Vertical or horizontal installation | Universal Controller. Available for multiple primary power supply voltages with a separate transformer unit. Electricity regeneration function for palletizing robots. (energy saving) |
| Drive system | | Full digital servo system | Full digital servo system | Full digital servo system |
| Teaching method | | Easy operation teaching or AS language programming | Easy operation teaching or AS language programming | Easy operation teaching or AS language programming |
| Teach pendant | | Color LCD teach pendant | Color LCD teach pendant | Color LCD teach pendant |
| Memory capacity (MB) | | 16 | 8 | 8 |
| I/O signals | External operation | Emergency stop, Hold etc. | Emergency stop, Hold etc. | Emergency stop, Hold etc. |
| | Input (Channels) | 16 (max. 144) | 32 (max. 96) | 32 (max. 96) |
| | Output (Channels) | 16 (max. 144) | 32 (max. 96) | 32 (max. 96) |
| Structure | | Open structure with direct cooling system | Enclosed structure with indirect cooling system | Enclosed structure with indirect cooling system |
| Mass (kg) without options | | 8,3 | 40 | 40/45 |
| Available Options | | | | |
| Hardware Options | | | | |
| Harness | | Arm Power/Signal Harness Set, 5m steps from 5 to 40 m | Arm Power/Signal Harness Set, 5m steps from 5 to 40 m | Arm Power/Signal Harness Set, 5m steps from 5 to 40 m |
| Cubic-S | | Hardware module to customize workspace and safety settings | Hardware module to customize workspace and safety settings | Hardware module to customize workspace and safety settings |
| Bus-Modules | | DeviceNet (Slave/Master), PROFIBUS (Slave/Master), Interbus (Slave), EtherNet/IP (Slave/Master), Modbus-TCP – Server (Slave), CANopen (Slave), PROFINET IO (Slave/Master), ControlNet (Slave), EtherCAT (Slave) and CC-Link (Slave). | DeviceNet (Slave/Master), PROFIBUS (Slave/Master), Interbus (Slave), EtherNet/IP (Slave/Master), Modbus-TCP – Server (Slave), CANopen (Slave), PROFINET IO (Slave/Master), ControlNet (Slave), EtherCAT (Slave) and CC-Link (Slave). | DeviceNet (Slave/Master), PROFIBUS (Slave/Master), Interbus (Slave), EtherNet/IP (Slave/Master), Modbus-TCP – Server (Slave), CANopen (Slave), PROFINET IO (Slave/Master), ControlNet (Slave), EtherCAT (Slave) and CC-Link (Slave). |
| Conveyor Tracking | | Tracking of up to four external conveyor belts and operation of up to 16 robots | Tracking of up to four external conveyor belts and operation of up to 16 robots | Tracking of up to four external conveyor belts and operation of up to 16 robots |
| Pedestal | | Space-saving, sturdy and light-weight pedestals for BX200L, BX300L, RS020N and MG15HL | Space-saving, sturdy and light-weight pedestals for BX200L, BX300L, RS020N and MG15HL | Space-saving, sturdy and light-weight pedestals for BX200L, BX300L, RS020N and MG15HL |
| Arm-ID Board | | Providing additional in- and outputs through an IO interface board | Providing additional in- and outputs through an IO interface board | Providing additional in- and outputs through an IO interface board |
| External Axis | | Including all necessary equipment to operate up to 16 individual axes per controller | Including all necessary equipment to operate up to 16 individual axes per controller | Including all necessary equipment to operate up to 16 individual axes per controller |
| Brake Release Box | | Makes it possible to release individual brakes. | Makes it possible to release individual brakes. | Makes it possible to release individual brakes. |
| External Operator Panel | | Equipped with additional switches. | Equipped with additional switches. | Equipped with additional switches. |
| IP54 Option for F60 | | Option for upgrading the F-Controller to protection class IP54 | N/A | N/A |
| Remote IO Unit PNP & NPN | | Provides additional in- and outputs | Provides additional in- and outputs | Provides additional in- and outputs |
| IO-Connector Harness | | Connection line between IOs and the F-Controller | N/A | N/A |
| IO-Connector Interface Module | | Transfer module for attaching adapter cable to the IO connection of the F-Controller | N/A | N/A |
| Sensor Harness | | Harnesses for setting up a signal connection of grippers to the Arm-ID Board | Harnesses for setting up a signal connection of grippers to the Arm-ID Board | Harnesses for setting up a signal connection of grippers to the Arm-ID Board |
| Teach Pendant Light Harness Options | | Available options: 5/15/20/25/30 m | Available options: 5/15/20/25/30 m | Available options: 5/15/20/25/30 m |
| Cable Reel for Teach Pendant Light | | Available options: 10/15 m | Available options: 10/15 m | Available options: 10/15 m |
| Additional In/Output Boards | | Analogue IO Board, Digital IO Board (PNP/NPN) | Digital IO Board (PNP/NPN), Analogue Input Board, Analogue Output Board (Analogue Boards include 32 Digital IOs (NPN/PNP)) | Digital IO Board (PNP/NPN), Analogue Input Board, Analogue Output Board (Analogue Boards include 32 Digital IOs (NPN/PNP)) |
| Filter Option for Controller/Transformer | | Additional filters to protect the inside of Controller | Additional filters to protect the inside of Controller | N/A |
| K-Vision | | Flexible vision system for numerous applications | Flexible vision system for numerous applications | Flexible vision system for numerous applications |
| Software Options | | | | |
| Collision Detection | | Monitoring of motor current values according to selectable thresholds | Monitoring of motor current values according to selectable thresholds | Monitoring of motor current values according to selectable thresholds |
| Spin Control Function | | Available for robots and external axes – allowing for the endless rotation of axis 6 in ± range | Available for robots and external axes – allowing for the endless rotation of axis 6 in ± range | Available for robots and external axes – allowing for the endless rotation of axis 6 in ± range |
| Changing Servo System Gain | | Allows soft switching of the control parameters of individual axes | Allows soft switching of the control parameters of individual axes | Allows soft switching of the control parameters of individual axes |
| Soft Absorber | | Supports the soft switching of the control parameters of individual axes | Supports the soft switching of the control parameters of individual axes | Supports the soft switching of the control parameters of individual axes |
| K-IDE | | Intuitive programming interface for Kawasaki robots | Intuitive programming interface for Kawasaki robots | Intuitive programming interface for Kawasaki robots |
| K-ROSET | | Enables simple 3D simulations and offline programming of Kawasaki robots | Enables simple 3D simulations and offline programming of Kawasaki robots | Enables simple 3D simulations and offline programming of Kawasaki robots |
| K-Sparc | | Palletizing software for Kawasaki robots | Palletizing software for Kawasaki robots | Palletizing software for Kawasaki robots |
| K-Ladder | | Additional programming software for K-Logic | Additional programming software for K-Logic | Additional programming software for K-Logic |
| Open AS | | Easy-to-use development environment | Easy-to-use development environment | Easy-to-use development environment |



E4X-Controller



E45/E47-Controller



E58-Controller

| | | E4X-Controller | E45/47-Controller | E58-Controller |
|--|--------------------|--|--|--|
| Features | | Controller for each region’s primary power supply voltage. High expandability and maintainability. | Controller and teach pendant explosion proofed (ATEX Spec.) | The E58 controller supports the extra large payload robots (MG series). This universal controller can cope with different voltages of the primary supply in the world. |
| Drive system | | Full digital servo system | Full digital servo system | Full digital servo system |
| Teaching method | | Easy operation teaching or AS language programming | Easy operation teaching or AS language programming | Easy operation teaching or AS language programming |
| Teach pendant | | Color LCD teach pendant | Explosion-proof teach pendant, Color LCD teach pendant | Color LCD teach pendant |
| Memory capacity (MB) | | 8 | 8 | 8 |
| I/O signals | External operation | Emergency stop, Hold etc. | Emergency stop, Hold etc. | Emergency stop, Hold etc. |
| | Input (Channels) | 32 (max. 128) | 32 (max. 128) | 32 (max. 128) |
| | Output (Channels) | 32 (max. 128) | 32 (max. 128) | 32 (max. 128) |
| Structure | | Enclosed structure with indirect cooling system | Enclosed structure with indirect cooling system | Enclosed structure with indirect cooling system |
| Mass (kg) without options | | 145-195 | 170 | 215 |
| Available Options | | | | |
| Hardware Options | | | | |
| Harness | | Arm Power/Signal Harness Set, 5 m steps from 5 to 40 m | Arm Power/Signal Harness Set, 5 m steps from 5 to 40 m | Arm Power/Signal Harness Set, 5 m steps from 5 to 40 m |
| Cubic-S | | Hardware module to customize workspace and safety settings | Hardware module to customize workspace and safety settings | Hardware module to customize workspace and safety settings |
| Bus-Modules | | DeviceNet (Slave/Master), PROFIBUS (Slave/Master), Interbus (Slave), EtherNet/IP (Slave/Master), Modbus-TCP – Server (Slave), CANopen (Slave), PROFINET IO (Slave/Master), ControlNet (Slave), EtherCAT (Slave) and CC-Link (Slave). | DeviceNet (Slave/Master), PROFIBUS (Slave/Master), Interbus (Slave), EtherNet/IP (Slave/Master), Modbus-TCP – Server (Slave), CANopen (Slave), PROFINET IO (Slave/Master), ControlNet (Slave), EtherCAT (Slave) and CC-Link (Slave). | DeviceNet (Slave/Master), PROFIBUS (Slave/Master), Interbus (Slave), EtherNet/IP (Slave/Master), Modbus-TCP – Server (Slave), CANopen (Slave), PROFINET IO (Slave/Master), ControlNet (Slave), EtherCAT (Slave) and CC-Link (Slave). |
| Conveyor Tracking | | Tracking of up to four external conveyor belts and operation of up to 16 robots | Tracking of up to four external conveyor belts and operation of up to 16 robots | Tracking of up to four external conveyor belts and operation of up to 16 robots |
| Pedestal | | Space-saving, sturdy and light-weight pedestals for BX200L, BX300L, RS020N and MG15HL | Space-saving, sturdy and light-weight pedestals for BX200L, BX300L, RS020N and MG15HL | Space-saving, sturdy and light-weight pedestals for BX200L, BX300L, RS020N and MG15HL |
| Arm-ID Board | | Providing additional in- and outputs through an IO interface board | Providing additional in- and outputs through an IO interface board | Providing additional in- and outputs through an IO interface board |
| External Axis | | Including all necessary equipment to operate up to 16 individual axes per controller | Including all necessary equipment to operate up to 16 individual axes per controller | Including all necessary equipment to operate up to 16 individual axes per controller |
| Brake Release Box | | N/A | N/A | Making it possible to release the individual brakes of a robot |
| External Operator Panel | | N/A | N/A | Equipped with an Emergency Off Switch, a Teach/Repeat Switch and an optional Fast Check Switch |
| IP54 Option for F60 | | N/A | N/A | N/A |
| Remote IO Unit PNP & NPN | | N/A | N/A | N/A |
| IO-Connector Harness | | N/A | N/A | N/A |
| IO-Connector Interface Module | | N/A | N/A | N/A |
| Sensor Harness | | Harnesses for setting up a signal connection of grippers to the Arm-ID Board | Harnesses for setting up a signal connection of grippers to the Arm-ID Board | Harnesses for setting up a signal connection of grippers to the Arm-ID Board |
| Teach Pendant Light Harness Options | | Available options: 5/15/20/25/30 m | Available options: 5/15/20/25/30 m | Available options: 5/15/20/25/30 m |
| Cable Reel for Teach Pendant Light | | Available options: 10/15 m | Available options: 10/15 m | Available options: 10/15 m |
| Additional In/Output Boards | | Digital IO Board (PNP/NPN), Analogue Input Board, Analogue Output Board (Analogue Boards include 32 Digital IOs (NPN/PNP)) | Digital IO Board (PNP/NPN), Analogue Input Board, Analogue Output Board (Analogue Boards include 32 Digital IOs (NPN/PNP)) | Digital IO Board (PNP/NPN), Analogue Input Board, Analogue Output Board (Analogue Boards include 32 Digital IOs (NPN/PNP)) |
| Filter Option for Controller/Transformer | | Additional filters to protect the inside of Controller | Additional filters to protect the inside of Controller | Additional filters to protect the inside of Controller |
| K-Vision | | Flexible vision system for numerous applications | Flexible vision system for numerous applications | Flexible vision system for numerous applications |
| Software Options | | | | |
| Collision Detection | | Monitoring of current values and encoder positions according to selectable thresholds | Monitoring of current values and encoder positions according to selectable thresholds | Monitoring of current values and encoder positions according to selectable thresholds |
| Spin Control Function | | Available for robots and external axes – allowing for the endless rotation of axis 6 in ± range | Available for robots and external axes – allowing for the endless rotation of axis 6 in ± range | Available for robots and external axes – allowing for the endless rotation of axis 6 in ± range |
| Changing Servo System Gain | | Allows soft switching of the control parameters of individual axes | Allows soft switching of the control parameters of individual axes | Allows soft switching of the control parameters of individual axes |
| Soft Absorber | | Supports the soft switching of the control parameters of individual axes | Supports the soft switching of the control parameters of individual axes | Supports the soft switching of the control parameters of individual axes |
| K-IDE | | Intuitive programming interface for Kawasaki robots | Intuitive programming interface for Kawasaki robots | Intuitive programming interface for Kawasaki robots |
| K-ROSET | | Enables simple 3D simulations and offline programming of Kawasaki robots | Enables simple 3D simulations and offline programming of Kawasaki robots | Enables simple 3D simulations and offline programming of Kawasaki robots |
| K-Sparc | | Palletizing software for Kawasaki robots | Palletizing software for Kawasaki robots | Palletizing software for Kawasaki robots |
| K-Ladder | | Additional programming software for K-Logic | Additional programming software for K-Logic | Additional programming software for K-Logic |
| Open AS | | Easy-to-use development environment | Easy-to-use development environment | Easy-to-use development environment |

As individual and reliable as our robots: Our Service

The Kawasaki Robotics Service Program

- To guarantee maximum availability of your robots and systems, our experts are available 24/7 - via our technical hotline and, of course, on site.
- Customers benefit from our international network, cross-industry expertise and excellent service.
- We help to avoid downtimes through fast fault analyses and predictive maintenance.



In addition to visual and functional checks, cleaning as well as grease and battery changes, we also check:

- Grease check for metal particles
- The braking power of the servo motors
- A detailed log is generated after each maintenance
- In case of malfunctions, our service technicians provide a fast analysis to keep downtimes as predictable and low as possible as well as quick and competent support in the selection of the right spare parts.



CS24 Support

Kawasaki Robotics provides numerous options for comprehensive technical support – with or without a maintenance contract.

- Our 24/7 Phone Support
- Tailor-made service for each customer – around the clock: They can always reach our trained service technicians via an individual hotline number.
- Spare parts service
- On-site support

Planning ahead:

The Kawasaki TREND Manager

The unique Kawasaki TREND Manager automatically and continuously analyses all status data of any given robot. This enables our diagnostic tool in the controller to predict inspections, signs of wear and problems at an early stage.

The advantages of the TREND Manager at a glance:

- Maximum availability of robots and systems
- Agile maintenance support
- Clear visualisation
- Local real-time recording of numerous parameters
- Improvement of service life through load testing and program optimisation
- Automatic motor current monitoring





EMEA Headquarters, Sales and Service

Kawasaki Robotics GmbH

<http://robotics.kawasaki.com>

Im Taubental 32, 41468 Neuss, Germany

Phone: +49-2131-3426-0 Fax: +49-2131-3426-22

Local Office

Kawasaki Robotics (UK) Ltd.

<http://robotics.kawasaki.com>

Unit 4 Easter Court, Europa Boulevard, Westbrook Warrington
Cheshire, WA5 7ZB, United Kingdom

Phone: +44-1925-71-3000 Fax: +44-1925-71-3001

Kawasaki Heavy Industries Russia LLC (KHI- Moscow)

<http://robotics.kawasaki.com>

Office 1206, entrance 3, 12 Krasnopresnenskaya emb.,
Moscow, Russian Federation 123610

Phone: +7-495-258-2115 Fax: +7-495-258-2116

Kawasaki Heavy Industries Middle East FZE (KHI-ME)

<http://robotics.kawasaki.com>

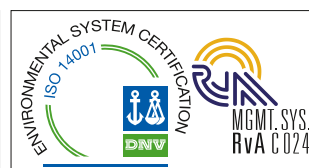
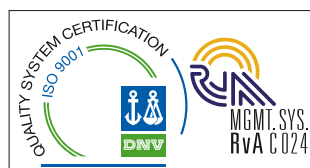
Dubai Aiport Free Zone, Bldg. W6, Block-A,
Office No. 709, PO BOX 54878, Dubai UAE

Phone: +971-(0)4-214-6730 Fax: +971-(0)4-214-6729



CAUTIONS TO BE TAKEN TO ENSURE SAFETY

- For those persons involved with the operation / service of your system, including Kawasaki Robot, they must strictly observe all safety regulations at all times. They should carefully read the Manuals and other related safety documents.
- Products described in this catalogue are general industrial robots. Therefore, if a customer wishes to use the Robot for special purposes, which might endanger operators or if the Robot has any problems, please contact us. We will be pleased to help you.
- Be careful as Photographs illustrated in this catalogue are frequently taken after removing safety fences and other safety devices stipulated in the safety regulations from the Robot operation system.



ISO certified in Akashi Works.