# IX-NNC2515[H]

Small SCARA robot, Cleanroom type Arm length 250mm, Vertical axis 150mm [High-power specification]

> **T2** Applicable controller

IX — NNC2515[H] —

Cable length

Cleanroom type Arm length 250mm Vertical axis 150mm

Series

5L:5 m (standard) T2: XSEL-PX/QX

10L: 10 m



#### Model/Specifications

Model	Avia configuration		Avia configuration		Avia configuration		Avia configuration		Arm	Motor	Work	Positioning Repeatability	Maximum	Standard cycle time			Axis 3 (vertical axis) push force (N) (Note 5)			
Model	Axis configuration	length capacity (W)	envelope	(mm) (Note 1)	operating speed (Note 2)	(sec) (Note 3)	Rated	Maximum	Maximum limit	limit	Allowable inertial moment (kg·m2) (Note 6)	torque								
	Axis 1	Arm 1	125	200	±120°	±0.010	3142mm/s [3191mm/s] (Composite speed) 0.49													
IX-NNC2515[H]-①-T2	Axis 2	Arm 2	125	100	±130°	(XY)		0.49	1	3	90.9	47.5	0.015	4.0						
1X 14102010[11] @ 12	Axis 3	Vertical axis	-	100	150mm	±0.010	1106mm/s [1316mm/s]	[0.44]			[111.0]	[58.0]		1.9						
	Axis 4	Rotating axis	-	50	±360°	±0.005	1600°/s													

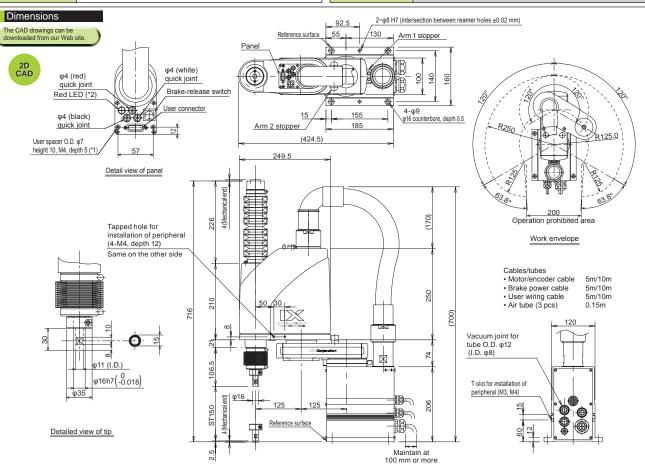
<sup>\*</sup>In the model number above, specify the cable length in 1

#### Common Specifications

Encoder type Absolute 15-conductor AWG26 D-sub/15-pin connector with shield (socket) User wiring User tubing Air tube (O.D. Ø4, I.D. Ø2.5) x 3 (Normal working pressure 0.8 MPa) Alarm indicator (Note 7) Small red LED indicator x 1 (24 V DC must be supplied.) Brake-release switch (Note 8) Allows remote release of Z-axis (24 VDC required)

*SCARA robots cannot operate continuously at 100% speed and acceleration.
For details on the operating conditions, refer to Reference Acceleration/
Deceleration Settings on page 45.

Vacuum joint	Applicable tube O.D. Ø12
Suction rate (Note 10)	60 N-liter/min
Cleanliness class	Conforming to ISO cleanliness class 4 (0.1 µm)
Ambient temperature/humidity	Temperature: 0–40 °C, humidity: 20–85%RH or less (no condensation)
Unit weight	19Kg
Cable length (Note 9)	5L: 5 m (standard), 10L: 10 m (optional)



- \*1: The external force applied to a spacer must not exceed 30 N in the axial direction, or 2 N·m in the rotating direction. (for each spacer)
  \*2: In order to use the LED, the user must wire it so that it responds to the controller's I/O output signal by supplying 24 V DC to the applicable LED terminal in the user wiring.

#### Applicable Controller Specifications

Applicable Colle	Tollor opositioations				
Applicable Controller	Features	Maximum I/O points (inputs/outputs)	Power-supply voltage	Reference page	
XSEL-PX-###-2[3]	Maximum 6 axes, 1600 [2400] W supported	192/192 points	Single-Phase	n 27	
XSEL-QX-###-2[3]	Cofoty Cotogony 1	192/192 points	230 VAC	p. 37	

<sup>\*</sup>The SCARA model with high-power specification [H] needs a 2.4 kW three-phase type controller XSEL-PX/QX-###-3.



For explanations of (Note 1) through (Note 9), refer to page 6.

(Note 10) In order to use the cleanroom type in an environment with ISO cleanliness class 4, the air inside the robot must be vacuumed from the air suction outlet located at the side (or back) of the robot base.

<sup>\*</sup>For details on the model items, refer to page 8

## IX-NNC3515[H]

Small SCARA robot, Cleanroom type Arm length 350mm, Vertical axis 150mm [High-power specification]

■Model items

IX — NNC3515[H] —

Series Cleanroom type Arm length 350mm

Vertical axis 150mm

Cable length

Applicable controller T2: XSEL-PX/QX

5L:5 m (standard) 10L: 10 m



\*For details on the model items, refer to page 8

#### Model/Specifications

Model	Avia	anfininstian	Arm	Motor	Work	Positioning Repeatability	, Maximum	Standard cycle time			Axis 3 (ve push force			
	Axis configuration	length capac (W)	capacity (W)	envelope	(mm) (Note 1)	operating speed (Note 2)	(sec) (Note 3)	Rated	Maximum	Maximum limit	Minimum limit	Allowable inertial moment (kg-m2) (Note 6)	torque	
	Axis 1	Arm 1	225	200	±120°	±0.010	3979mm/s							
IX-NN3515[H]-[1]-12	Axis 2	Arm 2	125	100	±135°	(XY)	[4042mm/s] (Composite speed)	0.58	1	3	90.9	47.5	0.015	1.9
	Axis 3	Vertical axis	-	100	150mm	±0.010	1106mm/s [1316mm/s]	[0.46]			[111.0]	[58.0]		
	Axis 4	Rotating axis	-	50	±360°	±0.005	1600°/s							

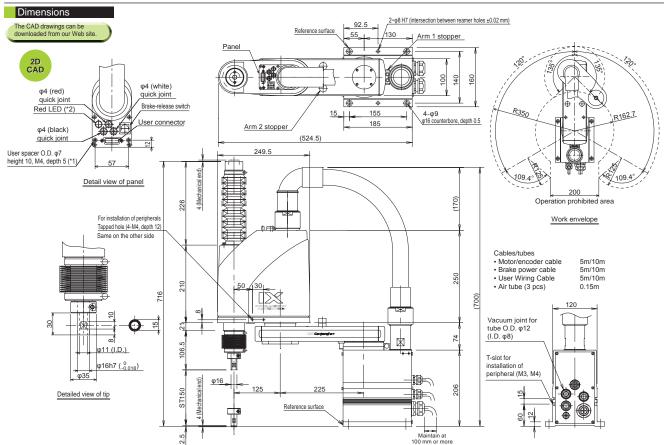
<sup>\*</sup>In the model number above, specify the cable length in ①

#### Common Specifications

Encoder type Absolute 15-conductor AWG26 D-sub/15-pin connector with shield (socket) User wiring User tubing Air tube (O.D. Ø4, I.D. Ø2.5) x 3 (Normal working pressure 0.8 MPa) Small red LED indicator x 1 (24 V DC must be supplied.) Alarm indicator (Note 7) Brake-release switch (Note 8) Allows remote release of Z-axis (24 VDC required)

*SCARA robots cannot operate continuously at 100% speed and acceleration.
For details on the operating conditions, refer to Reference Acceleration/
Deceleration Settings on page 45.

Vacuum joint	Applicable tube O.D. Ø12
Suction rate (Note 10)	60 N-liter/min
Cleanliness class	Conforming to ISO cleanliness class 4 (0.1 µm)
Ambient temperature/humidity	Temperature: 0–40 °C, humidity: 20–85%RH or less (no condensation)
Unit weight	20Kg
Cable length (Note 9)	5L: 5 m (standard), 10L: 10 m (optional)



- \*1: The external force applied to a spacer must not exceed 30 N in the axial direction, or 2 N·m in the rotating direction. (for each spacer)
  \*2: In order to use the LED, the user must wire it so that it responds to the controller's I/O output signal by supplying 24 V DC to the applicable LED terminal in the user wiring.

### Applicable Controller Specifications

Applicable Controller	Features	Maximum I/O points (inputs/outputs)	Power-supply voltage	Reference page	
XSEL-PX-###-2[3]	Maximum 6 axes, 1600 [2400] W supported	192/192 points	Single-Phase [Three-phase]	n 27	
XSEL-QX-###-2[3]	Safaty Catagory A	192/192 points	230 VAC	p. 37	

\*The SCARA model with high-power specification [H] needs a 2.4 kW three-phase type controller XSEL-PX/QX-###-3.



For explanations of (Note 1) through (Note 9), refer to page 6.

(Note 10) In order to use the cleanroom type in an environment with ISO cleanliness class 4, the air inside the robot must be vacuumed from the air suction outlet located at the side (or back) of the robot base.

### IX-NNC50□□

Medium SCARA robot, Cleanroom type Arm length 500mm, Vertical axis 200mm [High-power specification]

■Model items  $IX - NNC50 \square \square [H]$ **T2** 

NNC5020[H]: Arm length 500mm, Vertical axis 200mm NNC5030[H]: Arm length 500mm, Vertical axis 300mm

Applicable controller

T2: XSEL-PX/QX 5L:5 m (standard)

Cable length





Series

#### Model/Specifications

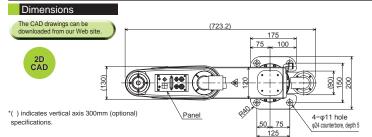
Model	Avie	configuration	Arm length	Motor capacity	Work	Positioning Repeatability		Standard cycle time		apacity Note 4)	Axis 3 (ver		Axi allowab	
	AXIS	Axis configuration	(mm)	(W)	envelope	(mm) (Note 1)	speed (Note 2)	(sec) (Note 3)	Rated	Maximum	Maximum limit	limit	Allowable inertial moment (kg·m2) (Note 6)	Allowable torque (N · m)
	Axis 1	Arm 1	250	400	±120°	±0.010	0.010 6283mm/s							
IX-NNC5020[H]-10-T2	Axis 2	Arm 2	250	200	±145°	(XY)	[6381mm/s] (Composite speed)	0.47			152	78		3.3
(IX-NNC5030[H]- 🔟 -T2)	Axis 3	Vertical axis	-	200	200mm (300mm)	±0.010	1393mm/s [1473mm/s]	0.47 [0.41]	2	10	[181]	[93]	0.06	[3.7]
	Axis 4	Rotating axis	-	100	±360°	±0.005	1200°/s [1857°/s]							

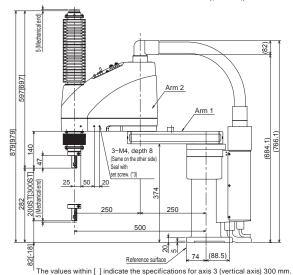
<sup>\*</sup>In the model number above, specify the cable length in ①.

#### Common Specifications

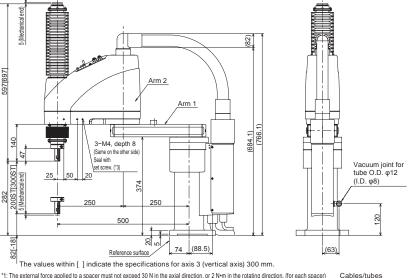
Encoder type	Absolute					
User wiring	25-conductor AWG26 D-sub/25-pin connector with shield (socket)					
Hear tubing	Air tube (O.D. Ø6, I.D. Ø4) x 2 (Normal working pressure 0.8 MPa)					
User tubing	Air tube (O.D. Ø4, I.D. Ø2.5) x 2 (Normal working pressure 0.8 MPa)					
Alarm indicator (Note 7)	Small red LED indicator x 1 (24 V DC must be supplied.)					
Brake-release switch (Note 8)	Allows remote release of Z-axis (24 VDC required)					

Vacuum joint	Quick joint, Applicable tube O.D. Ø12					
Suction rate (Note 10)	60 N-liter/min					
Cleanliness class Conforming to ISO cleanliness class 4 (0.1 µm)						
Ambient temperature/humidity	Temperature: 0–40 °C, humidity: 20–85%RH or less (no condensation)					
Unit weight	31.5Kg					
Cable length (Note 9)	5L: 5 m (standard), 10L: 10 m (optional)					





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3: The prepared hole 3-M4, depth 8 passes through the side panel of the arm. If the mounting screw is long, make sure it does not contact internal components. In addition, be sure to seal screws with tape.







 Motor/encoder cable
 Brake power cable
 User Wiring Cable · Air tube (4 pcs)

200 Work envelope φ6 air-tube quick joint φ4 air-tube quick joint D-sub/25-pin connector for u wiring, socket fixing jig M2.6 28 Red LED (\*3) Brake-release Spacer O.D. φ7 Height 10 M4 depth 30 Detail view of panel 5 (\*2) 0 A-A section φ14 hollow φ20h7(<sub>-0.021</sub>) 5m/10m Detailed view of tip

#### Applicable Controller Specifications

Applicable Controller	Features	Maximum I/O points (inputs/outputs)	Power-supply voltage	Reference page	
XSEL-PX-###-2[3]	Maximum 6 axes, 1600 [2400] W supported	402/402 mainta	Single-Phase [Three-phase]	p. 37	
XSEL-QX-###-2[3]	Safety Category 4 supported	192/192 points	230 VAC		

<sup>\*</sup>The SCARA model with high-power specification [H] needs a 2.4 kW three-phase type controller XSEL-PX/QX-###-3.



For explanations of (Note 1) through (Note 9), refer to page 6.

0.15m

(Note 10) In order to use the cleanroom type in an environment with ISO cleanliness class 4, the air inside the robot must be vacuumed from the air suction outlet located at the side (or back) of the robot base.

<sup>\*( )</sup> indicates vertical axis 300mm specifications. All other specifications are common to both the vertical axis 200mm and 300mm.

<sup>\*</sup>SCARA robots cannot operate continuously at 100% speed and acceleration. For details on the operating conditions, refer to Reference Acceleration/ Deceleration Settings on page 45.

## IX-NNC60□□

Medium SCARA robot, Cleanroom type Arm length 600mm, Vertical axis 200mm (300mm) [High-power specification]

IX — NNC60□□[H]

Cable length Type

**T2** Applicable controller

NNC6020[H]: Arm length 600mm, Vertical axis 200mm NNC6030[H]:

5L:5 m (standard) 10L: 10 m

T2: XSEL-PX/QX





Series

#### Model/Specifications

Model .		configuration	Arm	Motor	Work	Positioning Repeatability	PTP operation Maximum	Standard cycle time			Axis 3 (ve push force		Axi: allowab	
		configuration	length (mm)	(W)	envelope	(mm) (Note 1)	operating speed (Note 2)	(sec) (Note 3)	Rated	Maximum	Maximum limit	limit	Allowable inertial moment (kg·m2) (Note 6)	torque
	Axis 1	Arm 1	350	400	±120°	±0.010	7121mm/s [7232mm/s]							
IX-NNC6020[H]-10-T2	Axis 2	Arm 2	250	200	±145°	(XY)	(Composite speed)				152	78		3.3
(IX-NNC6030[H]	Axis 3	Vertical axis	-	200	200mm (300mm)	±0.010	1393mm/s [1473mm/s]	0.54 [0.45]	2	10	[181]	[93]	0.06	[3.7]
	Axis 4	Rotating axis	-	100	±360°	±0.005	1200°/s [1857°/s]							

<sup>\*</sup>In the model number above, specify the cable length in ①.

\*SCARA robots cannot operate continuously at 100% speed and acceleration. For details on the operating conditions, refer to Reference Acceleration/ Deceleration Settings on page 45.

114.3° 200

Operation prohibited ar Work envelope

63

White 

2 28

22.5

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#### Common Specifications

Encoder type	Absolute
User wiring	25-conductor AWG26 D-sub/25-pin connector with shield (socket)
User tubing	Air tube (O.D. Ø6, I.D. Ø4) x 2 (Normal working pressure 0.8 MPa) Air tube (O.D. Ø4, I.D. Ø2.5) x 2 (Normal working pressure 0.8 MPa)
Alarm indicator (Note 7)	Small red LED indicator x 1 (24 V DC must be supplied.)
Brake-release switch (Note 8)	Allows remote release of Z-axis (24 VDC required)

Vacuum joint	Quick joint, Applicable tube O.D. Ø12
Suction rate (Note 10)	60 N-liter/min
Cleanliness class	Conforming to ISO cleanliness class 4 (0.1 µm)
Ambient temperature/humidity	Temperature: 0–40 °C, humidity: 20–85%RH or less (no condensation)
Unit weight	32.5Kg
Cable length (Note 9)	5L: 5 m (standard), 10L: 10 m (optional)

φ6 air-tube quick joint

φ4 air-tube quick

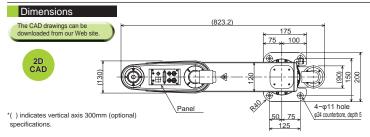
D-sub/25-pin connector for

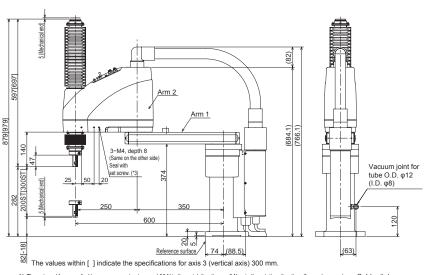
wiring, socket fixing jig M2.6

Red LED (\*3)

Brake-release switch

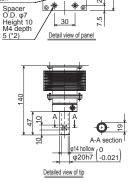
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- \*1: The external force applied to a spacer must not exceed 30 N in the axial direction, or 2 N•m in the rotating direction. (for each spacer)
- \*2: In order to use the LED, the user must wire it so that it responds to the controller's I/O output signal by supplying 24 V DC to the applicable LED terminal in the user wiring.
  \*3: The prepared hole 3-M4, depth 8 passes through the side panel of the arm. If the mounting screw is long, make sure it does not contact internal components. In addition, be sure to seal screws with tape.
- Cables/tubes Motor/encoder cable
- Brake power cable
   User Wiring Cable
   Air tube (4 pcs)

5m/10m 5m/10m 5m/10m 0.15m



#### Applicable Controller Specifications

Applica Contro		Features	Maximum I/O points (inputs/outputs)	Power-supply voltage	Reference page
XSEL-PX-#	##-2[3]	Maximum 6 axes, 1600 [2400] W supported	192/192 points	Single-Phase	p. 37
XSEL-QX-#		Safaty Catagory A	192/192 points	[Three-phase] 230 VAC	p. 37

<sup>\*</sup>The SCARA model with high-power specification [H] needs a 2.4 kW three-phase type controller XSEL-PX/QX-###-3.



For explanations of (Note 1) through (Note 9), refer to page 6.

(Note 10) In order to use the cleanroom type in an environment with ISO cleanliness class 4, the air inside the robot must be vacuumed from the air suction outlet located at the side (or back) of the robot base.

<sup>\*( )</sup> indicates vertical axis 300mm specifications. All other specifications are common to both the vertical axis 200mm and 300mm.

## IX-NNC70□□

Large SCARA robot, Cleanroom type Arm length 700mm, Vertical axis 200mm [High-power specification]

 $IX - NNC70 \square \square [H]$ 

**T2** Applicable controller

NNC7020[H]: Arm length 700mm, Vertical axis 200mm NNC7040[H]: Arm length 700mm, Vertical axis 400mm

5L:5 m (standard) 10L:10 m T2: XSEL-PX/QX



#### Model/Specifications

Model Axis con		oonfiguration	Arm	Motor capacity	Work	Positioning Repeatability	PTP operation Maximum operating	Standard cycle time		apacity Note 4)	Axis 3 (ver push force (		Axi: allowab	
		comiguration	length (mm)	(W)	envelope (mm) (Note 1)		speed (Note 2)	(sec) (Note 3)	Rated	Maximum	Maximum limit	Minimum	Allowable inertial moment (kg-m2) (Note 6)	Allowable torque (N · m)
	Axis 1	Arm 1	350	750	±125°	±0.010	6597mm/s							
IX-NNC7020[H]	Axis 2	Arm 2	350	400	±145°	(XY)	[7010mm/s] (Composite speed)	0.50			265	407.0		6.7
(IX-NNC7040[H]	Axis 3	Vertical axis	-	400	200mm (400mm)	±0.010	1583mm/s [1614mm/s]	0.52 [0.45]	5	20	[304]	127.3 [146.0]	0.1	6.7 [11.7]
	Axis 4	Rotating axis	-	200	±360°	±0.005	1200°/s [1266°/s]							

Air joint (\*4)

350

(971.5)

Arm 2 stopper

\*SCARA robots cannot operate continuously at 100% speed and acceleration. For details on the operating conditions, refer to Reference Acceleration/ Deceleration Settings on page 45.

#### Common Specifications

Encoder type	Absolute
User wiring	25-conductor AW26 D-sub/25-pin connector with shield (socket)
User tubing	Air tube (O.D. Ø6, I.D. Ø4) x 2 (Normal working pressure 0.8 MPa)
	Air tube (O.D. Ø4, I.D. Ø2.5) x 2 (Normal working pressure 0.8 MPa)
Alarm indicator (Note 7)	Small red LED indicator x 1 (24 V DC must be supplied.)
Brake-release switch (Note 8)	Allows remote release of Z-axis (24 VDC required)

(65)

Vacuum joint	Quick joint, Applicable tube O.D. Ø12
Suction rate (Note 10)	80 N-liter/min
Cleanliness class	Conforming to ISO cleanliness class 4 (0.1 µm)
Ambient temperature/humidity	Temperature: 0–40 °C, humidity: 20–85%RH or less (no condensation)
Unit weight	60Kg
Cable length (Note 9)	5L: 5 m (standard), 10L: 10 m (optional)

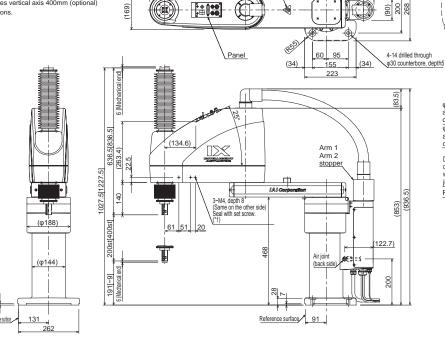
Applicable tube O.D. φ12 (I.D. φ8)

#### Dimensions

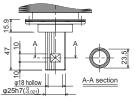
The CAD drawings can be downloaded from our Web site



\*( ) indicates vertical axis 400mm (optional) specifications.



φ6 air-tube quick joint φ4 air-tube quick joint 28 D-sub/25-pin connector for use 21.5 wiring, socket fixing jiq M2.6 28 Red LED (\*3) Brake-relea 22.5 se switch Spacer O.D. φ7 Height 10 M4 depth 5 (\*2) 30 Detail view of panel



- \*11. The bottom hole 3-M4, depth 8 passes through the side panel of the arm.

  \*2. The external force applied to a spacer must not exceed 30 N in the axial direction, or 2 N·m in the rotating direction. (for each spacer)

  \*3. In order to use the LED, the user must wire it so that it responds to the controller's I/O output signal by supplying 24 V DC to the
  applicable LED terminal in the user wiring.

  \*4. The joint can be installed in the opposite direction (by removing PT3/8 plug and switching the insertion direction of the joint).

- Cables/tubes

   Motor/encoder cable 5m/10m Brake power cable 5m/10m

<ul> <li>User Wiring Cable</li> </ul>	5m/10m
<ul> <li>Air tube (4 pcs)</li> </ul>	0.15m

#### Applicable Controller Specifications

Applicable Controller	Features	Maximum I/O points (inputs/outputs)	Power-supply voltage	Reference page	
XSEL-PX-###-2[3]	Maximum 6 axes, 1600 [2400] W supported	192/192 points	Single-Phase	n 27	
XSEL-QX-###-2[3]	Satety ('ategory /	192/192 points	[Three-phase] 230 VAC	p. 37	

<sup>\*</sup>The SCARA model with high-power specification [H] needs a 2.4 kW three-phase type controller XSEL-PX/QX-###-3.



For explanations of (Note 1) through (Note 9), refer to page 6.

(Note 10) In order to use the cleanroom type in an environment with ISO cleanliness class 4, the air inside the robot must be vacuumed from the air suction outlet located at the side (or back) of the robot base.

Detailed view of tip

<sup>\*</sup>For details on the model items, refer to page 8.

<sup>\*</sup>In the model number above, specify the cable length in ①

### IX-NNC80□□

Large SCARA robot, Cleanroom type Arm length 800mm, Vertical axis 200mm [High-power specification]

IX — NNC80□□[H]

Cable length

NNC8020[H]: Arm length 800mm, Vertical axis 200mm NNC8040[H]: Arm length 800mm, Vertical axis 400mm

5L:5~m~(standard) T2: XSEL-PX/QX 10L: 10 m



#### Model/Specifications

Model		configuration	Arm	Motor capacity	Work	Positioning Repeatability		Standard cycle time			Axis 3 (ve push force		Axi: allowab	
		comiguration	length (mm)	(W)	envelope (mm) (Note 1)		speed (Note 2)	(sec) (Note 3)	Rated	Maximum	Maximum limit	limit	Allowable inertial moment (kg-m2) (Note 6)	torque
	Axis 1	Arm 1	450	750	±125°	±0.010	7121mm/s							
IX-NNC8020[H]-10-T2	Axis 2	Arm 2	350	400	±145°	(XY)	[7586mm/s] (Composite speed)	0.50			265	127.3		6.7
(IX-NNC8040[H]-10-T2)	Axis 3	Vertical axis	-	400	200mm (400mm)	±0.010	1583mm/s [1614mm/s]	0.52 [0.46]	5	20	[304]	[146.0]	0.1	[11.7]
	Axis 4	Rotating axis	-	200	±360°	±0.005	1200°/s [1266°/s]							

Air joint (\*4)

(1071.5)

Arm 2 stoppe

### \*SCARA robots cannot operate continuously at 100% speed and acceleration. For details on the operating conditions, refer to Reference Acceleration/ Deceleration Settings on page 45.

#### Common Specifications

Encoder type	Absolute
User wiring	25-conductor AW26 D-sub/25-pin connector with shield (socket)
User tubing	Air tube (O.D. Ø6, I.D. Ø4) x 2 (Normal working pressure 0.8 MPa)
	Air tube (O.D. Ø4, I.D. Ø2.5) x 2 (Normal working pressure 0.8 MPa)
Alarm indicator (Note 7)	Small red LED indicator x 1 (24 V DC must be supplied.)
Brake-release switch (Note 8)	Allows remote release of Z-axis (24 VDC required)

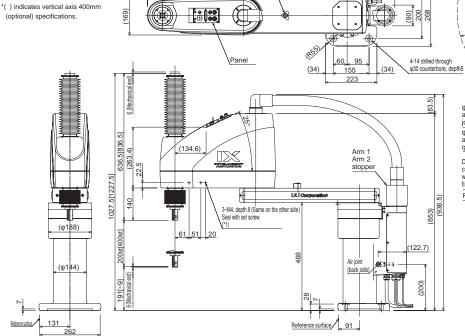
Vacuum joint	Quick joint, Applicable tube O.D. Ø12
Suction rate (Note 10)	80 N-liter/min
Cleanliness class	Conforming to ISO cleanliness class 4 (0.1 µm)
Ambient temperature/humidity	Temperature: 0–40 °C, humidity: 20–85%RH or less (no condensation)
Unit weight	62Kg
Cable length (Note 9)	5L: 5 m (standard), 10L: 10 m (optional)

99.1°

φ6 air-tube quick

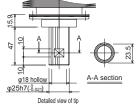
### The CAD drawings can be downloaded from our Web site. 2D CAD

Dimensions



joint φ4 air-tube ٨ quick joint **O** D-sub/25-pin connector for user wiring, socket fixing jig M2.6 White Red LED (\*3) Brake-relea se switch Spacer O.D. φ7 Height 10 M4 depth 5 (\*2) 30 Detail view of panel

ation prohibited area)
Work envelope



- \*1: The bottom hole 3-M4, depth 8 passes through the side panel of the arm.
  \*2: The external force applied to a spacer must not exceed 30 N in the axial direction, or 2 N+m in the rotating direction. (for each spacer)
  \*3. In order to use the LED, the user must wire it so that it responds to the controller's I/O output signal by supplying 24 V DC to the applicable LED terminal in the user wiring.
  \*4: The joint can be installed in the opposite direction.

- Cables/tubes
- Motor/encoder cable 5m/10m Brake power cable 5m/10m

Applicable tube O.D. φ12 (I.D. φ8)

- User Wiring Cable
  Air tube (4 pcs) 5m/10m 0.15m

Applicable Controller Specifications	

Applicable Controller	Features	Maximum I/O points (inputs/outputs)	Power-supply voltage	Reference page
XSEL-PX-###-2[3]	Maximum 6 axes, 1600 [2400] W supported	192/192 points	Single-Phase [Three-phase]	p. 37
XSEL-QX-###-2[3]			230 VAC	μ. 37

<sup>\*</sup>The SCARA model with high-power specification [H] needs a 2.4 kW three-phase type controller XSEL-PX/QX-###-3.

For explanations of (Note 1) through (Note 9), refer to page 6.

(Note 10) In order to use the cleanroom type in an environment with ISO cleanliness class 4, the air inside the robot must be vacuumed from the air suction outlet located at the side (or back) of the robot base.

<sup>\*</sup>For details on the model items, refer to page 8.

<sup>\*</sup>In the model number above, specify the cable length in ①