

**BU015X** 

8.8

# Kawasaki Robot BU015N/X Robot for sealing and under-body coating

# Features:

# Internal hose & cable routing

The robots' hollow structure allows cable harnesses to be housed inside the wrist, upper arm and base, eliminating the risk of interference caused by adjacent robots or peripheral equipment, and reducing the risk of hose damage.

# Expanded working range

The BU015X model's long reach and 7 axes greatly expand its work envelope, delivering smooth, even coverage to areas a 6-axis robot is unable to reach. Both robots offer a slim arm design, thing body and small footprint for installation in high-density applications.

## Symmetrical arm design

The BU015N and BU015X models' symmetrical design reduces interference to enable easy programming during mirroring, thus reducing time spent offline programming and on-site teaching

**BU015N** 

#### Motion Range & Dimensions



## **Specifications**

		BU015N	BU015X
Construction (Type)		Articulated	
Degrees of Freedom (Axes)		6	7
Max. Payload (kg)		15	15
Max. Reach (mm)		1,550	2,887.5
Positional Repeatability (mm) *1		±0.04	±0.06
Motion Range (° )	Arm Swing (Arm Rotation ) (JT1)	±180	
	Before and after the wrist (Arm out-in) (JT2)	+140105	
	Arm up-down (JT3)	+155120	+30170
	Wrist swivel (JT4)	±210	
	Wrist bend (JT7)	-	+110130
	Wrist rotation (JT5)	±120	
	Wrist twist (JT6)	±360	
Max. Speed (°/s)	Arm Swing (Arm Rotation ) (JT1)	250	200
	Before and after the wrist (Arm out-in) (JT2)	250	200
	Arm up-down (JT3)	215	200
	Wrist swivel (JT4)	280	290
	Wrist bend (JT7)	-	170
	Wrist rotation (JT5)	280	
	Wrist twist (JT6)	360	
Moment (N • m)	JT4	27.0	-
	JT5	27.0	
	JT6	22.0	
Moment of Inertia *2 (kg • m²)	JT4	0.70	-
	JT5	0.70	
	JT6	0.25	
Mass (kg)		160	590
Installation		Floor	
Environmental Condition	Ambient Temperature (°C)	0 - 45	
	Relative Humidity (%)	35 - 85 (no condensation)	
Options		Mechanical Stopper (JT1)	
		Traversing device (stroke mm)	
		Installation stand (600mmH, 300mmH)	
		Base plate (750mm x 750mm)	
		-	Air, 3 valves
		Please consult u	is for other cases

## Controller

BU015N uses E51<sup>1</sup> controller BU015X uses E52 controller

Controllers conform to each country's safety standards. Please contact your sales representative for details.



#### E51/E52

 $^{\star}\mathrm{1}$  E51: Korean safety standard (KCs) is not supported

\*1 Conforms to ISO9283

\*2 The values in this table indicate the allowable moment of inertia when the maximum allowable torque is applied

to each wrist axis. Please contact us for other details.

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