



Standard Specifications

BX165N-C00x

BX165N-F00x

1st ed. 28-Sep-16

3rd ed. 17-Nov-20

Kawasaki Heavy Industries, Ltd.
Robot Business Division

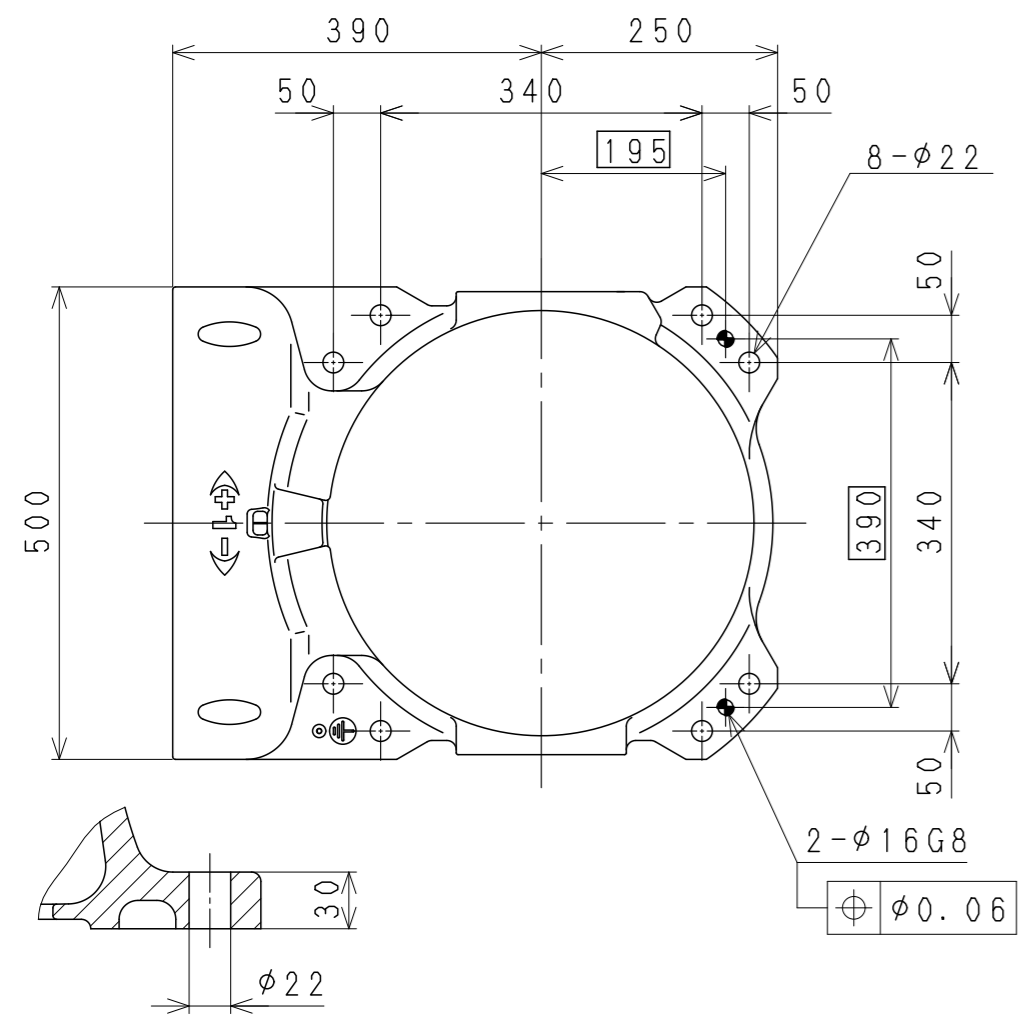
Specification number : 90151-0166DEC

Materials and specifications are subject to change without notice.

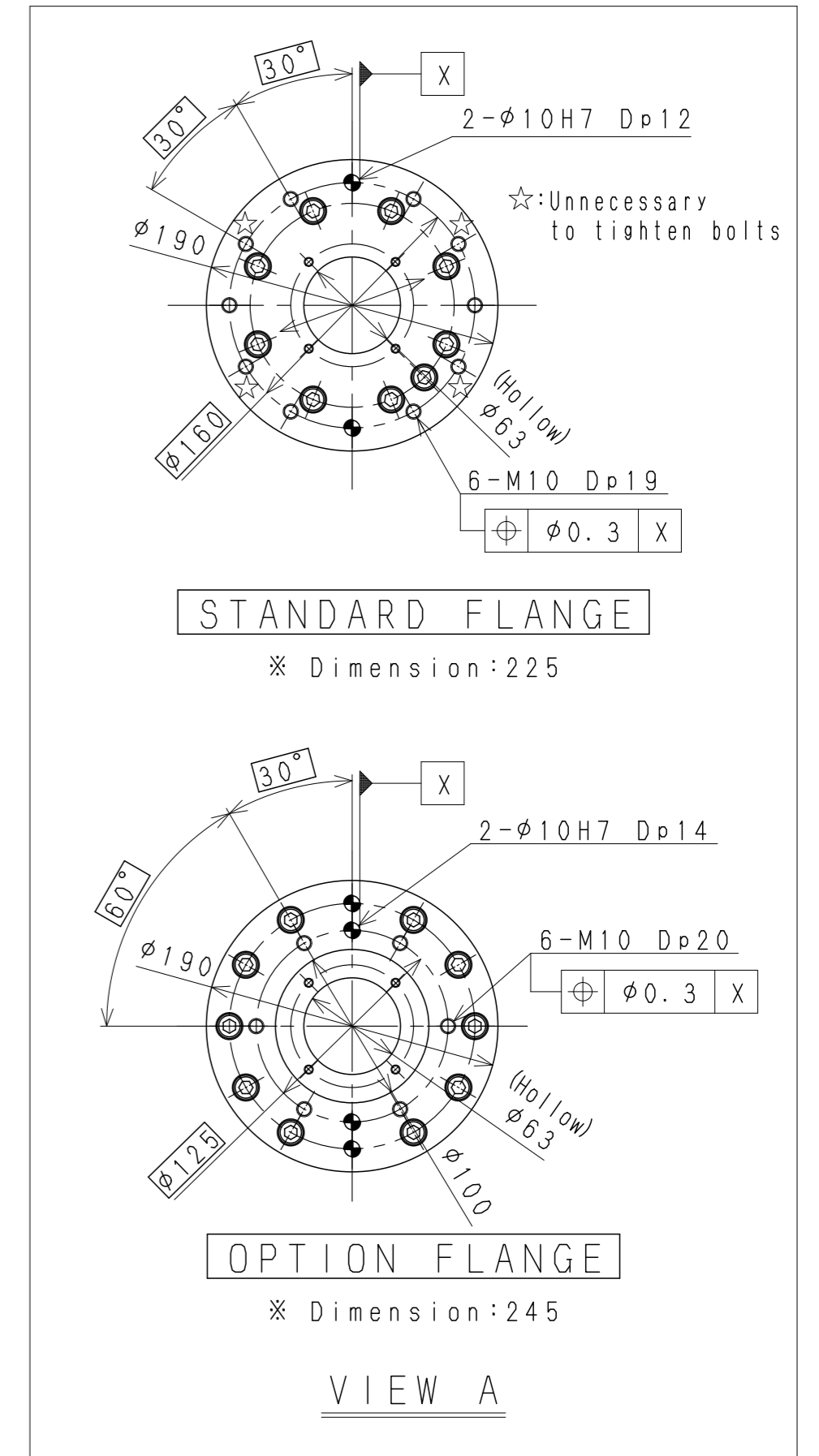
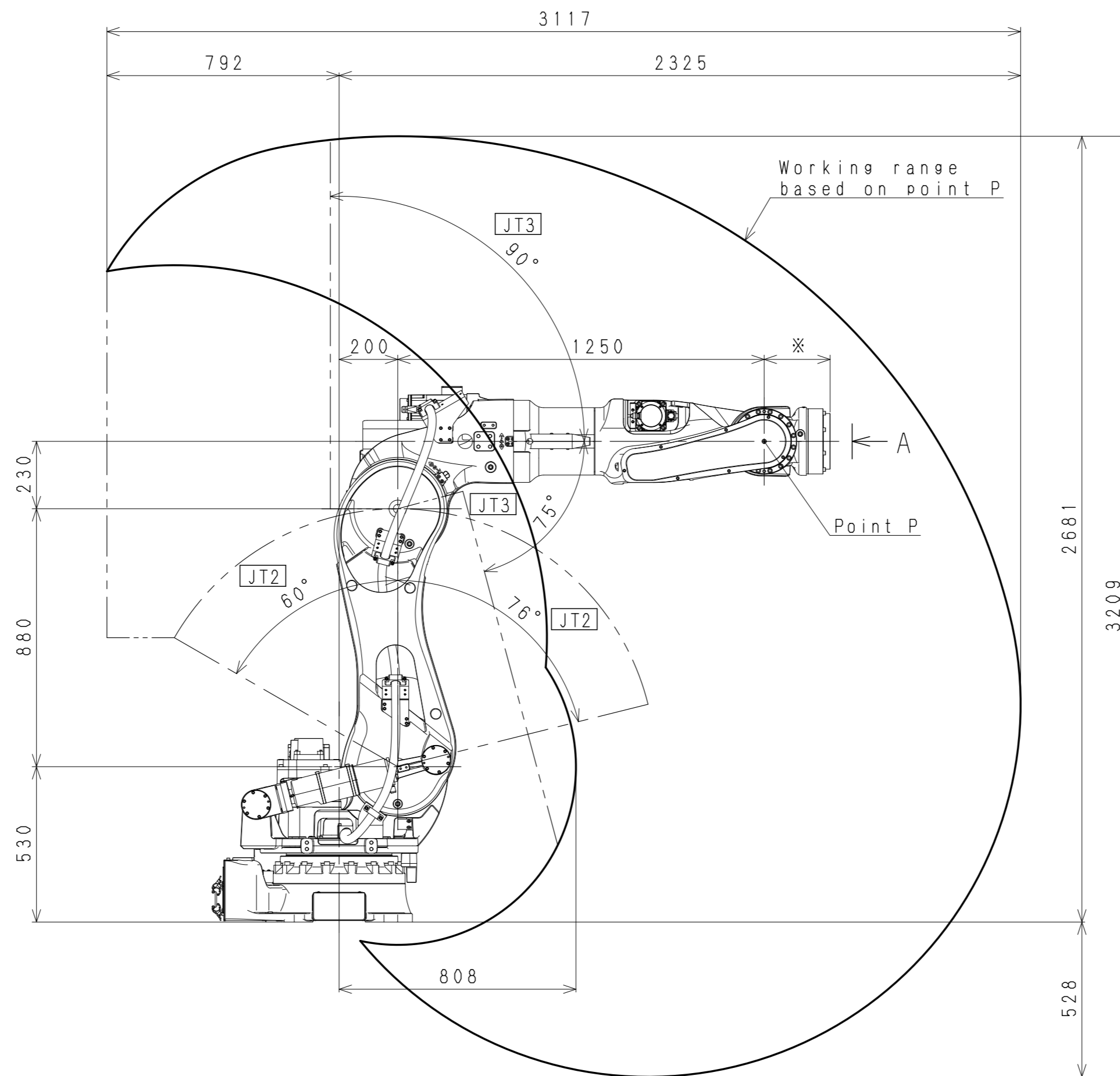
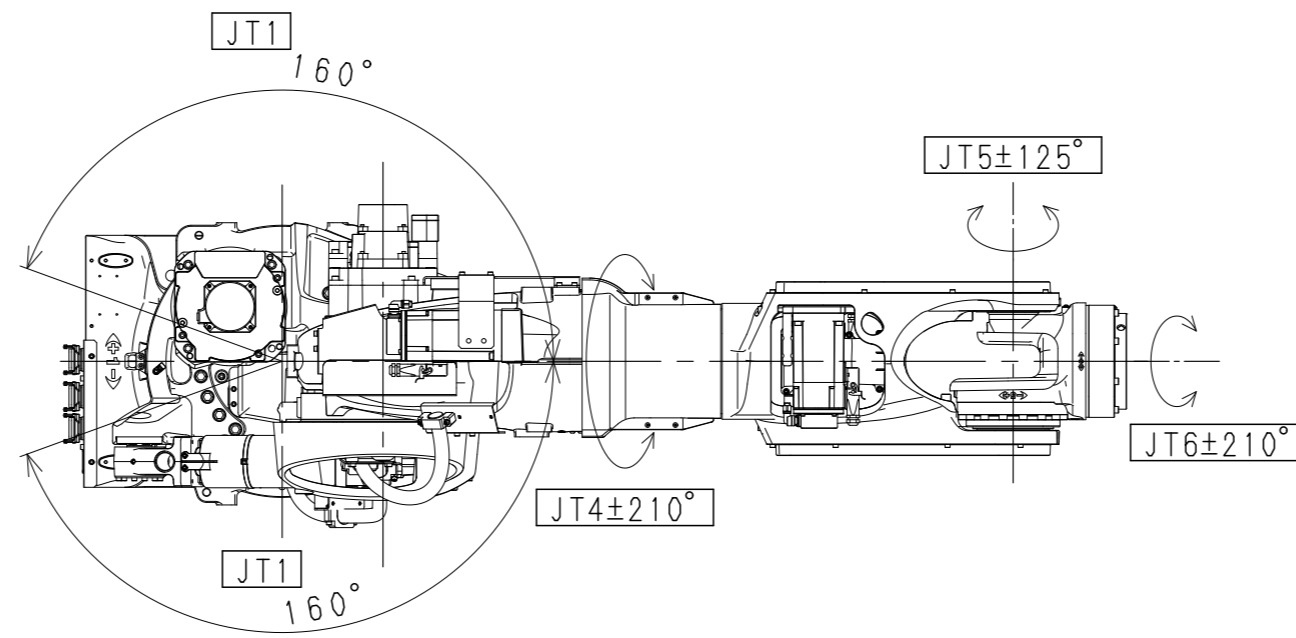
Robot specifications

1. Model	BX165N-C, BX165N-F																						
2. Type	Articulated robot																						
3. Degree of freedom	6 axes (Option 7 axes)																						
4. Max. payload	165 kg																						
5. Max. reach	2,325 mm																						
6. Position repeatability	±0.06 mm (wrist flange surface) conforms to ISO 9283																						
7. Axis specification	<table border="1"> <thead> <tr> <th>Operating axis</th> <th>Motion range</th> <th>Max. speed</th> </tr> </thead> <tbody> <tr> <td>Arm rotation (JT1)</td> <td>±160°</td> <td>105°/s</td> </tr> <tr> <td>Arm out-in (JT2)</td> <td>+ 76° - - 60°</td> <td>130°/s</td> </tr> <tr> <td>Arm up-down (JT3)</td> <td>+ 90° - - 75°</td> <td>130°/s</td> </tr> <tr> <td>Wrist swivel (JT4)</td> <td>±210°</td> <td>120°/s</td> </tr> <tr> <td>Wrist bend (JT5)</td> <td>±125°</td> <td>160°/s</td> </tr> <tr> <td>Wrist twist (JT6)</td> <td>±210°</td> <td>300°/s</td> </tr> </tbody> </table>		Operating axis	Motion range	Max. speed	Arm rotation (JT1)	±160°	105°/s	Arm out-in (JT2)	+ 76° - - 60°	130°/s	Arm up-down (JT3)	+ 90° - - 75°	130°/s	Wrist swivel (JT4)	±210°	120°/s	Wrist bend (JT5)	±125°	160°/s	Wrist twist (JT6)	±210°	300°/s
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8. Load capacity of wrist	<table border="1"> <thead> <tr> <th></th> <th>Max. torque</th> <th>Moment of inertia*</th> </tr> </thead> <tbody> <tr> <td>JT4</td> <td>930 N·m</td> <td>99 kg·m²</td> </tr> <tr> <td>JT5</td> <td>930 N·m</td> <td>99 kg·m²</td> </tr> <tr> <td>JT6</td> <td>490 N·m</td> <td>49.5 kg·m²</td> </tr> </tbody> </table> <p>Note* Each value in this table shows allowable moment of inertia of JT4/JT5/JT6 when max. allowed torque is applied to each axis. If more detailed data is required for your application, please contact Kawasaki.</p>			Max. torque	Moment of inertia*	JT4	930 N·m	99 kg·m ²	JT5	930 N·m	99 kg·m ²	JT6	490 N·m	49.5 kg·m ²									
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9. Mass	875 kg (without options)																						
10. Mounting	Floor mounting																						
11. Installation Environment	Ambient Temperature: 0 - 45 °C Relative Humidity: 35 - 85 % (with no dew condensation)																						
12. Color	Munsell 10GY9/1 equivalent																						
13. Degree of protection	Wrist: IP67 equivalent, Arm: IP54 equivalent																						
14. Dressing	Cable length between flange and tool is 1.5m. Consult Kawasaki when non-standard dressing will be applied.																						
15. Options	Mechanical stopper	Adjustable stoppers JT1/JT2/JT3																					
	Adapter bracket	between flange and tool																					

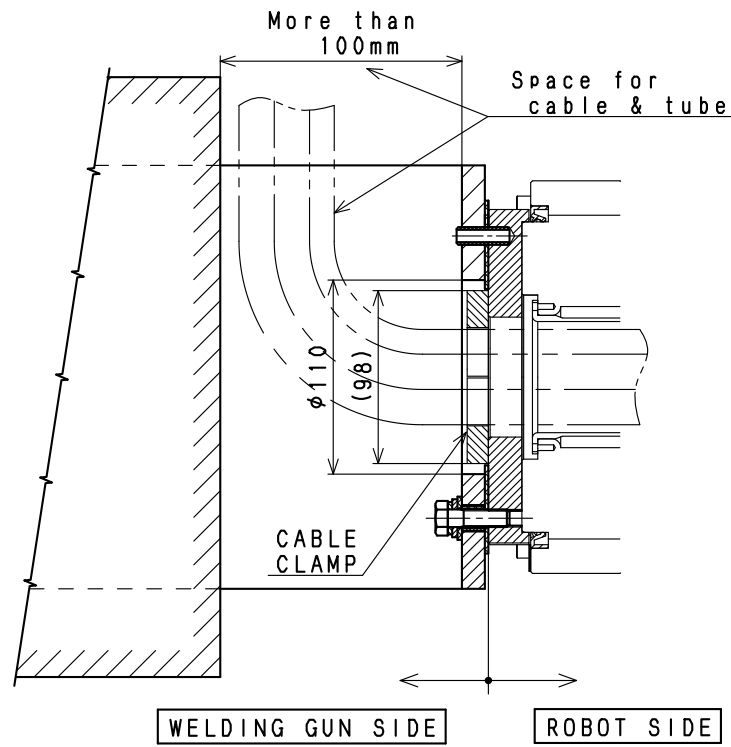
Consult Kawasaki about maintenance parts and spare parts.



Installation Dimensions



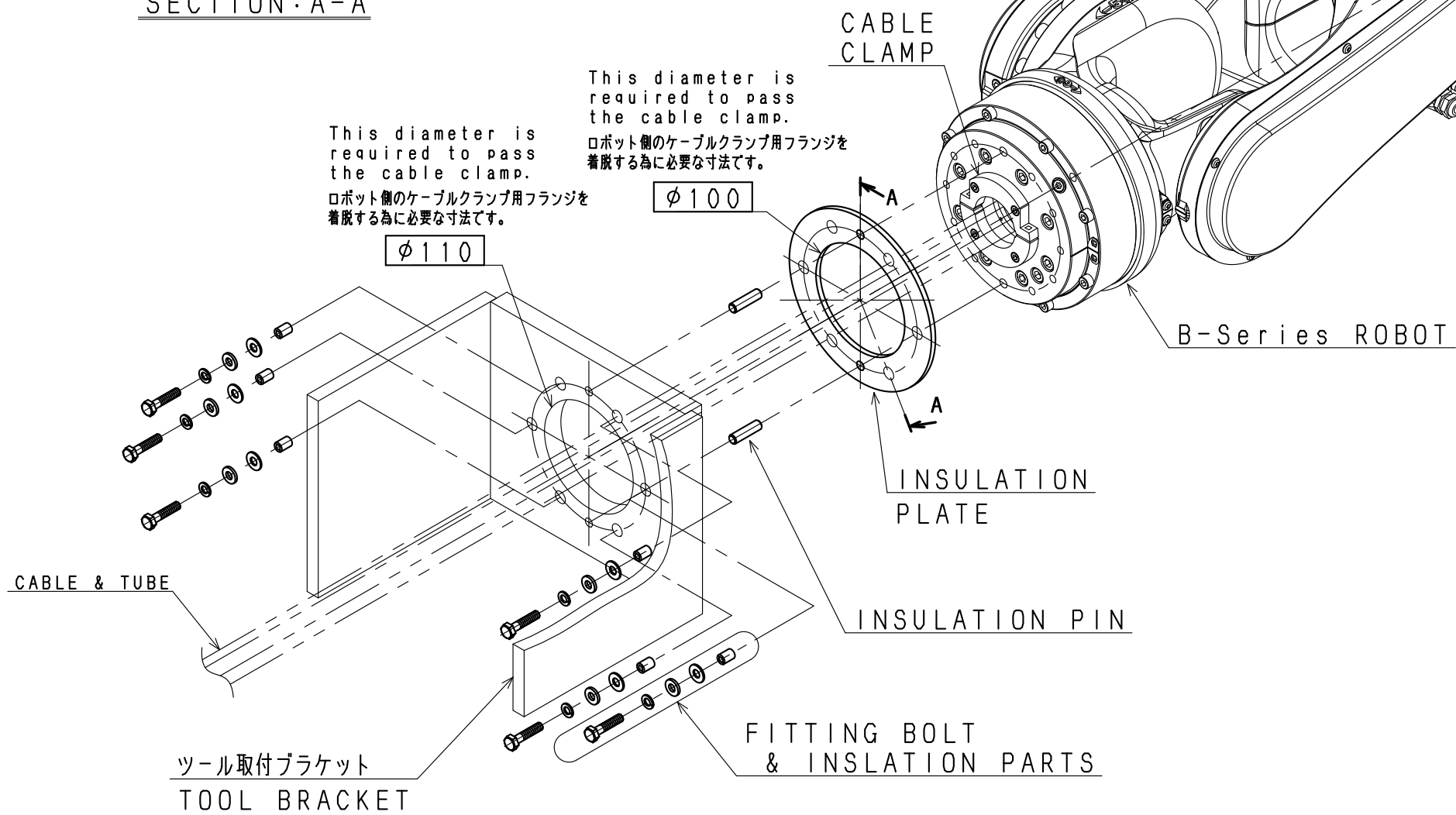
BX165N
WORKING RANGE



NULL POSITION OF THE ROBOT

ロボット標準姿勢

SECTION: A-A



This diameter is required to pass the cable clamp.
ロボット側のケーブルクランプ用フランジを着脱するに必要な寸法です。

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注記
1. 本図は、一例としてロボット手首へのツールの取付要領を示します。

NOTES
1. This figure shows as an example how to install a tool to the robot wrist.

B-Series ROBOT
TOOL INSTALLATION PROCEDURE
(ツール取付要領図)