

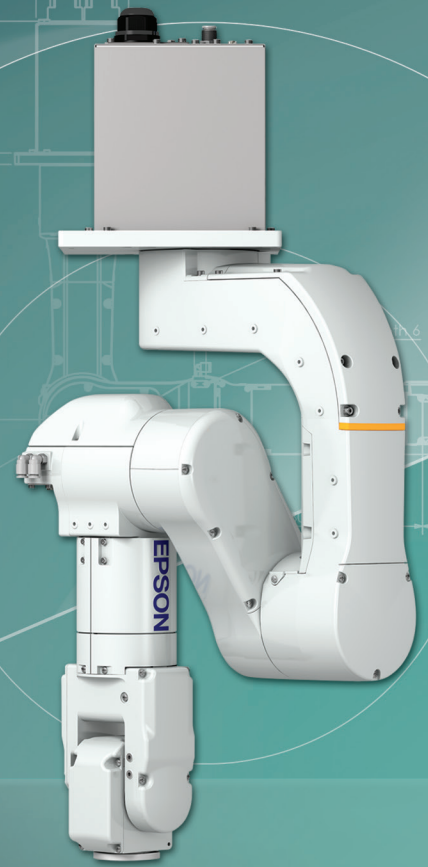
# Flexion N2

## 6-Axis Robots

### Space-Saving 6-Axis Robot with Revolutionary Design

- New Compact Folding Arm Technology – World's First\*
- Maximizes Motion Efficiency for Faster Cycle Times\*
- Reduces Required Workspace Area by up to 40% Versus Standard 6-Axis Robots\*
- Unique Tight Space Motion Capability Keeps Arm Extremities Out of the Way\*
- 450 mm Reach and 2.5 kg Maximum Payload

\*Features Exclusive to Epson's N-Series Technology



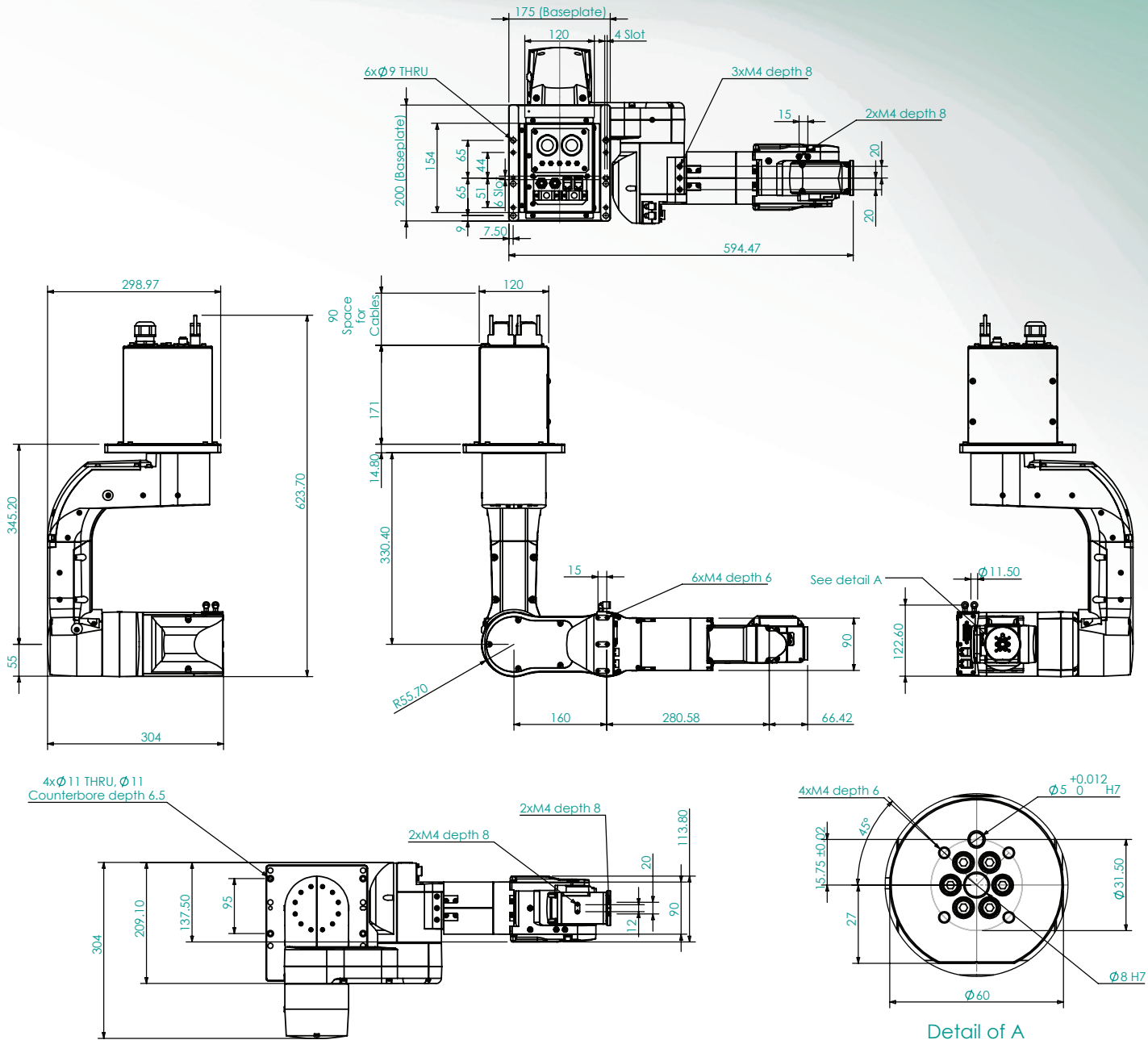
### Specifications

		N2-A450	
		Tabletop <sup>1</sup>	Ceiling
<b>Mounting type</b>		Tabletop <sup>1</sup>	Ceiling
<b>Degree of freedom</b>		6	
<b>Max. motion range</b>	<b>P point:</b> through the center of J4/J5/J6	450mm	
<b>Wrist flange surface</b>		532.2mm	
<b>Max. operating speed</b>	<b>Joint #1</b>	297 °/s	
	<b>Joint #2</b>	297 °/s	
	<b>Joint #3</b>	356°/s	
	<b>Joint #4</b>	356°/s	
	<b>Joint #5</b>	360°/s	
	<b>Joint #6</b>	360°/s	
<b>Weight (cable not included)</b>		19 kg	
<b>Repeatability</b>	<b>Joint #1-#6</b>	±0.02mm	
<b>Max. motion range</b>	<b>Joint #1</b>	±180°	
	<b>Joint #2</b>	±180°	
	<b>Joint #3</b>	±180°	
	<b>Joint #4</b>	±195°	
	<b>Joint #5</b>	±130	
	<b>Joint #6</b>	±360°	
<b>Payload<sup>2</sup></b>	<b>Rated</b>	1 kg	
	<b>Maximum</b>	2.5 kg	
<b>Allowable moment of inertia<sup>3</sup></b>	<b>Joint #4</b>	0.2 kg•m <sup>2</sup>	
	<b>Joint #5</b>	0.2 kg•m <sup>2</sup>	
	<b>Joint #6</b>	0.08 kg•m <sup>2</sup>	
<b>Motor power consumption</b>	<b>Joint #1</b>	100W	
	<b>Joint #2</b>	100W	
	<b>Joint #3</b>	100W	
	<b>Joint #4</b>	30W	
	<b>Joint #5</b>	30W	
	<b>Joint #6</b>	15W	
<b>Installed wire for customer use</b>		15 wires (D-sub) 8 pin (RJ45) Cat 5e or equivalent (2 cables)	
<b>Installed pneumatic tube for customer use</b>		Ø6 mm pneumatic tubes (2 tubes), Allowable pressure: 0.59 Mpa (6 kgf/cm <sup>2</sup> ) (89 psi)	
<b>Installation environment</b>		Standard	
<b>Available controllers</b>		RC700A	
<b>Safety standards</b>		CE, ANSI/RIA15.06-2012	

1 Manipulators are set to "Ceiling mounting" at shipment. To use the manipulators as "Table Top mounting", you need to change the model settings.

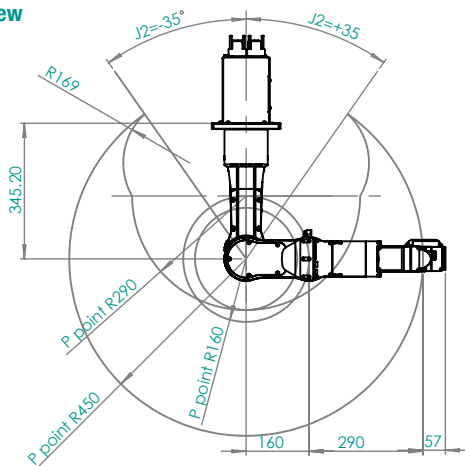
2 Do not exceed the maximum payload.

3 If the center of gravity is at the center of each arm. If the center of gravity is not at the center of each arm, set the eccentric quantity using INERTIA command.

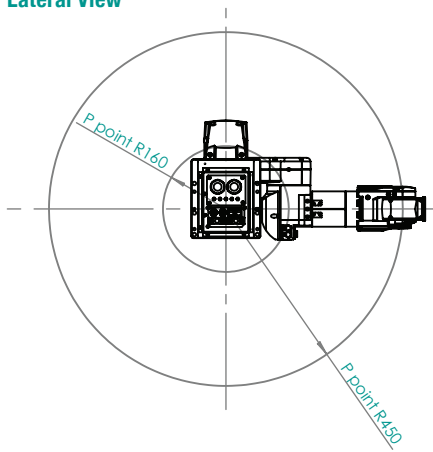


Motion Range

Top View



Lateral View



Front View

