



Z-Arm 4160B

Product Manual

Industrial Robot / Collaborative Robot / Electric Gripper/
Intelligent Actuator / Automation Solution



Z-Arm 4160B/Z-Arm XX60B



High Precision

Repeatability
 $\pm 0.02\text{mm}$

Z-axis Customization

0.1-0.8m

High payload

Standard payload:4kg
Max payload:5kg

High Speed

Standard payload:5kg
Max linear speed 2m/s

Competitive Price

Industrial-level quality
Consumptive price

Model Definition

Z-Arm T4160BN0-A0M1-FXXX-01

T	41	60	B	N	0	A0	M1
Blank: Four axis F: Five axis T: Three axis	If z-axis stroke is 410, here is 41	If robot arm span is 600, here is 60	B: High-end version Empty: Standard version	C: Collaborative N: Non-collaborative	0: Silver 1: Black	A0: Means two straight-through cables A2: Means two vacuum tubes	M1: Second arm motion range $\pm 164^\circ$ (rotate outwards) M2: Second arm motion range $15^\circ - 345^\circ$ (rotate inwards)
FXXX-01							
F: Non-standard customized option, if it is a standard product, it is blank XXX: Customer label number 01: version number							

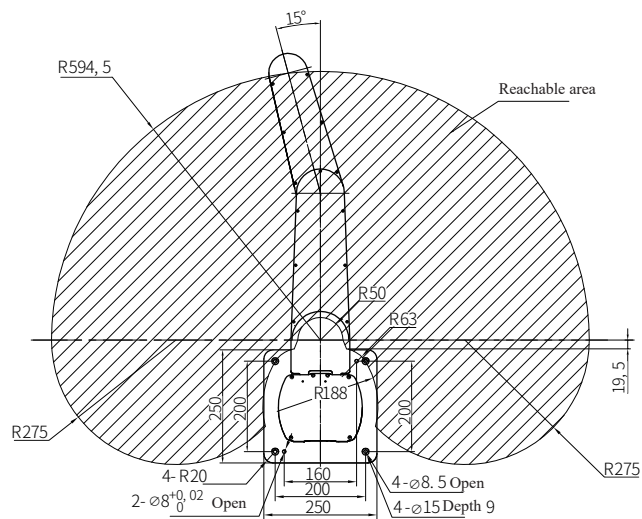
Specification

Z-Arm XX42 Collaborative Robot arm	Parameters
1 axis arm length	325mm
1 axis rotation angle	±90°
2 axis arm length	275mm
2 axis rotation angle	±164° Optional: 15°-345°
Z axis stroke	410mm (height can be customized)
R axis rotation range	±1080°without mechanical limit / ±170°with mechanical limit
Linear speed	2000mm/s (payload 4kg)
Repeatability	±0.02mm
Standard payload	4kg
Maximum payload	5kg
Degree of freedom	4
Power supply	220V/110V50-60HZ adapt to 48VDC peak power2000W
Communication	Ethernet
Z-axis can be customized in height	0.1m-0.8m
Electrical interface reserved	Standard configuration: 4*23awg (unshielded) wires from the socket panel through the lower arm cover Optional: 2 φ4 vacuum tubes through the socket panel and flange
Optional accessories	Z-EFG-8S/Z-EFG-12/Z-EFG-20/Z-EFG-20S/Z-EFG-20F/Z-ERG-20C/ Z-EFG-30/Z-EFG-50/Z-EFG-100, the fifth axis, 3D painting
Use environment	Ambient temperature: 0-45°C Humidity: RH20-80 (no frost)
I/O port digital input (isolated)	9+3+ forearm extension (8 in 8 out; Gripper dedicated port: pulse or 485)
I/O port digital output (isolated)	9+3+ forearm extension (8 in 8 out; Gripper dedicated port: pulse or 485)
I/O port analog input (4-20mA)	/
I/O port analog output (4-20mA)	/
Robot arm height	860mm
Robot arm weight	410mm stroke net weight 36.5kg
Base size	250mm*250mm*15mm
Distance between base fixing holes	200mm*200mm with four M8*20 screws
Collision detection	/
Drag teaching	/
Emergency stop	√
Debugging/Online upgrade (USB port)	√

Technical drawing of a robot arm with a circular reachable area. The drawing includes the following labels and dimensions:

- Reachable area:** The large shaded circular region.
- R600:** Label pointing to the top of the arm structure.
- R98:** Label pointing to the upper joint of the arm.
- R63:** Label pointing to the lower joint of the arm.
- R188:** Label pointing to the end effector.
- R275:** Label pointing to the base of the arm.
- Dimensions:**
 - Vertical dimensions: 250, 200, 200, 250.
 - Horizontal dimensions: 160, 200, 250.
- Arm Configuration:**
 - 4-R20
 - 2- $\phi 8^{+0.02}_0$ Open
 - 4- $\phi 8.5$ Open
 - 4- $\phi 15$ Depth 9

Figure 1: Dimensions of the robot arm. The diagram shows a side view of a robotic arm with various dimensions and labels. The total height is 860. The base width is 275. The distance from the base to the first joint is 325. The distance from the first joint to the end effector is 225. The end effector has a width of 82 ± 1. The base has a width of 492. The base is labeled with 'USB port', 'Power supply', 'I/O port', 'Straight line port', 'Switch', 'Ethernet cable port', and 'Emergency stop port'. The end effector has two 'DB15' ports.

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Interface Introduction

The mounting interfaces of the Z-Arm 4160B manipulator are distributed in 2 positions, the side of the manipulator base (defined as A) and the bottom surface of the end arm (defined as B).

Interface Diagram and Instructions for Use

1. General schematic diagram of the base interface at A (as shown in Figure 1)

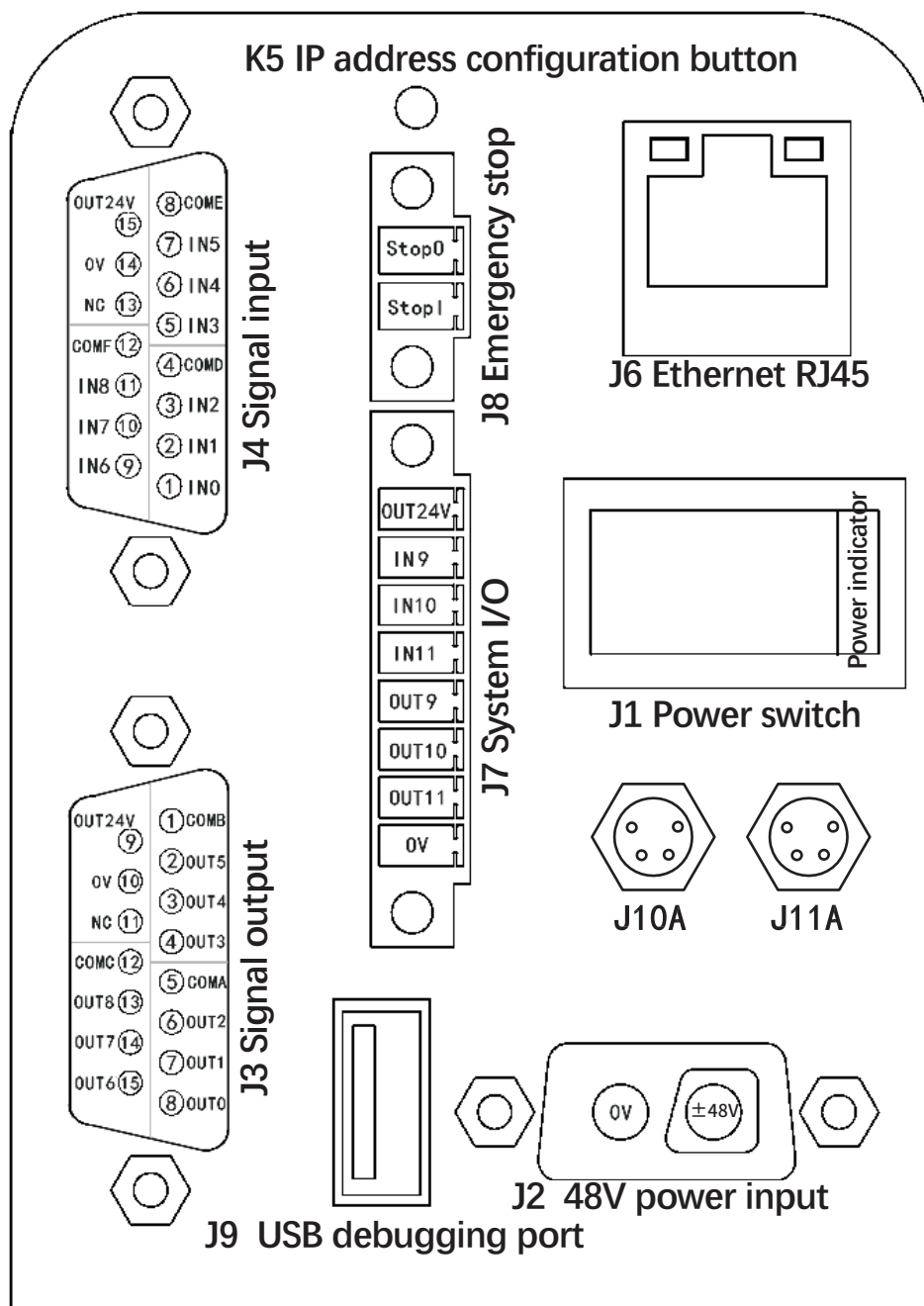


Figure 1

2. Figure 1 interface definition description

- (1) J1 is the power switch interface, which is used to control the power on and off;
- (2) J2 is the power input port, 48V DC voltage input;
- (3) J3 is the I/O output port, with 9 groups of internal optocoupler isolated NPN outputs;
- (4) J4 is the user I/O input port, with 9 groups of internal optocoupler isolated inputs;
- (5) K5 is the IP address configuration button of robot arm , press and hold the button to power on, the robot arm enters the IP address configuration state;
- (6) J6 is the Ethernet port, used for computer communication;
- (7) J7 is the system I/O, there are 3 groups of common ground optocoupler isolation input and output inside;
- (8) J8 is the emergency stop interface, which can be connected to the emergency stop button to control the emergency stop function of the robotic arm;
- (9) J9 is the USB debugging port;
- (10) J10A is a 4-core straight through wire aviation plug to the end or straight air pipe $\varnothing 4$ to the end (optional);
- (11) J11A is a 4-core straight through wire aviation plug to the end or straight air pipe $\varnothing 4$ to the end (optional).

3.The internal circuit design of the J3 and J4 interfaces (as shown in Figure 2)

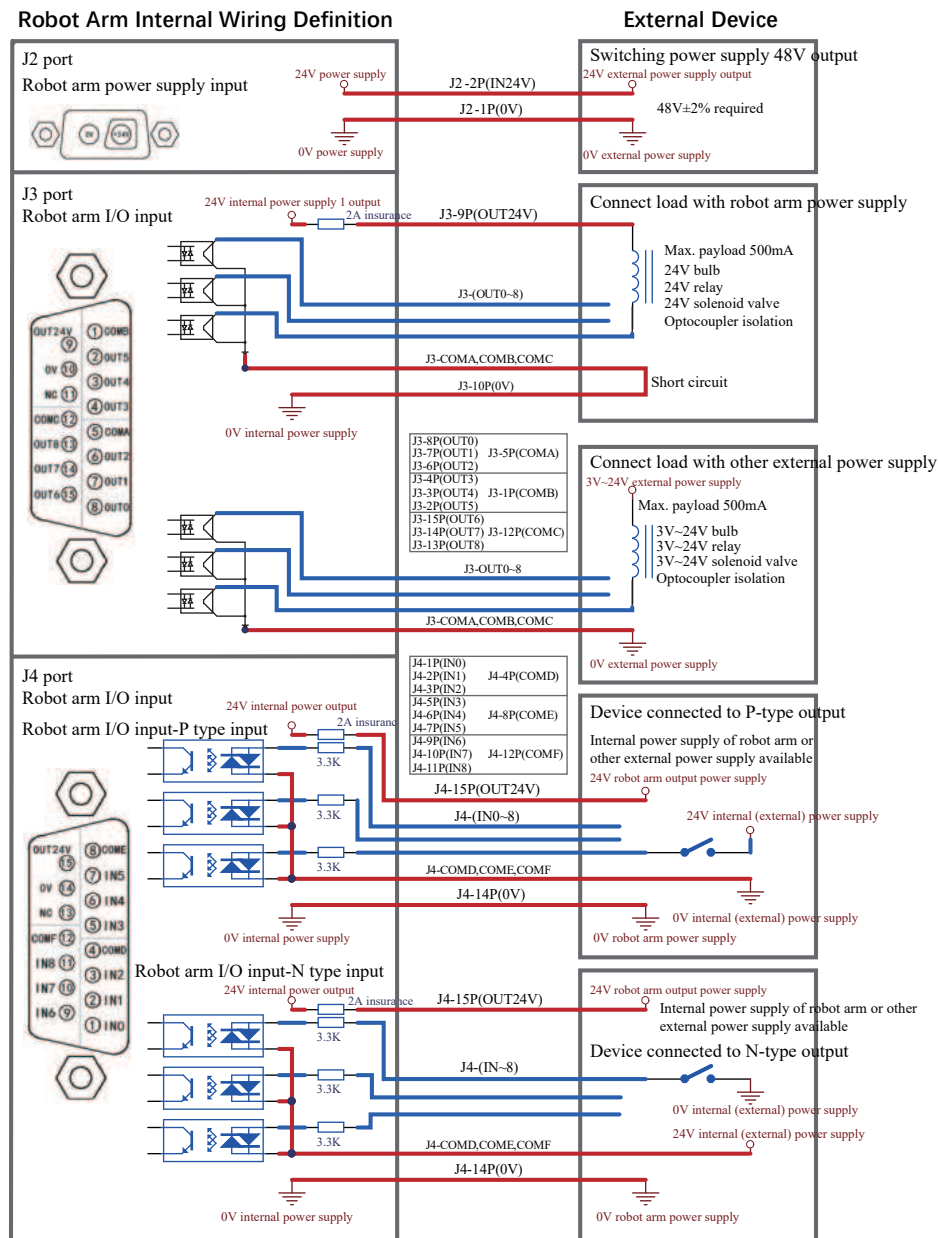


Figure 2

4. J7, J8 interface male socket pin definition (as shown in Figure 3)

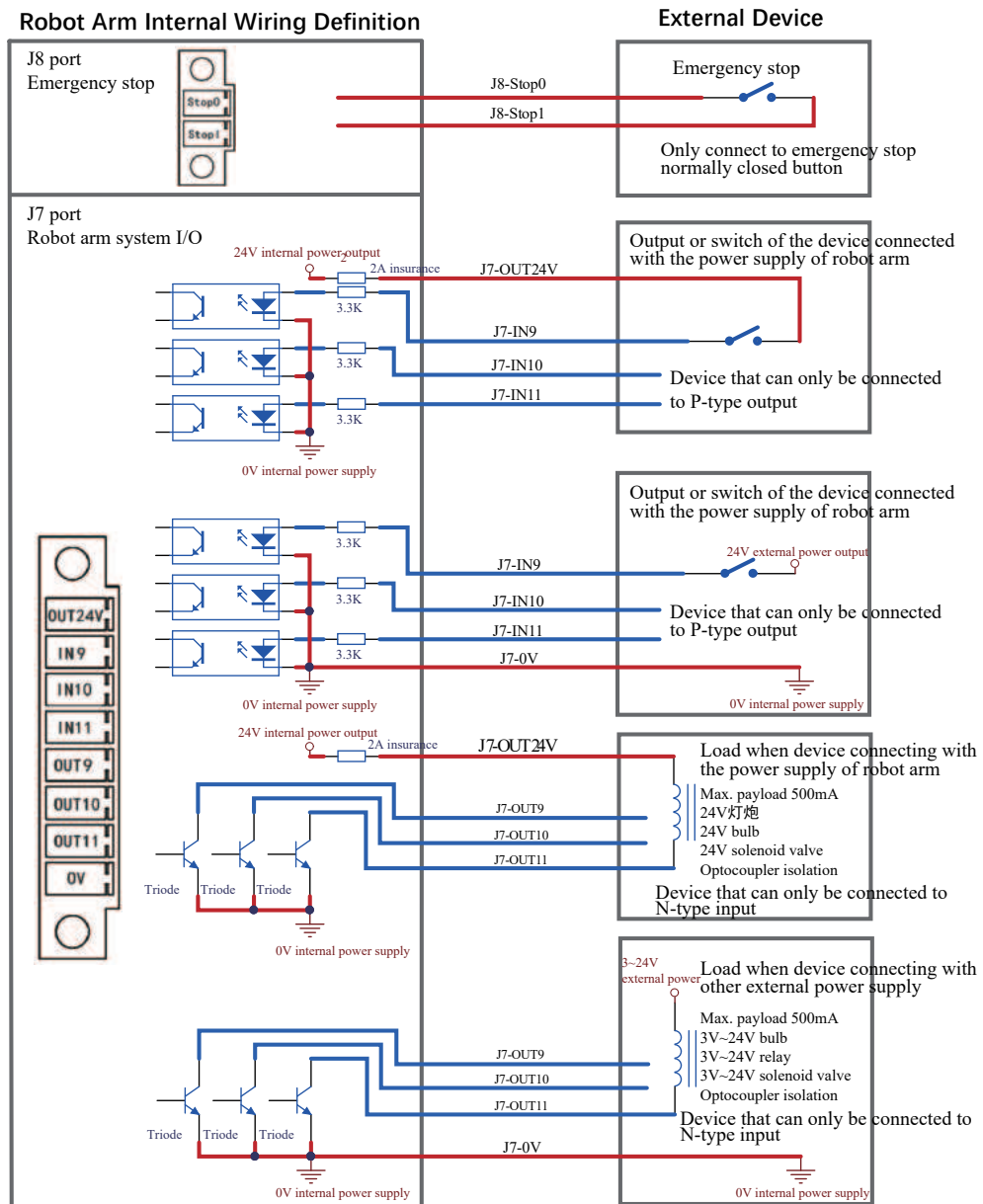


Figure 3

5. General schematic diagram of the I/O interface panel at B (as shown in Figure 4)

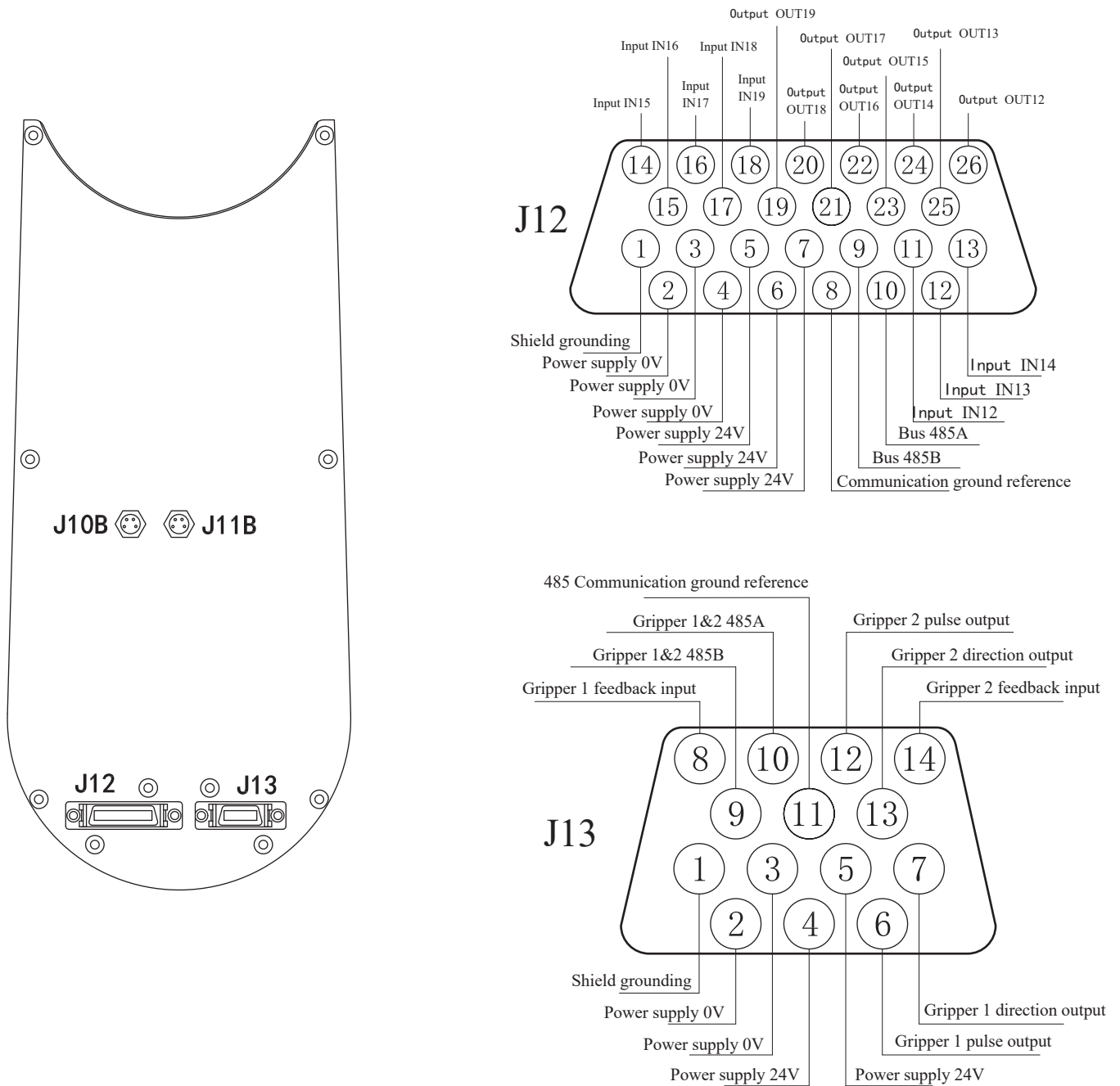


Figure 4

6. Interface definition description at B

- (1) J10B is a 4-core straight through wire aviation plug to the end of J10A;
- (2) J11B is a 4-core straight through wire aviation plug to the end of J11A.

7. J12 interface internal circuit design (as shown in Figure 5)

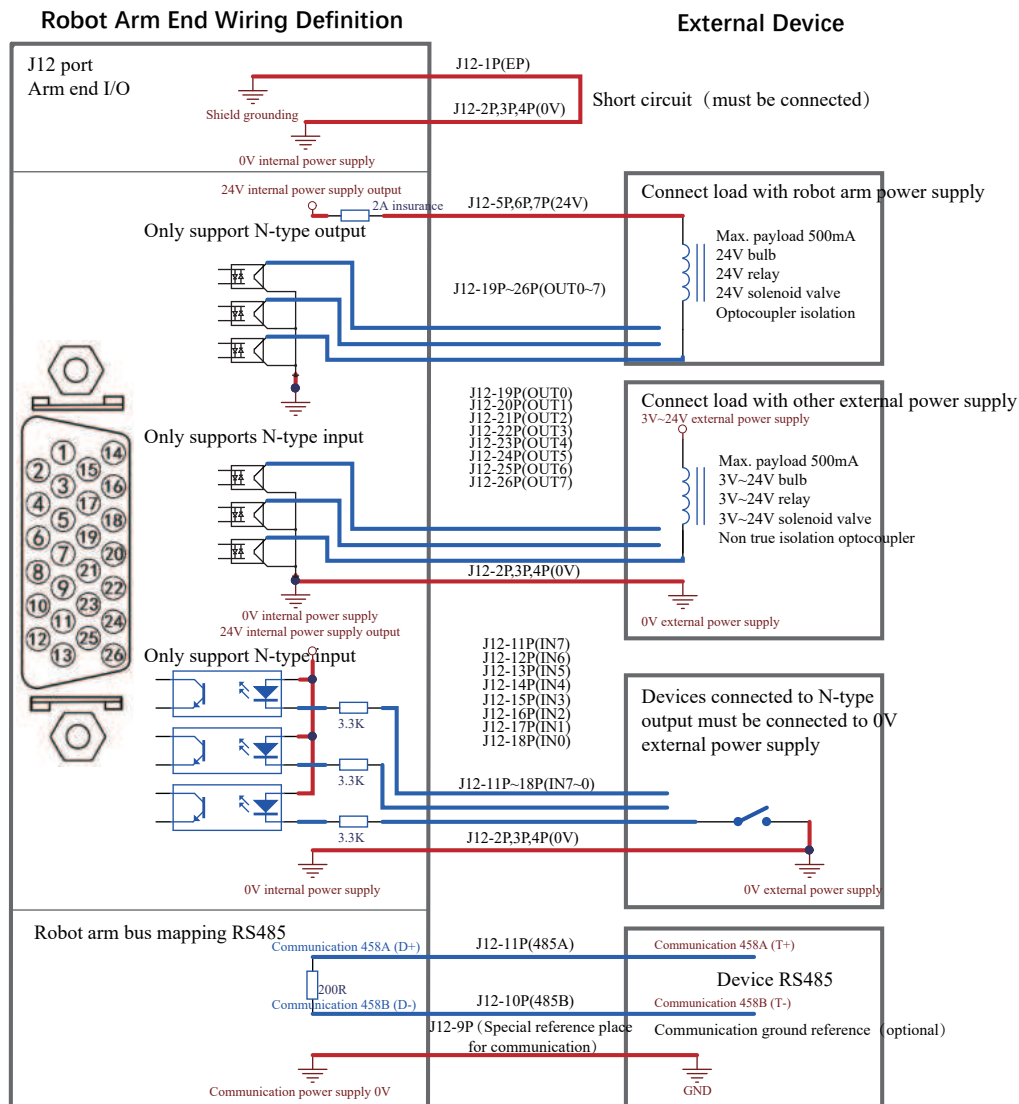


Figure 5

8. J13 interface DB9 male sock with needle pin definition (as shown in Figure 6)

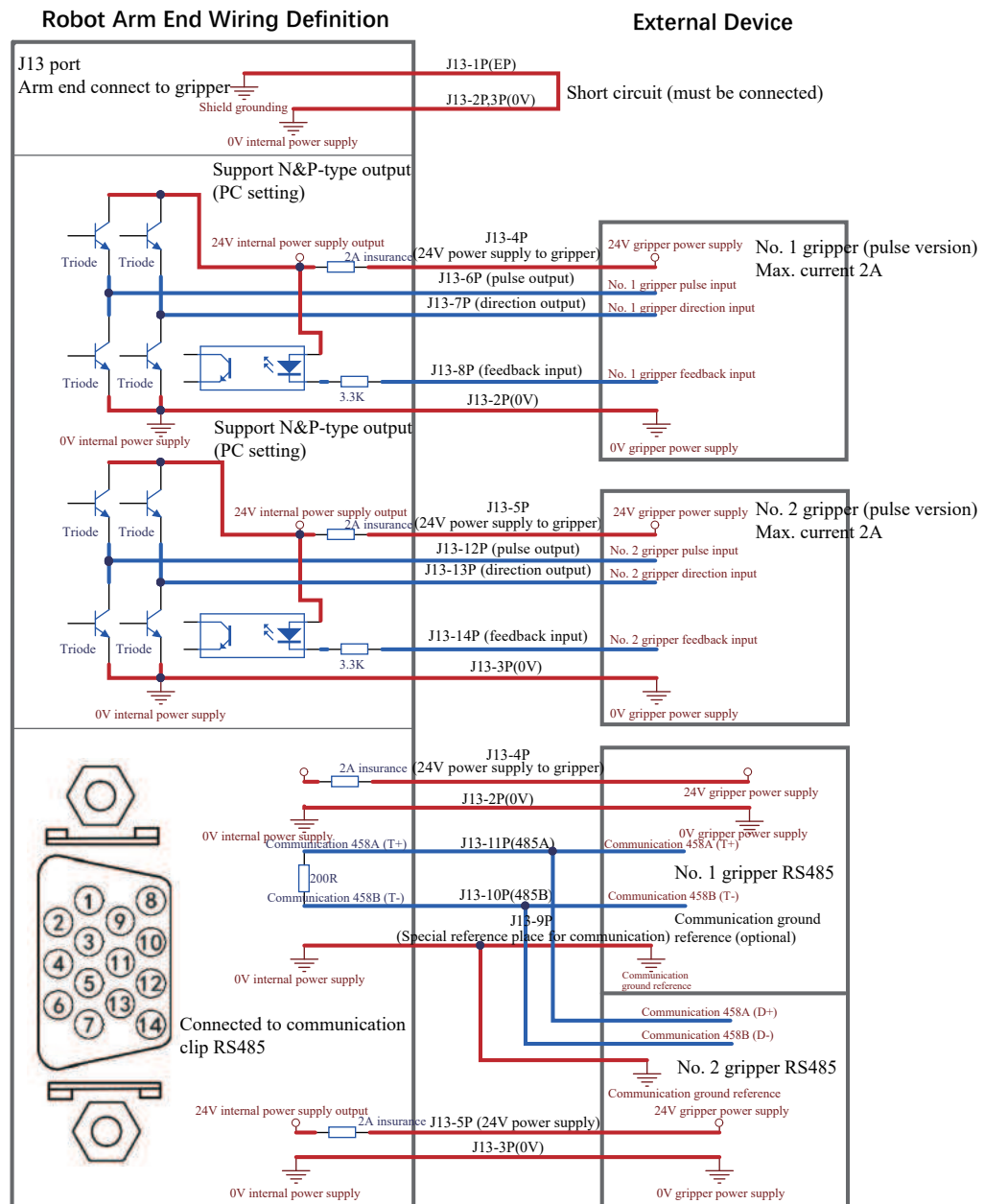


Figure 6

9. Wide I/O Board Diagram (as shown in Figure 7)

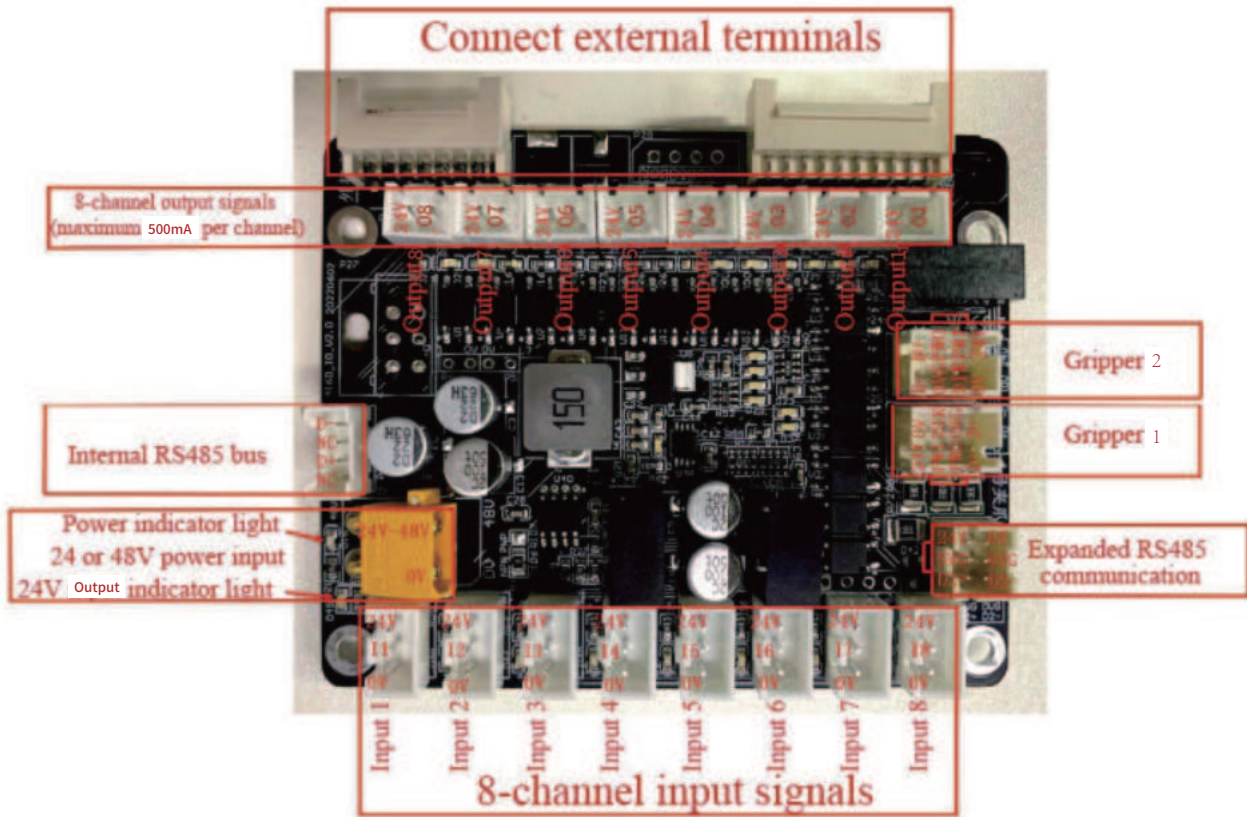


Figure 7

IO board wiring definition

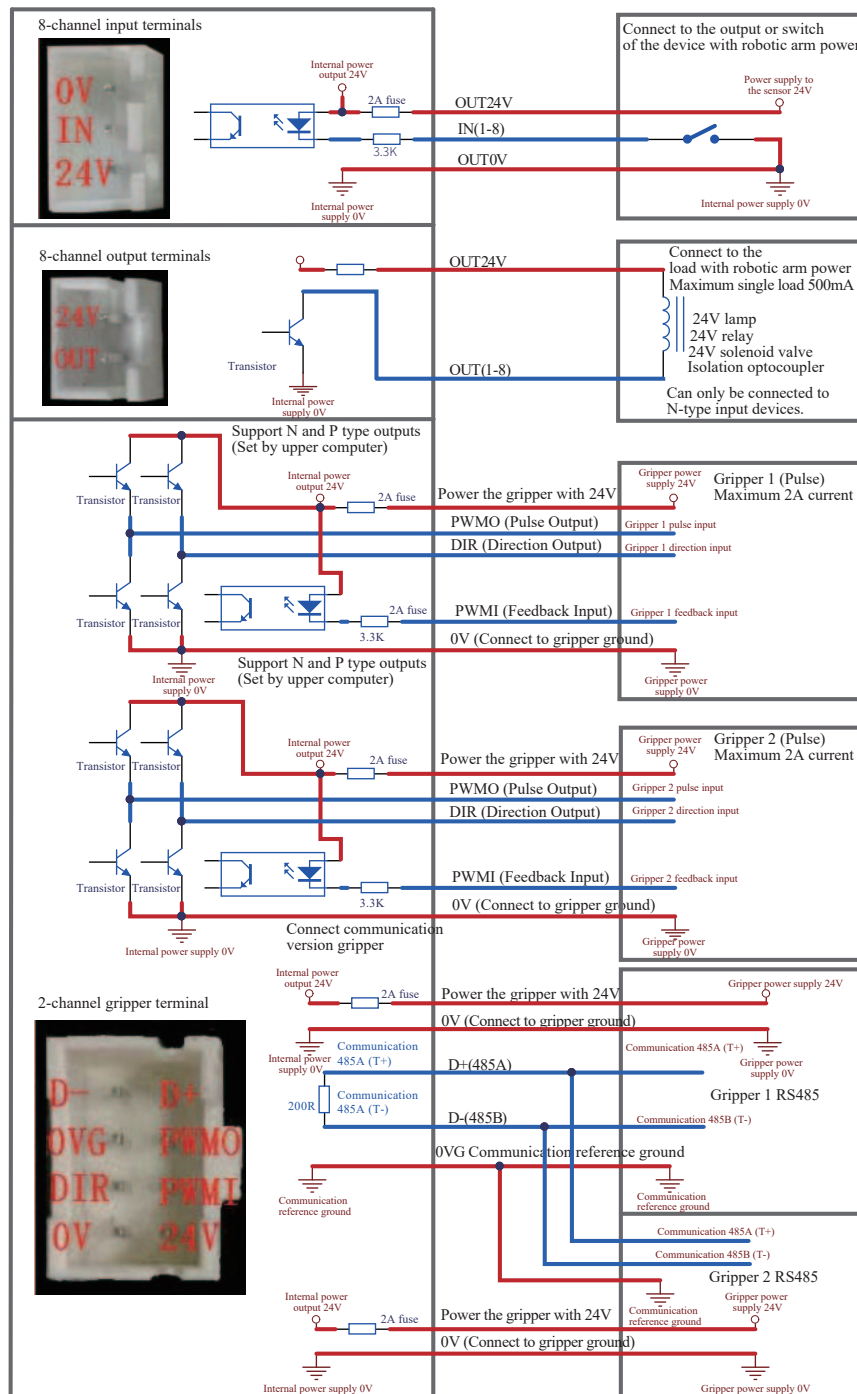


Figure 8

Precautions

1. Payload inertia

The payload center of gravity and the recommended payload range with the Z axis movement inertia are shown in Figure 9.

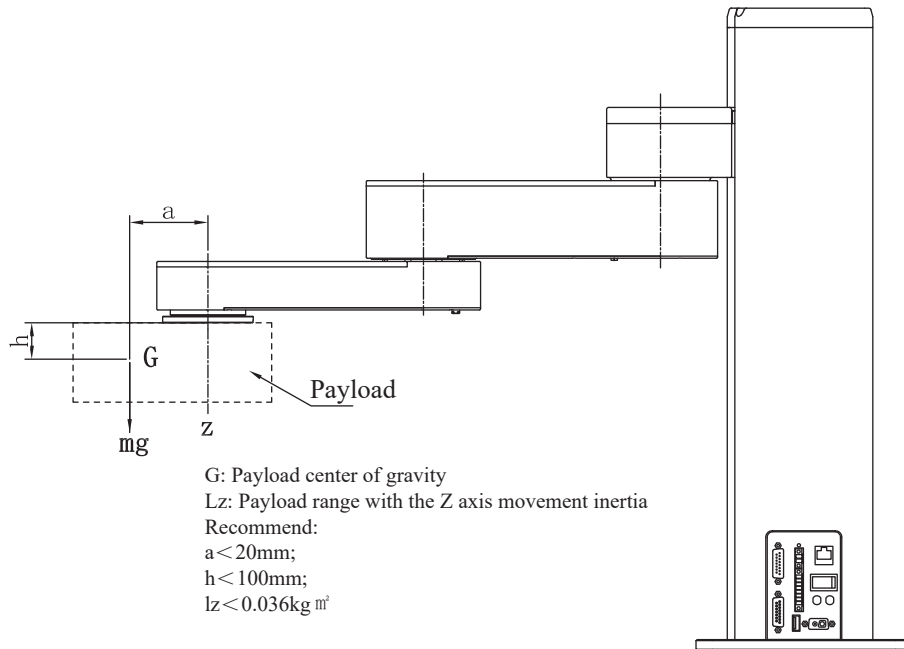


Figure 9

2. Collision force

Trigger force of horizontal joint collision protection: XX60B non-collaboration

3. Z-axis external force

The external force of the Z axis shall not exceed 120N (as shown in Figure 10).

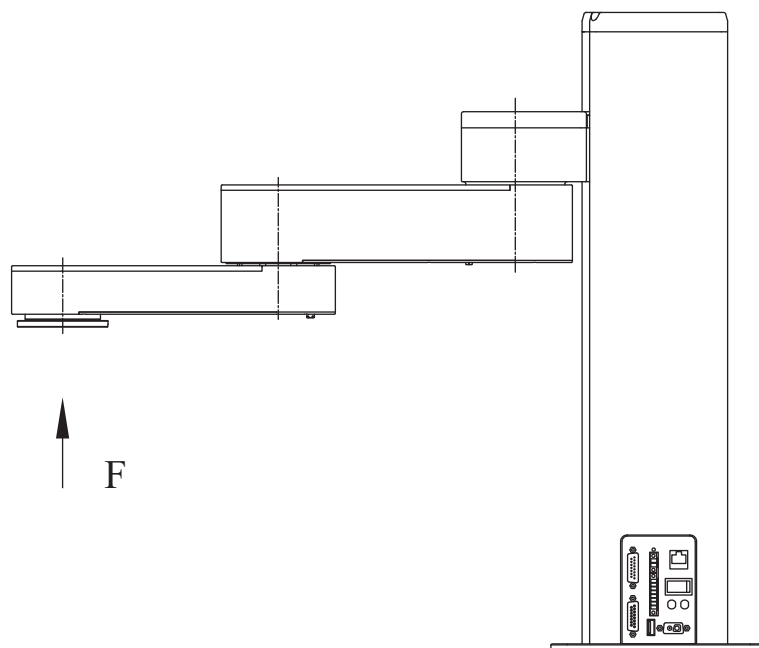


Figure 10

4. Notes for installation of customized Z axis, see Figure 11 for details.

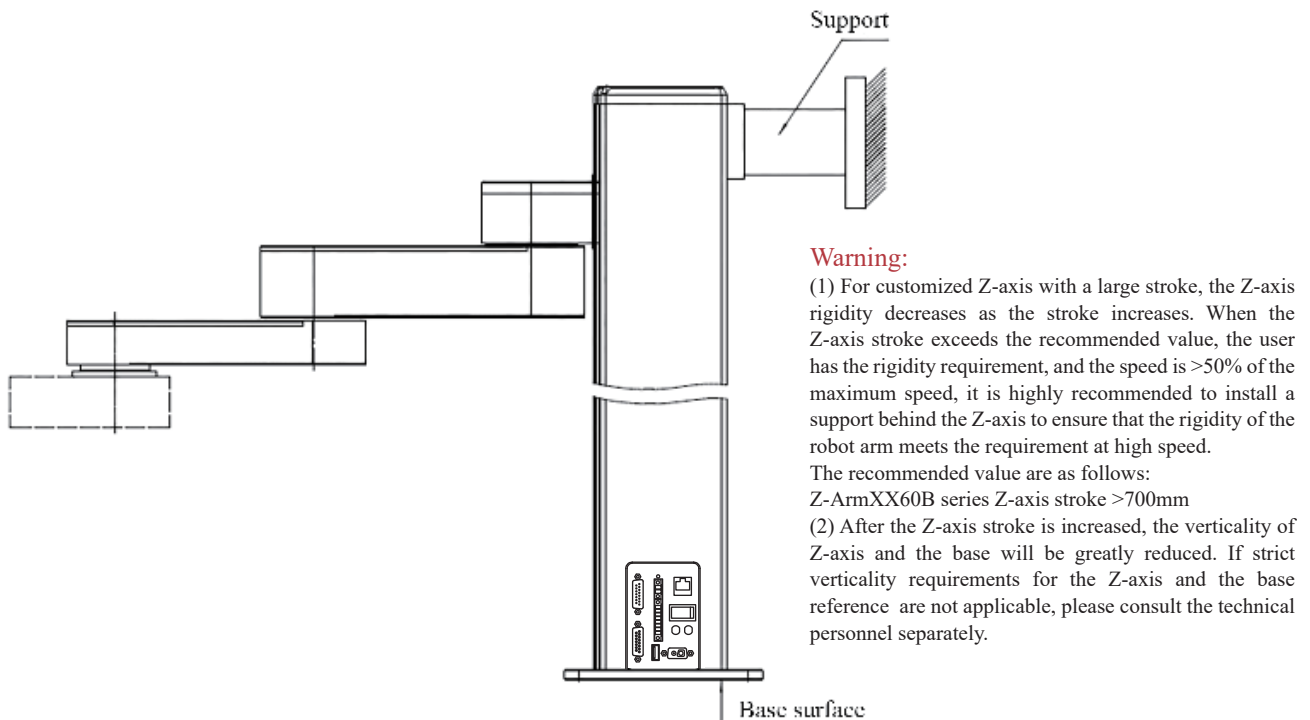


Figure 11

5. Power cable hot-plugging forbidden. Warning when the positive and negative poles of the power supply are reversed (as shown in Figure 10).

6. Do not press down the horizontal arm when the power is off (as shown in Figure 12).

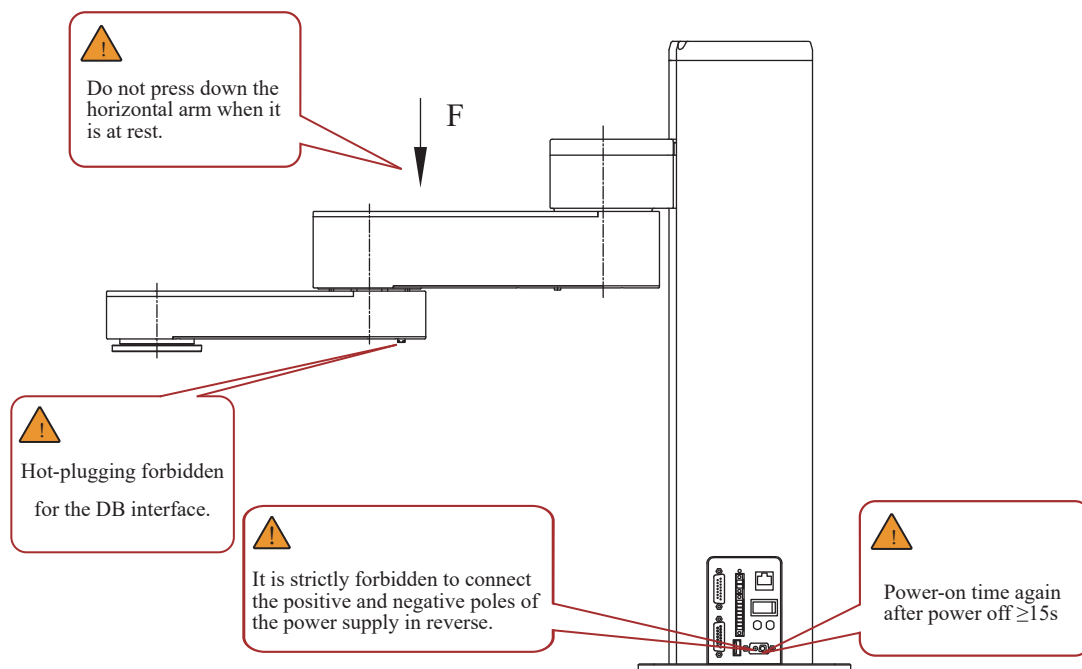


Figure 12

DB15 Connector Recommendation

Recommended model: Gold-plated male head with ABS shell YL-SCD-15M

Gold-plated female with ABS shell YL-SCD-15F

Size Description: 55mm*43mm*16mm

(Refer to Figure 13)



Figure 13

Robot Arm Compatible Grippers Table

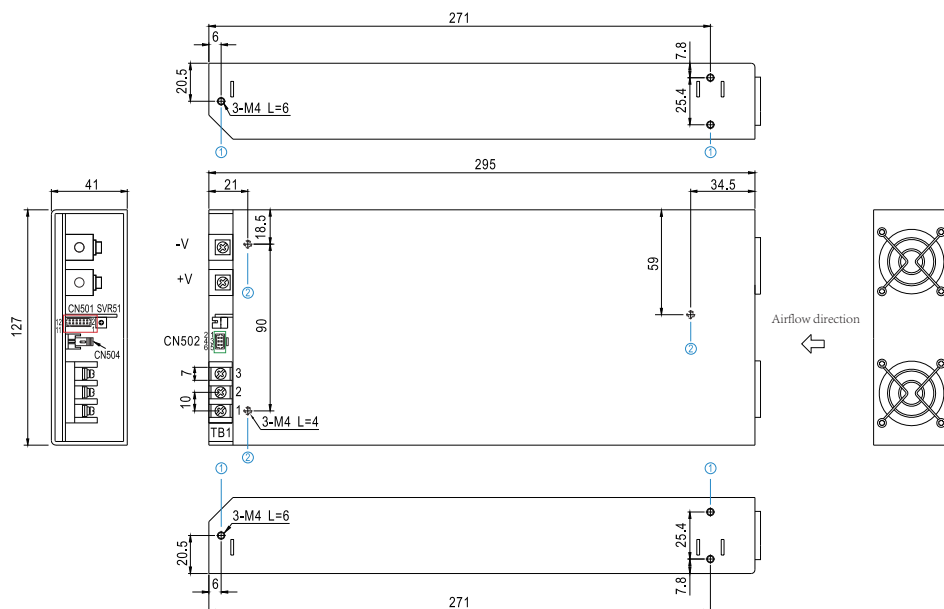
Robot arm Model No.	Compatible grippers
XX60B	Z-EFG-8S/Z-EFG-12/Z-EFG-20/Z-EFG-20S/Z-EFG-30/ Z-EFG-50/, the fifth axis, 3D painting

Power Adapter Installation Size Diagram

XX60B configuration 48V 2000W PSP-2000-SPEL-CN power supply

Machine case number: 952D Unit: mm

■ structure size



※ Pin Definition of AC Input End

Pin Number	Pin Function	Picture	Tightening torque
1	AC/N		18Kgf-cm
2	AC/L		
3	FG		

※ Pin Definition of DC Input End

Pin Function	Picture	Tightening torque
+V, -V		10Kgf-cm

Instructions

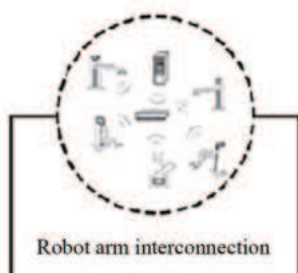
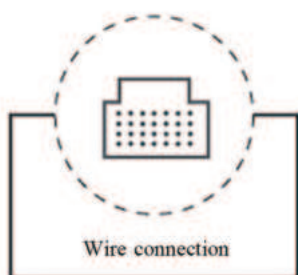
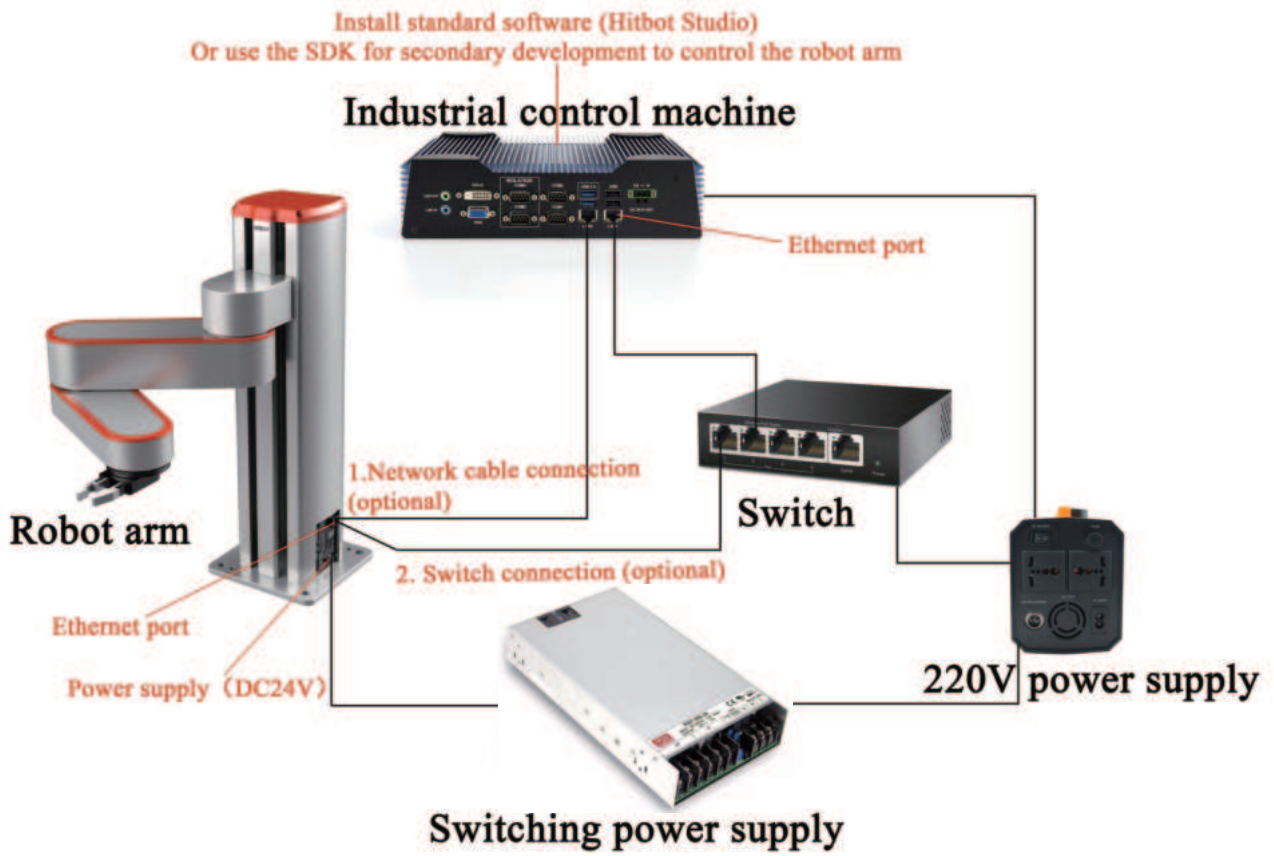


Diagram of the External Use Environment of the Robot Arm





M a k i n g A u t o m a t i o n E a s i e r

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