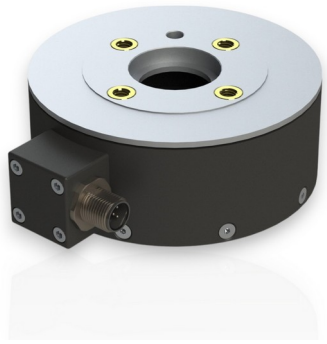
6-Axis Force Sensor F6D100-50e 600N/60Nm

Item number: 8185



The multi-component sensor F6D100 is used for force and torque measurement in three mutually perpendicular axes.

The multi-component sensor F6D100 is equipped with mounting flanges according to DIN EN ISO 9409-1 for industrial robots. The measuring flange of the sensor contains tapped holes M6 on the same pitch circle. The F6D force / torque sensor can be mounted to the robot flange without additional adapters, making it particularly flat and light compared to the K6D series sensors.

The evaluation of the force and moment load is carried out with an integrated electronics type GSV-6.

The sensors are made of an aluminum alloy.

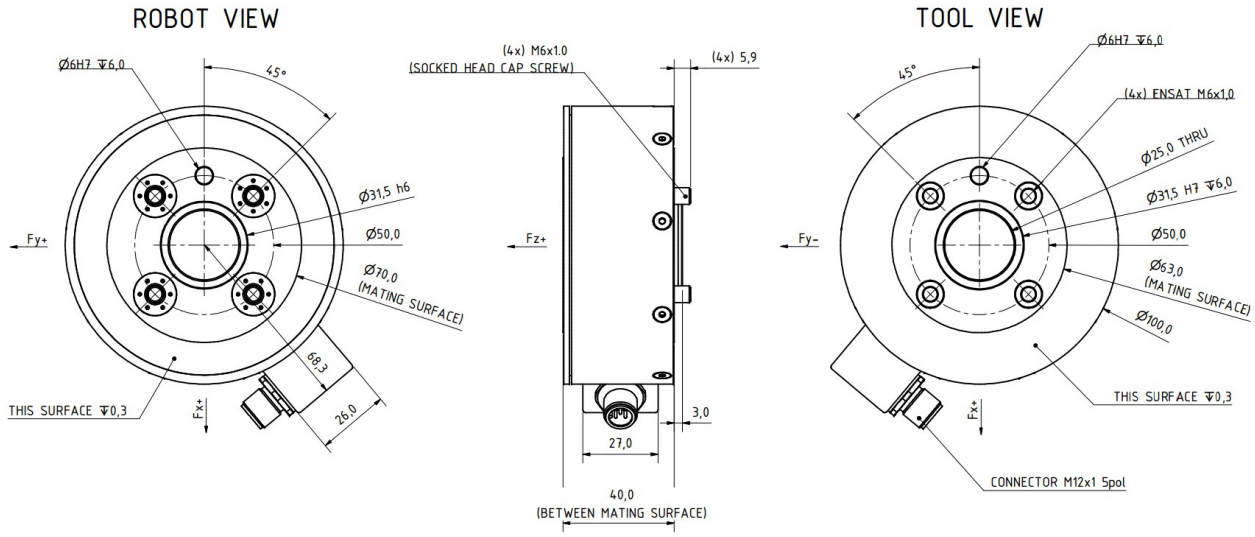
Our partner IPR – Intelligente Peripherien für Roboter GmbH offers solutions for applications of force / torque sensors.

ME-Meßsysteme GmbH
Eduard-Maurer-Str. 9
DE-16761 Hennigsdorf

Tel: +49 (0)3302 8982 4 10
Mail: vertrieb@me-systeme.de
Web: www.me-systeme.de

Stand: 20.03.2026

Technical Drawing



ME-Meßsysteme GmbH
Eduard-Maurer-Str. 9
DE-16761 Hennigsdorf

Tel: +49 (0)3302 8982 4 10
Mail: vertrieb@me-systeme.de
Web: www.me-systeme.de

Stand: 20.03.2026

Technical Data

Basic Data		Unit
Type	6-axis force sensor	
Force direction	Tension/Compression	
Rated force Fx	600	N
Rated force Fy	600	N
Rated force Fz	1200	N
Force introduction	Internal thread	
Dimension 1	4xM6	
Sensor Fastening	Through-hole	
Dimension 2	M6	
Operating force	200	%FS
Rated displacement	0.05	mm
Twist	0.04	rad
Material	alluminum-alloy	
Height	40	mm
Length or Diameter	100	mm
Rated torque Mx	60	Nm
Rated torque My	60	Nm
Rated torque Mz	60	Nm
Breaking force	600	%FS

ME-Meßsysteme GmbH
Eduard-Maurer-Str. 9
DE-16761 Hennigsdorf

Tel: +49 (0)3302 8982 4 10
Mail: vertrieb@me-systeme.de
Web: www.me-systeme.de

Stand: 20.03.2026

Electrical Data		Unit
Input resistance	1000	Ohm
Tolerance input resistance	50	Ohm
Output resistance	1000	Ohm
Tolerance output resistance	50	Ohm
Insulation resistance	2	GOhm
Rated range of excitation voltage from	2.5	V
Rated range of excitation voltage to	5	V
Operating range of excitation voltage from	1	V
Operating range of excitation voltage to	10	V
Zero signal	1	mV/V
Rated output	0.4	mV/V / FS

Eccentricity and Crosstalk	Unit

Accuracy Data		Unit
Accuracy class	1	
Relative linearity error	0.1	%FS
Relative zero signal hysteresis	0.1	%FS
Temperature effect on zero signal	0.1	%FS/K
Temperature effect on characteristic value	0.05	%RD/K
Relative creep	0.1	%FS
Relative repeatability error	0.5	%FS

Measuring Frequency		Unit
Data frequency from	10	Hz
Data frequency to	800	Hz
Sampling frequency	12	kHz

ME-Meßsysteme GmbH
Eduard-Maurer-Str. 9
DE-16761 Hennigsdorf

Tel: +49 (0)3302 8982 4 10
Mail: vertrieb@me-systeme.de
Web: www.me-systeme.de

Stand: 20.03.2026

Supply		Unit
Supply voltage from	18	V
Supply voltage to	28	V
Current consumption from	100	mA
Current consumption to	250	mA

Environmental Data		Unit
Rated temperature range from	-10	°C
Rated temperature range to	70	°C
Operating temperature range from	-10	°C
Operating temperature range to	85	°C
Storage temperature range from	-10	°C
Storage temperature range to	85	°C
Environmental protection	IP64	

Abbreviation : RD: „Reading"; FS: „Full Scale";The application of a calibration matrix is required for the determination of the forces Fx, Fy, Fz and moments Mx, My, and Mz from the 6 measurement channels, and to compensate for the crosstalk.
The calibration data are individually determined and documented for the sensor.
The measurement error is expressed individually by the specification of the extended measurement uncertainty (k = 2) for the forces Fx, Fy, Fz, and moments Mx, My, Mz.

Mounting

Pin configuration

Signal	Description	Wire color	PIN
CAN_GND	Mass CAN	brown	1
+24V	Operating voltage 24V	white	2
GND_24V	Mass operating voltage	blue	3

CAN_H	Can High	black	4
CAN_L	CAN Low	grey	5

Calibration matrix

The calibration matrix contains 36 calibration factors for calculating the forces and torques from the 6 output signals of the force sensor. A Labview vi is available for processing the calibration matrix

Measuring amplifier

The measuring amplifier GSV-8DS or GSV-8AS has 24-pole plug connector to connect the 6-axis froce/torque sensor. The mechanical forces and torques are calculated from 6 output voltages of each measuring channel with the calibration matrix.

Software

The GSVmulti software is included in delivery with measuring amplifiers GSV-8. The software allows the application of the calibration matrix and the displacement of the coordinate system to represent the torques around a freely selectable reference point.

To create your own software, a Labview VI is available.

Mounting instruction

The force is applied to a circular ring (Ø80-Ø40) on the live end of the sensor. The area inside the circular ring remains unloaded.

A center hole Ø6 serves to secure the angular position.

4x M6 external thread for mounting on robot flange (mounted with Allen key from the tool side, the screws are integrated in the F6D sensor, can not be lost);

4x M6 internal thread for mounting the tool (this flange corresponds again to the robot flange);

Summary: The sensor has M6 internal thread and M6 external thread.

Robotics solutions from IPR

Our robotics partner IPR offers solutions for applications of force / torque sensors in the areas of

- Mounting and handling technology
- Machine loading
- Foundry and blacksmith
- Cavity preservation
- Sealing and damping
- Lack and paint
- Services

IPR - Intelligente Peripherien für Roboter GmbH

Jakob-Dieffenbacher-Str. 4/2
75031 Eppingen
Deutschland

T: +49 7262 9239-100
F: +49 7262 9239-400
M: info@iprworldwide.com
W: www.iprworldwide.com

Stiffness Matrix

76.7 kN/mm	0.0	0.0	0.0	6137 kN	0.0
0.0	76.7 kN/mm	0.0	-6137 kN	0.0	0.0
0.0	0.0	760.1kN	0.0	0.0	0.0
0.0	-6137 kN	0.0	697.3 kNm	0.0	0.0
6137 kN	0.0	0.0	0.0	697.3 kNm	0.0
0.0	0.0	0.0	0.0	0.0	219.7 kNm

- The elements with the unit kN/mm describe the relationship between force and path.
- The elements with the unit kNm describe the relationship between torque and twist.
- The elements with the unit kN describe the relationship between torque and path (columns 1 to 3) or the relationship between force and twist (columns 4 to 6)