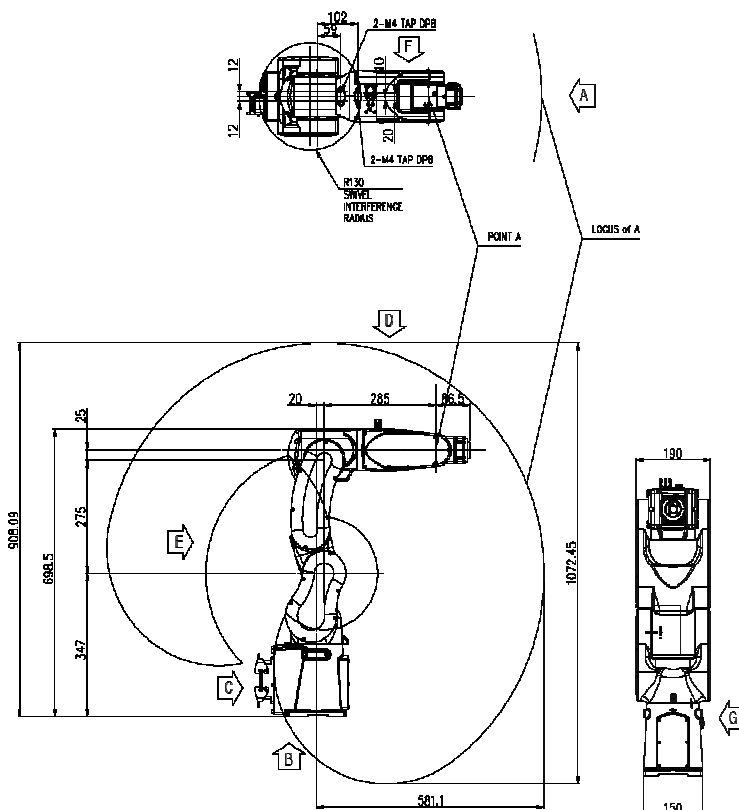


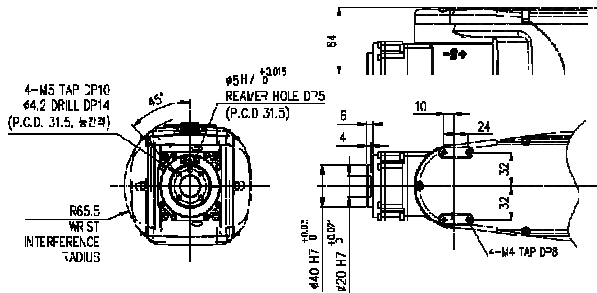
HH4

Installation method		Application	
Floor	●	Spot welding	
Ceiling		Arc welding	
Wall surface		Handling	●
		Assembly	
		Sealing	
		Painting	

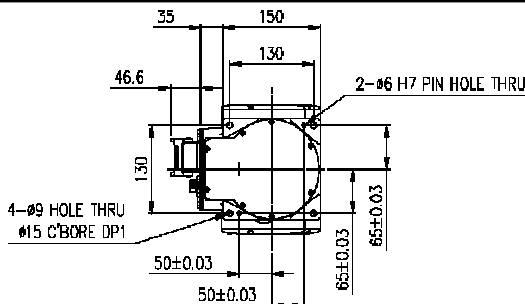


Item	Specification
Robot model	HH4
Payload	4 Kg
Structure	Articulated
Degree of freedom	6 axes
Drive system	AC SERVO MOTOR
Max. working envelope	A Swivel $\pm 2.967 \text{ rad } (\pm 170^\circ)$
	H Horizontal 55°
	V Vertical $+3.49 \sim -1.17 \text{ rad } (+200^\circ \sim -67^\circ)$
	R2 Rotation 2 $\pm 3.316 \text{ rad } (\pm 190^\circ)$
	B Bending $\pm 2.182 \text{ rad } (\pm 125^\circ)$
Wrist	R1 Rotation 1 $\pm 6.283 \text{ rad } (\pm 360^\circ)$
	A Swivel $8.378 \text{ rad/s } (480^\circ/\text{s})$
	H Horizontal $8.029 \text{ rad/s } (460^\circ/\text{s})$
Max. working speed	V Vertical $9.075 \text{ rad/s } (520^\circ/\text{s})$
	R2 Rotation 2 $9.599 \text{ rad/s } (550^\circ/\text{s})$
	B Bending $9.599 \text{ rad/s } (550^\circ/\text{s})$
Wrist torque	R1 Rotation 1 $17.453 \text{ rad/s } (1000^\circ/\text{s})$
	R2 Rotation 2 $8.8 \text{ N.m } (0.90 \text{ Kgf.m})$
	B Bending $8.8 \text{ N.m } (0.90 \text{ Kgf.m})$
	R1 Rotation 1 $4.9 \text{ N.m } (0.50 \text{ Kgf.m})$
Accuracy of position repeatability	$\pm 0.02 \text{ mm}$
Ambient Temperature	$0 \sim 40^\circ \text{ C } (273 \sim 313 \text{ K})$
Robot's Weight	22.4 Kg
Working envelope section area	0.72 m^2

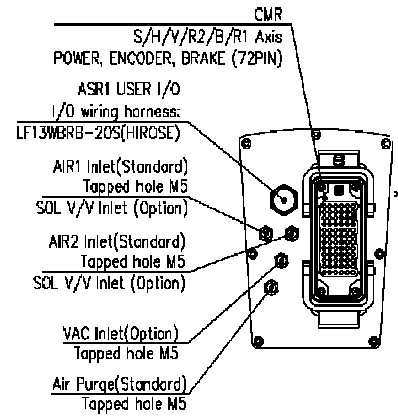
View A,F : Detailed drawing of the wrist attachment part



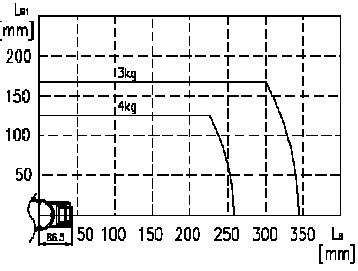
View B: Dimensional drawing for the floor installation of the body



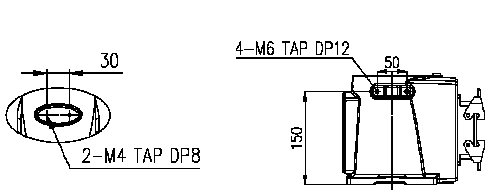
View C: Application cable connection part



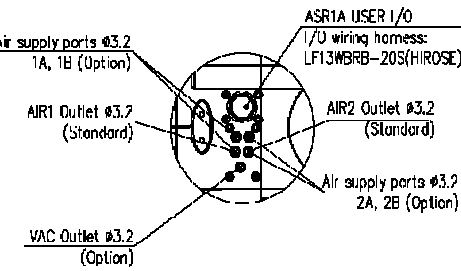
Wrist-axis torque line diagram



View E, G: Details of the application ancillary part attachment



View D: Application cable connection part



** For product improvement, some of the ratings, specifications, dimensions, etc. are subject to changes without notice.