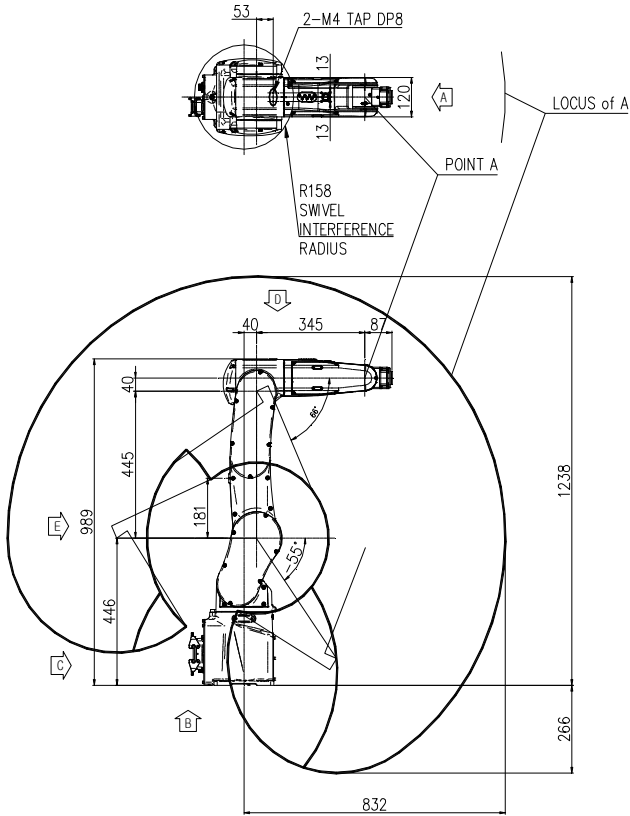


# HH8

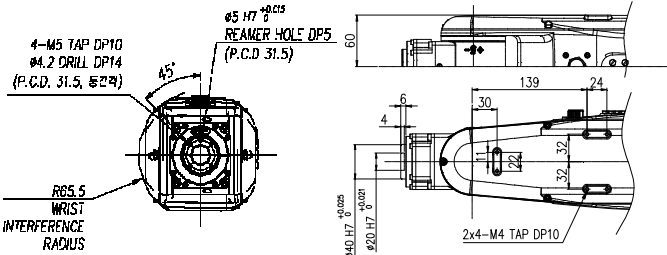
| Installation method |   | Application  |   |
|---------------------|---|--------------|---|
| Floor               | ● | Spot welding |   |
| Ceiling             |   | Arc welding  |   |
| Wall surface        |   | Handling     | ● |
|                     |   | Assembly     |   |
|                 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



**View A: Detailed drawing of the wrist attachment part**

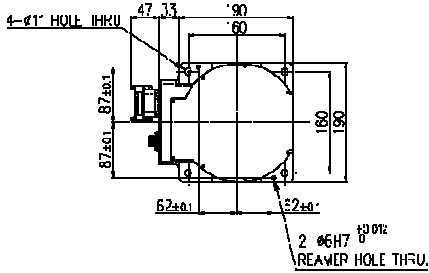
| Item                               |               | Specification                                 |  |
|------------------------------------|---------------|---|--|
| Robot model                        |               | HH8   |  |
| Payload                            |               | 8 Kg  |  |
| Structure                          |               | Articulated                                   |  |
| Degree of freedom                  |               | 6 axes  |  |
| Drive system                       |               | AC SERVO MOTOR                                |  |
| Max. working envelope              | A r m*        | S Swivel                                      | $\pm 2.967$ rad ( $\pm 170^\circ$ )                    |
|                                    |               | H Horizontal                                  | $55^\circ$   |
|                                    |               | V Vertical                                    | $+3.71 \sim -1.22$ rad ( $+213^\circ \sim -70^\circ$ ) |
|                                    | Wrist         | R2 Rotation 2                                 | $\pm 3.316$ rad ( $\pm 190^\circ$ )                    |
|                                    |               | B Bending                                     | $\pm 2.356$ rad ( $\pm 135^\circ$ )                    |
| Max. working speed                 | A r m         | S Swivel                                      | $7.941$ rad / s ( $455^\circ$ / s)                     |
|                                    |               | H Horizontal                                  | $6.719$ rad / s ( $385^\circ$ / s)                     |
|                                    |               | V Vertical                                    | $9.075$ rad / s ( $520^\circ$ / s)                     |
|                                    | Wrist         | R2 Rotation 2                                 | $9.599$ rad / s ( $550^\circ$ / s)                     |
|                                    |               | B Bending                                     | $9.599$ rad / s ( $550^\circ$ / s)                     |
| Wrist torque                       | R1 Rotation 1 | $17.453$ rad / s ( $1000^\circ$ / s)          |  |
|                                    | R2 Rotation 2 | $17$ N.m (1.73 Kgf.m)                         |  |
|                                    | B Bending     | $17$ N.m (1.73 Kgf.m)                         |  |
| Accuracy of position repeatability |               | $\pm 0.02$ mm                                 |  |
| Ambient Temperature                |               | $0 \sim 45^\circ\text{C}$ ( $273 \sim 318$ K) |  |
| Robot's Weight                     |               | 41 Kg   |  |
| Working envelope section area      |               | $1.46$ m <sup>2</sup>                         |  |

\*) When the optional limit switch is attached, the action range of the main axis will be limited (see the manual)



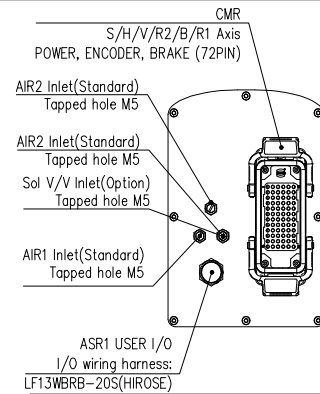
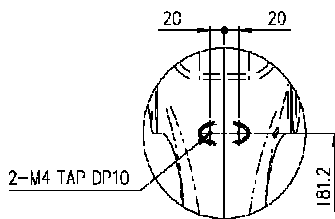
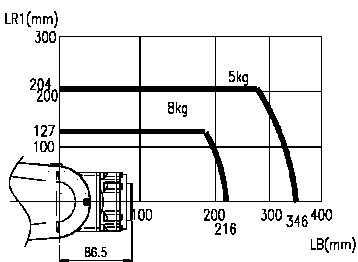
**View B: Dimensional drawing for the floor installation of the body**

**View G: Application part mounting**

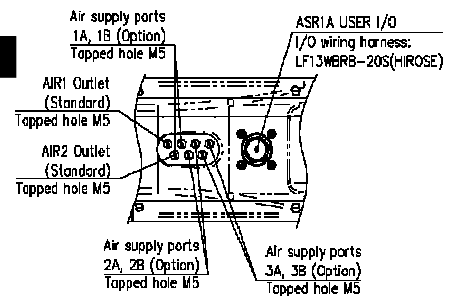


**Wrist-axis torque line diagram**

**View E: Details of the application ancillary part**



**View D: Application cable connection part**



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