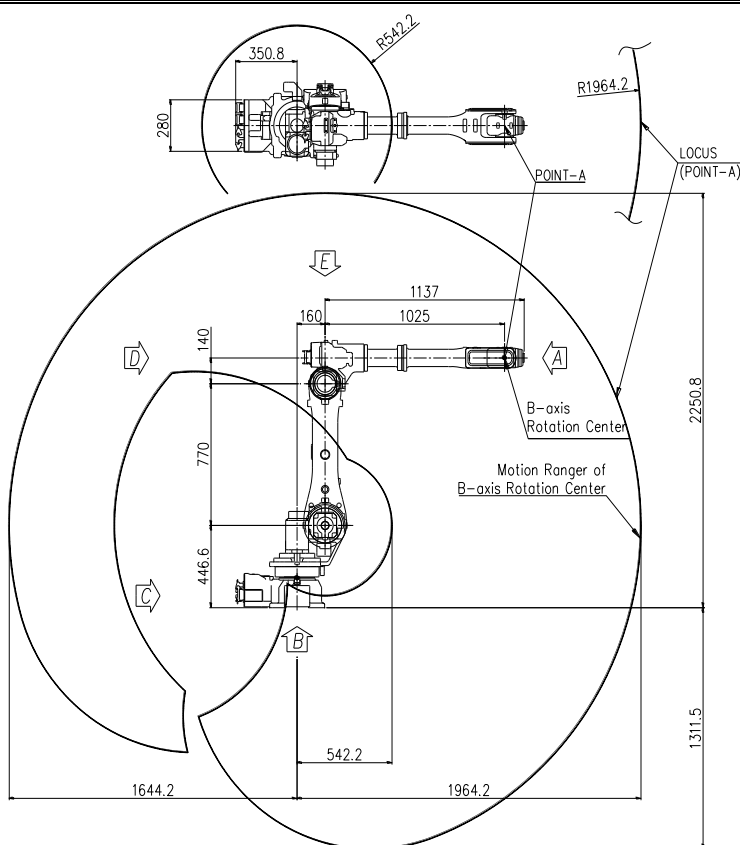
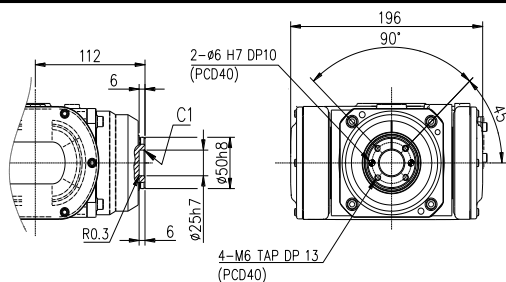
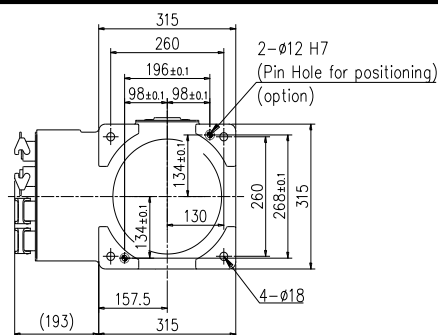




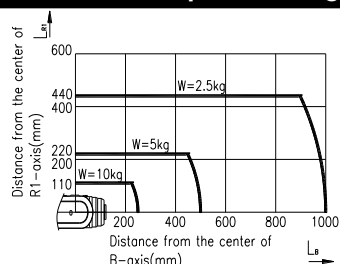
View A: Detailed drawing of the wrist attachment part



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



Wrist-axis torque line diagram



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

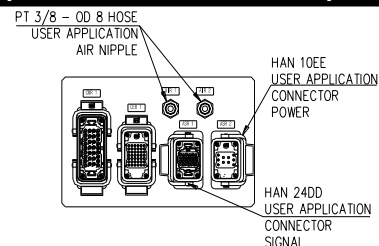
HH010L

Payload 10Kgf

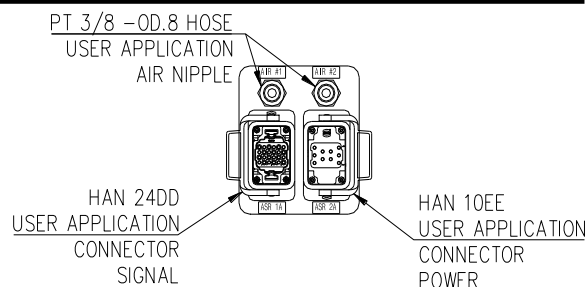
Installation method		Application	
Floor	●	Spot welding	
Ceiling	●	Arc welding	●
Wall surface	●	Handling	●
		Assembly	●
		Sealing	●
		Painting	

Item				Specification	
Robot model				HH010L	
Payload				10 Kg	
Structure				Articulated	
Degree of freedom				6 axes	
Drive system				AC SERVO MOTOR	
Max. working envelope	A r m	S	Swivel	$\pm 3.229 \text{ rad } (\pm 185^\circ)$	
		H	Horizontal	$+3.403 \sim -1.222 \text{ rad } (+195^\circ \sim -70^\circ)$	
		V	Vertical	$+3.141 \sim -1.396 \text{ rad } (+180^\circ \sim -80^\circ)$	
	Wrist	R2	Rotation 2	$\pm 3.403 \text{ rad } (\pm 195^\circ)$	
		B	Bending	$\pm 2.356 \text{ rad } (\pm 135^\circ)$	
		R1	Rotation 1	$\pm 6.283 \text{ rad } (\pm 360^\circ)$	
Max. working speed	A r m	S	Swivel	$3.316 \text{ rad / s } (190^\circ / \text{s})$	
		H	Horizontal	$3.142 \text{ rad / s } (180^\circ / \text{s})$	
		V	Vertical	$3.316 \text{ rad / s } (190^\circ / \text{s})$	
	Wrist	R2	Rotation 2	$6.632 \text{ rad / s } (380^\circ / \text{s})$	
		B	Bending	$6.632 \text{ rad / s } (380^\circ / \text{s})$	
		R1	Rotation 1	$10.472 \text{ rad / s } (600^\circ / \text{s})$	
Wrist torque		R2	Rotation 2	24.5 Nm (2.5 Kgfm)	
		B	Bending	24.5 Nm (2.5 Kgfm)	
		R1	Rotation 1	10.5 Nm (1.1 Kgfm)	
Accuracy of position repeatability				$\pm 0.08 \text{ mm}$	
Ambient Temperature				$0 \sim 45^\circ \text{C } (273 \sim 318 \text{ K})$	
Robot's Weight				230 Kg	
Working envelope section area				7.88 m^2	

View C: Application cable connection part (Option)



View D: Application cable connection part (Option)



View E: Details of the application ancillary part attachment

