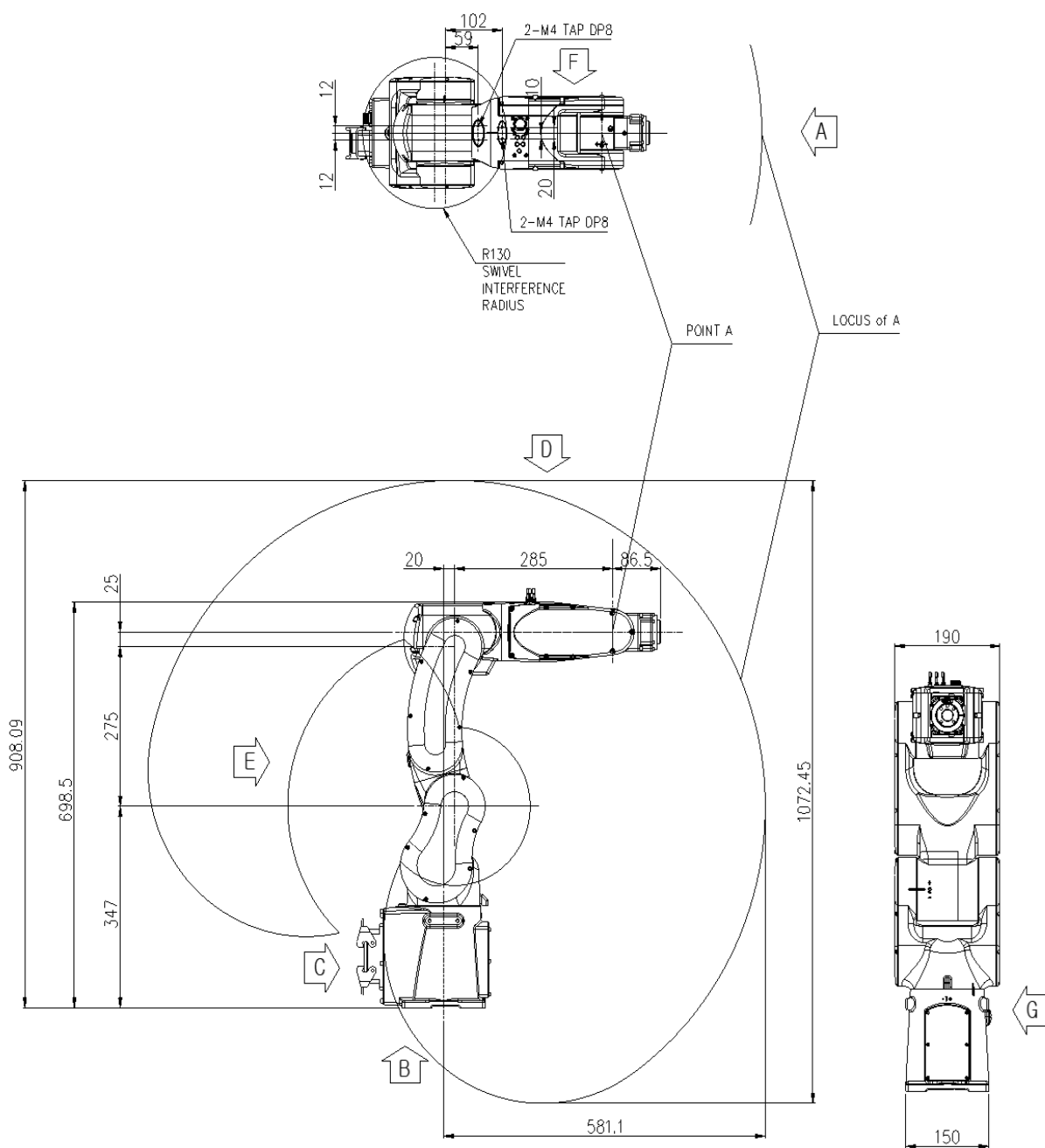


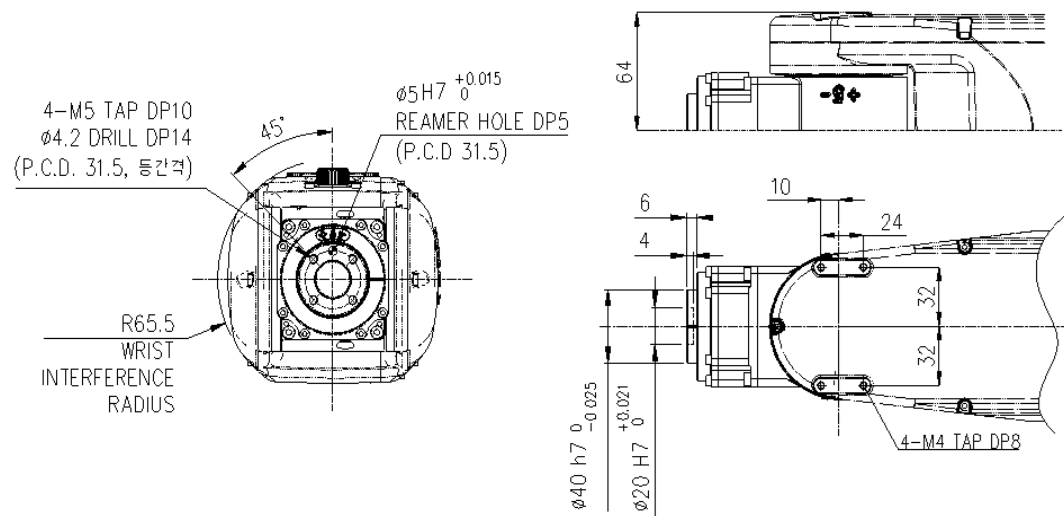
HH4

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



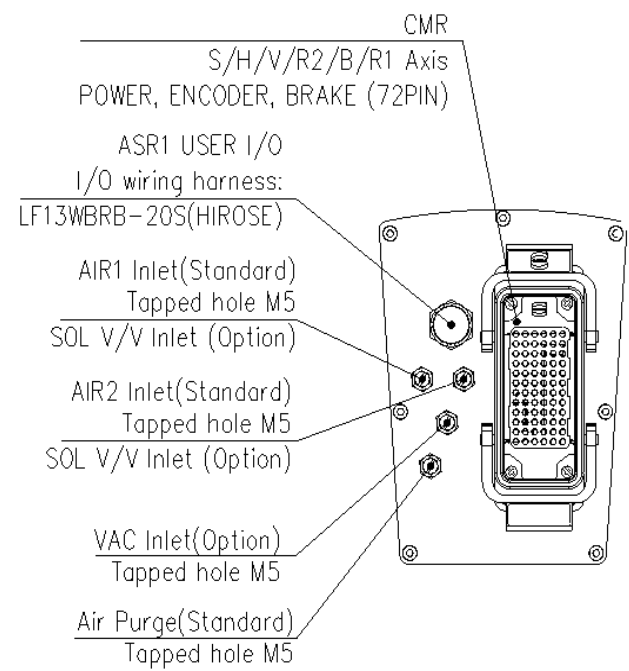
View A, F : Detailed drawing of the wrist attachment part

Item	Specification	
Robot model	HH4	
Payload	4 Kg	
Structure	Articulated	
Degree of freedom	6 axes	
Drive system	AC SERVO MOTOR	
Max. working envelope	Arm	S Swivel ± 2.967 rad ($\pm 170^\circ$)
		H Horizontal 55°
		V Vertical $+3.49 \sim -1.17$ rad ($+200^\circ \sim -67^\circ$)
Max. working speed	Wrist	R2 Rotation 2 ± 3.316 rad ($\pm 190^\circ$)
		B Bending ± 2.182 rad ($\pm 125^\circ$)
		R1 Rotation 1 ± 6.283 rad ($\pm 360^\circ$)
Wrist torque	Arm	S Swivel 8.378 rad / s ($480^\circ / s$)
		H Horizontal 8.029 rad / s ($460^\circ / s$)
		V Vertical 9.075 rad / s ($520^\circ / s$)
Wrist torque	Wrist	R2 Rotation 2 9.599 rad / s ($550^\circ / s$)
		B Bending 9.599 rad / s ($550^\circ / s$)
		R1 Rotation 1 17.453 rad / s ($1000^\circ / s$)
Accuracy of position repeatability	± 0.02 mm	
Ambient Temperature	$0 \sim 45^\circ\text{C}$ ($273 \sim 318$ K)	
Robot's Weight	27 Kg	
Working envelope section area	0.72 m ²	



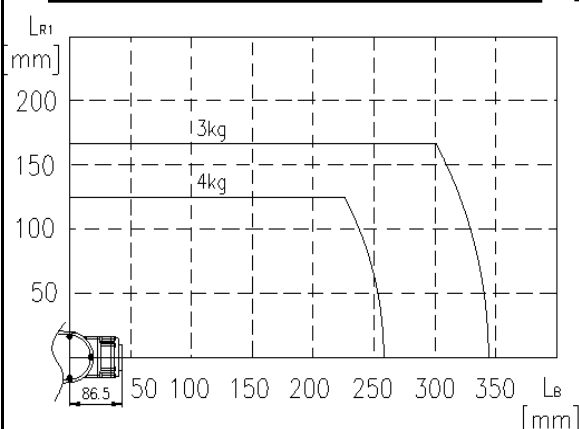
View B: Dimensional drawing for the floor installation of the body

View C: Application cable connection part

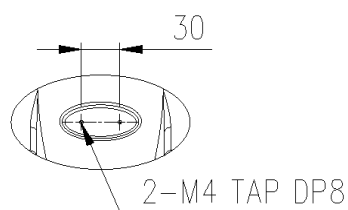


※ Precaution : When installing robot, please apply positioning pins. (2xØ6)

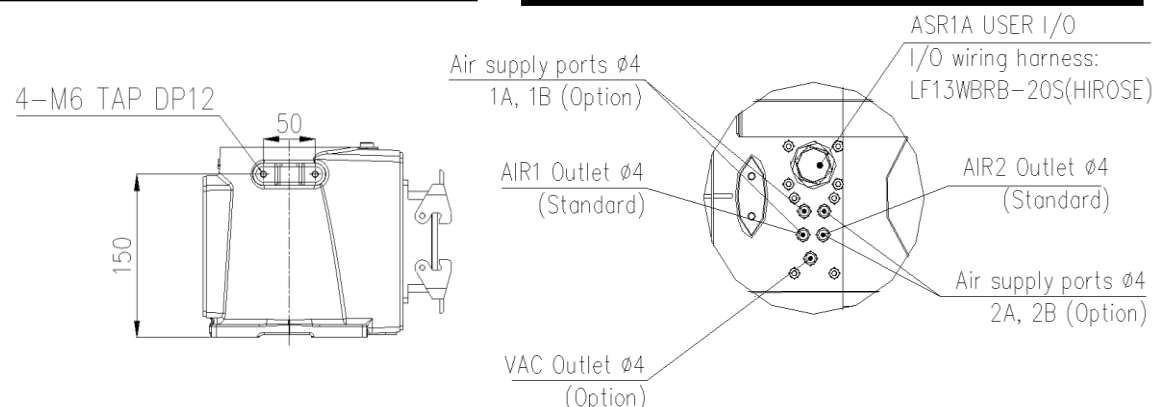
Wrist-axis torque line diagram



View E, G: Details of the application ancillary part



View D: Application cable connection



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