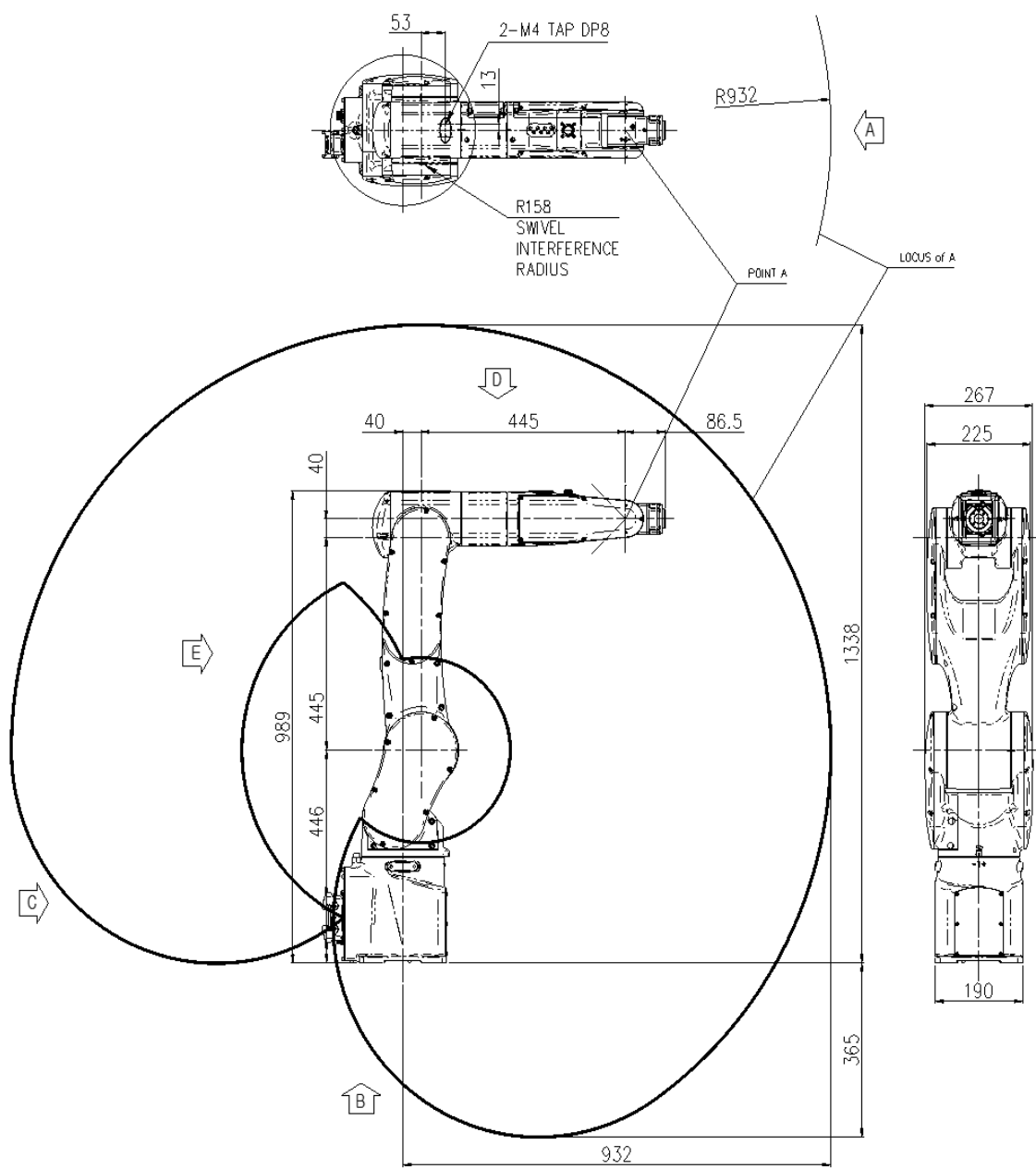


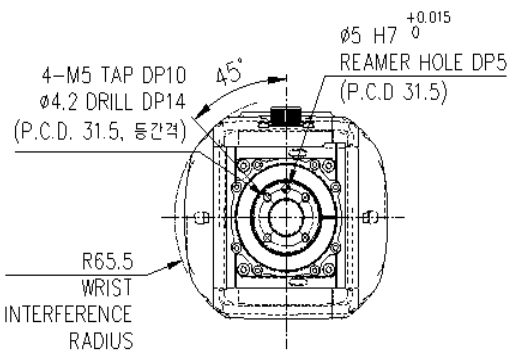
# HH7

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

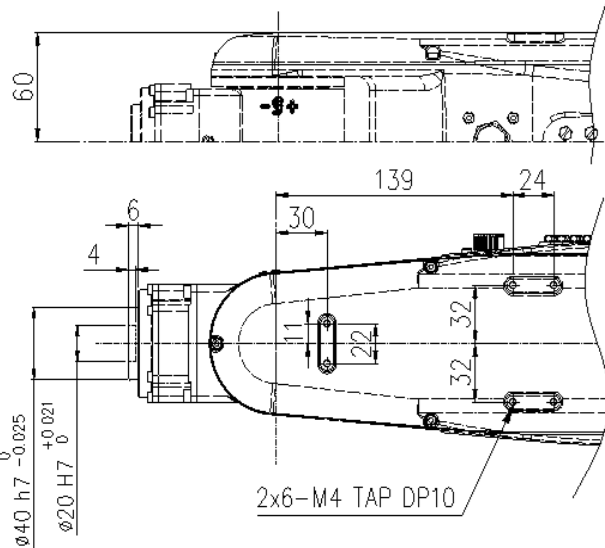


View A: Detailed drawing of the wrist attachment part

Item	Specification		
Robot model	HH7		
Payload	7 Kg		
Structure	Articulated		
Degree of freedom	6 axes		
Drive system	AC SERVO MOTOR		
Max. working envelope	A	S Swivel	$\pm 2.967 \text{ rad } (\pm 170^\circ)$
	r	H Horizontal	$+3.14 \sim -0.96 \text{ rad } (+180^\circ \sim -55^\circ)$
		V Vertical	$+3.71 \sim -1.15 \text{ rad } (+213^\circ \sim -70^\circ)$
		Wrist	
	m*	R2 Rotation 2	$\pm 3.316 \text{ rad } (\pm 190^\circ)$
		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	S Swivel	6.544 rad / s (375° / s)
	r	H Horizontal	5.497 rad / s (315° / s)
		V Vertical	7.155 rad / s (410° / s)
		Wrist	
	m	R2 Rotation 2	9.599 rad / s (550° / s)
		B Bending	9.599 rad / s (550° / s)
R1 Rotation 1		17.453 rad / s (1000° / s)	
Wrist torque	R2 Rotation 2	17 N.m (1.73 Kgf.m)	
	B Bending	17 N.m (1.73 Kgf.m)	
	R1 Rotation 1	10 N.m (1.02 Kgf.m)	
Accuracy of position repeatability	$\pm 0.03 \text{ mm}$		
Ambient Temperature	0 ~ 45 °C (273 ~ 318 K)		
Robot's Weight	48 Kg		
Working envelope section area	1.98 m <sup>2</sup>		

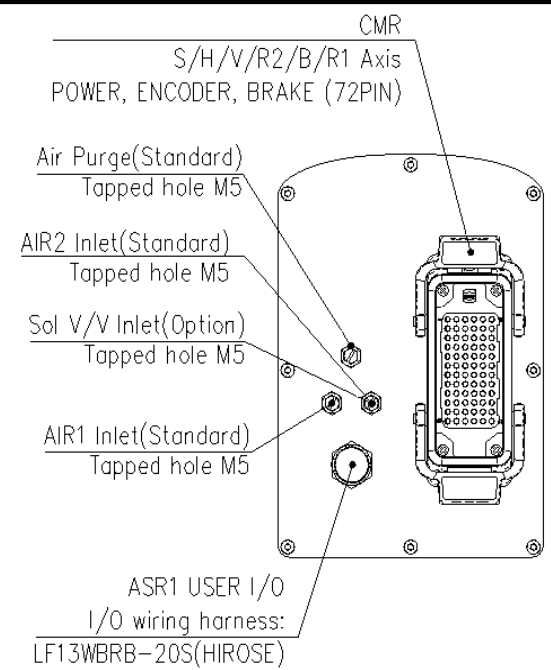


View B: Dimensional drawing for the floor installation of the body

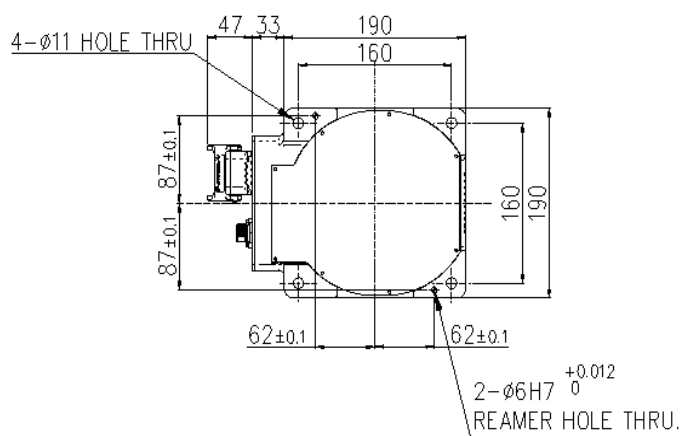
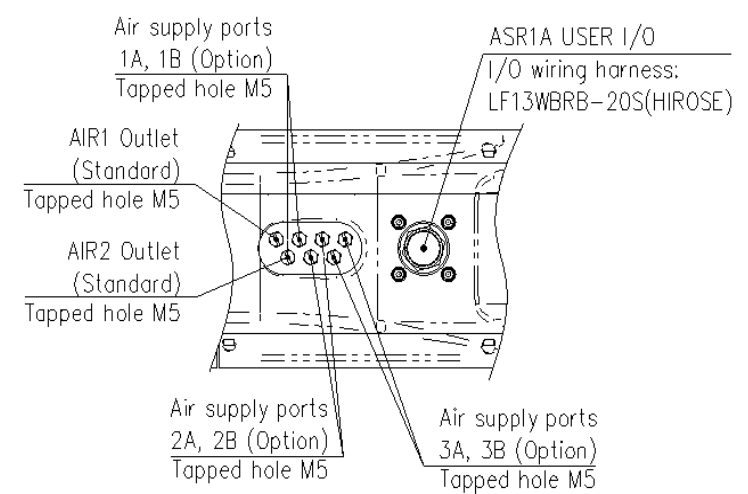


View G: Application part mounting

View C: Application cable connection part



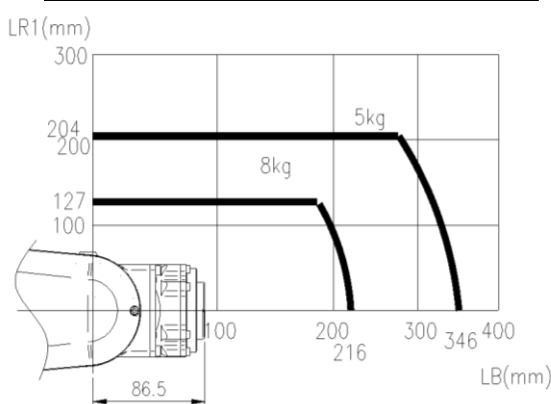
View D: Application cable connection part



View E: Application part mounting

※ Precaution : When installing robot, please apply positioning pins. (2xø6)

Wrist-axis torque line diagram



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