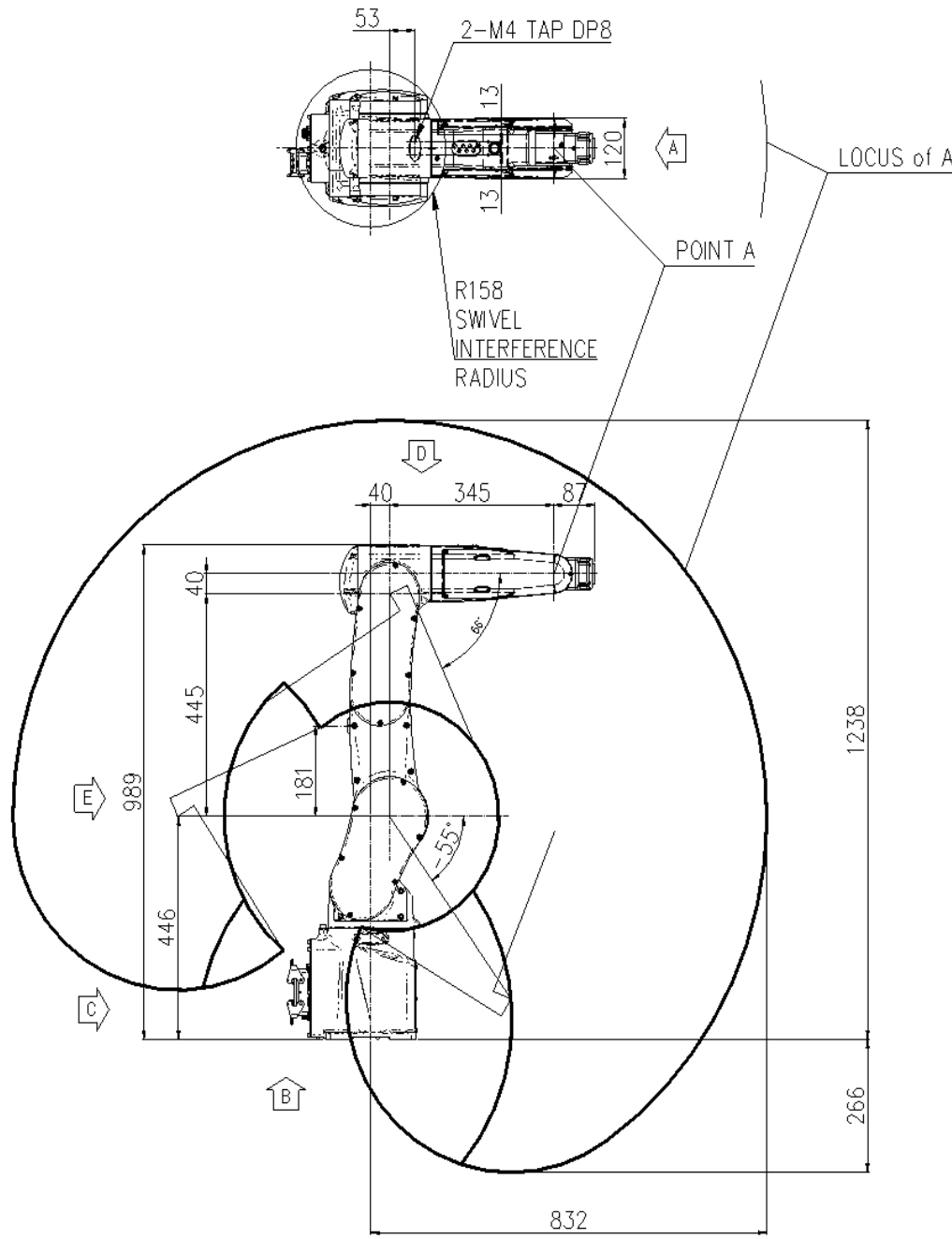


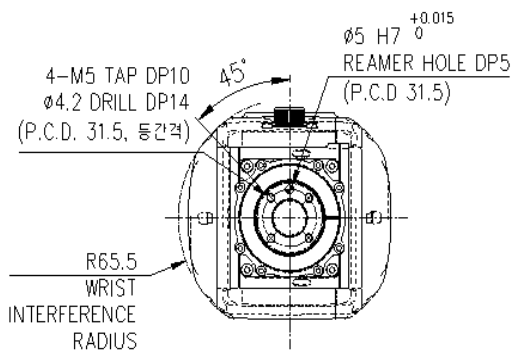
# HH8

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

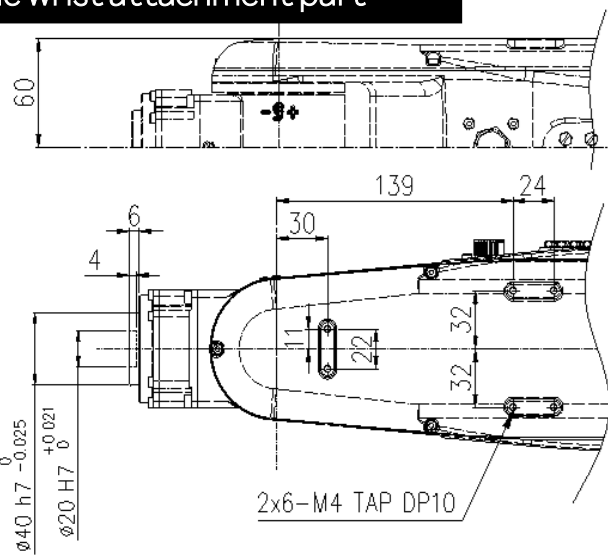


View A: Detailed drawing of the wrist attachment part

Item	Specification
Robot model	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 $+3.14 \sim -0.96$ rad ( $+180^\circ \sim -55^\circ$ )
	V Vertical $70^\circ$
	Wrist R2 Rotation 2 $\pm 3.316$ rad ( $\pm 190^\circ$ )
	B Bending $\pm 2.356$ rad ( $\pm 135^\circ$ )
	R1 Rotation 1 $\pm 6.283$ rad ( $\pm 360^\circ$ )
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 ( $550^\circ / s$ )
	R1 Rotation 1 $17.453$ rad / s ( $1000^\circ / s$ )
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	$\pm 0.02$ mm
Ambient Temperature	$0 \sim 45^\circ\text{C}$ ( $273 \sim 318$ K)
Robot's Weight	$47$ Kg
Working envelope section area	$1.46$ m <sup>2</sup>

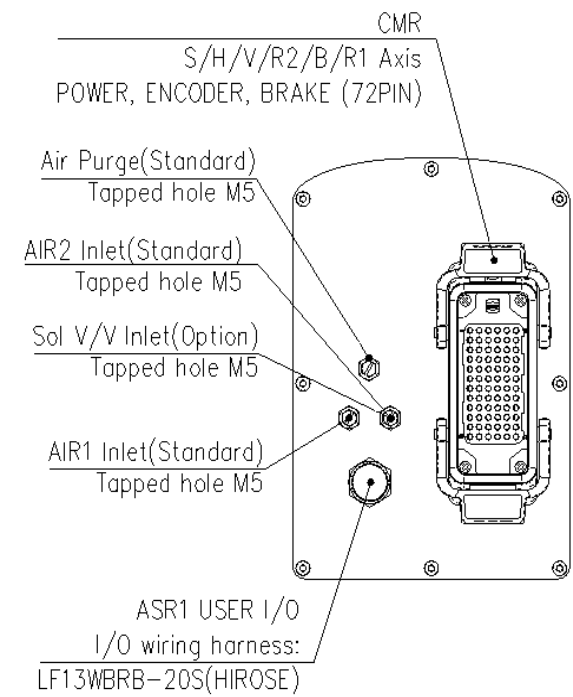


View B: Dimensional drawing for the floor installation of the body

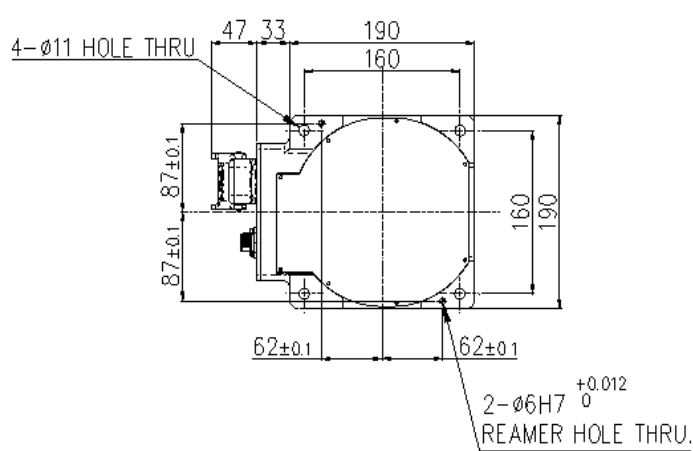


View G: Application part mounting

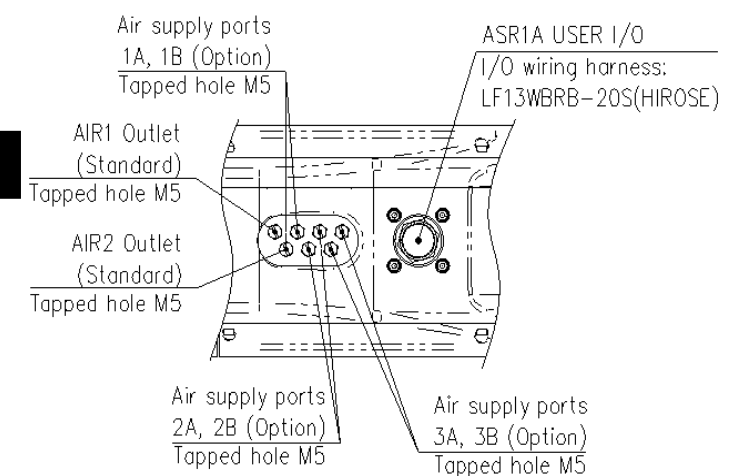
View C: Application cable connection part



View D: Application cable connection part



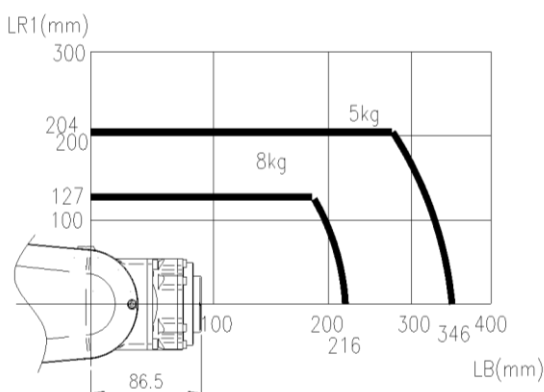
View E: Details of the application ancillary part



View F: Application cable connection part

※ 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.