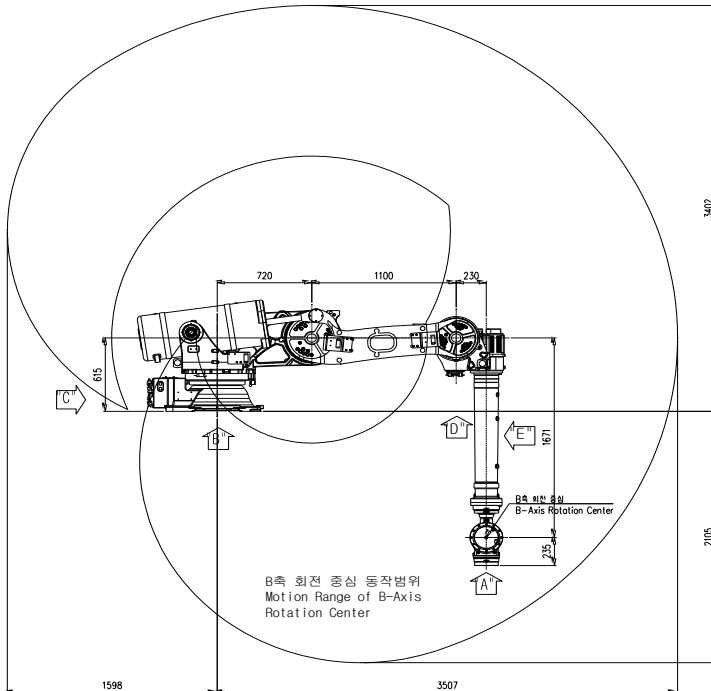
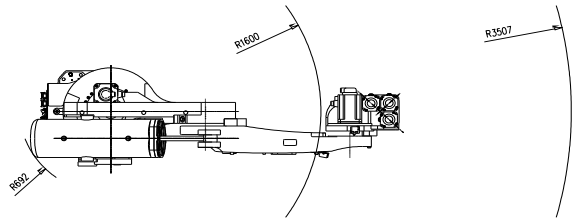


HH100SL

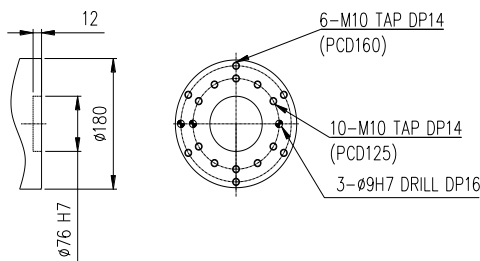
Payload 100Kgf

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

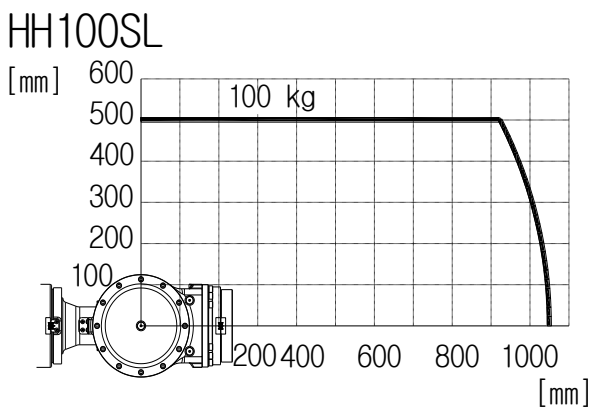
Item	Specification		
Robot model	HH100SL		
Payload	100 Kg		
Structure	Articulated		
Degree of freedom	6 axes		
Max. working envelope	A	S Swivel	$\pm 3.142 \text{ rad } (\pm 180^\circ)$
	r	H Horizontal	$+2.181 \sim -1.221 \text{ rad } (+125^\circ \sim -70^\circ)$
		V Vertical	$+3.316 \sim -1.396 \text{ rad } (+190^\circ \sim -80^\circ)$
		R2 Rotation 2	$\pm 6.283 \text{ rad } (\pm 360^\circ)$
	m	B Bending	$\pm 2.182 \text{ rad } (\pm 125^\circ)$
R1 Rotation 1		$\pm 6.283 \text{ rad } (\pm 360^\circ)$	
Max. working speed	A	S Swivel	$1.658 \text{ rad / s } (105^\circ / \text{s})$
	r	H Horizontal	$1.483 \text{ rad / s } (85^\circ / \text{s})$
		V Vertical	$1.571 \text{ rad / s } (95^\circ / \text{s})$
		R2 Rotation 2	$2.618 \text{ rad / s } (170^\circ / \text{s})$
	m	B Bending	$2.443 \text{ rad / s } (155^\circ / \text{s})$
R1 Rotation 1		$3.840 \text{ rad / s } (270^\circ / \text{s})$	
Wrist torque	R2 Rotation 2	1030 Nm (105 Kgfm)	
	B Bending	1030 Nm (105 Kgfm)	
	R1 Rotation 1	490 Nm (50 Kgfm)	
Accuracy of position repeatability	$\pm 0.15 \text{ mm}$		
Ambient Temperature	$0 \sim 45^\circ \text{C } (273 \sim 318 \text{ K})$		
Robot's Weight	1,450Kg		
Working envelope section area	12.5 m ²		



View A: Detailed drawing of the wrist attachment part

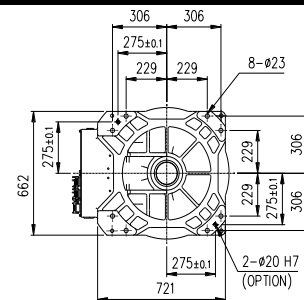


Wrist-axis torque line diagram

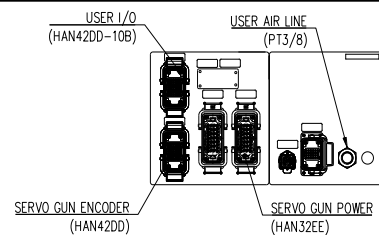


** For product improvement, some of the ratings, specifications, dimensions, etc. are subject to changes without notice.

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



View C: Application cable connection part



View D: Application cable connection part

