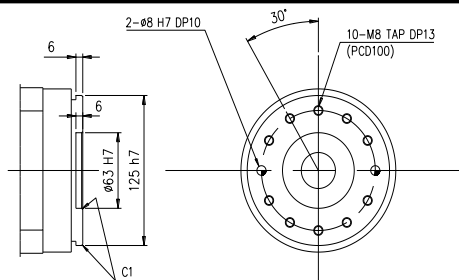


Payload 50Kgf

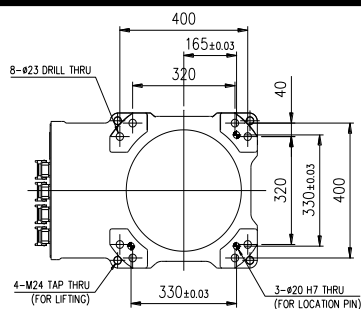
Installation method		Application	
Floor	●	Spot welding	
Ceiling	●	Arc welding	
Wall surface	●	Handling	●
		Assembly	
		Sealing	●
		Painting	

Item			Specification	
Robot model			HH050	
Payload			50 Kg	
Structure			Articulated	
Degree of freedom			6 axes	
Max. working envelope	A r m	S	Swivel	± 3.142 rad ($\pm 180^\circ$)
		H	Horizontal	$+2.967 \sim -1.134$ rad ($+170^\circ \sim -65^\circ$)
		V	Vertical	$+3.141 \sim -1.396$ rad ($+180^\circ \sim -80^\circ$)
	Wrist	R2	Rotation 2	± 6.283 rad ($\pm 360^\circ$)
		B	Bending	± 2.182 rad ($\pm 125^\circ$)
		R1	Rotation 1	± 6.283 rad ($\pm 360^\circ$)
Max. working speed	A r m	S	Swivel	3.054 rad / s (175° / s)
		H	Horizontal	3.054 rad / s (175° / s)
		V	Vertical	3.054 rad / s (175° / s)
	Wrist	R2	Rotation 2	4.363 rad / s (250° / s)
		B	Bending	4.363 rad / s (250° / s)
		R1	Rotation 1	6.109 rad / s (350° / s)
Wrist torque	R2	Rotation 2	216 Nm (22.0 Kgfm)	
	B	Bending	216 Nm (22.0 Kgfm)	
	R1	Rotation 1	147 Nm (15.0 Kgfm)	
Accuracy of position repeatability				± 0.1 mm
Ambient Temperature				$0 \sim 45^\circ\text{C}$ ($273 \sim 318\text{ K}$)
Robot's Weight				645 Kg

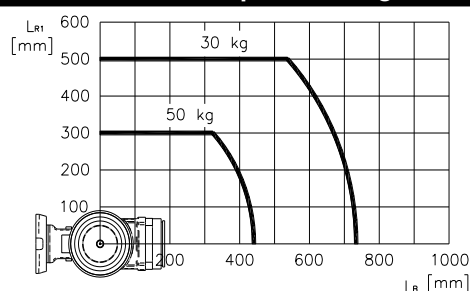
View A: Detailed drawing of the wrist attachment part



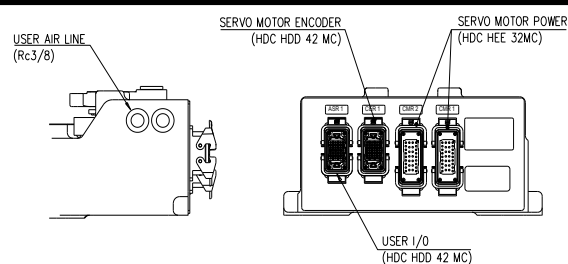
View B: Dimensional drawing for the floor installation of the body



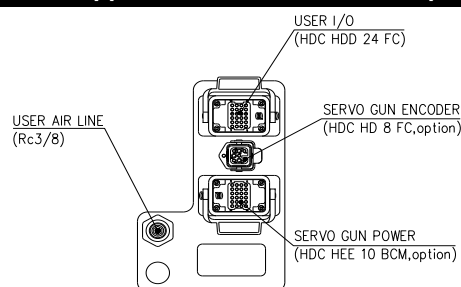
Wrist-axis torque line diagram



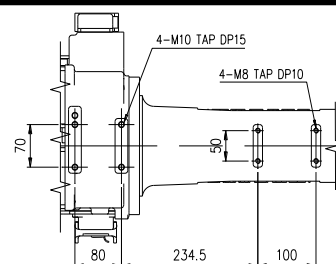
View C: Application cable connection part



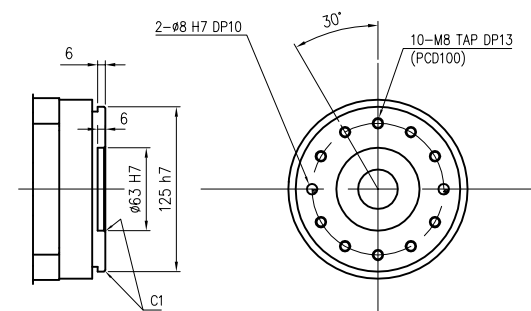
View D: Application cable connection part



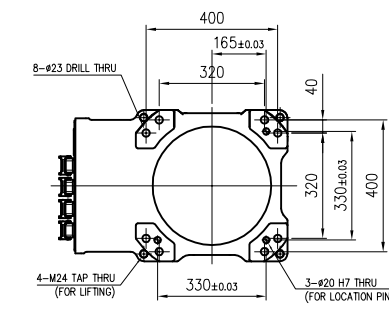
View E: Details of the application ancillary part attachment



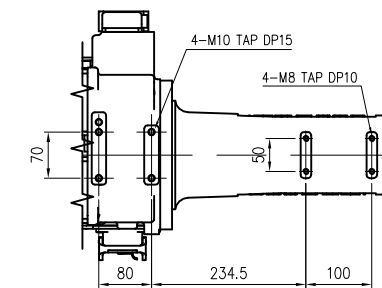
**** For product improvement, some of the ratings, specifications, dimensions, etc. are subject to changes without notice.**



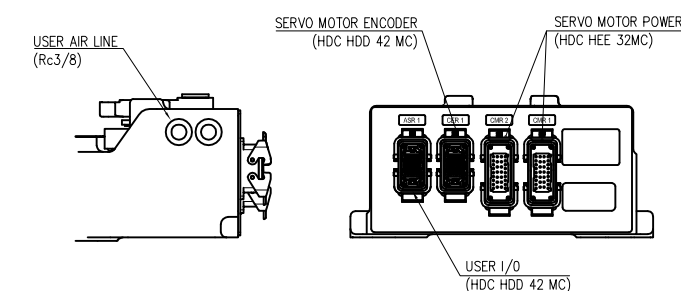
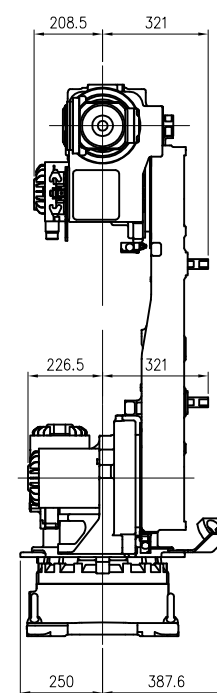
VIEW "A"
(SCALE : 4/1)



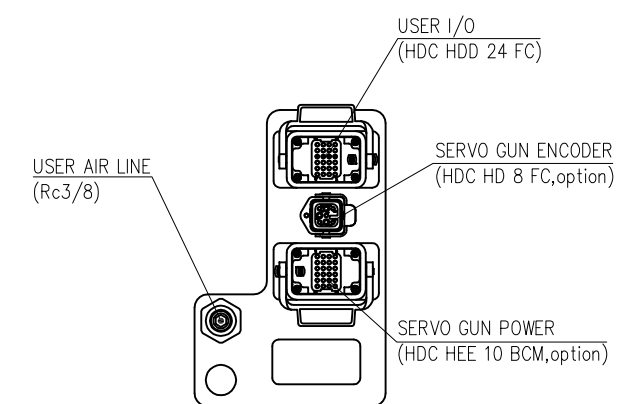
VIEW "B"



VIEW "E"
(SCALE : 2/1)



VIEW "C"
(SCALE 2/1)



VIEW "D"
(SCALE : 4/1)

MODEL	HH050	issue.0
DATE	2018.06.19	

 **HYUNDAI ROBOTICS**

TECHNICAL SPECIFICATION SUBJECT TO
CHANGE WITHOUT NOTICE