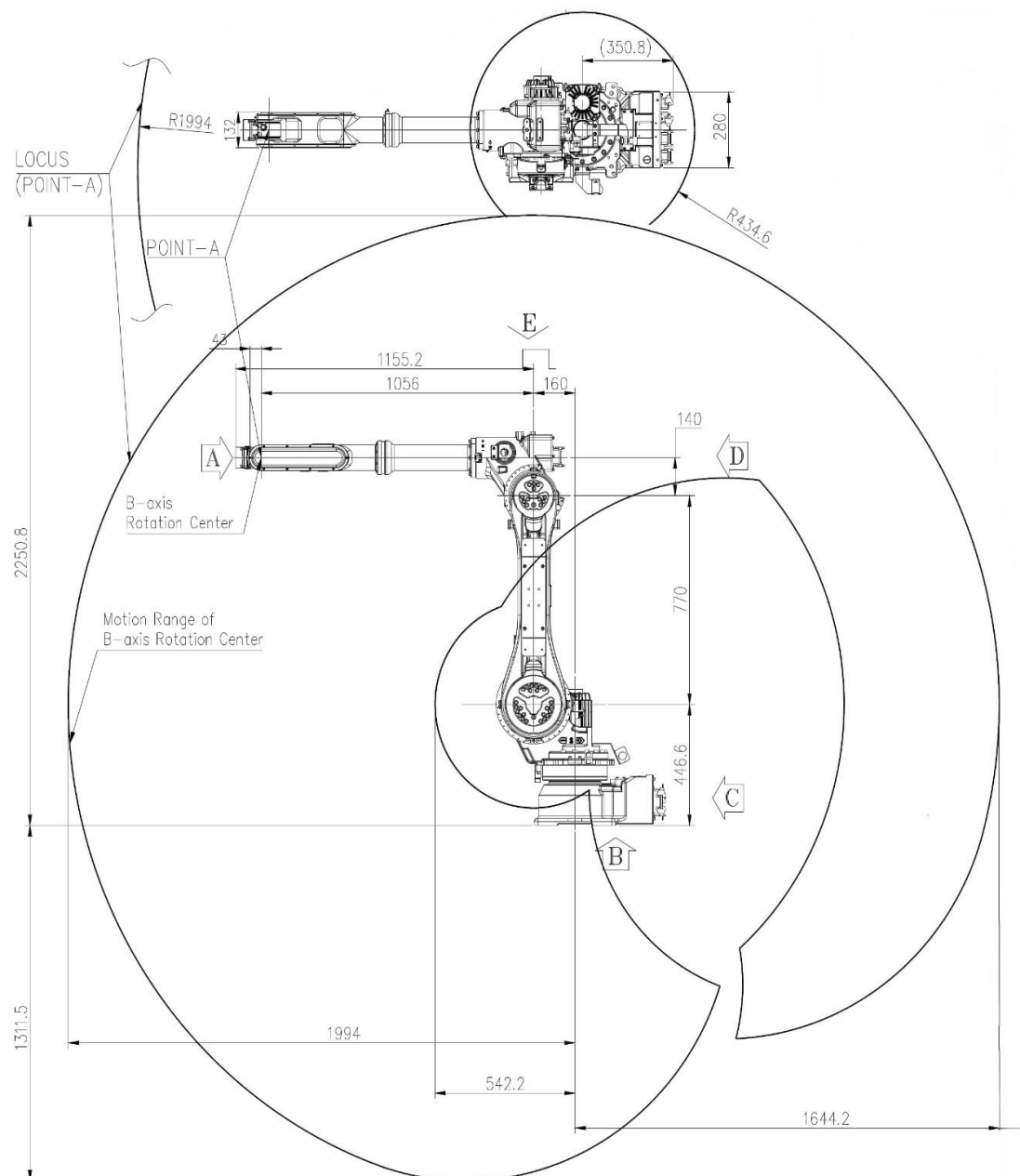
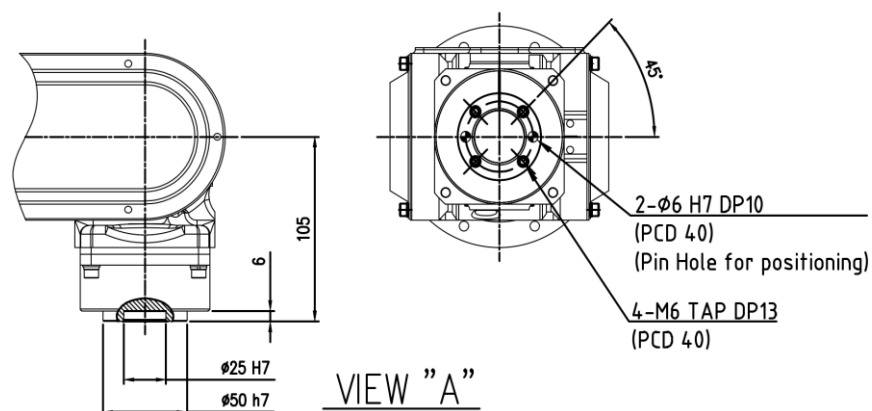


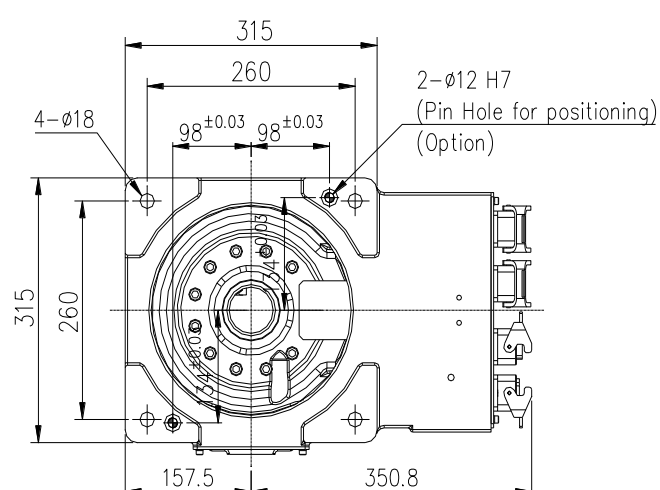
HDR10L-



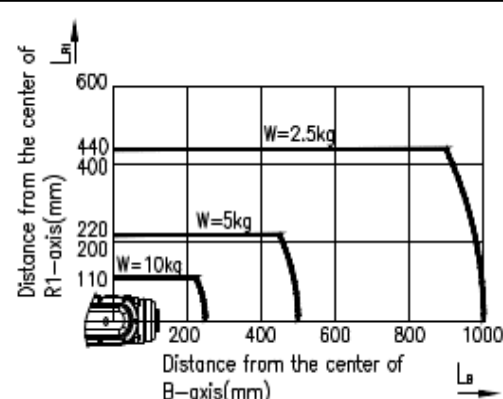
View A: Detailed drawing of the wrist attachment part



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



Wrist-axis torque line diagram

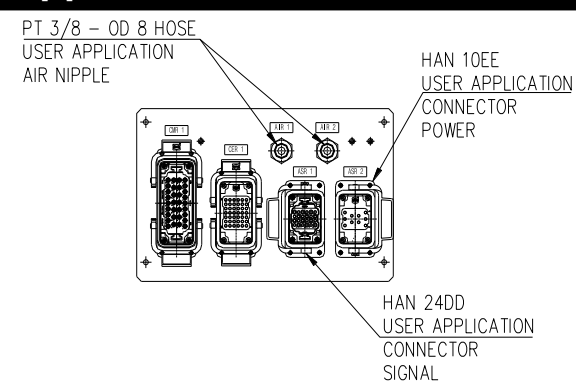


**** For product improvement, some of the ratings, specifications, dimensions, etc. are subject to changes without notice.**

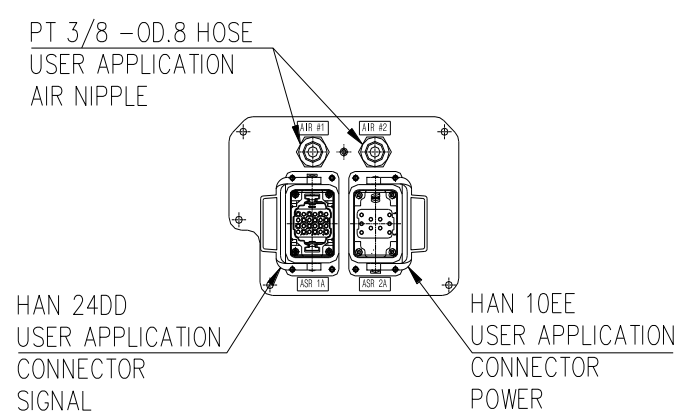
Installation method		Application	
Floor	●	Spot welding	
Ceiling	●	Arc welding	●
Wall surface	●	Handling	●
Angle		Assembly	
		Sealing	●
		Painting	

Item				Specification
Robot model				HDR10L-19
Payload				10 Kg
Structure				Articulated
Degree of freedom				6 axes
Drive system				AC SERVO MOTOR
Max. working envelope	A r m	S	Swivel	± 3.22 rad ($\pm 185^\circ$)
		H	Horizontal	$+3.4 \sim -1.22$ rad ($+195^\circ \sim -70^\circ$)
		V	Vertical	$+3.14 \sim -1.39$ rad ($+180^\circ \sim -80^\circ$)
	Wrist	R2	Rotation 2	± 3.4 rad ($\pm 195^\circ$)
		B	Bending	± 2.35 rad ($\pm 135^\circ$)
		R1	Rotation 1	± 6.28 rad ($\pm 360^\circ$)
Max. working speed	A r m	S	Swivel	3.66 rad / s (210° / s)
		H	Horizontal	3.66 rad / s (210° / s)
		V	Vertical	3.84 rad / s (220° / s)
	Wrist	R2	Rotation 2	7.33 rad / s (420° / s)
		B	Bending	7.85 rad / s (450° / s)
		R1	Rotation 1	10.47 rad / s (720° / s)
Wrist torque		R2	Rotation 2	17.64 N.m (0.65 kgf.m)
		B	Bending	17.64 N.m (0.65 kgf.m)
		R1	Rotation 1	1.66 N.m (0.17 kgf.m)
Accuracy of position repeatability				± 0.03 mm
Ambient Temperature				0 $\sim$ 45 $^\circ$ C (273 $\sim$ 318 K)
Robot's Weight				211 Kg

View C: Application cable connection part (Option)



View D: Application cable connection part (Option)



View E: Details of the application ancillary part attachment

