

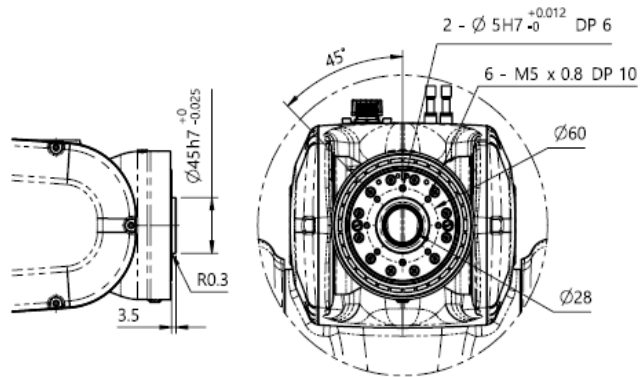
HDF12H-14

PAYLOAD 12Kgf

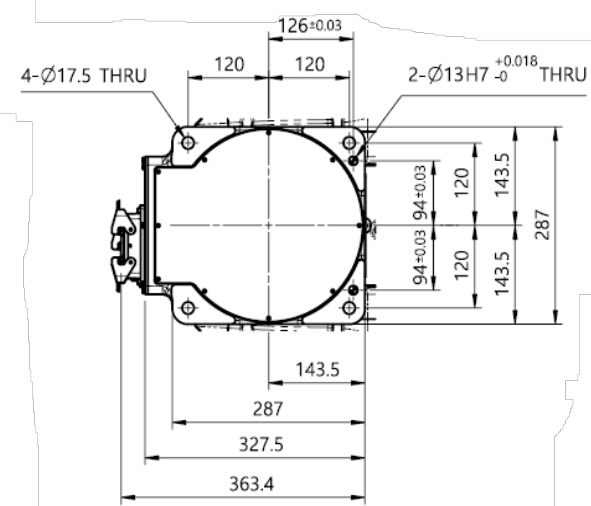
Installation method		Application	
Floor	●	Spot welding	
Ceiling	●	Arc welding	
Wall surface		Handling	●
Angle	●	Assembly	●
		Sealing	●
		Painting	

Item				Specification
Robot model				HDF12H-14
Payload				12 Kg
Structure				Articulated
Degree of freedom				6axes
Max. working envelope	A r m*	S	Swivel	± 3 rad ($\pm 172^\circ$)
		H	Horizontal	$+3.14 \sim -1.43$ rad ($+180^\circ \sim -82^\circ$)
		V	Vertical	$+3.14 \sim -1.41$ rad ($+180^\circ \sim -81^\circ$)
	Wrist	R2	Rotation 2	± 3.31 rad ($\pm 190^\circ$)
		B	Bending	± 2.44 rad ($\pm 140^\circ$)
		R1	Rotation 1	± 6.28 rad ($\pm 360^\circ$)
최대 동작 속도	A r m	S	Swivel	4.88 rad (280° / s)
		H	Horizontal	4.54 rad (260° / s)
		V	Vertical	4.88 rad (280° / s)
	Wrist	R2	Rotation 2	8.2 rad (470° / s)
		B	Bending	8.37 rad (480° / s)
		R1	Rotation 1	11.69 rad (670° / s)
Wrist torque		R2	Rotation 2	21.95 N.m (2.7 kgf.m)
		B	Bending	21.95 N.m (2.7 kgf.m)
		R1	Rotation 1	11.76 N.m (1.2 kgf.m)
Accuracy of position repeatability				± 0.04 mm
Ambient Temperature				0 ~ 45 °C (273 ~ 318 K)
Robot's Weight				124 Kg

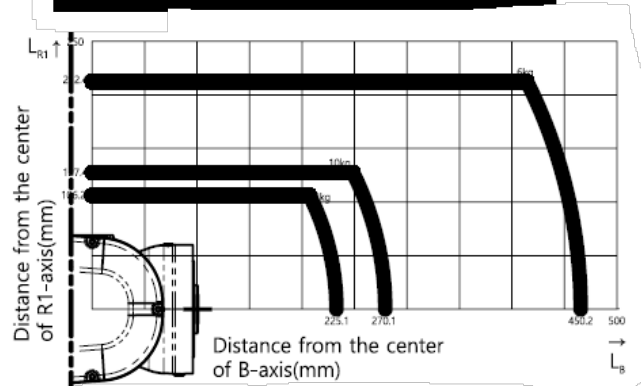
View A: Detailed drawing of the wrist attachment part



View B: Dimensional drawing for the floor

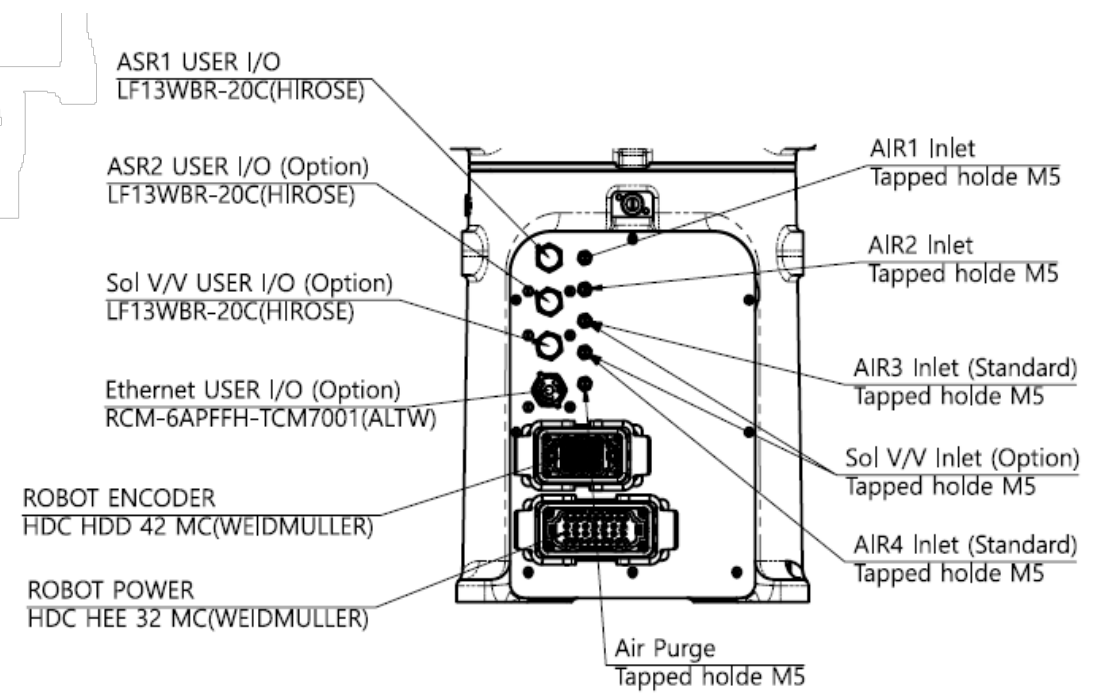


Wrist-axis torque line diagram



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

View C: Application cable connection part



View D: Details of the application ancillary part attachment

