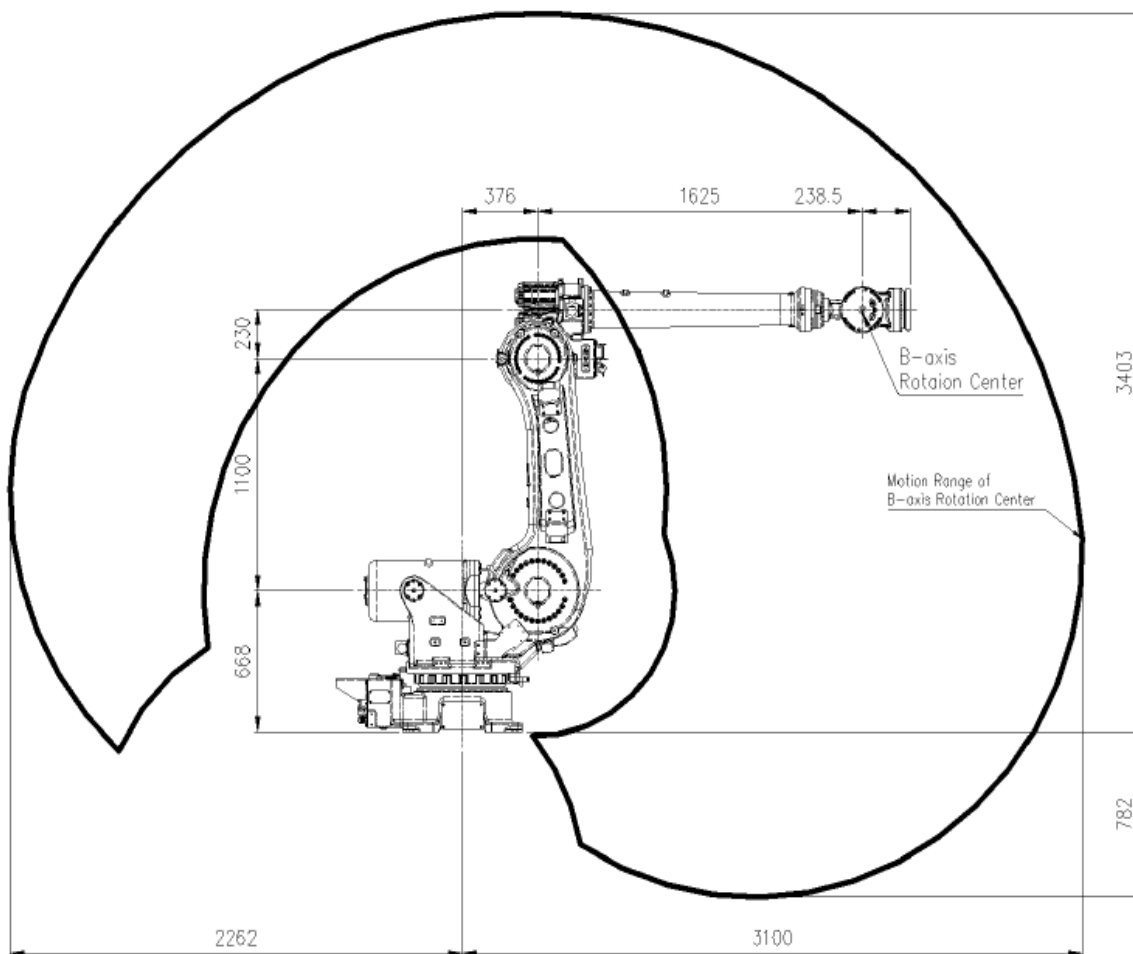
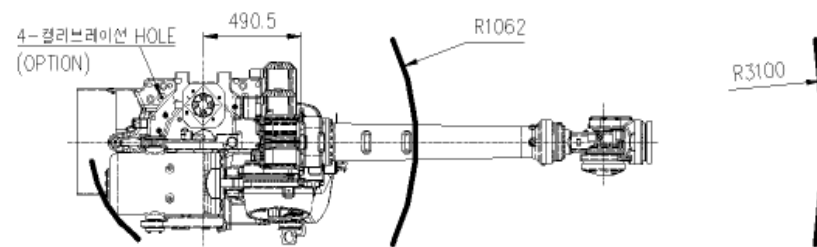


HDR150L-31

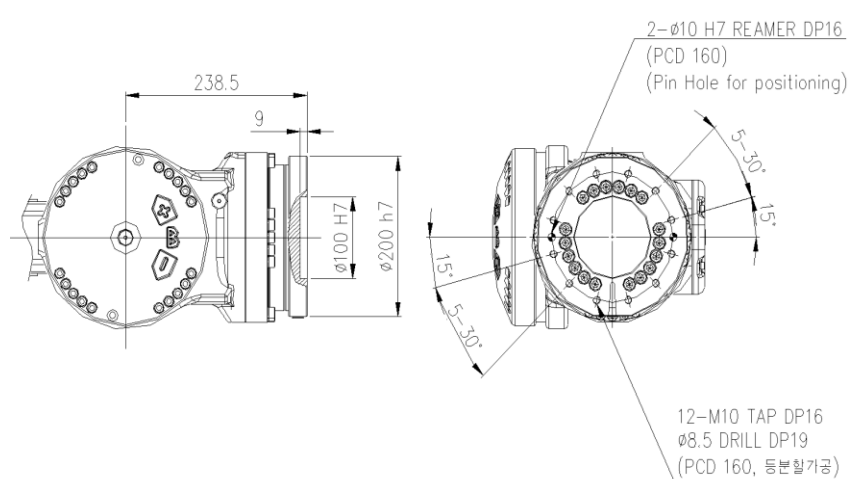
Payload 150Kgf



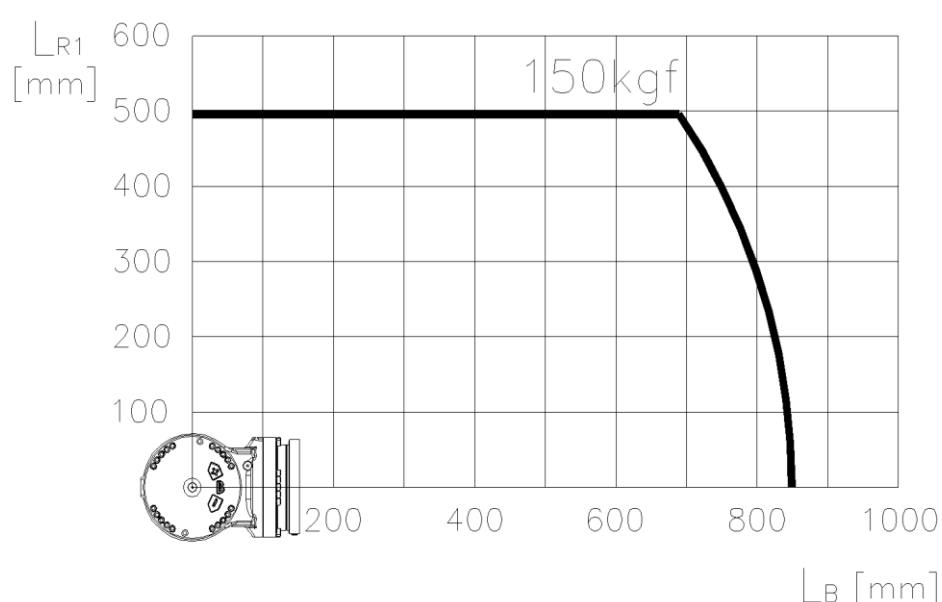
Installation method		Application	
Floor	●	Spot welding	●
Ceiling		Arc welding	
Wall surface		Handling	●
		Assembly	●
		Sealing	
		Painting	

Item				Specification
Robot model				HDR150L-31
Payload				150 Kg
Structure				Articulated
Degree of freedom				6 axes
Max. working envelope	A r m	S	Swivel	$\pm 3.14 \text{ rad } (\pm 180^\circ)$
		H	Horizontal	$+2.70 \sim +0.17 \text{ rad } (+155^\circ \sim +10^\circ)$
		V	Vertical	$+3.31 \sim -1.39 \text{ rad } (+190^\circ \sim -80^\circ)$
	Wrist	R2	Rotation 2	$\pm 6.28 \text{ rad } (\pm 360^\circ)$
		B	Bending	$\pm 2.18 \text{ rad } (\pm 125^\circ)$
		R1	Rotation 1	$\pm 6.28 \text{ rad } (\pm 360^\circ)$
Max. working speed	A r m	S	Swivel	$2.09 \text{ rad / s } (120^\circ / \text{s})$
		H	Horizontal	$2.00 \text{ rad / s } (115^\circ / \text{s})$
		V	Vertical	$2.00 \text{ rad / s } (115^\circ / \text{s})$
	Wrist	R2	Rotation 2	$2.96 \text{ rad / s } (170^\circ / \text{s})$
		B	Bending	$2.70 \text{ rad / s } (155^\circ / \text{s})$
		R1	Rotation 1	$4.88 \text{ rad / s } (280^\circ / \text{s})$
Wrist torque		R2	Rotation 2	$1,250 \text{ Nm } (127 \text{ Kgfm})$
		B	Bending	$1,250 \text{ Nm } (127 \text{ Kgfm})$
		R1	Rotation 1	$730 \text{ Nm } (74 \text{ Kgfm})$
Accuracy of position repeatability				$\pm 0.05 \text{ mm}$
Ambient Temperature				$0 \sim 45^\circ \text{C } (273 \sim 318 \text{ K})$
Robot's Weight				1,380Kg

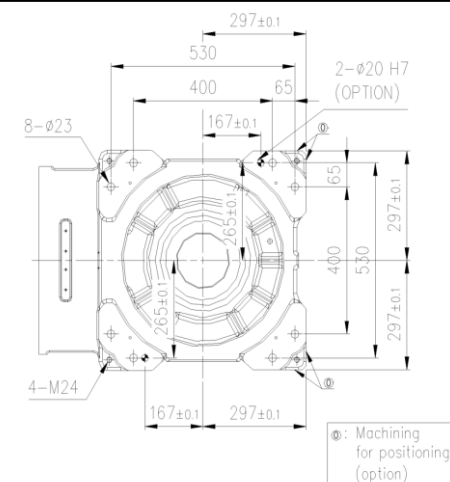
View A: Detailed drawing of the wrist attachment part



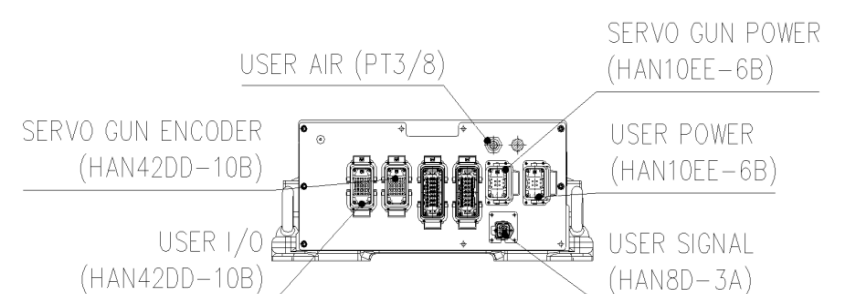
Wrist-axis torque line diagram



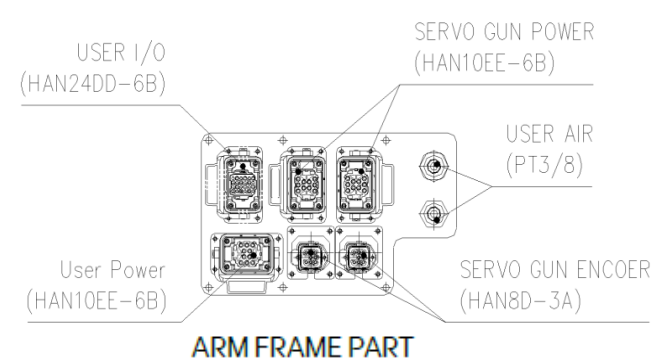
View B: Dimensional drawing for the floor installation of the body



View C: Application cable connection part



View D: Application cable connection part



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