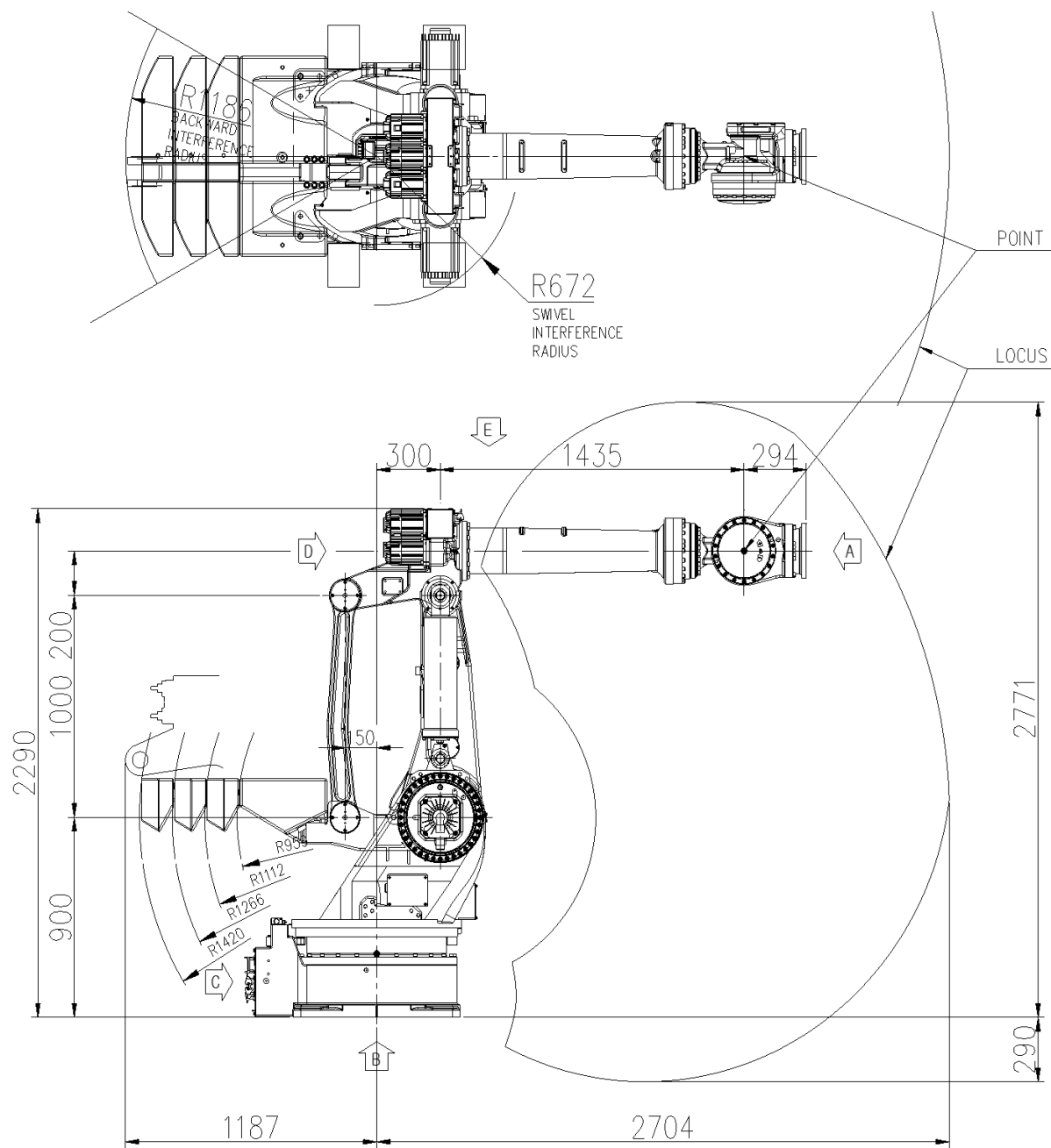


HDX600-27

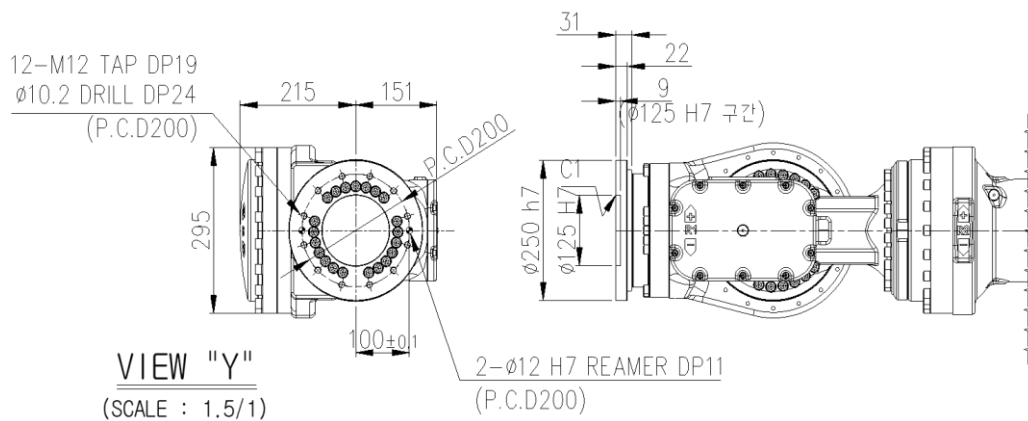
Payload 600Kgf

Installation method	
Floor	●
Ceiling	
Wall surface	

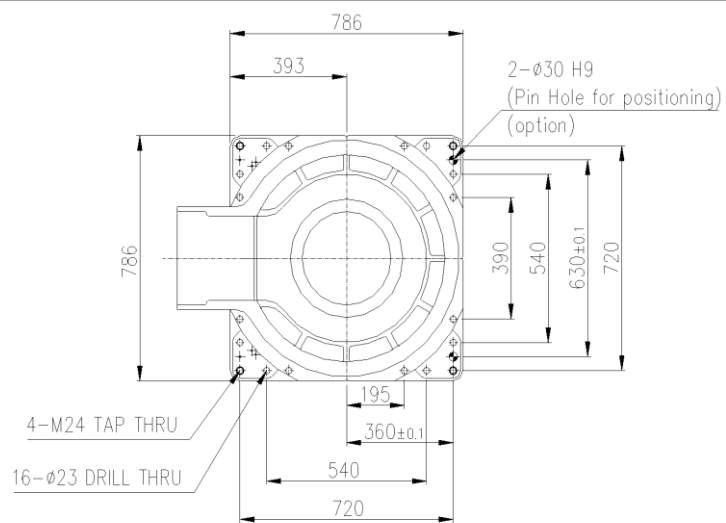
Application	
Spot welding	●
Arc welding	
Handling	●
Assembly	
Sealing	
Painting	



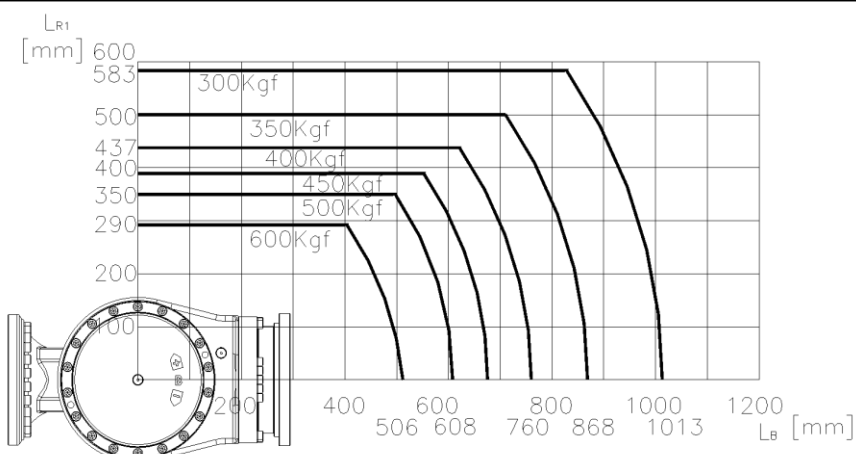
VIEW A: Detailed drawing of the wrist attachment part



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

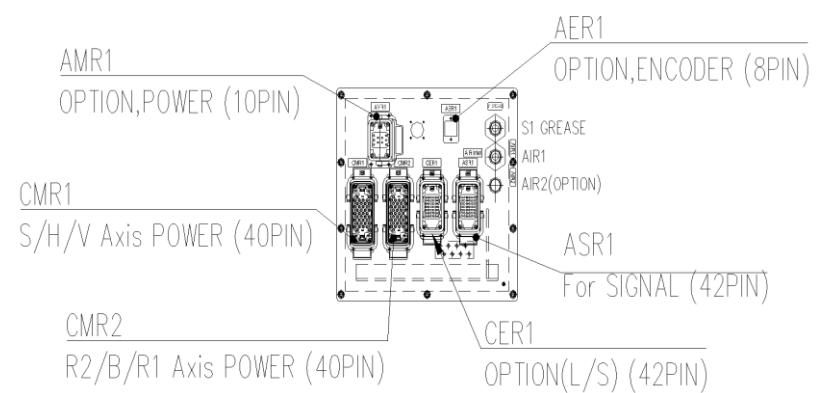


Wrist-axis torque line diagram

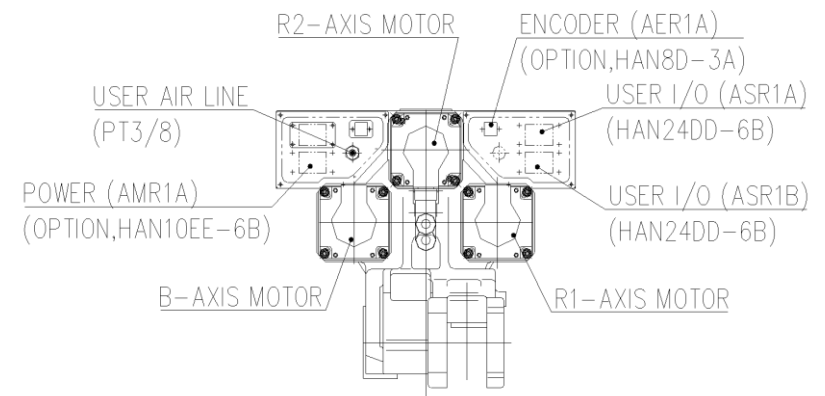


Item				Specification	
Robot model				HDX600-27	
Payload				600 Kg	
Structure				Articulated	
Degree of freedom				6 Axes	
Drive system				AC SERVO MOTOR	
Max. working envelope	A r m	S	Swivel	± 3.14 rad ($\pm 180^\circ$)	
		H	Horizontal	$+2.87 \sim +0.26$ rad ($+165^\circ \sim +15^\circ$)	
		V	Vertical	$+1.04 \sim -1.22$ rad ($+60^\circ \sim -70^\circ$)	
	Wrist	R2	Rotation 2	± 6.28 rad ($\pm 360^\circ$)	
		B	Bending	± 6.28 rad ($\pm 360^\circ$)	
		R1	Rotation 1	± 6.28 rad ($\pm 360^\circ$)	
Max. working speed	A r m	S	Swivel	1.22 rad / s (70° / s)	
		H	Horizontal	1.04 rad / s (60° / s)	
		V	Vertical	1.04 rad / s (60° / s)	
	Wrist	R2	Rotation 2	1.39 rad / s (80° / s)	
		B	Bending	1.39 rad / s (80° / s)	
		R1	Rotation 1	2.18 rad / s (125° / s)	
Wrist torque		R2	Rotation 2	3,273 N.m (334 Kgf.m)	
		B	Bending	3,273 N.m (334 Kgf.m)	
		R1	Rotation 1	1,882 N.m (192 Kgf.m)	
Accuracy of position repeatability				± 0.04 mm	
Ambient Temperature				$0 \sim 45^\circ \text{C}$ ($273 \sim 318 \text{ K}$)	
Robot's Weight				3,200 Kg	

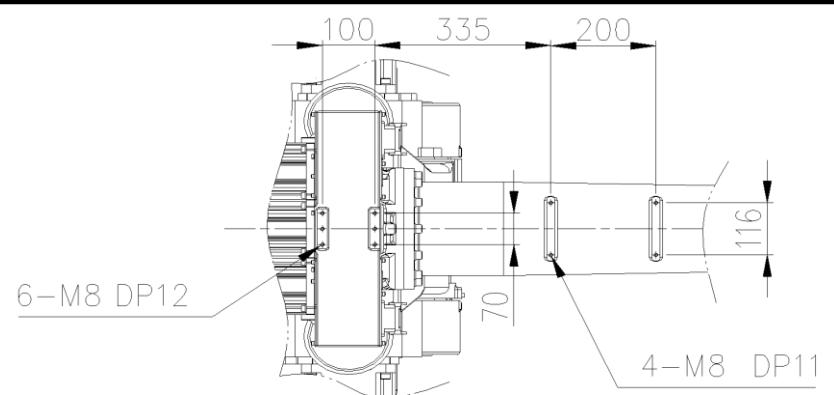
VIEW C: Application cable connection part (Option)



VIEW D: Application cable connection part (Option)



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.**