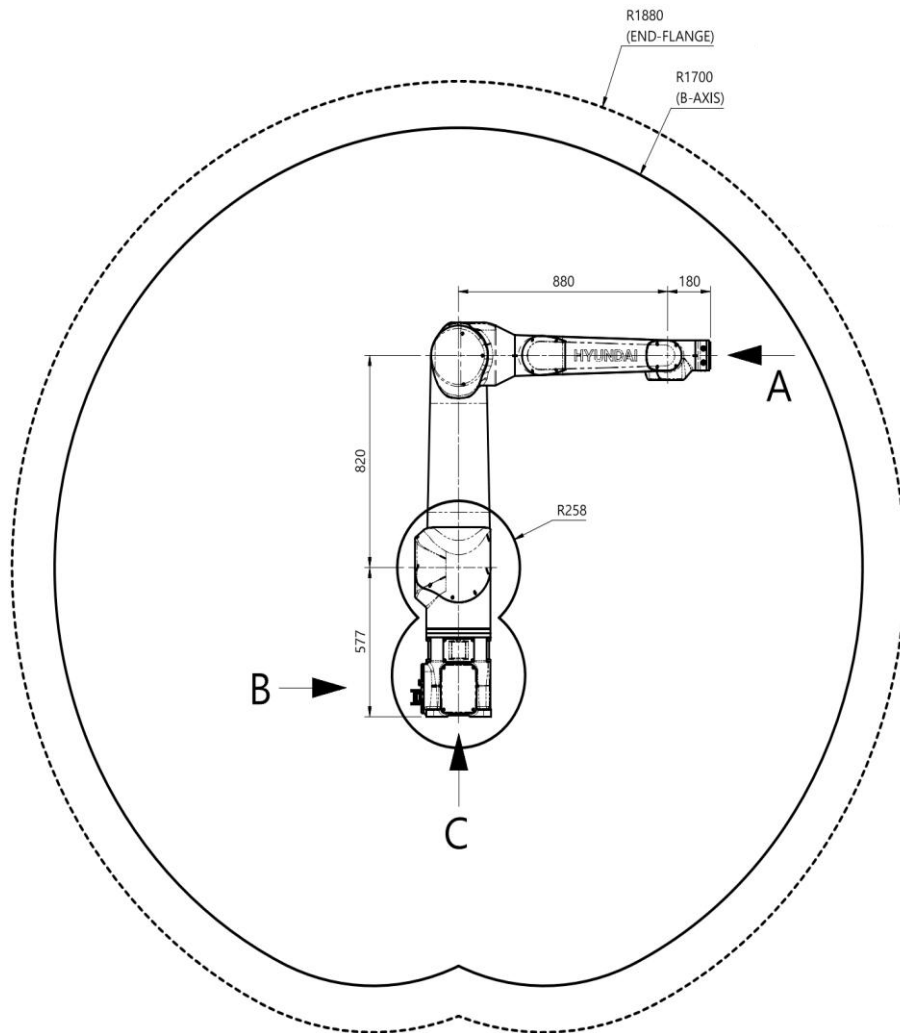
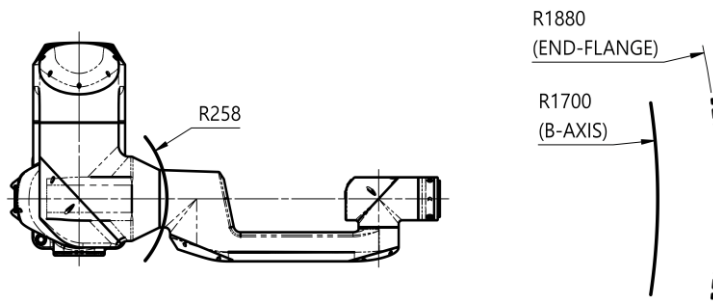
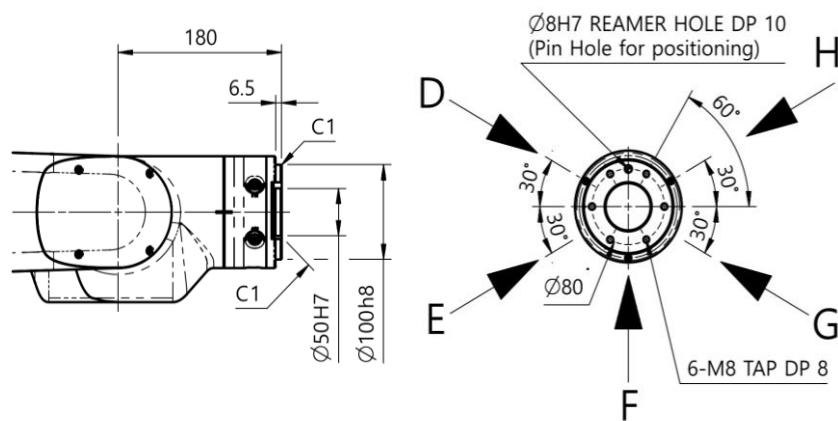


HDC35-18

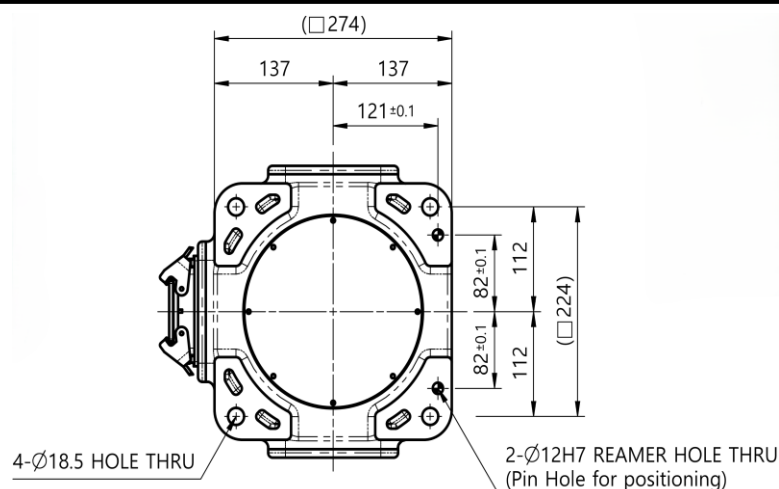
Payload 35Kgf



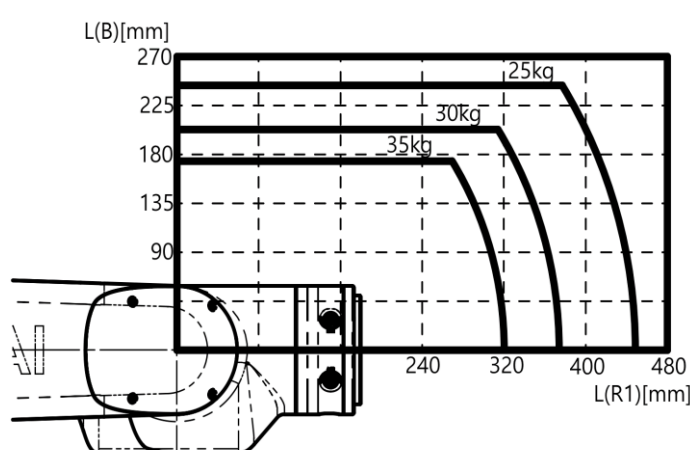
View A: Detailed drawing of the wrist attachment part



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

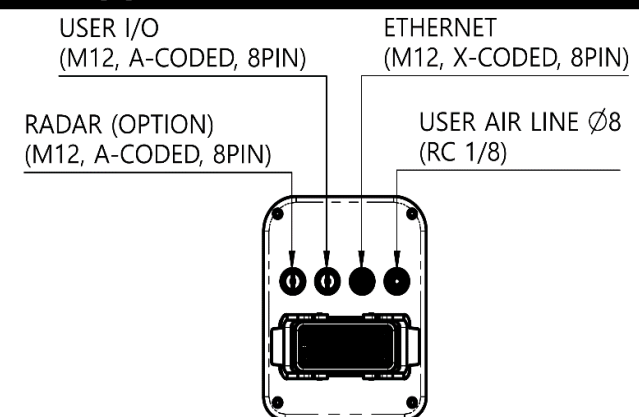


Wrist-axis torque line diagram



Item				Specification
Robot model				HDC35-18
Payload				35 Kg
Structure				Articulated
Degree of freedom				6 axes
Max. working envelope	A r m	S	Swivel	±190°
		H	Horizontal	+244° ~ -64°
		V	Vertical	+252° ~ -73°
		H/V	Interference	+260° ~ -170°
	Wrist	R2	Rotation 2	±190°
		B	Bending	±190°
		R1	Rotation 1	±190°
Max. working speed	A r m	S	Swivel	180° / sec
		H	Horizontal	170° / sec
		V	Vertical	200° / sec
	Wrist	R2	Rotation 2	350° / sec
		B	Bending	350° / sec
		R1	Rotation 1	400° / sec
Wrist torque		R2	Rotation 2	110 N.m (11.0 kgf.m)
		B	Bending	110 N.m (11.0 kgf.m)
		R1	Rotation 1	60 N.m (6.0 kgf.m)
Accuracy of position repeatability				±0.05 mm
Ambient Temperature				0 ~ 45 °C (273 ~ 318 K)
Robot's Weight				215 Kg

View B: Application cable connection part

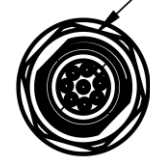


View D, E: Application cable connection part

ETHERNET (M12, X-CODED, 8PIN) USER I/O (M12, A-CODED, 8PIN)



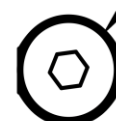
VIEW D



VIEW E

View F, G, H: Application cable connection part

USER AIR LINE Ø19 (G 1/4) TOOL I/O (M8, A-CODED, 8PIN) RS485 (M8, A-CODED, 8PIN)



VIEW F



VIEW G



VIEW H

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