

HM-G Series
Specifications : Basic model / Overhead-mount

Item		Basic model / Overhead-mount			
Model name of robot set (Note 1)		HMS-4070*G	HMS-4A70*G	HMS-4085*G	HMS-4A85*G
Model name of robot unit		HMS-4070*GM	HMS-4A70*GM	HMS-4085*GM	HMS-4A85*GM
Overall arm length		350(J1:first arm) + 350(J2:second arm) = 700mm		350(J1:first arm) + 500(J2:second arm) = 850mm	
Motion angle and stroke	J1(1st axis)	±165°			
	J2(2nd axis)	±145°		±142°	
	Z(3rd axis) (*)	* = 2 : 200mm, * = 3 : 300mm, * = 4 : 400mm			
	T(4th axis)	±360°			
Axis combination		J1(1st axis) + J2(2nd axis) + Z(3rd axis) + T(4th axis)			
Maximum payload		10kg	20kg	10kg	20kg
Maximum composite speed	At the center of the hand mounting flange	9,700mm/s		11,000mm/s	
	Z	2,760mm/s		2,300mm/s	2,110mm/s
	T	2,220°/s	1,540°/s	2,220°/s	1,540°/s
Position repeatability(at the constant ambient temperature)	J1+J2	±0.02mm		±0.025mm	
	Z	±0.01mm			
	T	±0.005°			
Maximum force-fit		98N(one second or less)			
Maximum allowable inertia moment (payload)		0.25kgm ² (10kg)	0.45kgm ² (20kg)	0.25kgm ² (10kg)	0.45kgm ² (20kg)
Position detection		Absolute encoder			
Drive motor and brake		AC servomotors for all joints, Z-axis air balance cylinder, Brake for Z-axis.			
Brake releasing		Enter a brake release command with the teach pendant or mini-pendant.			
User air piping		4 systems (φ6)			
User signal line		24(for proximity sensor signals, etc.)			
Air source	Operating pressure	0.05 to 0.35MPa			
	Maximum allowable pressure	0.59MPa			
Weight		approx. 52kg (115 lb)(Note : for the value of each model, refer to the nameplate)			

Note 1 : The model name of robot set refers to the model name of a complete set including a robot unit, controller. An asterisk * in model names denotes the Z-axis stroke.