

HM-G Series									
Specifications : Basic model / UL-listed									
Item		Basic model / UL-listed							
Model name of robot set (Note 1)		HM-4060*G-UL	HM-4A60*G-UL	HM-4070*G-UL	HM-4A70*G-UL	HM-4085*G-UL	HM-4A85*G-UL	HM-40A0*G-UL	HM-4AA0*G-UL
Model name of robot unit		HM-4060*GM-UL	HM-4A60*GM-UL	HM-4070*GM-UL	HM-4A70*GM-UL	HM-4085*GM-UL	HM-4A85*GM-UL	HM-40A0*GM-UL	HM-4AA0*GM-UL
Overall arm length		250(J1:first arm) + 350(J2:second arm) = 600mm		350(J1:first arm) + 350(J2:second arm) = 700mm		350(J1:first arm) + 500(J2:second arm) = 850mm		500(J1:first arm) + 500(J2:second arm) = 1,000mm	
Motion angle and stroke	J1(1st axis)	±165°							
	J2(2nd axis)	±143°				±147°			
	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	10kg	20kg	10kg	20kg
Maximum composite speed	At the center of the hand mounting flange	8,800mm/s		9,700mm/s		11,000mm/s		11,500mm/s	
	Z	2,760mm/s				2,300mm/s		2,110mm/s	
	T	2,220°/s	1,540°/s	2,220°/s	1,540°/s	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)	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 Brakes for J1, J2, Z-axis							
Brake releasing		(1) Press the brake release switch when the controller power is ON. (2) The teach pendant or mini-pendant cannot release the brakes.							
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. 54kg (119 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.