



Application				
Spot welding	•			
Arc welding	•			
Handling	•			
Assembly	•			
Sealing	•			
Painting				

	Item Robot model Payload				Specification
1					YL012
					12 kg
1	Structure				Articulated
ļ.,	Degree of freedom				6 axes
		Drive	syste	m	AC SERVO MOTOR
		Α	S	Swivel	±3.142 rad (±180°)
	Max.	r	Н	Horizontal	+2.37~-0.79rad(+270°~-90°)
	working	m*	٧	Vertical	±3.142rad(±180°)
	envelop e	Wrist	R2	Rotation 2	±3.142rad(±180°)
			В	Bending	±3.142rad(±180°)
			R1	Rotation 1	±3.142rad(±180°)
		Α	S	Swivel	3.142rad(180°/sec)
	Max.	r	Н	Horizontal	2.182rad(125°/sec)
		m	٧	Vertical	3.142rad(180°/sec)
	working speed		R2	Rotation 2	3.142rad(180°/sec)
	Speed	Wrist	В	Bending	3.142rad(180°/sec)
			R1	Rotation 1	3.142rad(180°/sec)
				Rotation 2	49 N.m (5.0 kgf.m)
	Wrist to	Wrist torque B Bending 54.9 N.m (5.0	54.9 N.m (5.6 kgf.m)		
				Rotation 1	27.4 N.m (2.8 kgf.m)
	Accuracy of position repeatability				±0.1 mm
	Ambient Temperature				0 ~ 45 °C (273 ~ 313 K)
	Robot's Weight Working envelope section area				43 Kg
					1305

*) When the optional limit switch is attached, the action range of the main

will be limited (see the manual)

View C: Application cable connection part



CONNECTOR: T4171130012-001(TE)

User I/O Port						
Pin No.	Description	Pin No.	Description			
1	Digital out CHO	7	Digital in CH2			
2	Digital out CH1	8	Digital in CH3			
3	Digital out CH2	9	Analog in CHO			
4	Digital out CH3	10	Analog in CH1			
5	Digital in CHO	11	Voltage out			
6	Digital in CH1	12	GND			



CONNECTOR: T4071017041-001(TE)

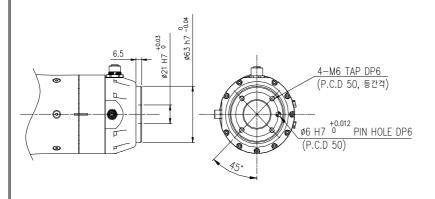
EtherCAT Port		
Pin No.	Description	
1	TX +	
2	TX -	
3	RX +	
4	RX -	

View C: Detailed drawing of the wrist attachment

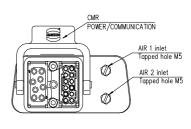
125.7

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

2-ø6 H7 0 PIN HOLE DP6



View B: Application cable connection part



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



Homepage: http://www.hyundai-robotics.com

"B"--|

4-ø9 HOLE THRU

107.13

107.13

"A"

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