stalling the eyeglass lens peripheral edge processing system is less likely to be limited, and an installation space is easily reduced.

[0010] The robot arm may perform both an operation for pivoting the holding unit to orient the holding unit toward the eyeglass manufacturing device and an operation for driving the arm unit to change a distance between the eyeglass manufacturing device and the holding unit. In this case, the disposition of the plurality of eyeglass manufacturing devices is much less likely to be limited.

[0011] The installation surface of the robot arm may be a horizontal surface. The plurality of eyeglass manufacturing devices may be disposed to surround the robot arm along a circumferential direction round on the rotation axis (hereinafter, referred to as a "pivot axis") around which the robot arm installed on the installation surface pivots the holding unit. In this case, for example, compared to a case where the plurality of eyeglass manufacturing devices are aligned on a straight line along the conveyor, a space for installing the eyeglass lens peripheral edge processing system can be more easily reduced. Furthermore, the robot arm pivots the holding unit. In this manner, the robot arm can easily move (switch) the eyeglass lens between the plurality of eyeglass manufacturing devices disposed to surround the robot arm. Therefore, the eyeglass lens is more properly processed.

[0012] In a case where three or more eyeglass manufacturing devices are used, the plurality of eyeglass manufacturing devices may be disposed clockwise or counterclockwise in the order of performing the steps on the eyeglass lens when viewed in a direction of the pivot axis of the robot arm. In this case, the robot arm can smoothly move the eyeglass lens to each of the plurality of eyeglass manufacturing devices in the order of performing the steps.

[0013] In addition, in the eyeglass lens peripheral edge processing system, a standby position where the eyeglass lens stands before the plurality of steps are performed by the plurality of eyeglass manufacturing devices may be set. The standby position may be provided at a position that surrounds the robot arm along the circumferential direction round on the pivot axis together with the plurality of eyeglass manufacturing devices. In addition, in the eyeglass lens peripheral edge processing system, a completion position for moving the eyeglass lens after the plurality of steps are completed by the plurality of eyeglass manufacturing devices may be set. The completion position may be provided at a position that surrounds the robot arm along the circumferential direction round on the pivot axis together with the plurality of eyeglass manufacturing devices. In this case, an installation space of the eyeglass lens peripheral edge processing system including at least one of the standby position and the completion position can be further reduced.

[0014] The robot arm may further include an arm movement unit that moves the arm unit in a direction which is at least parallel to a placement surface. In this case, the robot arm can properly move the object by moving the arm unit itself in a direction parallel to the placement surface, even in a case where a movement distance of the object is longer than a movable range of the arm unit. Therefore, the plurality of eyeglass lens peripheral edge processing devices are freely disposed in a further improved manner.

[0015] In addition, the arm movement unit may move the arm unit in a direction (height direction) perpendicular to the placement surface. In this case, for example, an insertion angle when the eyeglass lens is inserted into the eyeglass manufacturing device is freely set in a further improved manner by changing a height of the arm unit.

[0016] However, a position of the robot arm may be fixed. Even in this case, the plurality of eyeglass manufacturing devices is freely disposed in a sufficiently improved manner, compared to a case where only a conveyor is used. In addition, in a case where the arm movement unit is used, the arm movement unit may move the arm unit in both the direction parallel to the placement surface and the direction perpendicular to the installation surface, or may move the arm unit only in one of the direction parallel to the placement surface and the direction perpendicular to the installation surface.

[0017] The eyeglass lens peripheral edge processing system may include a plurality of the robot arms. In this case, each of the plurality of robot arms can be independently driven. Accordingly, the plurality of eyeglass lenses can be moved in parallel by the plurality of robot arms. Therefore, the plurality of steps can be more smoothly performed. In addition, the object (for example, the eyeglass lens) may be transferred between the plurality of robot arms. In this case, compared to a case where one robot arm is used, a range in which the object can be moved by the robot arm is enlarged. Therefore, the eyeglass lens peripheral edge processing system is freely disposed in the further improved manner.

[0018] An eyeglass lens peripheral edge processing system described as an example in the present disclosure includes a plurality of eyeglass manufacturing devices, a robot arm, and a controller. The plurality of eyeglass manufacturing devices perform mutually different steps out of a plurality of steps for processing an eyeglass lens, and have mutually different housings. The robot arm includes an arm unit and a holding unit. The arm unit has a plurality of joint portions. The holding unit is provided in the arm unit to hold and release an object. The robot arm rotates the arm unit via the joint portion to move the object held by the holding unit. The controller performs various controls on the eyeglass lens peripheral edge processing system. The controller performs a position storing process and a movement process. The controller that performs the position storing process stores installation position information indicating an installation position where the eyeglass lens is installed and unloaded for each of the plurality of eyeglass manufacturing devices, in a memory device. The controller that performs the movement process controls an operation of the robot