

ABSTRACT

The present invention provides a robot capable of easily performing positioning of a workpiece without providing a positioning jig at a predetermined position. The robot includes: a restricting member configured to restrict a horizontal movement of a predetermined workpiece, the restricting member being provided at a first hand tip provided at a tip end of a first arm; and a workpiece moving member configured to generate an action for horizontally moving the workpiece, the workpiece moving member being provided at a second hand tip provided at a tip end of a second arm. The controller performs a control operation of positioning the workpiece at a stop position in such a manner that: based on predetermined size information of the workpiece and preset stop position information of the workpiece, the restricting member is positioned at a predetermined restricting position included in the stop position for the workpiece, and the workpiece moving member acts on the workpiece and is moved toward the restricting position to horizontally move the workpiece; and the workpiece is brought into contact with the restricting member.