second end 250, and an elongated portion 252 extending therebetween. The first end 248 of the first portion 246 of the arm 244 can be generally cylindrical and can be rotatably mounted within a portion of the transverse member 242 of the bridge. A motor (not shown) can be disposed within the first end 248 of the first portion 246 of the arm 244. The motor can be a servomotor, a stepper motor, or the like. Further, actuating the motor may cause the arm 244 to rotate around an axis 254, passing through a center of the first end 248 of the first portion 246 of the arm 244, that may be generally perpendicular to the first and second portions 238, 240 of the bridge 232. The second end 250 of the first portion 246 of the arm 244 can be formed with a bore 256 extending substantially perpendicularly therethrough. Further, the second end 250 of the first portion 246 of the arm 244 can include a slot 258 extending therethrough at least partially along the length of the elongated portion 252 of the first portion 246 of the arm 244.

The articulating arm 244 can also include a second portion 260 having a first end 262, a second end 264, and an elongated portion 266 extending therebetween. The elongated portion 266 can include an offset disc-shaped portion 268 located centrally along the elongated portion 266 of the second portion 260 of the arm 244. The offset disc-shaped portion 268 has a center that is spaced apart a distance, D, from the longitudinal axis of the elongated portion 266 of the second portion 260 of the articulating arm 244. The offset disc-shaped portion 268 of the second portion 260 of the arm 244 is configured to fit into and rotate within the bore 256 formed in the second end 250 of the first portion 246 of the arm 244. The slot 258 formed in the second end 250 of the first portion of the arm 244 can allow the second portion 260 of the arm 244 to rotate nearly 180° with respect to the first portion 246 of the arm 244 and can allow the second portion 260 of the arm 244 to be rotated nearly parallel to the first portion 246 of the arm 244.

In a particular aspect, a motor (not shown) can be disposed within the offset disc-shaped portion 268 of the second portion 260 of the articulating arm 244. The motor can be a servomotor, a stepper motor, or the like. Further, actuating the motor can cause the second portion 260 of the articulating arm 244 to rotate with respect to the first portion 246 of the articulating arm 244 around an axis 270, passing through a center of the offset disc-shaped portion 268 of the second portion 260 of the articulating arm 244, that is generally perpendicular to the first and second portions 238, 240 of the bridge 232.

As further shown in the figures, the HTHS 230 can include a first gripper 280 attached to, or disposed on, the first end 262 of the second portion 260 of the articulating arm 244. Further, the HTHS 230 can include a second gripper 282 attached to, or disposed on,

CLAIMS

1. A system for conducting subterranean operations comprising:

a vertically orientated support structure rotationally coupled to a rig floor;

a first tubular handler coupled to the support structure, the first tubular handler configured to manipulate a first tubular;

a second tubular handler coupled to the support structure and distinct from the first tubular handler, wherein the second tubular handler is configured to move along the support structure relative to the first tubular handler, and wherein the second tubular handler is configured to manipulate a second tubular; and

characterized in that the first tubular handler and the second tubular handler are configured to spin an end of the first tubular into or out of an end of the second tubular.

2. The system of claim 1, further comprising a tool system coupled to the support structure and adapted to perform an operation on the first tubular.

3. The system of claim 2, wherein the tool system comprises at least one of a torque wrench, a robotic arm, an electric motor, a pipe rack system, or any combination thereof.

4. The system of claim 1, wherein the pipe handler further comprises a first torque wrench that is statically coupled with the support structure.

5. The system of claim 4, wherein the pipe handler further comprises a second torque wrench coupled to the support structure.

6. The system of claim 5, wherein the first tubular handler is disposed circumferentially between the first and second torque wrenches.

7. The system of claim 5, wherein the first torque wrench is disposed at a first location along the support structure and the second torque wrench is disposed at a second location along the support structure, and wherein the first and second locations are disposed at a same vertical elevation.

8. The system of claim 5, wherein the first torque wrench is disposed at a first location along the support structure and the second torque wrench is disposed at a second location along the support structure, and wherein the first and second locations are disposed at different vertical elevations.

9. The system of claim 5, wherein the first torque wrench is adapted to receive the first tubular of a first diameter and the second torque wrench is adapted to receive a second tubular of a second diameter, and wherein the first diameter is different than the second diameter.

10. The system of claim 1, wherein the first tubular handler is adapted to:

spin an end of the first tubular into an end of a tubular string at a well center, or

spin the end of the first tubular from the end of the tubular string.

11. The system of claim 1, wherein the second tubular handler is disposed at a vertical elevation above the first tubular handler.

12. The system of claim 1, wherein the first tubular handler comprises:

a first portion coupled to the support structure;

a second portion coupled to the first portion;

a third portion coupled to the second portion;

a fourth portion coupled to the third portion; and

a gripper coupled with the fourth portion, wherein the gripper is adapted to engage with the first tubular and spin the first tubular.

13. The system of claim 12, wherein the gripper is pivotally coupled to the fourth portion.

14. The system of claim 12, wherein the first portion is rotatably coupled to the second portion at a second vertical axis, and wherein the second portion is configured to rotate relative to the first portion about the second vertical axis.