ABSTRACT

ROBOT HAND FOR SUBSTRATE TRANSFER

There is provided a robot hand (3) for substrate transfer in which the robot hand is so arranged that, even in case a substrate (S) gives rise to warping, the substrate (S) can be stably supported. On an upper surface of the robot hand (3) there is formed a first seating surface (6) on which is seated a lower-surface peripheral portion of the substrate (S) and, on a periphery thereof, there is formed an upwardly extended step (8). The step (8) is provided with a plurality of stair-shaped stages (8a, 8b, 8c). On an upper surface of the robot hand (3) inwardly away from the first seating surface (6) there is provided a second seating surface (9) which is inclined downward toward the center of the substrate (S) such that a lower surface of the substrate (S) is seated on the second seating surface (9) when the substrate (S) is warped downward into a concave shape.

Figure 3.