

# DELTA RL3-ATS-1200-6kg

Article number: A\_00050-02-ATS

Lubricant variant: Synthetic lubricants



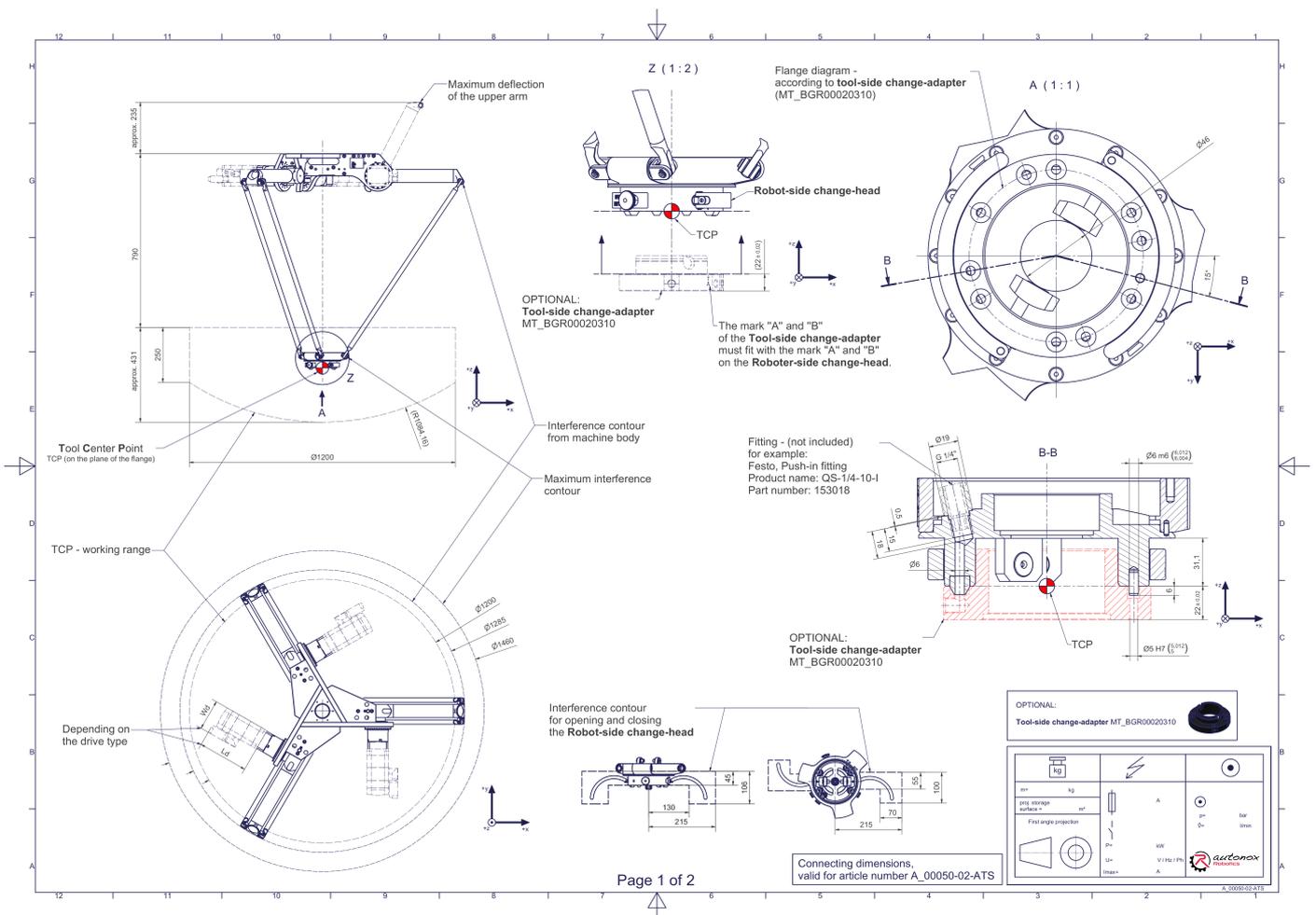
### Description:

This type of robot is based on the principle of parallel kinematics. All drives are mounted in a fixed position on the robot head. Motor cables are not moved. The robot has three (3) translational degrees of freedom.

### Scope of delivery:

Robot mechanics incl. gearbox, Servo motor adapter, Threaded protection caps, Transport and packing instructions

### Connecting dimensions:



**Downloads:** [Connecting dimensions \(PDF\)](#), [3D model \(STP\)](#), [3D model \(PDF\)](#)

We refer to our [General Terms of Sale and Supply](#) and [Terms of use](#).

## Technical specifications:

|  |  |
|--|--|
| Field of application   | Standard (not hygienic)  |
| Kinematics   | Parallel   |
| Translatory Degrees of Freedom (X,Y,Z)                         | 3  |
| Rotational Degrees of Freedom ( $\alpha,\beta,\gamma$ )        | 0  |
| Nominal payload [kg   lbs] *                                   | 6   13.2   |
| Working area-diameter [mm   in]                                | 1200   47.2  |
| Working height outside [mm   in]                               | 250   9.8  |
| Working height center [mm   in]                                | 431   17.0   |
| Manual tool changing system ATS                                | Tenfold media transmission (Compressed air 6 bar   87.0 psi / vacuum -850 mbar   -12.3 psi / min. inner-Ø: 6 mm   0.24 in) |
| Bearing type of the arm joints                                 | Roller bearing   |
| Lubricants of the gearboxes                                    | Synthetic  |
| Cleaning   | No high pressure   |
| Ambient temperature [°C   °F]                                  | 0 to +40   +32 to +104   |
| Relative humidity level [%]                                    | 95 (free of condensation)  |
| Mounting position  | Floor, Ceiling, Wall (on request), Angle (on request)  |
| Robot weight without drive engineering (esp. drive) [kg   lbs] | 34   75.0  |

\* All given values are nominal values (nominal payload referred to a nominal performance) and can vary under realworld conditions depending on the application (tool specifications, load distances, reduction (partly) of the nominal performance when using food-grade lubricants, ...). Please consider our technical data sheets regarding the load capacity.

## Gearbox article number for this robot mechanics:

| Function                | Article number    | Document                              |
|-------------------------|-------------------|---------------------------------------|
| Drive of the upper arms | MT_BGR00013366-xx | Operating manual gearbox type 3 (PDF) |