

DELTA RL4-ATS-1300-6kg

Article number: A_00053-ATS

Lubricant variant: Synthetic lubricants



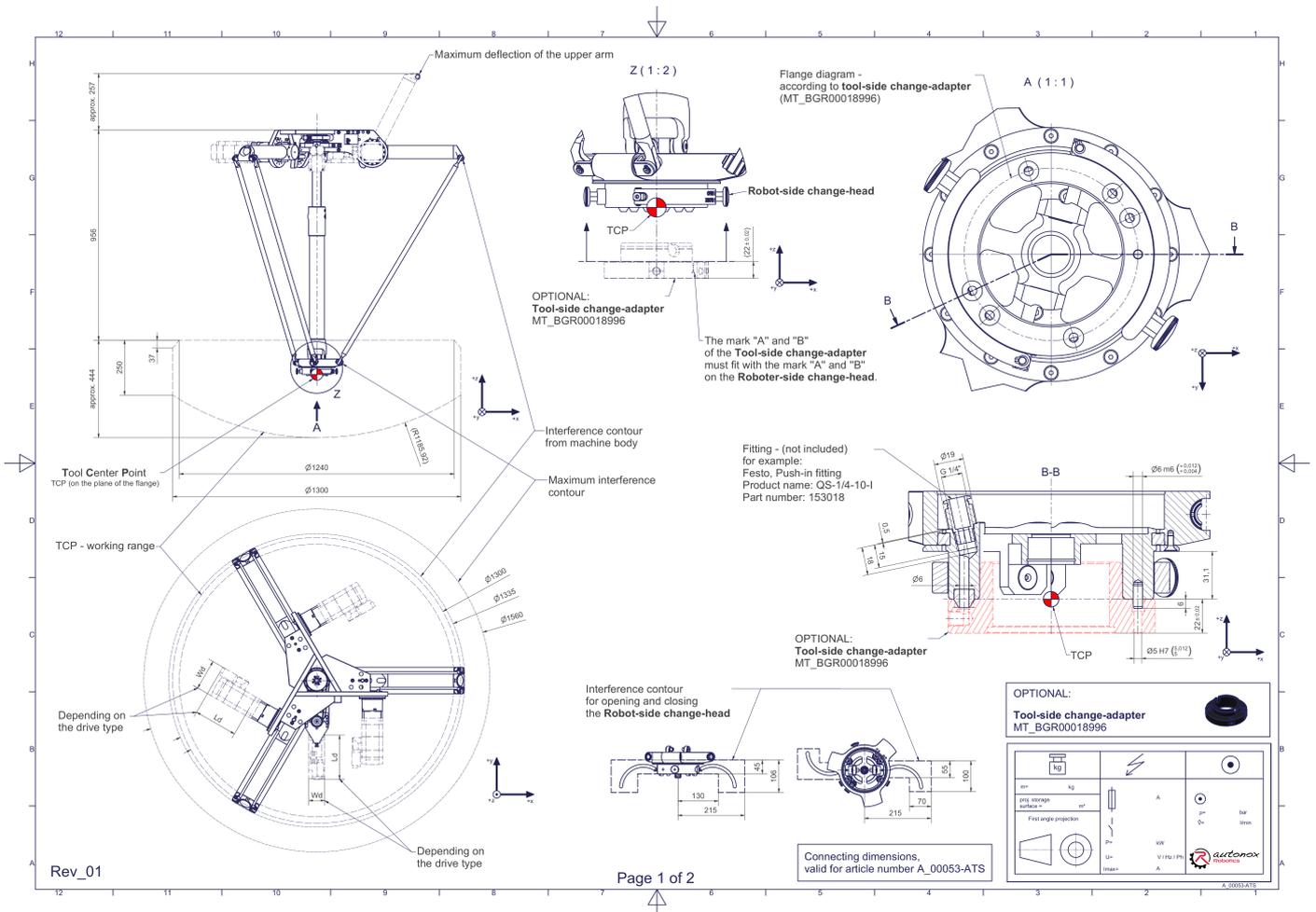
Description:

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 and one (1) rotational degree(s) 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 \(PDF\)](#)

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Technical specifications:

| | |
|--|--|
| Field of application | Standard (not hygienic) |
| Kinematics | Parallel |
| Translatory Degrees of Freedom (X,Y,Z) | 3 |
| Rotational Degrees of Freedom (α, β, γ) | 1 |
| Nominal payload [kg lbs] * | 6 13.2 |
| Working area-diameter [mm in] | 1300 51.2 |
| Working height outside [mm in] | 250 9.8 |
| Working height center [mm in] | 444 17.5 |
| Manual tool changing system ATS | Sixfold media transmission (Compressed air 6 bar 87.0 psi / vacuum -850 mbar -12.3 psi / min. inner- \varnothing : 6 mm 0.24 in) |
| Max. acceleration torque of the rotation γ around Z at the output [Nm in.lbs] | 40 354.0 |
| Nominal torque of the rotation γ around Z at the output [Nm in.lbs] | 33 292.1 |
| Max. speed of the rotation γ around Z at the output [1/min] | 225 |
| Nominal speed of the rotation γ around Z at the output [1/min] | 150 |
| Bearing type of the telescopic shaft(s) | Roller bearing |
| Bearing type of the arm joints | Roller bearing |
| Lubricants of the gearboxes | Synthetic |
| Cleaning | No high pressure |
| Ambient temperature [$^{\circ}$ C $^{\circ}$ 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] | 43 94.8 |

* 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) |
| Drive of the telescopic shaft for rotation γ around Z | MT_BGR00013360-xx | Operating manual gearbox type 1 (PDF) |

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