

# DELTA RL4-T1-1400-20kg

Article number: A\_00065-T1

Lubricant variant: Synthetic lubricants



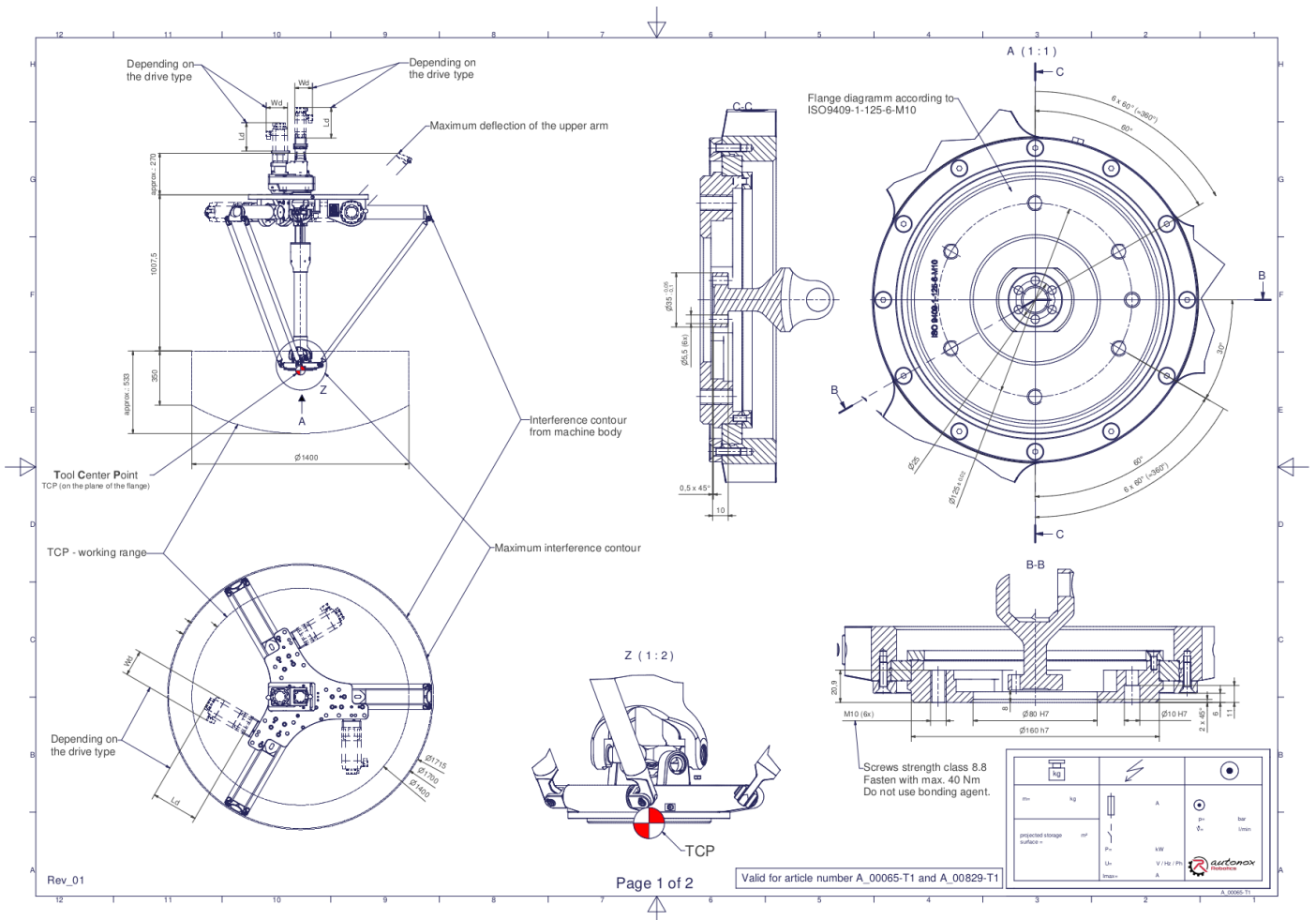
**Description:**

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 \(PDF\)](#)

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 ( $\alpha, \beta, \gamma$ )	1
Nominal payload [kg   lbs] *	20   44.1
Working area-diameter [mm   in]	1400   55.1
Working height outside [mm   in]	350   13.8
Working height center [mm   in]	533   21.0
Output type of the tool actuation	Flange (T)
Number of the tool actuation (telescopic shaft(s))	1
Max. acceleration torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]	240   2124.2
Nominal torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]	240   2124.2
Max. speed of the rotation $\gamma$ around Z at the output [1/min]	177
Nominal speed of the rotation $\gamma$ around Z at the output [1/min]	124
Max. acceleration torque of the tool actuation T/TS1 at the output [Nm   in.lbs]	40   354.0
Nominal torque of the tool actuation T/TS1 at the output [Nm   in.lbs]	23   203.6
Max. speed of the tool actuation T/TS1 at the output [1/min]	171
Nominal speed of the tool actuation T/TS1 at the output [1/min]	114
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 [°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]	125   275.6

\* 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_BGR00017292-U-xx	Operating manual gearbox type 3 (PDF)
Drive of the telescopic shaft for rotation $\gamma$ around Z	MT_BGR00018858-xx	Operating manual gearbox type 7 (PDF)
Drive of the telescopic shaft for tool actuation T/TS1	MT_WST00058592-xx	Operating manual gearbox type 6 (PDF)