

# DELTA RL3-TS1-ATS-900-6kg

Article number: A\_00086-TS1-ATS

Lubricant variant: Synthetic lubricants



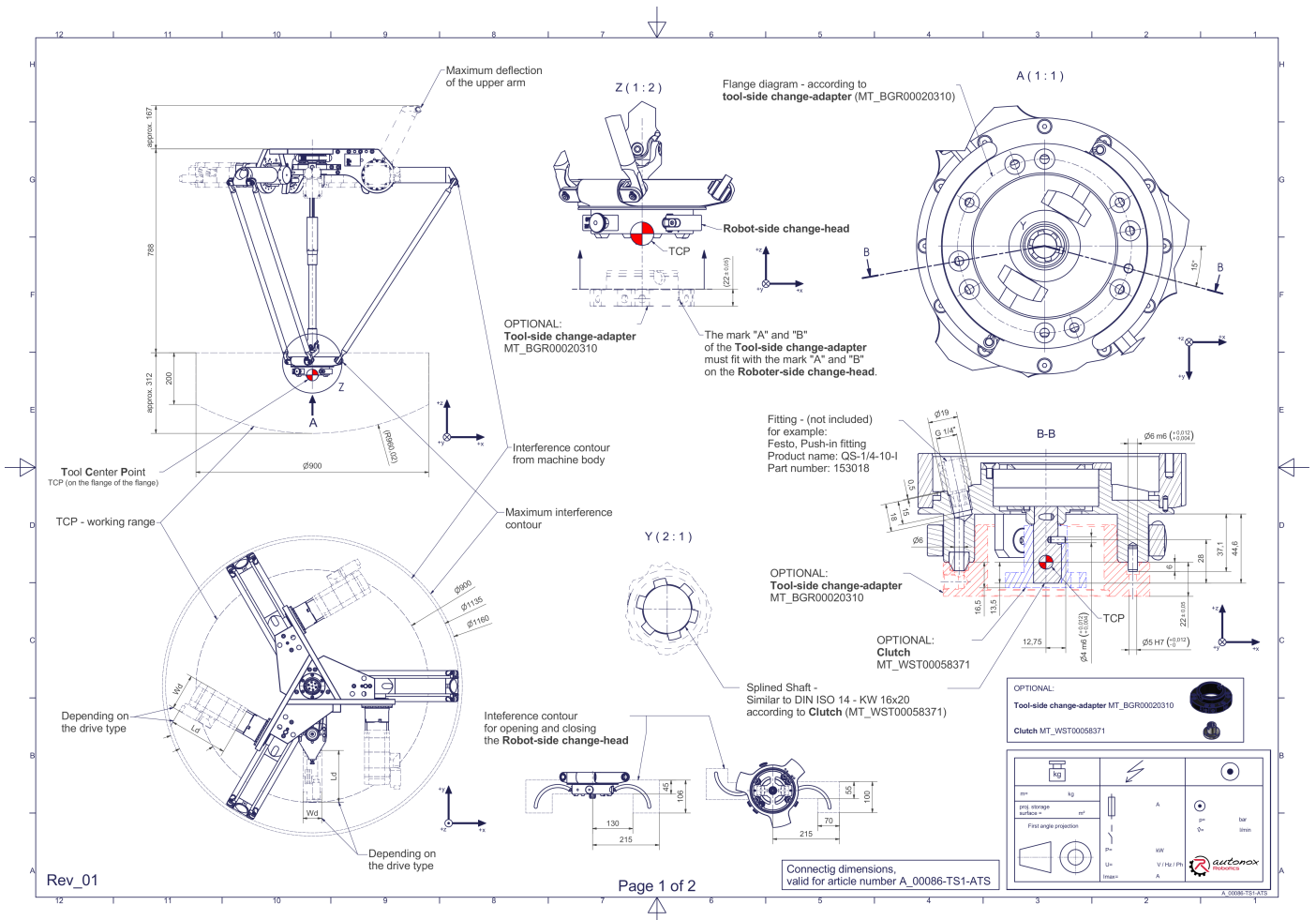
**Description:**

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 \(PDF\)](#)

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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)  | 0  |
| Nominal payload [kg   lbs] *   | 6   13.2   |
| Working area-diameter [mm   in]  | 900   35.4   |
| Working height outside [mm   in]   | 200   7.9  |
| Working height center [mm   in]  | 312   12.3   |
| Output type of the tool actuation  | Shaft (TS)   |
| Number of the tool actuation (telescopic shaft(s))                               | 1  |
| 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) |
| 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]           | 33   292.1   |
| Max. speed of the tool actuation T/TS1 at the output [1/min]                     | 225  |
| Nominal speed of the tool actuation T/TS1 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 [°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]                   | 42   92.6  |

\* 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_BGR00013366-xx | Operating manual gearbox type 3 (PDF) |
| Drive of the telescopic shaft for tool actuation T/TS1 | MT_BGR00013360-xx | Operating manual gearbox type 1 (PDF) |

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