



## 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] *	0,5   1.1
Working area-diameter [mm   in]	300   11.8
Working height outside [mm   in]	75   3.0
Working height center [mm   in]	112   4.4
Pose repeatability (RP) according to ISO 9283 [mm]	+/- 0,005
Max. acceleration torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]	3   26.6
Nominal torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]	1,5   13.3
Max. speed of the rotation $\gamma$ around Z at the output [1/min]	800
Nominal speed of the rotation $\gamma$ around Z at the output [1/min]	800
Bearing type of the telescopic shaft(s)	Roller bearing
Bearing type of the arm joints	Roller bearing
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 incl. drive engineering of the upper arm [kg   lbs]	92   202.8
Special features	High-end direct drives and high-precision joints for maximum repeatability, absolute accuracy and path accuracy in the 1/1000 mm range

\* 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.