DELTA RLL3-T1-1600-50kg



Article number: A_00650-T1

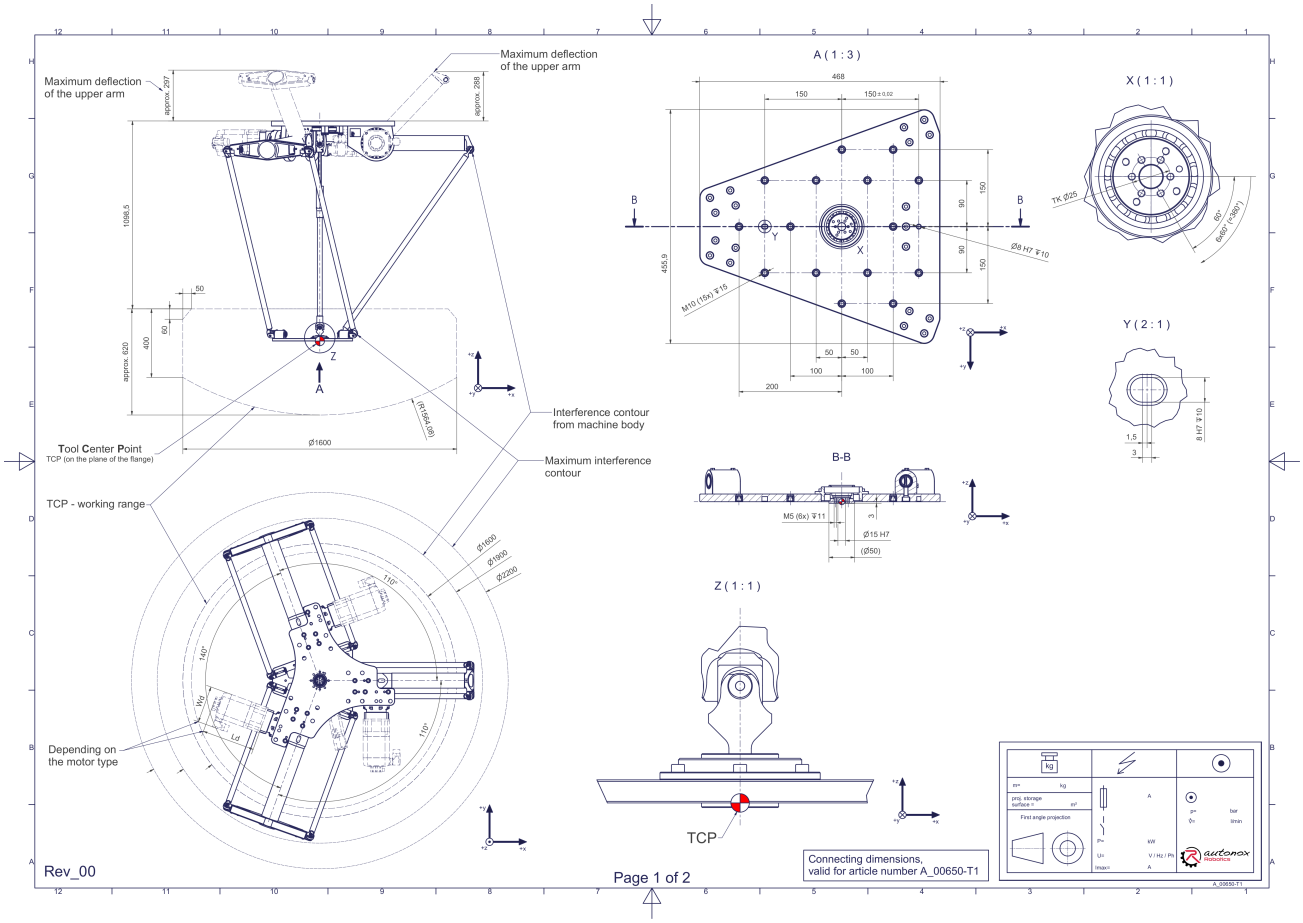
Lubricant variant: Synthetic lubricants

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 degrees of freedom.

Highlight:
The special RLL design features extreme tilting rigidity of the tool holder. This property allows applications with very long end effectors (e. g. multi-grippers), which introduce high tilting moments into the mechanics during movement.

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,ß,γ)	0
Nominal payload [kg|lbs] *	50 | 110.2
Working area-diameter [mm|in]	1600 | 63.0
Working height outside [mm|in]	400 | 15.7
Working height center [mm|in]	620 | 24.4
Output type of the tool actuation	Flange (T)
Number of the tool actuation (telescopic shaft(s))	1
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. motors) [kg|lbs]	126 | 277.8

* 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_BGR00021669-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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