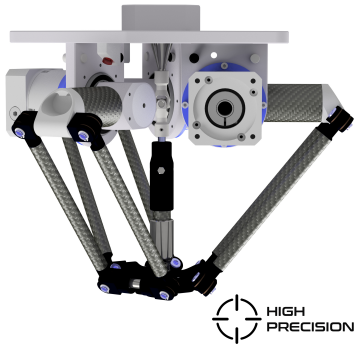
DELTA RL4-200-0,5kg

Article number: A_00807

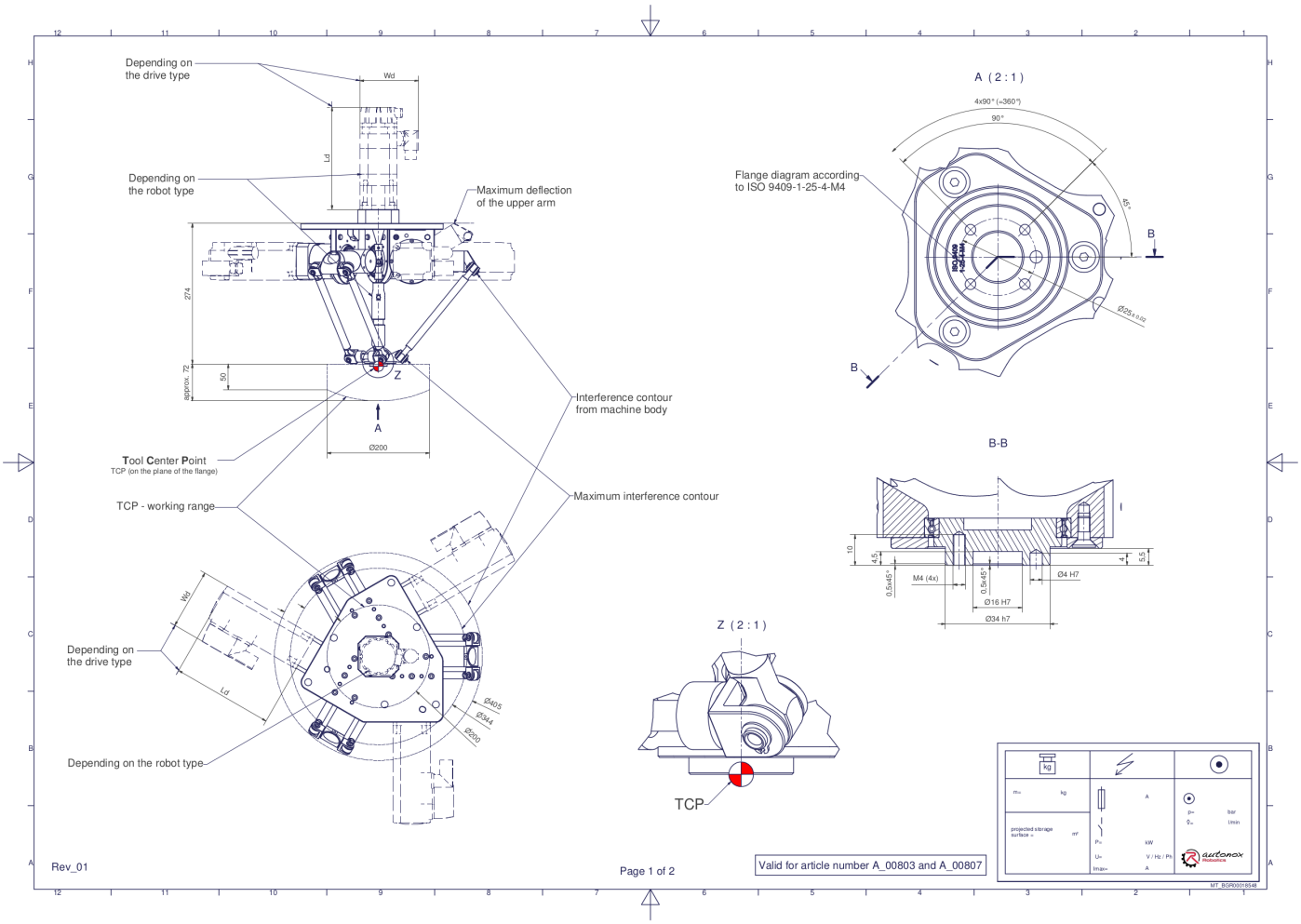
Lubricant variant: Synthetic lubricants



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), Precision
Kinematics	Parallel
Translatory Degrees of Freedom (X,Y,Z)	3
Rotational Degrees of Freedom (α,ß,γ)	1
Nominal payload [kg|lbs] *	0,5 | 1.1
Working area-diameter [mm|in]	200 | 7.9
Working height outside [mm|in]	50 | 2.0
Working height center [mm|in]	72 | 2.8
Pose repeatability (RP) according to ISO 9283 [mm] **	+/- 0,01
Max. acceleration torque of the rotation γ around Z at the output [Nm|in.lbs]	5,5 | 48.7
Nominal torque of the rotation γ around Z at the output [Nm|in.lbs]	5,5 | 48.7
Max. speed of the rotation γ around Z at the output [1/min]	800
Nominal speed of the rotation γ 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
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]	9,5 | 20.9

* 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.

** The accuracy achievable in practice depends, among other factors, on the control system used, as well as its parameter settings and control performance, and may therefore differ from the values stated here.

Gearbox article number for this robot mechanics:

Function	Article number	Document
Drive of the upper arms	MT_BGR00017965-xx	Operating manual gearbox type 3 (PDF)

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