

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)	2
Nominal payload [kg lbs] *	6 13.2
Working area-diameter [mm in]	1900 74.8
Working height outside [mm in]	400 15.7
Working height center [mm in]	740 29.1
Max. acceleration torque of the rotation α/β around X/Y at the output [Nm in.lbs]	135 1194.9
Nominal torque of the rotation α/β around X/Y at the output [Nm in.lbs]	135 1194.9
Max. speed of the rotation α/β around X/Y at the output [1/min]	77
Nominal speed of the rotation α/β around X/Y at the output [1/min]	77
Max. acceleration torque of the rotation γ around Z at the output [Nm in.lbs]	240 2124.2
Nominal torque of the rotation γ around Z at the output [Nm in.lbs]	240 2124.2
Max. speed of the rotation γ around Z at the output [1/min]	177
Nominal speed of the rotation γ around Z at the output [1/min]	124
Bearing type of the telescopic shaft(s)	Roller bearing
Bearing type of the arm joints	Roller bearing
Lubricants of the bearings	Synthetic
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]	127 280.0

* 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 γ around Z	MT_BGR00018858-xx	Operating manual gearbox type 7 (PDF)

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