

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] *	3 6.6
Working area-diameter [mm in]	1100 43.3
Working height outside [mm in]	200 7.9
Working height center [mm in]	387 15.2
Max. acceleration torque of the rotation α/β around X/Y at the output [Nm in.lbs]	16 141.6
Nominal torque of the rotation α/β around X/Y at the output [Nm in.lbs]	16 141.6
Max. speed of the rotation α/β around X/Y at the output [1/min]	82
Nominal speed of the rotation α/β around X/Y at the output [1/min]	82
Max. acceleration torque of the rotation γ around Z at the output [Nm in.lbs]	40 354.0
Nominal torque of the rotation γ around Z at the output [Nm in.lbs]	40 354.0
Max. speed of the rotation γ around Z at the output [1/min]	193
Nominal speed of the rotation γ around Z at the output [1/min]	79
Bearing type of the telescopic shaft(s)	Roller bearing
Bearing type of the arm joints	Roller bearing
Lubricants of the gearboxes	Gearbox of the upper arms: Synthetic; gearbox of the telescopic shaft: Food-grade (FO)
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]	51 112.4

* 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 rotation γ around Z	MT_WST00112739-xx-FO	Operating manual gearbox type 7 (PDF)

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