



## 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] *	12   26.5
Working area-diameter [mm   in]	1200   47.2
Working height outside [mm   in]	300   11.8
Working height center [mm   in]	453   17.8
Max. acceleration torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]	160   1416.1
Nominal torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]	80   708.1
Max. speed of the rotation $\gamma$ around Z at the output [1/min]	200
Nominal speed of the rotation $\gamma$ around Z at the output [1/min]	135
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]	96   211.6

\* 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_BGR00020777-U-xx	Operating manual gearbox type 3 (PDF)
Drive of the telescopic shaft for rotation $\gamma$ around Z	MT_BGR00018723-xx	Operating manual gearbox type 1 (PDF)

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