



## 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] *	3   6.6
Working area-diameter [mm   in]	1400   55.1
Working height outside [mm   in]	250   9.8
Working height center [mm   in]	449   17.7
Max. acceleration torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]	40   354.0
Nominal torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]	33   292.1
Max. speed of the rotation $\gamma$ around Z at the output [1/min]	225
Nominal speed of the rotation $\gamma$ around Z 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 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]	42   92.6
Special features	All drives (gearbox, reduction gearing, ...) are located below the head plate. Increased torque is available for Z rotation. Advantages: Easily accessible, easy to maintain, compact, high accelerations/decelerations around Z

\* 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_BGR00013926-xx	Operating manual gearbox type 3 (PDF)
Drive of the telescopic shaft for rotation $\gamma$ around Z	MT_BGR00013360-xx	Operating manual gearbox type 1 (PDF)

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