

## DELTA RLE4-1200-6kg

Article number: A\_00850

Lubricant variant: Synthetic lubricants



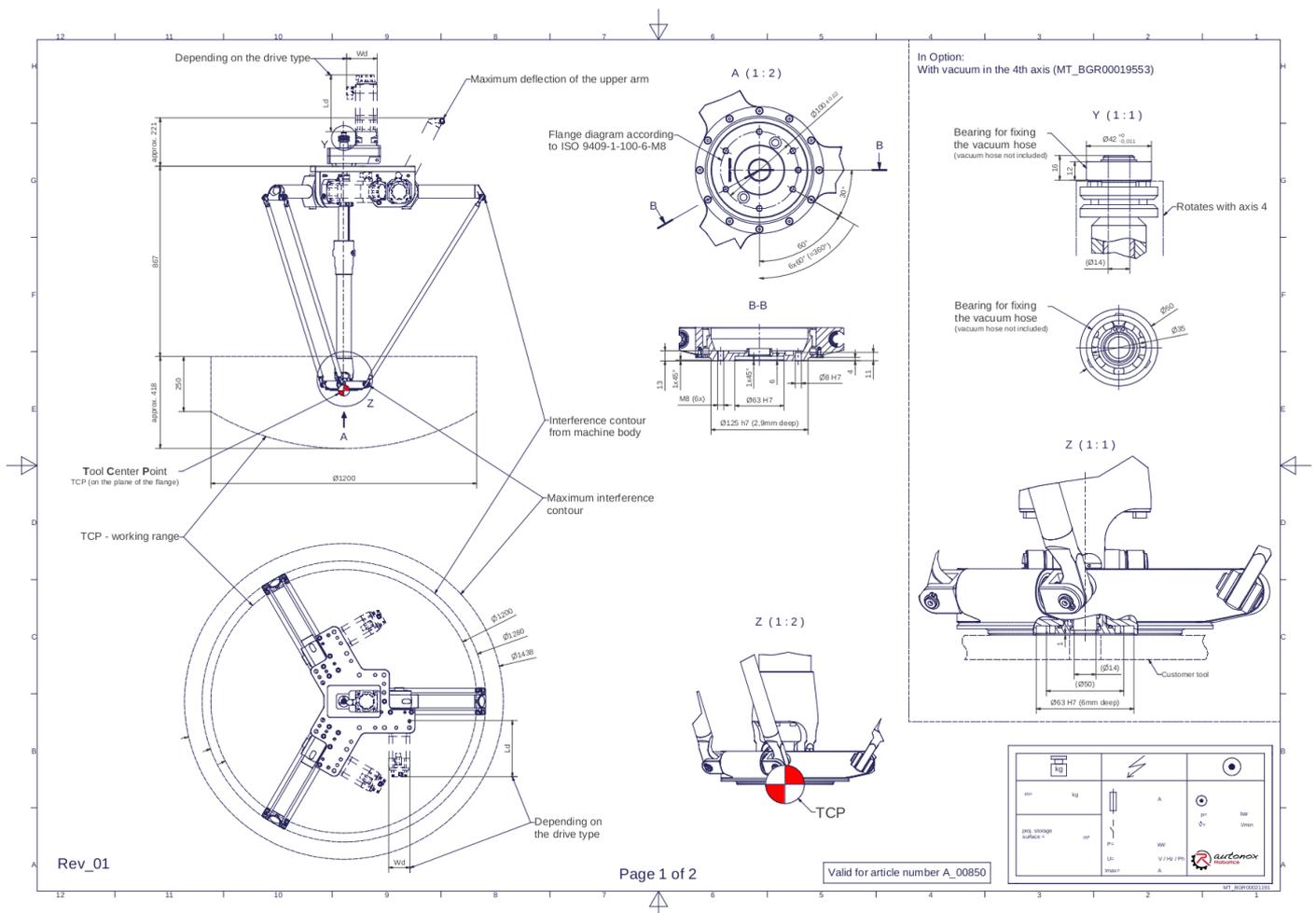
### Description:

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)                               |
| Kinematics   | Parallel  |
| Translatory Degrees of Freedom (X,Y,Z)   | 3   |
| Rotational Degrees of Freedom ( $\alpha, \beta, \gamma$ )                              | 1   |
| Nominal payload [kg   lbs] *   | 6   13.2  |
| Working area-diameter [mm   in]  | 1200   47.2   |
| Working height outside [mm   in]   | 250   9.8   |
| Working height center [mm   in]  | 418   16.5  |
| Max. acceleration torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs] | 100   885.1   |
| Nominal torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]           | 88   778.9  |
| Max. speed of the rotation $\gamma$ around Z at the output [1/min]                     | 558   |
| Nominal speed of the rotation $\gamma$ around Z at the output [1/min]                  | 413   |
| 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. drive) [kg   lbs]                         | 65   143.3  |

\* 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_BGR00021338    | Operating manual gearbox type 8 (PDF) |
| Drive of the telescopic shaft for rotation $\gamma$ around Z | MT_WST00057594-xx | Operating manual gearbox type 7 (PDF) |

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