

## Product data sheet <a href="https://autonoxfinder.com/en/A\_00855-01">https://autonoxfinder.com/en/A\_00855-01</a>

Date of download: Oct 21, 2025 Time of download: 17:43 UTC

### **DELTA RL3-1600-6kg**

Article number: A\_00855-01

Lubricant variant: Synthetic lubricants



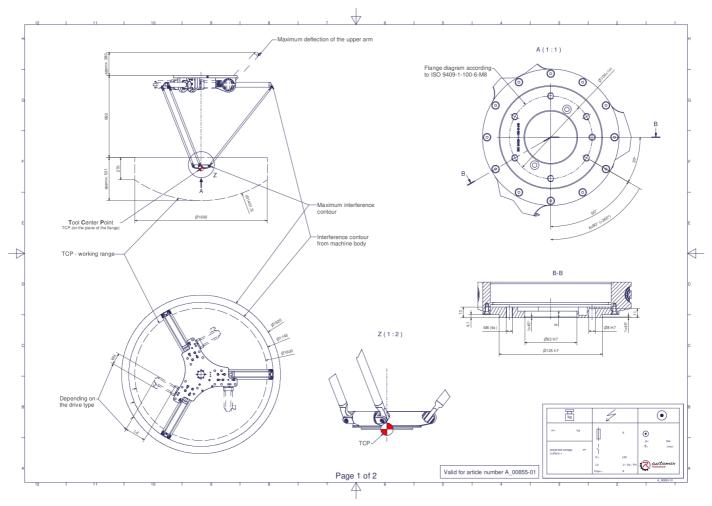
#### **Description:**

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 degrees of freedom.

#### **Scope of delivery:**

Robot mechanics incl. gearbox, Servo motor adapter, Threaded protection caps, Transport and packing instructions

### **Connecting dimensions:**



<u>Downloads:</u> <u>Connecting dimensions (PDF)</u> <u>3D model (STP)</u> <u>3D model (PDF)</u>



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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 ( $\alpha,\beta,\gamma$ )	0	
Nominal payload [kg lbs] *	6   13.2	
Working area-diameter [mm in]	1600   63.0	
Working height outside [mm in]	270   10.6	
Working height center [mm in]	521   20.5	
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)	

<sup>\*</sup> 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_WST00101407-xx	Operating manual gearbox type 3 (PDF)