



## 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-width X/Y [mm   in]	1175/1300   46.3/51.2
Working height outside [mm   in]	250   9.8
Working height center [mm   in]	400   15.7
Max. acceleration torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]	7,2   63.7
Nominal torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]	6   53.1
Max. speed of the rotation $\gamma$ around Z at the output [1/min]	500
Nominal speed of the rotation $\gamma$ around Z at the output [1/min]	460
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]	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 arm (X)	MT_BGR00020873-xx	Operating manual gearbox type 4 (PDF)
Drive of the upper arms (Y)	MT_WST00107969-xx	Operating manual gearbox type 3 (PDF)
Drive of the telescopic shaft for rotation $\gamma$ around Z	MT_WST00108161-xx	Operating manual gearbox type 1 (PDF)

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