

## DELTA RLT4-1100-3kg

Article number: A\_00869

**Lubricant variant:** Synthetic lubricants



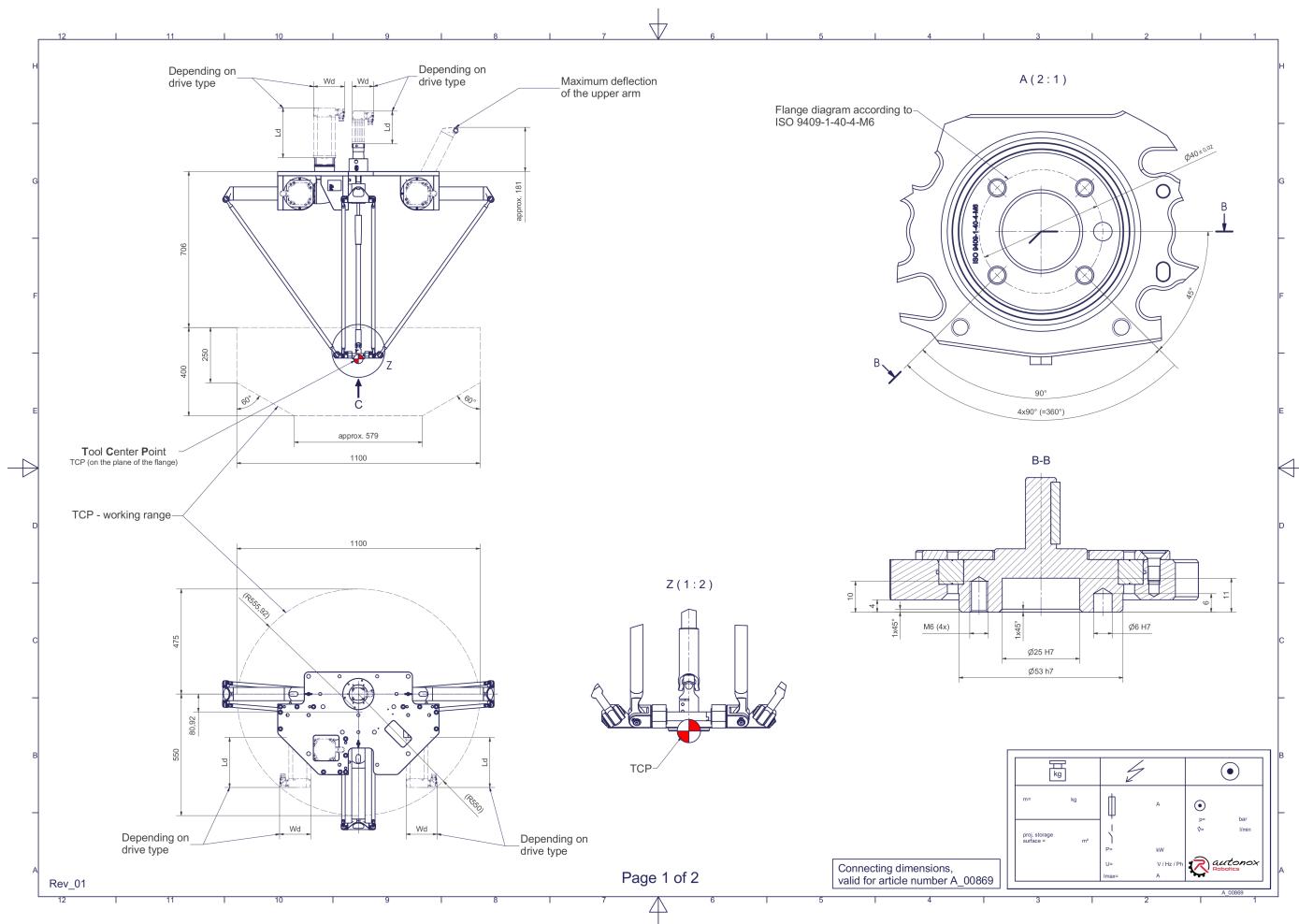
**Description:**

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 \(PDF\)](#)

We refer to our [General Terms of Sale and Supply](#) and [Terms of use](#).

## Technical specifications:

<b>Field of application</b>	Standard (not hygienic)
<b>Kinematics</b>	Parallel
<b>Translatory Degrees of Freedom (X,Y,Z)</b>	3
<b>Rotational Degrees of Freedom (α,β,γ)</b>	1
<b>Nominal payload [kg   lbs] *</b>	3   6.6
<b>Working area-width X/Y [mm   in]</b>	1025/1100   40.4/43.3
<b>Working height outside [mm   in]</b>	250   9.8
<b>Working height center [mm   in]</b>	400   15.7
<b>Max. acceleration torque of the rotation y around Z at the output [Nm   in.lbs]</b>	7,2   63.7
<b>Nominal torque of the rotation y around Z at the output [Nm   in.lbs]</b>	6   53.1
<b>Max. speed of the rotation y around Z at the output [1/min]</b>	500
<b>Nominal speed of the rotation y around Z at the output [1/min]</b>	460
<b>Bearing type of the telescopic shaft(s)</b>	Roller bearing
<b>Bearing type of the arm joints</b>	Roller bearing
<b>Lubricants of the bearings</b>	Synthetic
<b>Lubricants of the gearboxes</b>	Synthetic
<b>Cleaning</b>	No high pressure
<b>Ambient temperature [°C   °F]</b>	0 to +40   +32 to +104
<b>Relative humidity level [%]</b>	95 (free of condensation)
<b>Mounting position</b>	Floor, Ceiling, Wall (on request), Angle (on request)
<b>Robot weight without drive engineering (esp. drive) [kg   lbs]</b>	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 y around Z	MT_WST00108161-xx	Operating manual gearbox type 1 (PDF)