

# DuoPod RVS3Y-750-3kg

Article number: A\_00900-MV-FO

Mirror-inverted variant: Yes

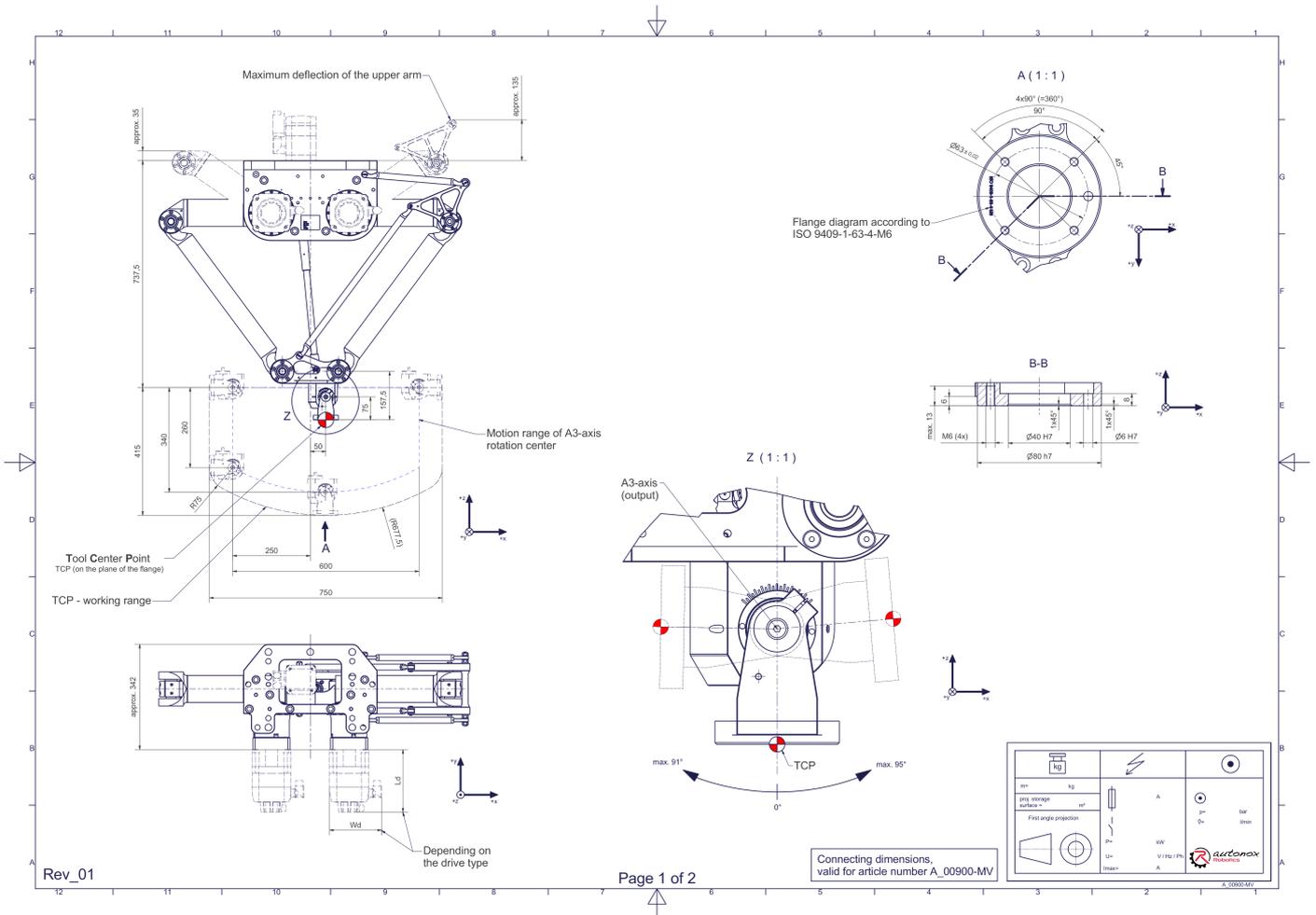
Lubricant variant: Food-grade lubricants (FO)



**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 two (2) translational and one (1) rotational degree(s) of freedom. The article number extension 'MV' (Mirrored Version) identifies the mirrored version of the mechanics. **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:

Field of application	Standard (not hygienic)
Kinematics	Parallel
Translatory Degrees of Freedom (X,Y,Z)	2
Rotational Degrees of Freedom ( $\alpha, \beta, \gamma$ )	1
Nominal payload [kg   lbs] *	3   6.6
Working area-width [mm   in]	750   29.5
Working height outside [mm   in]	260   10.2
Working height center [mm   in]	415   16.3
Max. acceleration torque of the rotation $\beta$ around Y at the output [Nm   in.lbs]	16   141.6
Nominal torque of the rotation $\beta$ around Y at the output [Nm   in.lbs]	16   141.6
Max. speed of the rotation $\beta$ around Y at the output [1/min]	82
Nominal speed of the rotation $\beta$ around Y at the output [1/min]	82
Bearing type of the telescopic shaft(s)	Roller bearing
Bearing type of the arm joints	Roller bearing
Lubricants of the bearings	Food-grade (FO)
Lubricants of the gearboxes	Food-grade (FO)
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]	53   116.8

\* 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_BGR00102242-xx-FO	Operating manual gearbox type 3 (PDF)