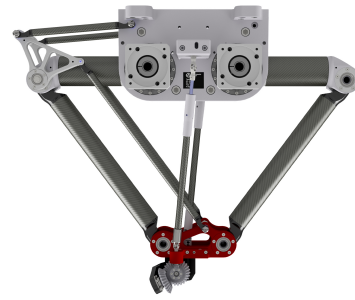


# DuoPod RVS3Y-T1-750-3kg

Article number: A\_00900-T1

Lubricant variant: Synthetic lubricants



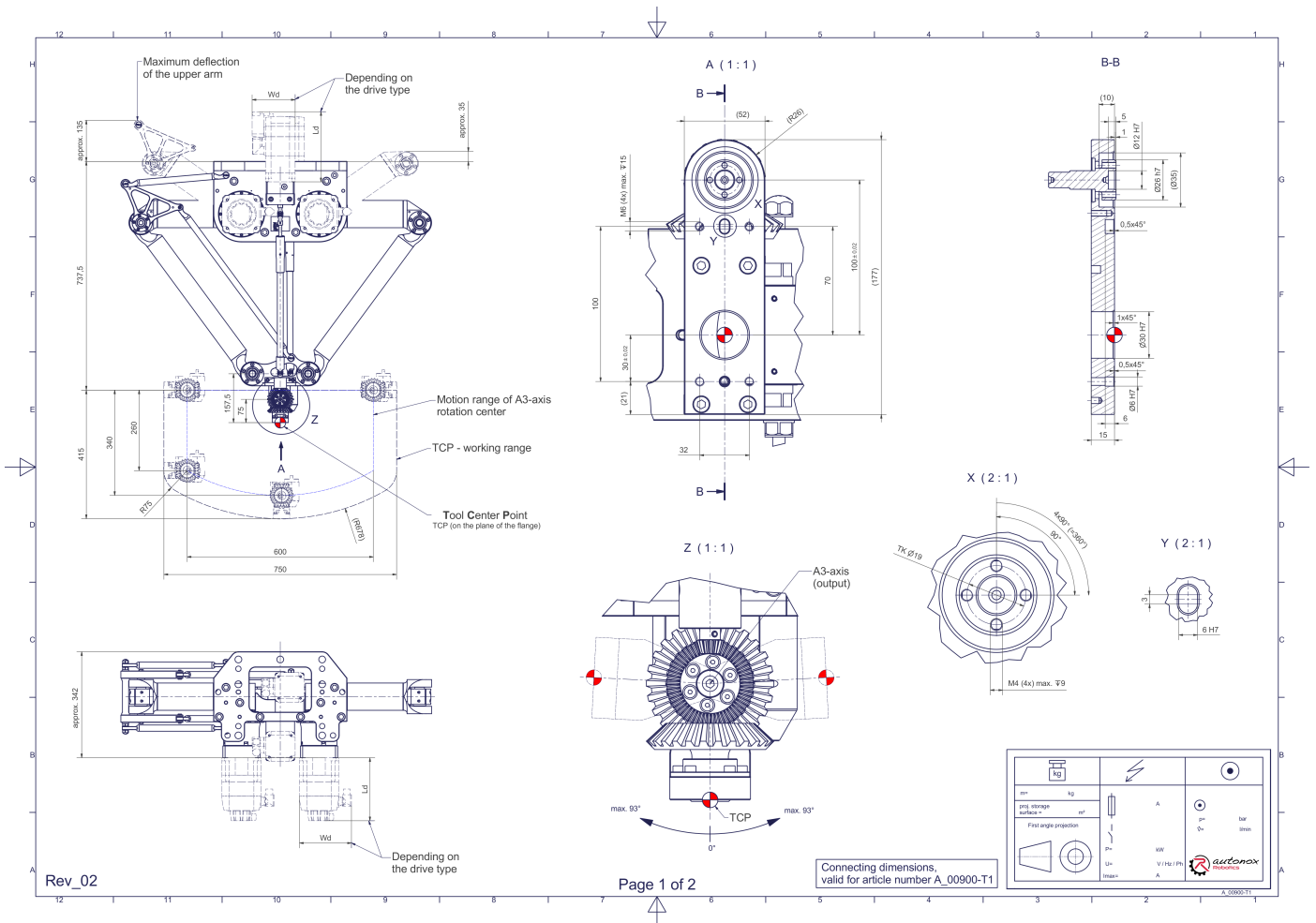
**Description:**

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 two (2) 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)  | 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]  | 275   10.8  |
| Working height center [mm   in]   | 415   16.3  |
| Output type of the tool actuation   | Flange (T)  |
| Number of the tool actuation (telescopic shaft(s))                                    | 1   |
| 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  |
| Max. acceleration torque of the tool actuation T/TS1 at the output [Nm   in.lbs]      | 13,3   117.7  |
| Nominal torque of the tool actuation T/TS1 at the output [Nm   in.lbs]                | 13,3   117.7  |
| Max. speed of the tool actuation T/TS1 at the output [1/min]                          | 228   |
| Nominal speed of the tool actuation T/TS1 at the output [1/min]                       | 228   |
| Bearing type of the telescopic shaft(s)   | Roller bearing  |
| 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) |
| Robot weight without drive engineering (esp. drive) [kg   lbs]                        | 57   125.7  |

\* 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_BGR00021002-U-xx | Operating manual gearbox type 3 (PDF) |

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