

## DuoPod RVS2-750-3kg

Article number: A\_00911

### Mirror-inverted variant: No

**Lubricant variant:** Synthetic lubricants



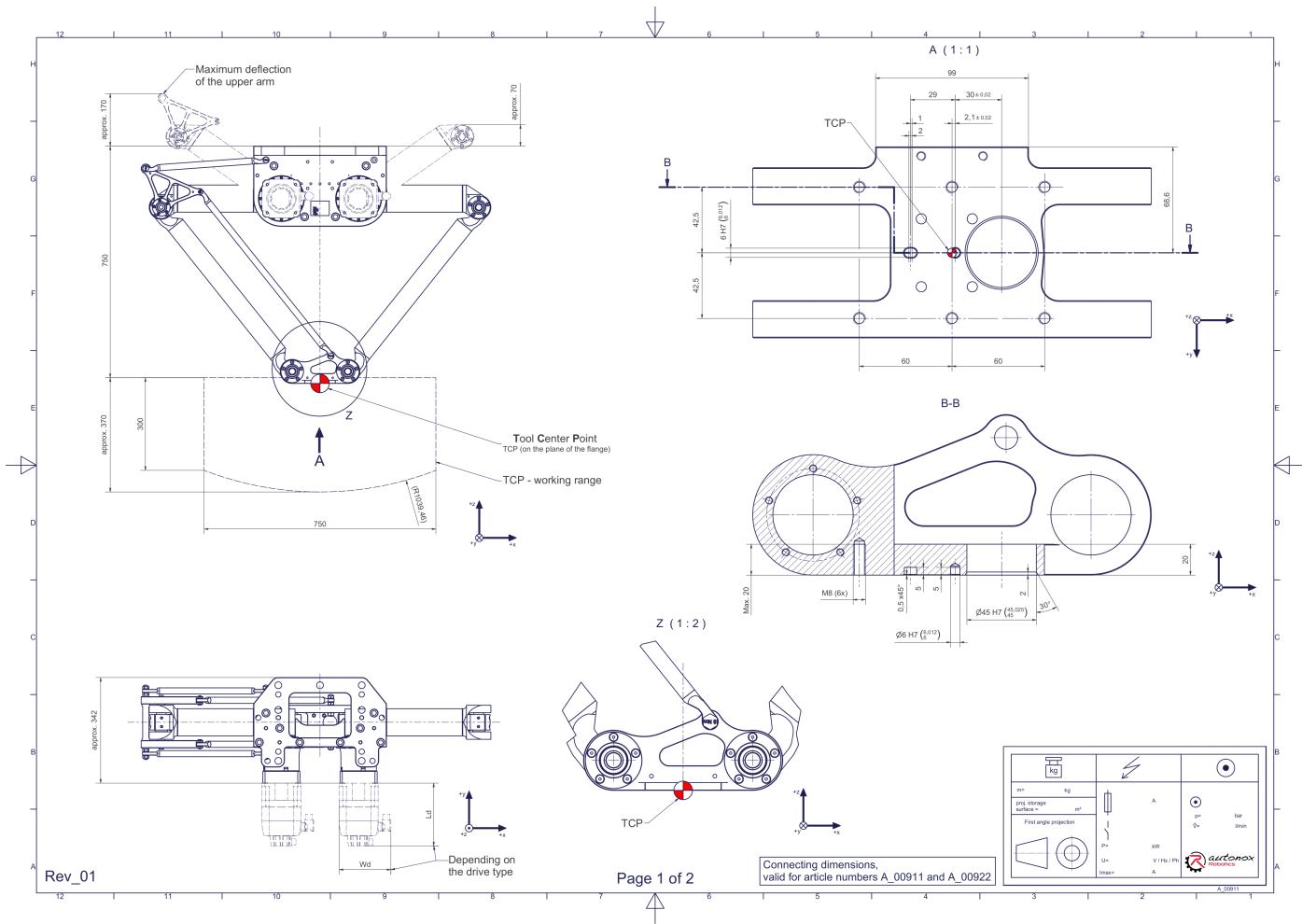
**Description:**

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 degrees 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:

Field of application	Standard (not hygienic)
Kinematics	Parallel
Translatory Degrees of Freedom (X,Y,Z)	2
Rotational Degrees of Freedom ( $\alpha, \beta, \gamma$ )	0
Nominal payload [kg   lbs] *	3   6.6
Working area-width [mm   in]	750   29.5
Working height outside [mm   in]	300   11.8
Working height center [mm   in]	370   14.6
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]	49   108.0

\* 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_BGR00020777-U-xx	Operating manual gearbox type 3 (PDF)