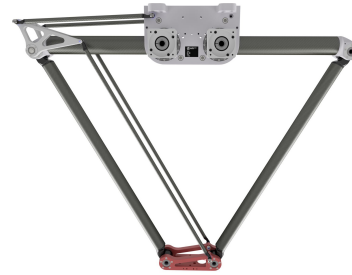


# DuoPod RVS2-1400-12kg

Article number: A\_00919

Lubricant variant: Synthetic lubricants



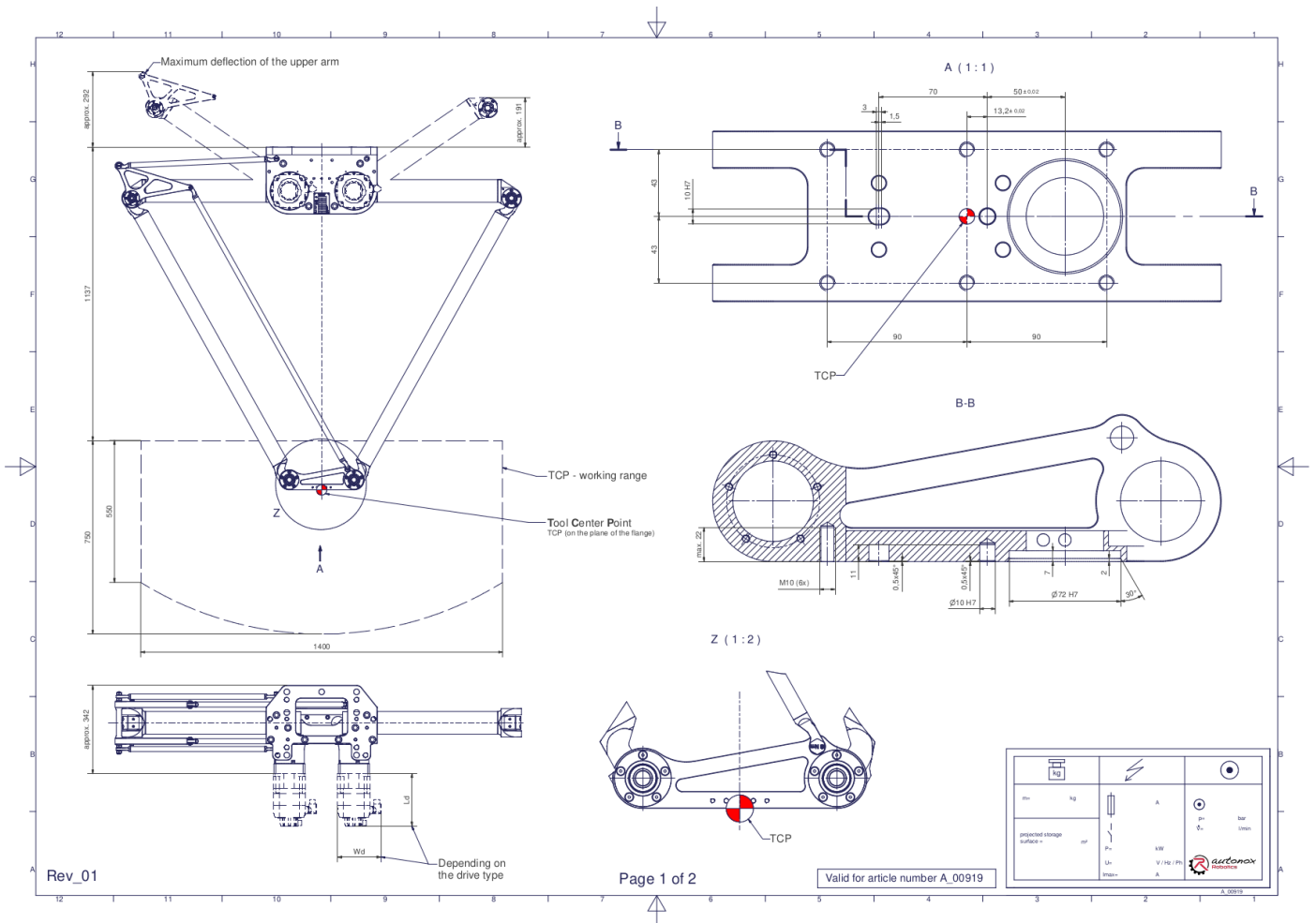
**Description:**

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](#), [Terms of use](#) and [Disclaimer and Copyright notices](#).

## 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] *                                | 12   26.5   |
| Working area-width [mm in]                                | 1400   55.1   |
| Working height outside [mm in]                            | 550   21.7  |
| Working height center [mm in]                             | 750   29.5  |
| 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) |

\* 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_BGR00017292-U-xx | Operating manual gearbox type 3 (PDF) |