



## Technical specifications:

Field of application	Standard (not hygienic)
Kinematics	Parallel
Translatory Degrees of Freedom (X,Y,Z)	3
Rotational Degrees of Freedom ( $\alpha, \beta, \gamma$ )	1
Nominal payload [kg   lbs] *	3   6.6
Working area-diameter [mm   in]	1200   47.2
Working height outside [mm   in]	500   19.7
Working height center [mm   in]	665   26.2
Length of the tool holder extension [mm   in]	ca. 160   ca. 6.3
Max. acceleration torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]	27   239.0
Nominal torque of the rotation $\gamma$ around Z at the output [Nm   in.lbs]	27   239.0
Max. speed of the rotation $\gamma$ around Z at the output [1/min]	1000
Nominal speed of the rotation $\gamma$ around Z at the output [1/min]	1000
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]	59   130.1

\* 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_BGR00021338	Operating manual gearbox type 8 (PDF)