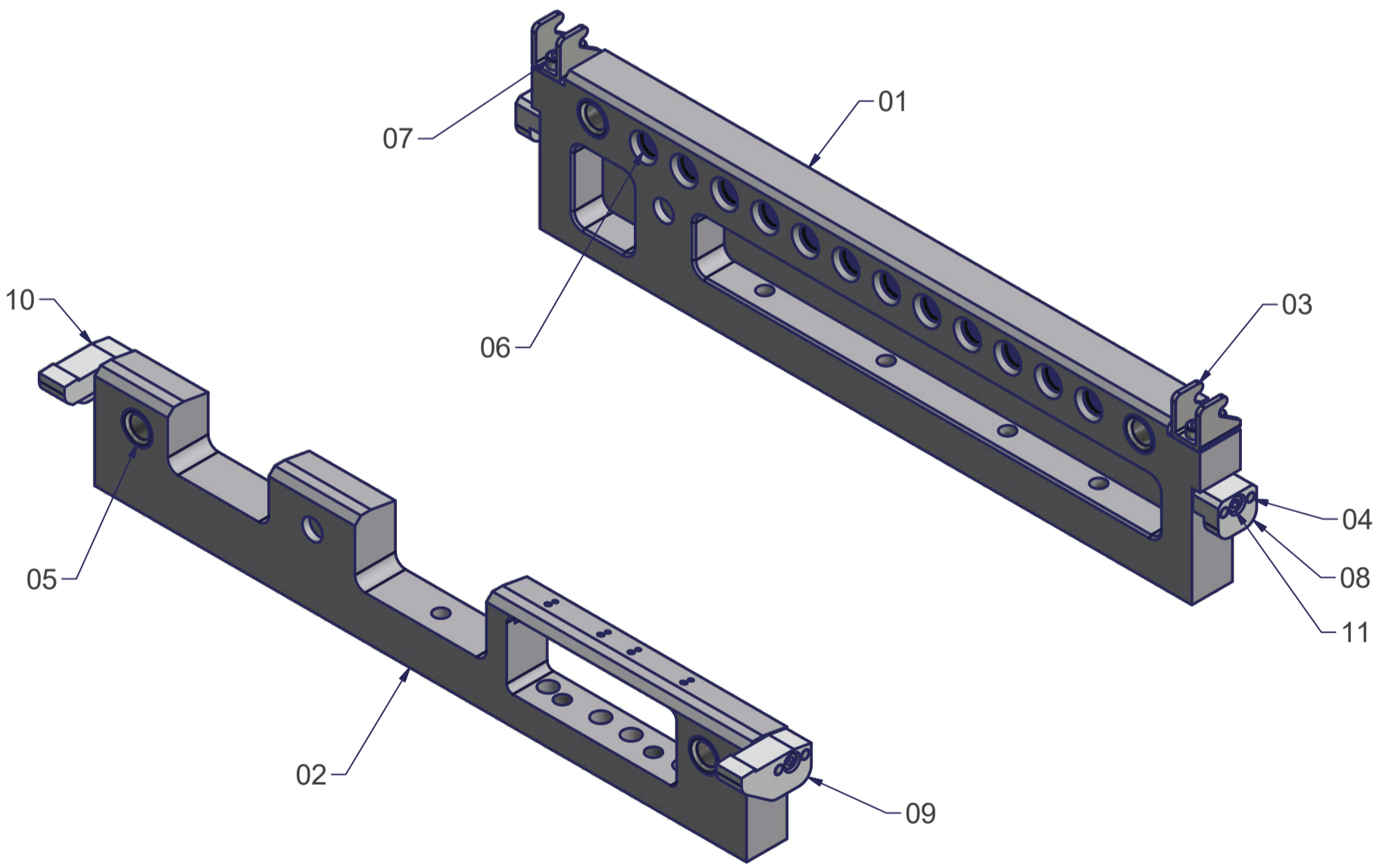


TCP of the robot mechanics referring to the document "Connecting\_dimensions".



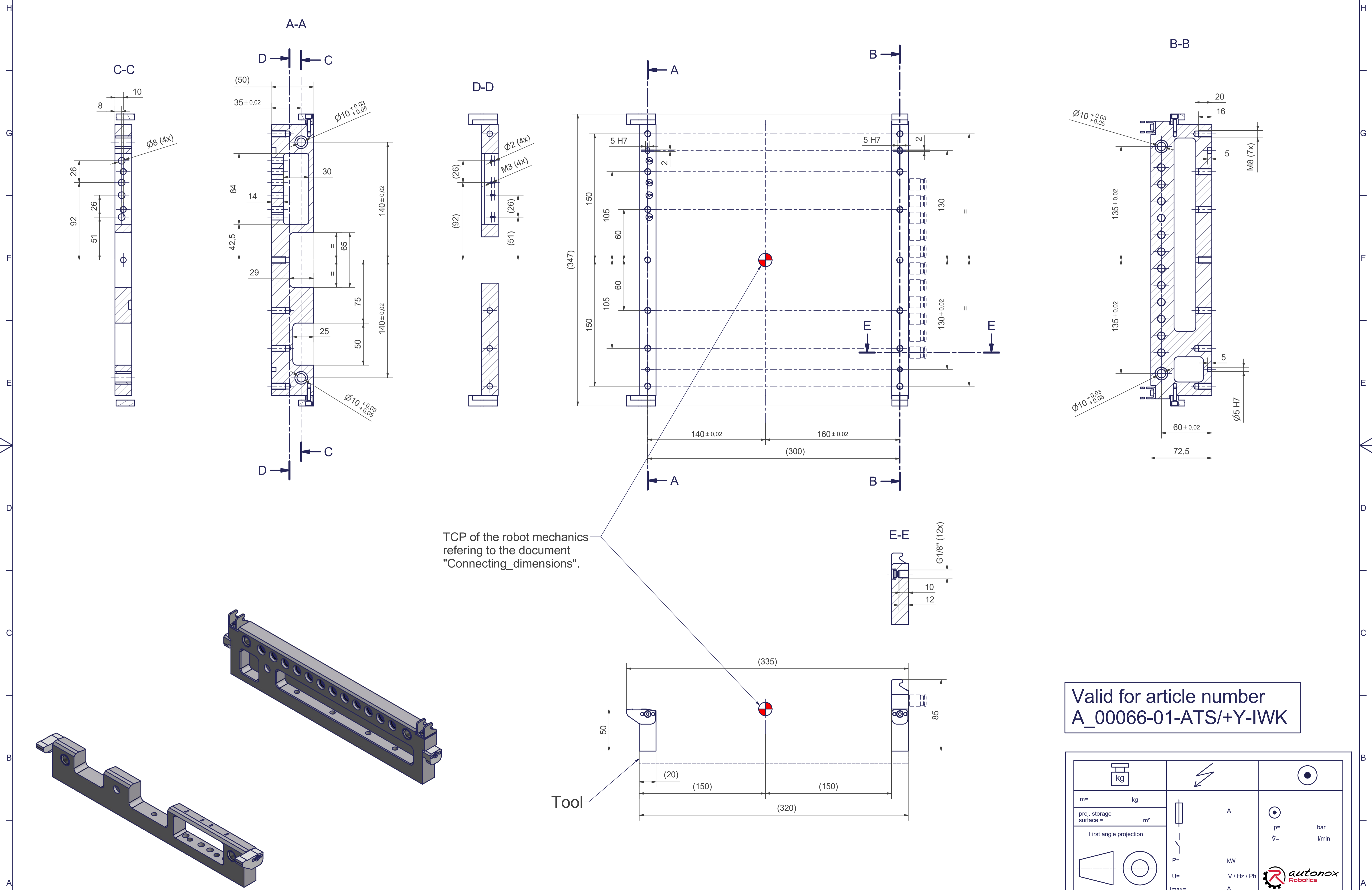
Stückliste				
Pos	Menge	Bezeichnung	autonox Art.-Nr.	Lieferanten Art.-Nr.
01	1	Adapter	MT_WST00111837	-
02	1	Adapter	MT_WST00111838	-
03	2	Halterung	MT_WST00069626	E 851-2.1-160 (Otto Ganter GmbH & Co. KG)
04	8	Bolzen	MT_NRM00001567	DIN 7 A2 4m6x20
05	4	Ring	MT_WST00102191	-
06	12	O-Ring	MT_WST00058414	DIN 3771 8x2,2 NBR70
07	4	Schraube	MT_NRM00001619	DIN 912 A2 4x10
08	2	Adapter	MT_WST00113750	-
09	1	Adapter	MT_WST00113726	-
10	1	Adapter	MT_WST00113757	-
11	4	Schraube	MT_NRM00001605	DIN 912 A2 4x16

Valid for article number  
A\_00067.01-T1-ATS-IWK

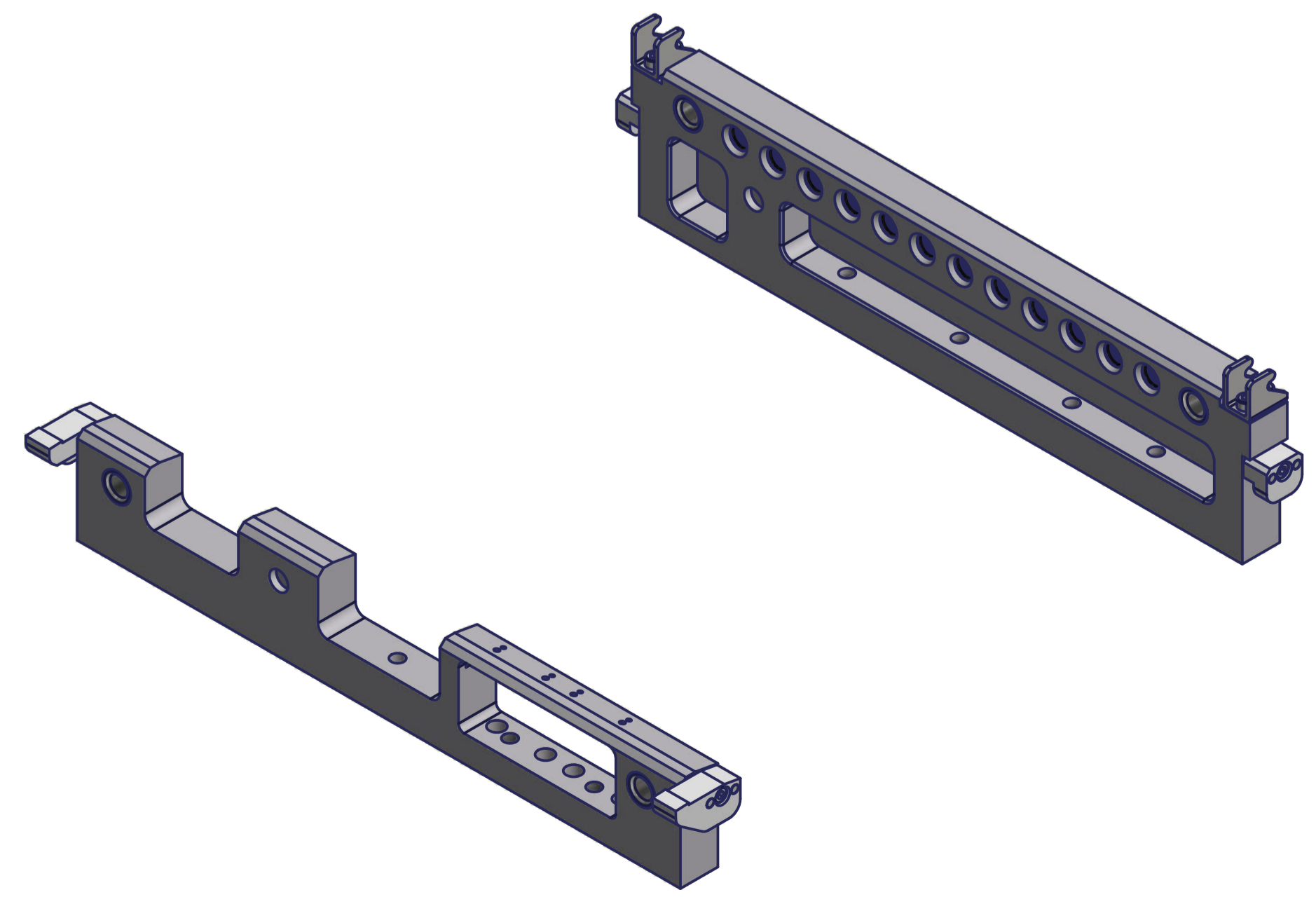
m= kg	A	p= bar
proj. storage surface = m²		v̇= l/min
First angle projection		

autonox Robotics

Connecting dimensions, valid for article number MT\_BGR00105351



TCP of the robot mechanics referring to the document "Connecting\_dimensions".



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m= kg	A	$\phi$ = bar
proj. storage surface = m <sup>2</sup>		$\dot{V}$ = l/min
First angle projection	P= kW	
	U= V / Hz / Ph	
	Imax= A	