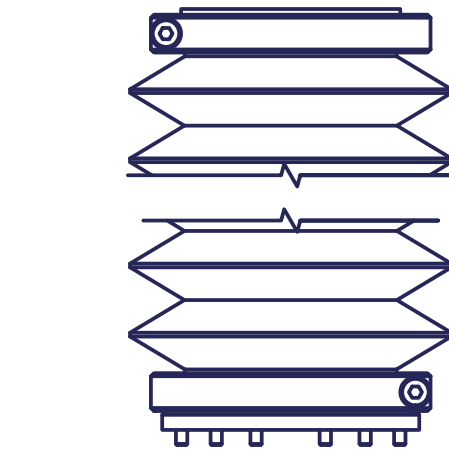


A minimum distance of 100mm between the cable harness and any (machine)parts is recommended to avoid any collision

Optional Bellows (1 : 2)



TCP - working range when using optional Bellows (MT_BGR00105809)

Kinematic origin

A1-axis A2-axis

A3- & A4-axis

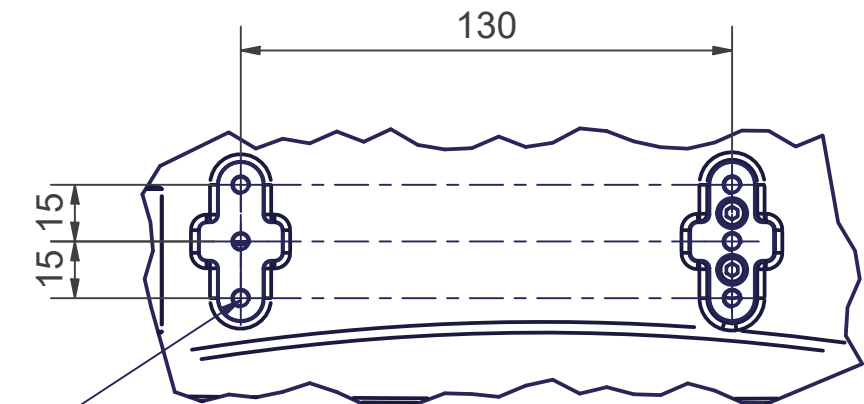
TCP

TCP - working range

Push button, for example to be able to release the motor brakes (details for connection see table "PIN assignment")

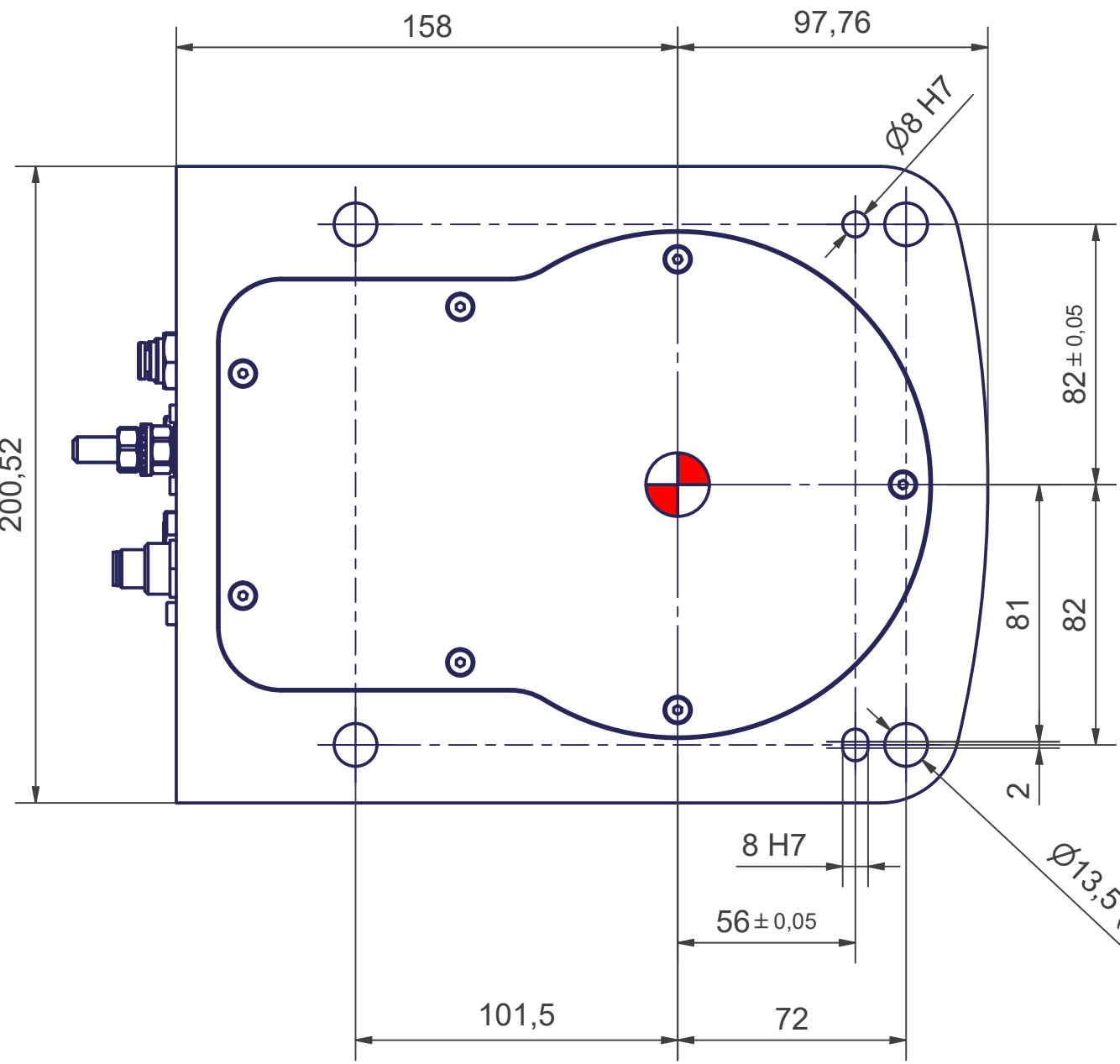
Maximum interference

Y (1 : 2)



M5 ∇ 6 (12x) for the supplementary load on arm

C (1 : 2)
Base frame



PIN assignment by autonox Robotics

PIN number	Connection to	M12 8-pin male
1	Push button	
2	Push button	
3 to 8	Not connected	

for screws M12 (DIN ISO 4014/4017-8.8) the tightening torque for these screws is 83 Nm (in steel frame).

Incl. fourfold integrated media supply to the end effector (compressed air 8 bar / vacuum -1 bar / D = 6mm d= 4mm)

sCara4-700-6kg		Motion	
Axes	4	Axes	Range fully usable
Payload (on TCP)	6 kg	A1	$\pm 135^\circ$
Reach	700 mm	A2	$\pm 145^\circ$
Mounting position	Floor, ceiling, wall	A3	- 127 mm / + 273 mm
		A4	$\pm 360^\circ$

More information can be found in the document "calibration dimensions"

Connecting dimensions, valid for article number: AT_00020-400

m= kg	A	p= bar
proj. storage surface = m ²	P= kW	$\dot{V}$ = l/min
U= V / Hz / Ph	Imax= A	

OPTIONAL:

Bellows MT_BGR00105809

