CLAIMS

1. A robot arm having a number N of arm components A_n, which is connected to a robot body via a number N of actuator-drivable joint connections GV_n where n = 1, 2, …, N; wherein

   - a distal arm component A_N of the robot arm is connected at its proximal end to an arm component A_{N-1} via a joint connection GV_N,
   - a proximal arm component A_1 is connected at its proximal end to the robot body via a joint connection GV_1,
   - the joint connection GV_N permits a rotation of the distal arm component A_N about a rotational axis D_N,
   - the distal arm component A_N of the robot arm extends along an axis L1 and the axis L1 encloses an angle of 50° to 130° with the rotational axis D_N,
   - a distal end of the distal arm component A_N is connected to an actuator E via an actuator-drivable joint connection GV_{N+1}, wherein the joint connection GV_{N+1} permits a rotation of the actuator E about a rotational axis D_{N+1}, wherein
     - o the rotational axes D_N and D_{N+1} enclose an angle W1 in the range from 50° to 130°,
     - o the rotational axis D_{N+1} and the axis L1 enclose an angle W2 in the range from 50° to 130°,
     - o the distal arm component A_N has a grip-like projection F1 rigidly connected thereto, which projection extends concentrically with respect to the rotational axis D_{N+1},
     - o a free end FE of the projection F1 is rotated with respect to the rest of the projection F1 about the rotational axis D_{N+1} or is arranged rotatably about the rotational axis D_{N+1}, and
     - o the free end FE has input elements EE for the manual input of data.

2. The robot arm according to claim 1,
   in which the input elements EE are arranged on a surface which is inclined at an angle of 5° to 60° with respect to a surface perpendicular to the rotational axis D_{N+1}.

3. The robot arm according to one of claims 1 to 2,
in which the free end FE is detachably securely connected (for example, by means of latching or clip connections) to the rest of the projection F1 in different alignments about the rotational axis D_{N+1}.

4. The robot arm according to one of claims 1 to 3,
in which the free end FE is securely connected rotatably about the rotational axis D_{N+1} to the rest of the projection F1.

5. The robot arm according to one of claims 1 to 4,
in which a mechanical and/or electrical and/or a magnetic latching device, which allows a rotation of the free end FE about the rotational axis D_{N+1} with a specified resolution, is provided between the free end FE and the rest of the projection F1.

6. The robot arm according to one of claims 1 to 5,
in which a projection F2 is formed on the actuator E or on an intermediate part ZW arranged between the joint connection GV_{N+1} and the actuator E, which projection extends perpendicular to the rotational axis D_{N+1} and is graspable by a hand.

7. The robot arm according to claim 6,
in which one or more input elements EE_{ZW} are arranged on the intermediate part ZW within reach of a thumb of the hand.

8. A robot having a robot arm according to one of claims 1 to 7.

9. The robot according to claim 8,

having

- sensors for detecting a mechanical state Z(t) of the robot arm,
- a unit for detecting inputs EG(t) via the input elements,
- a unit for evaluating the states Z(t) and the inputs EG(t) to determine evaluation results AW(t), and

- a storage unit for storing the evaluation results AW(t).

10. The robot according to claim 9,
in which the evaluation results AW(t) are control instructions for controlling the robot arm or control instructions for changing a control program of the robot and/or of its parameters.