

ROBOT ARM

ABSTRACT

The invention relates to a robot arm with a number N of arm component A_n , which can be connected to a robot body via a number N of actuator-drivable joint connections GV_n , where $n = 1, 2, \dots, N$, wherein the distal arm component A_N of the robot arm is connected by its proximal end to the arm component A_{N-1} via the joint connection GV_N ; the proximal arm component can be connected by its proximal end to the robot body via the joint connection GV_1 ; the joint connection GV_N permits a rotation of the arm component A_N about a rotational axis D_N ; the 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 ; the distal end of the arm component A_N can be 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 the rotational axes D_N and D_{N+1} enclose an angle $W1$ in the range from 50° to 130° ; the rotational axis D_{N+1} and the axis $L1$ enclose an angle $W2$ in the range from 50° to 130° ; and a protrusion $F2$ 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 protrusion extends perpendicular to the rotational axis D_{N+1} , can be gripped by a hand and is also rigidly connected. The robot arm according to the invention permits a more sensitive and precise operation in the offline programming of a robot having a robot arm of this type.