or operable by the thumb, even with different alignments of the hand.

Advantageously, an input element EE_0 of the input elements EE is arranged axially with respect to the rotational axis D_{N+1}. Advantageously, this central input element EE_0 serves to input or control current primary parameters, for example to input a start time and a finish time for teach-programming.

Advantageously, the parameters input or controlled by means of the input elements EE can in each case be variably assigned or selected automatically or manually depending on the particular task.

Advantageously, the projection F1 is designed such that it can be gripped by a hand of an operator, wherein a thumb of the hand comes to rest on the free end FE for operating the input elements EE. Advantageously, the projection F1 has a cylindrical shape or an ergonomic grip shape for this purpose.

Advantageously, the free end FE is ergonomically formed for operating the input elements EE with the thumb of the hand. For this purpose, in an embodiment, 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}. This inclination enables the input elements EE to be operated ergonomically, wherein, in particular, the distal thumb joint of the operating hand does not have to be bent, for example, at 90°.

Advantageously, the input elements EE have light elements with one or more controllable light sources. Advantageously, the light source/s are light emitting diodes LEDs.

Advantageously, the input elements EE are designed as buttons and/or rocker switches and/or pushbuttons and/or switches and/or rotary knobs and/or slide controllers. In a further advantageous embodiment, the input elements EE are designed as input fields of a touchpad (touch-sensitive surface) or a touchscreen (touch-sensitive display).

In a development of the proposed robot arm, the free end FE of the projection F1 can be detachably securely connected (for example, by means of latching or clip

CLAIMS

1. A robot arm having a number N of arm components 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, …, N; wherein

   - a distal arm component A_N of the robot arm is connected at its proximal end to the arm component A_{N-1} via the joint connection GV_N,

   - a proximal arm component A_1 can be connected at 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

     - 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 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 can be rotated with respect to the rest of the projection F1 about the rotational axis D_{N+1} or can be 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}.