Operating instructions

GEWO DELTA NEXXT

Table tennis robot

GEWO®
THE BETTER WAY TO PLAY

Features

- State-of-the-art 3-wheel ball guide technology for any form of spin
- Hard foam wheels with special coating for long durability
- Memory for 99 exercises, 40 pre-programmed exercises
- Programmable or random ejection of balls with different spin, speed, direction and trajectory
- Spin settings from empty balls to extreme rotation (90 different spin combinations)
- Natural timing of the balls within an exercise thanks to IFC (Individual Frequency Control)
- Includes handy remote control to start and stop exercises
- Integrated catch net for easy ball return
- Ejector head can be adjusted to 4 different heights to realistically simulate even more game situations
- Easy transport thanks to low weight of 6 kg
- 30 months warranty (see section „Warranty“)

Important notes!

- Please read this user manual carefully.
- The robot may only be connected to 100 V - 230 V power supplies.
- The wheels rotate at high speed. Do not touch them during operation!
- Only use the GEWO Omega Nexxt in dry rooms.

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1. Delivery scope & assembly

Delivery scope

Robot incl. power supply, power cable and power supply unit (Input: 100~240 V, Output: 24 V), remote control, GEWO Delta Nexxt Controlboard

Other parts included: Allen key (2 and 4 mm) for ejection discs, fitting piece for ejection wheels, replacement rubber rings for ball catcher net, Velcro strip, white replacement steel strip for the deflector plate, table bracket for the control board

Assembly

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1. Place the robot on the table tennis table and fold down both sides of the net until they snap into place at about 45° *(picture 1)*. Then turn the retaining hooks out to about 20 cm apart *(picture 2)*.

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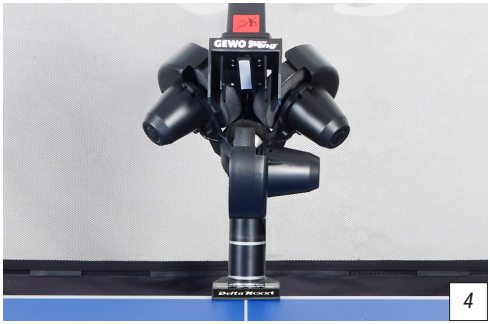

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2. Carefully loosen the locking screw behind the ball tube *(picture 3)*, while holding the head with the other hand, turn the head 180° so that the ejection points exactly towards the centre line *(picture 4)*. Pull the head upwards until the second ring can be seen slightly above the guide tube. Then tighten the locking screw again to fix the height.

! CAUTION: Do not overtighten the screw or damage to the tube may occur.

3. Now lift the robot with both hands and angle it slightly so that the retaining hooks can be guided under the table frame. Guide the robot to the edge of the table and then set it down carefully (*picture 5*). Connect the cable of the ejector head to the interface of the base (*picture 6*).

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ATTENTION: The GEWO Delta Nexxt robots are preset for tables with a 25 mm surface. To ensure a good grip and a clean ball ejection even with thinner surfaces, the retaining hooks are equipped with a height adjustment at their upper end. If necessary, turn the adjustment heads upwards enough to compensate for the difference in surface compared to the 25 mm of the standard setting.

TIP: If necessary, you can attach the longest of the Velcro straps supplied to the back of the table surface to additionally fix the robot head to the table

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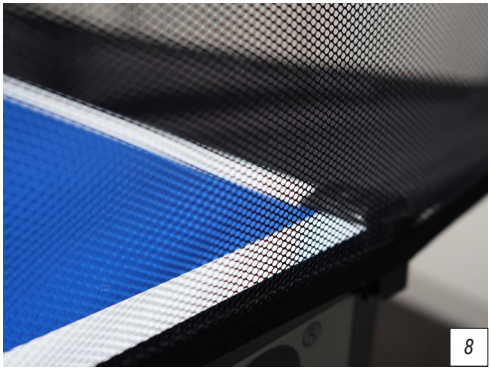
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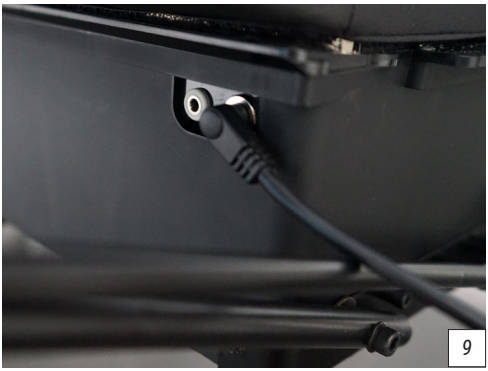
4. Now fold down the ball net completely.

5. Pull the side ball nets along the side edge of the table to your net. First pass the rubber loop under the net set (*picture 7*) and then fasten the rubber loop to the adjusting screw of the respective net post.

6. Then attach the corner caps to the edges of the table and connect the Velcro strip of the net to that of the respective holder at the corners of the table to provide additional stability (*picture 8*).

TIP: If necessary, the two short Velcro strips can be additionally attached to the corner caps to give the net even more support.

7. connect the power supply unit to your mains and connect the plug to the connector on the side of your robot (*picture 9,* next page).



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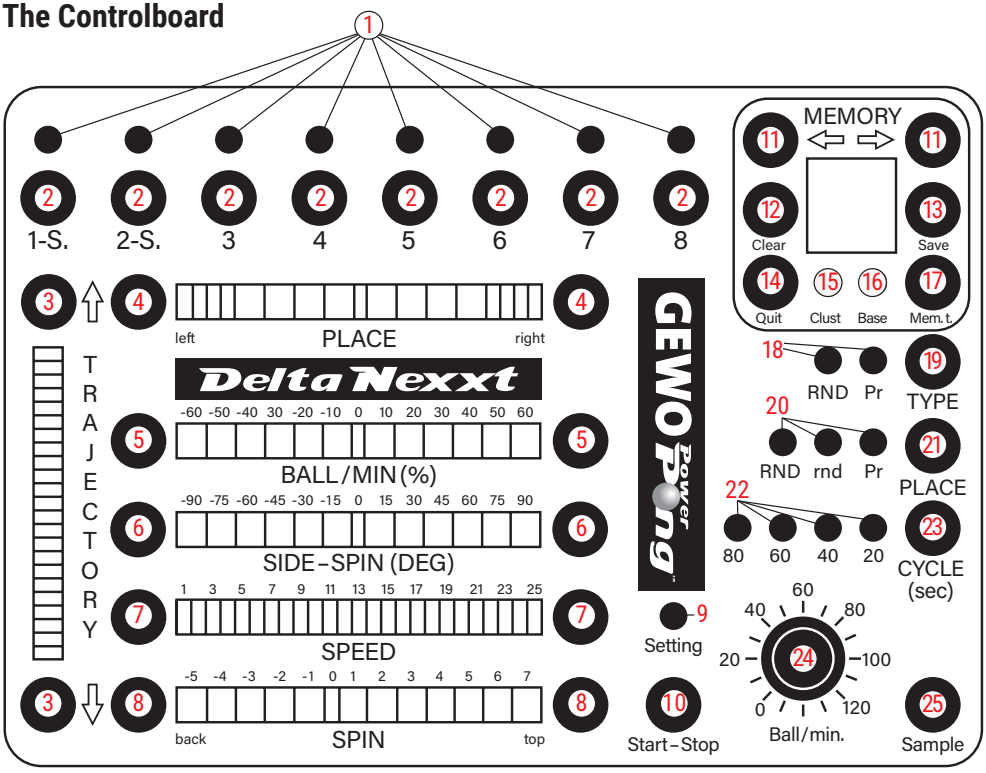
8. Connect the control box to your robot using the connection cable. Now you can clamp the table bracket to your table at a suitable place and hang the control box there.

9. ill at least 50 clean table tennis balls into the ball collection area (*picture 10*) before you start playing.

2. Operating

The Controlboard



① **Ball LEDs:** A flashing LED indicates which ball is currently selected. Permanently lit LEDs indicate that a corresponding ball is programmed at the court for the selected exercise.

② **Ball buttons:** The desired ball can be selected with the ball buttons, new balls can be added by pressing a ball button for which the corresponding ball LED is not lit. A programmed ball can be deleted by pressing and holding it down. All balls of an exercise can be deleted by pressing and holding down the 1st and 8th ball buttons.

③ **Flight height buttons:** Adjust the height of the ball ejection for a ball.

④ **Place buttons:** Adjust the placement of the ball ejection to the left or right for a ball.

⑤ **Ball/Min (%) buttons:** Control the Individual Frequency Control (IFC). These buttons can be used to ensure that individual balls are ejected slightly earlier or later within an exercise.

⑥ **Side spin (DEG) buttons:** Adjust the side spin for a ball.

⑦ **Speed buttons:** Adjust the speed for a ball.

⑧ **Spin buttons:** Add topspin or undercut to the ball.

⑨ **Setting LED:** Indicates whether the robot is in setting mode or game mode.

⑩ **Start-Stop button:** Starts the robot's ball ejection. Pressing it again stops the ejection.

⑪ **Memory selection buttons:** The selection buttons can be used to select exercises in the basic memory and in the cluster memory.

⑫ **Clear button:** Deletes the active exercise from the base memory or the current cluster from the cluster memory.

⑬ **Save button:** Saves changes in an exercise or in a cluster.

⑭ **Quit button:** Exits the currently selected storage system.

⑮ **Clust. LED:** Indicates whether the cluster memory is currently active.

⑯ **Base LED:** Indicates whether the base memory is currently active.

⑰ **Mem. T. key:** Opens the basic or cluster memory and ensures that exercises can be transferred from the basic memory to a cluster.

⑱ **TYPE LEDs:** Indicate which TYPE setting is active.

⑲ **TYPE button:** Activates the TYPE „RND" mode, in which balls of an exercise are ejected with random placement.

⑳ **PLACE LEDs:** Show which PLACE setting is active.

㉑ **PLACE button:** Activates PLACE „rnd", as well as PLACE „RND" mode, so that balls of an exercise are scattered and/or ejected in a random order.

㉒ **CYCLE LEDs:** Indicate which setting has been selected for cycle mode.

㉓ **CYCLE button:** Activates interval training.

㉔ **Ball/min. controller:** Adjusts the ball ejection speed of the robot.

㉕ **Sample button:** Ejects a sample ball with the currently selected settings.

Adjusting the head height

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To simulate the real game as well as possible, the robots of the GEWO Power Pong Nexxt series offer the possibility to adjust the head height. To do this, hold the ball tube firmly with one hand and loosen the large black locking screw with the other hand (*picture 11*). Then the tube can be adjusted to a different height by gently pushing or pulling it. To select another height, make sure that one of the silver rings at the transition of the lower tube is slightly visible before you tighten the screw again.

CAUTION: Do not overtighten the screw, otherwise the tube may be damaged. Tighten the screw only at the 4 marked positions. Incorrect head height can lead to ball blockages, incorrect ejections or other problems.

Starting and centring the robot

As soon as the control board is connected to the power, the **„Ball 1“ LED** (1) should start flashing. If you now turn the **„Ball/min“ control** (24) higher, the GEWO Nexxt robot will directly start pulling balls to the ejection head. The ball ejection speed can be set between 0 and 120 balls per minute and can be adjusted even during play. You can interrupt and restart this at any time using the **„Start-Stop“ button** (10).

The first balls played should be ejected along the centre line. If the balls do not land on or near the centre line of the table, stop the exercise, loosen the black locking screw on the tube of the robot head and carefully turn the head in the required direction. Now tighten the locking screw again and repeat the steps until the balls land as close to the centre line as possible.

ATTENTION: If the robot has not been properly centred before playing, it is possible that balls will not land on the table during some exercises!

Ball settings – placement, trajectory, speed, spin and IFC

If you want to adjust a ball, first select the ball by pressing the respective button (2). When you have selected a ball, the corresponding LED (1) starts to light up and the respective selected ball settings become visible.

Now you can make 6 different settings for your ball:

The placement of the ball can be adjusted using the two buttons left and right (4) on the **„Place“ display**.

The **„Trajectory“** can be changed via the controller (3) on the left side. To increase or decrease the trajectory, keep the respective button (3) pressed. The further down the **„Trajectory“** is displayed, the flatter the flight curve. Particularly low settings are suitable for serves.

The speed of the ball can be adjusted with the **„Speed“ control** (7). The following values are available values from 1 (very slow) to 25 (very fast) are available. The combination of **Trajectory** and **Speed** is decisive for the length of the ejected ball.

With **„Spin“** (8) the undercut or overcut of the ball can be set. The setting 0 corresponds to no spin, -5 to strong undercut and 7 to strong topspin.

„Sidespin“ (6) adds sidespin to the ejected balls. Here, the setting 0 again corresponds to no spin. The negative values from -90 (very strong) to -15 (light) correspond to left sidespin, while the positive values from 15 (light) to 90 (very strong) correspond to right sidespin.

The **„Ball/Min(%)“ control** (5) can be used to control the **IFC** (Individual Frequency Control). If this setting is set to 0, the selected ball is ejected exactly at the set pace of the exercise. Positive values ensure that the ball is ejected slightly earlier. A negative value can add a delay to the selected ball.

When a ball has been set with the help of the various controls, the settings made can be tested with the **„Sample“ button** (25) at the very bottom right. If you tap on the button“, the robot ejects exactly the selected ball once so that you can check whether the set ball actually corresponds to your ideas.

To create a new ball in the exercise with exactly the settings you have selected, you only have to press the next **„Ball“ button** (2) at the top. It is therefore advisable to already make all the desired settings for the first ball. It is often possible to adjust the placement of the other balls in order to placement in order to create a suitable exercise.

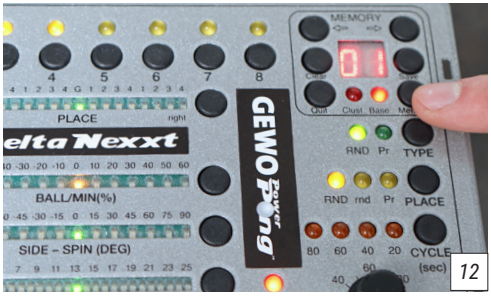
The first two balls can be set not only as an ordinary ball but also as a serve. To do this, press the respective **„Ball“ button** (2) twice quickly. If the corresponding **„Ball“ LED** (1) lights up green, the ball is set as a serve; if it lights up yellow, it is a normal ball. Setting a ball as a serve has the advantage that the serve is given a short break. You have the following options for setting serves:

– Ball 1 as serve: Each execution starts with the serve.
– Ball 2 as serve: Only the first execution starts with the serve.
– Ball 1 and ball 2 as serve: The robot randomly selects a serve.

i TIP: For very slow serves, the „Ball/Min(%)“ control should be used so that the second ball is not played while the serve is still being returned.

If a ball is to be deleted from an exercise, press and hold the corresponding **„Ball“ button** (2) until the LED is no longer lit. This function should only be used when a ball is no longer needed. A deleted ball cannot be restored afterwards.

Memory mode



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Saving exercises

To open the base memory of your control board, press the **„Mem.T" button** (17). Now the memory location „01" should be displayed first and the **„Base" LED** (16) should light up (*picture 12*). Memory locations that are not yet occupied flash. If an exercise is already stored, the number does not flash. To save the currently selected exercise to a memory location, select a flashing memory location using the **„Selection" buttons** (11) and press the ***„Save" button*** (13). To delete an already stored exercise, select the exercise and hold the **„Clear" button** (12).

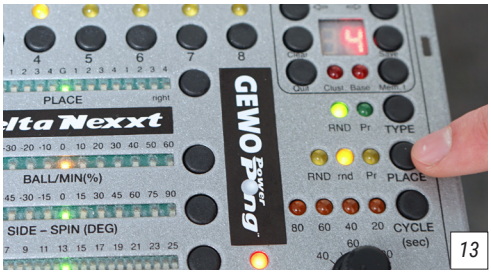
Editing and playing back saved exercises

To access a stored exercise, first open your base memory with the **„Mem. T" button** (17) to open your base memory. Now you can select your desired exercise with the **„Selection" buttons** (11) and then start it with the **„Start-Stop" button** (10). You can now also make adjustments to the selected exercise.

! ATTENTION: Changes made to saved exercises must be saved again to the same otherwise they will be lost.

i TIP: The memory locations 60 to 99 contain the 40 preset exercises.

Random functions – TYPE & PLACE



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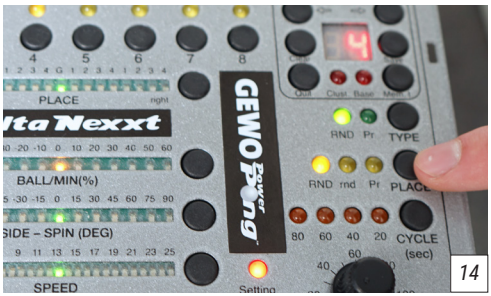

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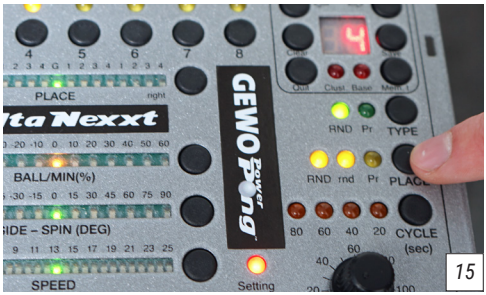
The GEWO Delta Nexxt provides you with various random functions to choose from.

1. **PLACE „rnd":** Tap the **„PLACE" button** (21) until only the **„rnd" LED** is illuminated (*picture 13*) to activate the scatter mode. With this function, the balls of the selected exercise can vary within a radius of 20 cm around the actually set ball. This function offers the decisive advantage that a realistic game can be simulated better. In the actual game situation, balls do not always come back precisely. The scattercan also be selected for exercises that consist of only one ball.

2. **LACE „RND":** Pressing the **„PLACE" button** (21) until only the **„RND" LED** is lit (*picture 14*), the random mode is activated, where the set balls of the selected exercise are ejected in random order. In this way, irregular exercises can be created with which one can improve the reactions. For this function, it is necessary that the selected exercise consists of more than one ball.

3. **PLACE „RND“ & „rnd“:** When both LEDs (20) light up (*picture 15*), the selected exercise is played in random order and the balls are scattered in a 20 cm diameter. This function is also only possible for exercises with at least two balls.

4. **TYPE „RND“:** If TYPE random mode is activated (*picture 16*), the spin, speed and trajectory settings of the exercise are maintained. However, the placement is randomly generated for each ball played.



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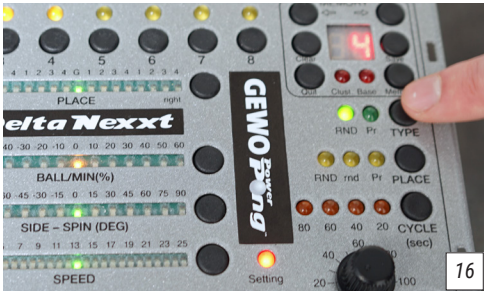

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ATTENTION: Please note that random settings cannot be saved. If you want to start your saved exercises in any random mode, you have to select the desired random option again each time.

CYCLE FUNCTION

With the **„Cycle“ function**, the GEWO Delta Nexxt can be used for interval training. To use the Cycle function, press and hold the **„Cycle“ button** (23) during the exercise you want to play as an interval until the first **„Cycle“ LED** (22) next to the button lights up (*picture 17*). You can choose between a playing time of 20, 40, 60 and 80 seconds. After that, the robot pauses for 10 seconds before resuming play.

To start the ball ejection in interval training, simply tap the **„Start-Stop“ button** (10) after the setting has been made.

NOTE: Please note that Cycle settings cannot be saved. If you want to start your saved exercises in interval training, you have to select the cycle function again each time.

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Groupings

Create groupings

To play several exercises one after the other, you can use the cluster function.

1. First open your basic exercise memory by pressing the **„Mem. T“ button** (17).

2. Now use the two **„Selection“ buttons** (11) to choose the first exercise you want to add to your grouping and press the **„Mem. T“ button** (17) to open your cluster memory. Now the **„Clust.“-LED** (15) should start to light up (*picture 18*).

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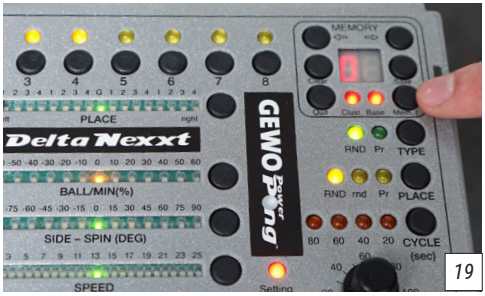
3. Now use the two **„Selection“ buttons** (11) to choose a cluster memory location (C0-C9) to which you want to add your selected exercise. To add your exercise to the cluster, press the **„Mem. T“ button** (17). Now both **„Clust.“** and **„Base“ LED** should light up (*picture 19*).



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4. With the **„Selection“ buttons** (11) you can now choose which place within the grouping the newly added exercise should take. If you are just adding your first exercise, this point is omitted. Save your cluster with the **„Save“ button** (13).

5. To add more exercises, repeat these 4 steps

If you want to play saved groupings, open your cluster memory by tapping the **„Mem. T“ button** (17) twice. Now the display should show C0 first. You can select the desired grouping with the **„Selection“ buttons** (11) and then start it with the **„Start-Stop“ button** (10).

***i* TIP: If a grouping is played while the TYPE RND function is active, the exercises of the cluster are played in random order.**

Edit exercises within a grouping

If, while playing a grouping, you realise that you want to edit a certain exercise, first interrupt the playing with the **„Start-Stop“ button** (10). By pressing the **„Mem. T“ button** (17), you now move from the **„Cluster“ to the „Base memory“**. And the selected exercise should now be called up in the basic memory. Make the desired changes in the base memory and save them before you start your grouping again from the beginning.

If you want to delete an exercise from a grouping, first open the **„Cluster“ memory** by pressing the **„Mem. T“ button** (17) twice. Now use the **„Select“ buttons** (11) to select the cluster memory location from which you want to delete an exercise and edit the cluster with the „Mem. T“ button. When you are in cluster editing, the LEDs **„Clust.“** (15) and **„Base“** (16) should light up. Now select the exercise you want to delete and hold the **„Clear“ button** (12). To leave the cluster memory again, hold the **„Quit“ button** (14).

NOTE: Exercises deleted from a cluster remain in the base memory.

Delete groupings

To delete a complete grouping you have created, first call up the **„Cluster“ memory** by pressing the **„Mem. T“ button** (17) twice. Now select the grouping you want to delete on the display and hold the **„Clear“ butto**n (12). Now all exercises from the selected cluster should be deleted.

Remote control – pairing, operation and battery replacement

Your GEWO Nexxt robot also comes with a handy little remote control in the shape of a car key. The remote control should be connected to your GEWO Nexxt robot when it is delivered. If you want to recalibrate your remote control, simultaneously tap the two **„Selection“ buttons** (<- and ->) for a longer period of time. The controllboard display should now show an **„L _“**.

A countdown of 10 seconds will start. Within these 10 seconds, press one of the 4 keys on your remote control. As soon as the 10 seconds have elapsed, your remote control is ready to start.

The remote control offers the following functions:

1. Pressing the **„START“ button** starts the exercise displayed on the Controlboard.
2. Pressing the **„+“ button** increases the speed of the ball by 5 balls per minute. Pressing the **„-“ button** decreases the speed accordingly. If the buttons are not pressed individually but held down, the speed adjustment is faster.
3. Pressing the **„STOP“ button** stops the exercise being played.

Battery replacement

If your remote control stops working properly, you may need to replace the remote control batteries. The remote control is powered by **two 3 V, CR2016** button cells. You open the remote control by inserting a small coin or slotted screwdriver into the slot at the end of the remote control and then twisting it with some force to open the remote control. You may need to carefully remove the silver metal bracket from the remote control first. When you have opened the remote control, remove the circuit board with the batteries and the circuit board with the batteries and carefully pull the black battery holder out of the circuit board. Now replace the two old batteries with your new batteries. Make sure that both batteries have the positive side facing up. Then reinsert the battery holder into the circuit board and reassemble the remote control.

3. Dismantling

1. Disconnect the robot from the power and roll up the power cable.

2. Loosen the rubber bands that hold the side nets to the table net and place the side nets into the ball collection container.

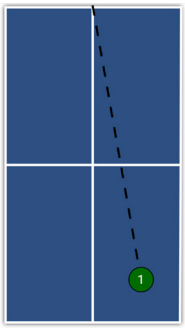
3. Fold the net up to the first stop of the folding mechanism. Now unhook the robot from the table and place it on the table.

***i* TIP: If you are only taking the GEWO Delta Nexxt off the table for a short time, you can leave the balls in the collection net and add accessories such as the cable and remote control after this step. Fold the collection net all the way up and put the robot down.**

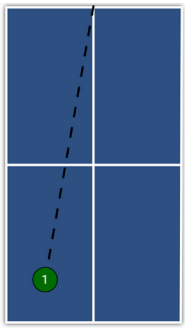
4. Hold the ball tube firmly just below the ball ejection head, loosen the black locking screw, turn the head 180 degrees, slide the head onto the first ring and tighten the locking screw again slightly. Also turn the two support legs backwards so that they point into the net.

5. Fold the net completely upwards until the Velcro fastener sticks together. Now you can store and transport the robot and accessories in a space-saving way.

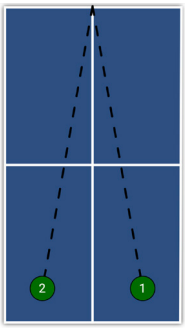
4. Exercises



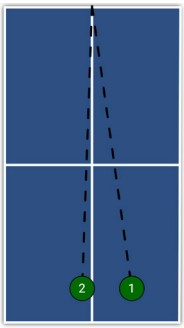
60) Topspin to FH #Topspin



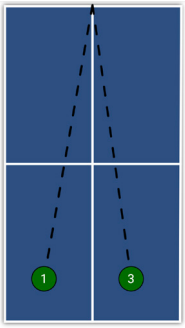
61) Topspin to BH #Topspin



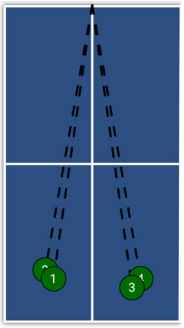
62) Topspin to FH/BH #Topspin



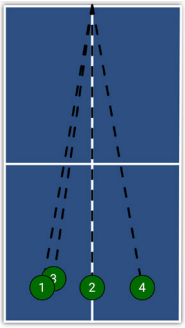
63) Topspin to FH, Topspin to MID #Topspin



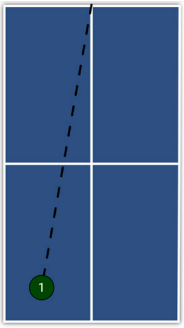
64) 2 Topspins to BH, 1 Topspin to FH #Topspin



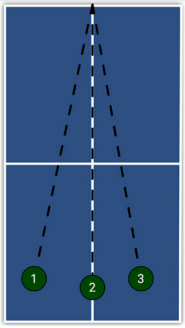
65) 2 Topspins to BH, 1 Topspin to FH # Topspin



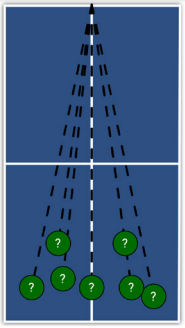
66) 2 Topspins to BH, 2 Topspins to FH #Topspin



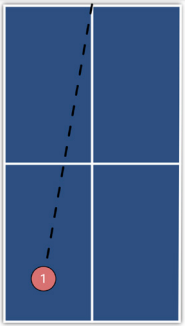
67) Heavy Topspin to BH #Topspin



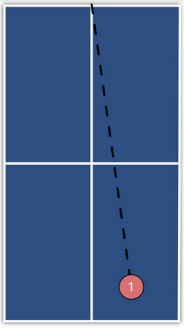
68) Heavy Topspin to BH, Mid, FH #Topspin



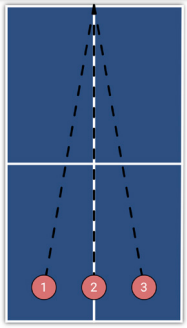
69) Topspin Random #Random #Topspin



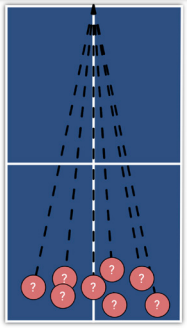
70) Backspin to BH #Backspin



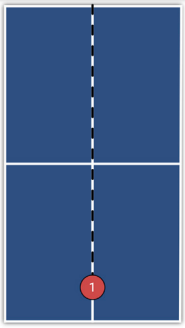
71) Backspin to FH #Backspin



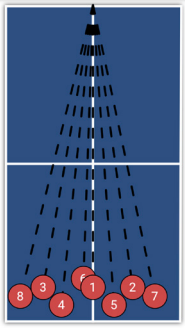
72) Backspin to BH, Mid, FH #Backspin



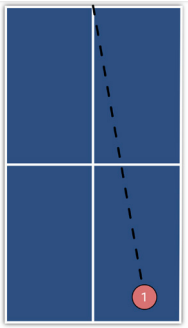
73) Backspin Random #Backspin #Random



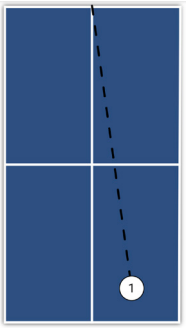
74) Heavy Backspin to Mid #Backspin



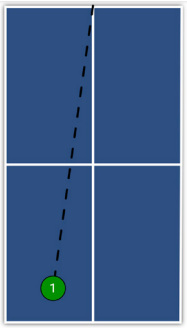
75) Heavy Backspin Random #Backspin



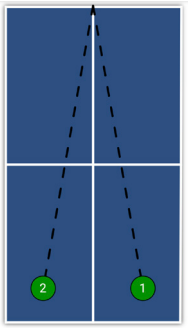
76) Backspin to FH, Heavy Backspin to FH #Backspin



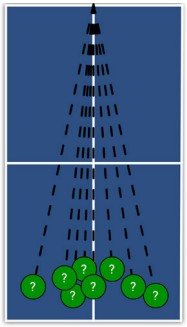
77) Nospin to FH



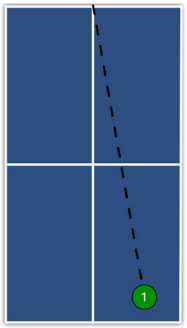
78) Smash to FH #Topspin



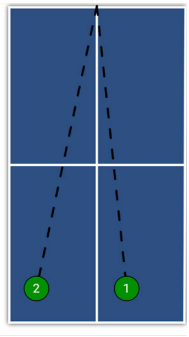
79) Smash to FH, BH #Topspin



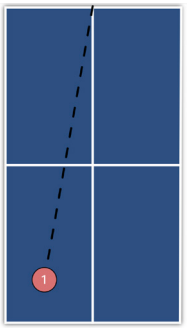
80) Smash Random #Random #Topspin



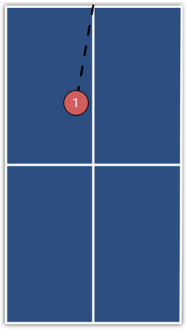
81) Topspin Lob to FH #Topspin



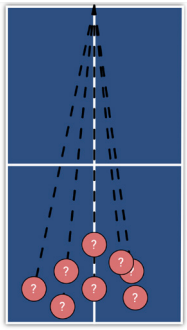
82) Topspin Lob to FH, BH #Topspin



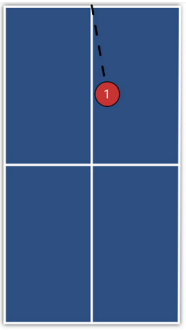
83) Backspin Lob to BH #Backspin



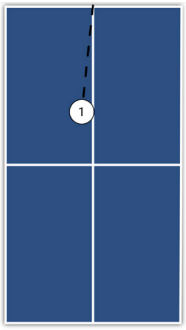
84) Backspin Serve to BH #Backspin #Serve



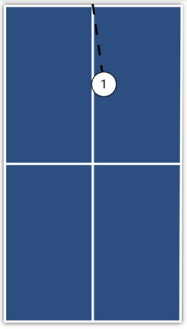
85) Backspin Lobs Random #Backspin #Random



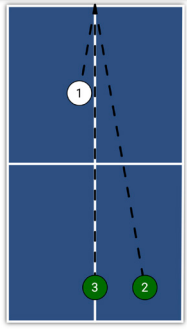
86) Right Sidespin Serve to BH #Backspin #Serve



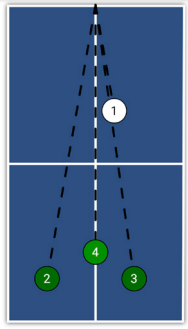
87) Left Sidespin Serve to BH #Serve #Sidespin



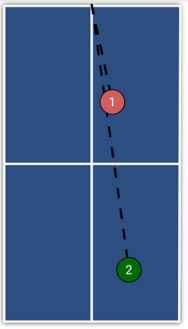
88) Deep Nospin Serve #Serve



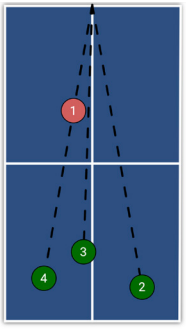
89) Nospin Serve to BH, Topspin to FH, Topspin to Mid #Serve #Topspin



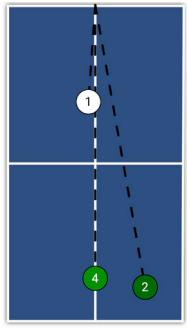
90) Nospin Serve to FH, Topspin to BH, Topspin to FH, Lob to Mid #Serve #Topspin



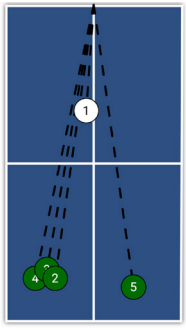
91) Backspin Serve to FH, Topspin to FH #Backspin #Serve #Topspin



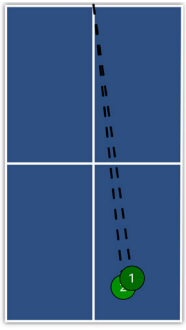
92) Backspin Serve to BH, Topspin to FH, Mid, BH #Backspin #Serve #Topspin



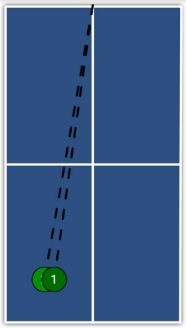
93) Right Sidespin Serve to BH, 2 Topspins to FH, 1 Lob to mid #Serve #Sidespin #Topspin



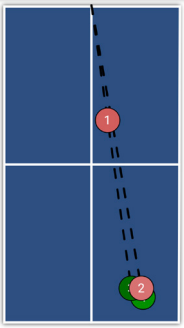
94) Left Sidespin to FH, 3 Tospins to BH, 1 Topspin to FH #Serve #Sidespin #Topspin



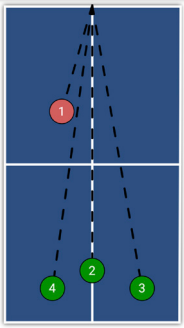
95) Topspin to FH, Smash to FH #Topspin



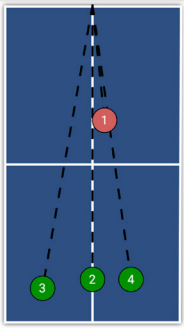
96) Topspin to BH, Smash to BH #Topspin



97) Backspin Serve to FH, Backspin to FH, Topspin to FH, Lob to FH, Smash to FH #Backspin #Serve #Topspin



98) Backspin Serve to BH, Lob to Mid, Smash to FH, Lob to BH #Backspin #Serve #Topspin



99) Backspin Serve to FH, Lob to Mid, Smash to BH, Lob to FH #Backspin #Serve #Topspin

5. Maintenance & Repair

WARNING: Before repairing or servicing your GEWO Delta Nexxt robot, please disconnect it from the power supply.

Vorsichtsmaßnahmen
Precautions

1. Make sure that no other objects fall into the net from where they could enter the machine. Foreign objects in the tube can cause a ball jam and affect the correct functioning of your robot.

2. To guarantee the best possible ejection characteristics and long durability, only use clean balls for your GEWO Delta Nexxt robot. If you add new balls that are still covered with manufacturing powder, please wash them with warm water and dry them before using them for the first time.

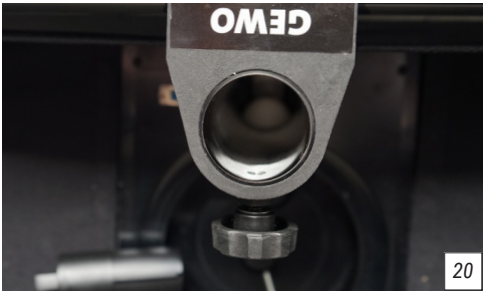
3. The shooting wheels are equipped with a special coating. Please do not use chemicals to clean the wheels.

4. To guarantee long durability, use your robot only in dry and closed rooms and avoid exposing your robot to high temperatures or humidity.

Ball jam

Falls es zu einem Ballstau kommt, versucht der Roboter das Problem zunächst automatisch zu beheben. Wenn die automatische Behebung nicht funktionieren sollte, trennen Sie bitte den Roboter vom Strom.

In the next step, pull the cable connecting the head and the base unit out of the base unit and loosen the black locking screw to completely separate the robot head from the base unit once. Now remove the remaining balls from the tubes and check if there is a foreign object interfering with the flow of the



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ball (*picture 20*). Use a narrow object such as a screwdriver to clear the tubes of any foreign objects. To check the ball intake area at the base unit, carefully tip the base unit onto the table. From the bottom of the base unit, there is a slot through which foreign objects can be pushed out (*picture 21*).

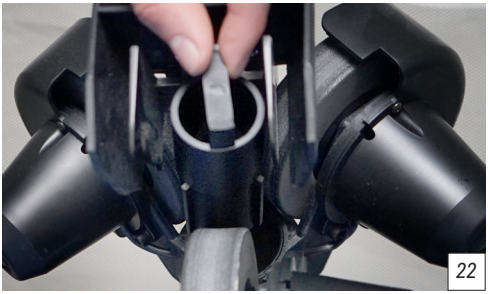
TIP: If possible, use a torch to be able to see more.

Now fill balls into the collection area again, reconnect the robot to the power and check whether the robot ejects the balls correctly again. If the problem could not be solved, please contact customer support.

Checking and adjusting the wheels

The shooting wheels of the GEWO Delta Nexxt are designed for a service life of about 1000 hours. As the wheels wear, the distance between the wheels gradually increases, causing the balls to be ejected more inaccurately and unevenly. If you notice that the ball ejection becomes imprecise, you should definitely check the distance between the 3 wheels and adjust it if necessary.

1. Place the distance test piece (black roller) between the 3 wheels so that the burrs of the roller are in the gaps between the wheels. If the wheel distance is correct, all 3 wheels should turn slightly. If not all wheels are touching the distance test piece, or the wheels are too tight on the test piece, then the distance should be adjusted (*picture 22*).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2. To adjust the distance, loosen the 4 mm hex screw on the motor cover of one wheel (*picture 23*) and turn the motor slightly in the desired direction until the wheel lightly touches the test piece. Then tighten the hexagon screw again to fix the position.

3. Now proceed in the same way for the other 2 wheels, so that when you carefully move the test piece back and forth, all 3 wheels rotate slightly.

i NOTE: The robot works properly up to a wheel distance diameter of 37 mm. The optimal distance diameter is 35 mm, which corresponds to the diameter of the test piece.

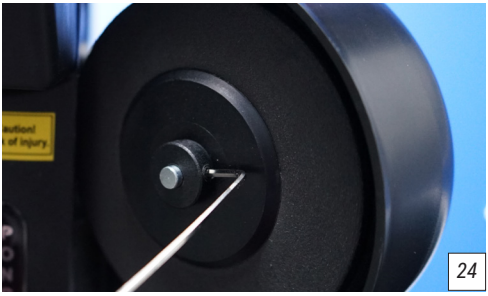
Replacing the wheels

After long use, the wheels may be so worn that they can no longer be adjusted. If the wheels no longer provide a clean ball ejection, you should order replacement wheels and replace the wheels. To replace the wheels, proceed as follows.

1. Start with the lower wheel. Use a 2 mm hexagonal spanner to loosen the small screw that fixes the shooting wheel to the motor (*picture 24)*.

2. Carefully pull the wheel out of its holder and replace it with the new wheel (*picture 25*).

3. Before tightening the screw again, make sure that the wheel can rotate freely and does not rub against the material on any side. As a rule, the wheel must be placed somewhat centrally on the holder for this.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Then tighten the screw again and turn the wheel a little again to make sure that the wheel is well positioned.

4. For the two upper wheels, before the wheel can be removed, the set screw must first be completely unscrewed with the 4 mm hexagonal spanner.

5. Now the cable connecting the motor to the power supply should be pulled out as far as possible to ensure more clearance for the motor to rotate. Do not pull too hard on the cable so as not to damage it.

6. Now turn the motor as far away from the ball ejector as possible. Now you can repeat steps 1-3 in the same way as for the lower wheel. You may have to press the foam of the wheels slightly to get past the robot head.

7. After changing the upper wheels, always make sure that you have to readjust the ball distance using the black test piece. And push the two cables back into the motor cover a little so that they are better protected.

i TIP: To avoid uneven ball ejection, we recommend always replacing all 3 wheels at the same time. A different degree of wear between the wheels can have an effect on the ejection behaviour.

Other maintenance

In case of various problems, a system restart of the robot can lead to a solution. To do this, disconnect the robot from the power supply for at least one minute so that no more processes are running in the buffer. Then reconnect the robot to the power supply as usual.

After a long period of use, the ejector may wear out. If the balls are only ejected very imprecisely, it may help to remove the white steel strip, carefully clean the ejector with cleaning alcohol and then attach a new steel strip.

2 replacement strips are included with your GEWO Delta Nexxt robot. If you need more replacement strips, please contact a GEWO dealer.

6. Technical data

Technical specifications: 100~240V, 50~60 Hz AC, Output: 24V, 3A
Suitable for a temperature range of 0~40°C.
Weight: approx. 6 kg with mains
Overall dimensions (with mains): Height 78 cm, depth 32 cm, width 25 cm (folded).
Height 86 cm, depth 160 cm, width 157 cm (assembled)

7. Warranty

30 months manufacturer‘s warranty

If your GEWO Delta Nexxt robot experiences any problems during the warranty period that restrict normal operation, please contact your GEWO dealer and describe your problem. We will send you suitable spare parts through your dealer to repair the robot. If the problem is serious, we will provide your GEWO dealer with a replacement product free of charge. Please ensure that you pack the returned robot securely and that it does not receive any further damage during return transport.

This warranty is not transferable and does not cover normal wear and tear or damage caused by improper handling or use of the robot. The warranty is void if the product has been worn, damaged or altered in any way from its original condition.

8. Disposal information

The symbol of the crossed-out wheeled bin means that this product and its accessories marked with the symbol shown above must be disposed of in accordance with the applicable legal regulations and separately from household waste. If you wish to dispose of individual parts marked with the crossed-out dustbin, hand them in at an official collection point near you.

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