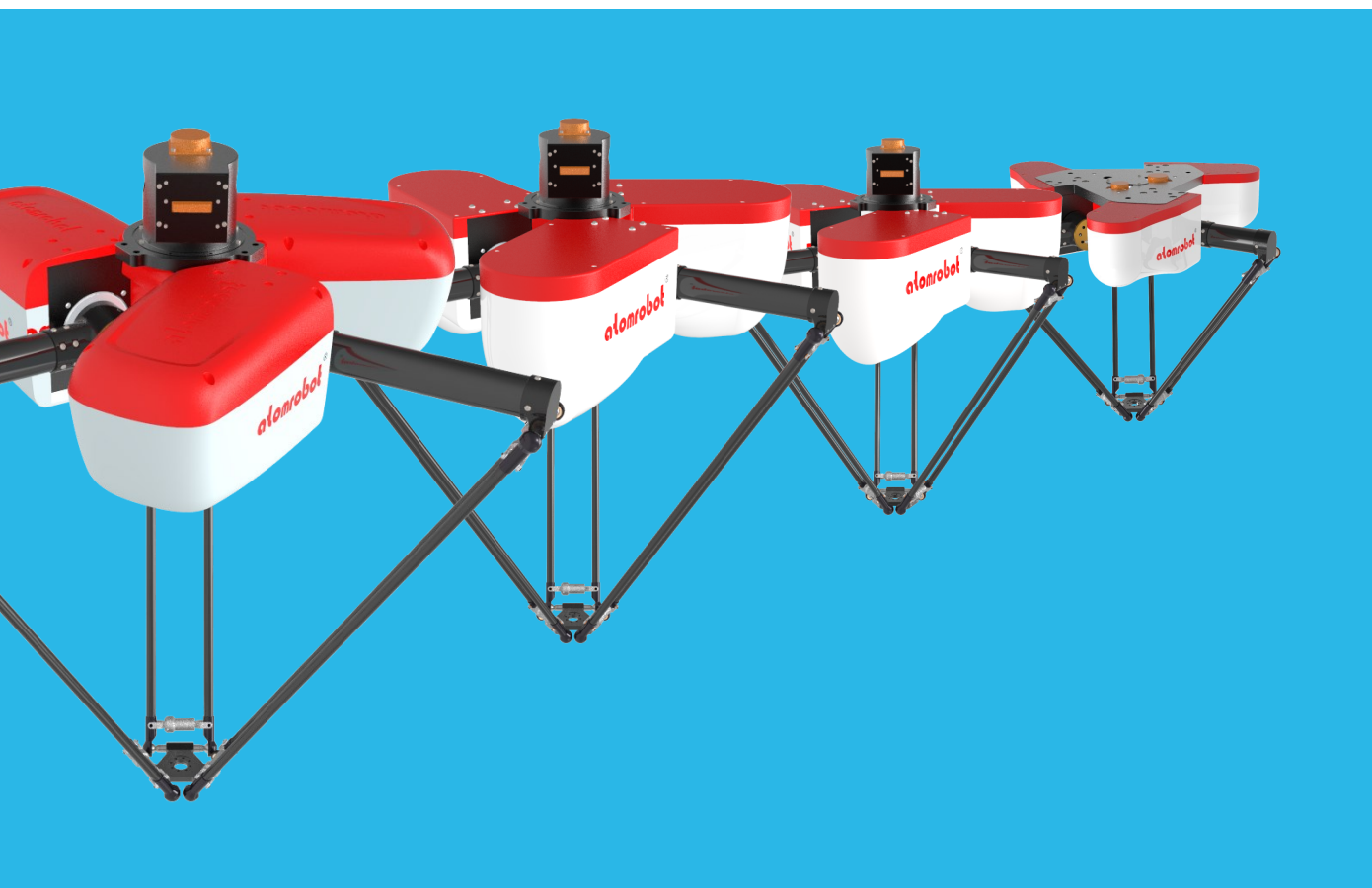


# 并联机器人

## 选型手册

Parallel robot selection Manual

D3W



## • 型号和符号

| D3W | 1100 | P0        | A2               | E1                                   | FXGX                   |
|-----|------|-----------|------------------|--------------------------------------|------------------------|
| 机型  | 型号   | 负载        | 控制器类型            | 控制柜类型                                | 视觉                     |
| D3W | 600  | P0: 标准    | A1: ATOMCONTROL  | E1: ATOM-01<br>E2: ATOM-02<br>E3: 定制 | F0G0: 无视觉<br>FXGX: 有视觉 |
|     | 800  |           |                  |                                      |                        |
|     | 1100 | P15: 15KG | A2: KEBA CONTROL |                                      |                        |
|     | 1200 |           |                  |                                      |                        |
|     | 1300 | P25: 25KG |                  |                                      |                        |
|     | 1400 |           |                  |                                      |                        |
|     | 1600 |           |                  |                                      |                        |

## • Model and Symbol

D3W

1100

P0

A2

E1

FXGX

| Robot type | Type | Load Type    | Control Type     | Control Cabinet                          | Vision Type                                     |
|------------|------|--------------|------------------|------------------------------------------|-------------------------------------------------|
| D3W        | 600  | P0: Standard | A1: ATOMCONTROL  | E1: ATOM-01<br>E2: ATOM-02<br>E3: Custom | F0G0:<br>Without vision<br>FXGX:<br>With vision |
|            | 800  |              |                  |                                          |                                                 |
|            | 1100 | P15: 15KG    | A2: KEBA CONTROL |                                          |                                                 |
|            | 1200 |              |                  |                                          |                                                 |
|            | 1300 | P25: 25KG    |                  |                                          |                                                 |
|            | 1400 |              |                  |                                          |                                                 |
|            | 1600 |              |                  |                                          |                                                 |

## D3W-600-P0



高速度  
高精度  
高稳定性  
小巧、敏捷

High speed  
High precision  
High stability  
Small and Agile

- ◆ 标准循环时间小于0.5s,满足追求最高速度和最小体积需求

The standard cycle time is less than 0.5s, meeting your pursuit for the maximum speed and the minimum volume.

- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

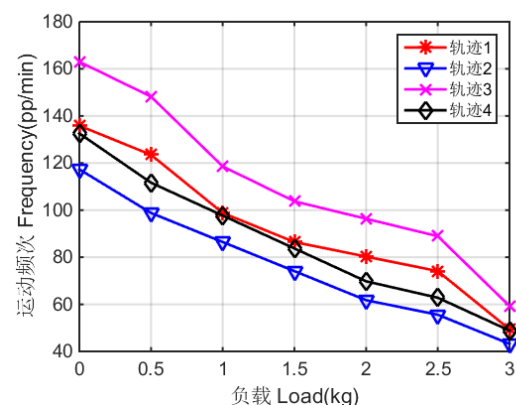
Advanced design of compression spring ,enables the parallel-arm to be used for a long time and be easily dis-mounted.

- ◆ 非常适于狭小空间内作业、3C制造等行业的高速高精生产作业, 主要用于小型工件的装配、搬运、检测等

The robot is ideal for narrow space operations, as well as high-speed and high-precision in 3C field. Widely used in assembly, handling and testing of small work pieces.

| 型号 Type                                           |                    | D3W-600-P0                                  |
|---------------------------------------------------|--------------------|---------------------------------------------|
| 轴数 Axes                                           |                    | 3                                           |
| 最大负载 Payload                                      |                    | 3kg                                         |
| 机器人本体<br>Manipulator                              | 重量 Weight          | 38.7kg                                      |
|                                                   | 工作空间直径<br>Diameter | 600mm                                       |
| 重复定位精度<br>repeatability                           | 位置 Position        | 0.05mm                                      |
|                                                   | 旋转 Rotation        | —                                           |
| 旋转范围 Rotation range                               |                    | —                                           |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |                    | —                                           |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up              | 42.5°                                       |
|                                                   | 下摆 Down            | 69.8°                                       |
| 输入电源<br>Power supply                              |                    | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |
| 电源容量<br>Power capacity                            |                    | 3KVA                                        |
| 额定功率<br>Rated Power                               |                    | 1.2kw                                       |
| 保存温度<br>Storage temperature                       |                    | -10°C~70°C                                  |
| 工作环境<br>Work environment                          |                    | -10°C~50°C, RH≤80%                          |
| 防护等级<br>Protection                                |                    | IP55                                        |

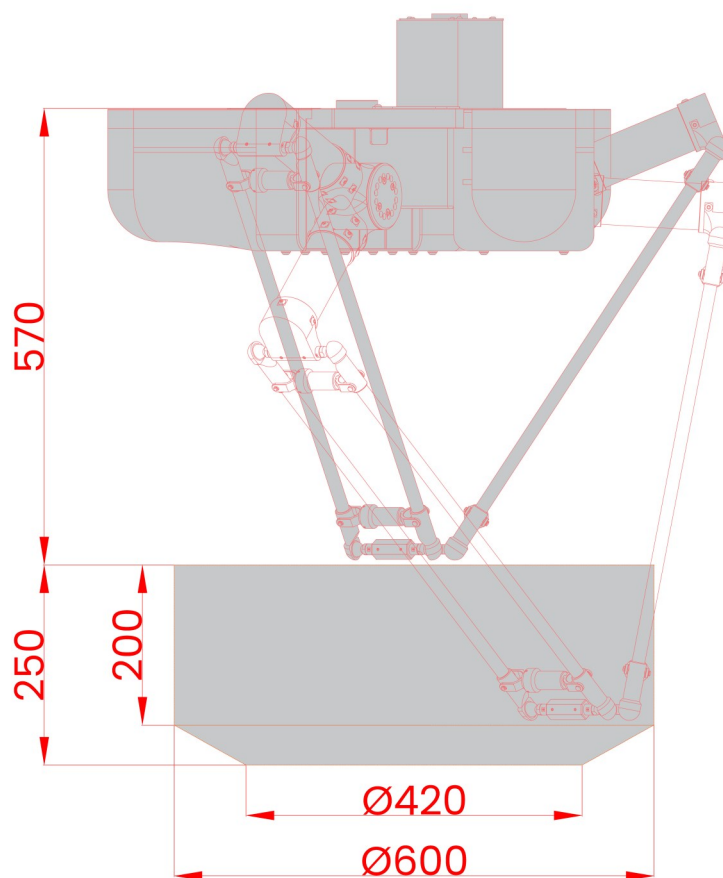
## ● 负载-频次 Load-Frequency



| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3 | P1 → P2 → P3 → P2 → P1           | h=25, b=305   |
| 轨迹4 Trajectory4 | P1 → P2 → P3 → P2 → P1           | h=25, b=500   |

特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。

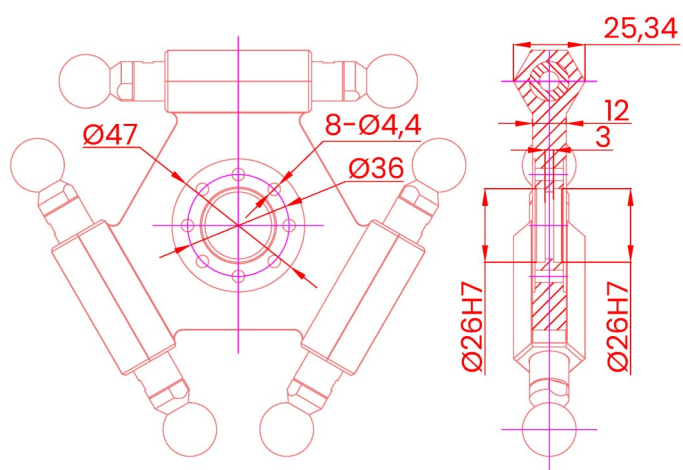
### 外形尺寸及运动范围 Outline dimensions and Working range (mm)



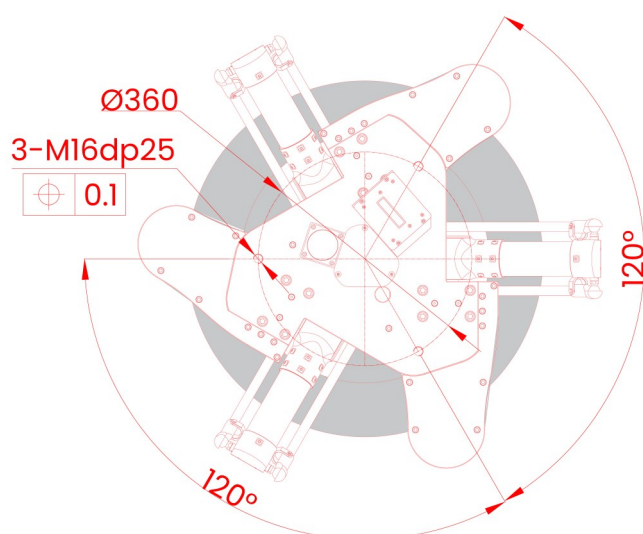
**说明:**  
图示下部加深部分为机器人动平台几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

**Instruction:**  
The bottom gray part is the workplace of the center point of moving platform, which is composed of a cylinder at the top and a circular truncated cone at the bottom.

### 法兰 Flange (mm)



### 基座安装 Base installation (mm)





## D3W-800-P0



高速度  
高精度  
高稳定性  
经济实用

High speed  
High precision  
High stability  
Economic & Practical

- ◆ 标准循环时间小于0.45s,满足追求最高速度和最经济需求

The standard cycle time is less than 0.45s, meeting your pursuit for the maximum speed and economic.

- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

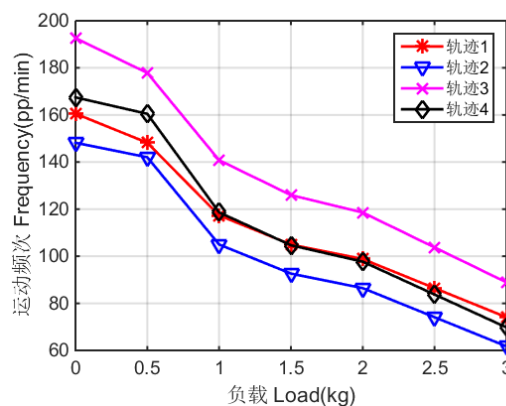
Advanced design of compression spring ,enables the parallel-arm to be used for a long time and be easily dis-mounted.

- ◆ 非常适于食品、医药等行业的高速生产作业, 主要用于小型物料的装配、搬运、分拣等

The robot is ideal for high-speed production in food and medicine industry. Widely used in assembly, handling and pick-and-place of small materials.

| 型号 Type                                           |                    | D3W-800-P0                                  |
|---------------------------------------------------|--------------------|---------------------------------------------|
| 轴数 Axes                                           |                    | 3                                           |
| 最大负载 Payload                                      |                    | 3kg                                         |
| 机器人本体<br>Manipulator                              | 重量 Weight          | 69.5kg                                      |
|                                                   | 工作空间直径<br>Diameter | 800mm                                       |
| 重复定位精度<br>repeatability                           | 位置 Position        | 0.05mm                                      |
|                                                   | 旋转 Rotation        | —                                           |
| 旋转范围 Rotation range                               |                    | —                                           |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |                    | —                                           |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up              | 42.5°                                       |
|                                                   | 下摆 Down            | 65.8°                                       |
| 输入电源<br>Power supply                              |                    | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |
| 电源容量<br>Power capacity                            |                    | 6KVA                                        |
| 额定功率<br>Rated Power                               |                    | 2.25kw                                      |
| 保存温度<br>Storage temperature                       |                    | -10°C~70°C                                  |
| 工作环境<br>Work environment                          |                    | -10°C~50°C, RH≤80%                          |
| 防护等级<br>Protection                                |                    | IP55                                        |

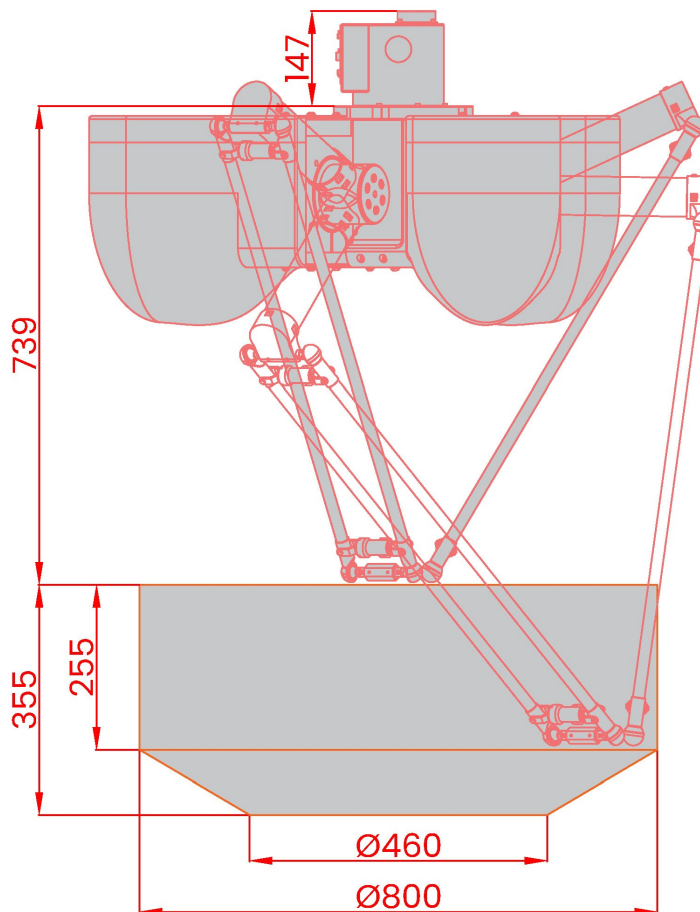
## ● 负载-频次 Load-Frequency



| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3 | P1 → P2 → P3 → P2 → P1           | h=25, b=305   |
| 轨迹4 Trajectory4 | P1 → P2 → P3 → P2 → P1           | h=25, b=500   |

特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。

外形尺寸及运动范围  
Outline dimensions and Working range (mm)



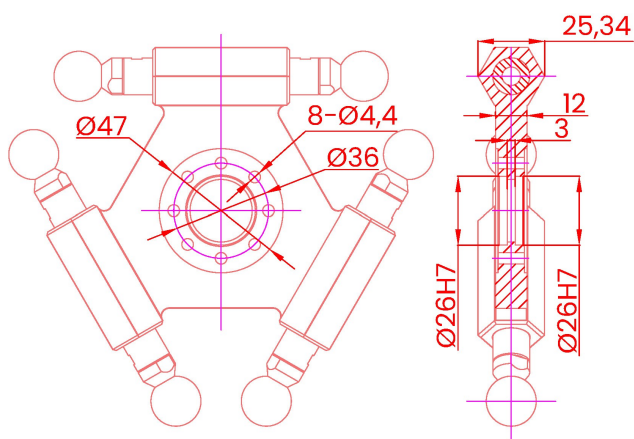
说明:

图示下部加深部分为机器人动平台几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

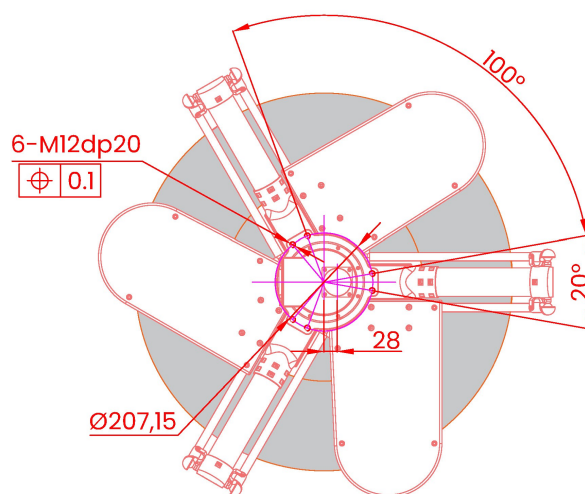
Instruction:

The bottom gray part is the workplace of the center point of moving platform, which is composed of a cylinder at the top and a circular truncated cone at the bottom.

法兰 Flange (mm)



基座安装 Base installation (mm)



## D3W-1100-P0



高速度  
高稳定性  
大空间  
经济实用

High speed  
High stability  
Large space  
Economic & Practical

- ◆ 标准循环时间小于0.4s,满足追求最高速度和最经济需求

The standard cycle time is less than 0.4s, meeting your pursuit for the maximum speed and economic.

- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

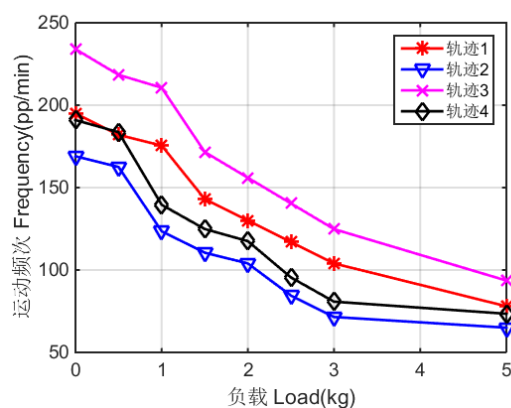
Advanced design of compression spring ,enables the parallel-arm to be used for a long time and be easily dis-mounted.

- ◆ 非常适于食品、医药等行业的高速生产作业, 主要用于小型物料的装配、搬运、分拣等

The robot is ideal for high-speed production in food and medicine industry. Widely used in assembly, handling and pick-and-place of small materials.

| 型号 Type                                           |                    | D3W-1100-P0                                 |
|---------------------------------------------------|--------------------|---------------------------------------------|
| 轴数 Axes                                           |                    | 3                                           |
| 最大负载 Payload                                      |                    | 5kg                                         |
| 机器人本体<br>Manipulator                              | 重量 Weight          | 88kg                                        |
|                                                   | 工作空间直径<br>Diameter | 1100mm                                      |
| 重复定位精度<br>repeatability                           | 位置 Position        | 0.05mm                                      |
|                                                   | 旋转 Rotation        | —                                           |
| 旋转范围 Rotation range                               |                    | —                                           |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |                    | —                                           |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up              | 32.5°                                       |
|                                                   | 下摆 Down            | 68.5°                                       |
| 输入电源<br>Power supply                              |                    | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |
| 电源容量<br>Power capacity                            |                    | 10KVA                                       |
| 额定功率<br>Rated Power                               |                    | 6kw                                         |
| 保存温度<br>Storage temperature                       |                    | -10°C~70°C                                  |
| 工作环境<br>Work environment                          |                    | -10°C~50°C, RH≤80%                          |
| 防护等级<br>Protection                                |                    | IP55                                        |

## ● 负载-频次 Load-Frequency

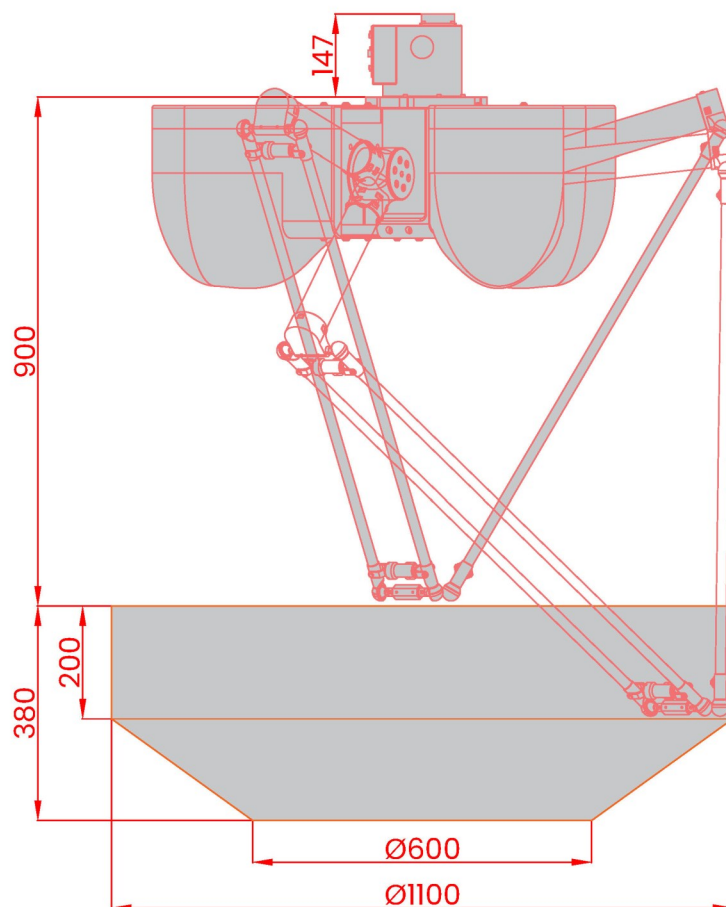


| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3 | P1 → P2 → P3 → P2 → P1           | h=25, b=305   |
| 轨迹4 Trajectory4 | P1 → P2 → P3 → P2 → P1           | h=25, b=500   |

特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。

## 外形尺寸及运动范围

## Outline dimensions and Working range (mm)



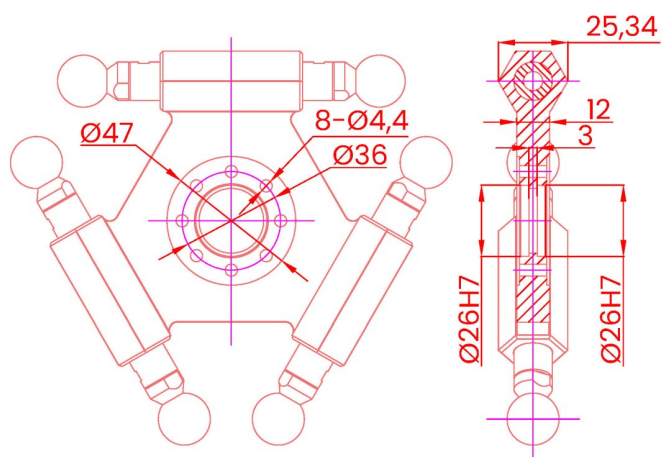
## 说明:

图示下部加深部分为机器人动平台几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

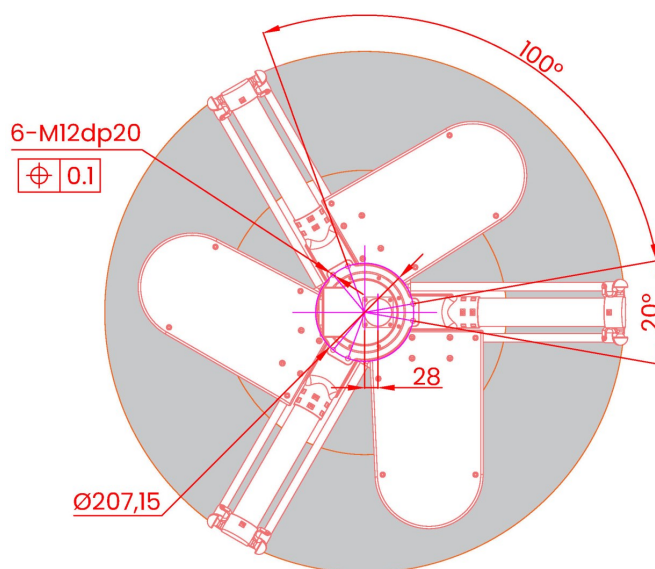
## Instruction:

The bottom gray part is the workplace of the center point of moving platform, which is composed of a cylinder at the top and a circular truncated cone at the bottom.

## 法兰 Flange (mm)



## 基座安装 Base installation (mm)



## D3W-1200-P0



高速度  
高稳定性  
大空间  
低高度

High speed  
High stability  
Large space  
Lower Height

- ◆ 标准循环时间小于0.4s,满足追求最高速度和最经济需求

The standard cycle time is less than 0.4s, meeting your pursuit for the maximum speed and economic.

- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

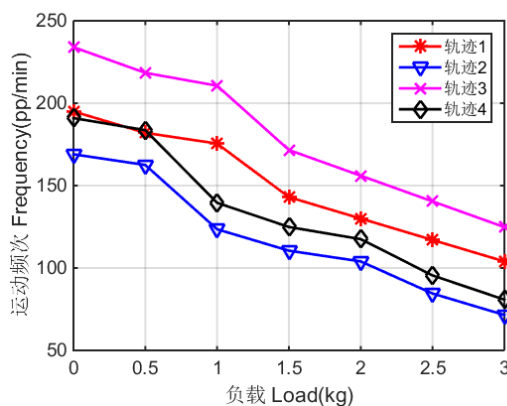
Advanced design of compression spring ,enables the parallel-arm to be used for a long time and be easily dis-mounted.

- ◆ 非常适于食品、医药等行业的高速生产作业, 主要用于空间高度受限场合的物料装配、搬运、分拣等

The robot is ideal for high-speed production in food and medicine industry. Widely used in assembly, handling and pick-and-place of small materials for space height limited occasions.

| 型号 Type                                           |                    | D3W-1200-P0                                 |
|---------------------------------------------------|--------------------|---------------------------------------------|
| 轴数 Axes                                           |                    | 3                                           |
| 最大负载 Payload                                      |                    | 3kg                                         |
| 机器人本体<br>Manipulator                              | 重量 Weight          | 73.6kg                                      |
|                                                   | 工作空间直径<br>Diameter | 1200mm                                      |
| 重复定位精度<br>repeatability                           | 位置 Position        | 0.05mm                                      |
|                                                   | 旋转 Rotation        | —                                           |
| 旋转范围 Rotation range                               |                    | —                                           |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |                    | —                                           |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up              | 33°                                         |
|                                                   | 下摆 Down            | 87°                                         |
| 输入电源<br>Power supply                              |                    | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |
| 电源容量<br>Power capacity                            |                    | 10KVA                                       |
| 额定功率<br>Rated Power                               |                    | 6kw                                         |
| 保存温度<br>Storage temperature                       |                    | -10°C~70°C                                  |
| 工作环境<br>Work environment                          |                    | -10°C~50°C, RH≤80%                          |
| 防护等级<br>Protection                                |                    | IP55                                        |

## ● 负载-频次 Load-Frequency

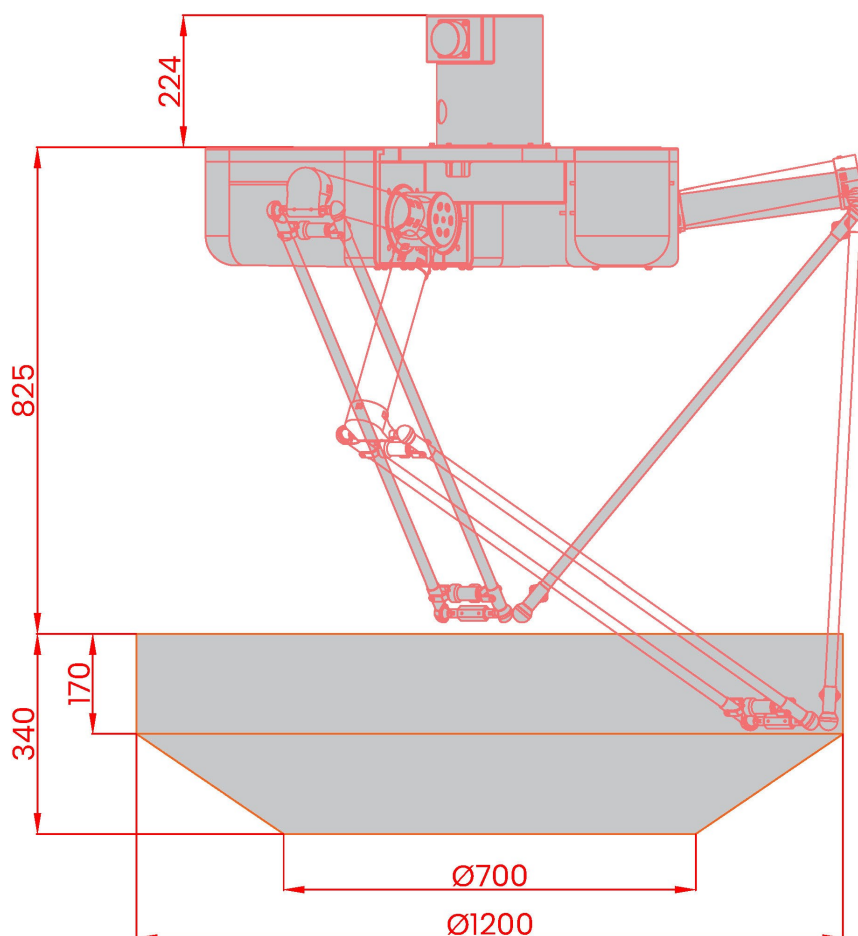


| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3 | P1 → P2 → P3 → P2 → P1           | h=25, b=305   |
| 轨迹4 Trajectory4 | P1 → P2 → P3 → P2 → P1           | h=25, b=500   |

特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。



### 外形尺寸及运动范围 Outline dimensions and Working range (mm)



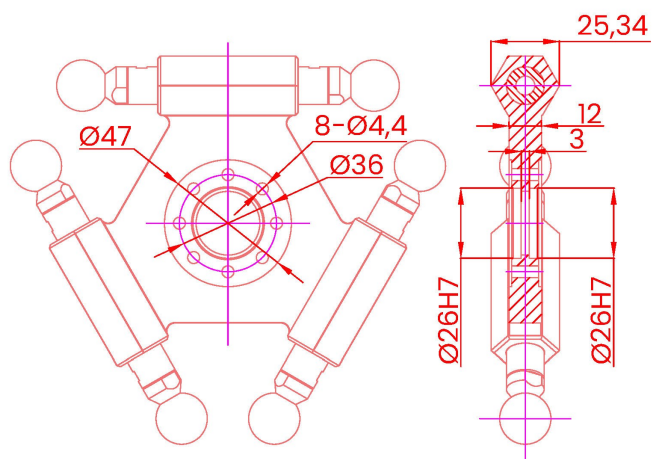
说明:

图示下部加深部分为机器人动平台几何中心的运动范围, 上部为圆柱空间, 并在下部向内收敛。

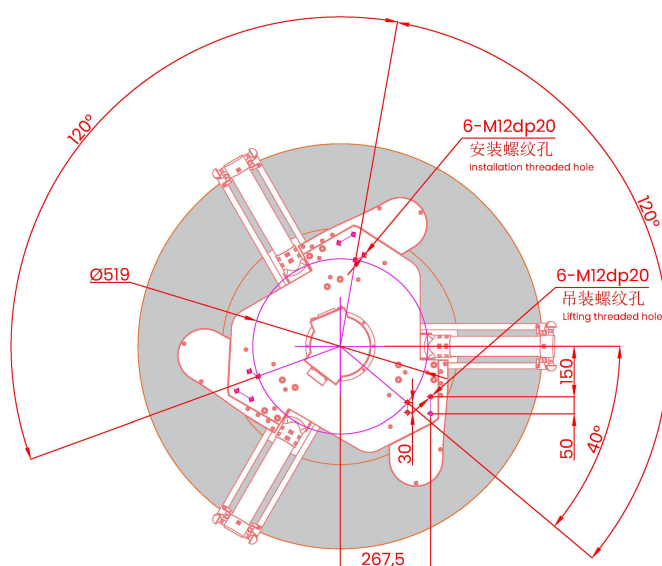
Instruction:

The bottom gray part is the workplace of the center point of moving platform, which is composed of a cylinder at the top and a circular truncated cone at the bottom.

法兰 Flange (mm)



基座安装 Base installation (mm)



## D3W-1300-P0



高速度  
高稳定性  
大空间  
经济实用

High speed  
High stability  
Large space  
Economic & Practical

- ◆ 标准循环时间小于0.4s,满足追求最高速度和最经济需求

The standard cycle time is less than 0.4s, meeting your pursuit for the maximum speed and economic.

- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

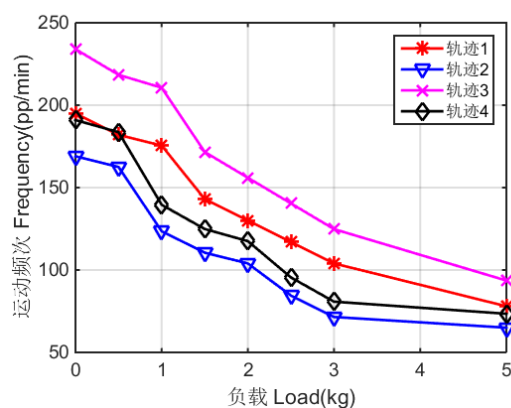
Advanced design of compression spring ,enables the parallel-arm to be used for a long time and be easily dis-mounted.

- ◆ 非常适于食品、医药等行业的高速生产作业, 主要用于小型物料的装配、搬运、分拣等

The robot is ideal for high-speed production in food and medicine industry. Widely used in assembly, handling and pick-and-place of small materials.

| 型号 Type                                           |                    | D3W-1300-P0                                 |
|---------------------------------------------------|--------------------|---------------------------------------------|
| 轴数 Axes                                           |                    | 3                                           |
| 最大负载 Payload                                      |                    | 5kg                                         |
| 机器人本体<br>Manipulator                              | 重量 Weight          | 90kg                                        |
|                                                   | 工作空间直径<br>Diameter | 1300mm                                      |
| 重复定位精度<br>repeatability                           | 位置 Position        | 0.05mm                                      |
|                                                   | 旋转 Rotation        | —                                           |
| 旋转范围 Rotation range                               |                    | —                                           |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |                    | —                                           |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up              | 31.5°                                       |
|                                                   | 下摆 Down            | 74°                                         |
| 输入电源<br>Power supply                              |                    | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |
| 电源容量<br>Power capacity                            |                    | 10KVA                                       |
| 额定功率<br>Rated Power                               |                    | 6kw                                         |
| 保存温度<br>Storage temperature                       |                    | -10°C~70°C                                  |
| 工作环境<br>Work environment                          |                    | -10°C~50°C, RH≤80%                          |
| 防护等级<br>Protection                                |                    | IP55                                        |

## ● 负载-频次 Load-Frequency



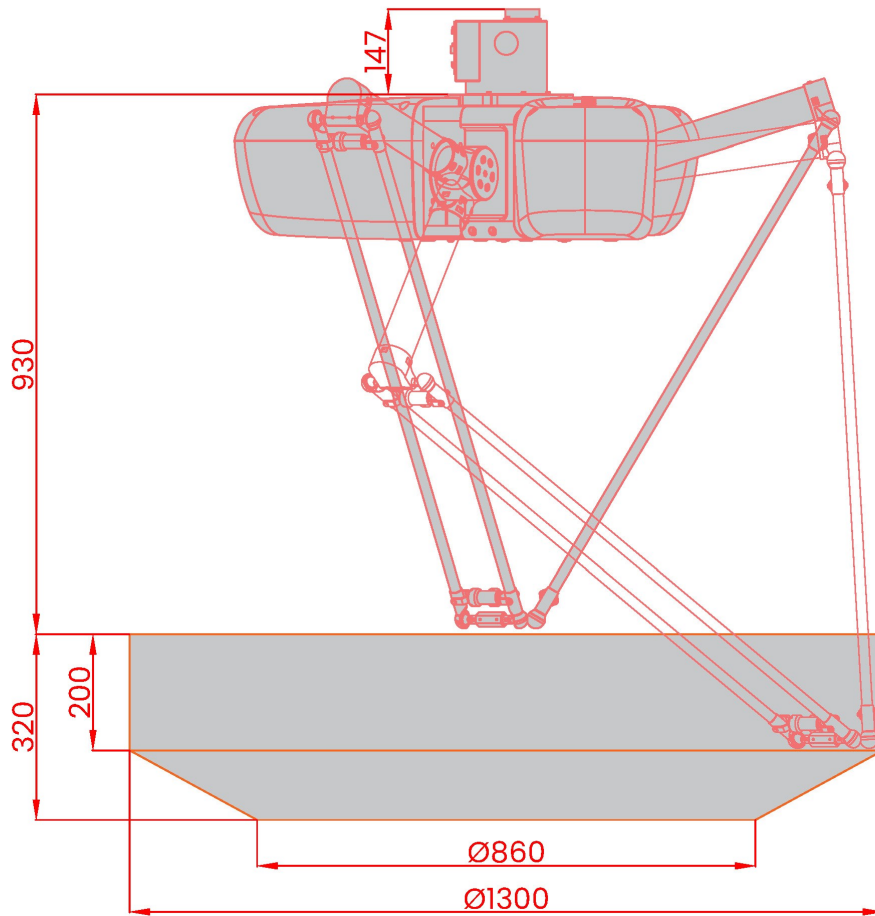
| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3 | P1 → P2 → P3 → P2 → P1           | h=25, b=305   |
| 轨迹4 Trajectory4 | P1 → P2 → P3 → P2 → P1           | h=25, b=500   |

特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。



## 外形尺寸及运动范围

## Outline dimensions and Working range (mm)



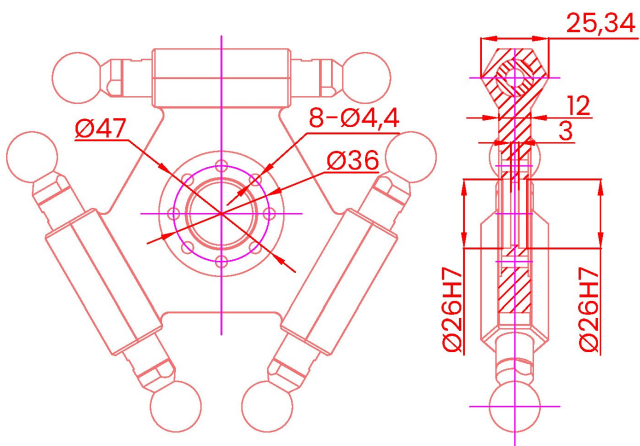
## 说明:

图示下部加深部分为机器人动平台几何中心的运动范围, 上部为圆柱空间, 并在下部向内收敛。

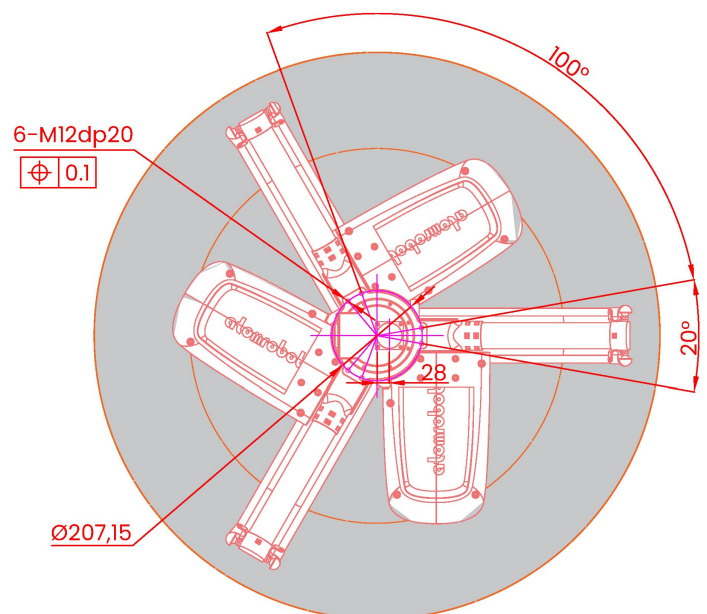
## Instruction:

The bottom gray part is the work-place of the center point of moving platform, which is composed of a cylinder at the top and a circular truncated cone at the bottom.

## 法兰 Flange (mm)



## 基座安装 Base installation (mm)



## D3W-1400-P0



高速度  
高稳定性  
大空间  
经济实用

High speed  
High stability  
Large space  
Economic & Practical

- ◆ 标准循环时间小于0.4s,满足追求最高速度和最经济需求

The standard cycle time is less than 0.4s, meeting your pursuit for the maximum speed and economic.

- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

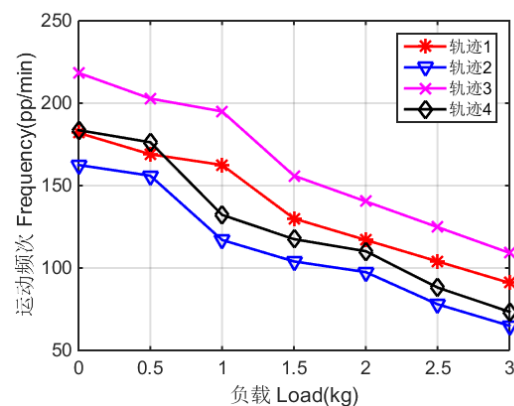
Advanced design of compression spring ,enables the parallel-arm to be used for a long time and be easily dis-mounted.

- ◆ 非常适于食品、医药等行业的高速生产作业, 主要用于小型物料的装配、搬运、分拣等

The robot is ideal for high-speed production in food and medicine industry. Widely used in assembly, handling and pick-and-place of small materials.

| 型号 Type                                           |                    | D3W-1400-P0                                 |
|---------------------------------------------------|--------------------|---------------------------------------------|
| 轴数 Axes                                           |                    | 3                                           |
| 最大负载 Payload                                      |                    | 3kg                                         |
| 机器人本体<br>Manipulator                              | 重量 Weight          | 91.5kg                                      |
|                                                   | 工作空间直径<br>Diameter | 1400mm                                      |
| 重复定位精度<br>repeatability                           | 位置 Position        | 0.05mm                                      |
|                                                   | 旋转 Rotation        | —                                           |
| 旋转范围 Rotation range                               |                    | —                                           |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |                    | —                                           |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up              | 22°                                         |
|                                                   | 下摆 Down            | 76°                                         |
| 输入电源<br>Power supply                              |                    | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |
| 电源容量<br>Power capacity                            |                    | 10KVA                                       |
| 额定功率<br>Rated Power                               |                    | 6kw                                         |
| 保存温度<br>Storage temperature                       |                    | -10°C~70°C                                  |
| 工作环境<br>Work environment                          |                    | -10°C~50°C, RH≤80%                          |
| 防护等级<br>Protection                                |                    | IP55                                        |

## ● 负载-频次 Load-Frequency

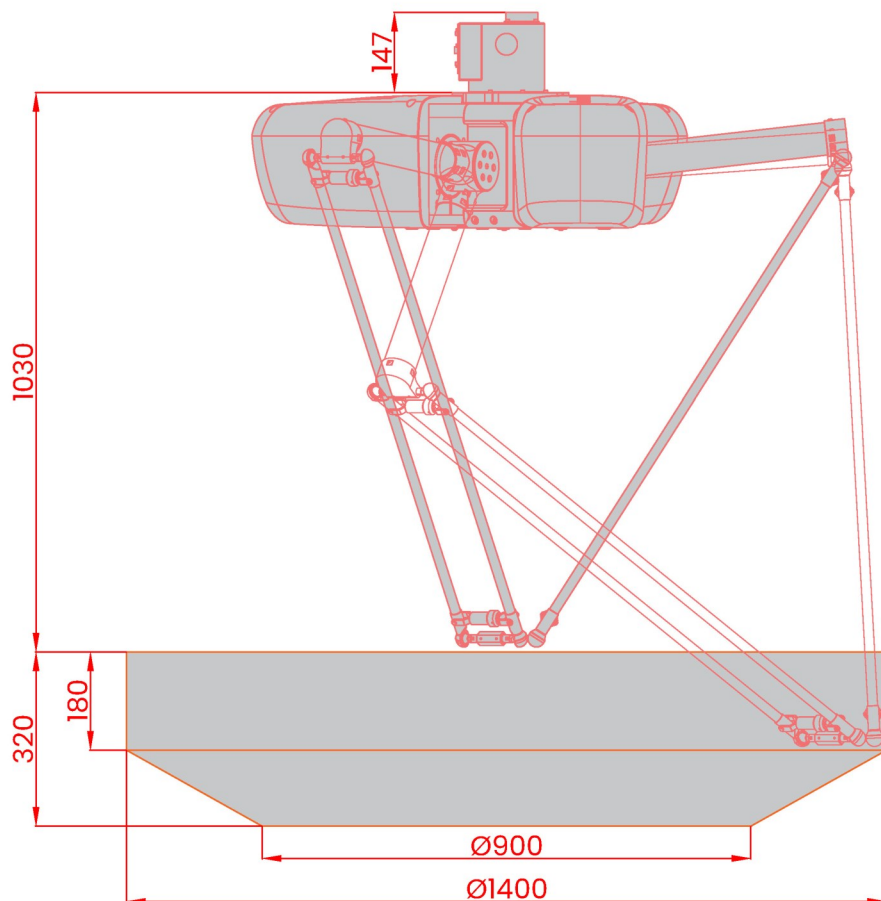


| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3 | P1 → P2 → P3 → P2 → P1           | h=25, b=305   |
| 轨迹4 Trajectory4 | P1 → P2 → P3 → P2 → P1           | h=25, b=500   |

特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。

## 外形尺寸及运动范围

## Outline dimensions and Working range (mm)



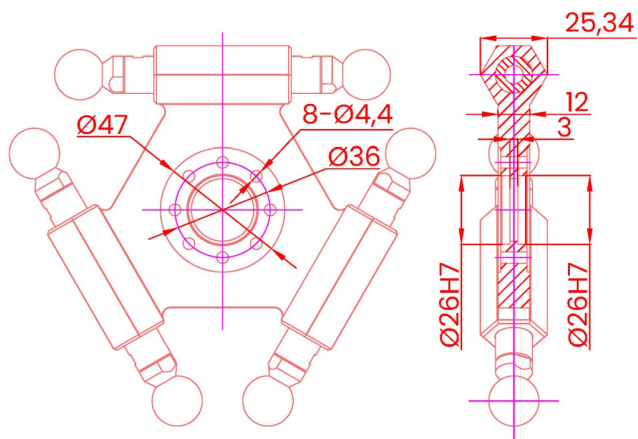
## 说明:

图示下部加深部分为机器人动平台几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

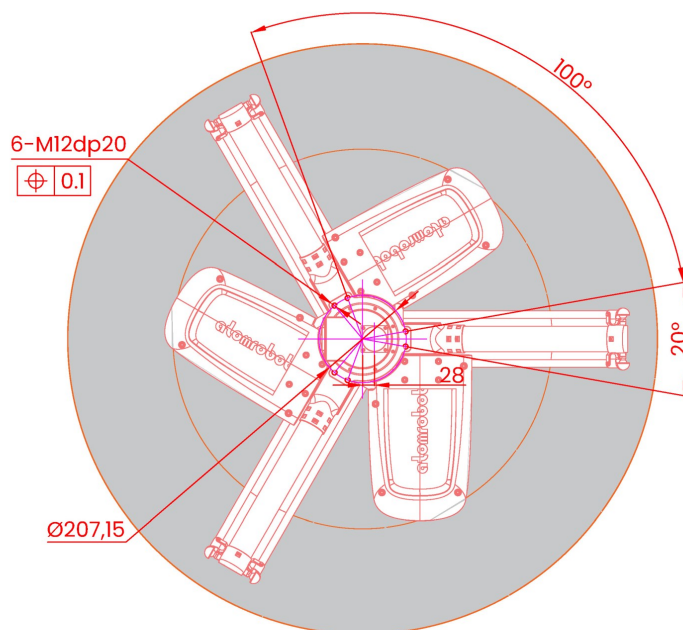
## Instruction:

The bottom gray part is the work-place of the center point of moving platform, which is composed of a cylinder at the top and a circular truncated cone at the bottom.

## 法兰 Flange (mm)



## 基座安装 Base installation (mm)



## D3W-1600-P0



高速度  
高稳定性  
大空间  
经济实用

High speed  
High stability  
Large space  
Economic & Practical

- ◆ 标准循环时间小于0.4s,满足追求最高速度和最经济需求

The standard cycle time is less than 0.4s, meeting your pursuit for the maximum speed and economic.

- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

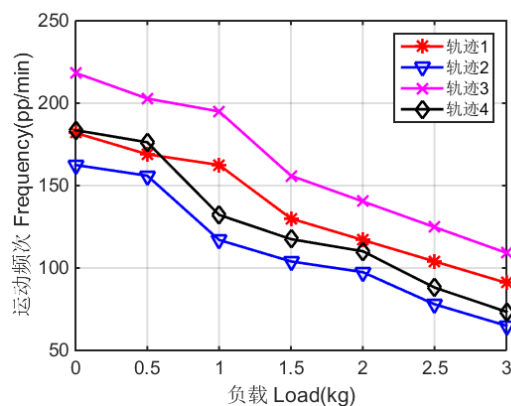
Advanced design of compression spring ,enables the parallel-arm to be used for a long time and be easily dis-mounted.

- ◆ 非常适于食品、医药等行业的高速生产作业, 主要用于小型物料的装配、搬运、分拣等

The robot is ideal for high-speed production in food and medicine industry. Widely used in assembly, handling and pick-and-place of small materials.

| 型号 Type                                           |                    | D3W-1600-P0                                 |
|---------------------------------------------------|--------------------|---------------------------------------------|
| 轴数 Axes                                           |                    | 3                                           |
| 最大负载 Payload                                      |                    | 3kg                                         |
| 机器人本体<br>Manipulator                              | 重量 Weight          | 93kg                                        |
|                                                   | 工作空间直径<br>Diameter | 1600mm                                      |
| 重复定位精度<br>repeatability                           | 位置 Position        | 0.05mm                                      |
|                                                   | 旋转 Rotation        | —                                           |
| 旋转范围 Rotation range                               |                    | —                                           |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |                    | —                                           |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up              | 22°                                         |
|                                                   | 下摆 Down            | 76°                                         |
| 输入电源<br>Power supply                              |                    | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |
| 电源容量<br>Power capacity                            |                    | 10KVA                                       |
| 额定功率<br>Rated Power                               |                    | 6kw                                         |
| 保存温度<br>Storage temperature                       |                    | -10℃~70℃                                    |
| 工作环境<br>Work environment                          |                    | -10℃~50℃, RH≤80%                            |
| 防护等级<br>Protection                                |                    | IP55                                        |

## ● 负载-频次 Load-Frequency

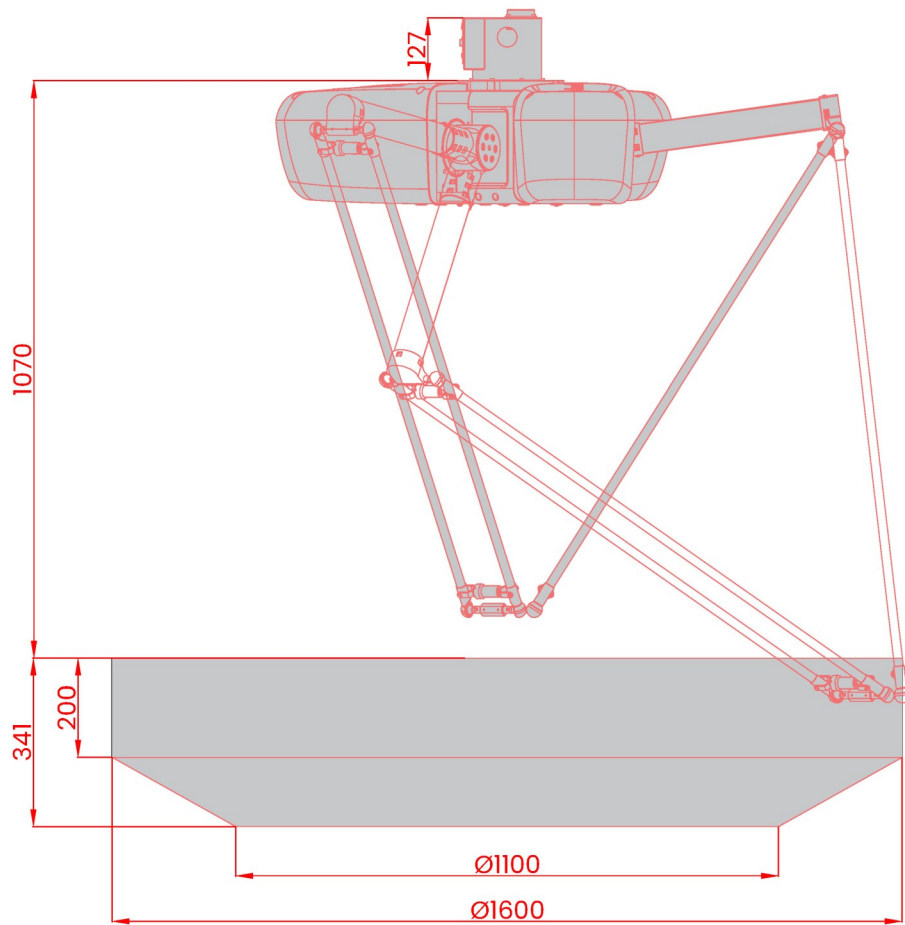


| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3 | P1 → P2 → P3 → P2 → P1           | h=25, b=305   |
| 轨迹4 Trajectory4 | P1 → P2 → P3 → P2 → P1           | h=25, b=500   |

特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。

## 外形尺寸及运动范围

## Outline dimensions and Working range (mm)



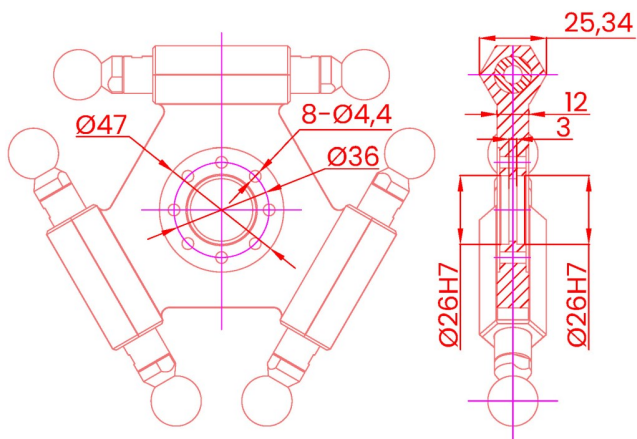
## 说明:

图示下部加深部分为机器人动平台几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

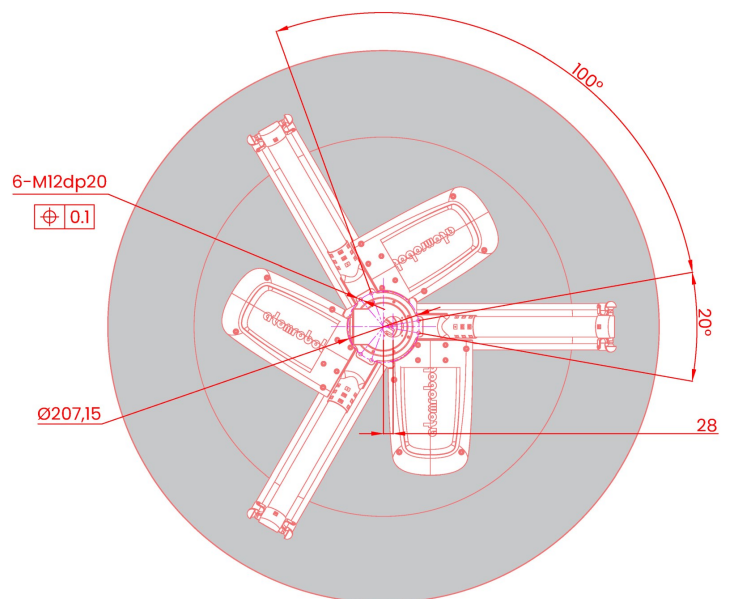
## Instruction:

The bottom gray part is the work-place of the center point of moving platform, which is composed of a cylinder at the top and a circular truncated cone at the bottom.

## 法兰 Flange (mm)



## 基座安装 Base installation (mm)





## D3W-1100-P15



高稳定性  
大空间  
重负载  
经济实用

High stability  
Large space  
Heavy load  
Economic & Practical

- ◆ 标准循环时间小于0.6s,满足追求最高负载和最经济需求

The standard cycle time is less than 0.6s, meeting your pursuit for the maximum load and economic.

- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

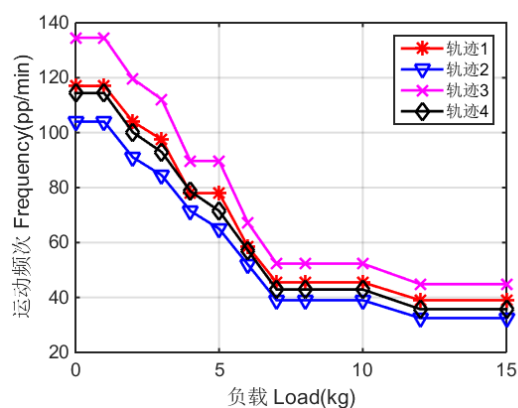
Advanced design of compression spring ,enables the parallel-arm to be used for a long time and be easily dis-mounted.

- ◆ 非常适于食品、医药等行业的高速生产作业, 主要用于较重型物料的装配、搬运、分拣等

The robot is ideal for high-speed production in food and medicine industry. Widely used in assembly, handling and pick-and-place of heavy materials.

| 型号 Type                                           |                    | D3W-1100-P15                                |
|---------------------------------------------------|--------------------|---------------------------------------------|
| 轴数 Axes                                           |                    | 3                                           |
| 最大负载 Payload                                      |                    | 15kg                                        |
| 机器人本体<br>Manipulator                              | 重量 Weight          | 115kg                                       |
|                                                   | 工作空间直径<br>Diameter | 1100mm                                      |
| 重复定位精度<br>repeatability                           | 位置 Position        | 0.05mm                                      |
|                                                   | 旋转 Rotation        | —                                           |
| 旋转范围 Rotation range                               |                    | —                                           |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |                    | —                                           |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up              | 23.5°                                       |
|                                                   | 下摆 Down            | 70°                                         |
| 输入电源<br>Power supply                              |                    | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |
| 电源容量<br>Power capacity                            |                    | 10KVA                                       |
| 额定功率<br>Rated Power                               |                    | 6kw                                         |
| 保存温度<br>Storage temperature                       |                    | -10°C~70°C                                  |
| 工作环境<br>Work environment                          |                    | -10°C~50°C, RH≤80%                          |
| 防护等级<br>Protection                                |                    | IP55                                        |

### ● 负载-频次 Load-Frequency

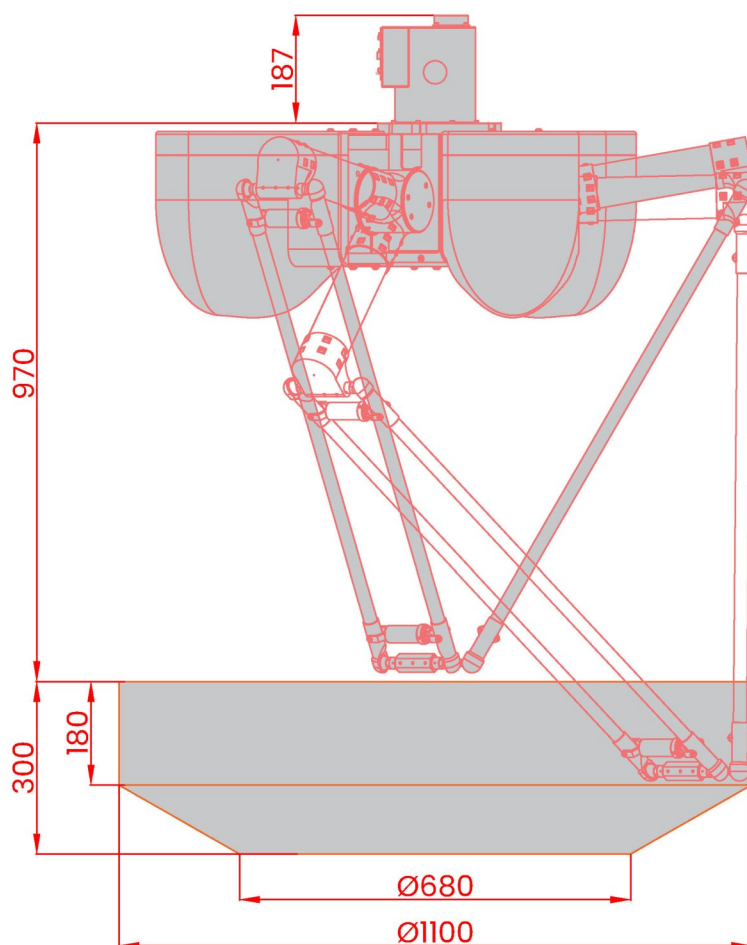


| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3 | P1 → P2 → P3 → P2 → P1           | h=25, b=305   |
| 轨迹4 Trajectory4 | P1 → P2 → P3 → P2 → P1           | h=25, b=500   |

特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。



### 外形尺寸及运动范围 Outline dimensions and Working range (mm)



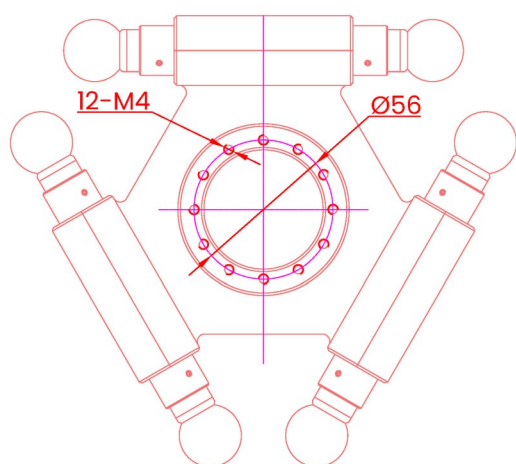
#### 说明:

图示下部加深部分为机器人动平台几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

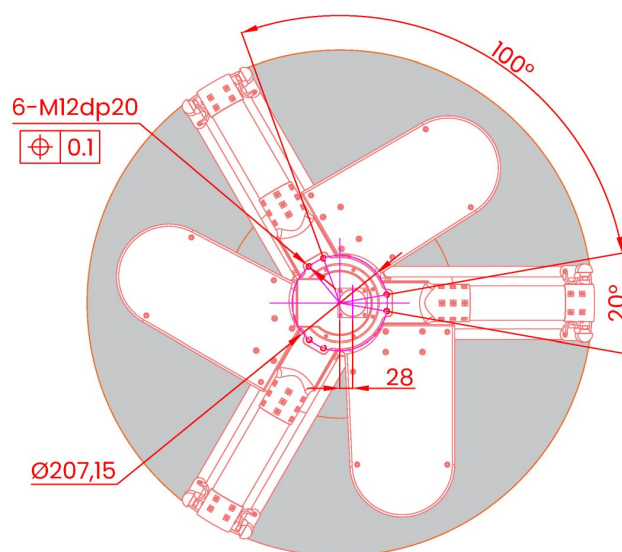
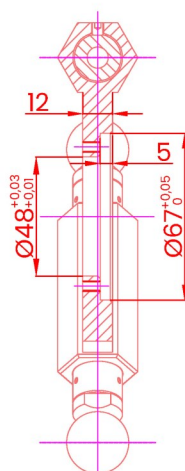
#### Instruction:

The bottom gray part is the workplace of the center point of moving platform, which is composed of a cylinder at the top and a circular truncated cone at the bottom.

### 法兰 Flange (mm)



### 基座安装 Base installation (mm)



## D3W-1400-P15



高稳定性  
大空间  
重负载  
经济实用

High stability  
Large space  
Heavy load  
Economic & Practical

- ◆ 标准循环时间小于0.6s,满足追求最高负载和最经济需求

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- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

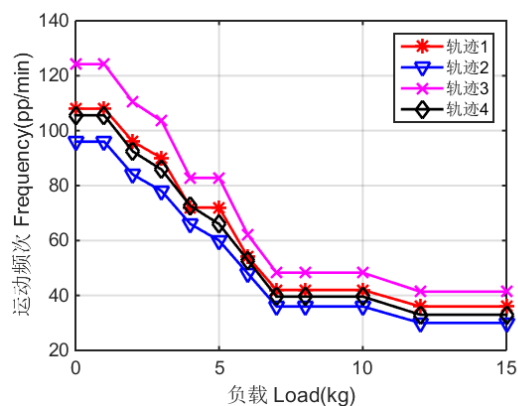
Advanced design of compression spring ,enables the parallel-arm to be used for a long time and be easily dis-mounted.

- ◆ 非常适于食品、医药等行业的高速生产作业, 主要用于较重型物料的装配、搬运、分拣等

The robot is ideal for high-speed production in food and medicine industry. Widely used in assembly, handling and pick-and-place of heavy materials.

| 型号 Type                                           |                    | D3W-1400-P15                                |
|---------------------------------------------------|--------------------|---------------------------------------------|
| 轴数 Axes                                           |                    | 3                                           |
| 最大负载 Payload                                      |                    | 15kg                                        |
| 机器人本体<br>Manipulator                              | 重量 Weight          | 127kg                                       |
|                                                   | 工作空间直径<br>Diameter | 1400mm                                      |
| 重复定位精度<br>repeatability                           | 位置 Position        | 0.05mm                                      |
|                                                   | 旋转 Rotation        | —                                           |
| 旋转范围 Rotation range                               |                    | —                                           |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |                    | —                                           |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up              | 29.9°                                       |
|                                                   | 下摆 Down            | 63.6°                                       |
| 输入电源<br>Power supply                              |                    | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |
| 电源容量<br>Power capacity                            |                    | 10KVA                                       |
| 额定功率<br>Rated Power                               |                    | 6kw                                         |
| 保存温度<br>Storage temperature                       |                    | -10°C~70°C                                  |
| 工作环境<br>Work environment                          |                    | -10°C~50°C, RH≤80%                          |
| 防护等级<br>Protection                                |                    | IP55                                        |

### ● 负载-频次 Load-Frequency

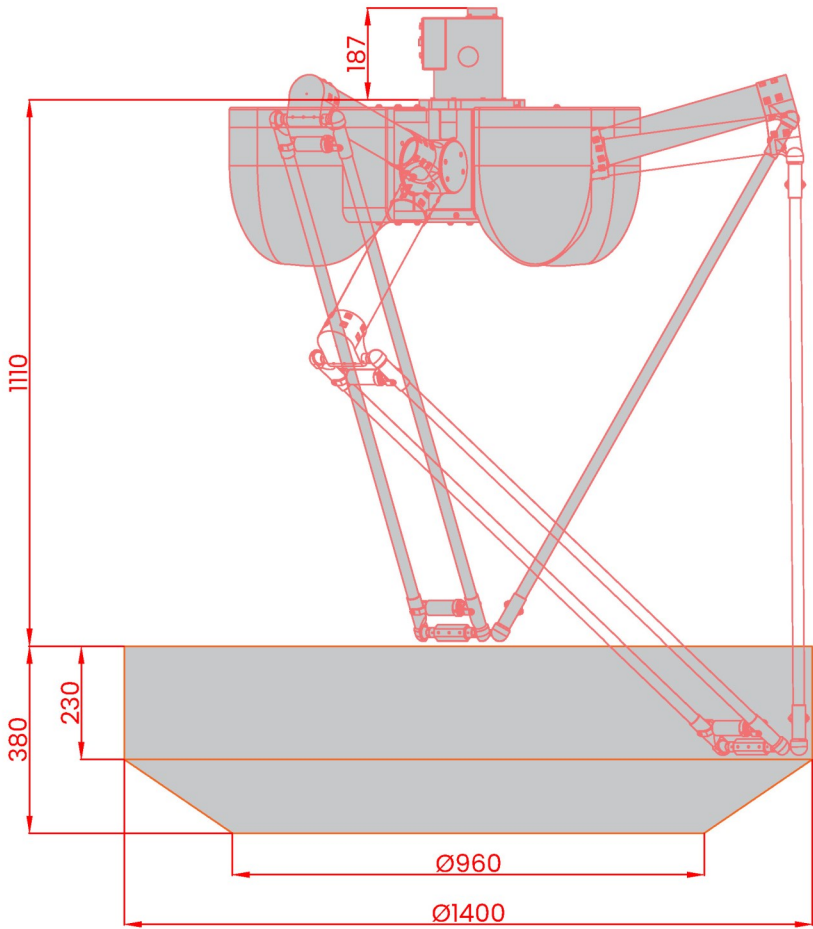


| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3 | P1 → P2 → P3 → P2 → P1           | h=25, b=305   |
| 轨迹4 Trajectory4 | P1 → P2 → P3 → P2 → P1           | h=25, b=500   |

特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。

外形尺寸及运动范围

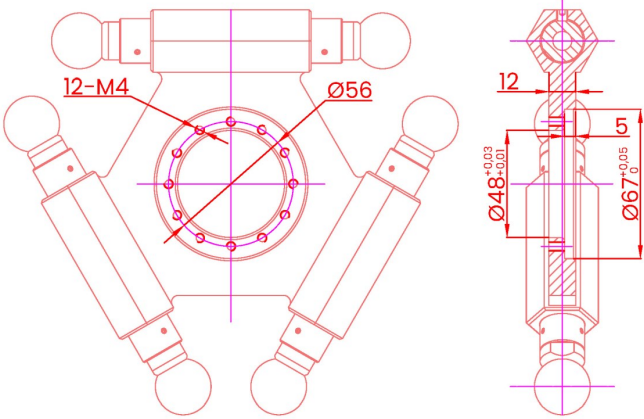
Outline dimensions and Working range (mm)



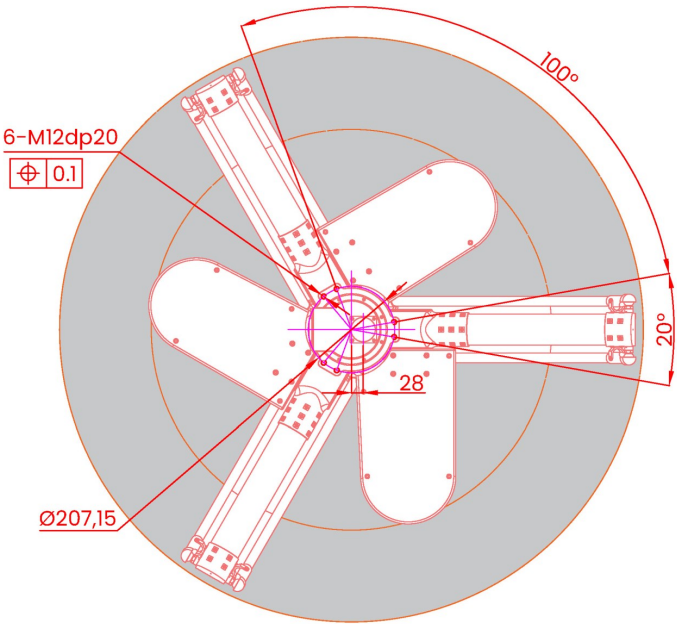
说明:  
图示下部加深部分为机器人动平台几何中心的运动范围,上部为圆柱空间,并在下部向内收敛。

Instruction:  
The bottom gray part is the workplace of the center point of moving platform, which is composed of a cylinder at the top and a circular truncated cone at the bottom.

法兰 Flange (mm)



基座安装 Base installation (mm)



## D3W-1600-P15



高稳定性  
大空间  
重负载  
经济实用

High stability  
Large space  
Heavy load  
Economic & Practical

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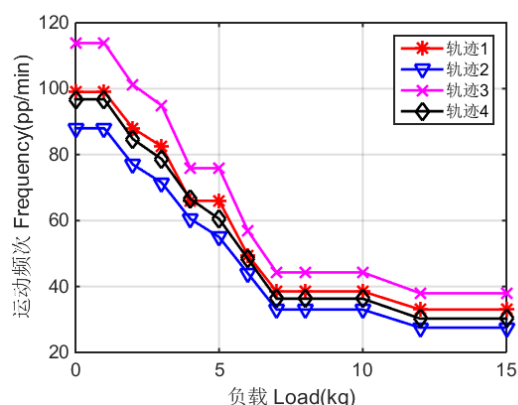
Advanced design of compression spring ,enables the parallel-arm to be used for a long time and be easily dis-mounted.

◆ 非常适于食品、医药等行业的高速生产作业, 主要用于较重型物料的装配、搬运、分拣等

The robot is ideal for high-speed production in food and medicine industry. Widely used in assembly, handling and pick-and-place of heavy materials.

| 型号 Type                                           |                    | D3W-1600-P15                                |
|---------------------------------------------------|--------------------|---------------------------------------------|
| 轴数 Axes                                           |                    | 3                                           |
| 最大负载 Payload                                      |                    | 15kg                                        |
| 机器人本体<br>Manipulator                              | 重量 Weight          | 133kg                                       |
|                                                   | 工作空间直径<br>Diameter | 1600mm                                      |
| 重复定位精度<br>repeatability                           | 位置 Position        | 0.05mm                                      |
|                                                   | 旋转 Rotation        | —                                           |
| 旋转范围 Rotation range                               |                    | —                                           |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |                    | —                                           |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up              | 23°                                         |
|                                                   | 下摆 Down            | 71.5°                                       |
| 输入电源<br>Power supply                              |                    | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |
| 电源容量<br>Power capacity                            |                    | 10KVA                                       |
| 额定功率<br>Rated Power                               |                    | 6kw                                         |
| 保存温度<br>Storage temperature                       |                    | -10°C~70°C                                  |
| 工作环境<br>Work environment                          |                    | -10°C~50°C, RH≤80%                          |
| 防护等级<br>Protection                                |                    | IP55                                        |

● 负载-频次 Load-Frequency

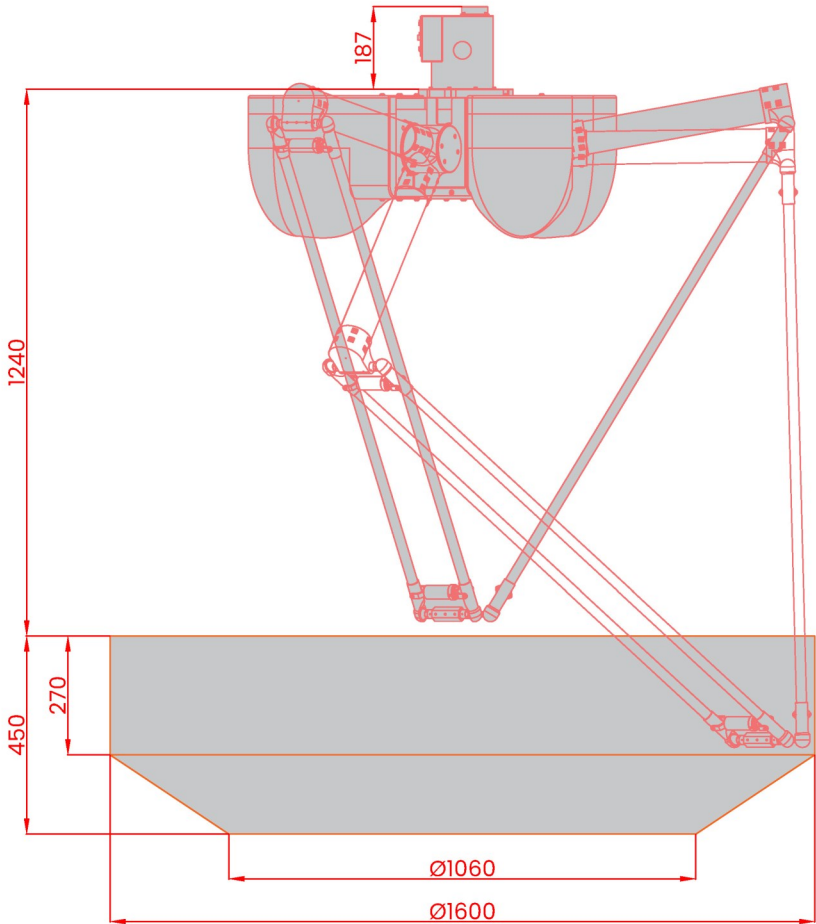


| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3 | P1 → P2 → P3 → P2 → P1           | h=25, b=305   |
| 轨迹4 Trajectory4 | P1 → P2 → P3 → P2 → P1           | h=25, b=500   |

特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。

外形尺寸及运动范围

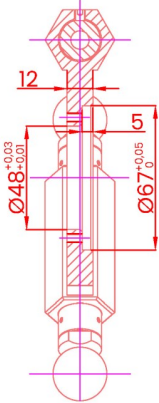
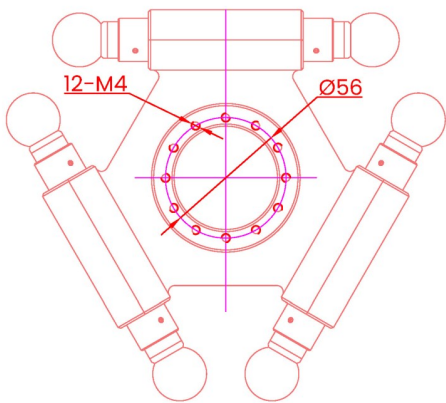
Outline dimensions and Working range (mm)



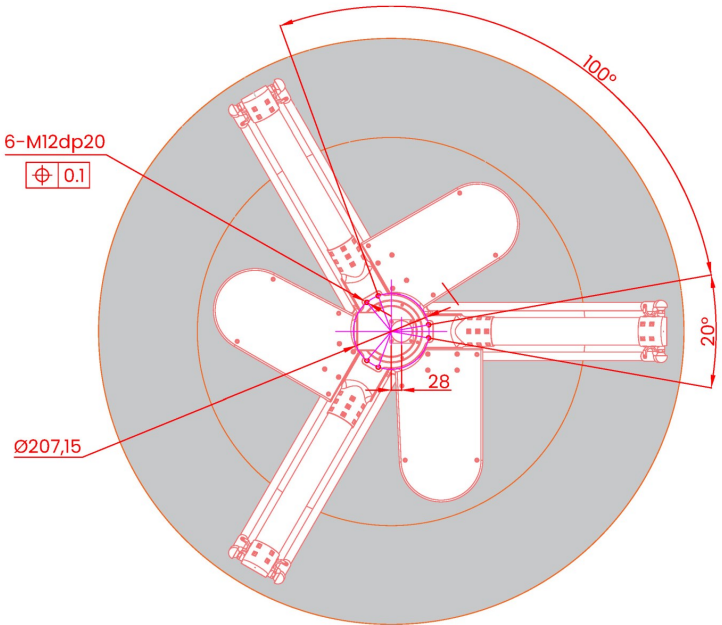
说明:  
图示下部加深部分为机器人动平台几何中心的运动范围, 上部为圆柱空间, 并在下部向内收敛。

Instruction:  
The bottom gray part is the workplace of the center point of moving platform, which is composed of a cylinder at the top and a circular truncated cone at the bottom.

法兰 Flange (mm)



基座安装 Base installation (mm)





## D3W-1200-P25



高稳定性  
大空间  
超重负载

High stability  
Large space  
Super-heavy load

- ◆ 标准循环时间小于0.67s,满足追求最高负载和最经济需求

The standard cycle time is less than 0.67s, meeting your pursuit for the maximum load and economic.

- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

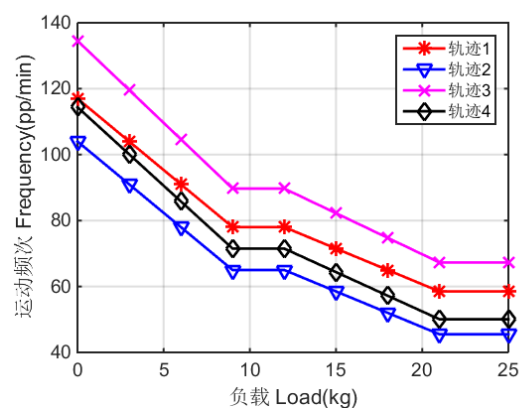
Advanced design of compression spring ,enables the parallel-arm to be used for a long time and be easily dis-mounted.

- ◆ 非常适于食品、医药等行业的高速生产作业, 主要用于较重型物料的装配、搬运、分拣等

The robot is ideal for high-speed production in food and medicine industry. Widely used in assembly, handling and pick-and-place of heavy materials.

| 型号 Type                                           |                    | D3W-1200-P25                                |
|---------------------------------------------------|--------------------|---------------------------------------------|
| 轴数 Axes                                           |                    | 3                                           |
| 最大负载 Payload                                      |                    | 25kg                                        |
| 机器人本体<br>Manipulator                              | 重量 Weight          | 143kg                                       |
|                                                   | 工作空间直径<br>Diameter | 1200mm                                      |
| 重复定位精度<br>repeatability                           | 位置 Position        | 0.05mm                                      |
|                                                   | 旋转 Rotation        | —                                           |
| 旋转范围 Rotation range                               |                    | —                                           |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |                    | —                                           |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up              | 33.8°                                       |
|                                                   | 下摆 Down            | 87.8°                                       |
| 输入电源<br>Power supply                              |                    | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |
| 电源容量<br>Power capacity                            |                    | 15KVA                                       |
| 额定功率<br>Rated Power                               |                    | 9kw                                         |
| 保存温度<br>Storage temperature                       |                    | -10°C~70°C                                  |
| 工作环境<br>Work environment                          |                    | -10°C~50°C, RH≤80%                          |
| 防护等级<br>Protection                                |                    | IP55                                        |

### ● 负载-频次 Load-Frequency

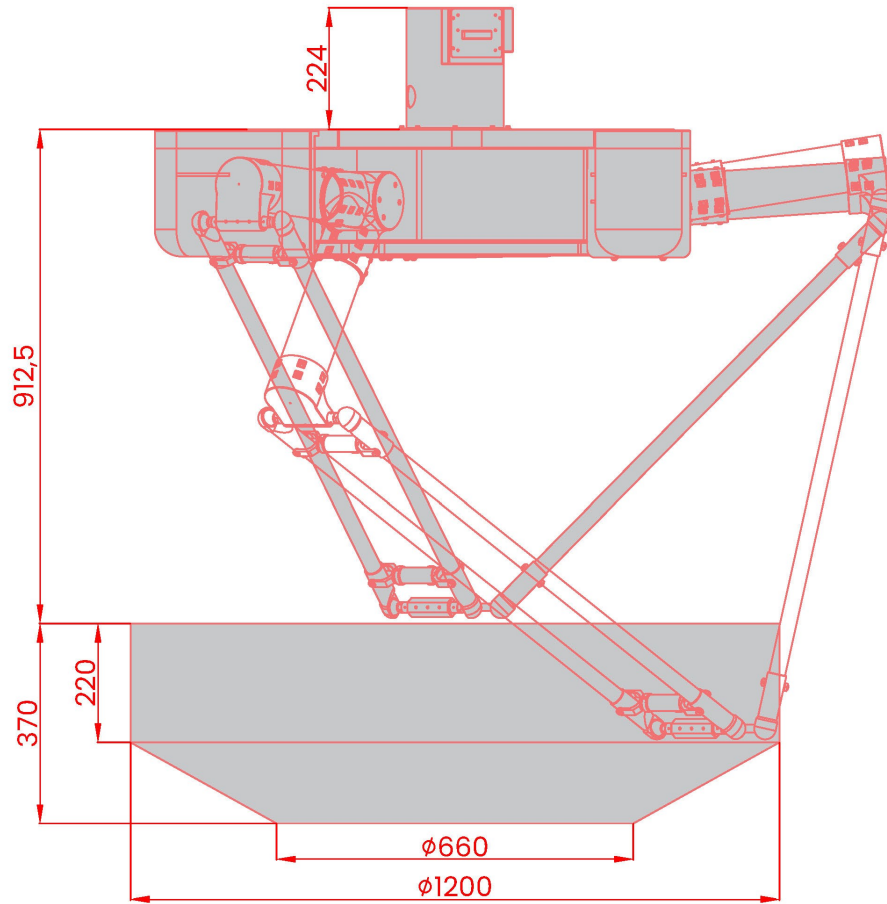


| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3 | P1 → P2 → P3 → P2 → P1           | h=25, b=305   |
| 轨迹4 Trajectory4 | P1 → P2 → P3 → P2 → P1           | h=25, b=500   |

特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。

# 外形尺寸及运动范围

## Outline dimensions and Working range (mm)



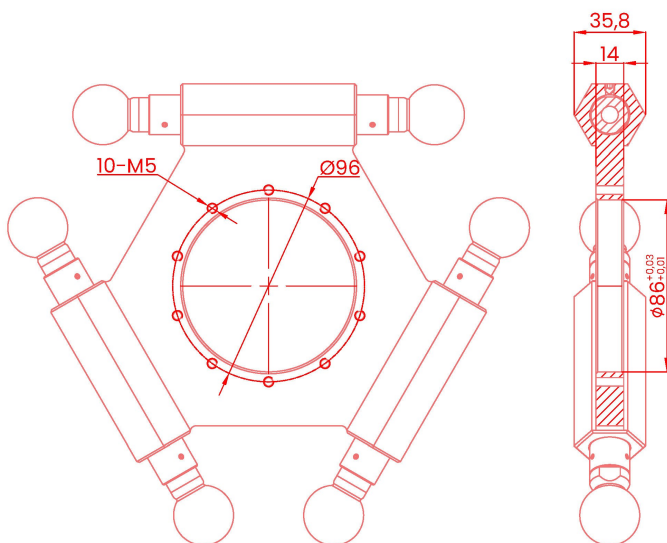
### 说明:

图示下部加深部分为机器人动平台几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

### Instruction:

The bottom gray part is the work-place of the center point of moving platform, which is composed of a cylinder at the top and a circular truncated cone at the bottom.

## 法兰 Flange (mm)



## 基座安装 Base installation (mm)

