

并联机器人

选型手册

Parallel Robot Selection Manual

D3P



● 型号和符号

D3P	1100	P3	A1	E1	FXGX
机型	型号	负载	控制器类型	控制柜类型	视觉
D3P	800	P3: 3kg P5: 5kg P8: 8kg	A1: ATOMCONTROL A2: KEBA CONTROL	E1: ATOM-01 E2: ATOM-02 E3: 定制	F0G0: 无视觉 FXGX: 有视觉
	1100				
	1300				
	1400				
	1600				

● Model and Symbol

D3P	1100	P3	A1	E1	FXGX
Robot type	Type	Load Type	Control Type	Control Cabinet	Vision Type
D3P	800	P3: 3kg P5: 5kg P8: 8kg	A1: ATOMCONTROL A2: KEBA CONTROL	E1: ATOM-01 E2: ATOM-02 E3: Custom	F0G0: Without vision FXGX: With vision
	1100				
	1300				
	1400				
	1600				

D3P-800-P3



高速度
高精度
高稳定性
低高度

High speed
High precision
High stability
Lower height

- ◆ 标准循环时间小于0.45s,满足追求最高速度和最小体积需求

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

- ◆ 特殊旋转轴铰链设计, 轻松应对高强度高频次重复运动需求

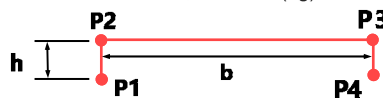
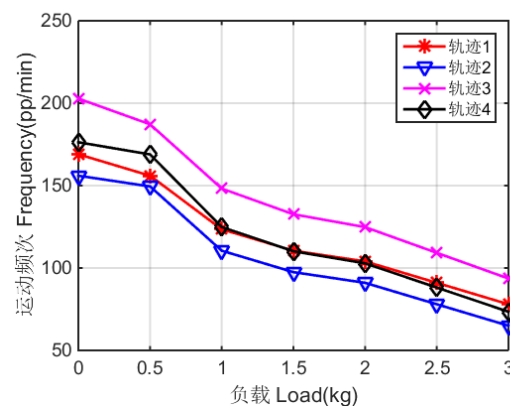
Advanced design of Hooke joint in the rotational axis, enables the robot to easily cope with the high-intensity repetitive operation.

- ◆ 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

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型号 Type		D3P-800-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	88.8kg
	工作空间直径 Diameter	800mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.1°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.16kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	30.2°
	下摆 Down	63.6°
输入电源 Power supply		三相 Three-phase 380VAC -10%~+10%, 49~61HZ
电源容量 Power capacity		6KVA
额定功率 Rated Power		2.35kw
保存温度 Storage temperature		-10°C~70°C
工作环境 Work environment		-10°C~50°C, RH≤80%
防护等级 Protection		IP55

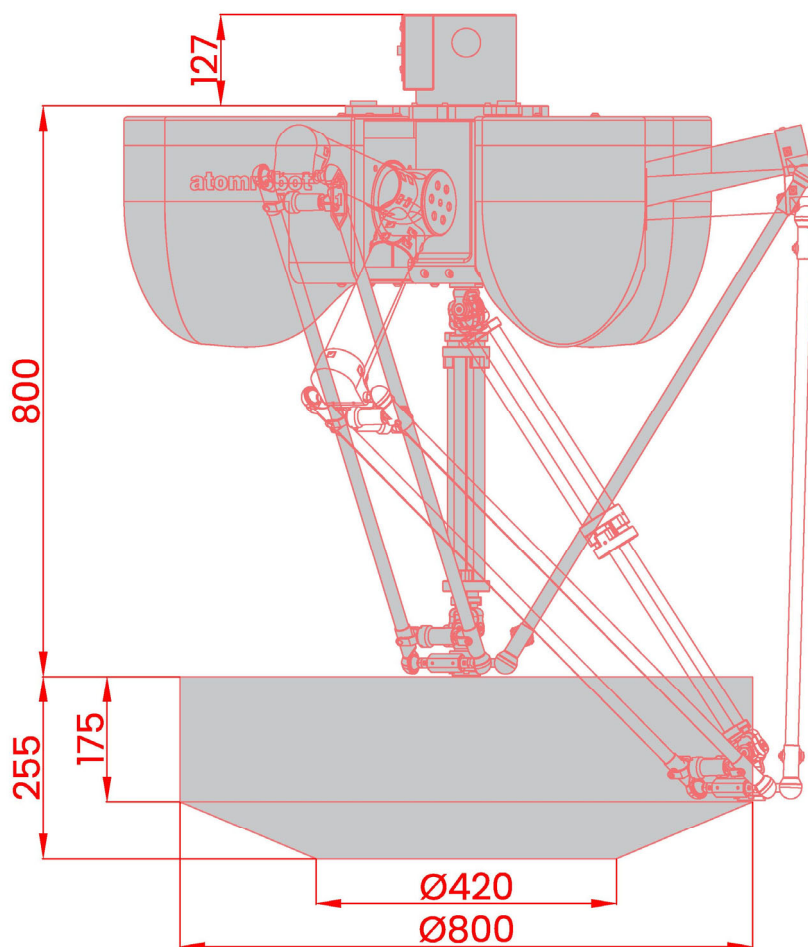
● 负载-频次 Load-Frequency



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)



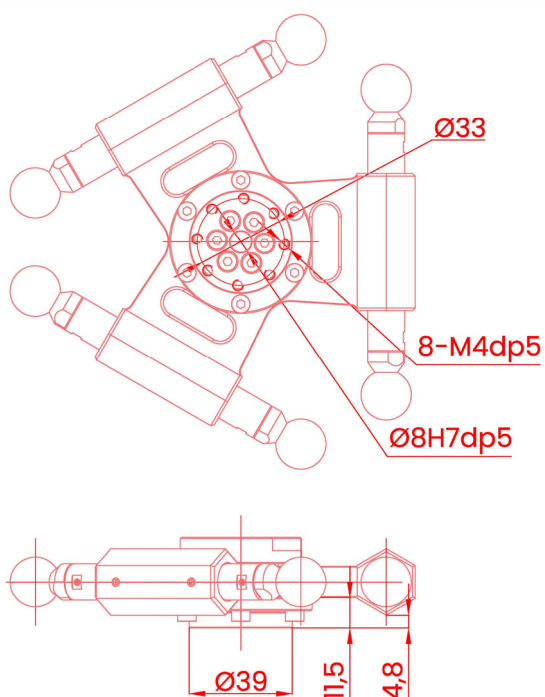
说明:

图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

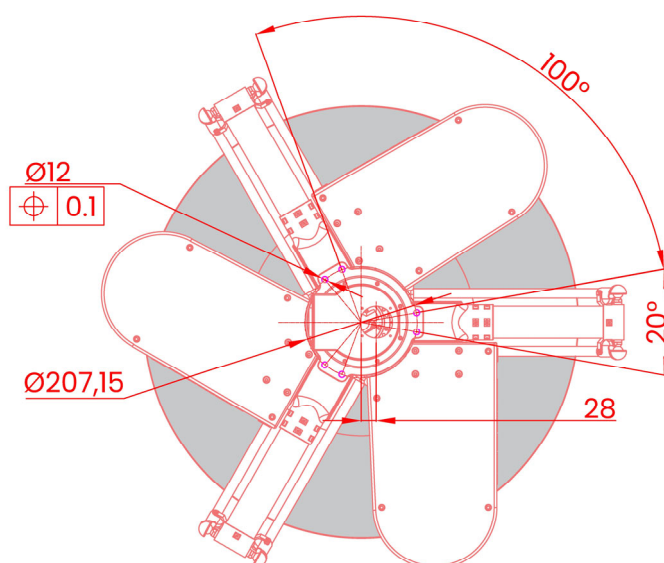
Instruction:

The bottom gray part is the workplace of bottom surface's center point of the end, 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)



D3P-1100-P3



高速度
高稳定性
大空间
经济实用

High speed
High stability
Large space
Economic & Practical

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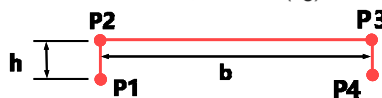
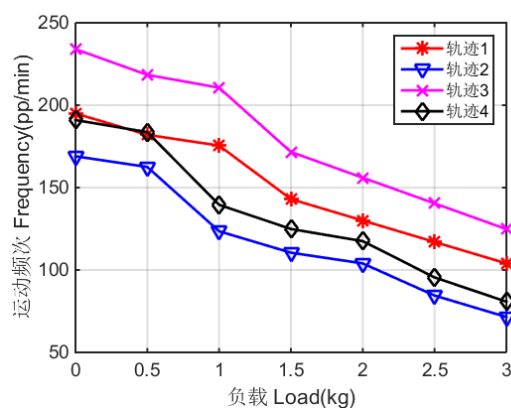
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型号 Type		D3P-1100-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	90.5kg
	工作空间直径 Diameter	1100mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.1°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.16kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	24.5°
	下摆 Down	73.5°
输入电源 Power supply		三相 Three-phase 380VAC -10%~+10%, 49~61HZ
电源容量 Power capacity		10KVA
额定功率 Rated Power		6.1kw
保存温度 Storage temperature		-10°C~70°C
工作环境 Work environment		-10°C~50°C, RH≤80%
防护等级 Protection		IP55

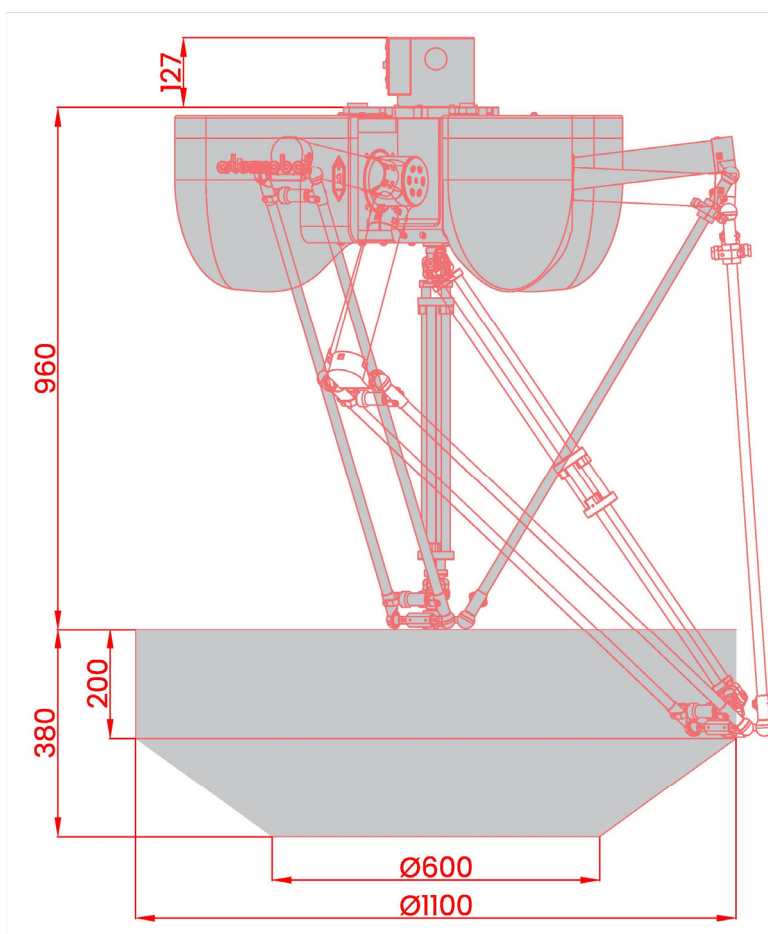
● 负载-频次 Load-Frequency



名称 Name	循环模式 Model	运动距离 Distance
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轨迹3 Trajectory3	P1→P2→P3→P2→P1	h=25, b=305
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外形尺寸及运动范围 Outline dimensions and Working range (mm)



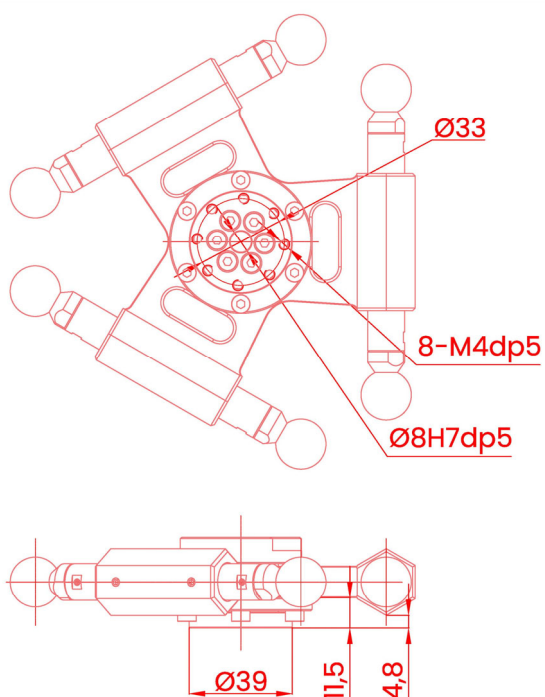
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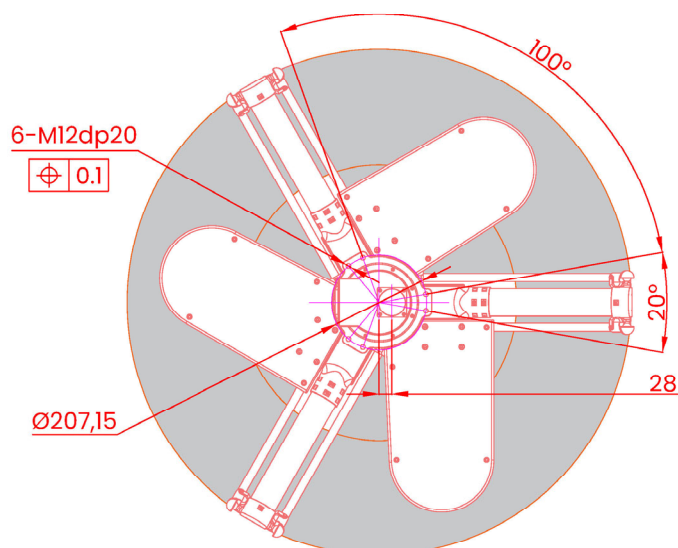
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法兰 Flange (mm)



基座安装 Base installation (mm)



D3P-1300-P3



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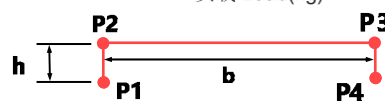
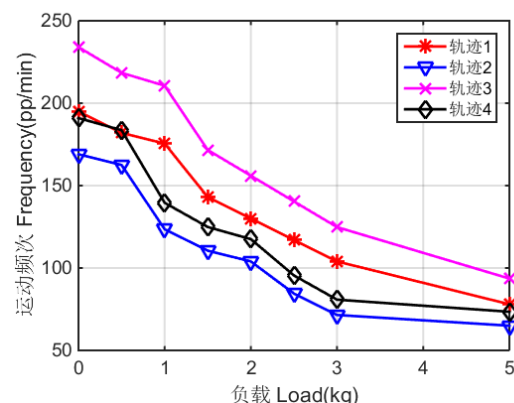
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型号 Type		D3P-1300-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	93.5kg
	工作空间直径 Diameter	1300mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.1°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.16kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	24.6°
	下摆 Down	78.5°
输入电源 Power supply		三相 Three-phase 380VAC -10%~+10%, 49~61HZ
电源容量 Power capacity		10KVA
额定功率 Rated Power		6.1kw
保存温度 Storage temperature		-10°C~70°C
工作环境 Work environment		-10°C~50°C, RH≤80%
防护等级 Protection		IP55

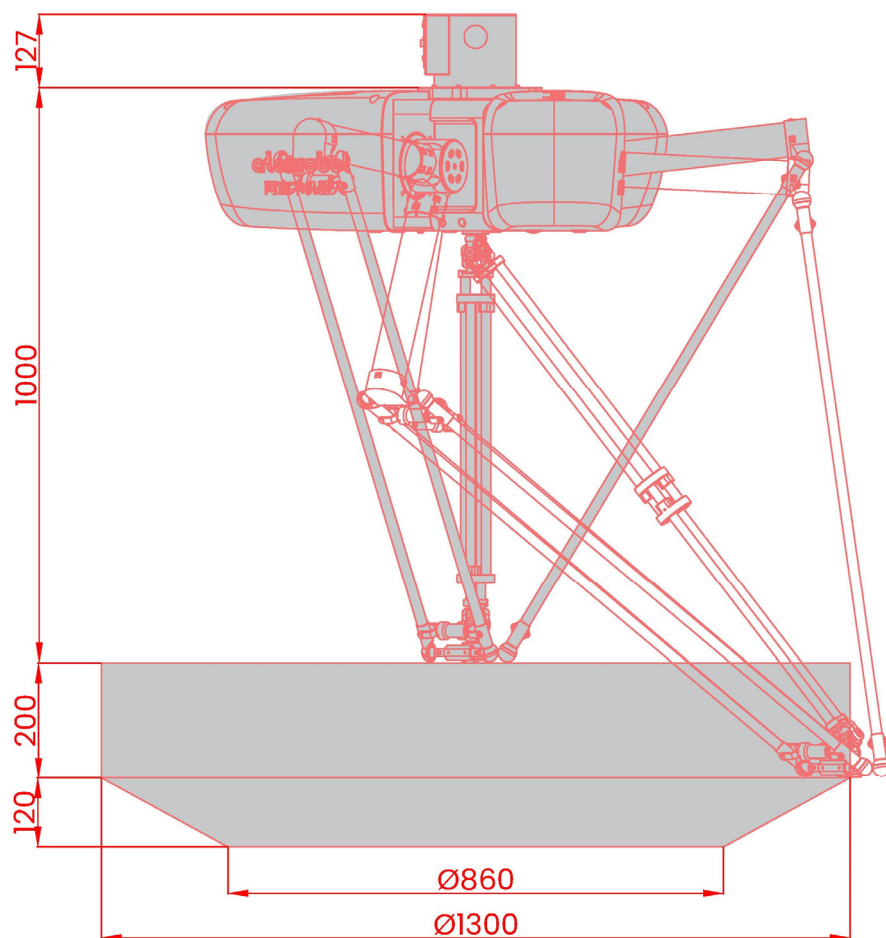
● 负载-频次 Load-Frequency



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



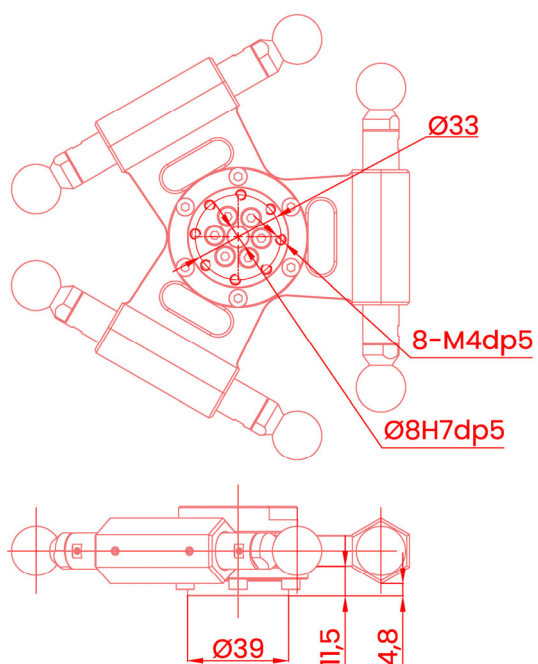
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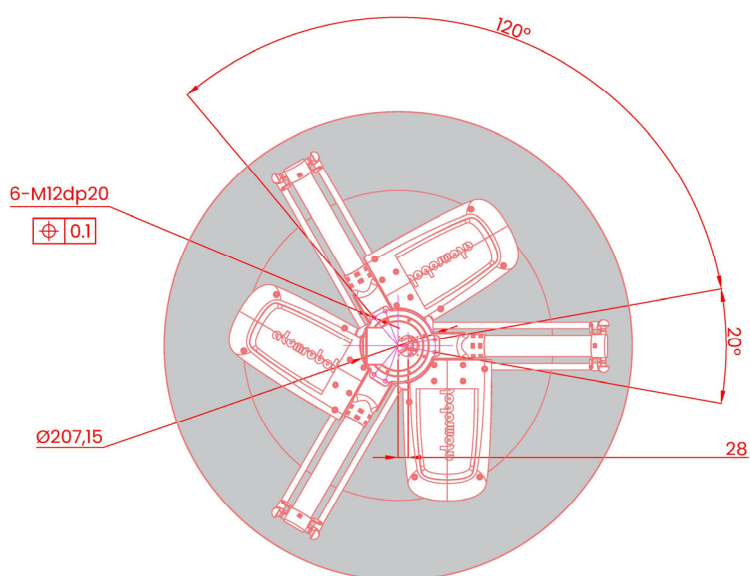
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法兰 Flange (mm)



基座安装 Base installation (mm)



D3P-1400-P3



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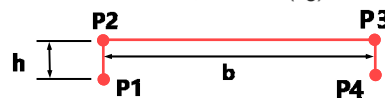
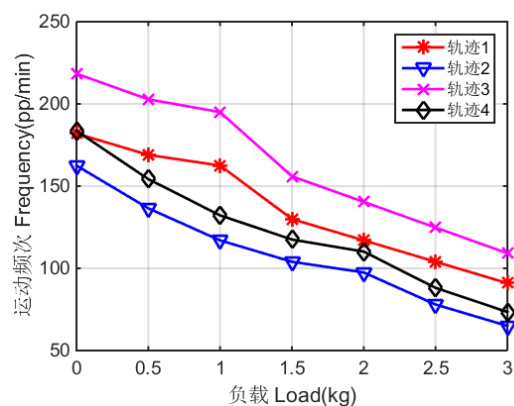
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型号 Type		D3P-1400-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	96.5kg
	工作空间直径 Diameter	1400mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.1°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.16kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	28°
	下摆 Down	73°
输入电源 Power supply		三相 Three-phase 380VAC -10%~+10%, 49~61HZ
电源容量 Power capacity		10KVA
额定功率 Rated Power		6.1kw
保存温度 Storage temperature		-10°C~70°C
工作环境 Work environment		-10°C~50°C, RH≤80%
防护等级 Protection		IP55

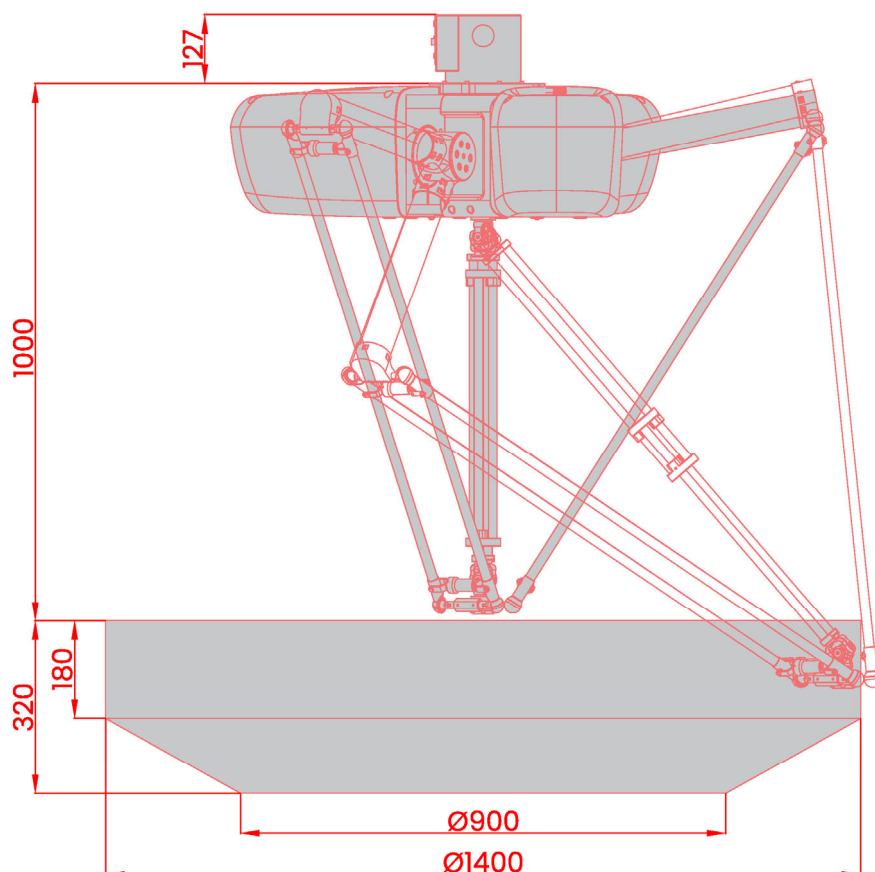
● 负载-频次 Load-Frequency



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



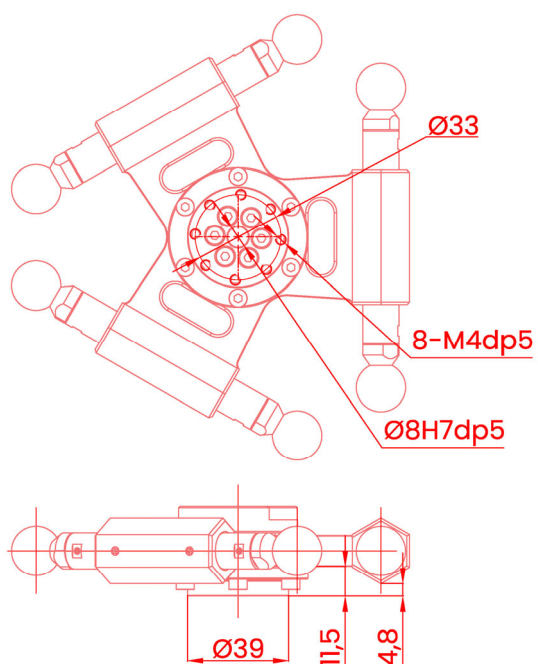
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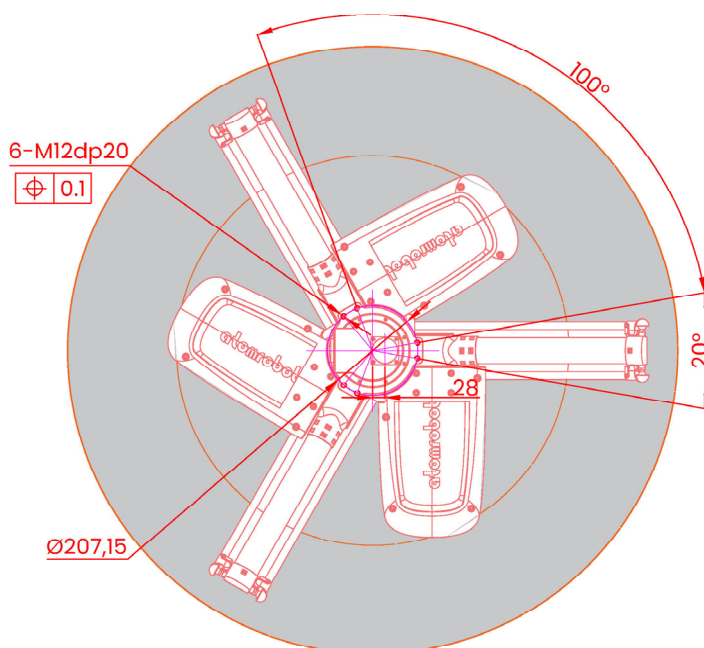
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法兰 Flange (mm)



基座安装 Base installation (mm)



D3P-1600-P3



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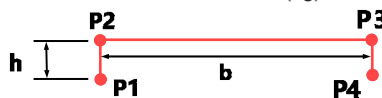
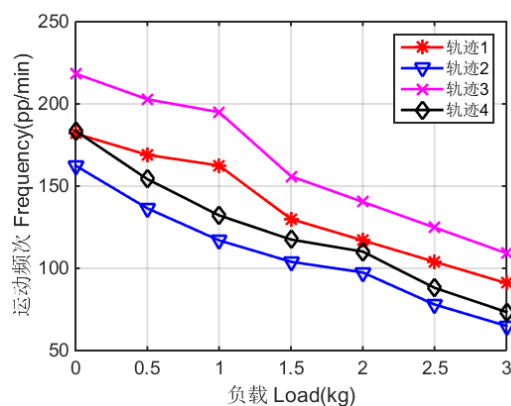
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轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	96.8kg
	工作空间直径 Diameter	1600mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.1°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.16kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	28°
	下摆 Down	73°
输入电源 Power supply		三相 Three-phase 380VAC -10%~+10%, 49~61HZ
电源容量 Power capacity		10KVA
额定功率 Rated Power		6.1kw
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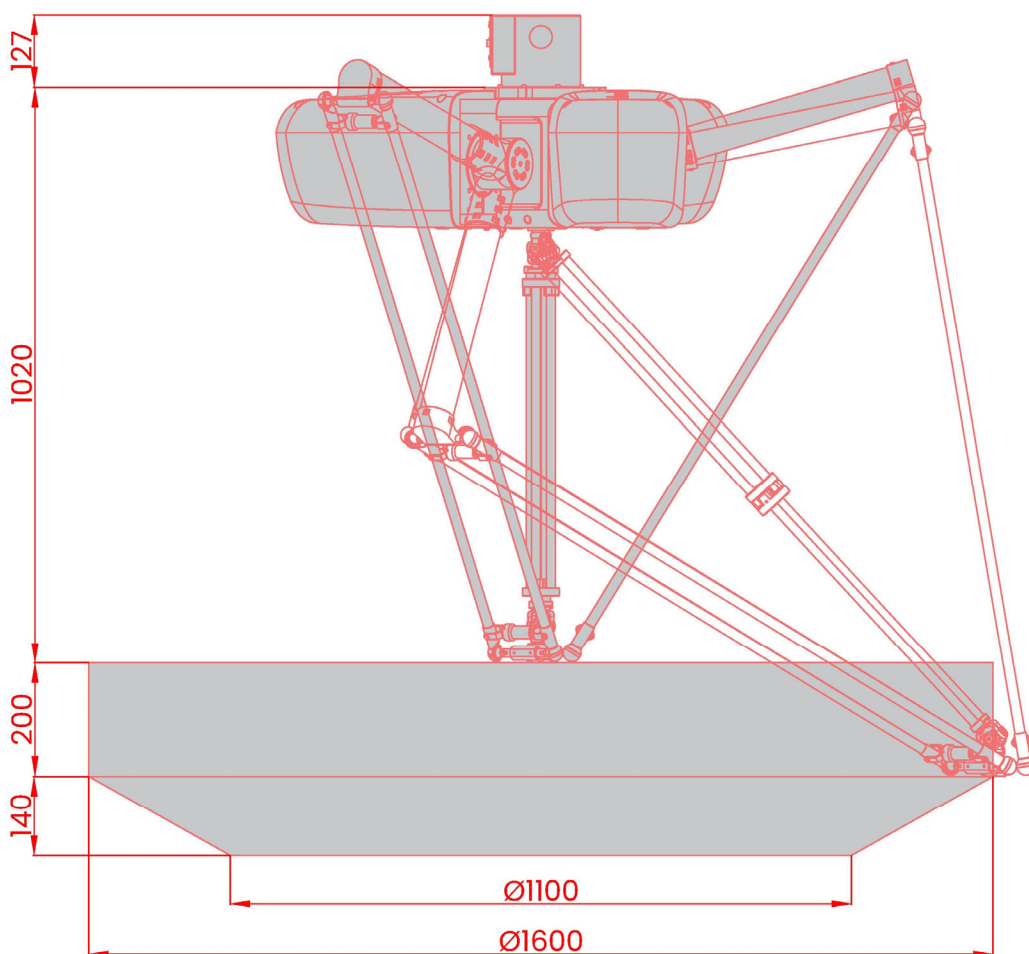
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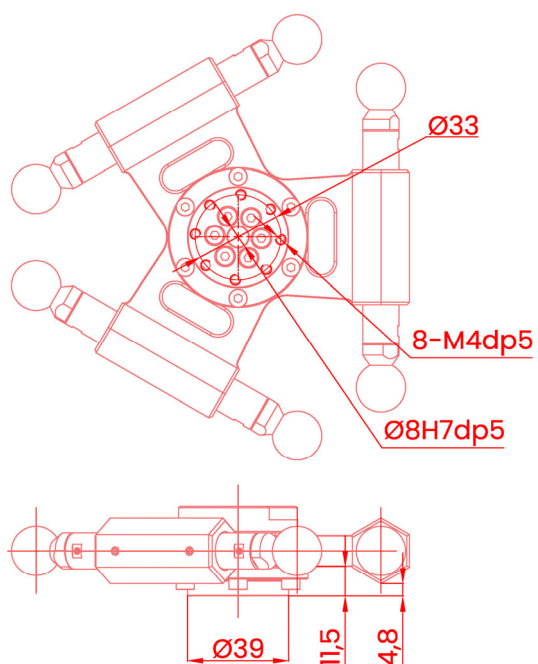
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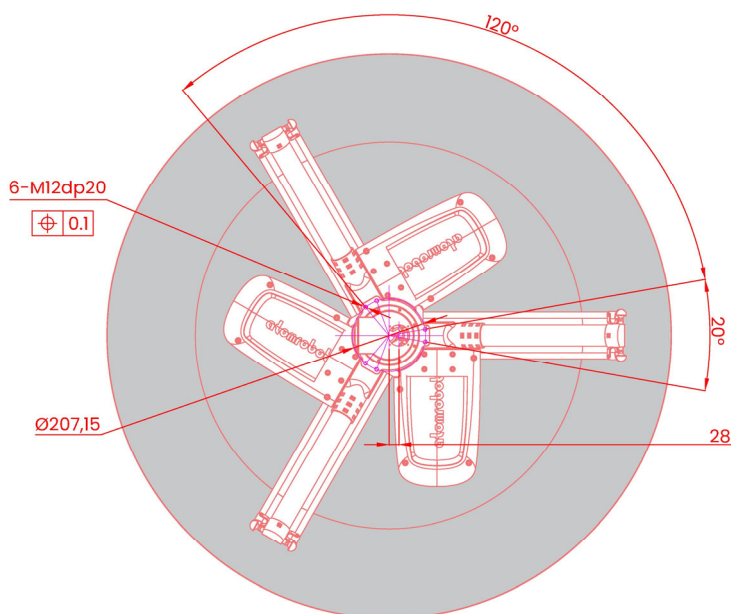
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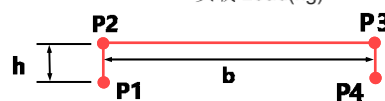
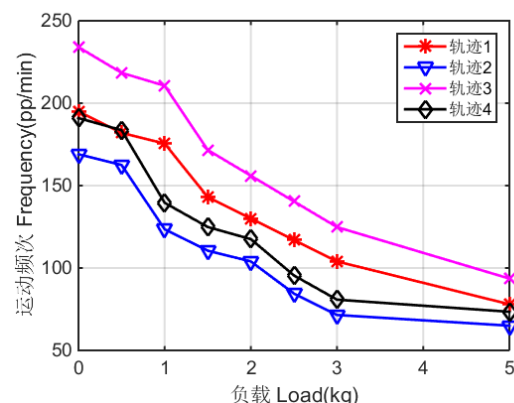
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轴数 Axes		3+1
最大负载 Payload		5kg
机器人本体 Manipulator	重量 Weight	104kg
	工作空间直径 Diameter	1100mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.1°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.3kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	27.5°
	下摆 Down	70°
输入电源 Power supply		三相 Three-phase 380VAC -10%~+10%, 49~61HZ
电源容量 Power capacity		10KVA
额定功率 Rated Power		6.4kw
保存温度 Storage temperature		-10°C~70°C
工作环境 Work environment		-10°C~50°C, RH≤80%
防护等级 Protection		IP55

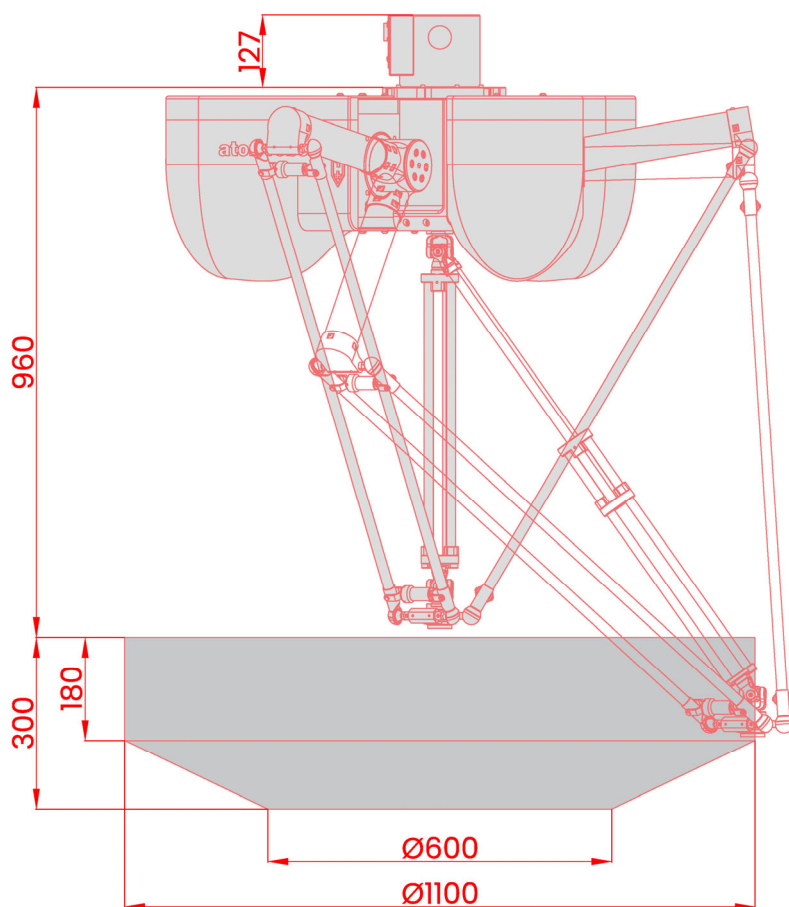
● 负载-频次 Load-Frequency



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)



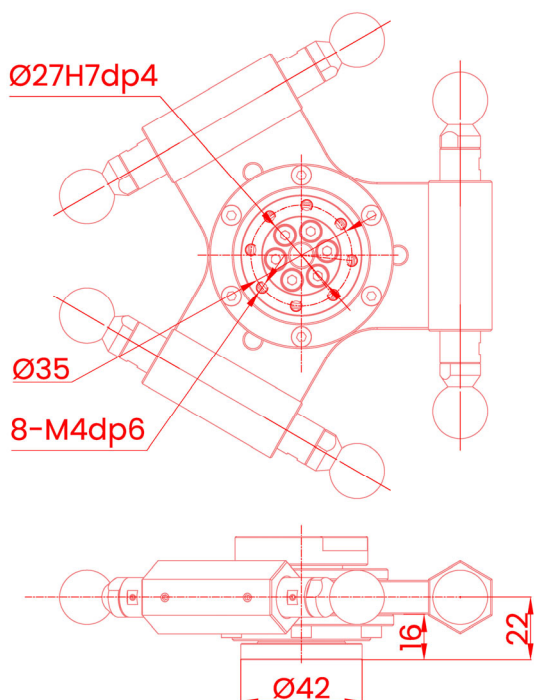
说明:

图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

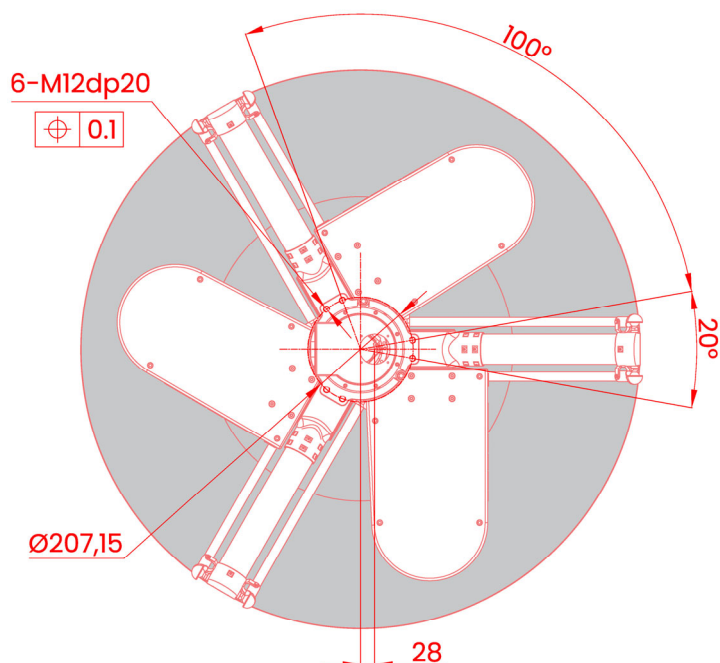
Instruction:

The bottom gray part is the workplace of bottom surface 's center point of the end, 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)



D3P-1300-P5



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.

◆ 特殊旋转轴铰链设计, 轻松应对高强度高频次重复运动需求

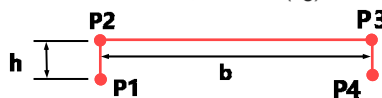
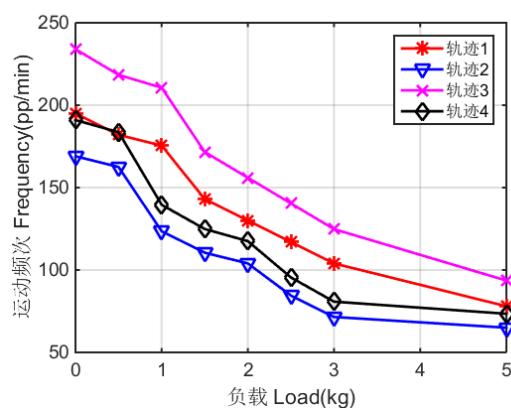
Advanced design of Hooke joint in the rotational axis, enables the robot to easily cope with the high-intensity repetitive operation.

◆ 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		D3P-1300-P5
轴数 Axes		3+1
最大负载 Payload		5kg
机器人本体 Manipulator	重量 Weight	111kg
	工作空间直径 Diameter	1300mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.1°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.3kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	27°
	下摆 Down	76°
输入电源 Power supply		三相 Three-phase 380VAC -10%~+10%, 49~61HZ
电源容量 Power capacity		10KVA
额定功率 Rated Power		6.4kw
保存温度 Storage temperature		-10°C~70°C
工作环境 Work environment		-10°C~50°C, RH≤80%
防护等级 Protection		IP55

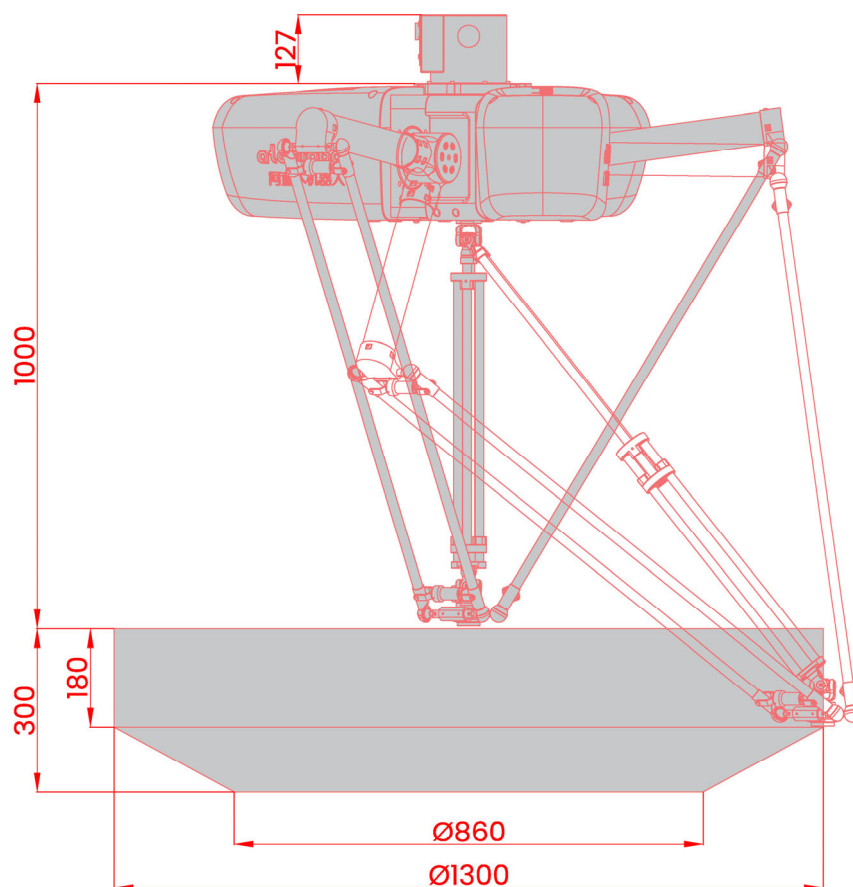
● 负载-频次 Load-Frequency



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)



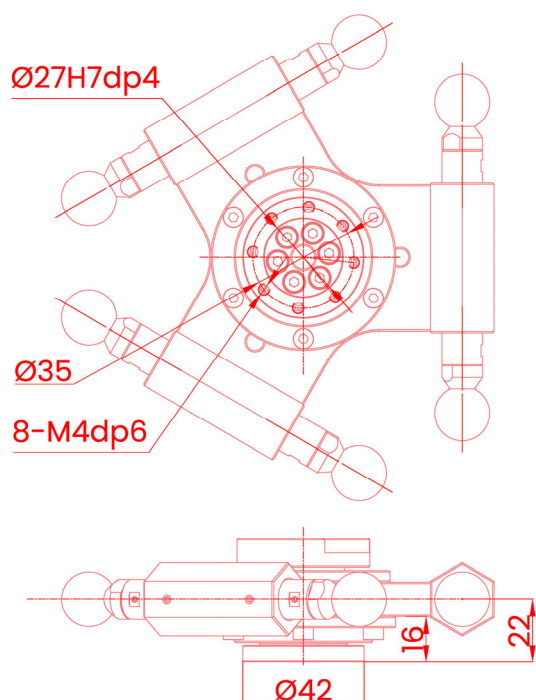
说明:

图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

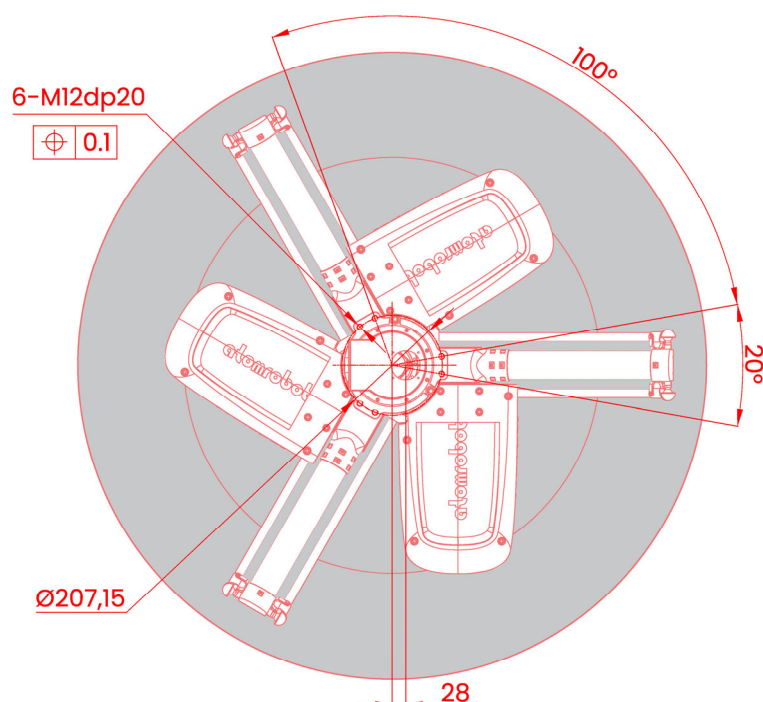
Instruction:

The bottom gray part is the workplace of bottom surface 's center point of the end, 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)



D3P-1600-P5



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.

◆ 特殊旋转轴铰链设计, 轻松应对高强度高频次重复运动需求

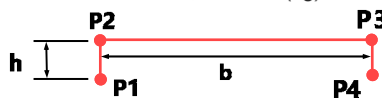
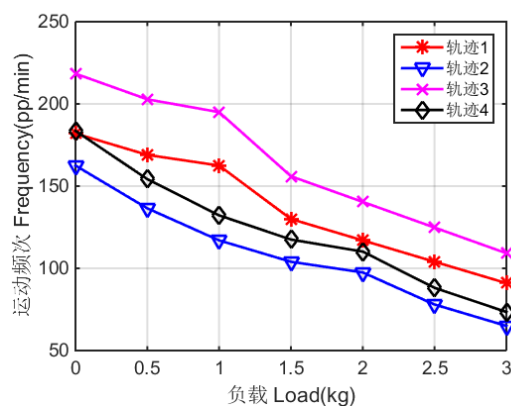
Advanced design of Hooke joint in the rotational axis, enables the robot to easily cope with the high-intensity repetitive operation.

◆ 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		D3P-1600-P5
轴数 Axes		3+1
最大负载 Payload		5kg
机器人本体 Manipulator	重量 Weight	97.8kg
	工作空间直径 Diameter	1600mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.1°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.3kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	28°
	下摆 Down	73°
输入电源 Power supply		三相 Three-phase 380VAC -10%~+10%, 49~61HZ
电源容量 Power capacity		10KVA
额定功率 Rated Power		6.4kw
保存温度 Storage temperature		-10°C~70°C
工作环境 Work environment		-10°C~50°C, RH≤80%
防护等级 Protection		IP55

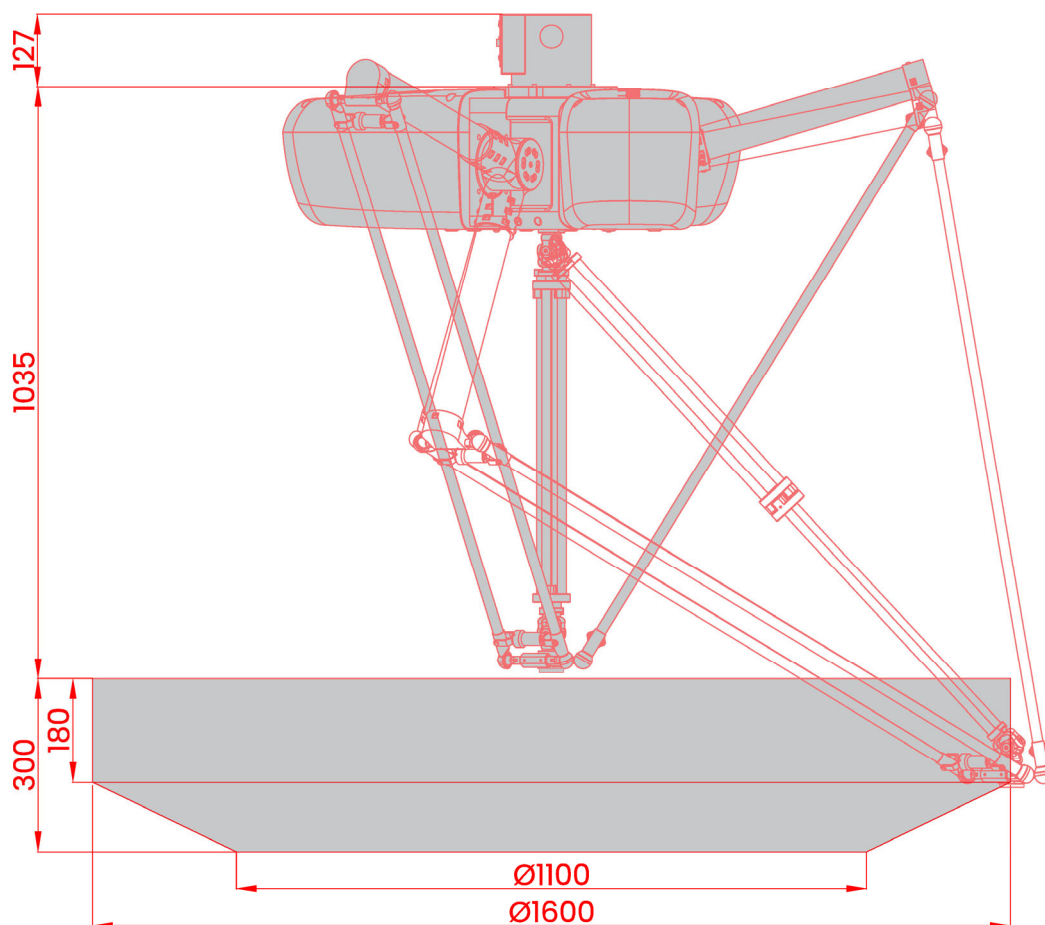
● 负载-频次 Load-Frequency



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)



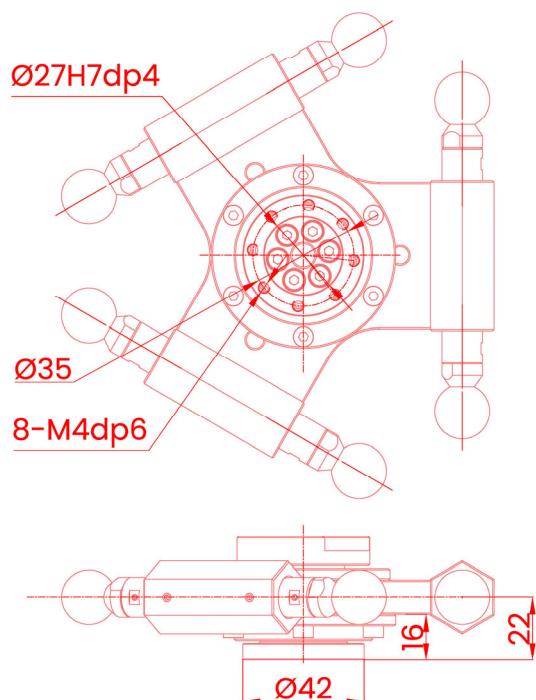
说明:

图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

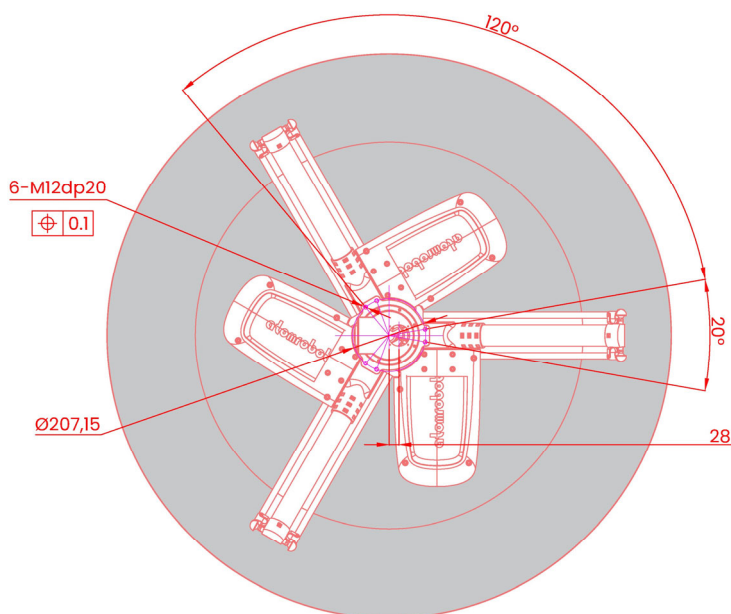
Instruction:

The bottom gray part is the workplace of bottom surface's center point of the end, 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)



D3P-1100-P8



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.

◆ 特殊旋转轴铰链设计, 轻松应对高强度高频次重复运动需求

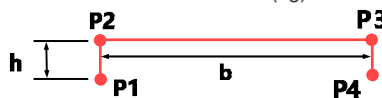
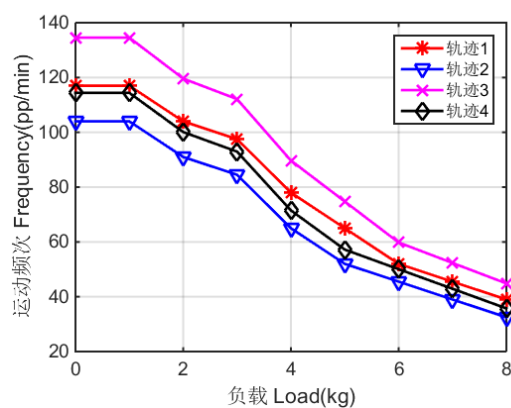
Advanced design of Hooke joint in the rotational axis, enables the robot to easily cope with the high-intensity repetitive operation.

◆ 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		D3P-1100-P8
轴数 Axes		3+1
最大负载 Payload		8kg
机器人本体 Manipulator	重量 Weight	128kg
	工作空间直径 Diameter	1100mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.1°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.3kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	29.5°
	下摆 Down	70°
输入电源 Power supply		三相 Three-phase 380VAC -10%~+10%, 49~61HZ
电源容量 Power capacity		10KVA
额定功率 Rated Power		6.4kw
保存温度 Storage temperature		-10°C~70°C
工作环境 Work environment		-10°C~50°C, RH≤80%
防护等级 Protection		IP55

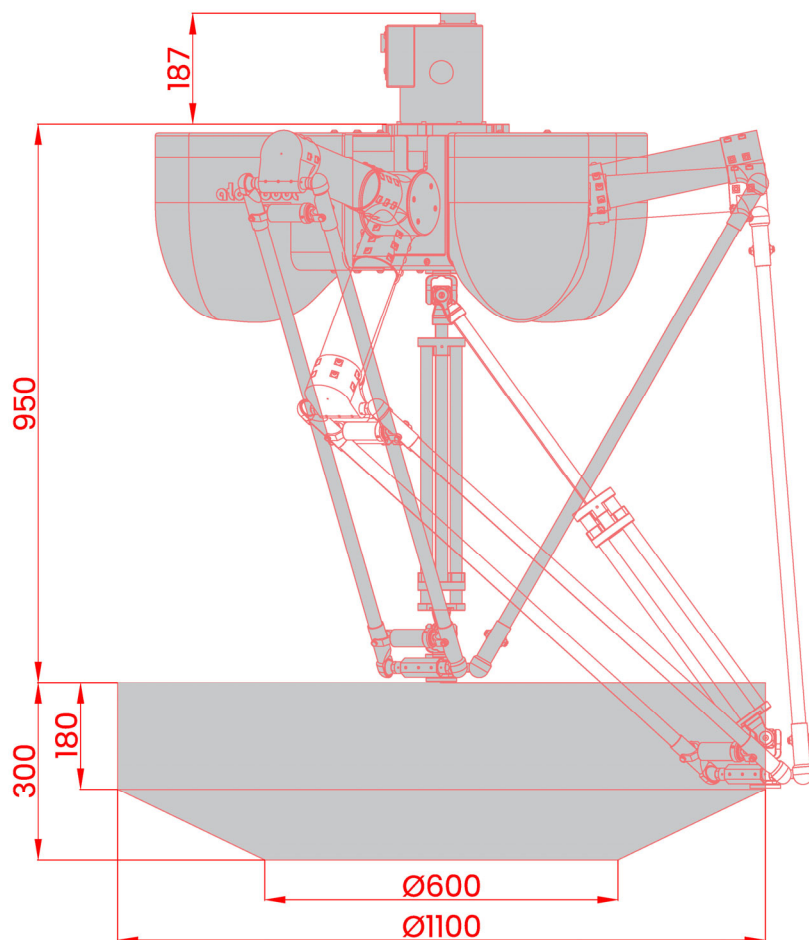
● 负载-频次 Load-Frequency



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)



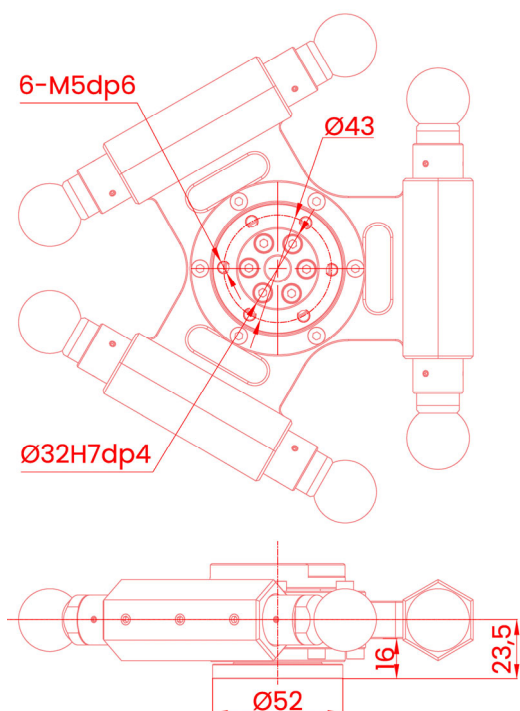
说明:

图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

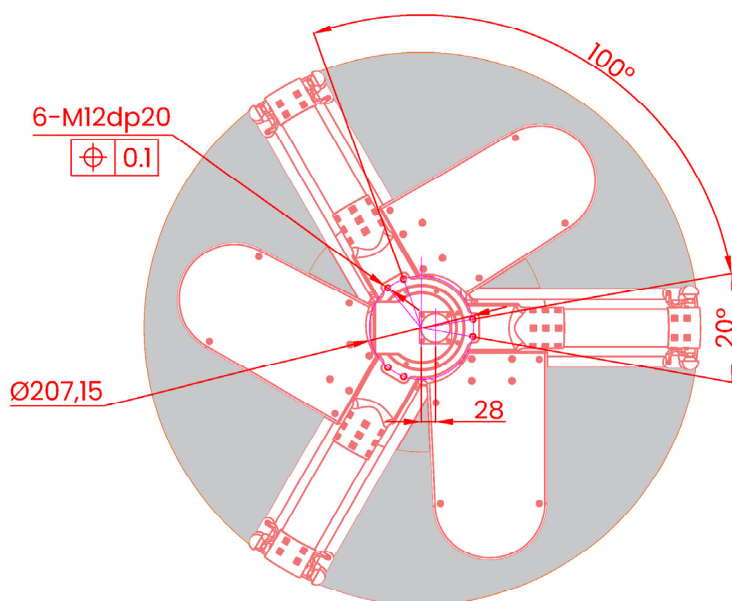
Instruction:

The bottom gray part is the workplace of bottom surface 's center point of the end, 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)



D3P-1400-P8



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大空间需求

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

- ◆ 特殊旋转轴铰链设计, 轻松应对高强度高频次重复运动需求

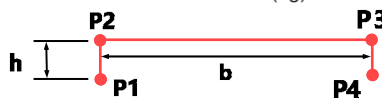
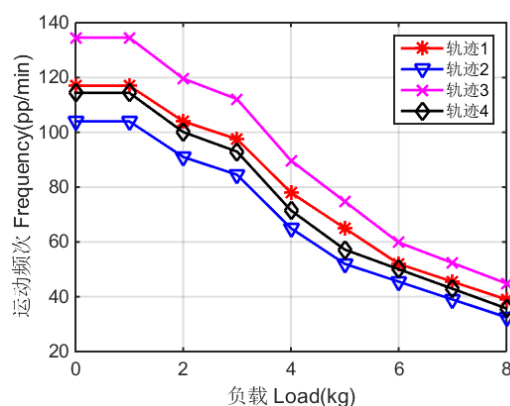
Advanced design of Hooke joint in the rotational axis, enables the robot to easily cope with the high-intensity repetitive operation.

- ◆ 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		D3P-1400-P8
轴数 Axes		3+1
最大负载 Payload		8kg
机器人本体 Manipulator	重量 Weight	135kg
	工作空间直径 Diameter	1400mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.1°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.3kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	30°
	下摆 Down	66°
输入电源 Power supply		三相 Three-phase 380VAC -10%~+10%, 49~61HZ
电源容量 Power capacity		10KVA
额定功率 Rated Power		6.4kw
保存温度 Storage temperature		-10°C~70°C
工作环境 Work environment		-10°C~50°C, RH≤80%
防护等级 Protection		IP55

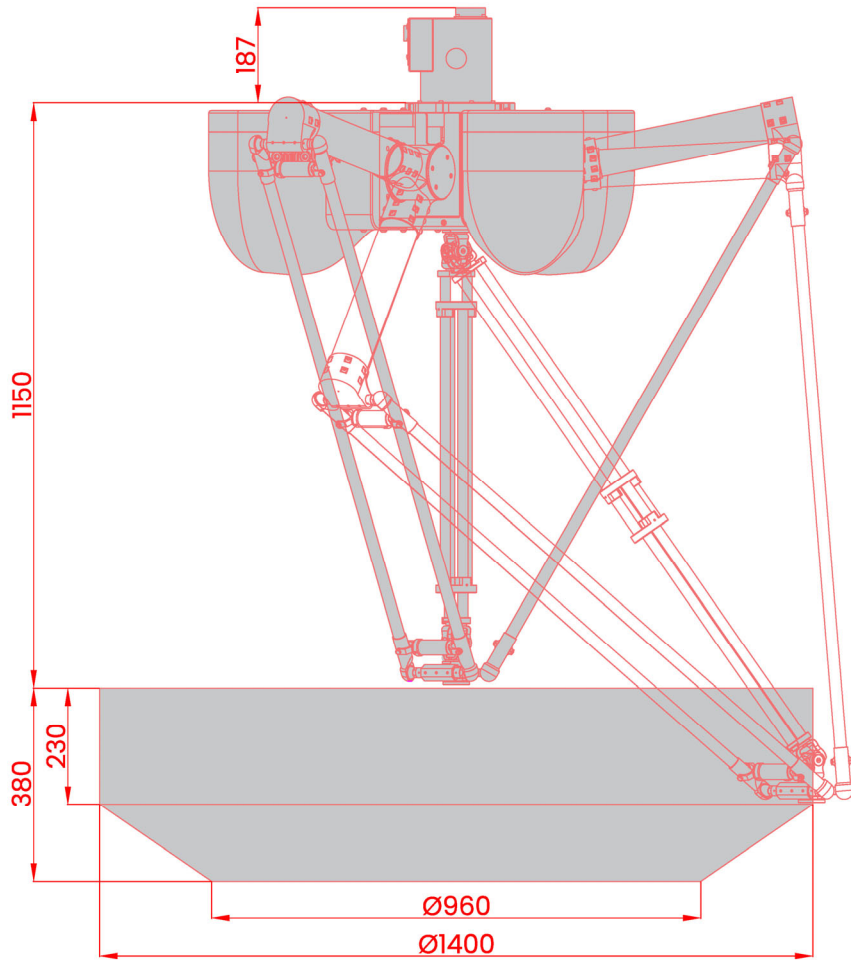
● 负载-频次 Load-Frequency



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。

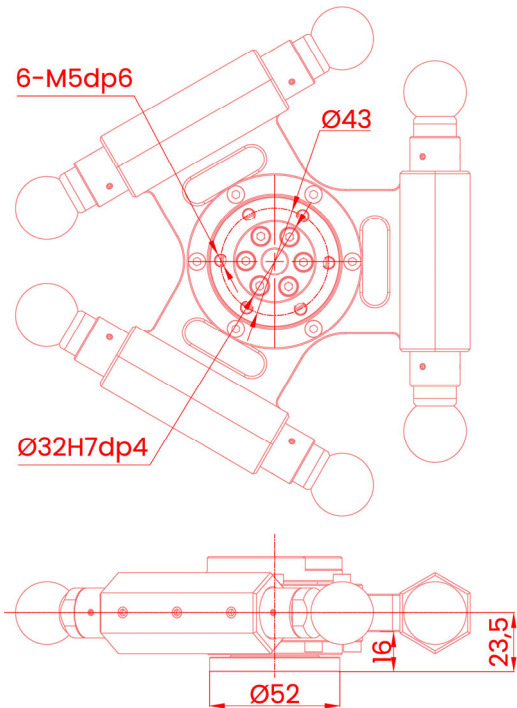
外形尺寸及运动范围
Outline dimensions and Working range (mm)



说明:
图示下部加深部分为机器人末端下表面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 bottom surface's center point of the end, 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)

