

**atomrobot**<sup>®</sup>  
阿童木机器人

# 并联机器人

## 选型手册

Parallel Robot Selection Manual

D3P



## ● 型号和符号

|     | D3P  | —      | 1100            | —                                    | P0                     | —   | A2  | —   | E1       | —  | FXGX             |      |      |      |
|-----|------|--------|-----------------|--------------------------------------|------------------------|-----|-----|-----|----------|----|------------------|------|------|------|
| 机型  | 型号   | 负载     | 控制器类型           | 控制柜类型                                | 视觉                     |     |     |     |          |    |                  |      |      |      |
| D3P | 450  | 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 | 450 | 600 | 800 | P3*: 3kg | 特款 | A2: KEBA CONTROL | 1200 | 1300 | 1400 |
|     | 600  |        |                 |                                      |                        |     |     |     |          |    |                  |      |      |      |
|     | 1100 |        |                 |                                      |                        |     |     |     |          |    |                  |      |      |      |

\*: P3针对D3P-1100以及D3P-800机型, 为搭配atomrobot自主控制器推荐款。

## ● Model and Symbol

|            | D3P  | —            | 1100            | —  | P0  | —   | A2  | —   | E1       | —       | FXGX             |      |      |      |
|------------|------|--------------|-----------------|--|---|-----|-----|-----|----------|---------|------------------|------|------|------|
| Robot type | Type | Load Type    | Control Type    | Control Cabinet                          | Vision Type                                     |     |     |     |          |         |                  |      |      |      |
| D3P        | 450  | P0: Standard | A1: ATOMCONTROL | E1: ATOM-01<br>E2: ATOM-02<br>E3: Custom | F0G0:<br>Without vision<br>FXGX:<br>With vision | 450 | 600 | 800 | P3*: 3kg | Special | A2: KEBA CONTROL | 1200 | 1300 | 1400 |
|            | 600  |              |                 |  |   |     |     |     |          |         |                  |      |      |      |
|            | 1100 |              |                 |  |   |     |     |     |          |         |                  |      |      |      |

\*: P3 is the recommended model for the ATOMCONTROL.

## D3P-450-P0



高速度  
高精度  
高稳定性  
小巧、敏捷

High speed  
High precision  
High stability  
Small and Agile

|   |   |  |
|---|---|--|
| 型号 Type   |   | D3P-450-P0                                     |
| 轴数 Axes   |   | 3+1  |
| 最大负载 Payload                                      |   | 3kg  |
| 机器人本体<br>Manipulator                              | 重量 Weight                                   | 41.5kg   |
|   | 工作空间直径<br>Diameter                          | 450mm  |
| 重复定位精度<br>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<br>Allowable maximum moment of inertia |   | $31 \times 10^{-4} \text{kg} \cdot \text{m}^2$ |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up                                       | 36.5°  |
|   | 下摆 Down                                     | 65.5°  |
| 输入电源<br>Power supply                              | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |  |
| 电源容量<br>Power capacity                            | 3KVA  |  |
| 额定功率<br>Rated Power                               | 1.3kw                                       |  |
| 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  |  |

◆ 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.

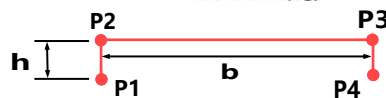
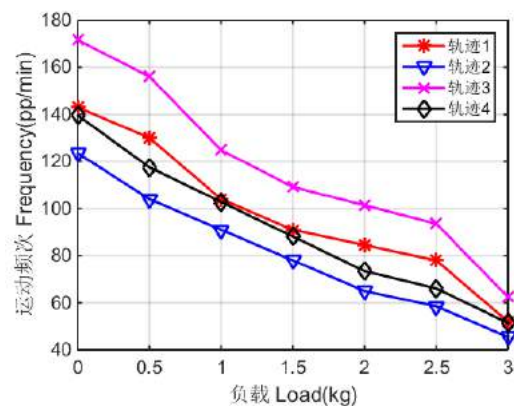
◆ 特殊旋转轴铰链设计, 轻松应对高强度高频次重复运动需求

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.

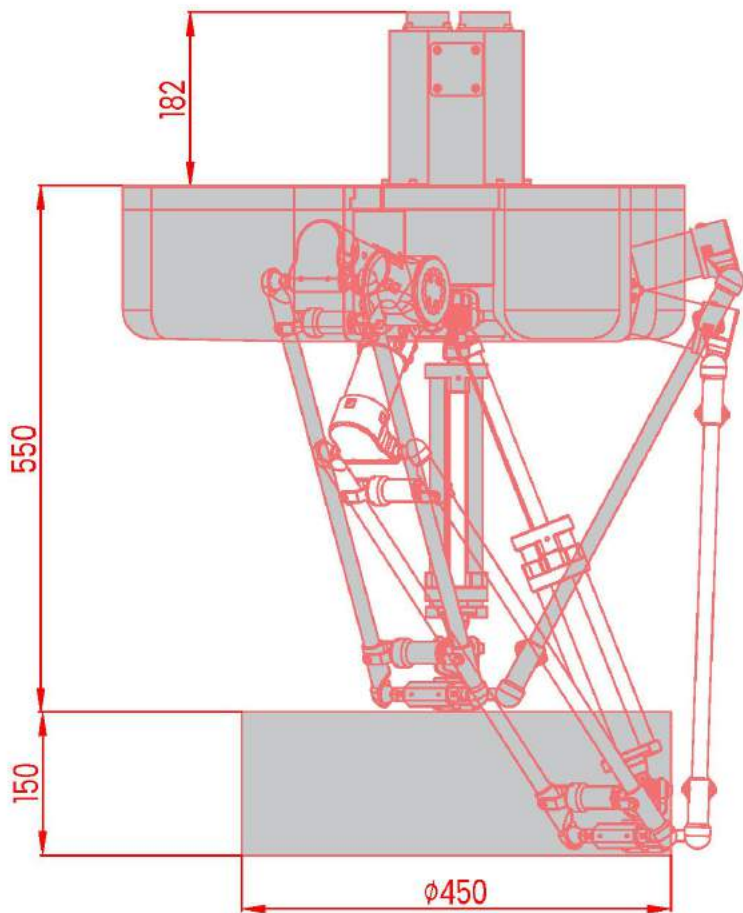
● 负载-频次 Load-Frequency



| 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   |

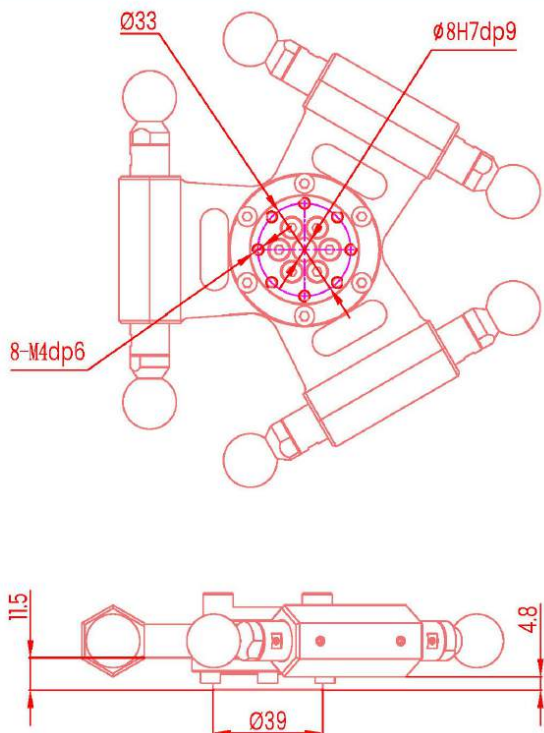
特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。

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

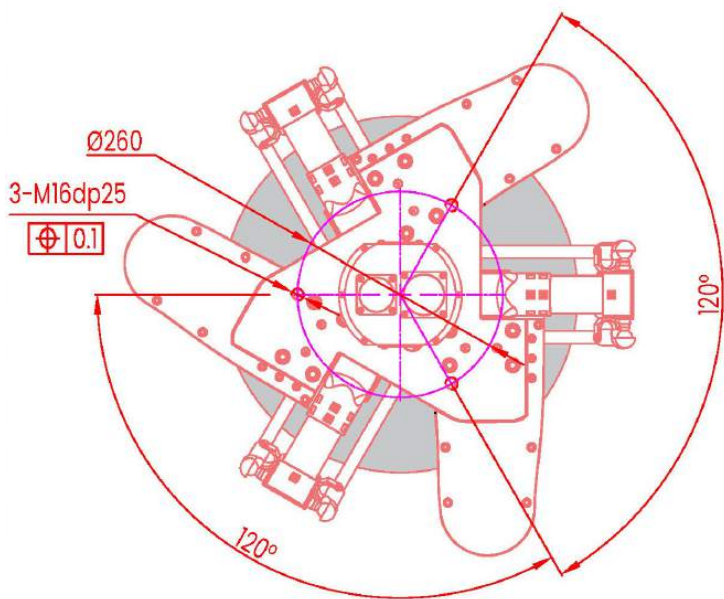


**说明:**  
 图示下部加深部分为机器人末端下表面几何中心的运动范围  
**Instruction:**  
 The bottom gray part is the workplace of bottom surface 's center point of the end, which is a cylinder .

**法兰 Flange (mm)**



**基座安装 Base installation (mm)**



## D3P-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

|   |   |        |
|---|---|--------|
| 型号 Type   | D3P-600-P0                                  |        |
| 轴数 Axes   | 3+1   |        |
| 最大负载 Payload                                      | 3kg   |        |
| 机器人本体<br>Manipulator                              | 重量 Weight                                   | 66kg   |
|   | 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                                 | 0.1°   |
| 旋转范围 Rotation range                               | ±360°                                       |        |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia | 31×10 <sup>-4</sup> kg·m <sup>2</sup>       |        |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up                                       | 36.5°  |
|   | 下摆 Down                                     | 65.5°  |
| 输入电源<br>Power supply                              | 三相 Three-phase 380VAC<br>-10%~+10%, 49~61HZ |        |
| 电源容量<br>Power capacity                            | 3KVA  |        |
| 额定功率<br>Rated Power                               | 1.3kw                                       |        |
| 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  |        |

◆ 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.

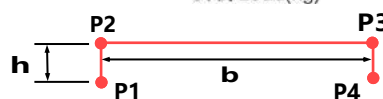
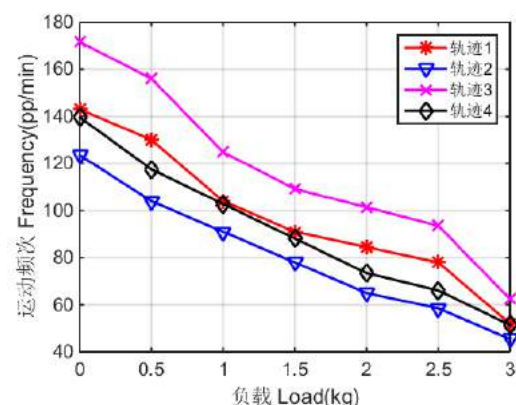
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● 负载-频次 Load-Frequency

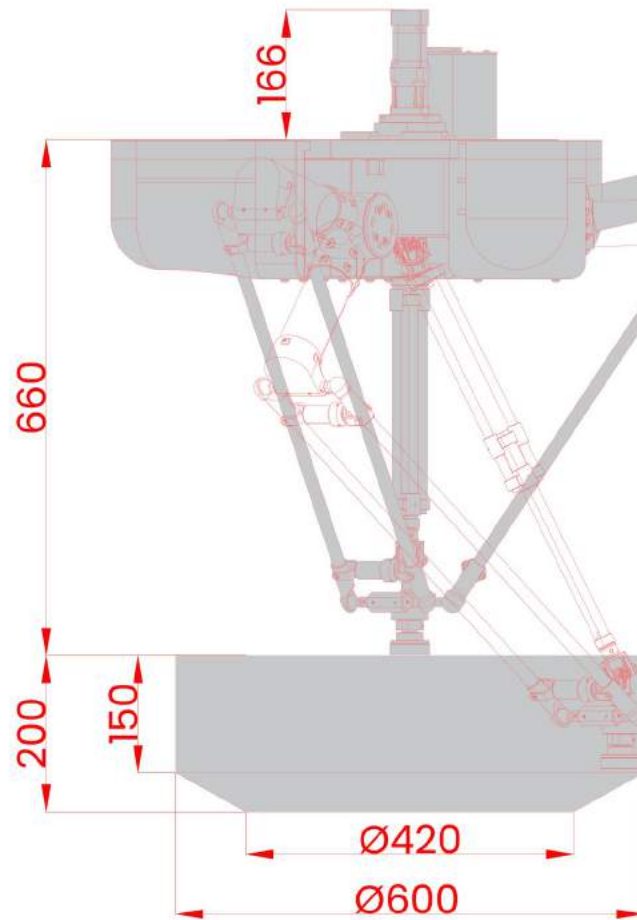


| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3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



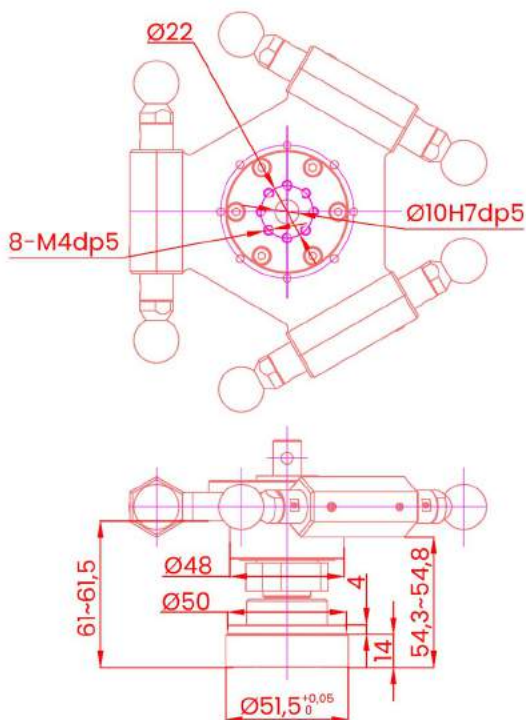
外形尺寸及运动范围  
Outline dimensions and Working range (mm)



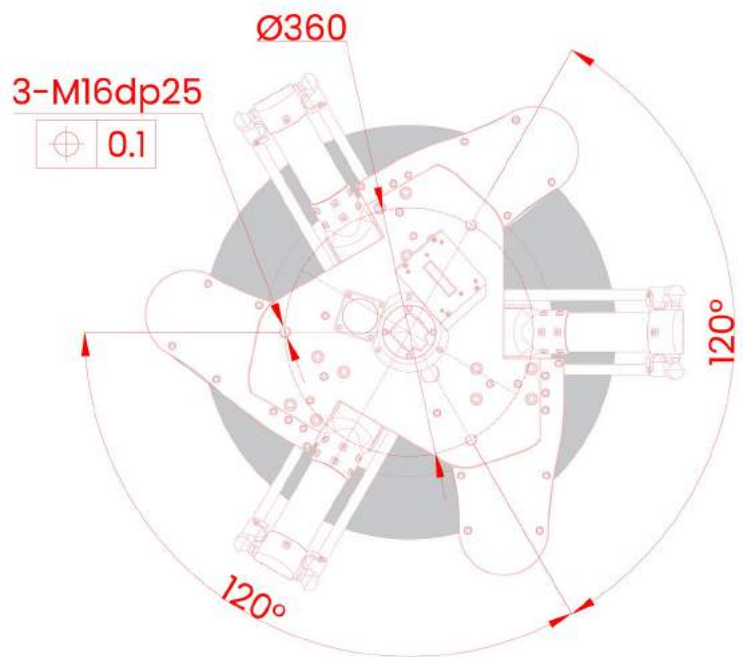
说明：  
图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

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-800-P3



高速度  
高精度  
高稳定性  
低高度

High speed  
High precision  
High stability  
Lower height

|   |   |        |
|---|---|--------|
| 型号 Type   | D3P-800-P3                                  |        |
| 轴数 Axes   | 3+1   |        |
| 最大负载 Payload                                      | 3kg   |        |
| 机器人本体<br>Manipulator                              | 重量 Weight                                   | 83.8kg |
|   | 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                                 | 0.1°   |
| 旋转范围 Rotation range                               | ±360°                                       |        |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia | 31×10 <sup>-4</sup> kg·m <sup>2</sup>       |        |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up                                       | 47.3°  |
|   | 下摆 Down                                     | 60.2°  |
| 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                               | 2.35kw                                      |        |
| 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  |        |

◆ 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.

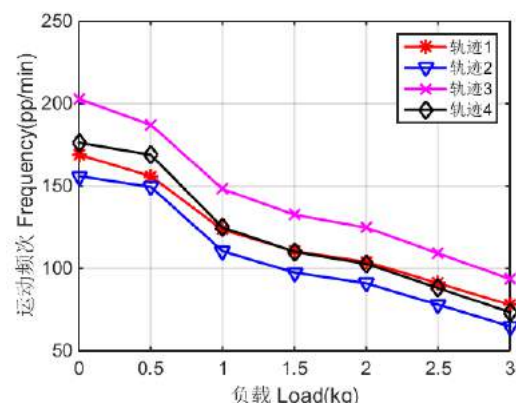
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The robot is ideal for high-speed production in food and medicine industry. Widely used in assembly, handling and pick-and-place of small materials.

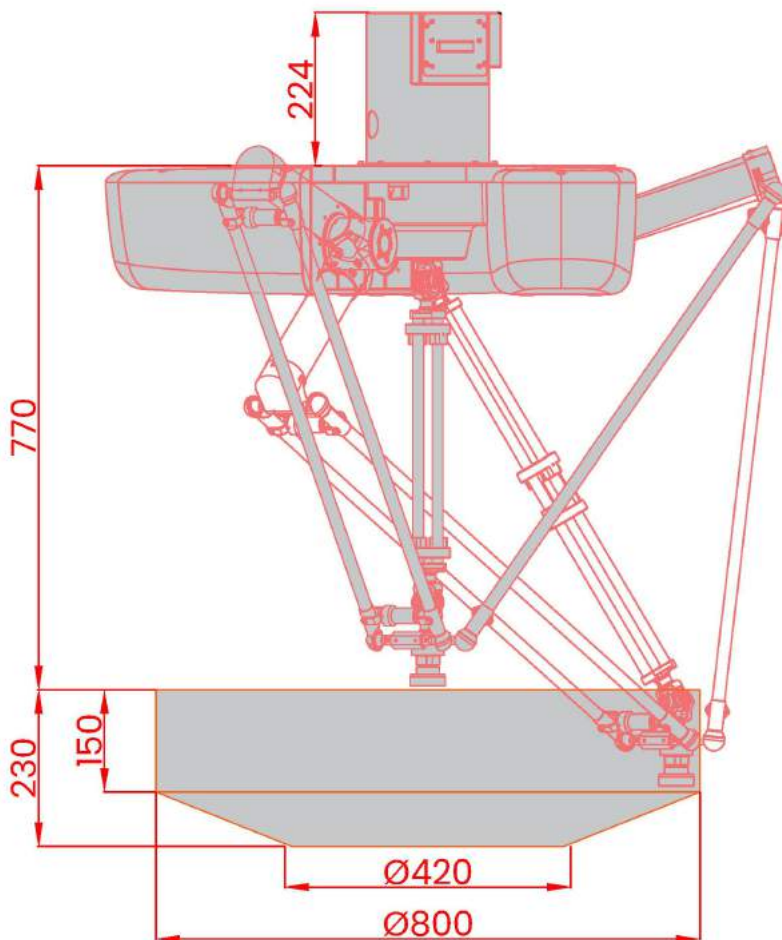
● 负载-频次 Load-Frequency



| 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。

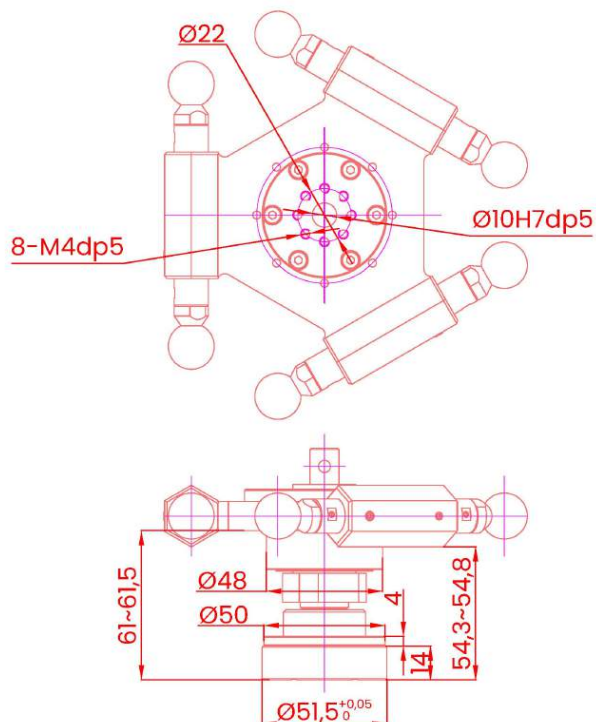
**外形尺寸及运动范围**  
**Outline dimensions and Working range (mm)**



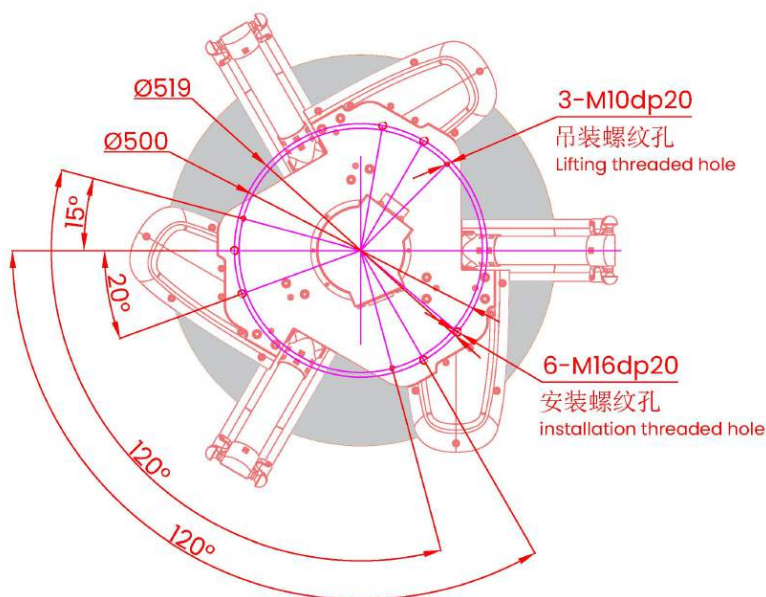
**说明:**  
图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

**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-800-P0



高速度  
高精度  
高稳定性  
低高度

High speed  
High precision  
High stability  
Lower height

|   |   |        |
|---|---|--------|
| 型号 Type   | D3P-800-P0                                  |        |
| 轴数 Axes   | 3+1   |        |
| 最大负载 Payload                                      | 3kg   |        |
| 机器人本体<br>Manipulator                              | 重量 Weight                                   | 88.8kg |
|   | 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                                 | 0.1°   |
| 旋转范围 Rotation range                               | ±360°                                       |        |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia | 31×10 <sup>-4</sup> kg·m <sup>2</sup>       |        |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up                                       | 30.2°  |
|   | 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                            | 6KVA  |        |
| 额定功率<br>Rated Power                               | 2.35kw                                      |        |
| 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  |        |

◆ 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.

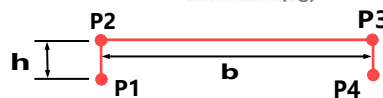
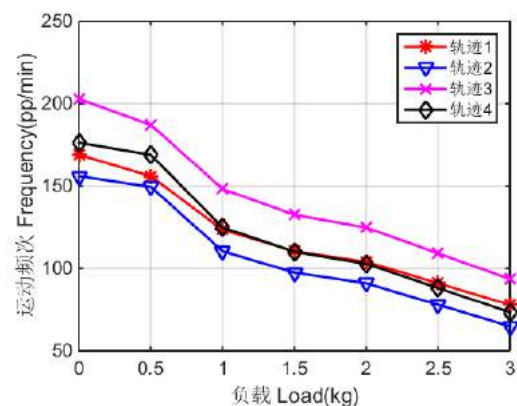
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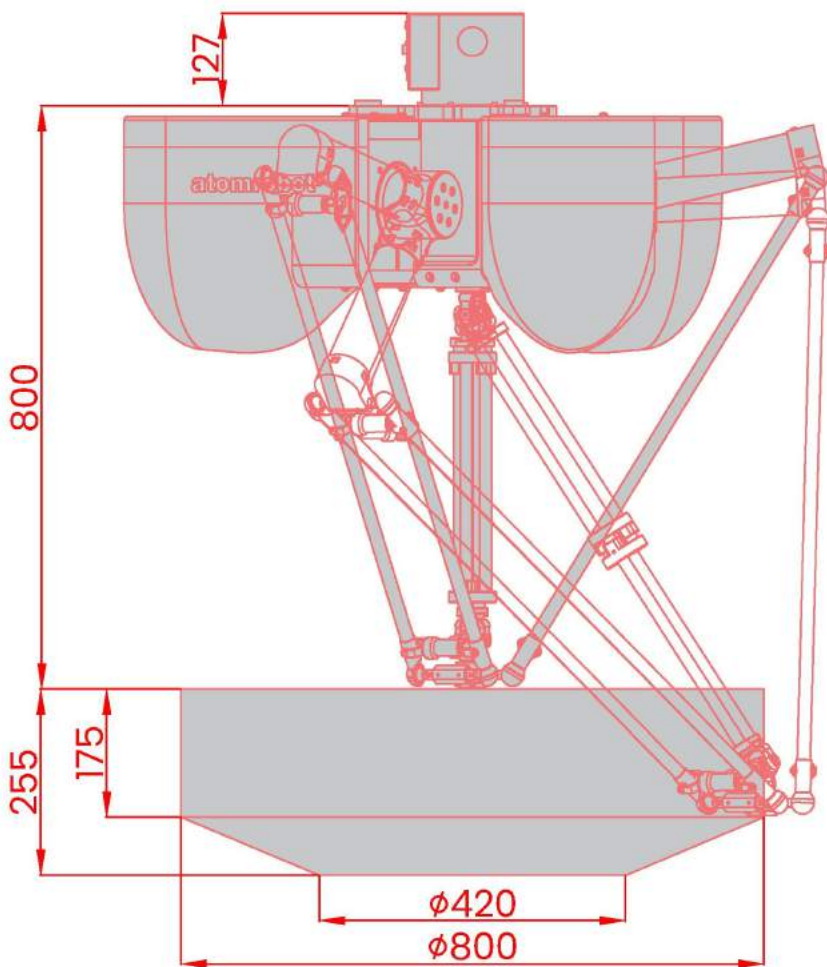
● 负载-频次 Load-Frequency



| 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。

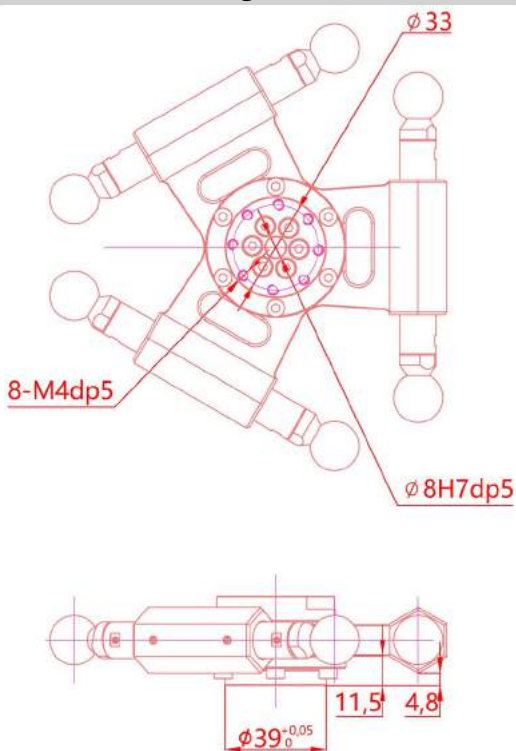
外形尺寸及运动范围  
Outline dimensions and Working range (mm)



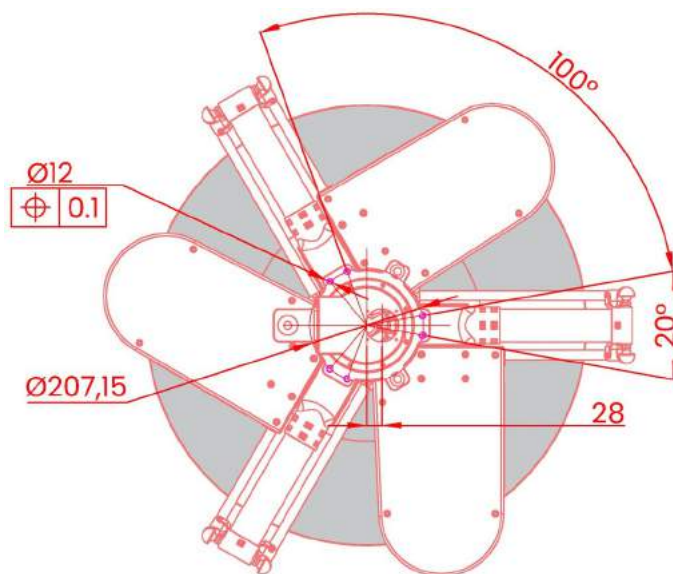
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图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

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  
高精度  
高稳定性  
低高度

High speed  
High precision  
High stability  
Lower height

|   |                    |  |
|---|--------------------|--|
| 型号 Type   |                    | D3P-1100-P3                                    |
| 轴数 Axes   |                    | 3+1  |
| 最大负载 Payload                                      |                    | 3kg  |
| 机器人本体<br>Manipulator                              | 重量 Weight          | 85.5kg   |
|   | 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        | 0.1°   |
| 旋转范围 Rotation range                               |                    | ±360°  |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |                    | $31 \times 10^{-4} \text{kg} \cdot \text{m}^2$ |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up              | 39.2°  |
|   | 下摆 Down            | 77.1°  |
| 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                               |                    | 6.1kw  |
| 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   |

◆ 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.

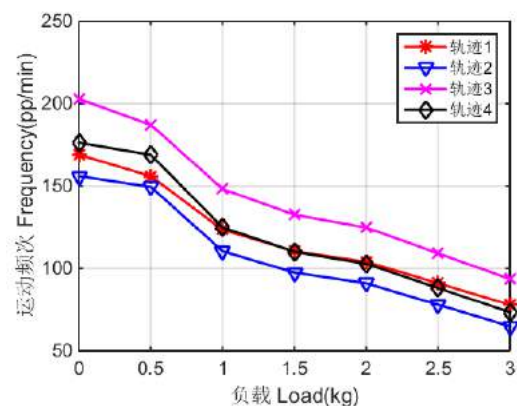
◆ 特殊旋转轴铰链设计, 轻松应对高强度高频次重复运动需求

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.

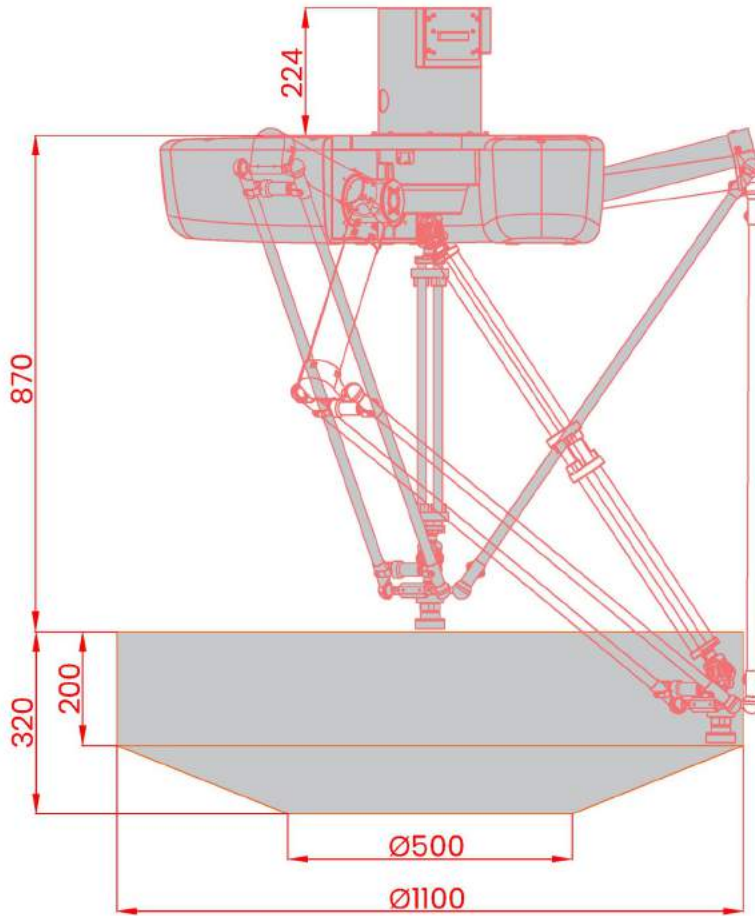
● 负载-频次 Load-Frequency



| 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)



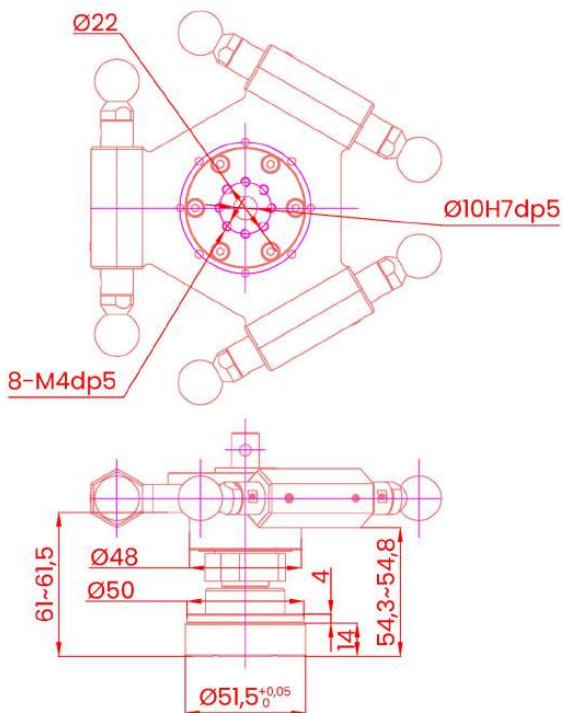
说明:

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。

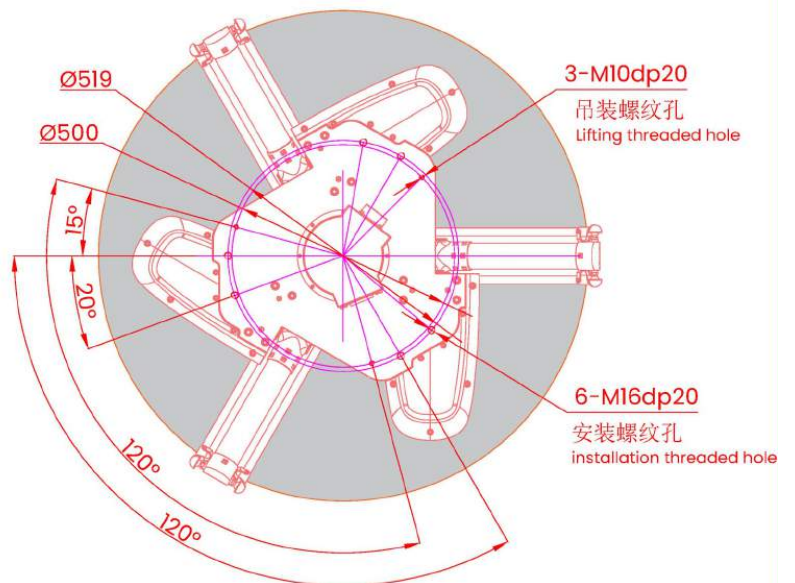
Instruction:

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-P0



高速度  
高稳定性  
大空间  
经济实用

High speed  
High stability  
Large space  
Economic & Practical

|   |   |        |
|---|---|--------|
| 型号 Type   | D3P-1100-P0                                   |        |
| 轴数 Axes   | 3+1   |        |
| 最大负载 Payload                                      | 5kg   |        |
| 机器人本体<br>Manipulator                              | 重量 Weight                                     | 90.5kg |
|   | 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                                   | 0.1°   |
| 旋转范围 Rotation range                               | ±360°   |        |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia | 80 × 10 <sup>-4</sup> kg · m <sup>2</sup>     |        |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up   | 24.5°  |
|   | 下摆 Down                                       | 73.5°  |
| 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                               | 6.1kw   |        |
| 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  |        |

◆ 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.

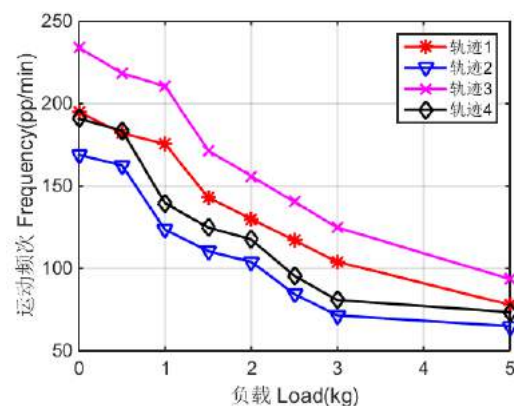
◆ 特殊旋转轴铰链设计, 轻松应对高强度高频次重复运动需求

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.

● 负载-频次 Load-Frequency

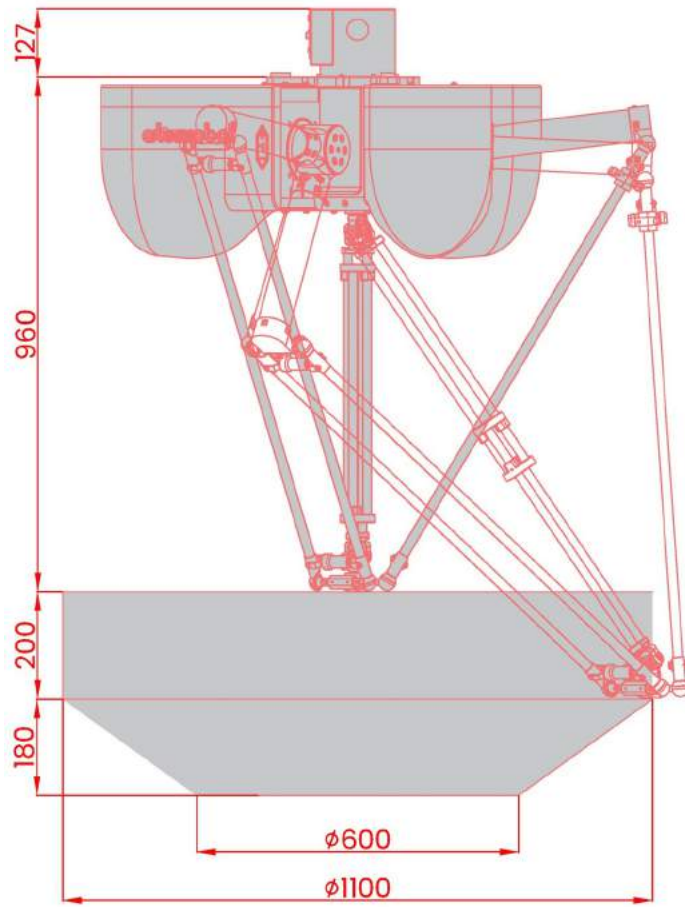


| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3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



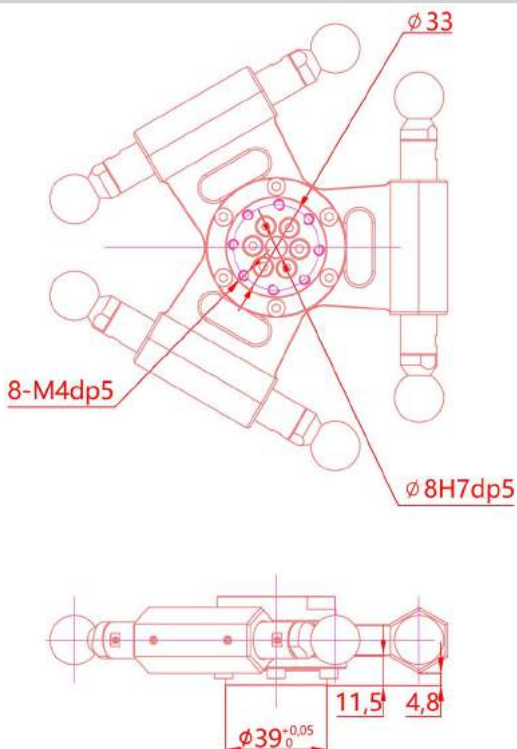
说明:

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。

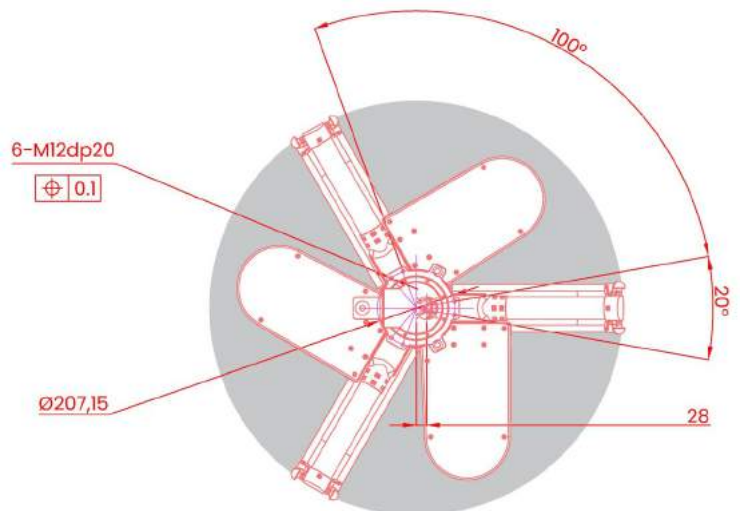
Instruction:

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-1200-P0



高速度  
高稳定性  
大空间  
低高度

High speed  
High stability  
Large space  
Lower Height

|   |   |  |
|---|---|--|
| 型号 Type   |   | D3P-1200-P0                                    |
| 轴数 Axes   |   | 3+1  |
| 最大负载 Payload                                      |   | 3kg  |
| 机器人本体<br>Manipulator                              | 重量 Weight                                   | 80.6kg   |
|   | 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                                 | 0.1°   |
| 旋转范围 Rotation range                               |   | ±360°  |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |   | $31 \times 10^{-4} \text{kg} \cdot \text{m}^2$ |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up                                       | 34.5°  |
|   | 下摆 Down                                     | 86.5°  |
| 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                               | 6.1kw                                       |  |
| 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  |  |

- 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.

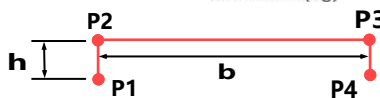
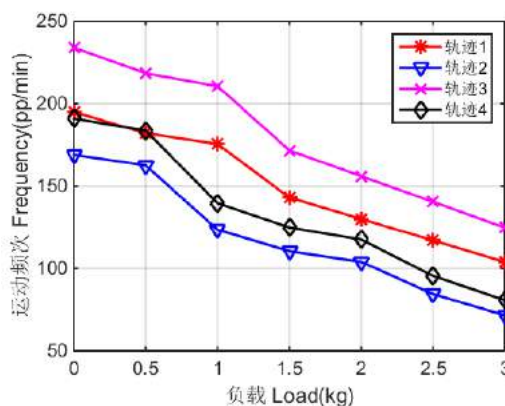
- 特殊旋转轴铰链设计, 轻松应对高强度高频次重复运动需求

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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.

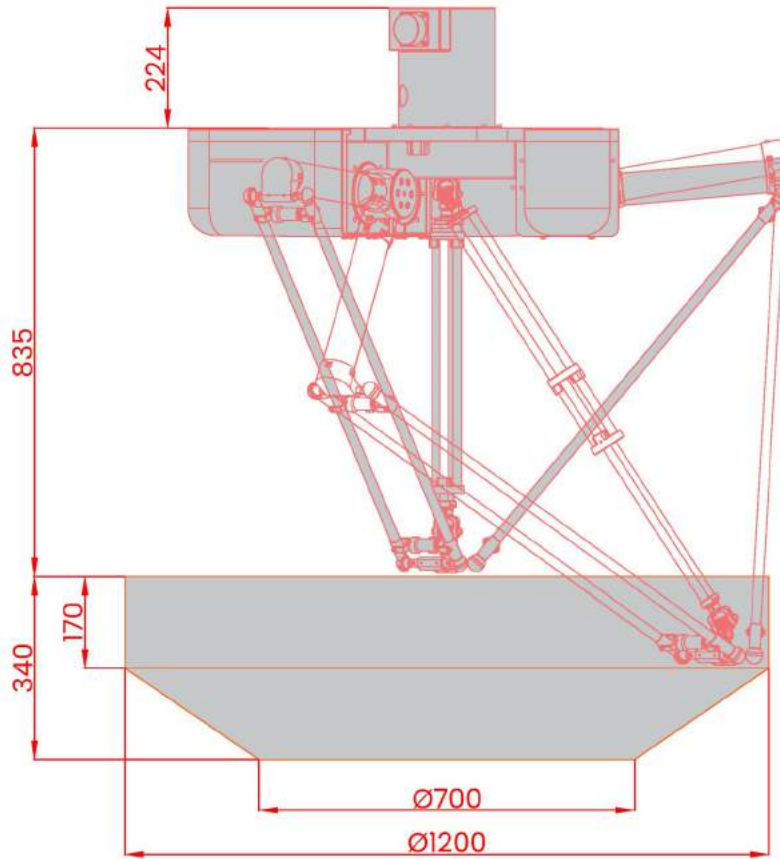
- 负载-频次 Load-Frequency



| 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。

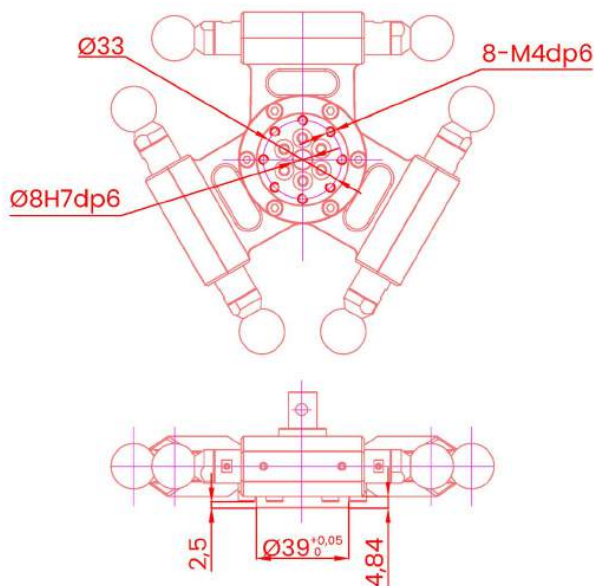
外形尺寸及运动范围  
Outline dimensions and Working range (mm)



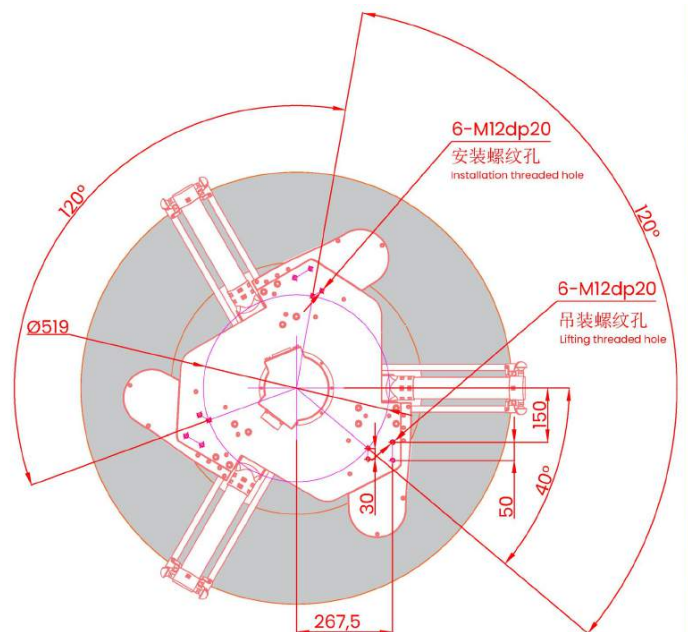
说明:  
图示下部加深部分为机器人末端下表面几何中心的运动范围,上部为圆柱空间,并在下部向内收敛。

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-P0



高速度  
高稳定性  
大空间  
经济实用

High speed  
High stability  
Large space  
Economic & Practical

|   |   |  |
|---|---|--|
| 型号 Type   |   | D3P-1300-P0                                    |
| 轴数 Axes   |   | 3+1  |
| 最大负载 Payload                                      |   | 5kg  |
| 机器人本体<br>Manipulator                              | 重量 Weight                                   | 93.5kg   |
|   | 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                                 | 0.1°   |
| 旋转范围 Rotation range                               |   | ±360°  |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |   | $80 \times 10^{-4} \text{kg} \cdot \text{m}^2$ |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up                                       | 24.6°  |
|   | 下摆 Down                                     | 78.5°  |
| 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                               | 6.1kw                                       |  |
| 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  |  |

◆ 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.

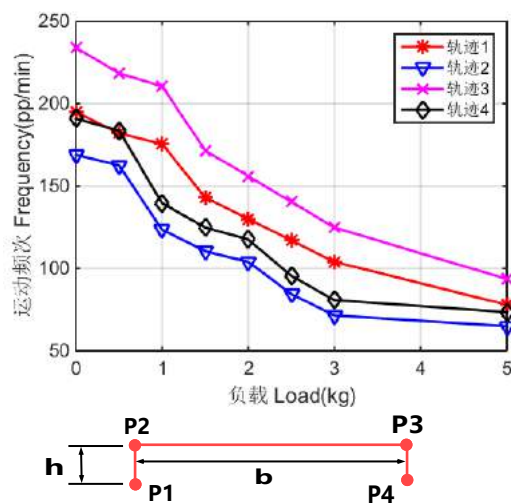
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● 负载-频次 Load-Frequency

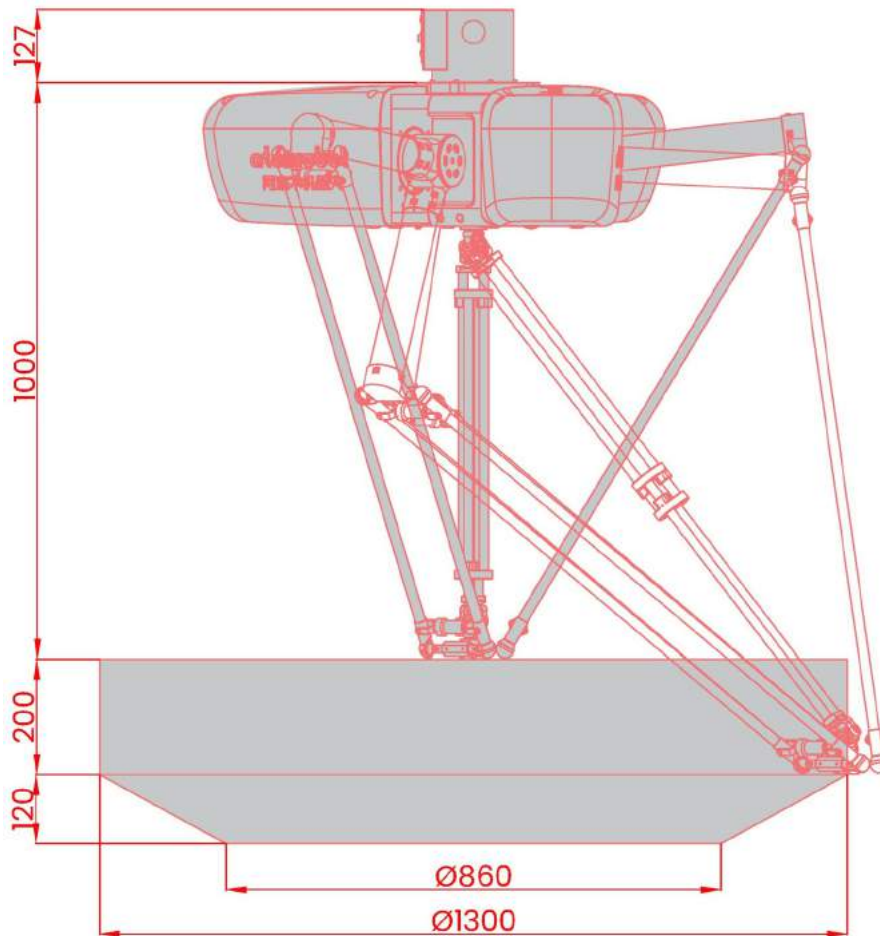


| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3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



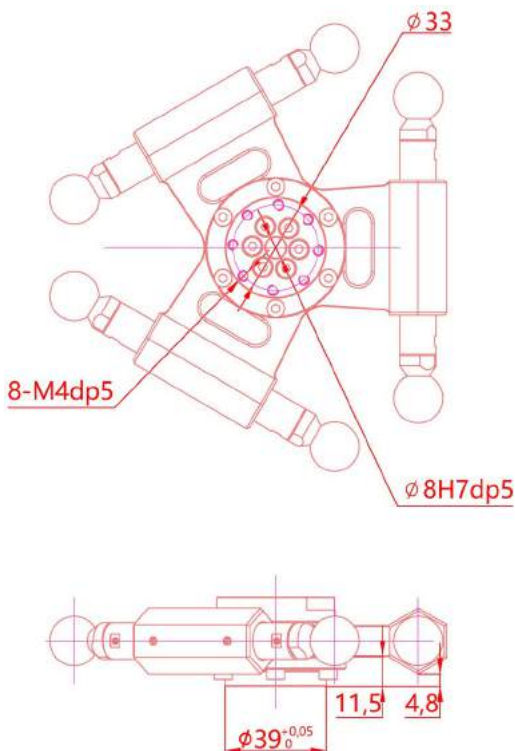
说明:

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。

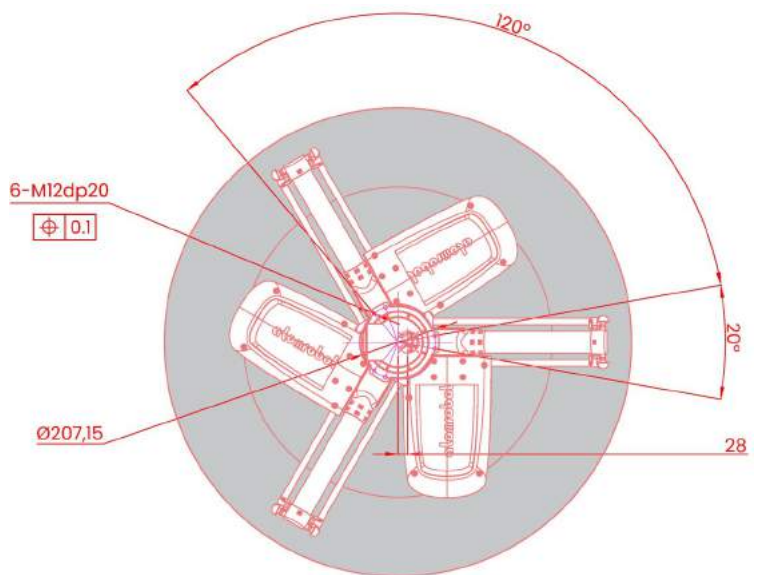
Instruction:

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-P0



高速度  
高稳定性  
大空间  
经济实用

High speed  
High stability  
Large space  
Economic & Practical

|   |   |        |
|---|---|--------|
| 型号 Type   | D3P-1400-P0                                 |        |
| 轴数 Axes   | 3+1   |        |
| 最大负载 Payload                                      | 3kg   |        |
| 机器人本体<br>Manipulator                              | 重量 Weight                                   | 96.5kg |
|   | 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                                 | 0.1°   |
| 旋转范围 Rotation range                               | ±360°                                       |        |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia | 80×10 <sup>-4</sup> kg·m <sup>2</sup>       |        |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up                                       | 28°    |
|   | 下摆 Down                                     | 73°    |
| 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                               | 6.1kw                                       |        |
| 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  |        |

◆ 标准循环时间小于0.4s,满足追求最高速度和最经济需求

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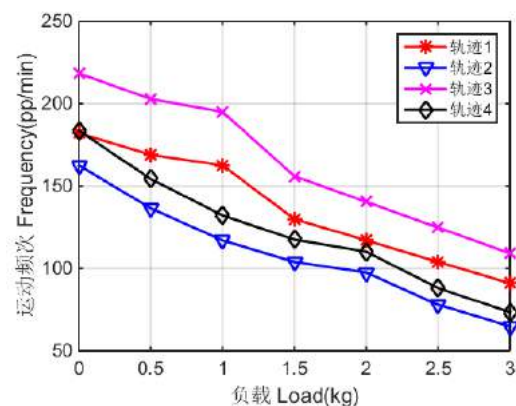
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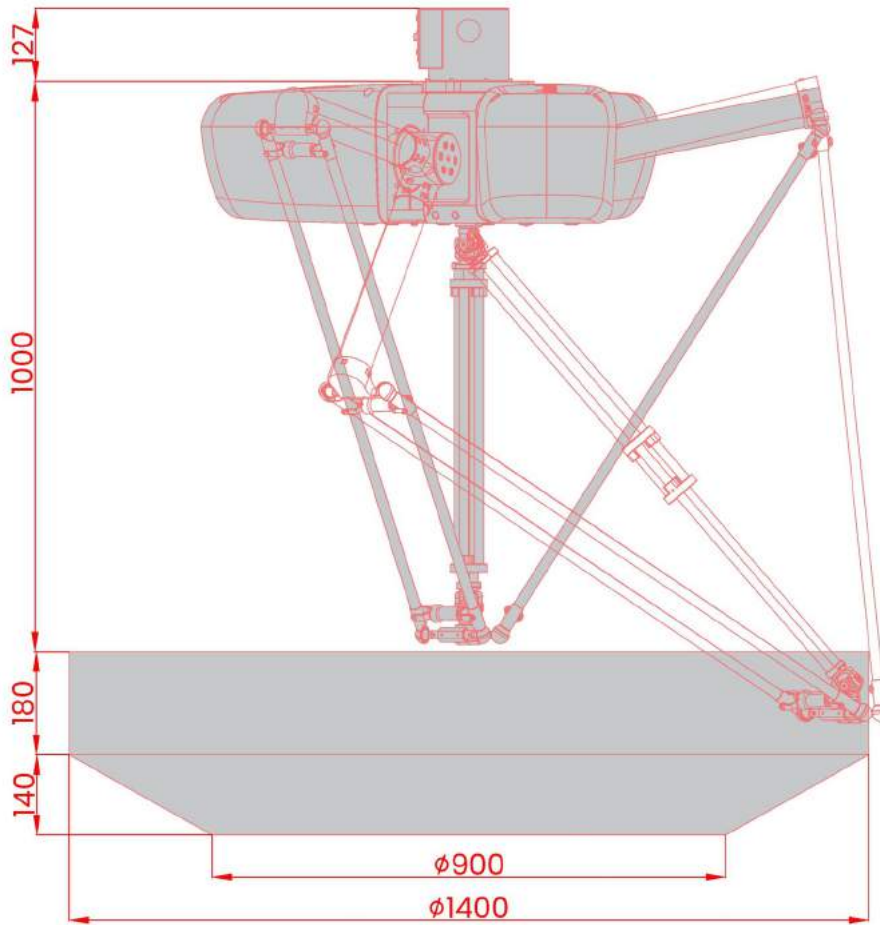
● 负载-频次 Load-Frequency



| 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)



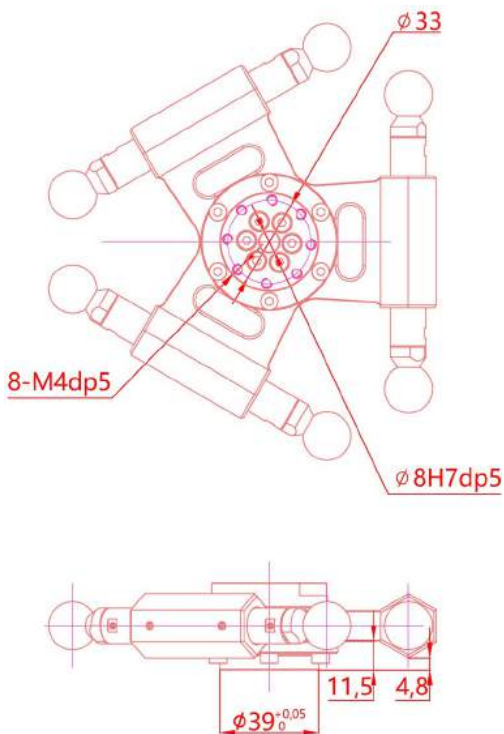
说明:

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。

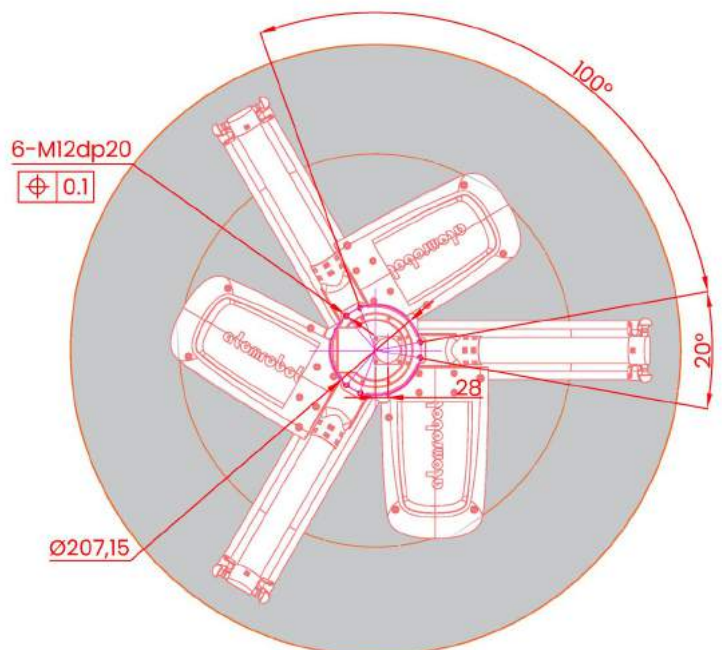
Instruction:

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)



底座安装 Base installation (mm)



## D3P-1600-P0



高速度  
高稳定性  
大空间  
经济实用

High speed  
High stability  
Large space  
Economic & Practical

|   |   |        |
|---|---|--------|
| 型号 Type   | D3P-1600-P0                                 |        |
| 轴数 Axes   | 3+1   |        |
| 最大负载 Payload                                      | 3kg   |        |
| 机器人本体<br>Manipulator                              | 重量 Weight                                   | 96.8kg |
|   | 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                                 | 0.1°   |
| 旋转范围 Rotation range                               | ±360°                                       |        |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia | 80×10 <sup>-4</sup> kg·m <sup>2</sup>       |        |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up                                       | 28°    |
|   | 下摆 Down                                     | 73°    |
| 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                               | 6.1kw                                       |        |
| 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  |        |

◆ 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.

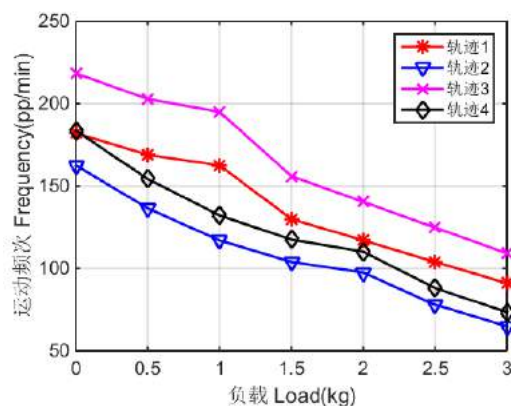
◆ 特殊旋转轴铰链设计, 轻松应对高强度高频次重复运动需求

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.

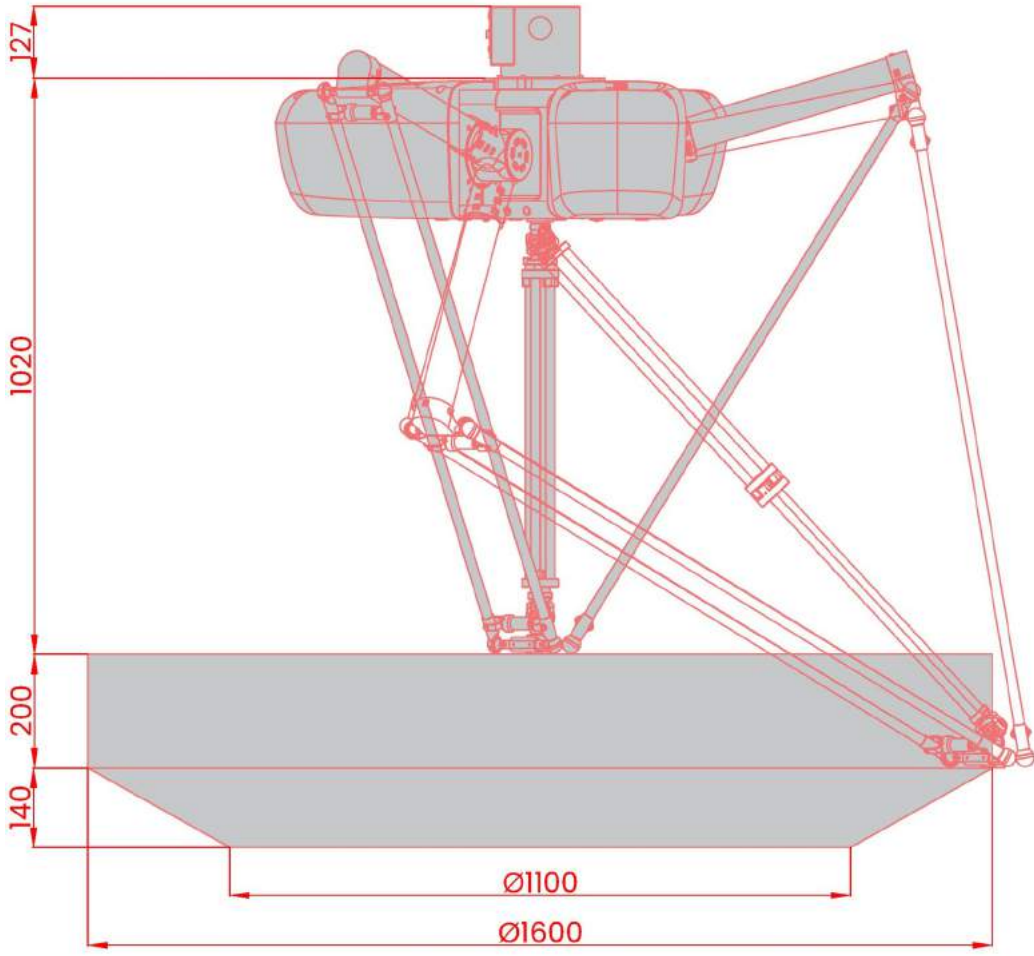
● 负载-频次 Load-Frequency



| 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)

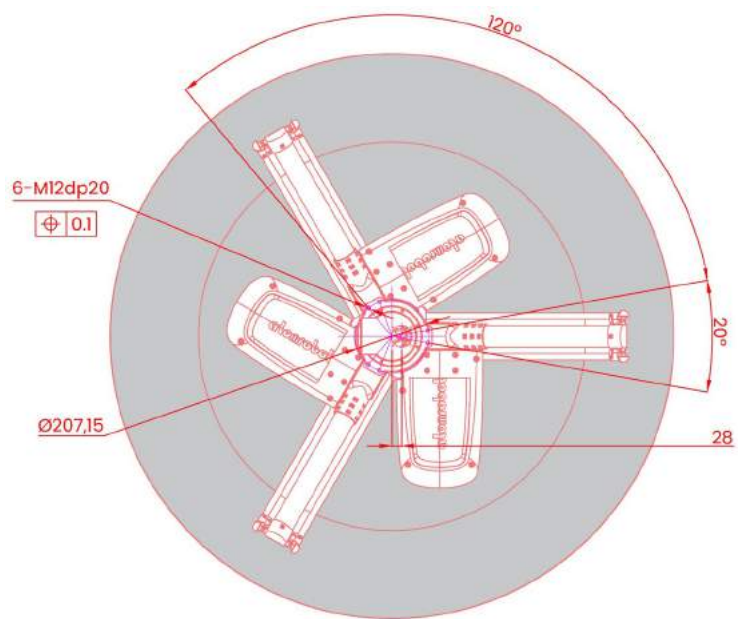
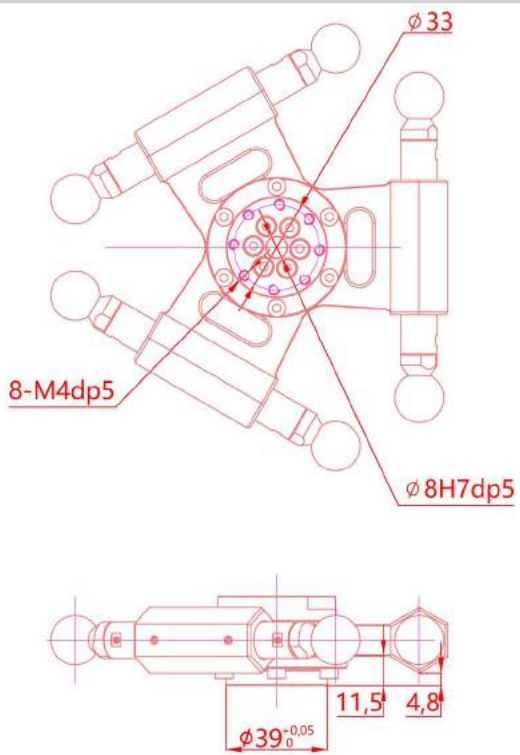


说明：  
图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

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

|   |   |   |
|---|---|---|
| 型号 Type   |   | D3P-1100-P8                                     |
| 轴数 Axes   |   | 3+1   |
| 最大负载 Payload                                      |   | 8kg   |
| 机器人本体<br>Manipulator                              | 重量 Weight                                   | 128kg   |
|   | 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                                 | 0.1°  |
| 旋转范围 Rotation range                               |   | ±360°   |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |   | $250 \times 10^{-4} \text{kg} \cdot \text{m}^2$ |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up                                       | 13.5°   |
|   | 下摆 Down                                     | 78.5°   |
| 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                               | 6.1kw                                       |   |
| 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  |   |

◆ 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.

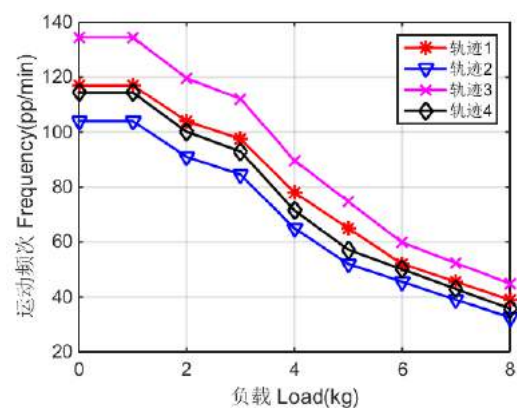
◆ 特殊旋转轴铰链设计, 轻松应对高强度高频次重复运动需求

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.

● 负载-频次 Load-Frequency

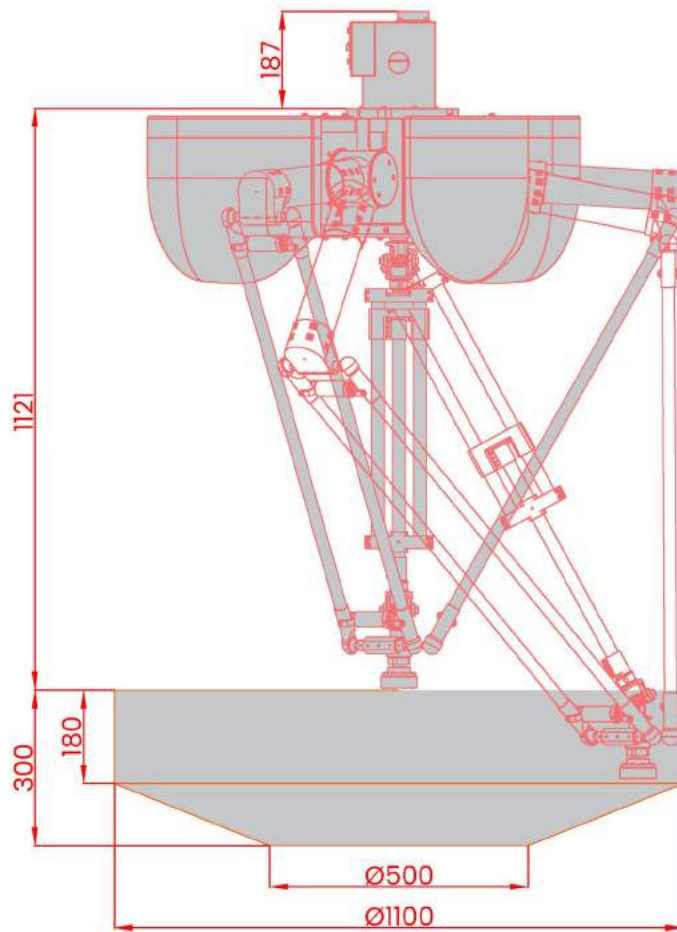


| 名称 Name         | 循环模式 Model                       | 运动距离 Distance |
|-----------------|----------------------------------|---------------|
| 轨迹1 Trajectory1 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=305   |
| 轨迹2 Trajectory2 | P1 → P2 → P3 → P4 → P3 → P2 → P1 | h=25, b=500   |
| 轨迹3 Trajectory3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

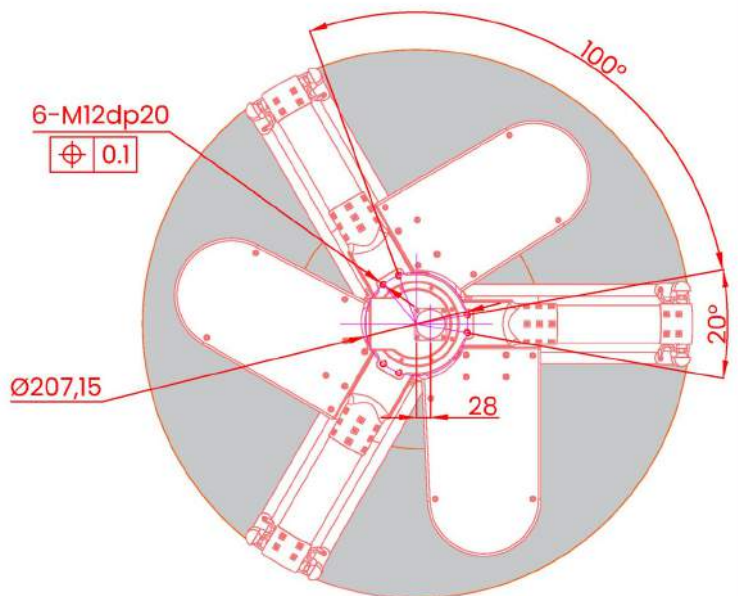
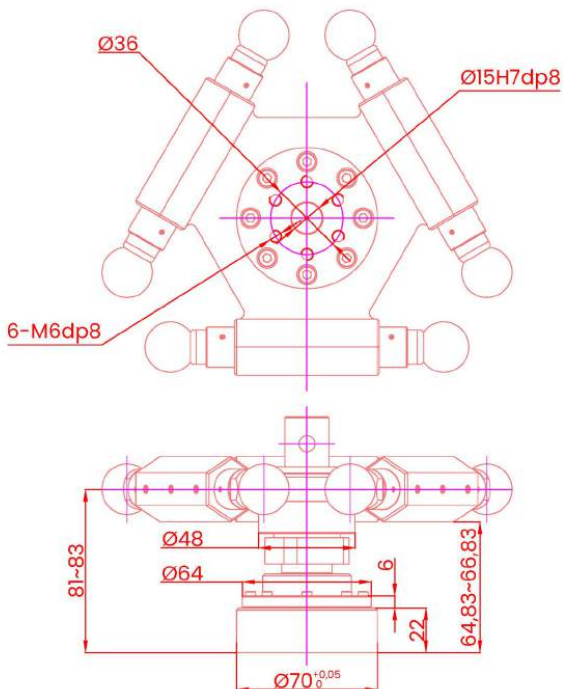
图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

**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

|   |   |   |
|---|---|---|
| 型号 Type   |   | D3P-1400-P8                                     |
| 轴数 Axes   |   | 3+1   |
| 最大负载 Payload                                      |   | 8kg   |
| 机器人本体<br>Manipulator                              | 重量 Weight                                   | 135kg   |
|   | 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                                 | 0.1°  |
| 旋转范围 Rotation range                               |   | ±360°   |
| 允许负载最大旋转惯量<br>Allowable maximum moment of inertia |   | $250 \times 10^{-4} \text{kg} \cdot \text{m}^2$ |
| 主动臂角度范围<br>Angle range of actuated arm            | 上摆 Up                                       | 23.5°   |
|   | 下摆 Down                                     | 68°   |
| 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                               | 6.1kw                                       |   |
| 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  |   |

◆ 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.

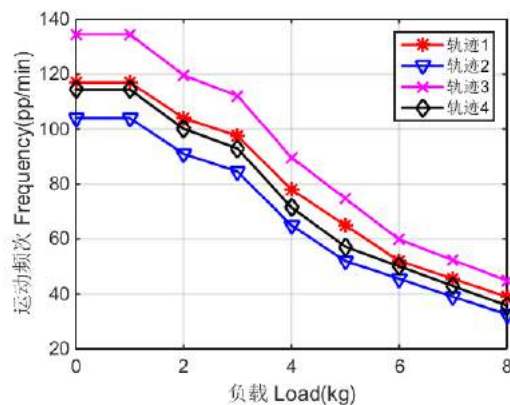
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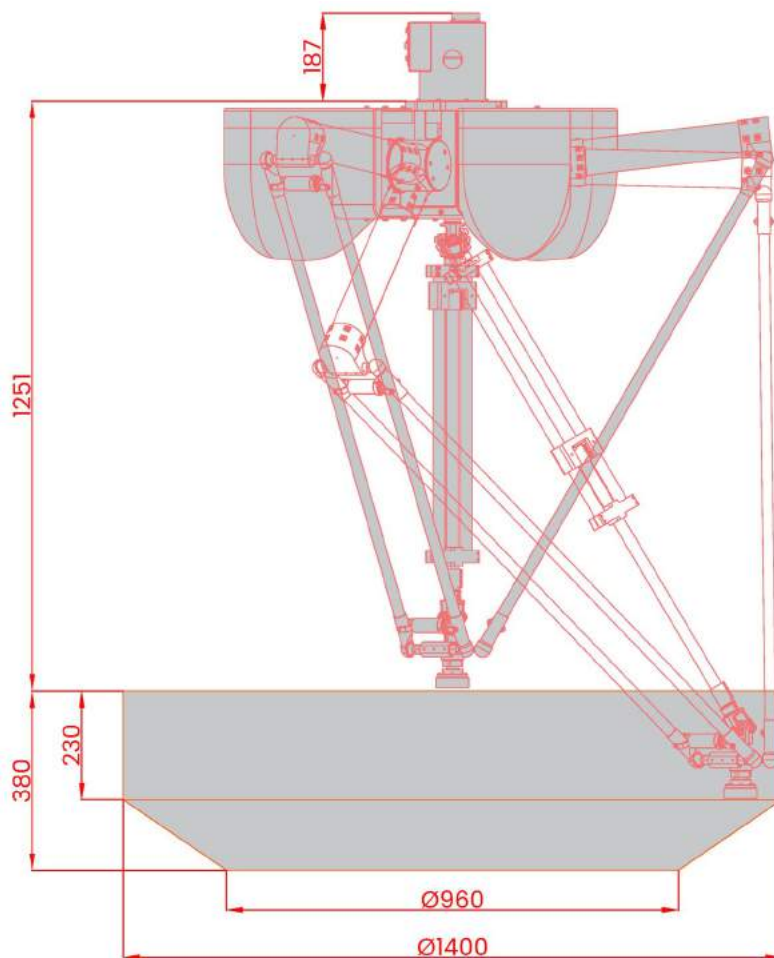
● 负载-频次 Load-Frequency



| 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。

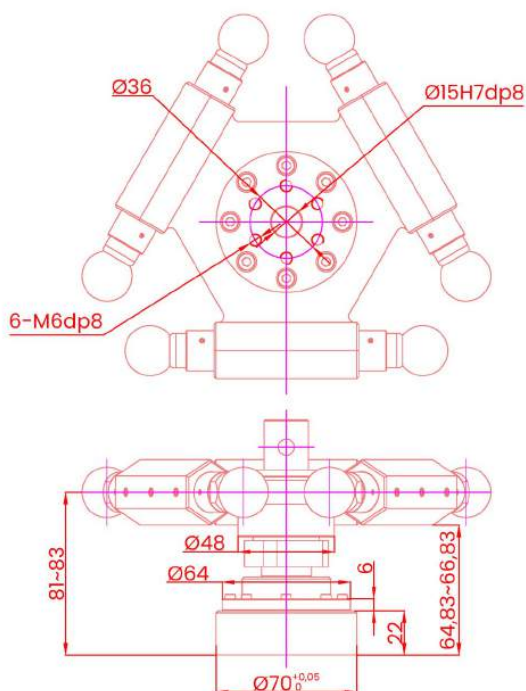
外形尺寸及运动范围  
Outline dimensions and Working range (mm)



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)

