

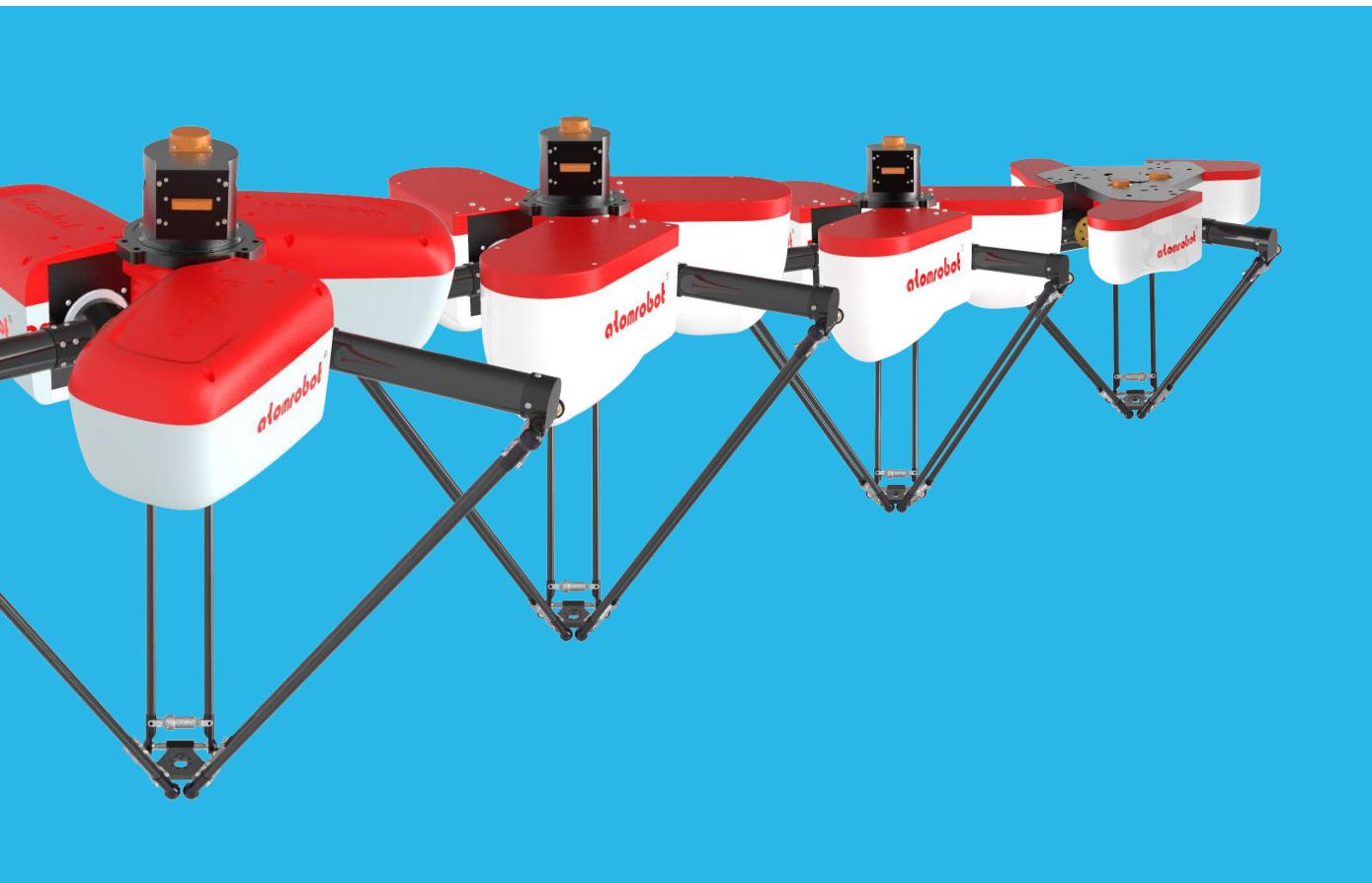


# 并联机器人

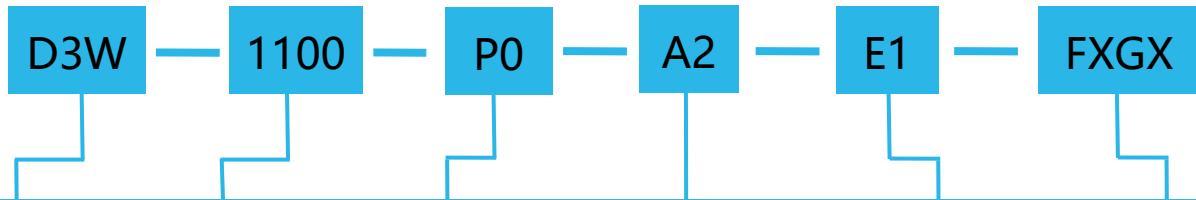
## 选型手册

Parallel robot selection Manual

D3W

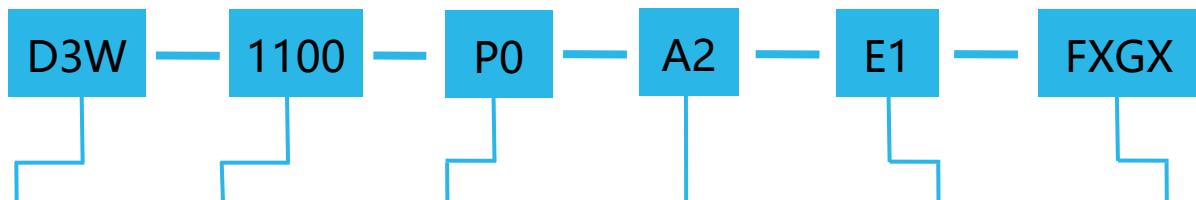


## ● 型号和符号



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 E2: ATOM-02 E3: 定制	FOGO: 无视觉 FXGX: 有视觉					
	800									
	1100	P15: 15KG								
	1200	A2: KEBA CONTROL								
	1300					P25: 25KG				
	1400									
	1600									

## ● Model and Symbol



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

## D3W-600-PO



**高速度** High speed  
**高精度** High precision  
**高稳定性** High stability  
**小巧、敏捷** Small and Agile

型号 Type		D3W-600-PO
轴数 Axes		3
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	38.7kg
	工作空间直径 Diameter	600mm
重复定位精度 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 Allowable maximum moment of inertia		—
主动臂角度范围 Angle range of actuated arm	上摆 Up	42.5°
	下摆 Down	69.8°
输入电源 Power supply	三相 Three-phase 380VAC -10%~+10%, 49~61HZ	
电源容量 Power capacity	3KVA	
额定功率 Rated Power	1.2kw	
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	

- ◆ 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.

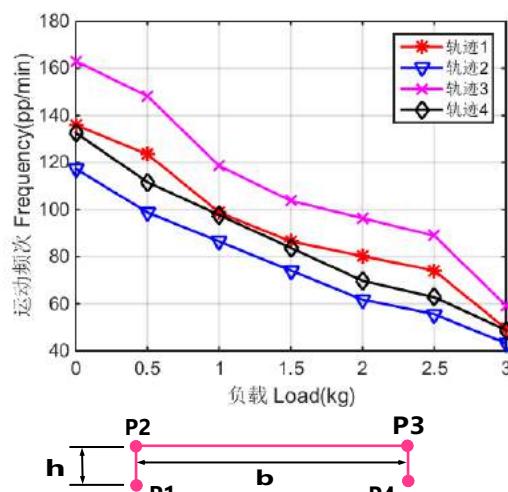
- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

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

- ◆ 非常适于狭小空间内作业、3C制造等行业的高速高精密生产作业, 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

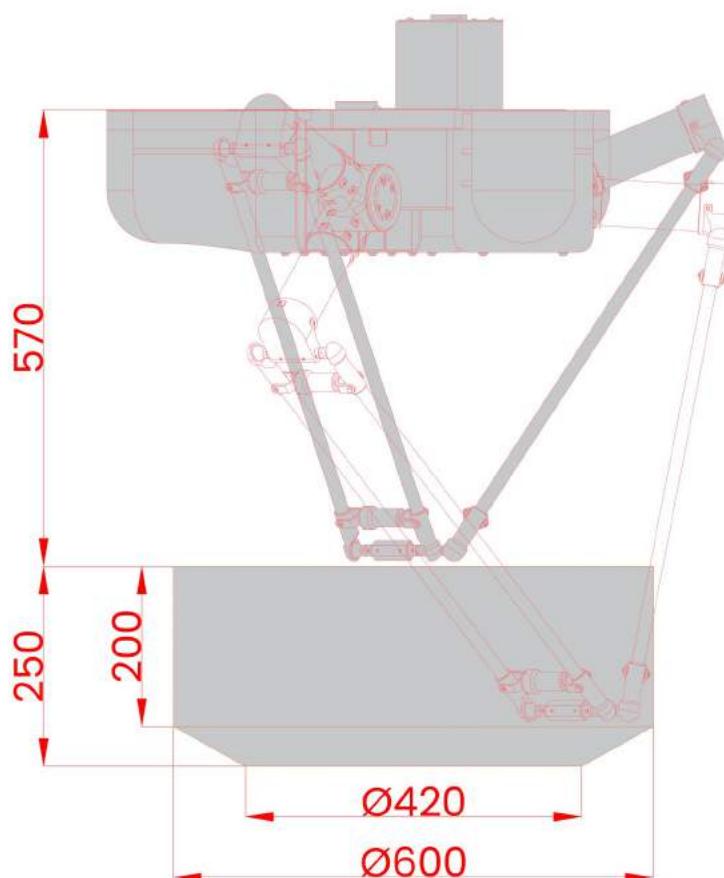


名称 Name	循环模式 Model	运动距离 Distance
轨迹1 Trajectory1	P1→P2→P3→P4→P3→P2→P1	h=25,b=305
轨迹2 Trajectory2	P1→P2→P3→P4→P3→P2→P1	h=25,b=500
轨迹3 Trajectory3	P1→P2→P3→P2→P1	h=25,b=305
轨迹4 Trajectory4	P1→P2→P3→P2→P1	h=25,b=500

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:

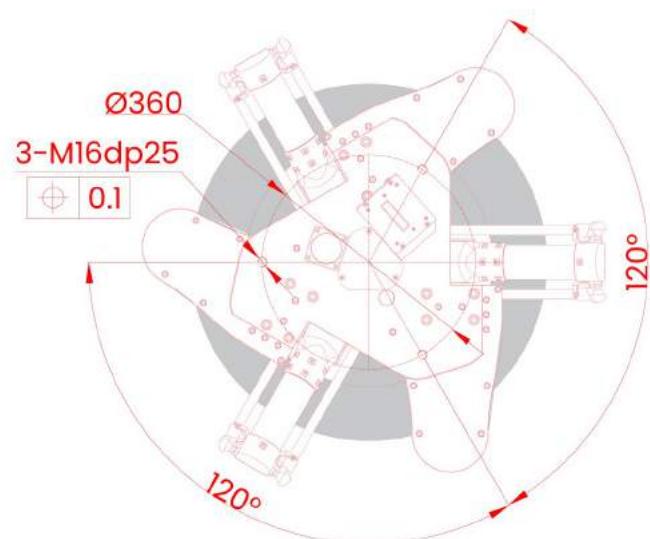
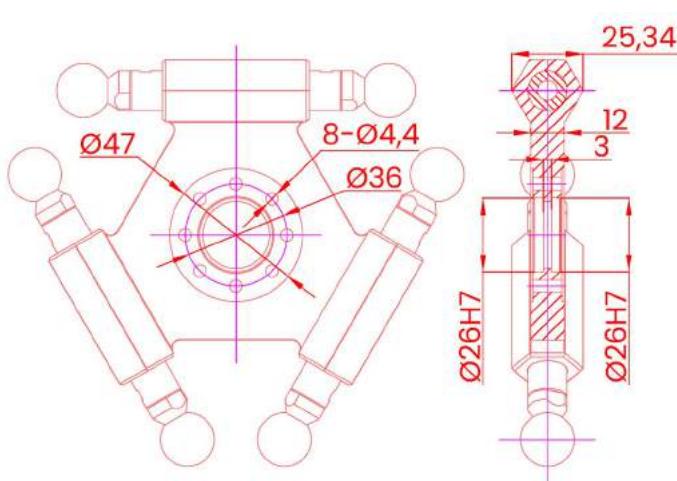
图示下部加深部分为机器人动平台几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

## 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-PO



型号 Type		D3W-800-PO
轴数 Axes		3
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	69.5kg
	工作空间直径 Diameter	800mm
重复定位精度 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 Allowable maximum moment of inertia		—
主动臂角度范围 Angle range of actuated arm	上摆 Up	42.5°
	下摆 Down	65.8°
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	2.25kw	
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	

**高速度****High speed****高精度****High precision****高稳定性****High stability****经济实用****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.

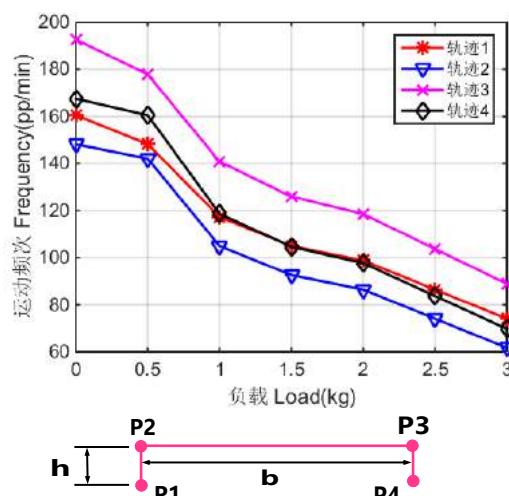
- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

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

- ◆ 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

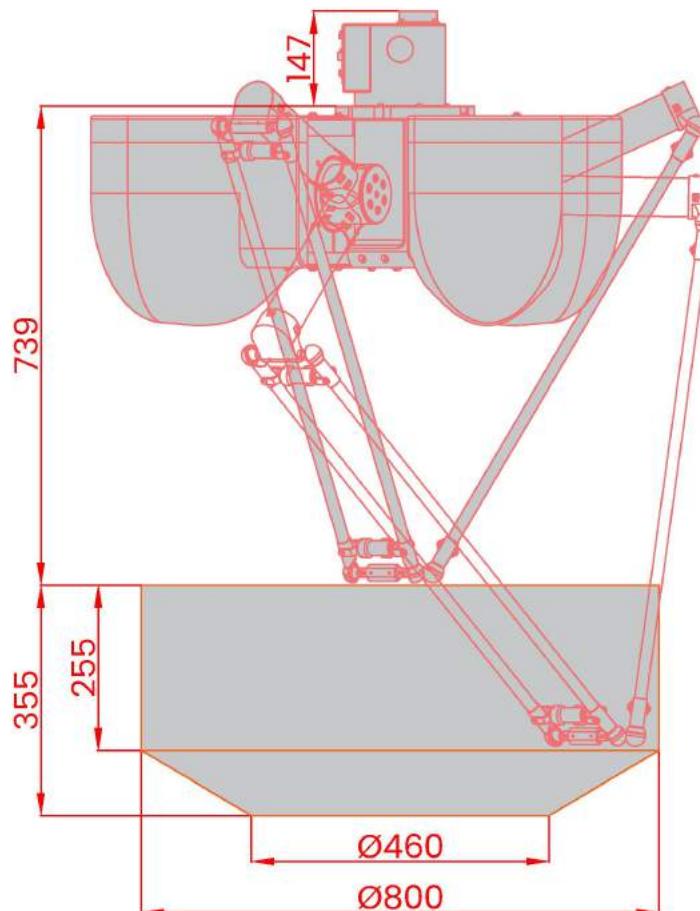


P2 P3  
h b P1 P4

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

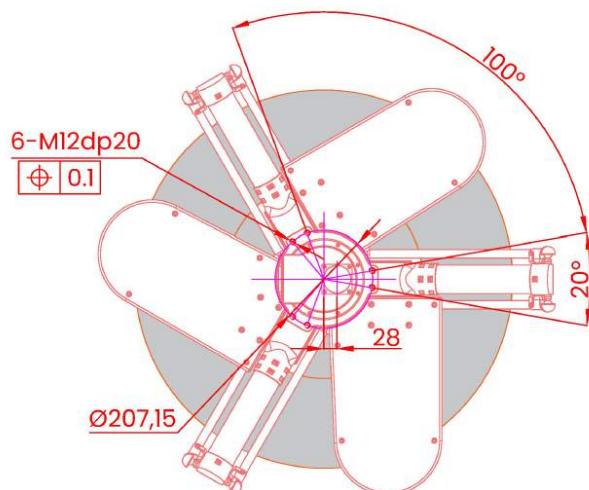
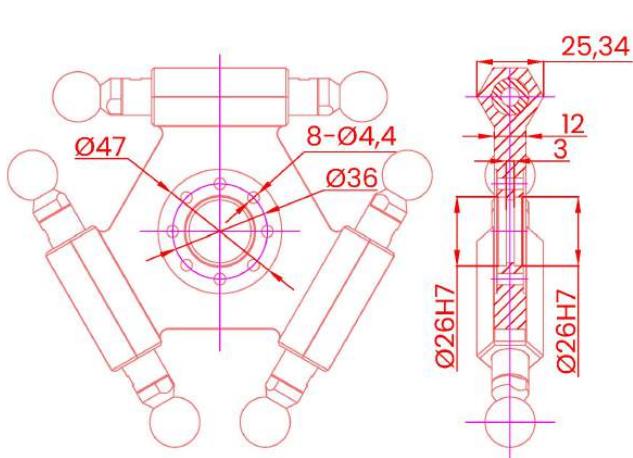
特别注意：图中节拍时间在实际条件下测得，但根据实际运用情况的不同（工具数据、路径半径、夹具启动等），节拍时间也会发生变化。

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



法兰 Flange (mm)

基座安装 Base installation (mm)



## D3W-1100-PO

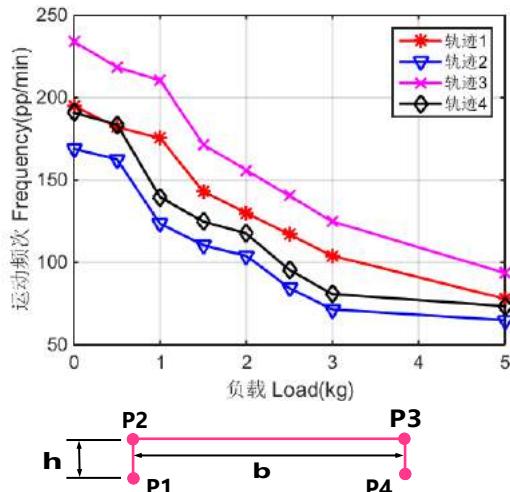


型号 Type		D3W-1100-PO
轴数 Axes		3
最大负载 Payload		5kg
机器人本体 Manipulator	重量 Weight	88kg
	工作空间直径 Diameter	1100mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	—
旋转范围 Rotation range		—
允许负载最大旋转惯量 Allowable maximum moment of inertia		—
主动臂角度范围 Angle range of actuated arm	上摆 Up	32.5°
	下摆 Down	68.5°
输入电源 Power supply		三相 Three-phase 380VAC -10%~+10%, 49~61HZ
电源容量 Power capacity		10KVA
额定功率 Rated Power		6kw
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

**高速度** High speed  
**高稳定性** High stability  
**大空间** Large space  
**经济实用** 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 dismounted.
- ◆ 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.

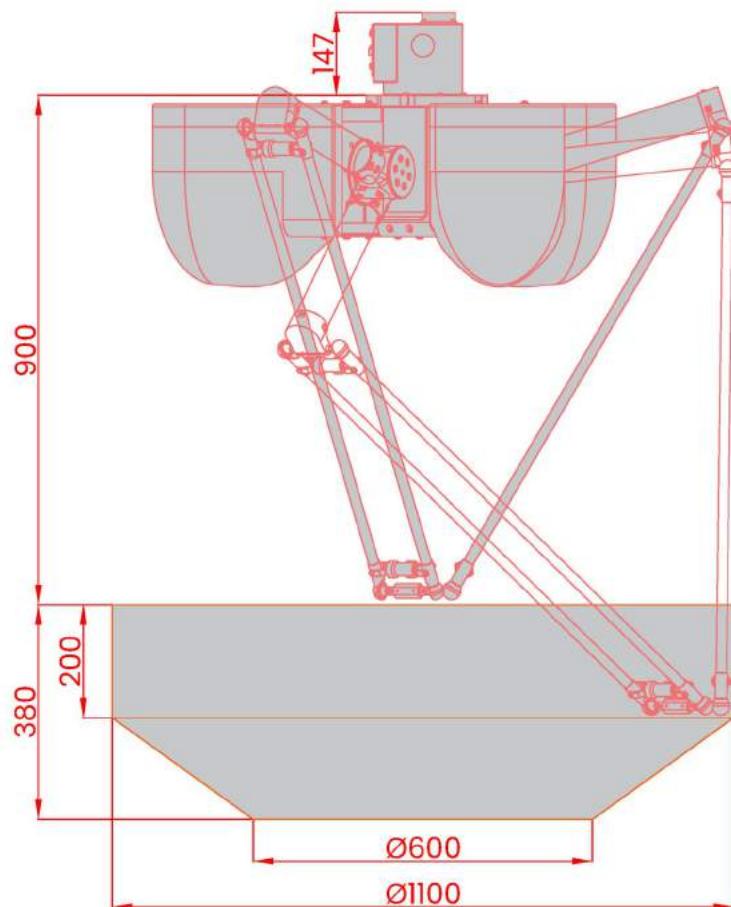
#### ● 负载-频次 Load-Frequency



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。

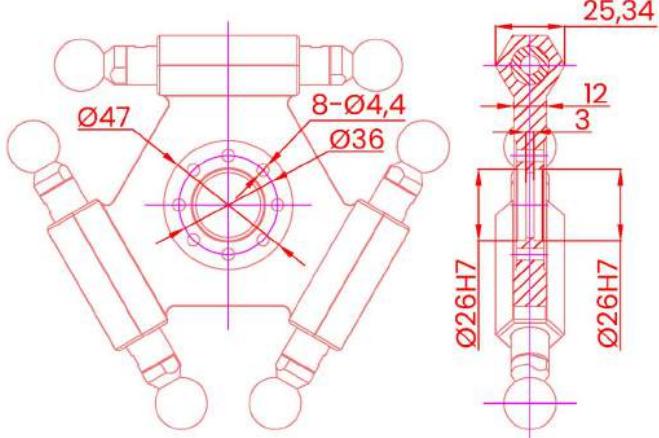
外形尺寸及运动范围  
Outline dimensions and Working range (mm)



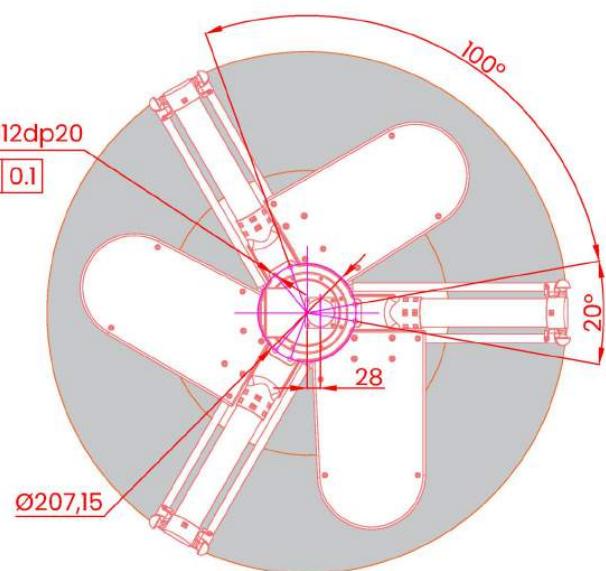
**说明:**  
图示下部加深部分为机器人动平台几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

**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-PO



**高速度**

**High speed**

**高稳定性**

**High stability**

**大空间**

**Large space**

**低高度**

**Lower Height**

型号 Type		D3W-1200-PO
轴数 Axes		3
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	73.6kg
	工作空间直径 Diameter	1200mm
重复定位精度 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 Allowable maximum moment of inertia		—
主动臂角度范围 Angle range of actuated arm	上摆 Up	33°
	下摆 Down	87°
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	6kw	
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	

- ◆ 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.

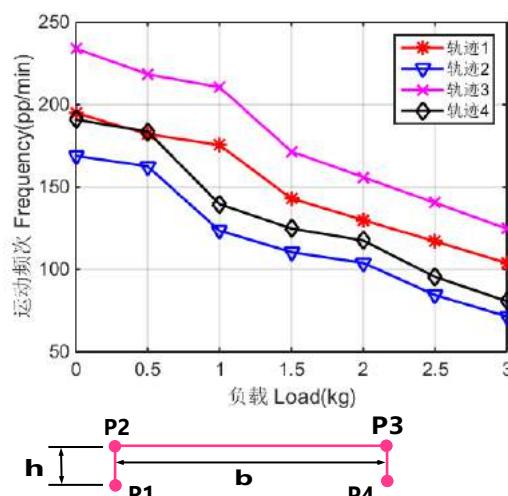
- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

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

- ◆ 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.

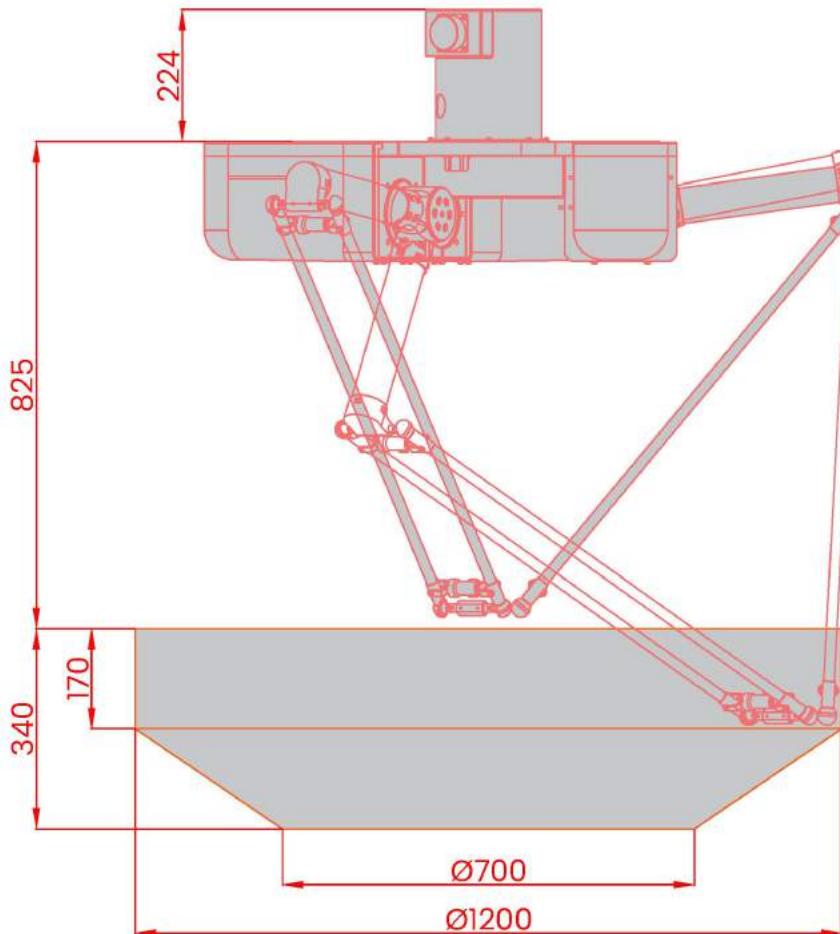
### ● 负载-频次 Load-Frequency



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。

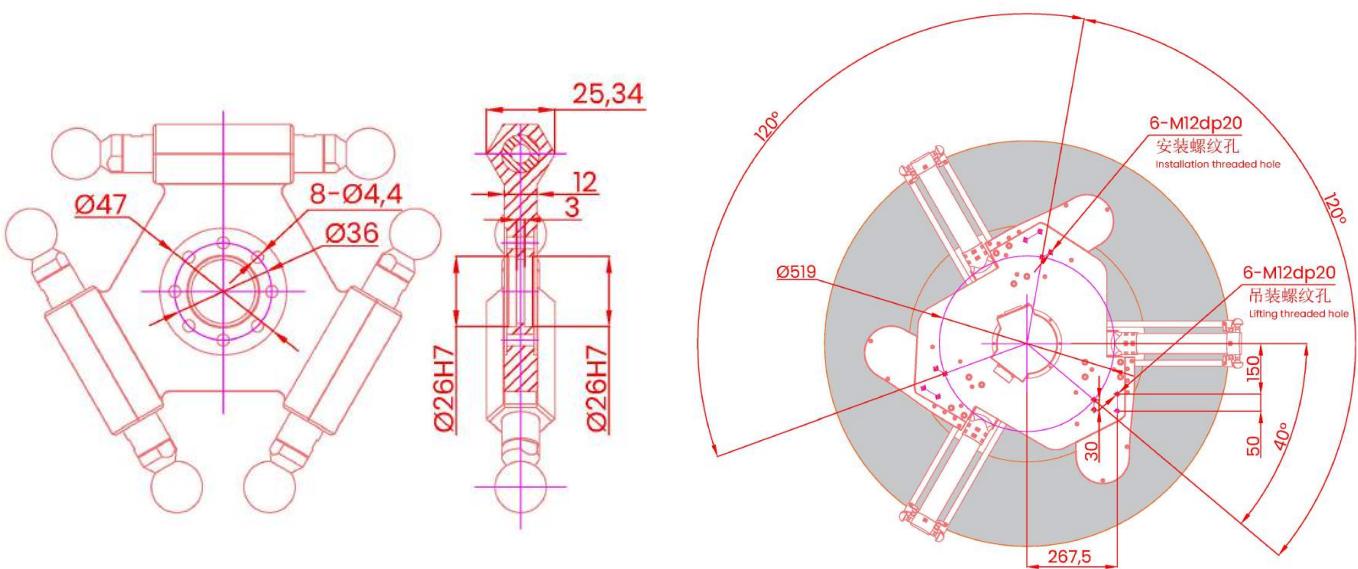
外形尺寸及运动范围  
Outline dimensions and Working range (mm)



**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

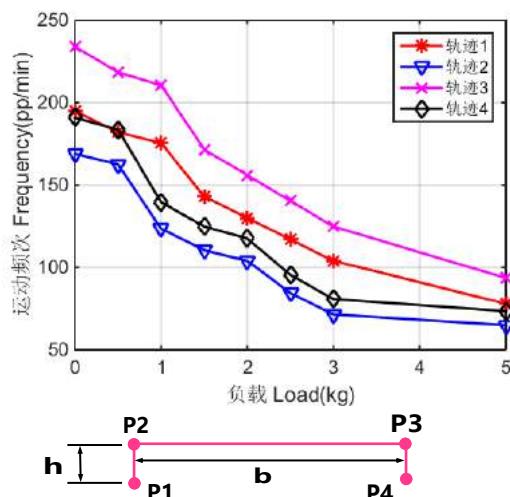


**高速度** High speed  
**高稳定性** High stability  
**大空间** Large space  
**经济实用** Economic & Practical

型号 Type		D3W-1300-P0
轴数 Axes		3
最大负载 Payload		5kg
机器人本体 Manipulator	重量 Weight	90kg
	工作空间直径 Diameter	1300mm
重复定位精度 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 Allowable maximum moment of inertia		—
主动臂角度范围 Angle range of actuated arm	上摆 Up	31.5°
	下摆 Down	74°
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		6kw
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

- ◆ 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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- ◆ 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  
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- ◆ 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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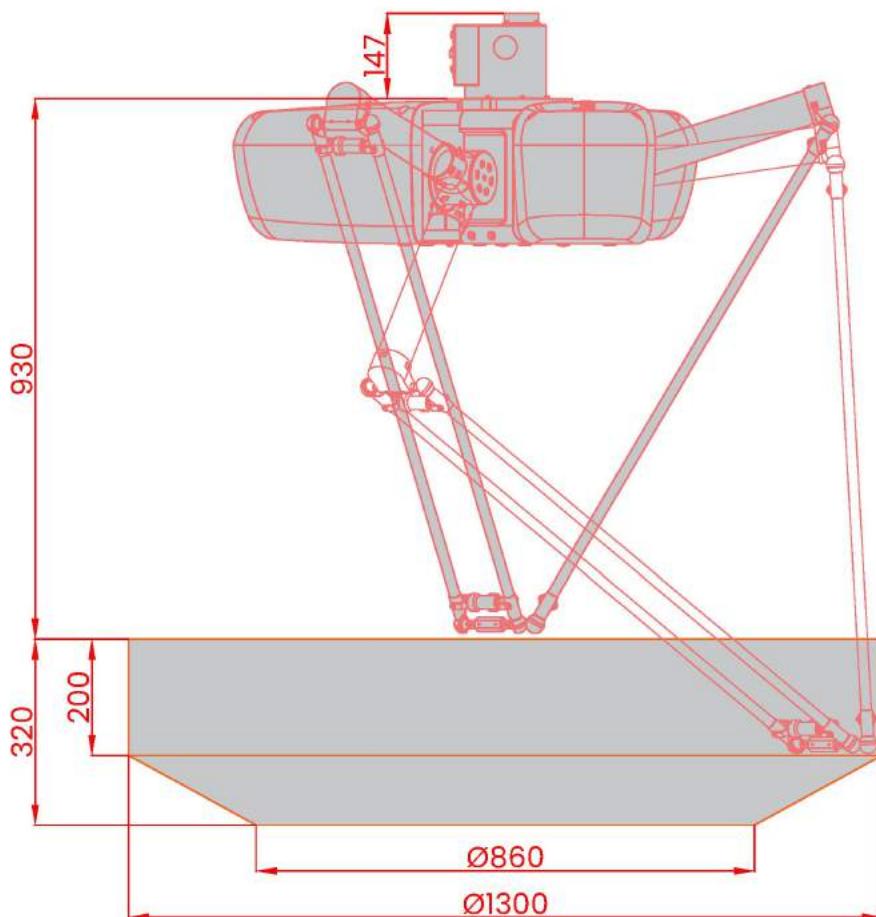
#### ● 负载-频次 Load-Frequency



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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	$h=25, b=500$

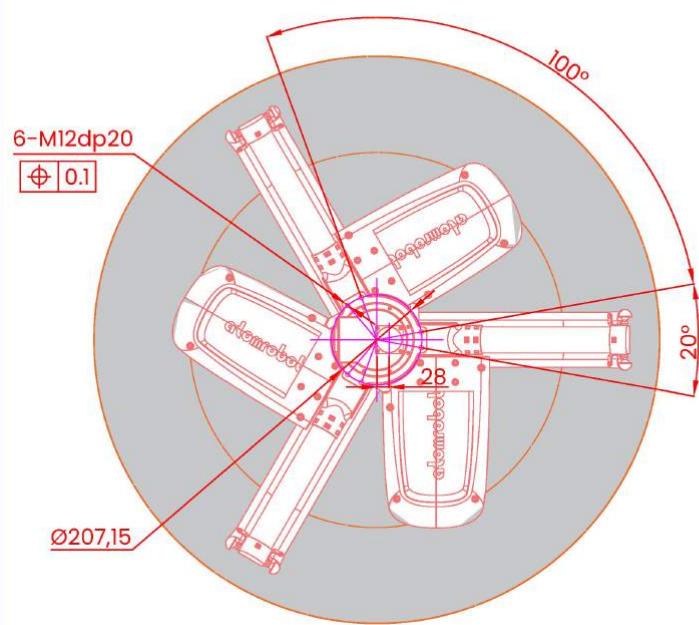
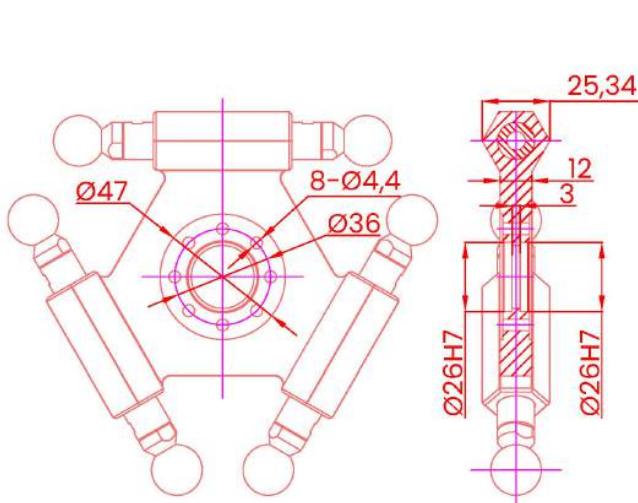
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外形尺寸及运动范围  
Outline dimensions and Working range (mm)



法兰 Flange (mm)

基座安装 Base installation (mm)



## D3W-1400-PO



**高速度** High speed  
**高稳定性** High stability  
**大空间** Large space  
**经济实用** Economic & Practical

<b>型号 Type</b>		D3W-1400-PO
<b>轴数 Axes</b>		3
<b>最大负载 Payload</b>		3kg
<b>机器人本体 Manipulator</b>	<b>重量 Weight</b>	91.5kg
	<b>工作空间直径 Diameter</b>	1400mm
<b>重复定位精度 repeatability</b>	<b>位置 Position</b>	0.05mm
	<b>旋转 Rotation</b>	—
<b>旋转范围 Rotation range</b>		—
<b>允许负载最大旋转惯量 Allowable maximum moment of inertia</b>		—
<b>主动臂角度范围 Angle range of actuated arm</b>	<b>上摆 Up</b>	22°
	<b>下摆 Down</b>	76°
<b>输入电源 Power supply</b>	三相 Three-phase 380VAC -10%~+10%, 49~61HZ	
<b>电源容量 Power capacity</b>	10KVA	
<b>额定功率 Rated Power</b>	6kw	
<b>保存温度 Storage temperature</b>	-10°C~70°C	
<b>工作环境 Work environment</b>	-10°C~50°C, RH≤80%	
<b>防护等级 Protection</b>	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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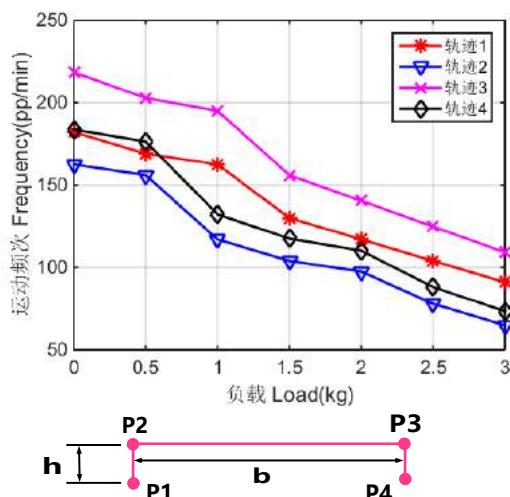
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- ◆ 非常适于食品、医药等行业的高速生产作业, 主要用于小型物料的装配、搬运、分拣等

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.

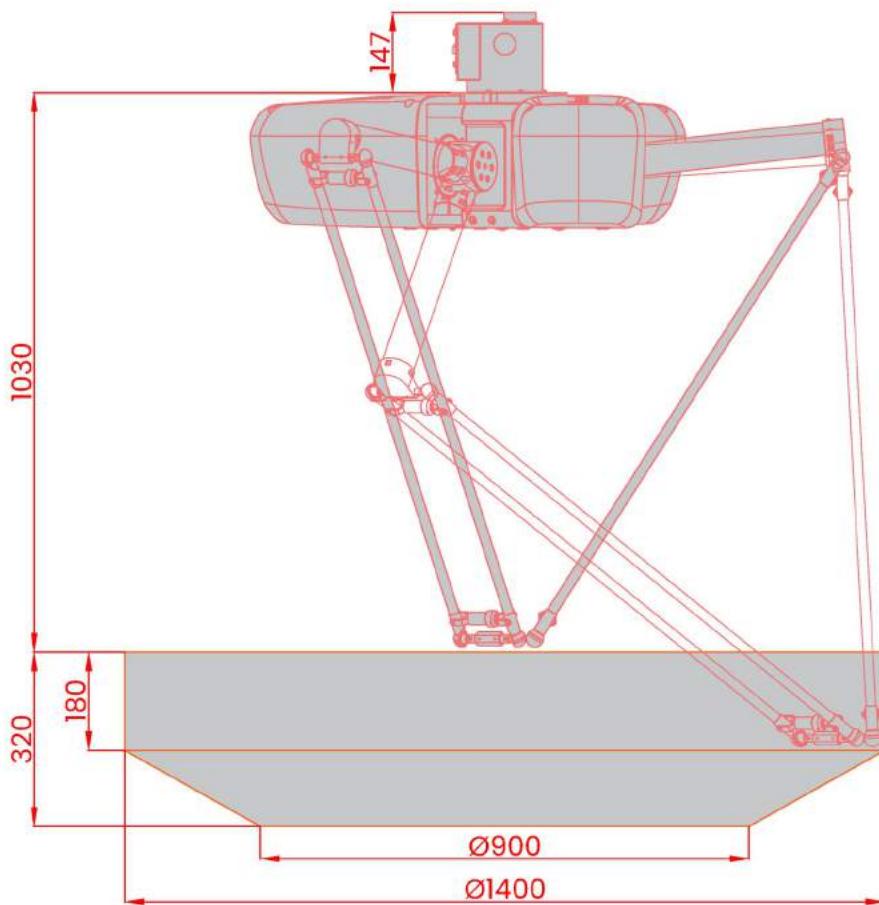
### ● 负载-频次 Load-Frequency



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

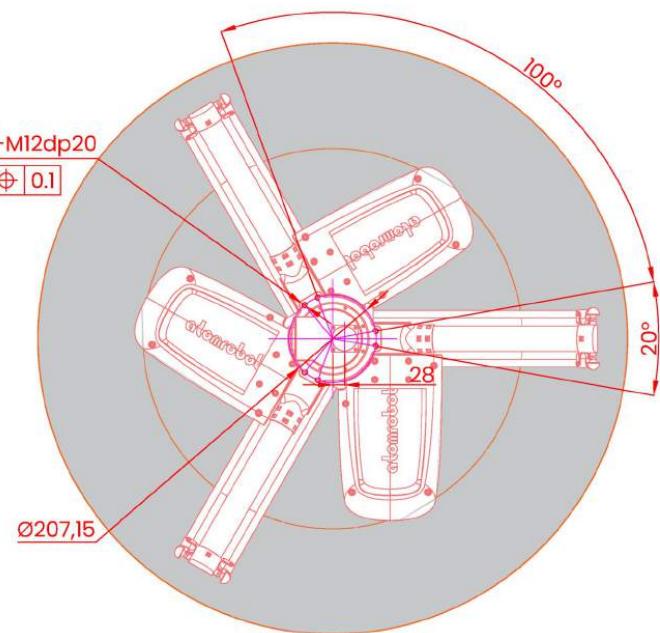
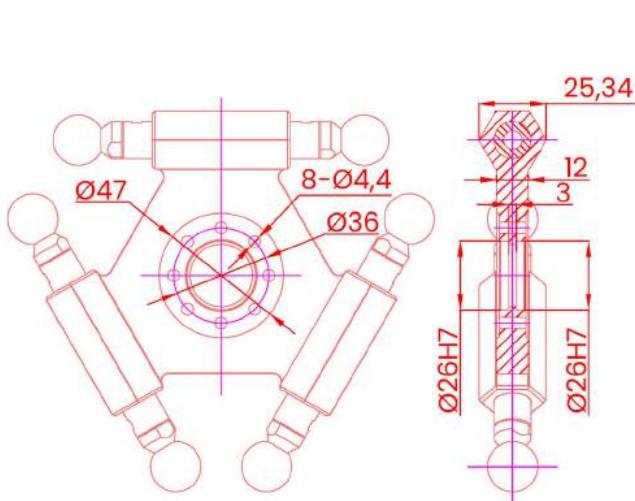
**特别注意:** 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同(工具数据、路径半径、夹具启动等), 节拍时间也会发生变化。

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



法兰 Flange (mm)

基座安装 Base installation (mm)



## D3W-1600-PO

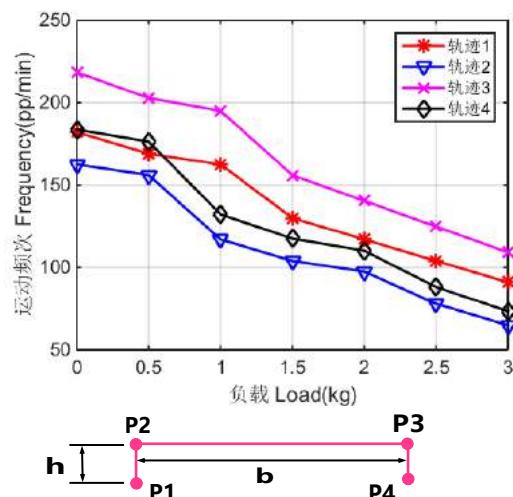


**高速度** High speed  
**高稳定性** High stability  
**大空间** Large space  
**经济实用** Economic & Practical

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

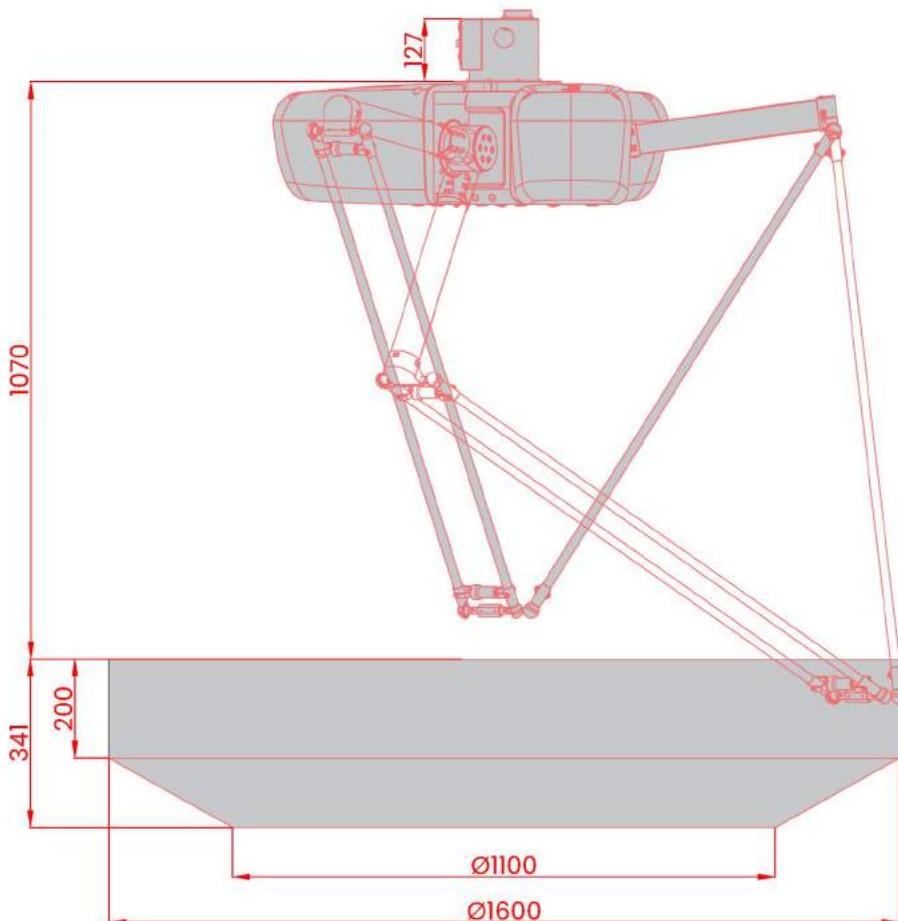
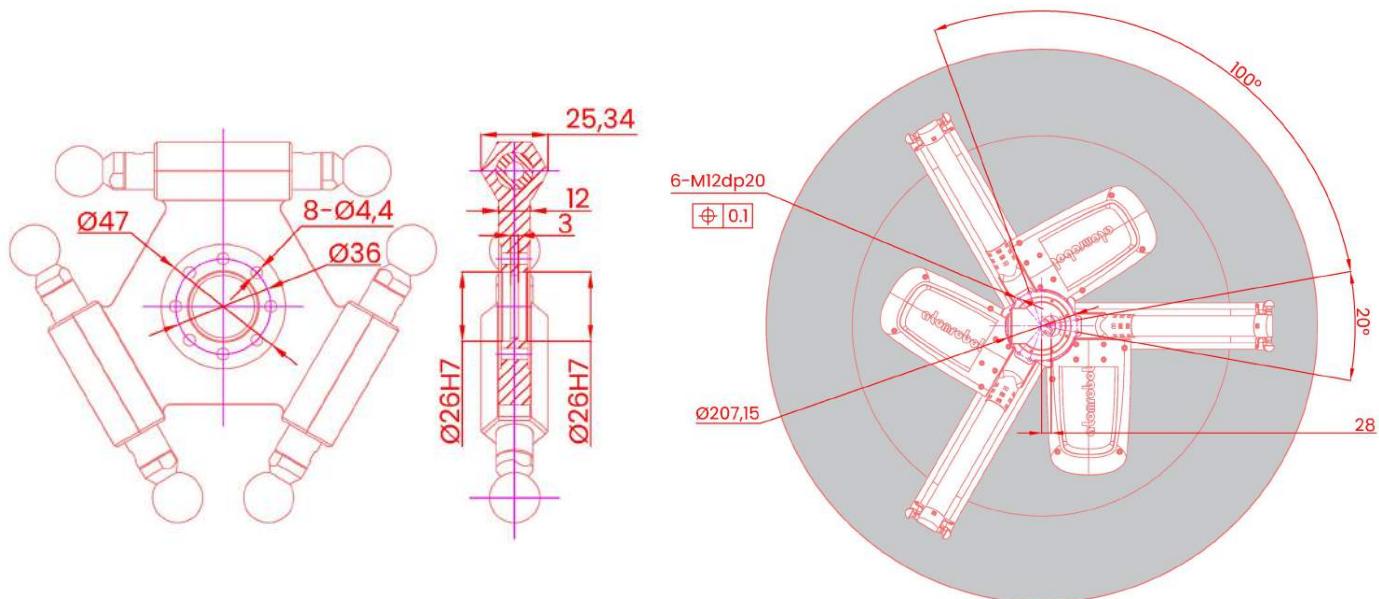
● **负载-频次 Load-Frequency**



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)**

**法兰 Flange (mm)****基座安装 Base installation (mm)**

## D3W-1100-P15



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

**高稳定性****High stability****大空间****Large space****重负载****Heavy load****经济实用****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.

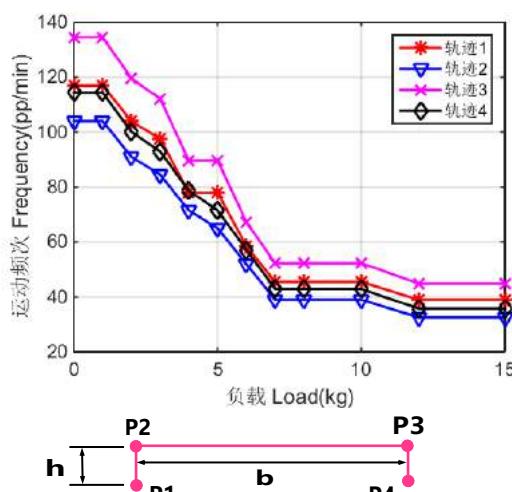
- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

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

- ◆ 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.

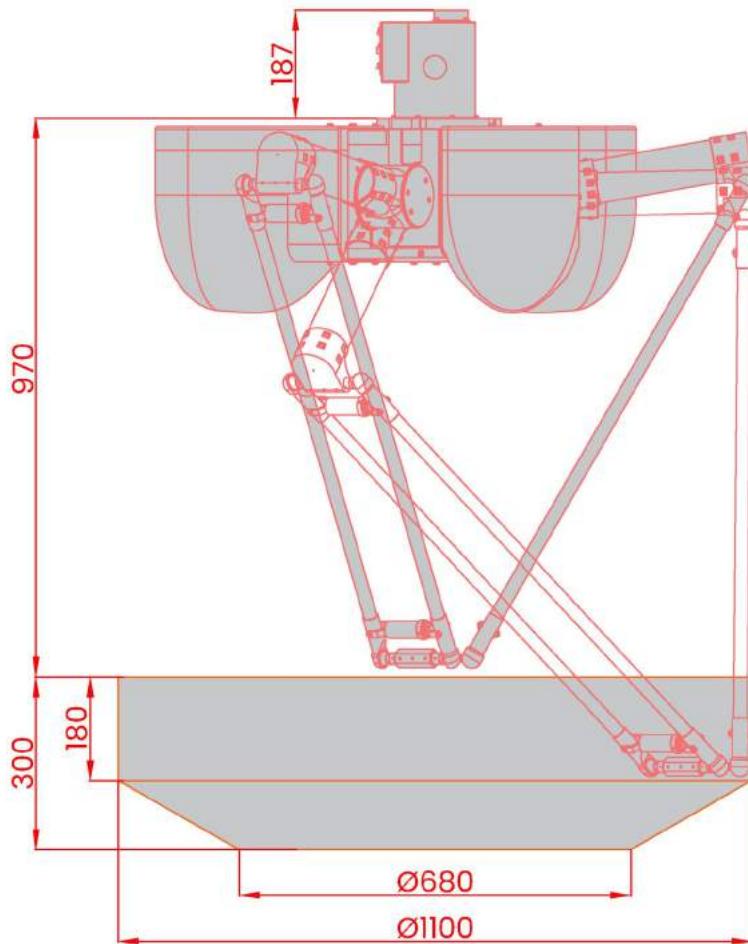
### ● 负载-频次 Load-Frequency



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	$h=25, b=500$

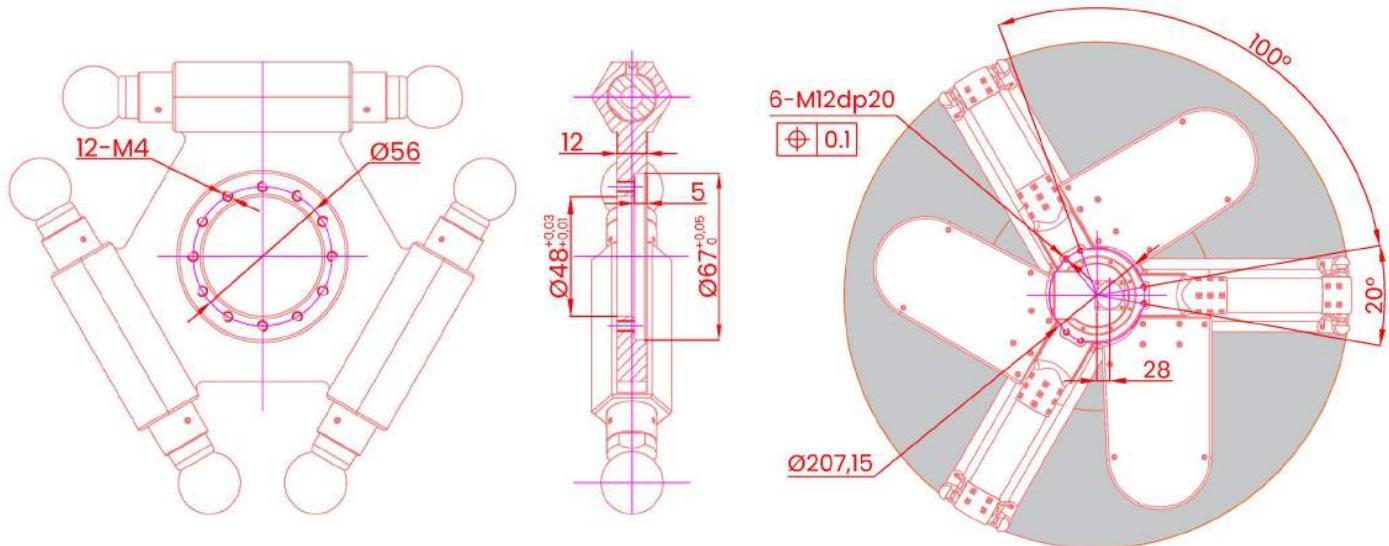
特别注意：图中节拍时间在实际条件下测得，但根据实际运用情况的不同（工具数据、路径半径、夹具启动等），节拍时间也会发生变化。

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



法兰 Flange (mm)

基座安装 Base installation (mm)



## D3W-1400-P15



**高稳定性**

**High stability**

**大空间**

**Large space**

**重负载**

**Heavy load**

**经济实用**

**Economic & Practical**

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

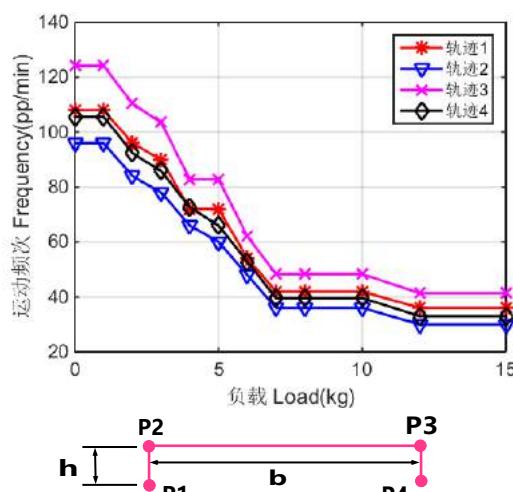
- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

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

- ◆ 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.

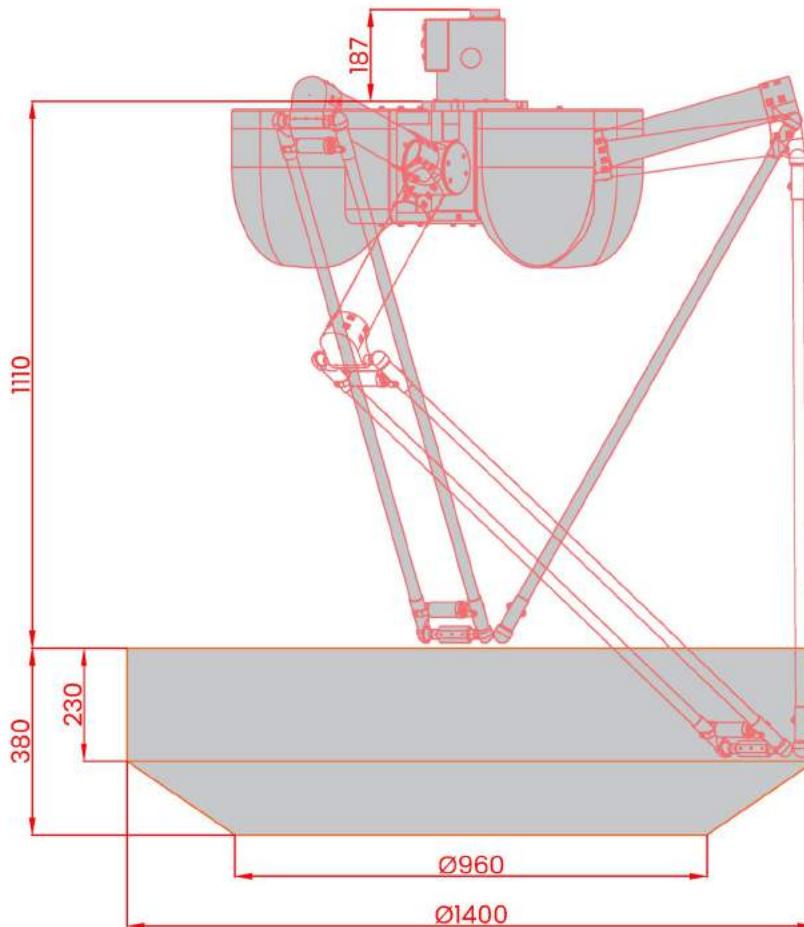
### ● 负载-频次 Load-Frequency



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)

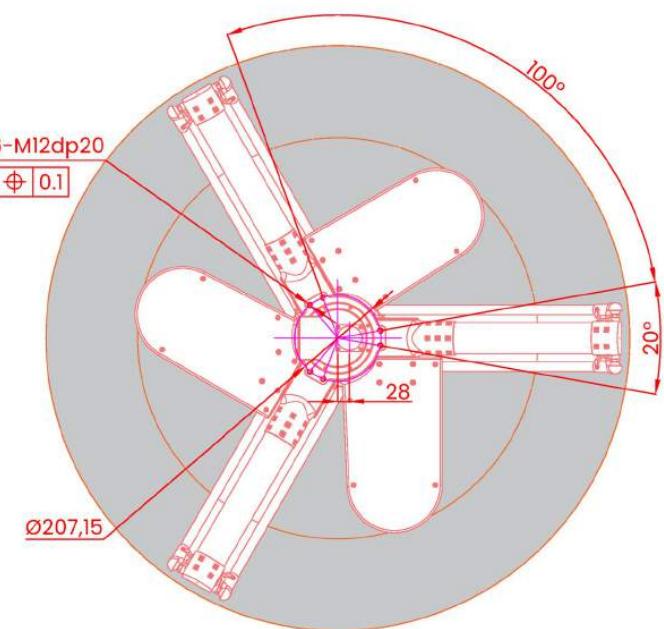
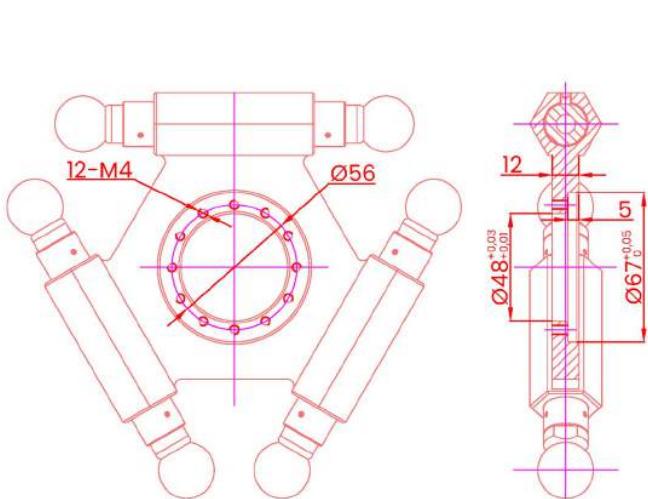


**说明:**  
图示下部加深部分为  
机器人动平台几何中  
心的运动范围, 上部  
为圆柱空间, 并在下  
部向内收敛。

**Instruction:**  
The bottom gray  
part is the work-  
place of the cen-  
ter point of mov-  
ing platform,  
which is com-  
posed of a cylin-  
der at the top and  
a circular truncat-  
ed cone at the  
bottom.

法兰 Flange (mm)

基座安装 Base installation (mm)



## D3W-1600-P15



高稳定性

**High stability**

大空间

**Large space**

重负载

**Heavy load**

经济实用

**Economic & Practical**

型号 Type		D3W-1600-P15
轴数 Axes		3
最大负载 Payload		15kg
机器人本体 Manipulator	重量 Weight	133kg
	工作空间直径 Diameter	1600mm
重复定位精度 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 Allowable maximum moment of inertia		—
主动臂角度范围 Angle range of actuated arm	上摆 Up	23°
	下摆 Down	71.5°
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	6kw	
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	

- ◆ 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.

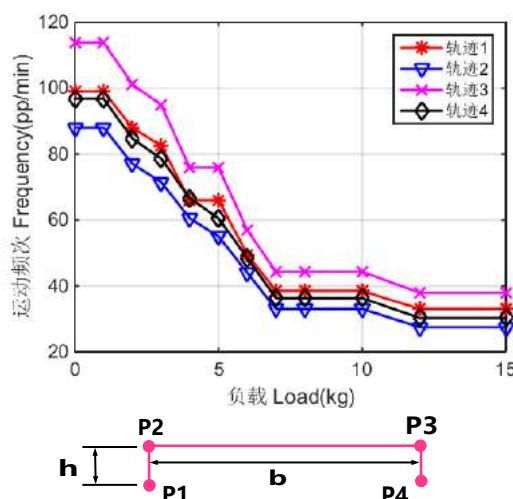
- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

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

- ◆ 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.

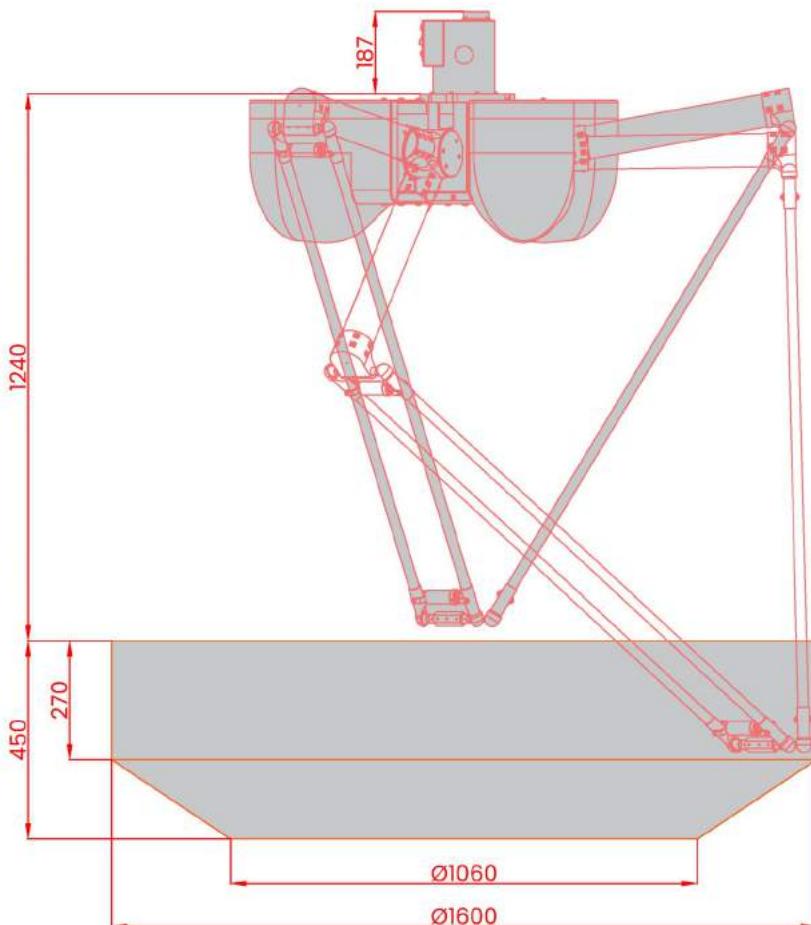
- 负载-频次 Load-Frequency



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)**

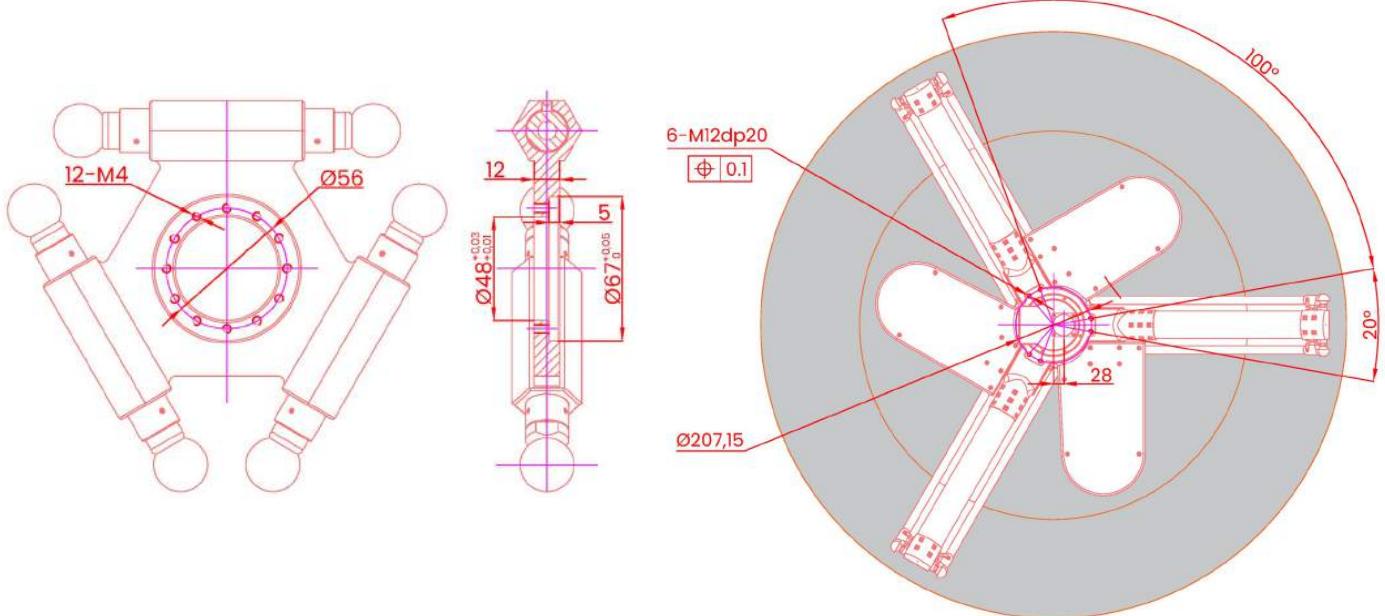


**说明:**  
 图示下部加深部分为机器人动平台几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

**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

**High stability**

大空间

**Large space**

超重负载

**Super-heavy load**

型号 Type		D3W-1200-P25
轴数 Axes		3
最大负载 Payload		25kg
机器人本体 Manipulator	重量 Weight	143kg
	工作空间直径 Diameter	1200mm
重复定位精度 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 Allowable maximum moment of inertia		—
主动臂角度范围 Angle range of actuated arm	上摆 Up	33.8°
	下摆 Down	87.8°
输入电源 Power supply	三相 Three-phase 380VAC -10%~+10%, 49~61HZ	
电源容量 Power capacity	15KVA	
额定功率 Rated Power	9kw	
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	

- ◆ 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.

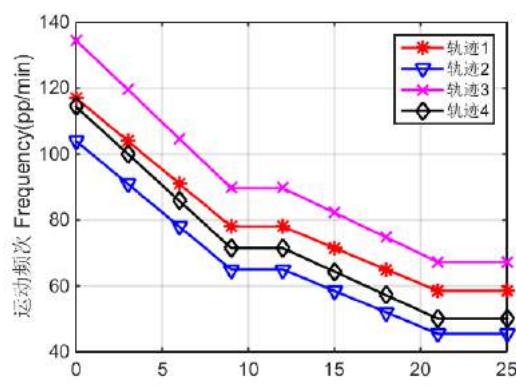
- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

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

- ◆ 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.

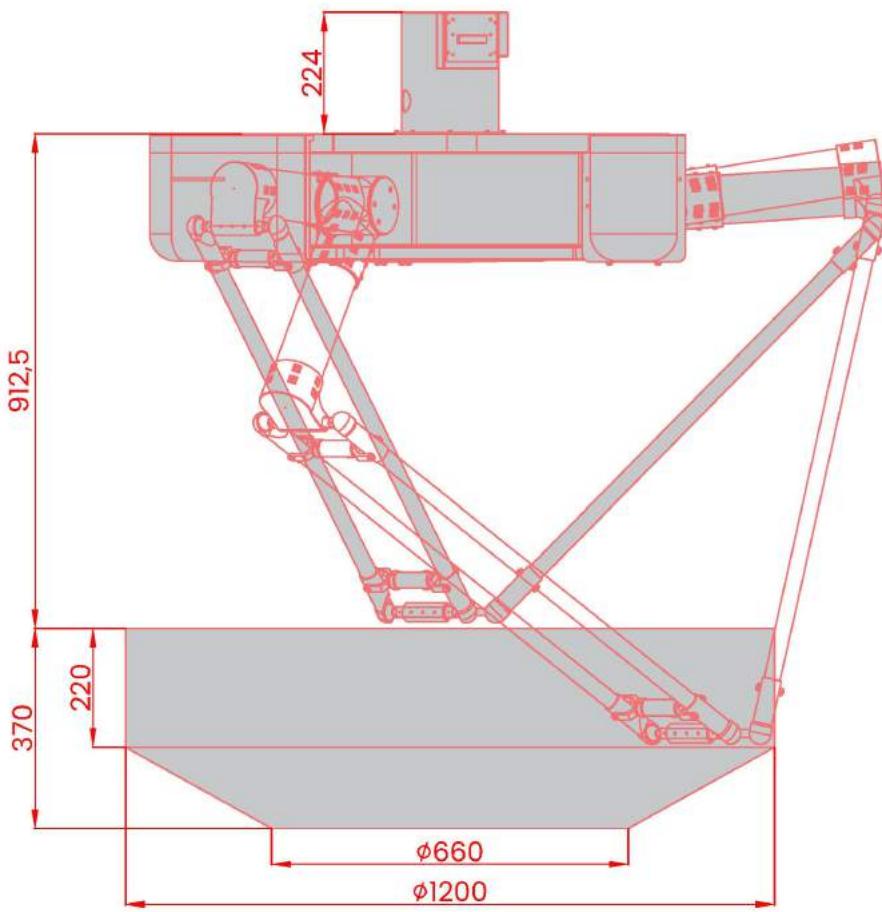
### ● 负载-频次 Load-Frequency



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)



**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)

