

并联机器人

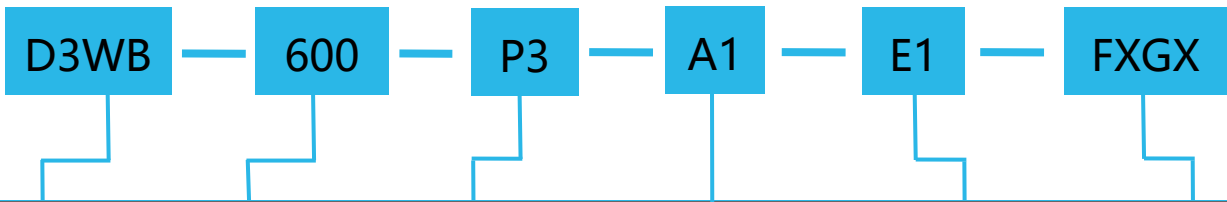
选型手册

Parallel robot selection Manual

D3WB

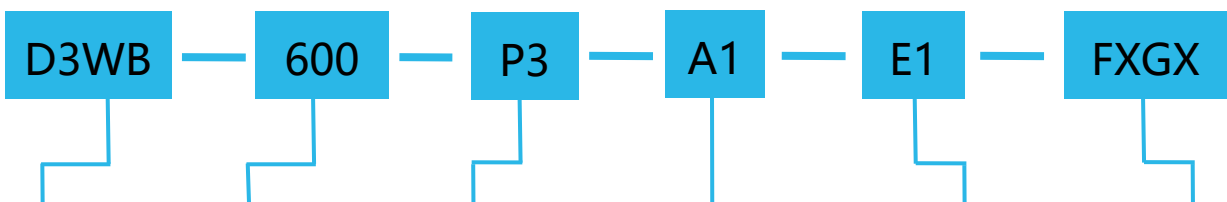


● 型号和符号



机型	型号	负载	控制器类型	控制柜类型	视觉
D3WB	450	P3: 3KG P25: 25KG	A1: ATOMCONTROL A2: KEBA CONTROL	E1: ATOM-01 E2: ATOM-02 E3: 定制	F0G0: 无视觉 FXGX: 有视觉
	600				
	1000				
	1200				

● Model and Symbol



Robot type	Type	Load Type	Control Type	Control Cabinet	Vision Type
D3WB	450	P3: 3KG P25: 25KG	A1: ATOMCONTROL A2: KEBA CONTROL	E1: ATOM-01 E2: ATOM-02 E3: Custom	F0G0: Without vision FXGX: With vision
	600				
	1000				
	1200				

D3WB-450-P3



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	D3WB-450-P3	
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	450mm
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.

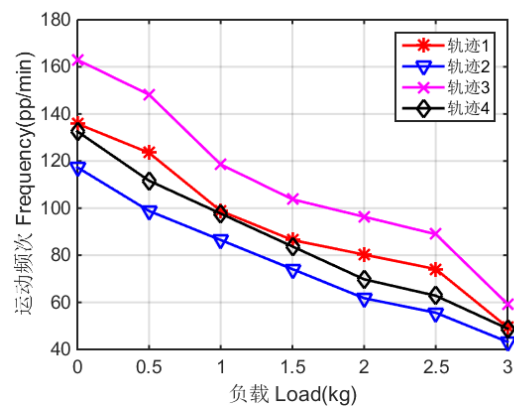
- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

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

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

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

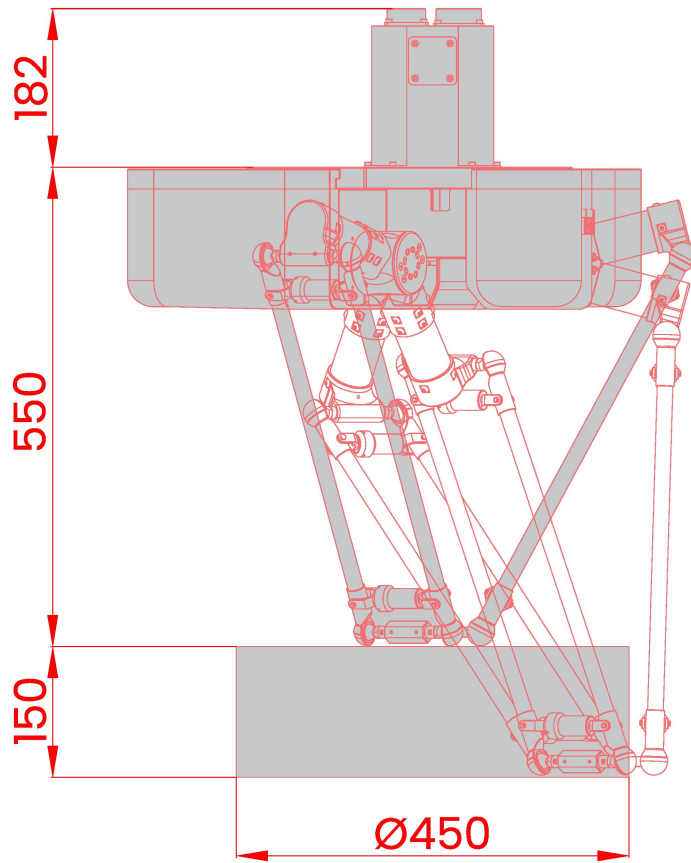
● 负载-频次 Load-Frequency



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)

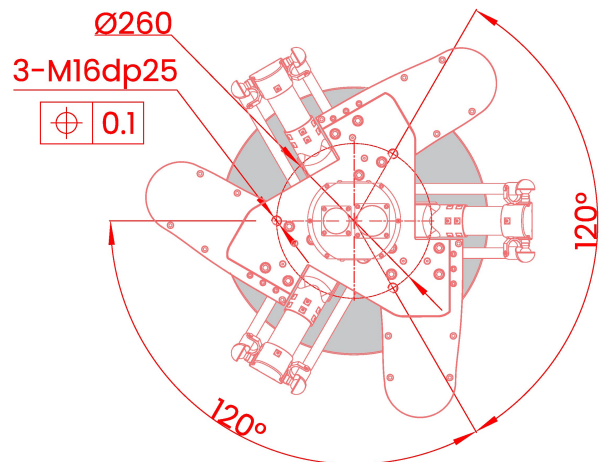
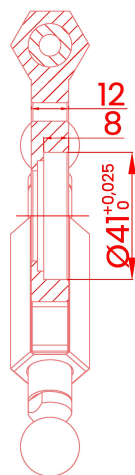
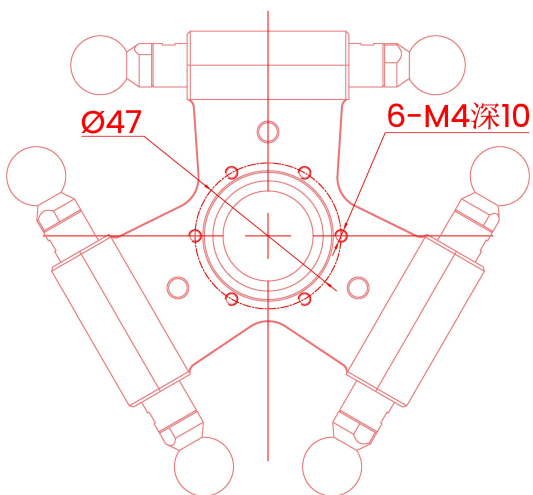


说明:
 图示下部加深部分为机器人动平台几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

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)



D3WB-600-P3



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		D3WB-600-P3
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	2.3kw	
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.

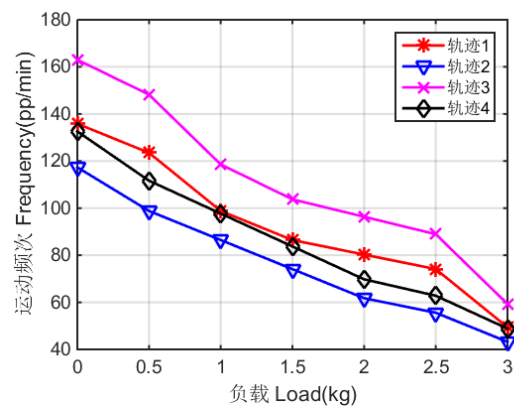
- ◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

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

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

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

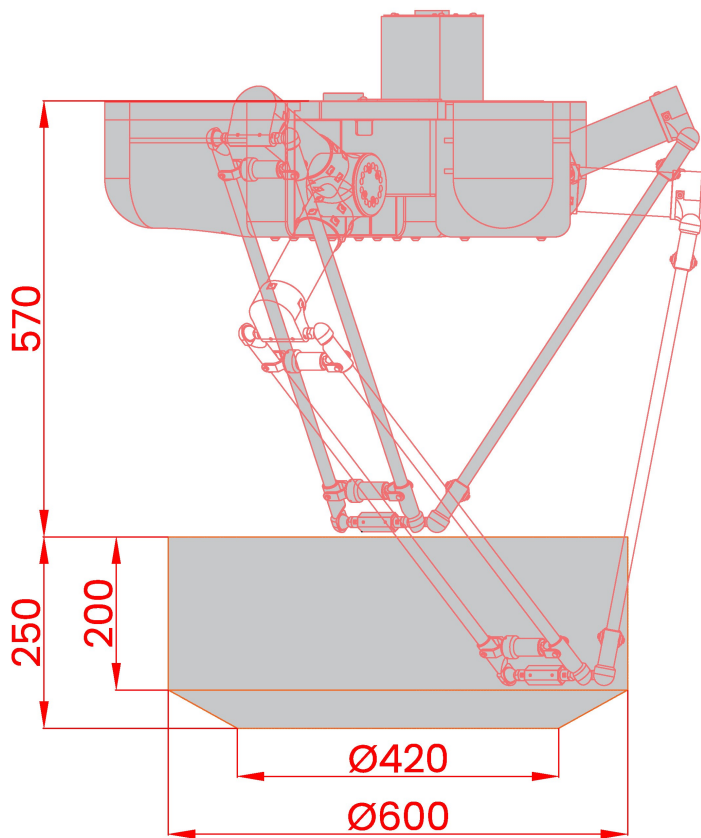
● 负载-频次 Load-Frequency



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)

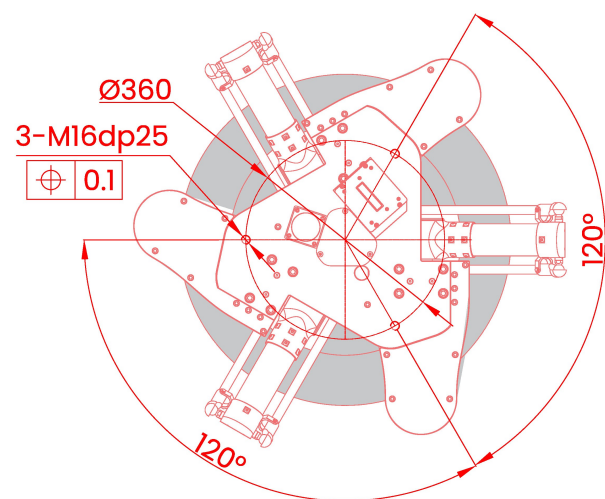
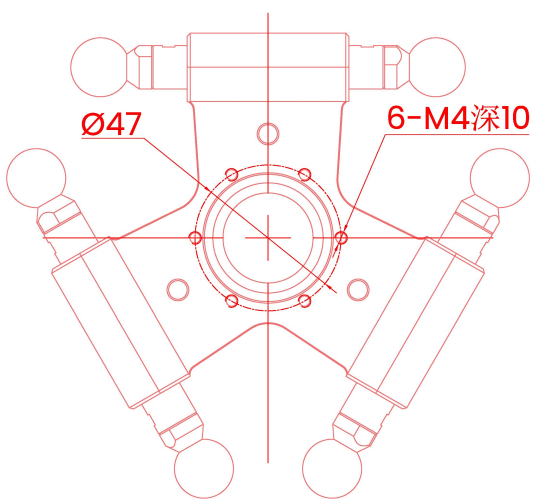


说明:
图示下部加深部分为机器人动平台几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

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)



D3WB-1000-P3



高速度
高稳定性
大空间
低高度

High speed
High stability
Large space
Lower Height

型号 Type		D3WB-1000-P3
轴数 Axes		3
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	70.6kg
	工作空间直径 Diameter	1000mm
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.

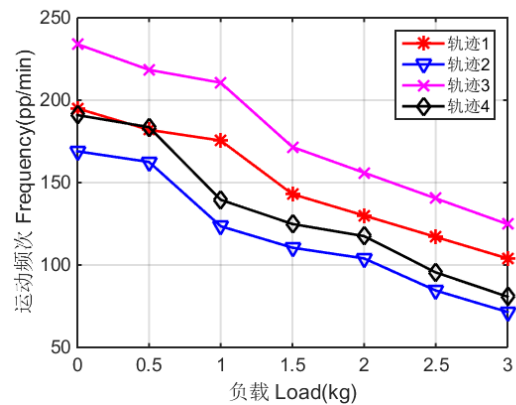
◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

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

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

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

● 负载-频次 Load-Frequency

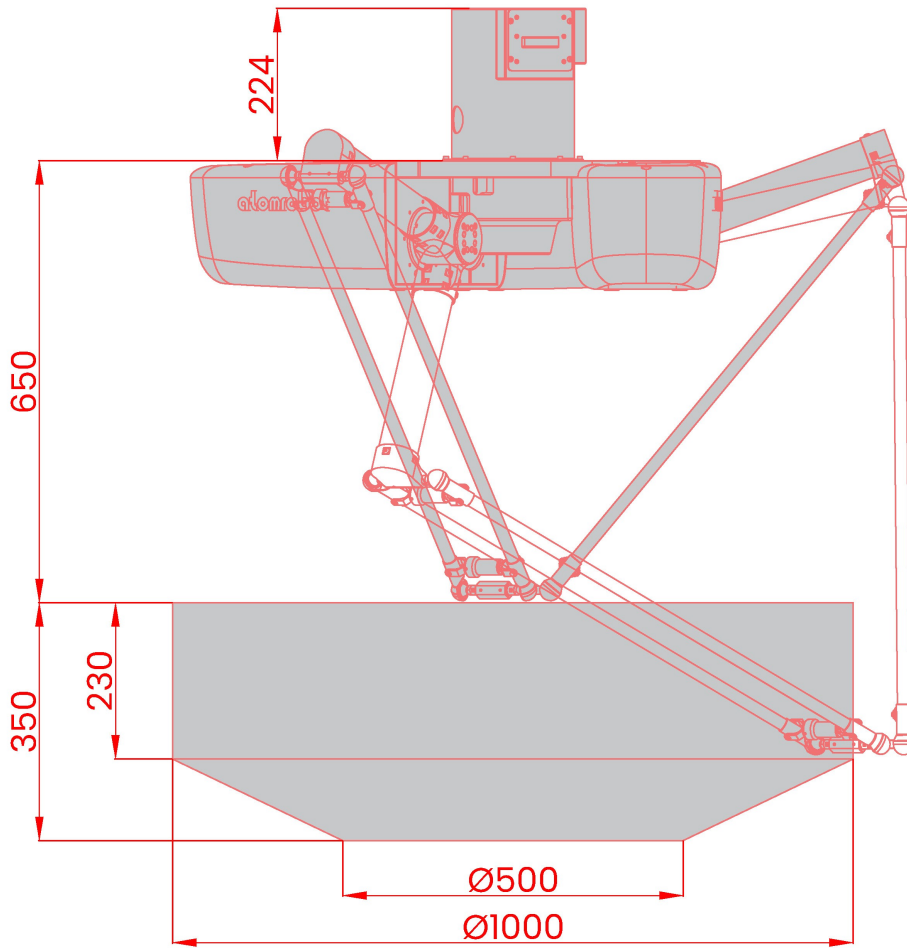


名称 Name	循环模式 Model	运动距离 Distance
轨迹1 Trajectory1	P1 → P2 → P3 → P4 → P3 → P2 → P1	h=25, b=305
轨迹2 Trajectory2	P1 → P2 → P3 → P4 → P3 → P2 → P1	h=25, b=500
轨迹3 Trajectory3	P1 → P2 → P3 → P2 → P1	h=25, b=305
轨迹4 Trajectory4	P1 → P2 → P3 → P2 → P1	h=25, b=500

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

外形尺寸及运动范围

Outline dimensions and Working range (mm)



说明:

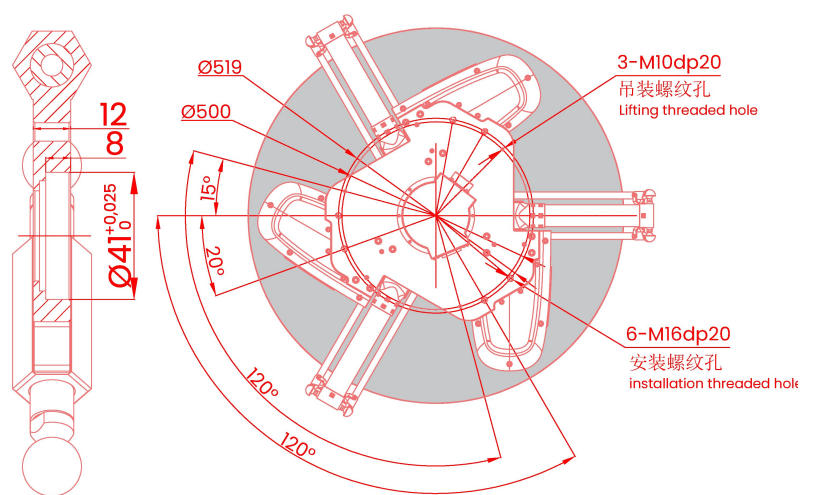
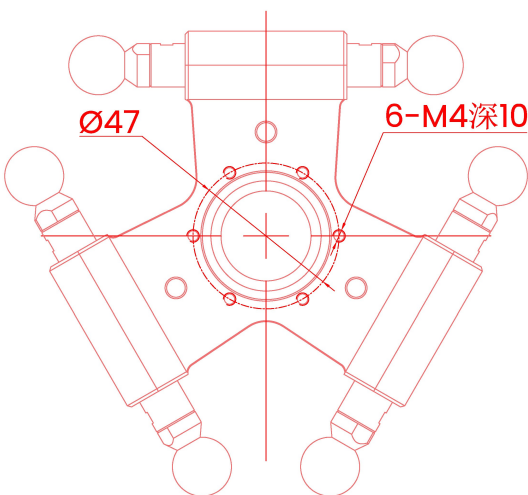
图示下部加深部分为机器人动平台几何中心的运动范围, 上部为圆柱空间, 并在下部向内收敛。

Instruction:

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

法兰 Flange (mm)

基座安装 Base installation (mm)



D3WB-1200-P3



高速度
高稳定性
大空间
低高度

High speed
High stability
Large space
Lower Height

型号 Type		D3WB-1200-P3
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.

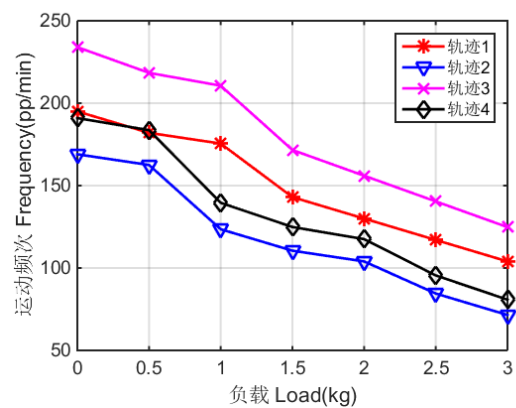
◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

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

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

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

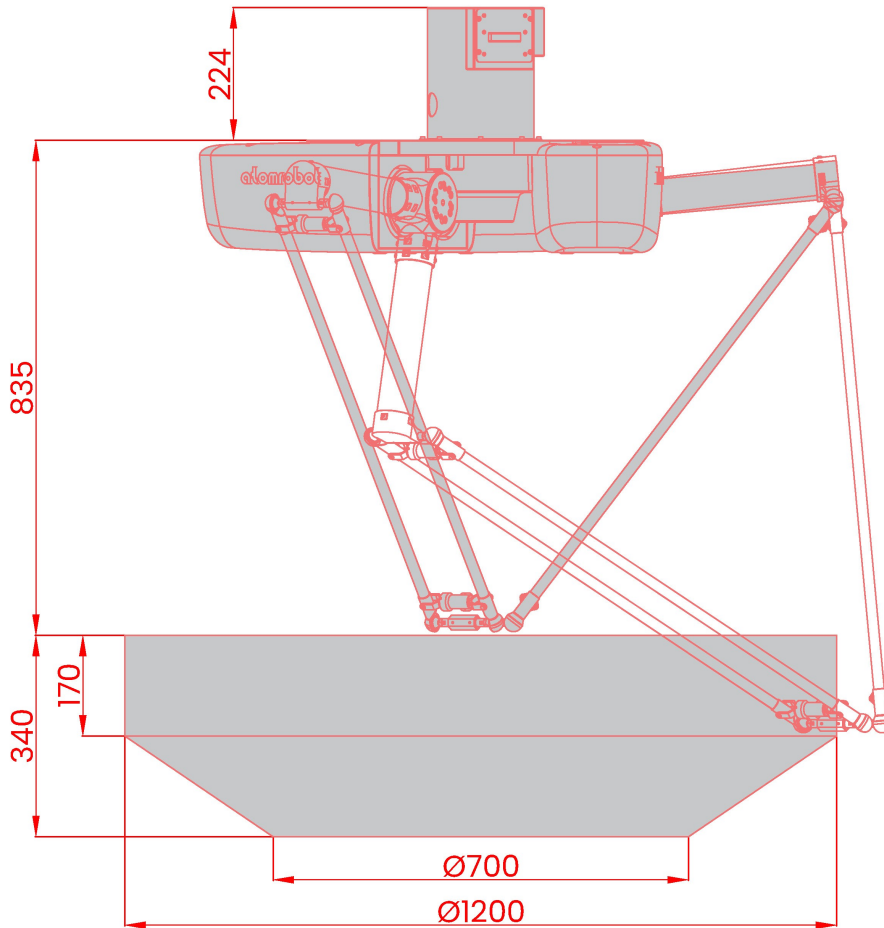
● 负载-频次 Load-Frequency



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

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

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



说明:

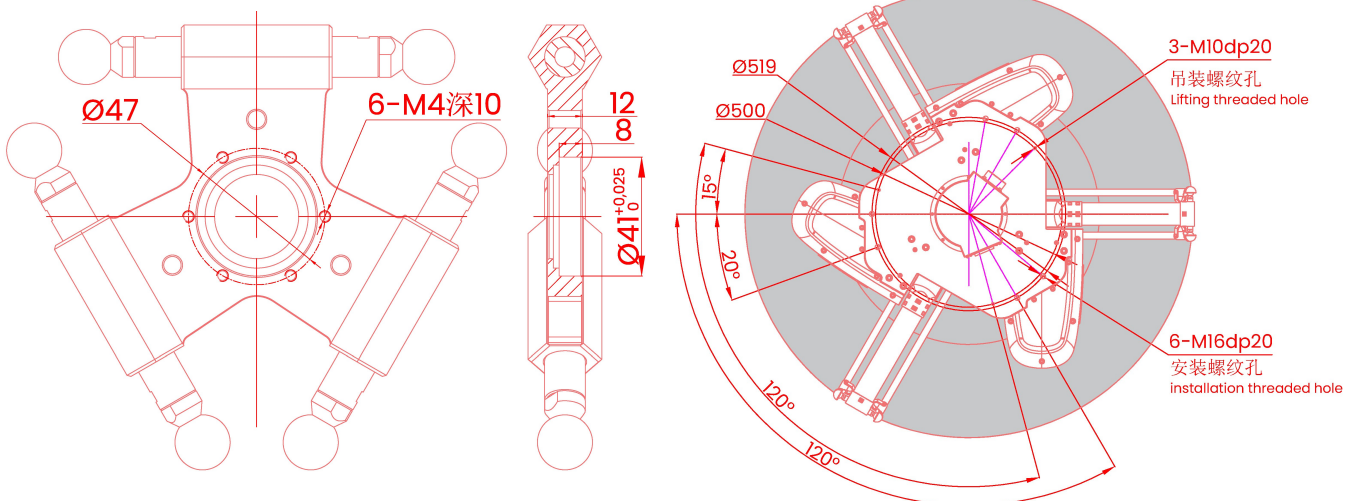
图示下部加深部分为机器人动平台几何中心的运动范围, 上部为圆柱空间, 并在下部向内收敛。

Instruction:

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

法兰 Flange (mm)

基座安装 Base installation (mm)



D3WB-1200-P25



高稳定性
大空间
超重负载

High stability
Large space
Super-heavy load

型号 Type		D3WB-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.

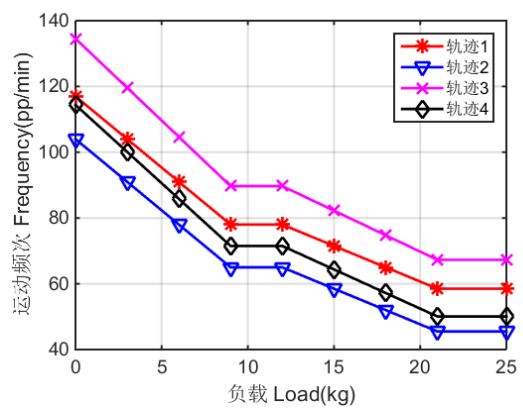
◆ 特殊从动臂压缩弹簧设计, 保证从动臂使用寿命且拆装方便

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

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

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

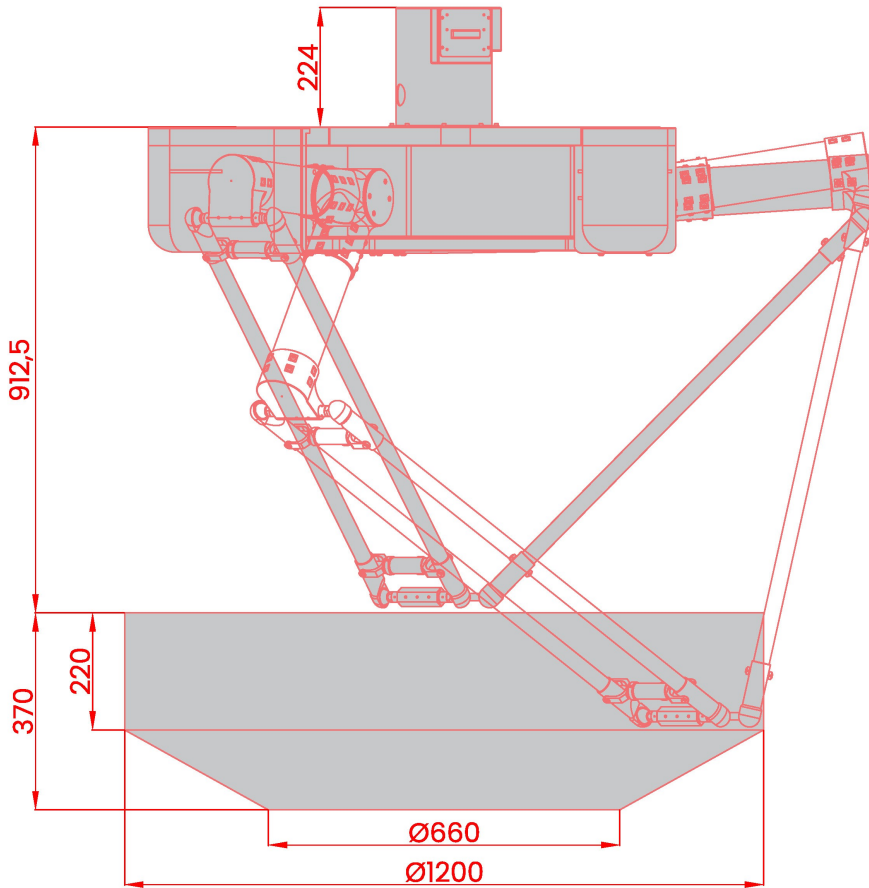
● 负载-频次 Load-Frequency



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)

