

并联机器人

选型手册

Parallel robot selection Manual

D3PMB



● 型号和符号

D3PMB

1100

P3

A1

E1

FXGX

机型	型号	负载	控制器类型	控制柜类型	视觉
D3PMB	450	P3: 3kg	A1: ATOMCONTROL	E1: ATOM-01 E2: ATOM-02 E3: 定制	F0G0: 无视觉 FXGX: 有视觉
	600				
	800				
	1100	P15: 15KG	A2: KEBA CONTROL		
	1200				
	1400				
	1800	P25: 25KG	A2: KEBA CONTROL		
	2200				
	2800				

● Model and Symbol

D3PMB

1100

P3

A1

E1

FXGX

Robot type	Type	Load Type	Control Type	Control Cabinet	Vision Type
D3PMB	450	P3: 3kg	A1: ATOMCONTROL	E1: ATOM-01 E2: ATOM-02 E3: Custom	F0G0: Without vision FXGX: With vision
	600				
	800				
	1100	P15: 15KG	A2: KEBA CONTROL		
	1200				
	1400				
	1800	P25: 25KG	A2: KEBA CONTROL		
	2200				
	2800				

D3PMB-450-P3



高速度 **High speed**
高旋转精度 **High rotation precision**
高稳定性 **High stability**
小巧、敏捷 **Small and Agile**

◆ 标准循环时间小于0.6s,满足追求高速度和最小体积需求

The standard cycle time is less than 0.6s, meeting your pursuit for the high speed and the minimum volume.

◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

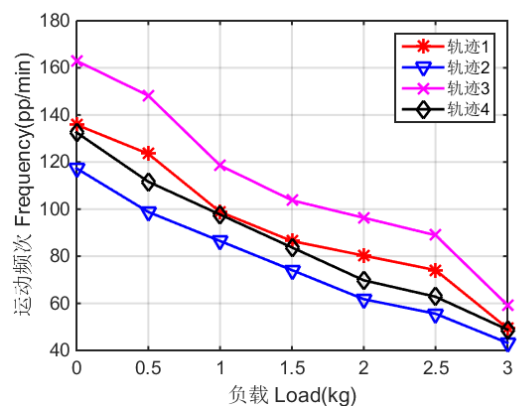
Advanced design of the rotational motor on moving platform, enables the robot to be easily achieve high rotation precision.

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

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

型号 Type		D3PMB-450-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	41kg
	工作空间直径 Diameter	450mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.05°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		$31 \times 10^{-4} \text{kg} \cdot \text{m}^2$
主动臂角度范围 Angle range of actuated arm	上摆 Up	44.2°
	下摆 Down	68.7°
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	1.3kw	
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	

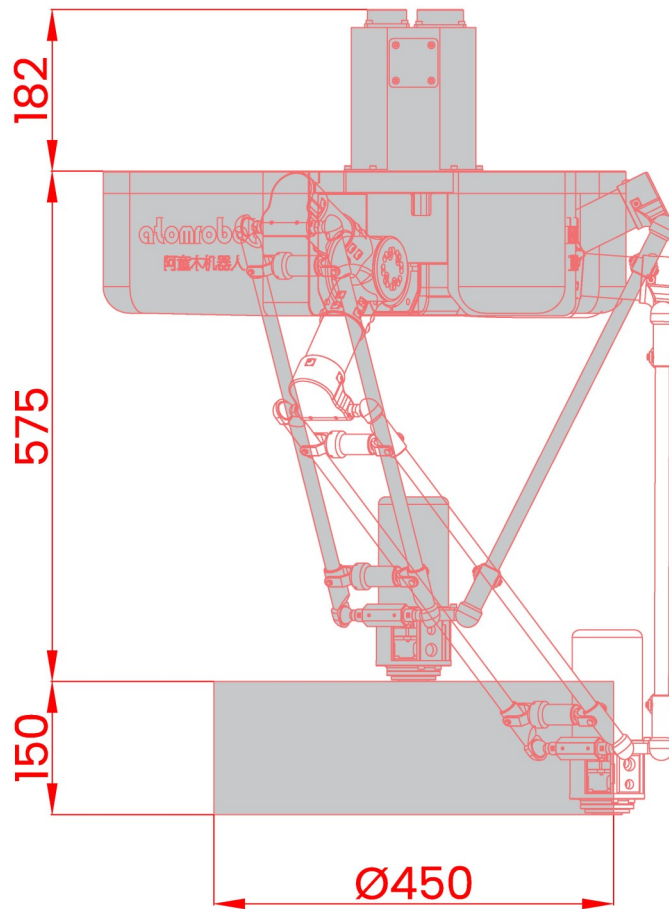
● 负载-频次 Load-Frequency



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。

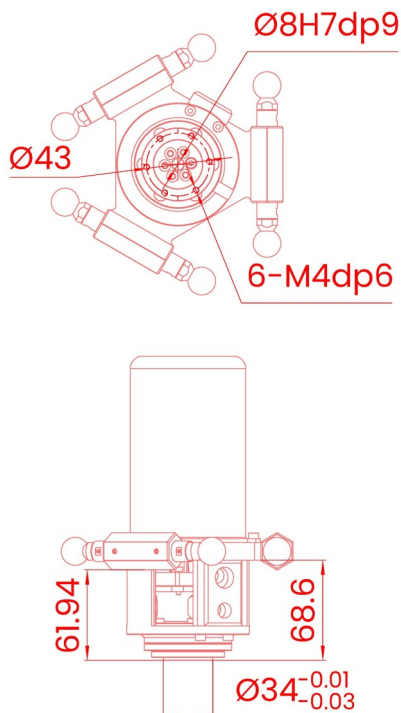
外形尺寸及运动范围
Outline dimensions and Working range (mm)



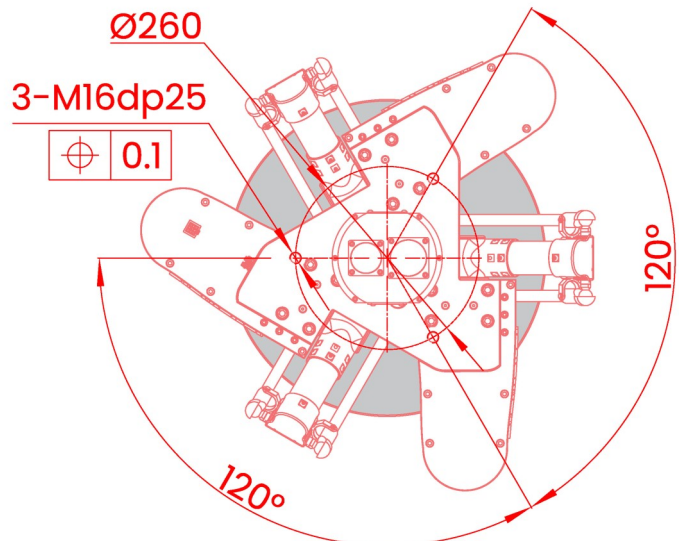
说明:
 图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

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)



D3PMB-600-P3



高速度 **High speed**
高旋转精度 **High rotation precision**
高稳定性 **High stability**
小巧、敏捷 **Small and Agile**

- ◆ 标准循环时间小于0.6s,满足追求高速度和最小体积需求

The standard cycle time is less than 0.6s, meeting your pursuit for the high speed and the minimum volume.

- ◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

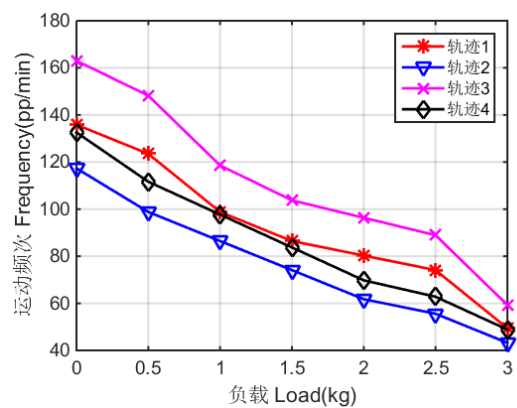
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The robot is ideal for narrow space operations, as well as high-speed and high-precision in 3C field. Widely used in assembly, handling and testing of small work pieces.

型号 Type		D3PMB-600-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	42kg
	工作空间直径 Diameter	600mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.05°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		$31 \times 10^{-4} \text{kg} \cdot \text{m}^2$
主动臂角度范围 Angle range of actuated arm	上摆 Up	44.2°
	下摆 Down	68.7°
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	2.4kw	
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	

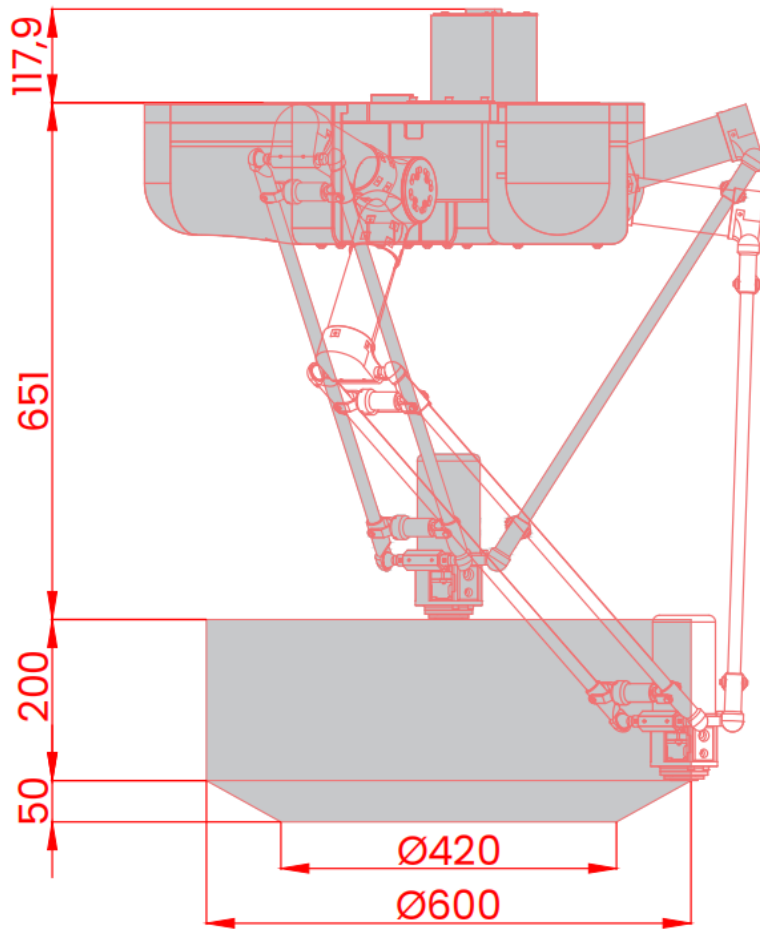
● 负载-频次 Load-Frequency



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。

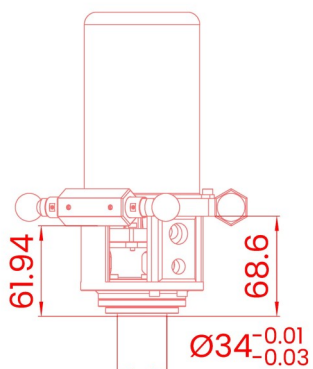
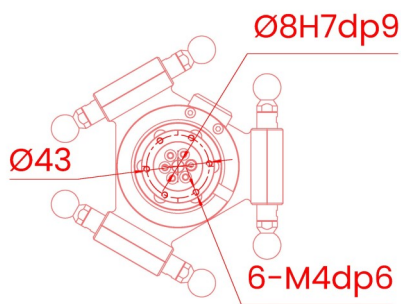
外形尺寸及运动范围
Outline dimensions and Working range (mm)



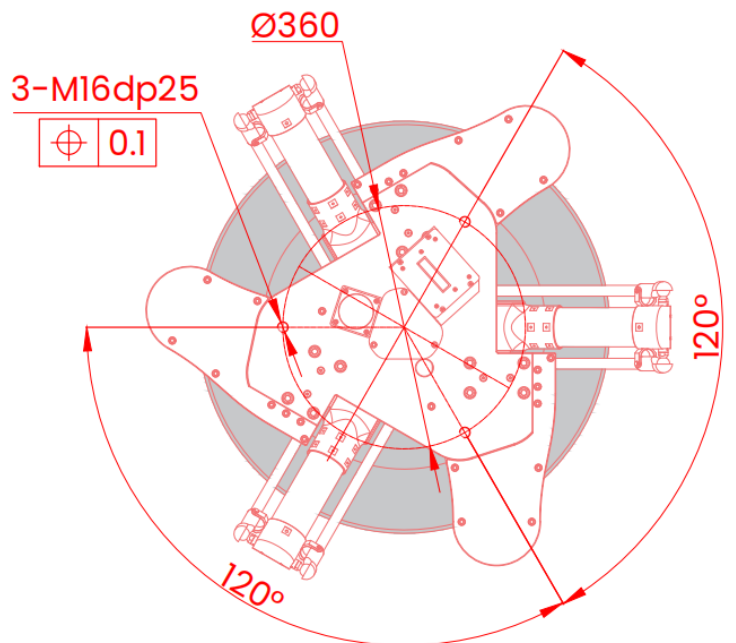
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Instruction:
The bottom gray part is the workplace of bottom surface 's center point of the end, which is composed of a cylinder at the top and a circular truncated cone at the bottom.

法兰 Flange (mm)



基座安装 Base installation (mm)



D3PMB-800-P3



高速度 **High speed**
高旋转精度 **High rotation precision**
高稳定性 **High stability**
小巧、敏捷 **Small and Agile**

- ◆ 标准循环时间小于0.6s,满足追求高速度和最小体积需求

The standard cycle time is less than 0.6s, meeting your pursuit for the high speed and the minimum volume.

- ◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

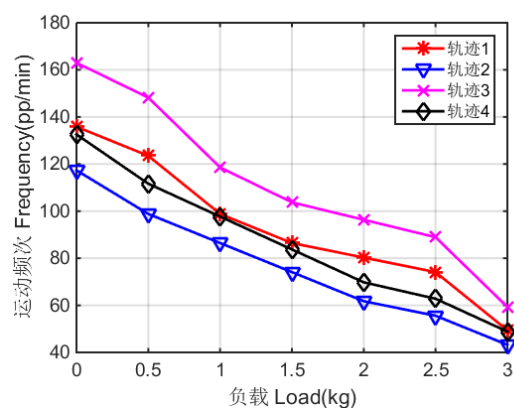
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型号 Type		D3PMB-800-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	60kg
	工作空间直径 Diameter	800mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.05°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		$31 \times 10^{-4} \text{kg} \cdot \text{m}^2$
主动臂角度范围 Angle range of actuated arm	上摆 Up	44.2°
	下摆 Down	68.7°
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	2.4kw	
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

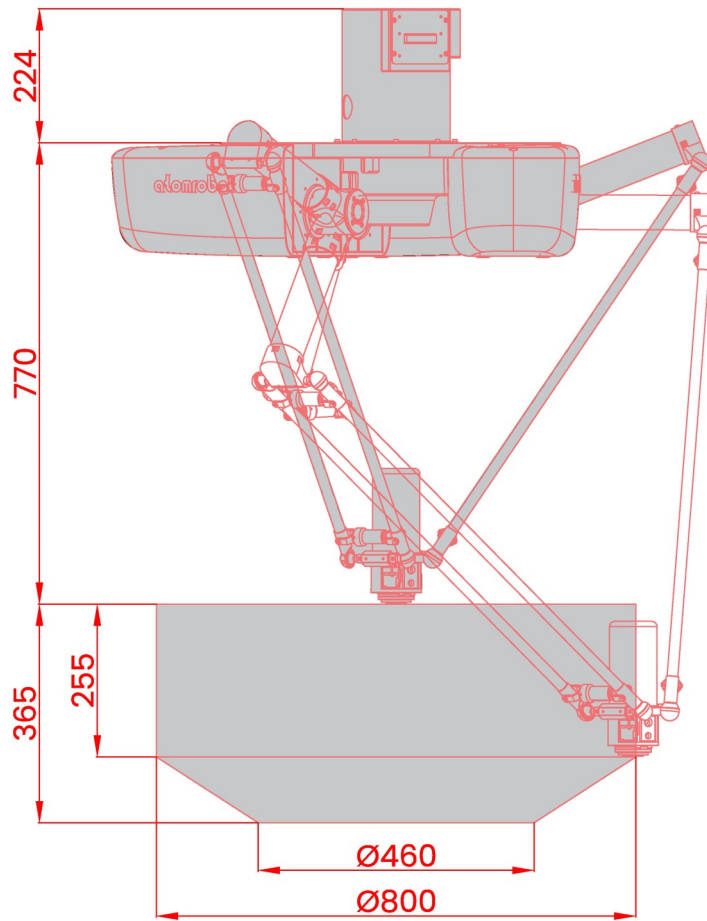


名称 Name	循环模式 Model	运动距离 Distance
轨迹1 Trajectory1	P1 → P2 → P3 → P4 → P3 → P2 → P1	h=25, b=305
轨迹2 Trajectory2	P1 → P2 → P3 → P4 → P3 → P2 → P1	h=25, b=500
轨迹3 Trajectory3	P1 → P2 → P3 → P2 → P1	h=25, b=305
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特别注意: 图中节拍时间在实际条件下测得, 但根据实际运用情况的不同 (工具数据、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)



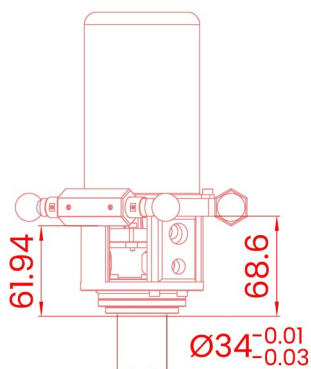
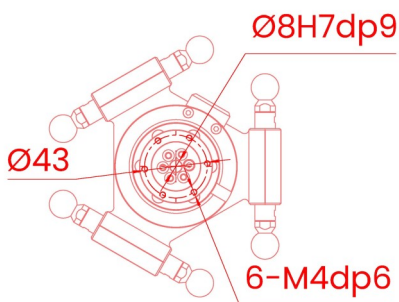
说明:

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。

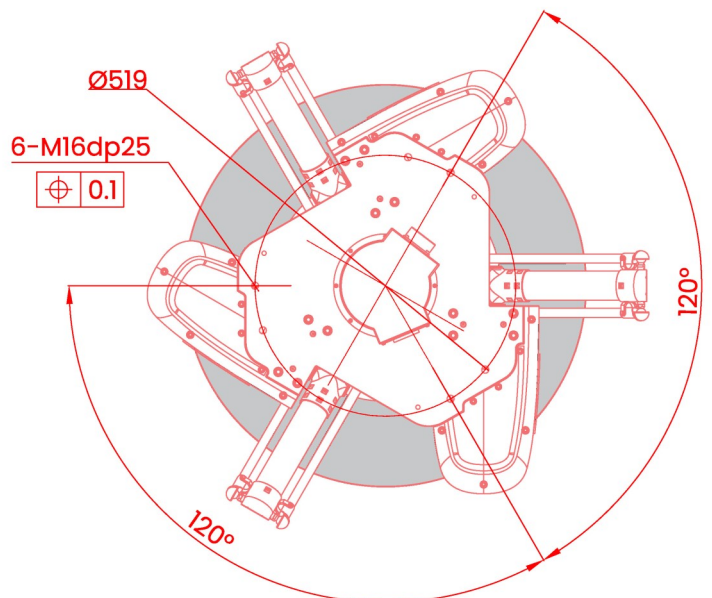
Instruction:

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法兰 Flange (mm)



基座安装 Base installation (mm)



D3PMB-1100-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		D3PMB-1100-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	65kg
	工作空间直径 Diameter	1100mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.05°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		$31 \times 10^{-4} \text{kg} \cdot \text{m}^2$
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	2.4kw	
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	

◆ 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.

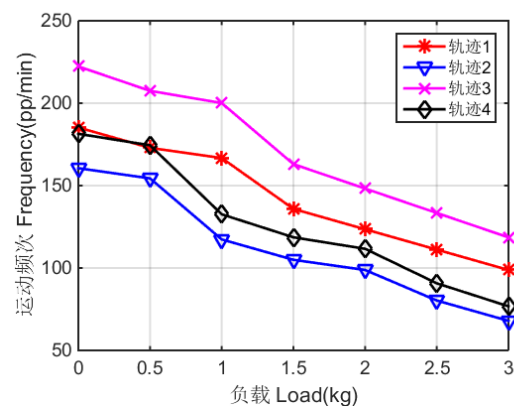
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The robot is ideal for high-speed production in food and medicine industry. Widely used in assembly, handling and pick-and-place of small materials for space height limited occasions.

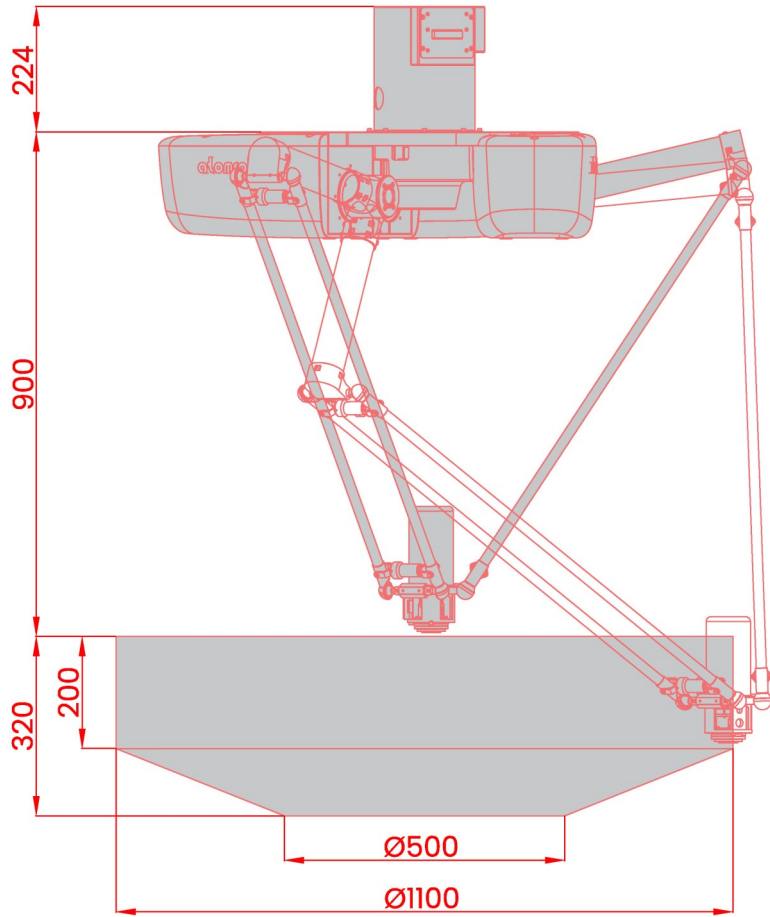
● 负载-频次 Load-Frequency



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



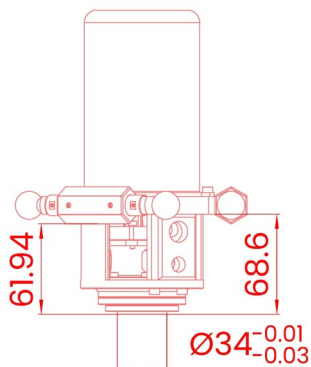
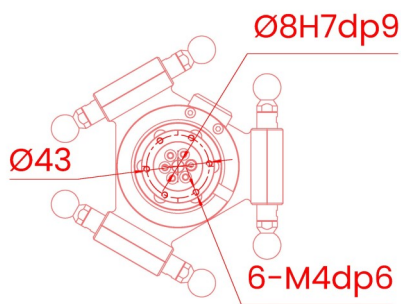
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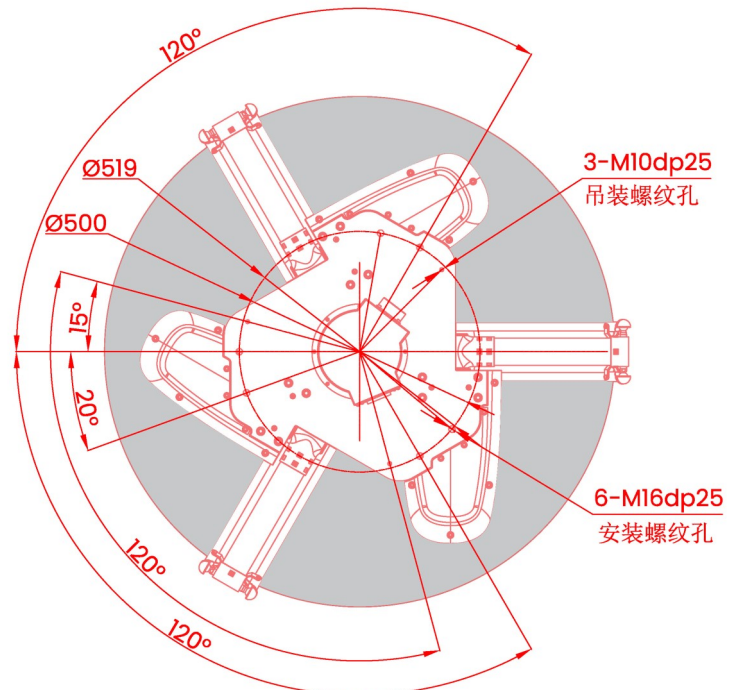
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法兰 Flange (mm)



基座安装 Base installation (mm)



D3PMB-1200-P3



高速度
高稳定性
大空间
低高度

High speed
High stability
Large space
Lower Height

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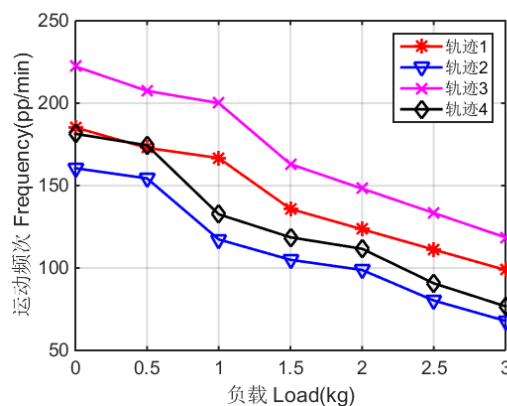
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型号 Type		D3PMB-1200-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	68kg
	工作空间直径 Diameter	1200mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.05°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		$31 \times 10^{-4} \text{kg} \cdot \text{m}^2$
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	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	

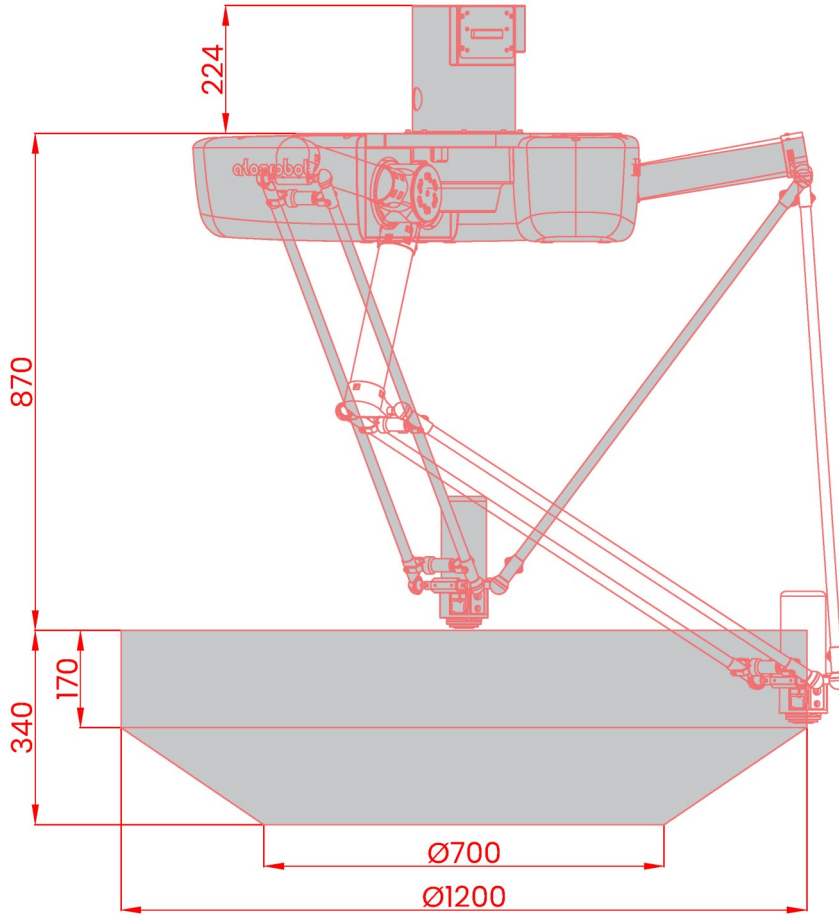
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轨迹4 Trajectory4	P1 → P2 → P3 → P2 → P1	h=25, b=500

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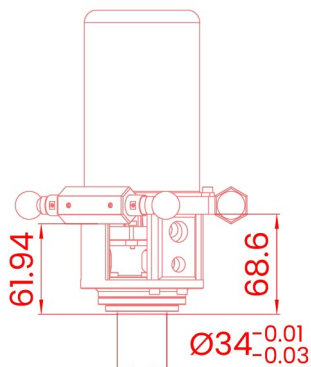
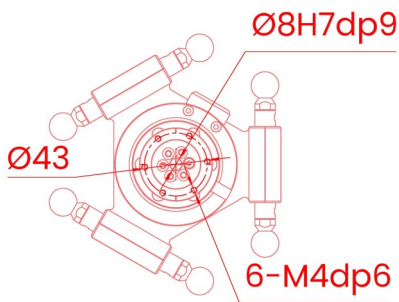
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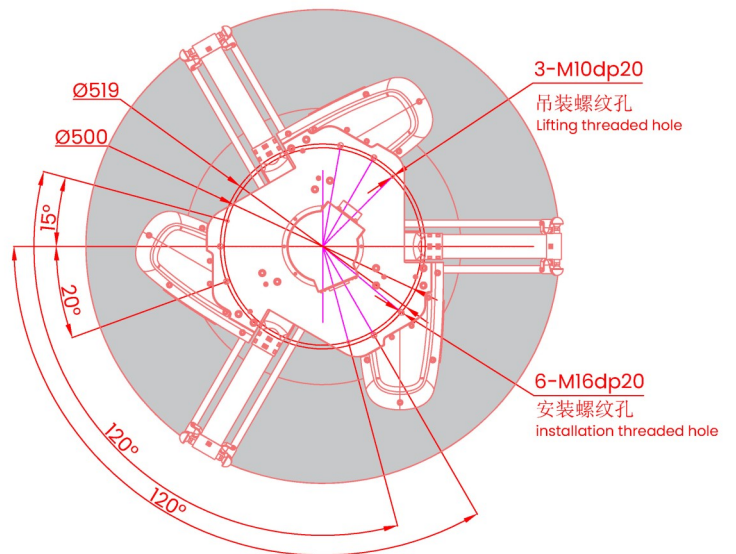
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Instruction:
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法兰 Flange (mm)



基座安装 Base installation (mm)



D3PMB-1400-P3



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		D3PMB-1400-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	79.7kg
	工作空间直径 Diameter	1400mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.05°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		$31 \times 10^{-4} \text{ kg} \cdot \text{m}^2$
主动臂角度范围 Angle range of actuated arm	上摆 Up	22°
	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	6.1kw	
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	

- ◆ 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 0.3s, meeting your pursuit for the maximum speed and economic.

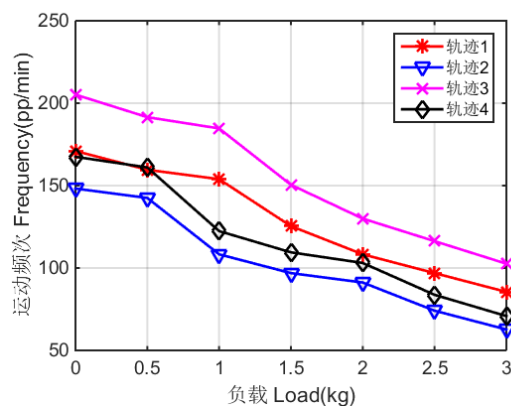
- ◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

Advanced design of the rotational motor on moving platform, enables the robot to be easily achieve high rotation precision.

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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.

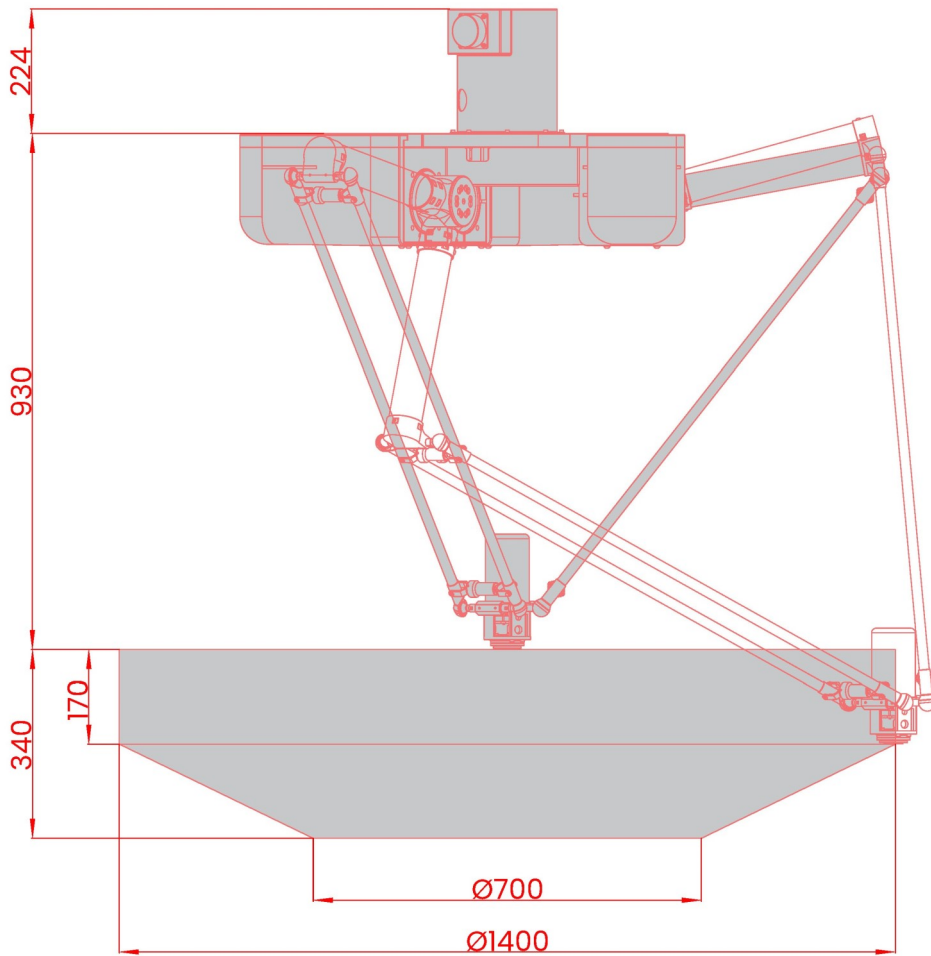
● 负载-频次 Load-Frequency



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)



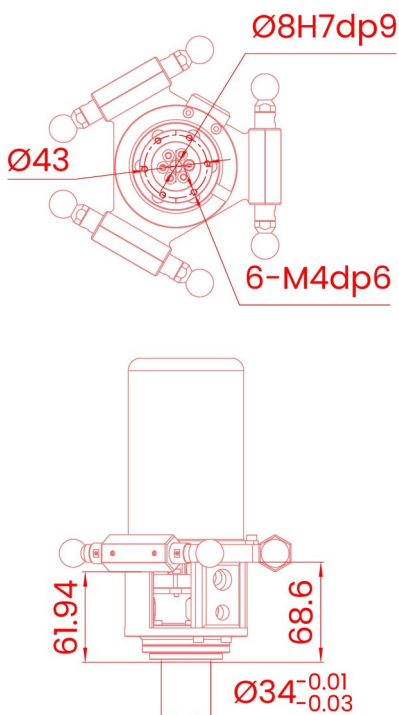
说明:

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。

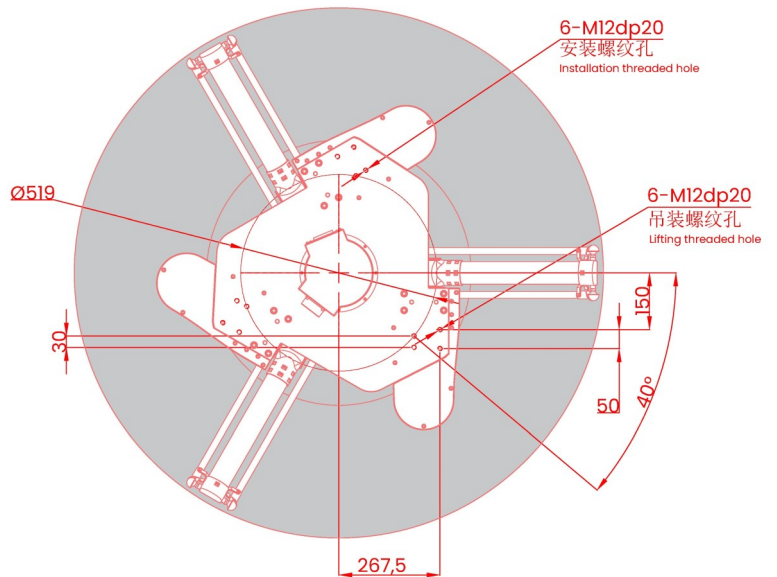
Instruction:

The bottom gray part is the workplace of 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)



D3PMB-1800-P15



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	D3PMB-1800-P15	
轴数 Axes	3+1	
最大负载 Payload	15kg	
机器人本体 Manipulator	重量 Weight	135kg
	工作空间直径 Diameter	1800mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.05°
旋转范围 Rotation range	±360°	
允许负载最大旋转惯量 Allowable maximum moment of inertia	$31 \times 10^{-4} \text{ kg} \cdot \text{m}^2$	
主动臂角度范围 Angle range of actuated arm	上摆 Up	22°
	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	6.2kw	
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0.4s,满足追求最高速度和最经济需求

The standard cycle time is less than 0.3s, meeting your pursuit for the maximum speed and economic.

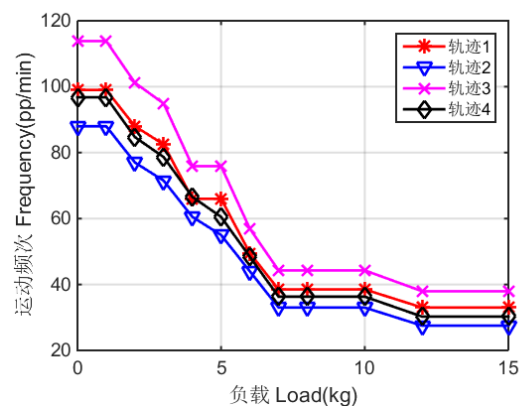
◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

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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.

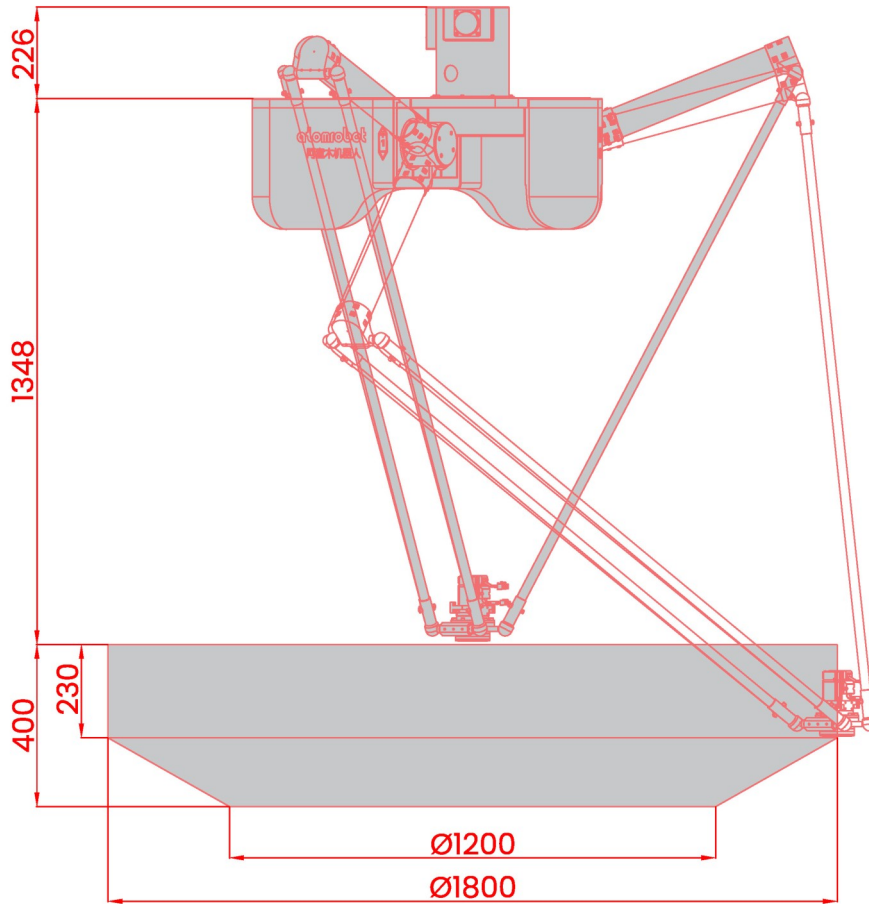
● 负载-频次 Load-Frequency



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)



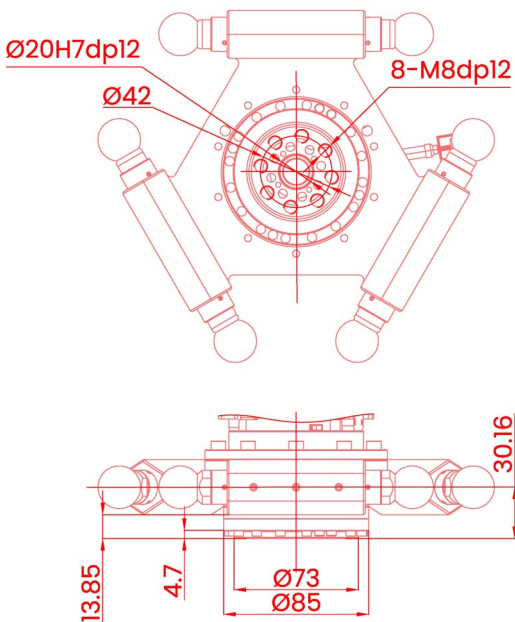
说明:

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。

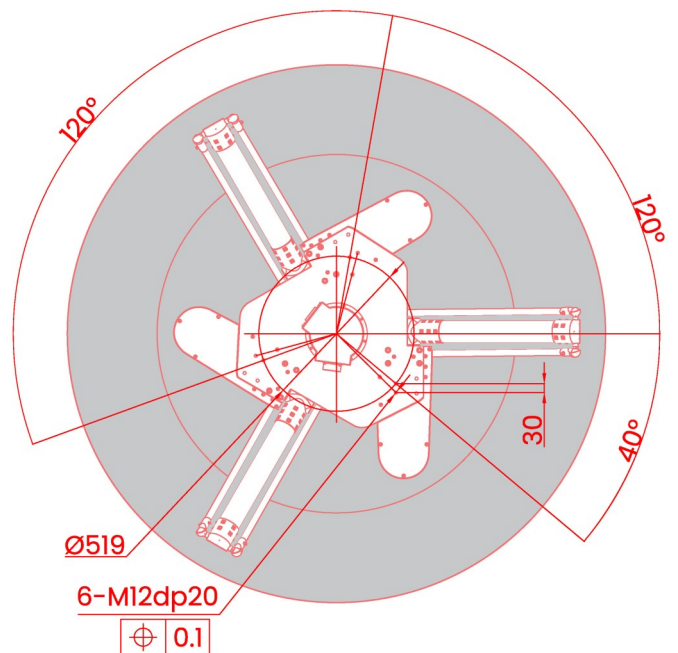
Instruction:

The bottom gray part is the workplace of 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)



D3PMB-1200-P25



高稳定性
大空间
超重负载
高旋转精度

High stability
Large space
Super-heavy load
High rotation preci-

型号 Type		D3PMB-1200-P25
轴数 Axes		3+1
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	0.025°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.224kg·m ²
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	9.2kw	
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0.67s,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.

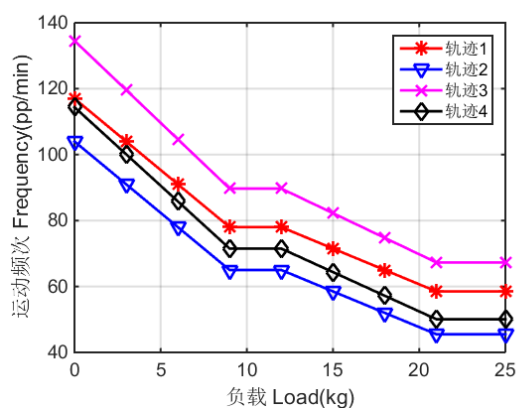
- ◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

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● 负载-频次 Load-Frequency

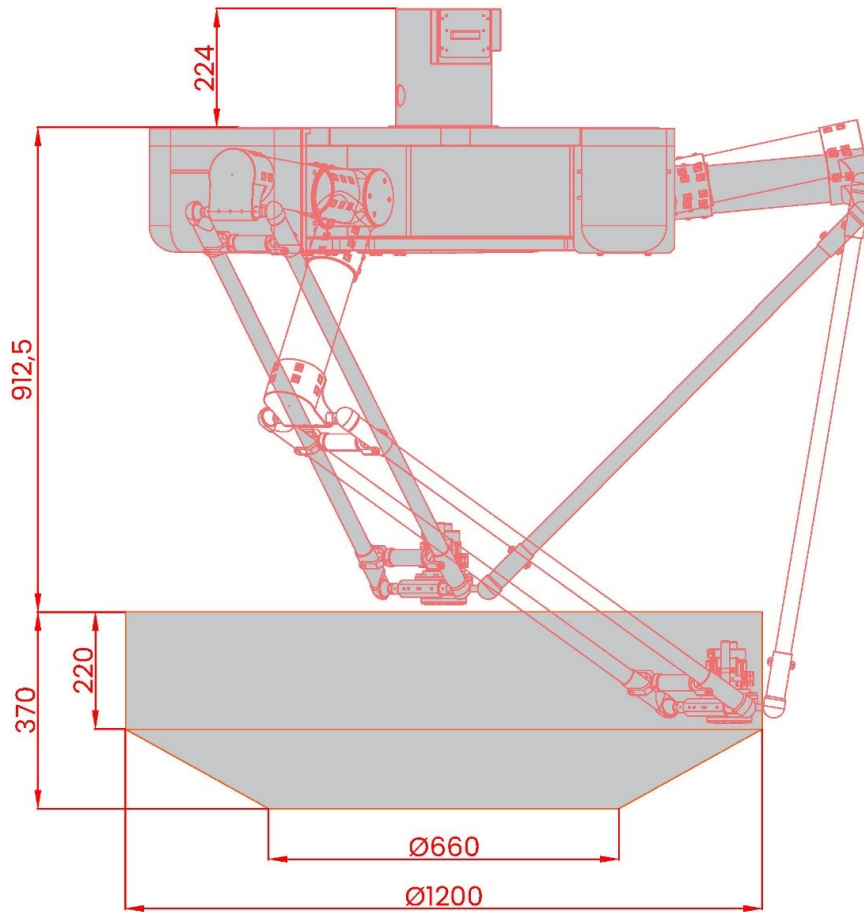


名称 Name	循环模式 Model	运动距离 Distance
轨迹1 Trajectory1	P1 → P2 → P3 → P4 → P3 → P2 → P1	h=25, b=305
轨迹2 Trajectory2	P1 → P2 → P3 → P4 → P3 → P2 → P1	h=25, b=500
轨迹3 Trajectory3	P1 → P2 → P3 → P2 → P1	h=25, b=305
轨迹4 Trajectory4	P1 → P2 → P3 → P2 → P1	h=25, b=500

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)



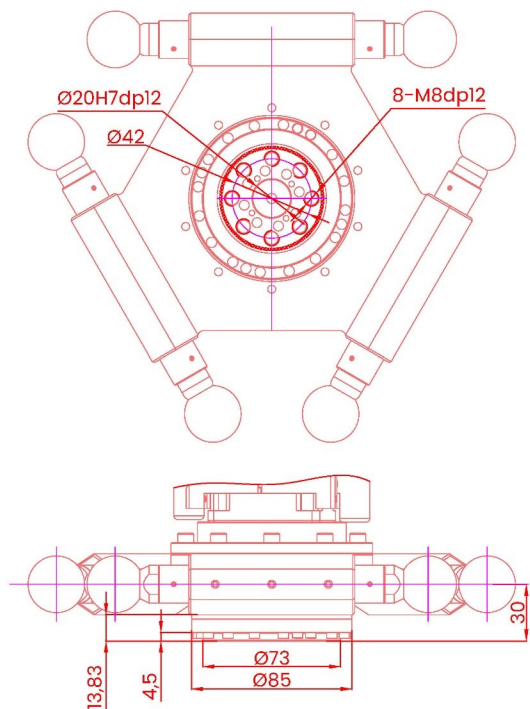
说明:

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。

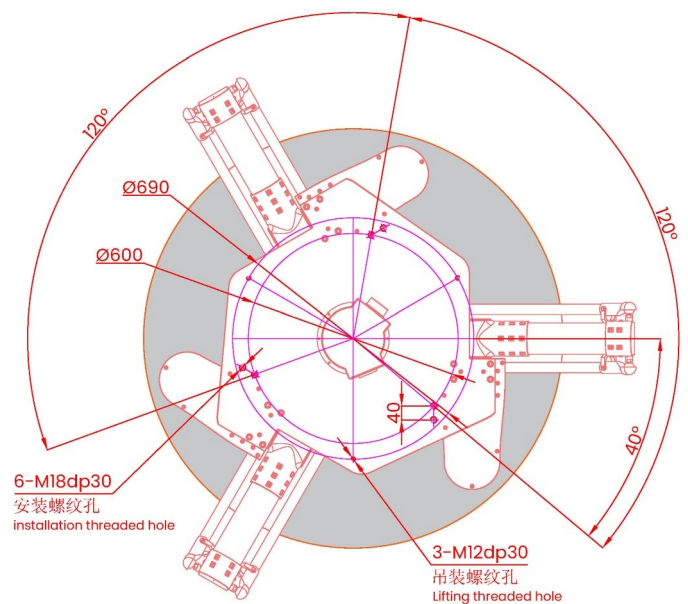
Instruction:

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)



D3PMB-1400-P25



高稳定性
大空间
超重负载
高旋转精度

High stability
Large space
Super-heavy load
High rotation preci-

型号 Type		D3PMB-1400-P25
轴数 Axes		3+1
最大负载 Payload		25kg
机器人本体 Manipulator	重量 Weight	146kg
	工作空间直径 Diameter	1400mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.025°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.224kg·m ²
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	9.2kw	
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0.67s,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.

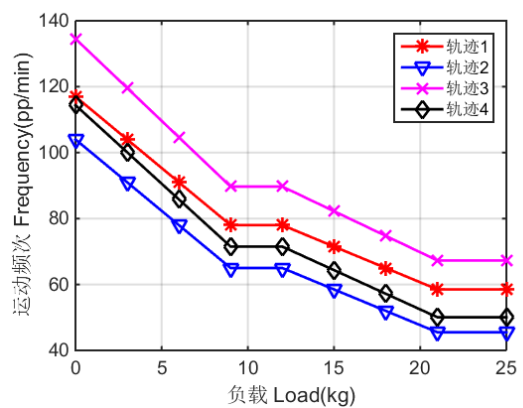
◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

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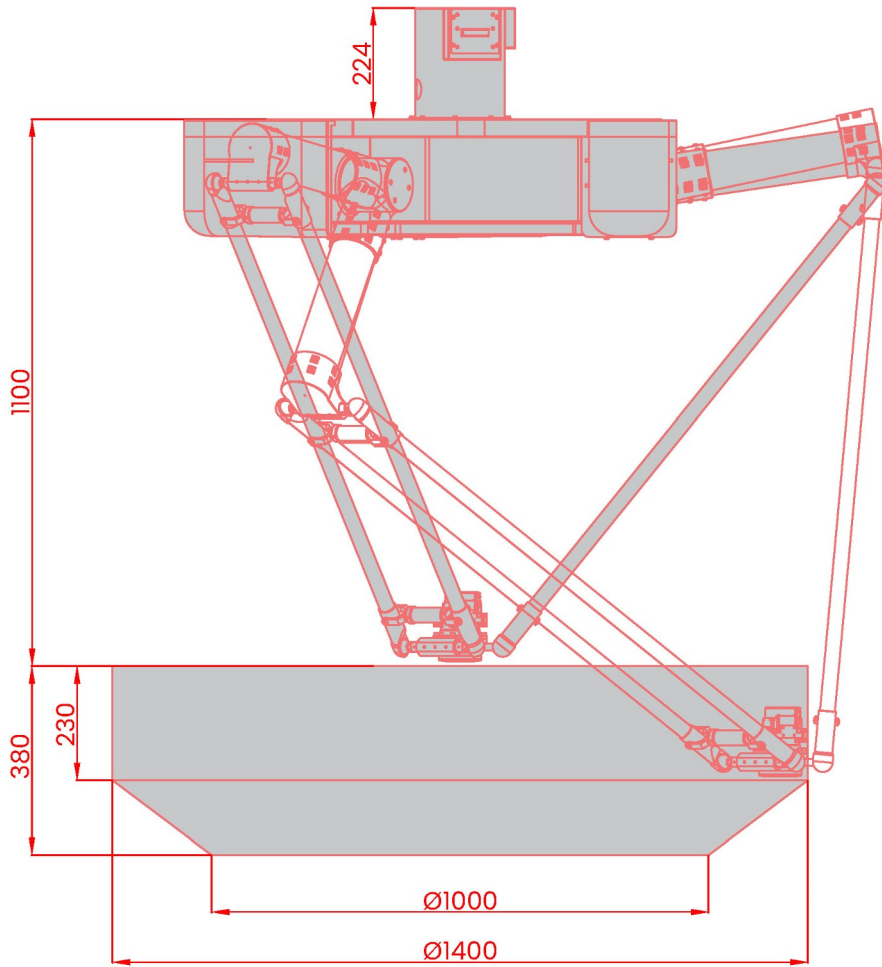
● 负载-频次 Load-Frequency



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。

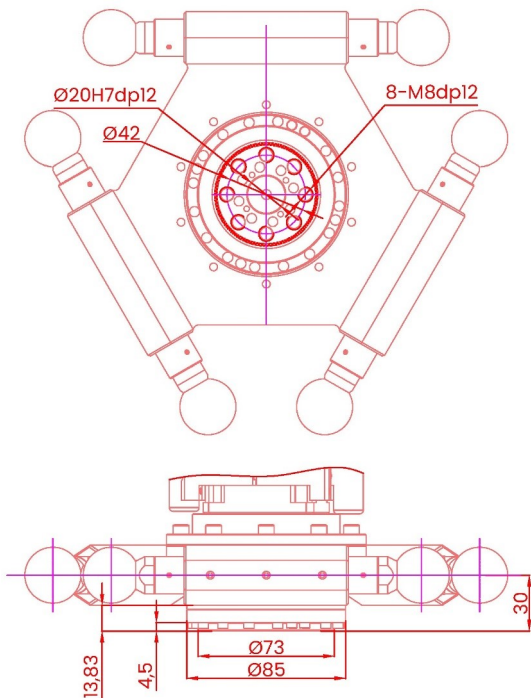
外形尺寸及运动范围
Outline dimensions and Working range (mm)



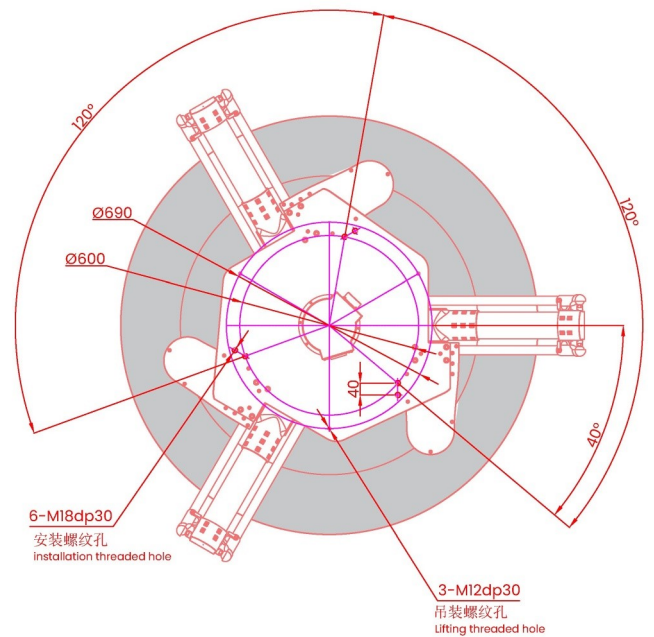
说明：
图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

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)



D3PMB-1800-P25



高稳定性
超大空间
超重负载
高旋转精度

High stability
Super-large space
Super-heavy load
High rotation preci-

型号 Type		D3PMB-1800-P25
轴数 Axes		3+1
最大负载 Payload		25kg
机器人本体 Manipulator	重量 Weight	149kg
	工作空间直径 Diameter	1800mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.05°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.224kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	42°
	下摆 Down	75°
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	9.2kw	
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0.67s,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.

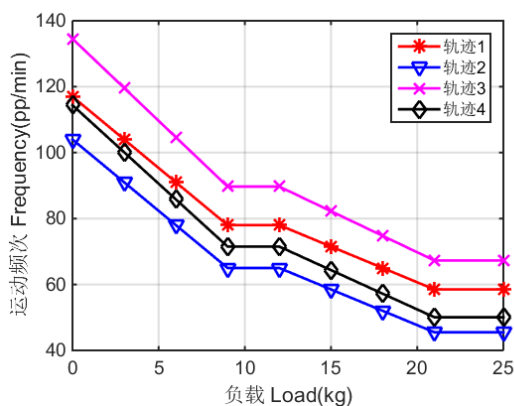
- ◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

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● 负载-频次 Load-Frequency

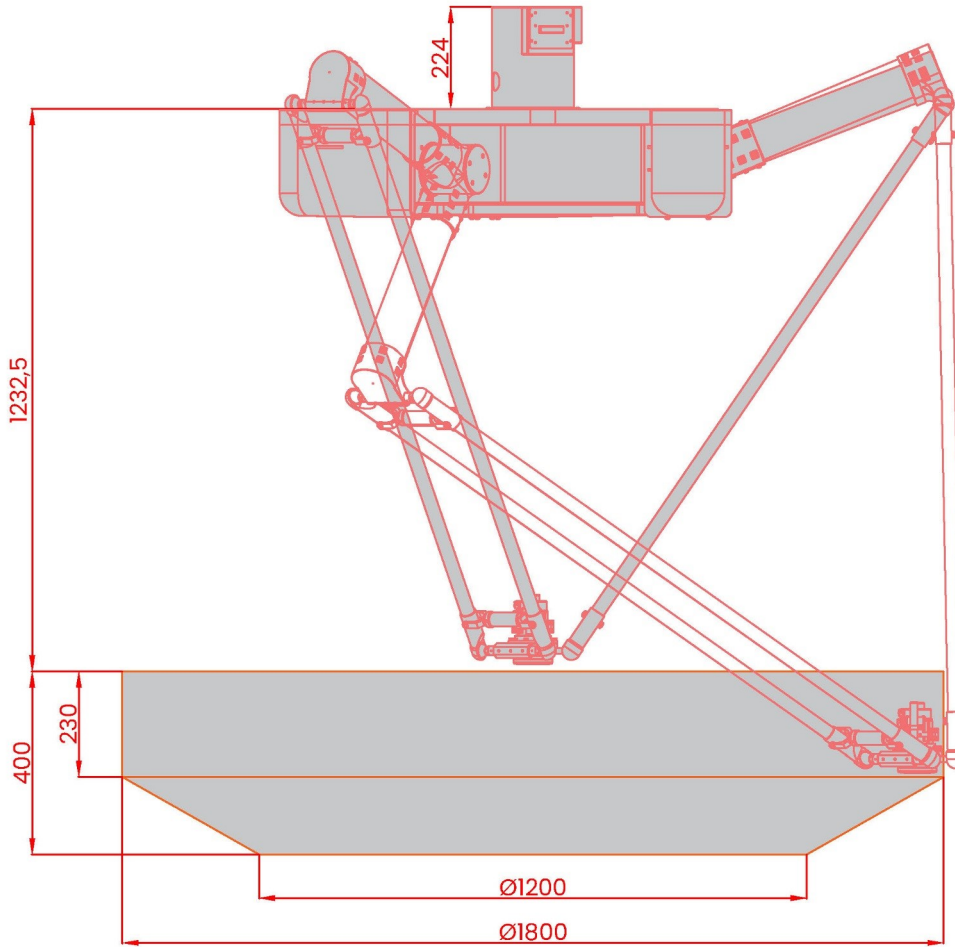


名称 Name	循环模式 Model	运动距离 Distance
轨迹1 Trajectory1	P1 → P2 → P3 → P4 → P3 → P2 → P1	h=25, b=305
轨迹2 Trajectory2	P1 → P2 → P3 → P4 → P3 → P2 → P1	h=25, b=500
轨迹3 Trajectory3	P1 → P2 → P3 → P2 → P1	h=25, b=305
轨迹4 Trajectory4	P1 → P2 → P3 → P2 → P1	h=25, b=500

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)



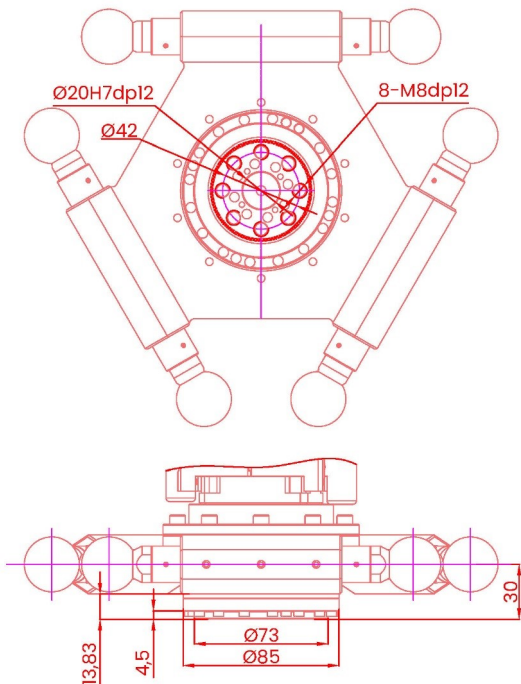
说明:

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。

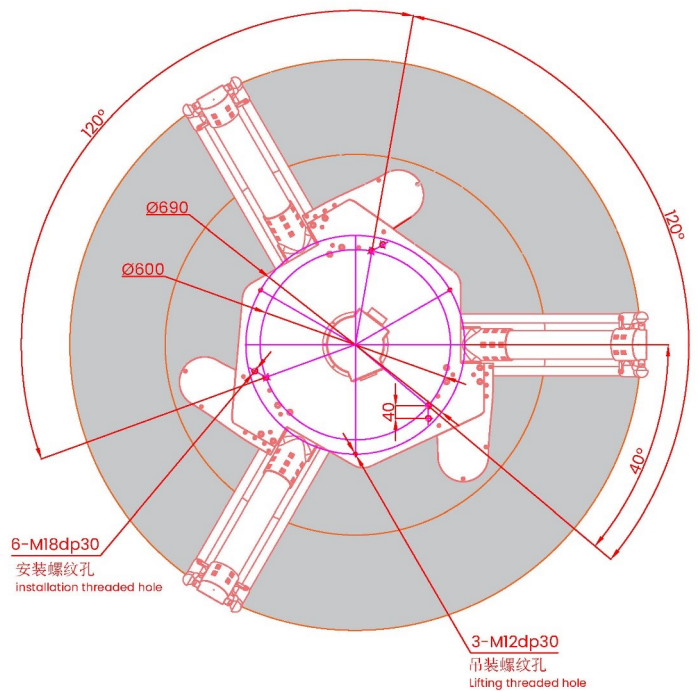
Instruction:

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)



D3PMB-2200-P25



高稳定性
超大空间
超重负载
高旋转精度

High stability
Super-large space
Super-heavy load
High rotation preci-

型号 Type		D3PMB-2200-P25
轴数 Axes		3+1
最大负载 Payload		25kg
机器人本体 Manipulator	重量 Weight	153kg
	工作空间直径 Diameter	2200mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.05°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.224kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	33.2°
	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	15KVA	
额定功率 Rated Power	9.2kw	
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0.67s,满足追求最高负载和最大空间需求

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

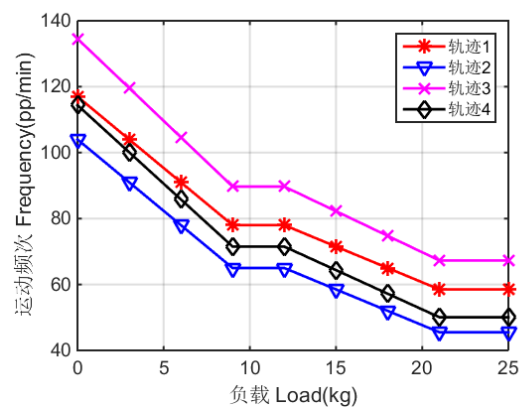
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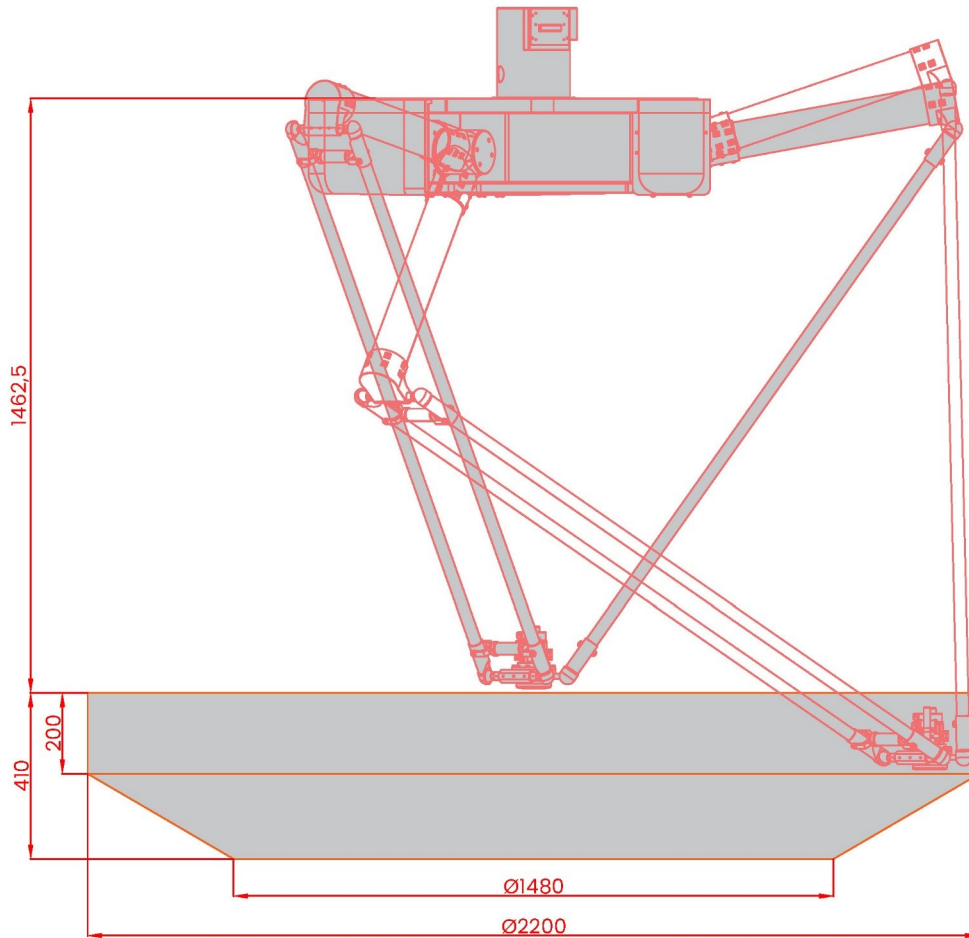
● 负载-频次 Load-Frequency



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。

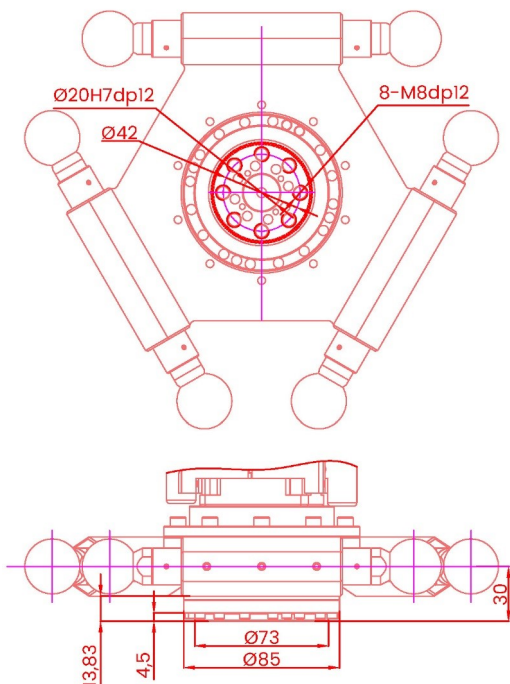
外形尺寸及运动范围
Outline dimensions and Working range (mm)



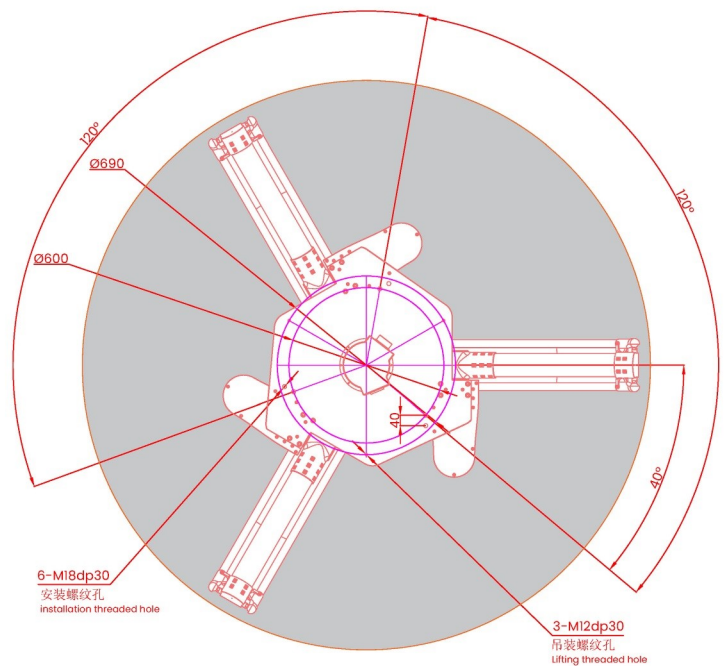
说明：
图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

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)



D3PMB-2800-P25



高稳定性
超大空间
超重负载
高旋转精度

High stability
Super-large space
Super-heavy load
High rotation preci-

型号 Type		D3PMB-2200-P25
轴数 Axes		3+1
最大负载 Payload		25kg
机器人本体 Manipulator	重量 Weight	173kg
	工作空间直径 Diameter	2800mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.05°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.224kg·m ²
主动臂角度范围 Angle range of actuated arm	上摆 Up	33.2°
	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	15KVA	
额定功率 Rated Power	9.2kw	
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0.67s,满足追求最高负载和最大空间需求

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

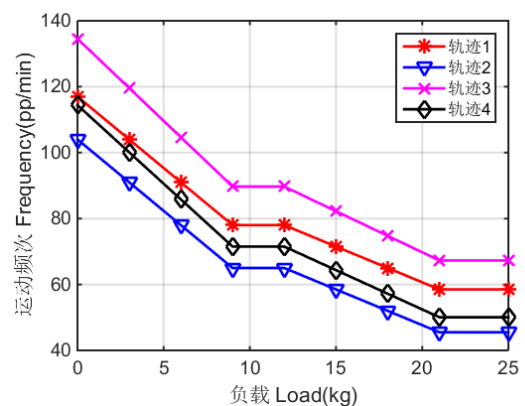
- ◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

Advanced design of the rotational motor on moving platform, enables the robot to be easily achieve high rotation precision.

- ◆ 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.

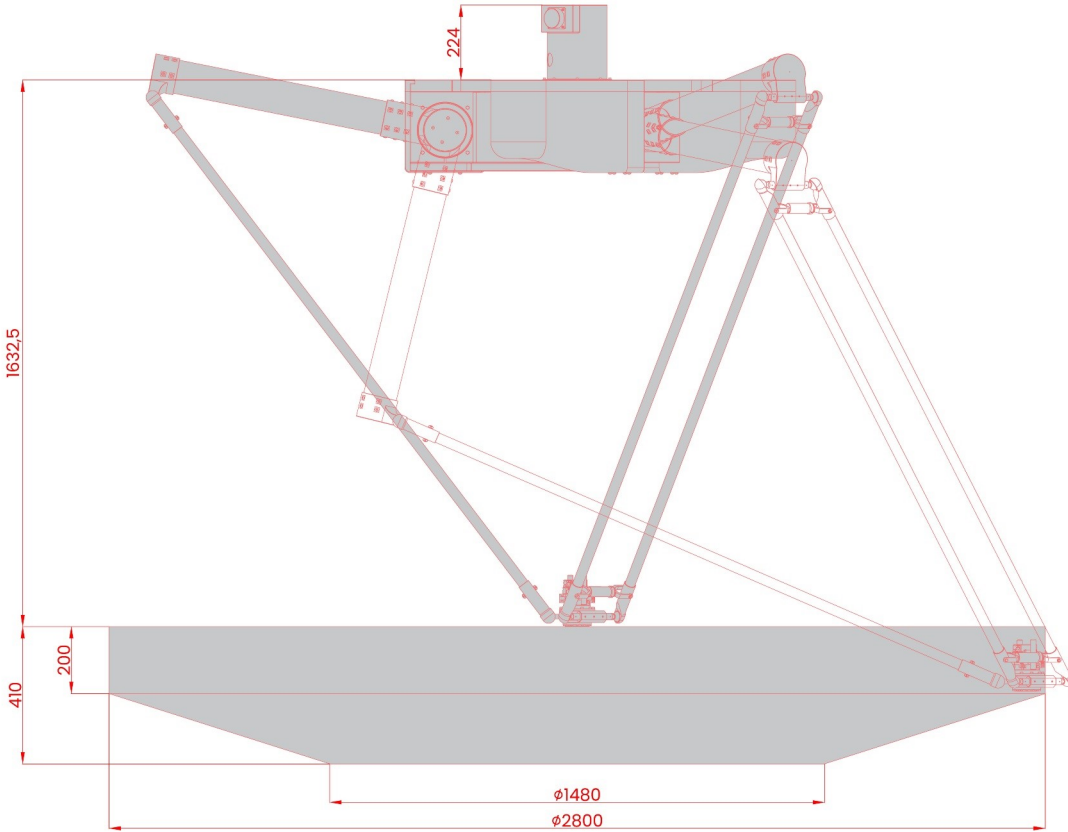
● 负载-频次 Load-Frequency



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)

