

# 并联机器人

## 选型手册

Parallel robot selection Manual

D3PM



## ● 型号和符号

D3PM	1100	P3	A1	E1	FXGX
机型	型号	负载	控制器类型	控制柜类型	视觉
D3PM	800	P3: 3kg P15: 15kg	A1: ATOMCONTROL A2: KEBA CONTROL	E1: ATOM-01 E2: ATOM-02 E3: 定制	F0G0: 无视觉 FXGX: 有视觉
	1100				
	1200				
	1300				
	1400				
	1600				
	1800				

## ● Model and Symbol

D3PM	1100	P3	A1	E1	FXGX
Robot type	Type	Load Type	Control Type	Control Cabinet	Vision Type
D3PM	800	P3: 3kg P15: 15kg	A1: ATOMCONTROL A2: KEBA CONTROL	E1: ATOM-01 E2: ATOM-02 E3: Custom	F0G0: Without vision FXGX: With vision
	1100				
	1200				
	1300				
	1400				
	1600				
	1800				

## D3PM-800-P3



**高速度**                      **High speed**  
**高旋转精度**                **High precision**  
**高稳定性**                    **High stability**  
**经济实用**                    **Economic & Practical**

型号 Type		D3PM-800-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	67.5kg
	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	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	2.35kw	
保存温度 Storage temperature	-10°C~70°C	
工作环境 Work environment	-10°C~50°C, RH≤80%	
防护等级 Protection	IP55	

◆ 标准循环时间小于0.5s,满足追求最高速度和最经济需求

The standard cycle time is less than 0.5s, meeting your pursuit for the maximum speed and economic.

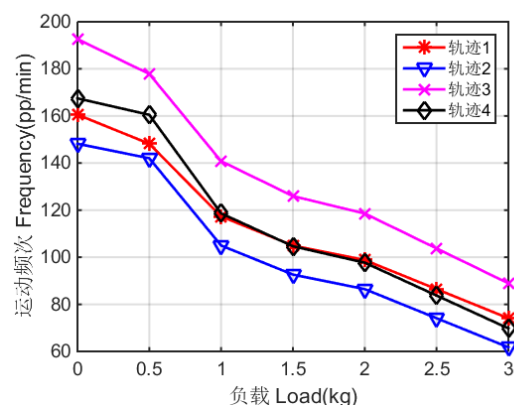
◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

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

◆ 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.

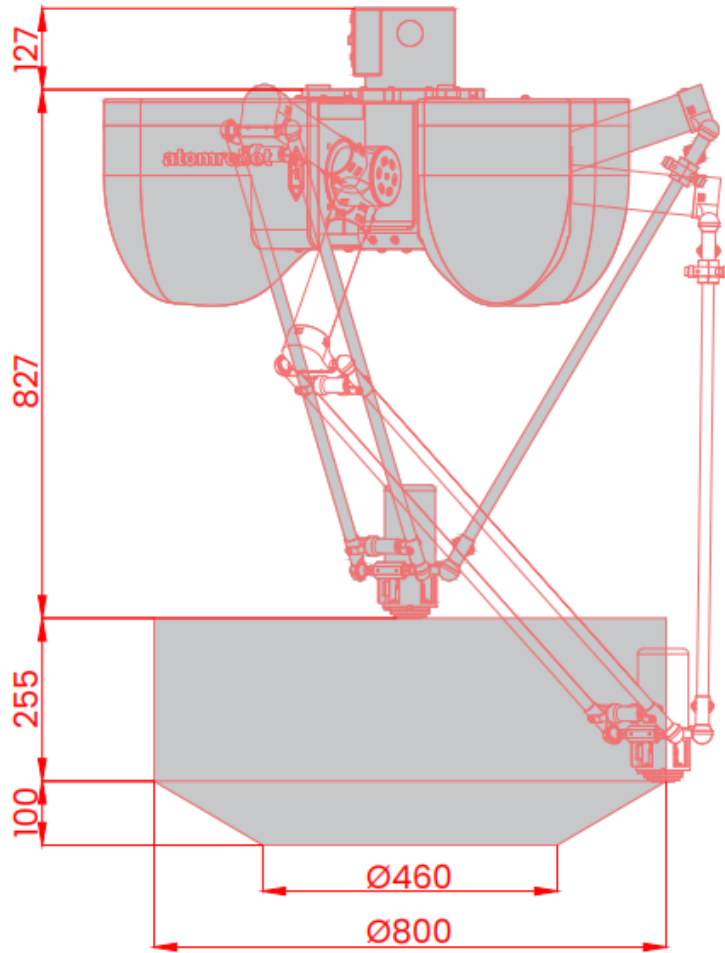
● 负载-频次 Load-Frequency



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。

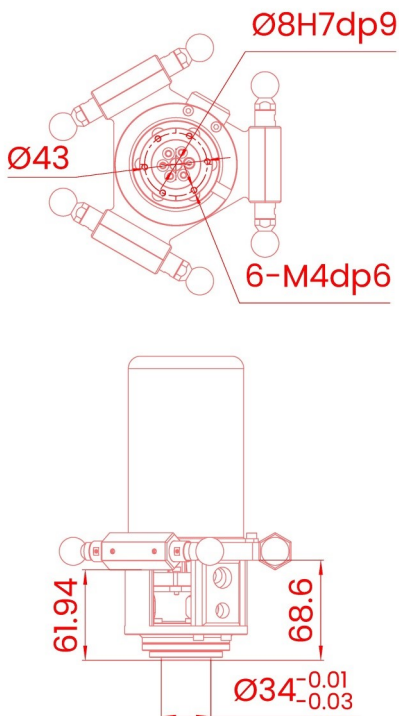
外形尺寸及运动范围  
Outline dimensions and Working range (mm)



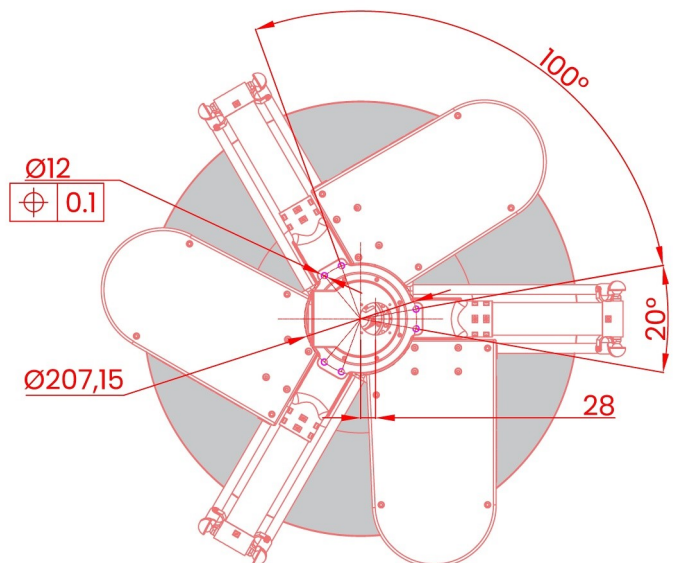
说明：  
图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

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)



## D3PM-1100-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		D3PM-1100-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	85kg
	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	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		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 0.4s, meeting your pursuit for the maximum speed and economic.

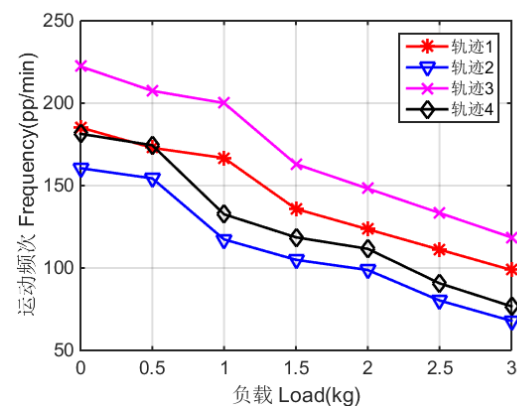
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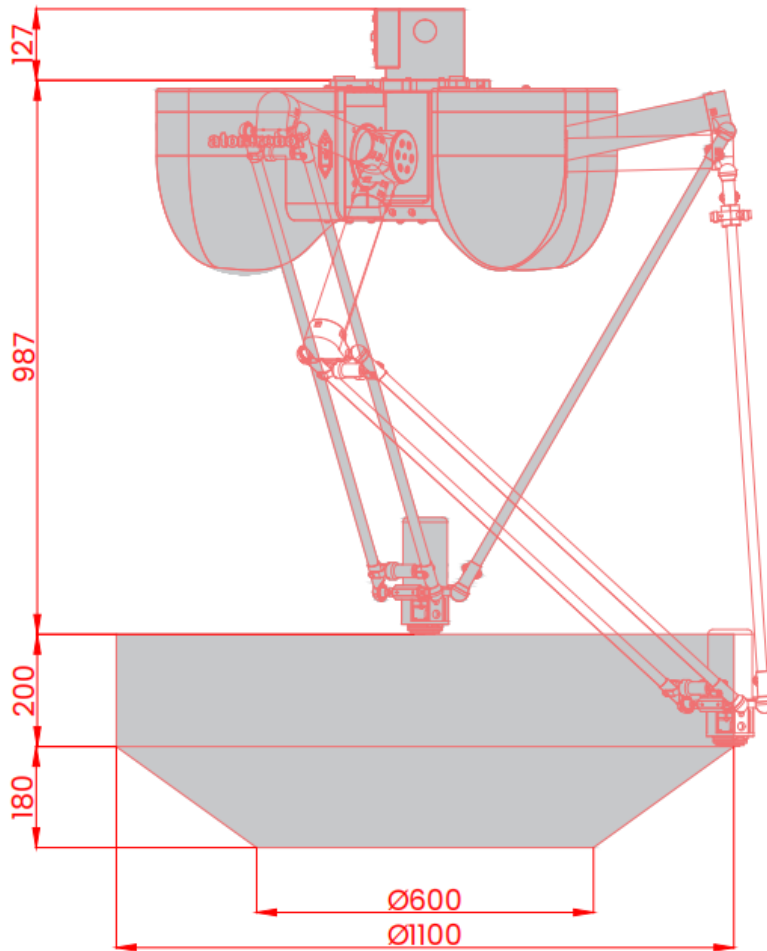
● 负载-频次 Load-Frequency



名称 Name	循环模式 Model	运动距离 Distance
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**外形尺寸及运动范围**  
**Outline dimensions and Working range (mm)**



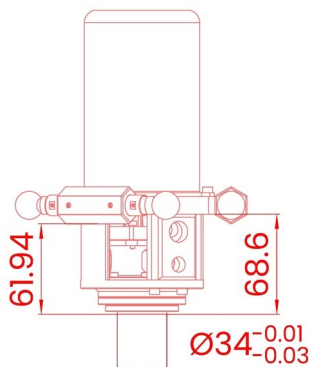
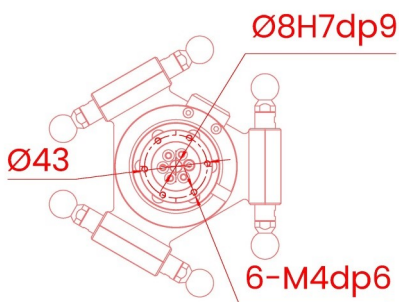
**说明:**

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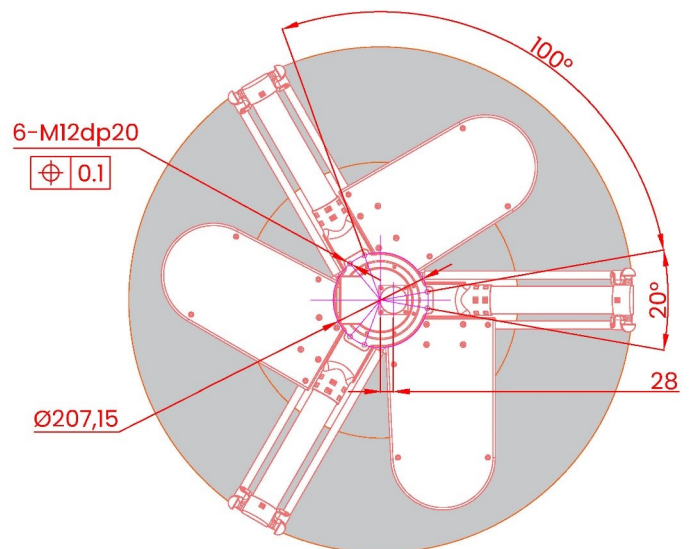
**Instruction:**

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**法兰 Flange (mm)**



**基座安装 Base installation (mm)**





## D3PM-1300-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		D3PM-1300-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	86.5kg
	工作空间直径 Diameter	1300mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.05°
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	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	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 0.4s, meeting your pursuit for the maximum speed and economic.

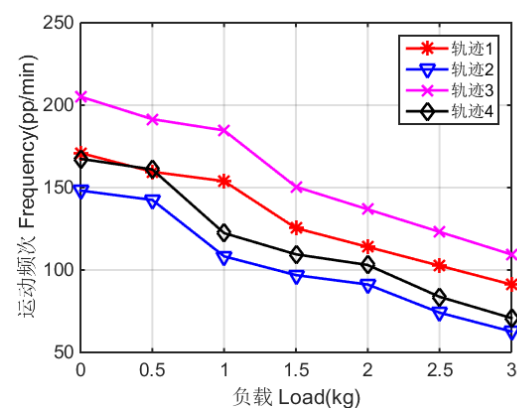
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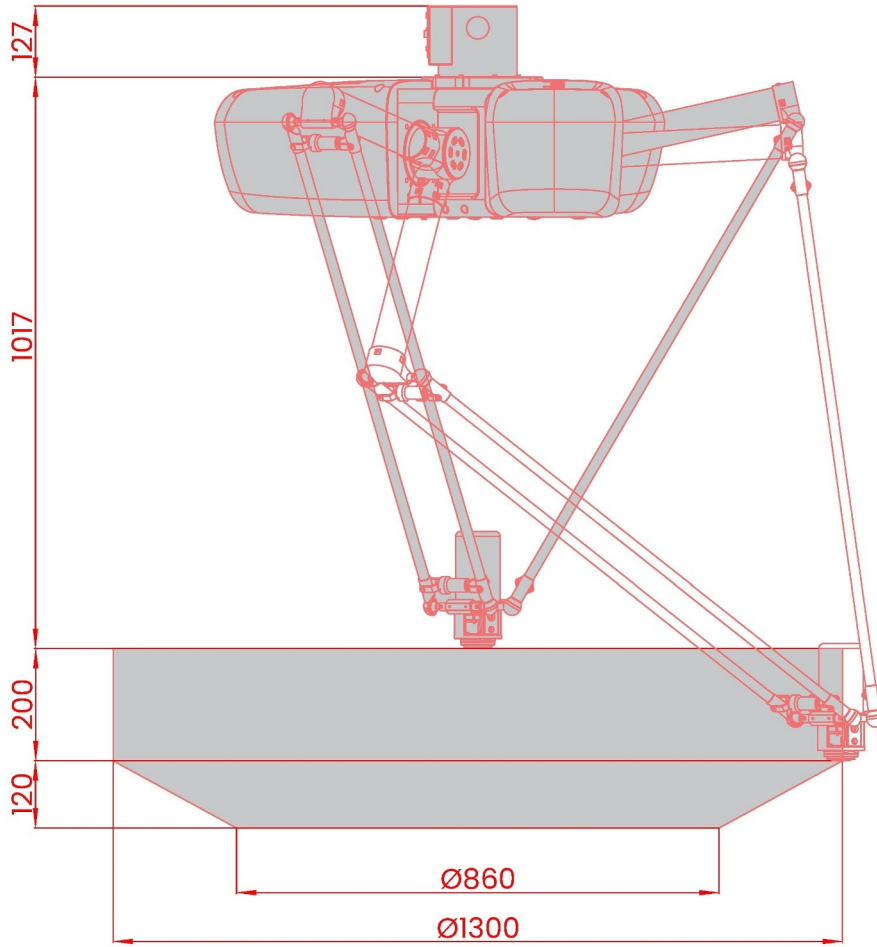
● 负载-频次 Load-Frequency



名称 Name	循环模式 Model	运动距离 Distance
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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)**



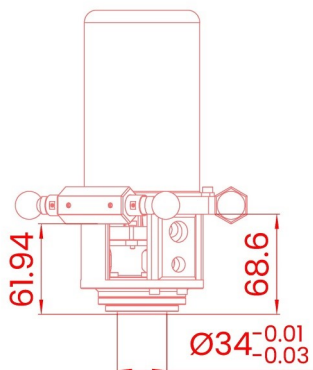
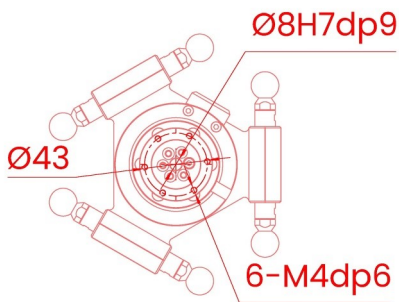
**说明:**

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。

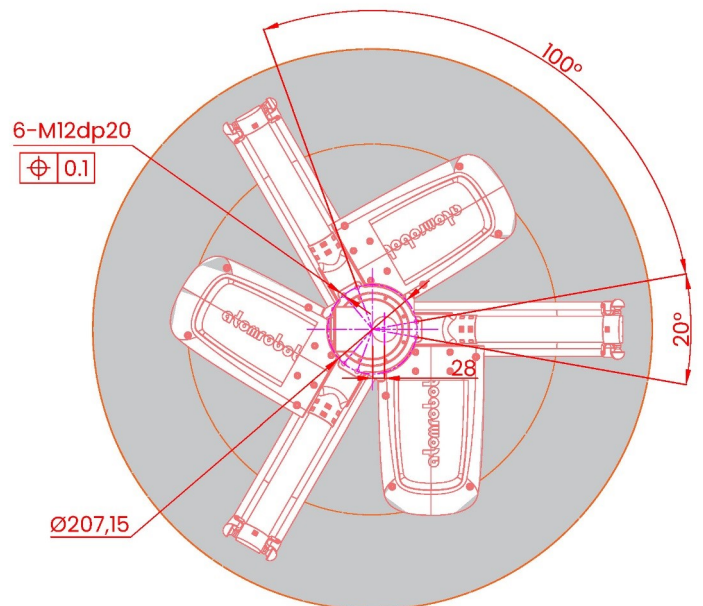
**Instruction:**

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)**





## D3PM-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		D3PM-1400-P3
轴数 Axes		3+1
最大负载 Payload		3kg
机器人本体 Manipulator	重量 Weight	79.5kg
	工作空间直径 Diameter	1400mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.05°
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.

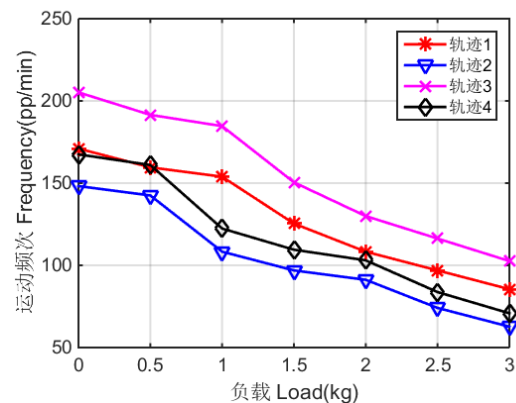
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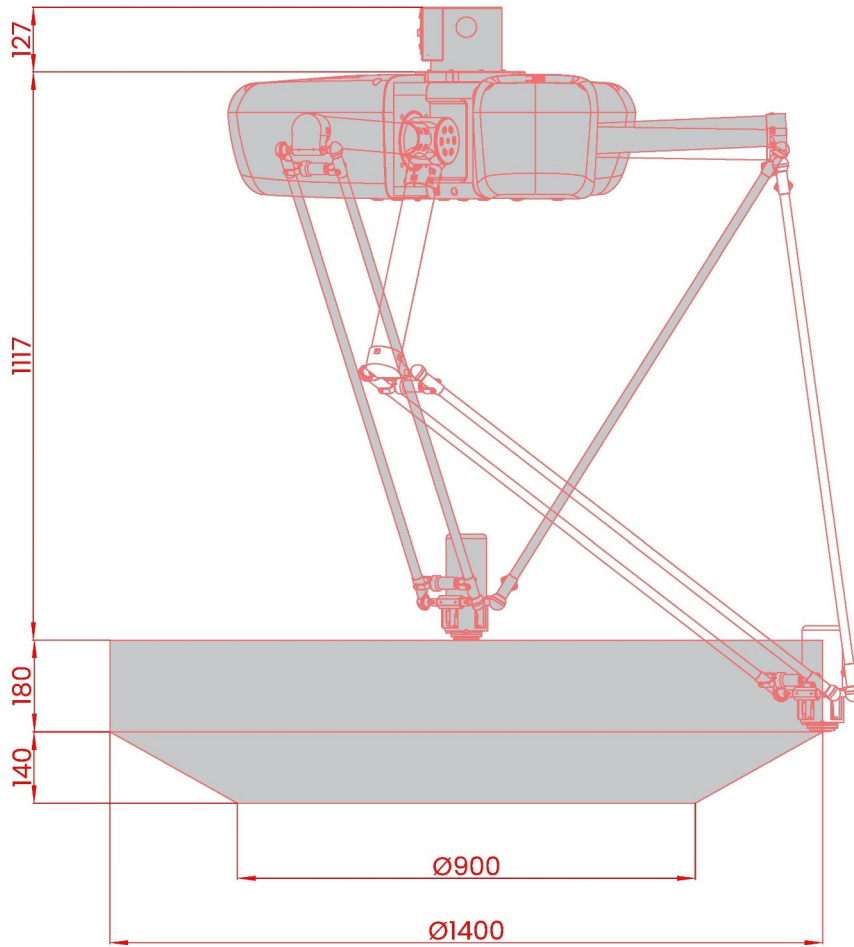
● 负载-频次 Load-Frequency



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)



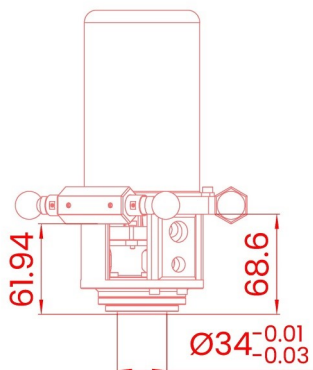
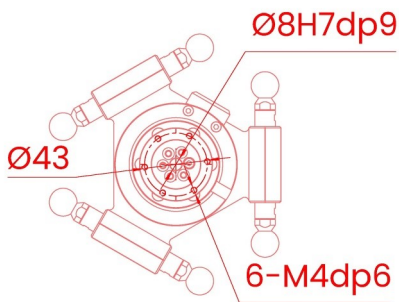
说明:

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。

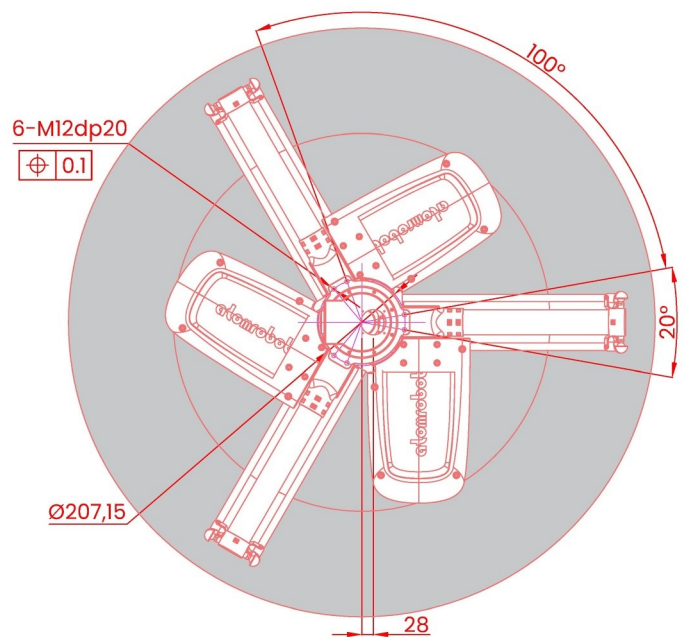
Instruction:

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)



## D3PM-1600-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		D3PM-1600-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	1600mm
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

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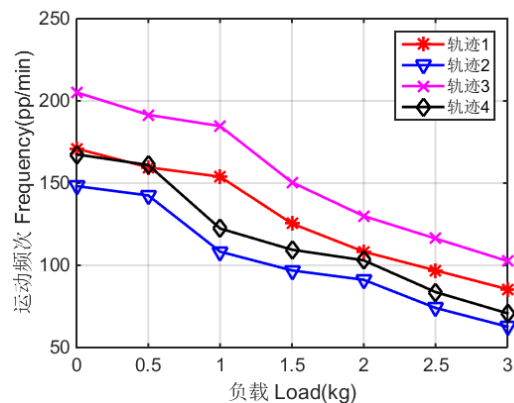
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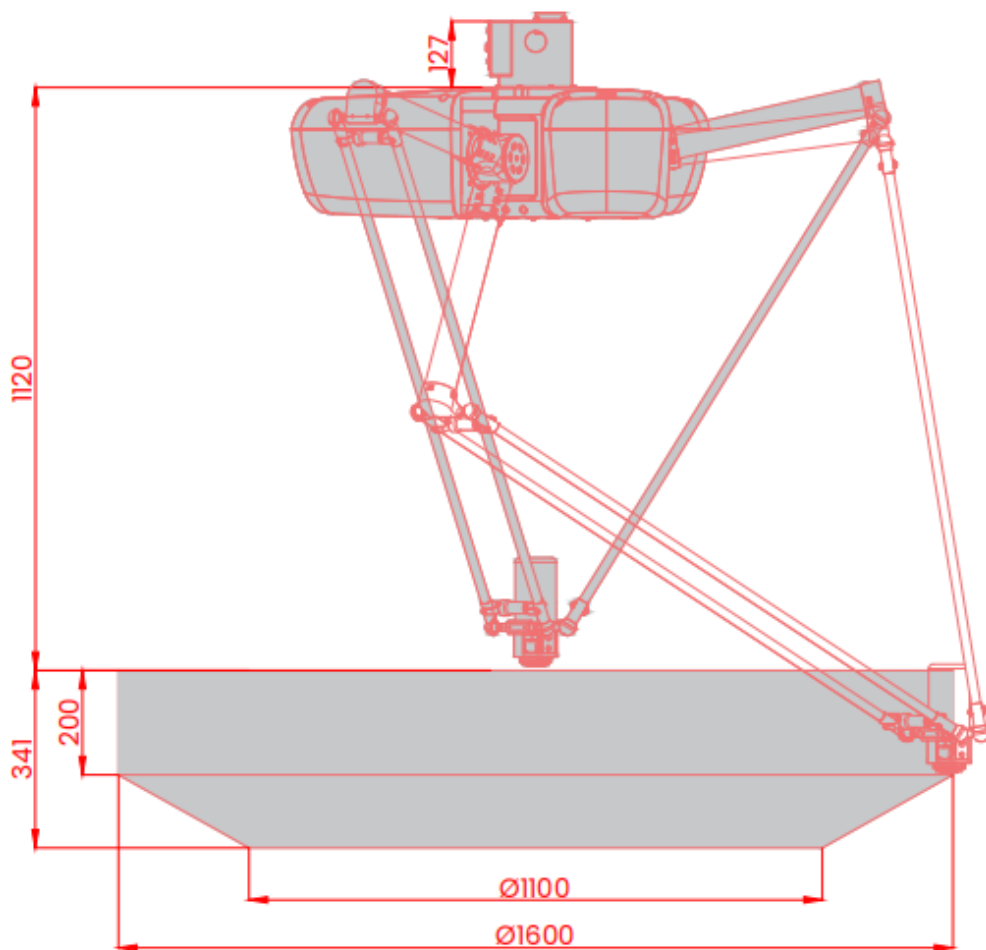
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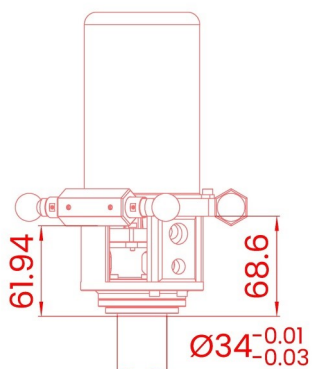
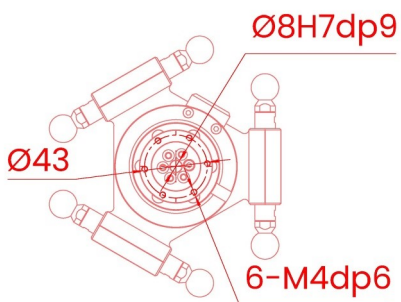
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Outline dimensions and Working range (mm)



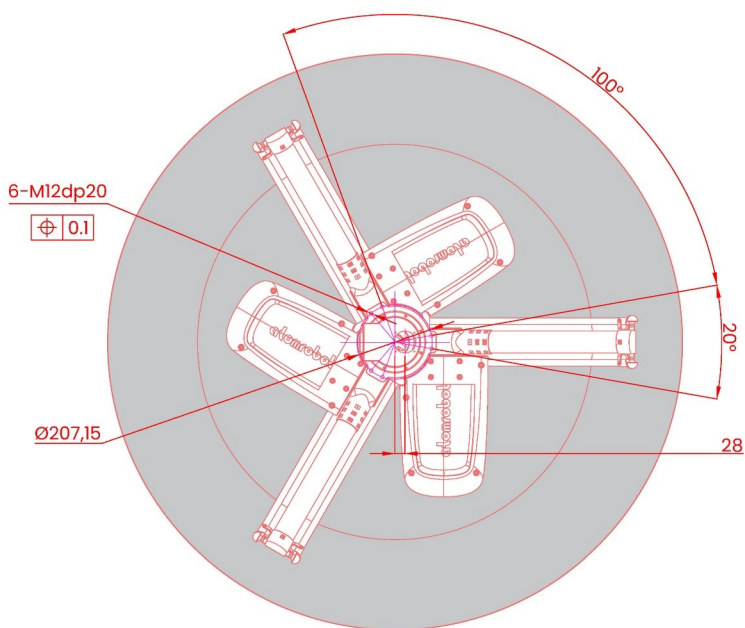
说明:  
图示下部加深部分为机器人末端运动范围, 上部为圆柱空间, 并在下部向内收敛。

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)



## D3PM-1100-P15



高稳定性

大空间

重负载

高旋转精度

High stability

Large space

Heavy load

High rotation precision

- ◆ 标准循环时间小于0.6s,满足追求最高负载和最经济需求

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- ◆ 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

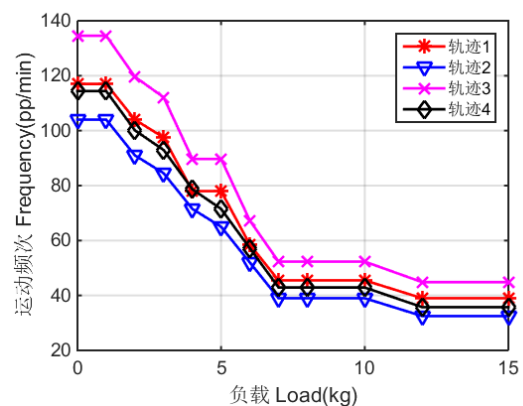
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型号 Type		D3PM-1100-P15
轴数 Axes		3+1
最大负载 Payload		15kg
机器人本体 Manipulator	重量 Weight	113kg
	工作空间直径 Diameter	1100mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.025°
旋转范围 Rotation range		±360°
允许负载最大旋转惯量 Allowable maximum moment of inertia		0.224kg·m <sup>2</sup>
主动臂角度范围 Angle range of actuated arm	上摆 Up	23.5°
	下摆 Down	70°
输入电源 Power supply	三相 Three-phase 380VAC -10%~+10%, 49~61HZ	
电源容量 Power capacity	10KVA	
额定功率 Rated Power	6.2kw	
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	

## ● 负载-频次 Load-Frequency

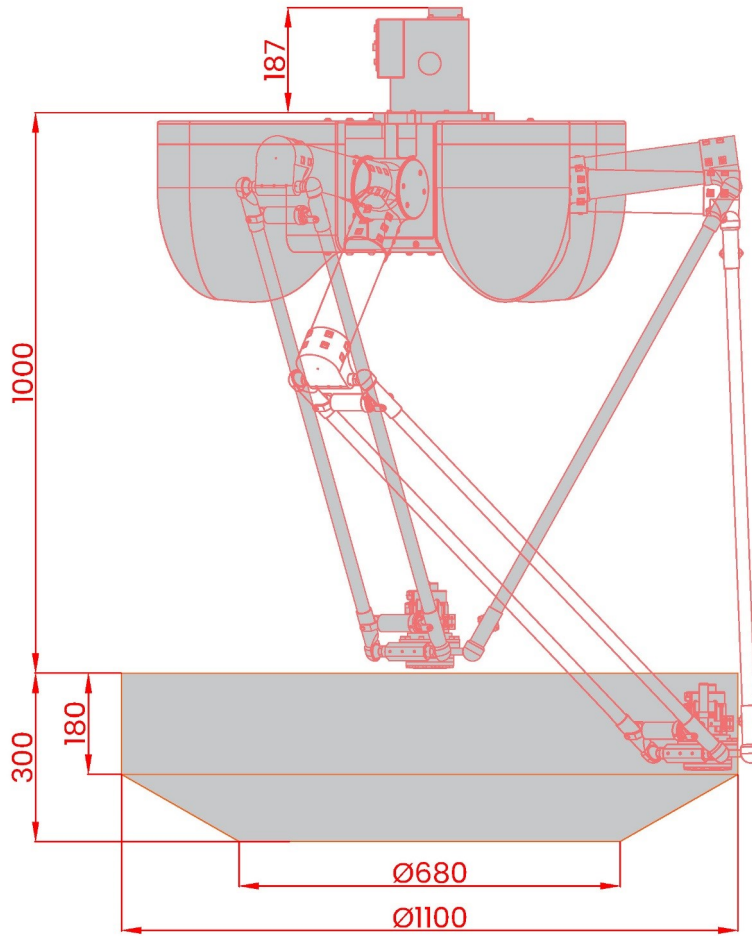


名称 Name	循环模式 Model	运动距离 Distance
轨迹1 Trajectory1	P1 → P2 → P3 → P4 → P3 → P2 → P1	h=25, b=305
轨迹2 Trajectory2	P1 → P2 → P3 → P4 → P3 → P2 → P1	h=25, b=500
轨迹3 Trajectory3	P1 → P2 → P3 → P2 → P1	h=25, b=305
轨迹4 Trajectory4	P1 → P2 → P3 → P2 → P1	h=25, b=500

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。



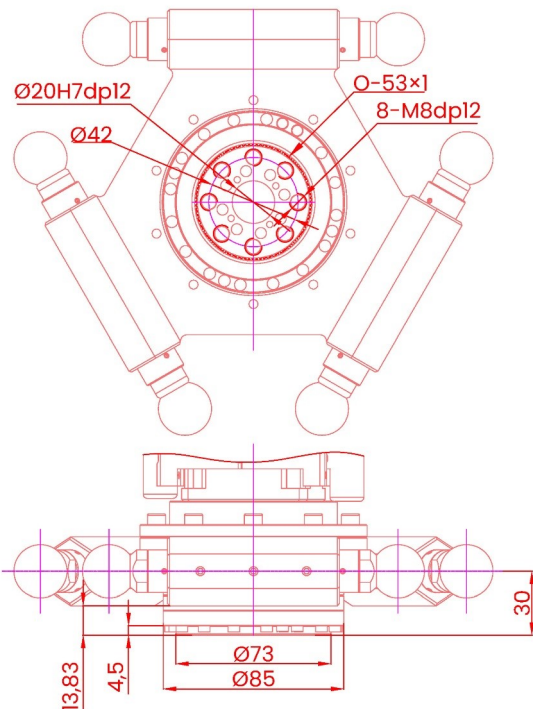
**外形尺寸及运动范围**  
**Outline dimensions and Working range (mm)**



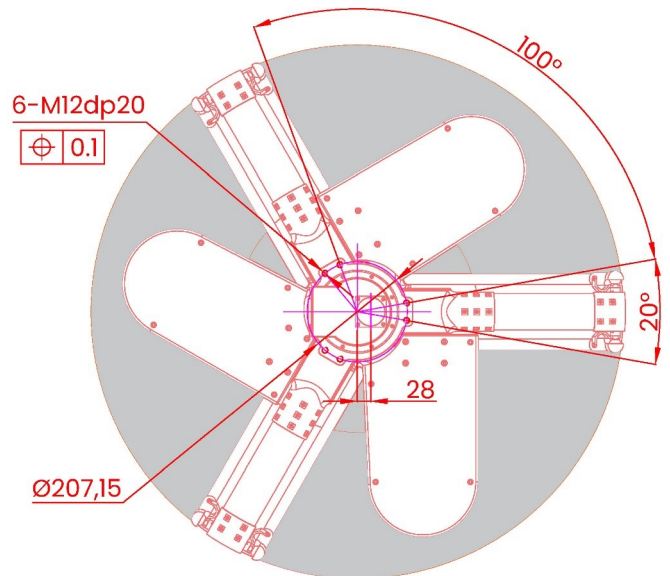
**说明:**  
图示下部加深部分为机器人末端下表面几何中心的运动范围，上部为圆柱空间，并在下部向内收敛。

**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)**





## D3PM-1400-P15



高稳定性

大空间

重负载

高旋转精度

High stability

Large space

Heavy load

High rotation precision

型号 Type		D3PM-1400-P15
轴数 Axes		3+1
最大负载 Payload		15kg
机器人本体 Manipulator	重量 Weight	125kg
	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 <sup>2</sup>
主动臂角度范围 Angle range of actuated arm	上摆 Up	29.9°
	下摆 Down	63.6°
输入电源 Power supply	三相 Three-phase 380VAC -10%~+10%, 49~61HZ	
电源容量 Power capacity	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0.6s,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.

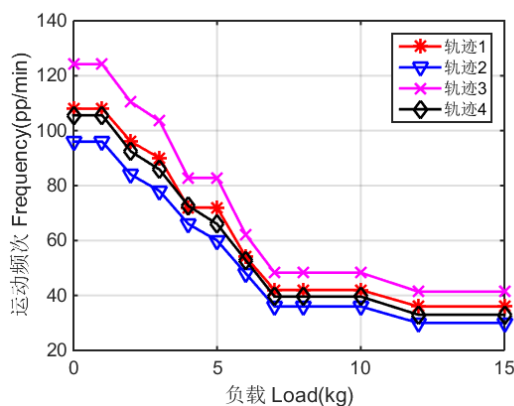
- ◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

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.

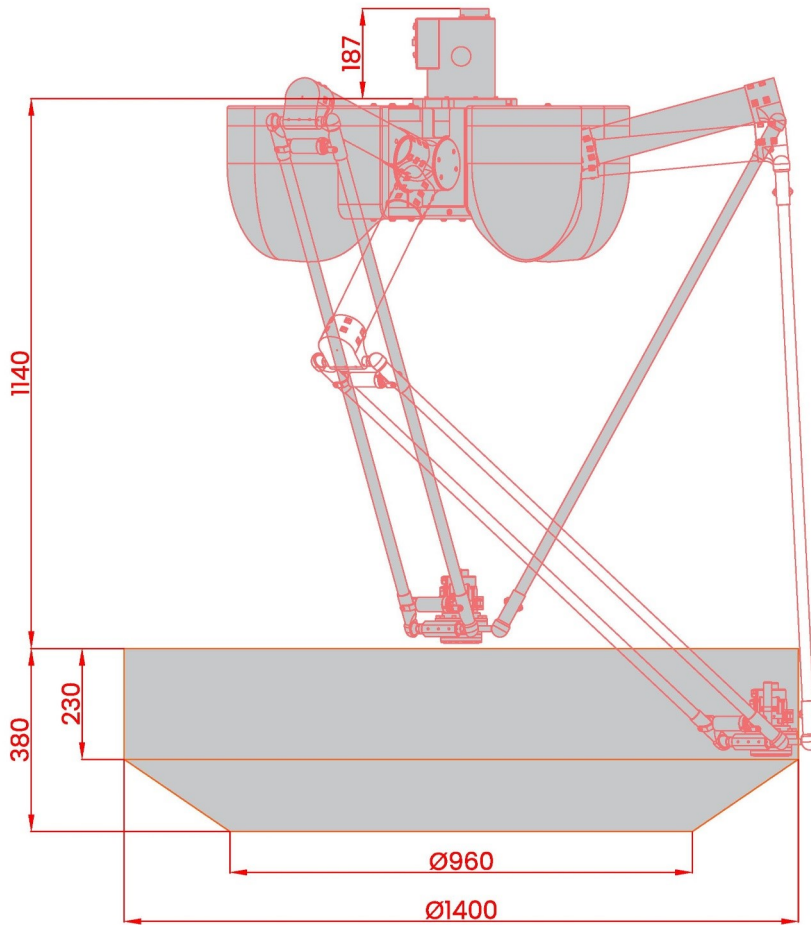
## ● 负载-频次 Load-Frequency



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。

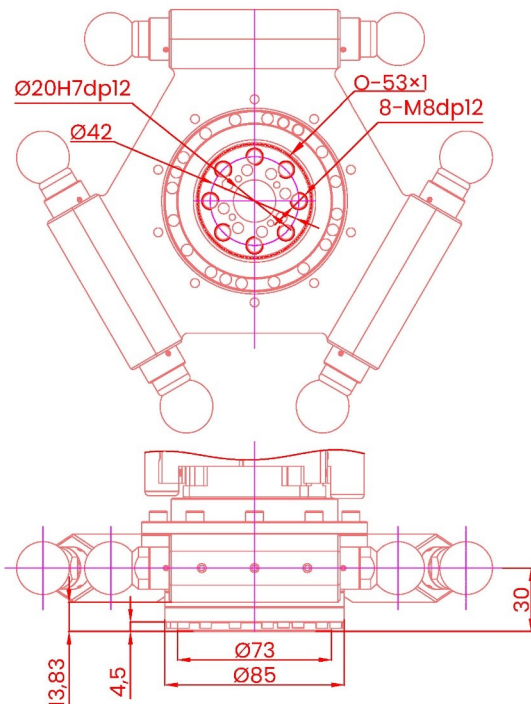
外形尺寸及运动范围  
Outline dimensions and Working range (mm)



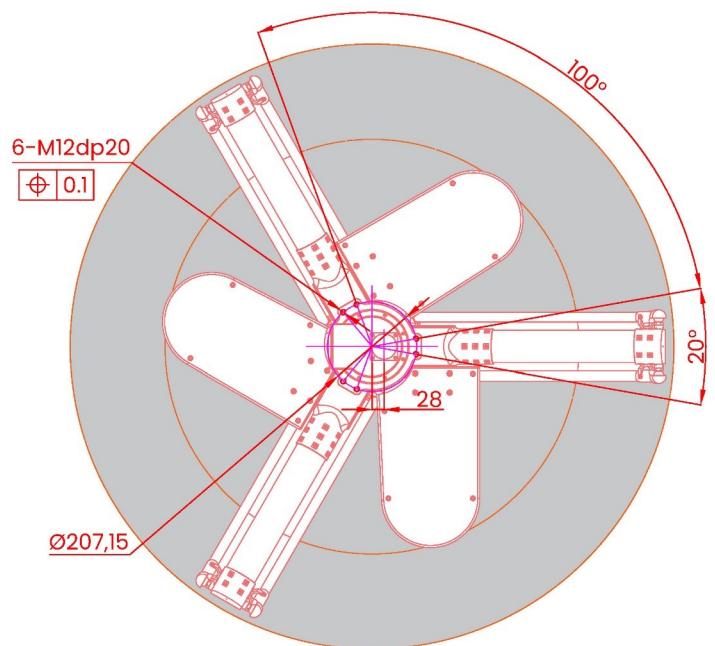
说明:  
图示下部加深部分为机器人末端下表面几何中心的运动范围, 上部为圆柱空间, 并在下部向内收敛。

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)



## D3PM-1600-P15



高稳定性

大空间

重负载

高旋转精度

High stability

Large space

Heavy load

High rotation precision

型号 Type		D3PM-1600-P15
轴数 Axes		3+1
最大负载 Payload		15kg
机器人本体 Manipulator	重量 Weight	131kg
	工作空间直径 Diameter	1600mm
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 <sup>2</sup>
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	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0.6s,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.

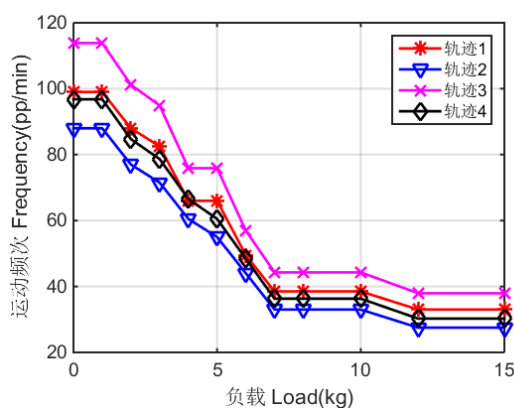
- ◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

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.

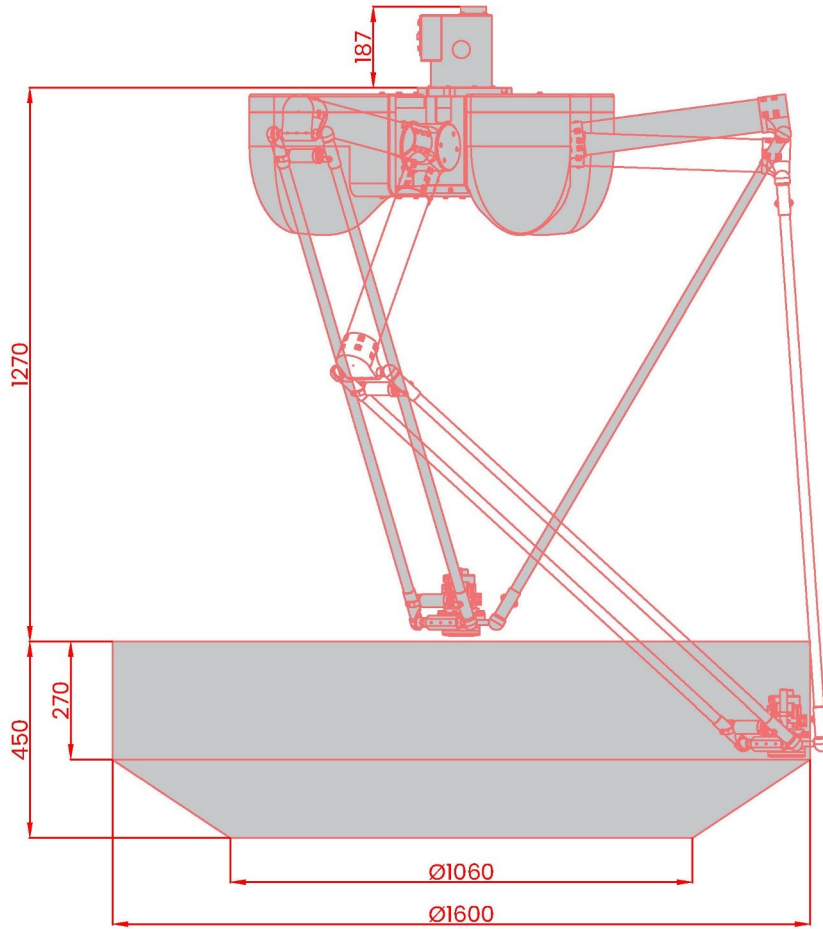
## ● 负载-频次 Load-Frequency



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。

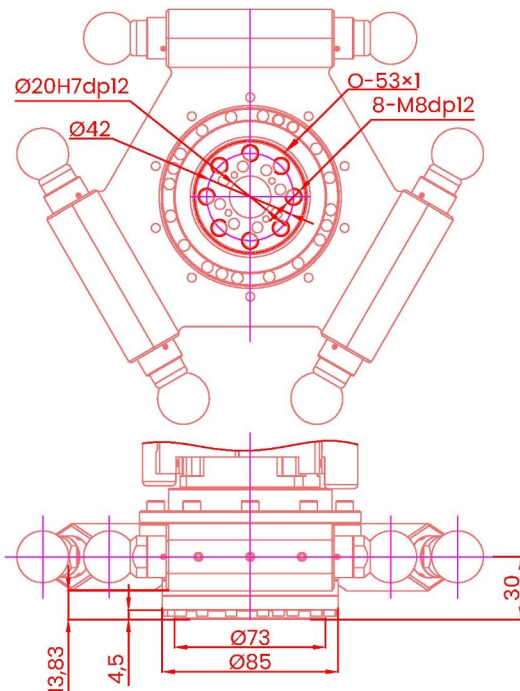
外形尺寸及运动范围  
Outline dimensions and Working range (mm)



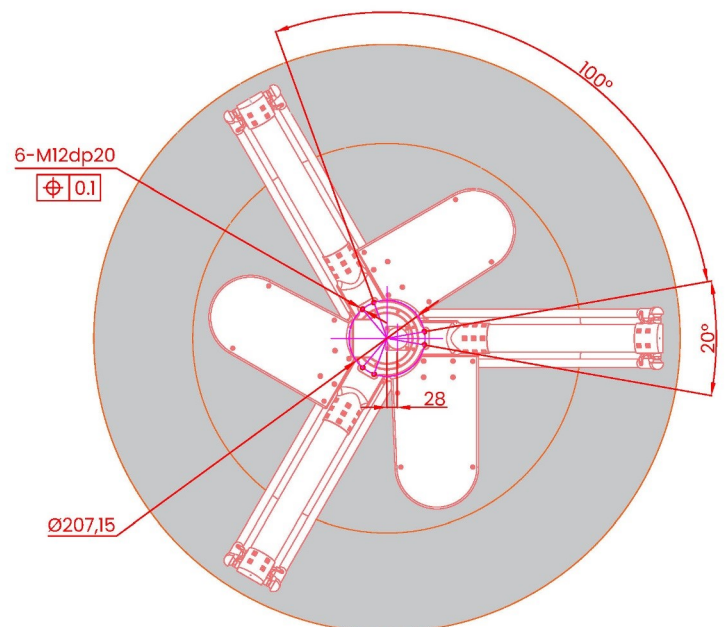
说明:  
图示下部加深部分为机器人末端下表面几何中心的运动范围, 上部为圆柱空间, 并在下部向内收敛。

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)



## D3PM-1800-P15



高稳定性

大空间

重负载

高旋转精度

High stability

Large space

Heavy load

High rotation precision

型号 Type		D3PM-1800-P15
轴数 Axes		3+1
最大负载 Payload		15kg
机器人本体 Manipulator	重量 Weight	134kg
	工作空间直径 Diameter	1800mm
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 <sup>2</sup>
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	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0.6s,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.

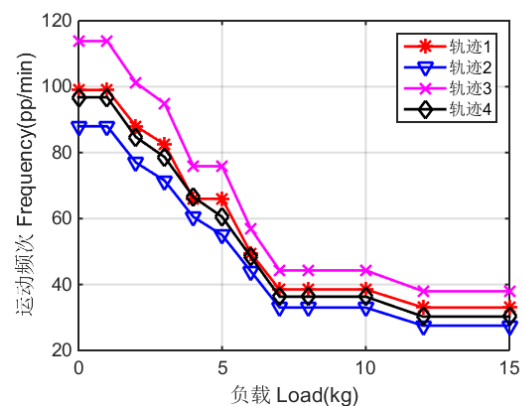
◆ 采用旋转伺服电机下置设计, 轻松满足高精度旋转作业需求

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

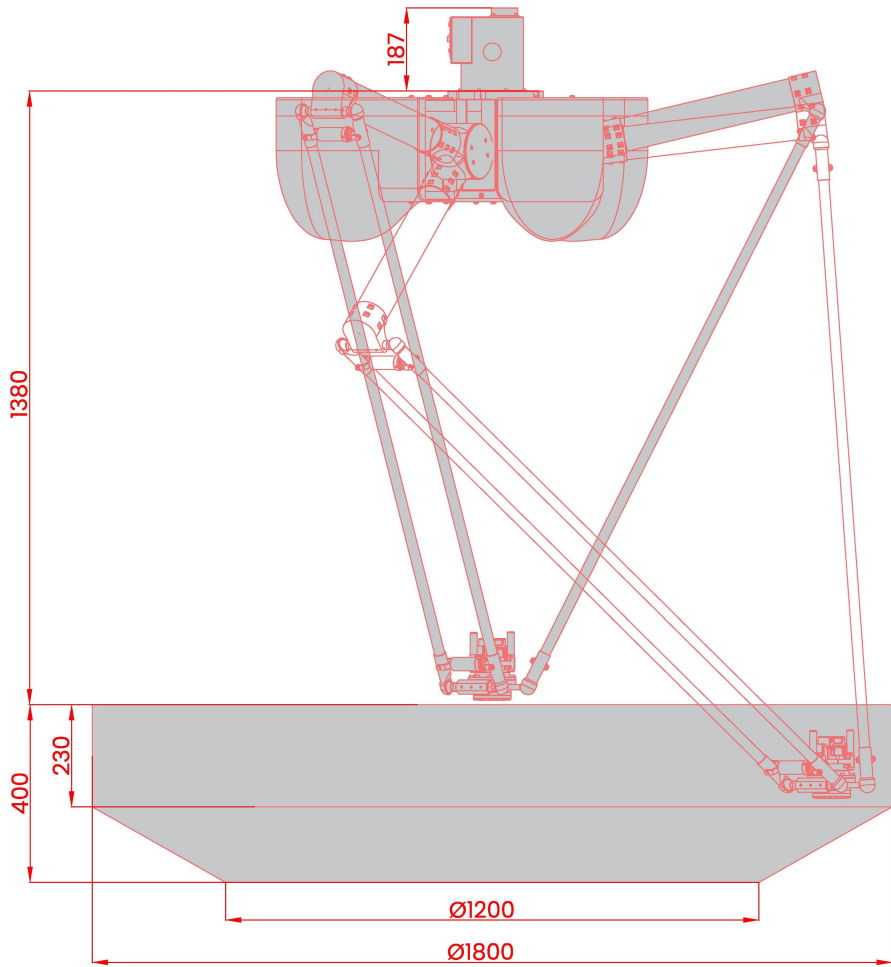


名称 Name	循环模式 Model	运动距离 Distance
轨迹1 Trajectory1	P1 → P2 → P3 → P4 → P3 → P2 → P1	h=25, b=305
轨迹2 Trajectory2	P1 → P2 → P3 → P4 → P3 → P2 → P1	h=25, b=500
轨迹3 Trajectory3	P1 → P2 → P3 → P2 → P1	h=25, b=305
轨迹4 Trajectory4	P1 → P2 → P3 → P2 → P1	h=25, b=500

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。



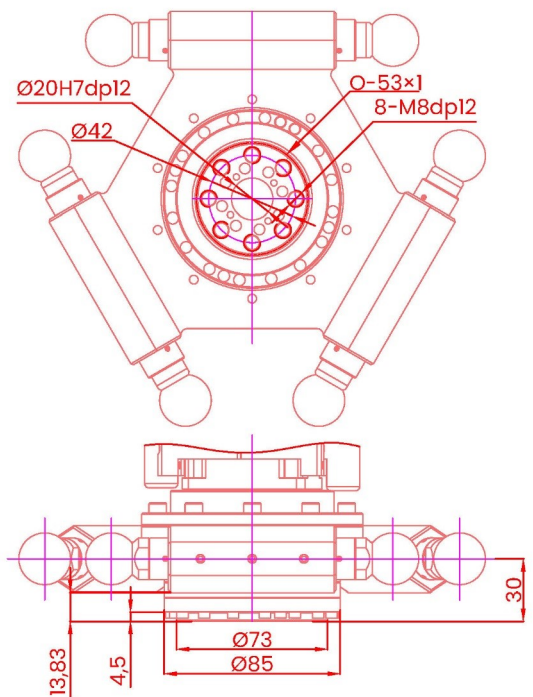
**外形尺寸及运动范围**  
**Outline dimensions and Working range (mm)**



**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)**

