



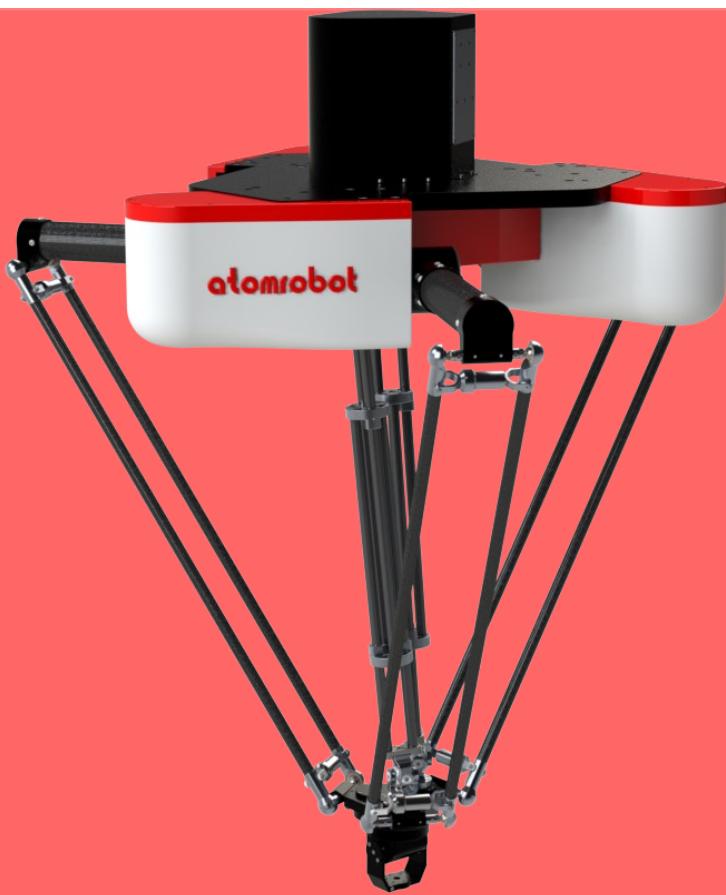
阿童木机器人

# 并联机器人

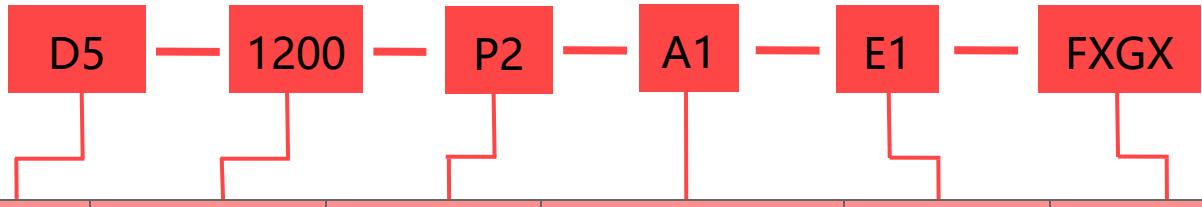
## 选型手册

Parallel Robot Selection Manual

D5

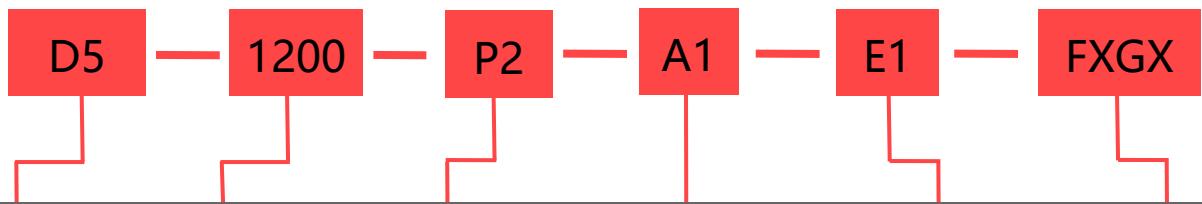


## ● 型号和符号



机型	型号	负载	控制器类型	控制柜类型	视觉
D5	800	P2: 2kg	A1: ATOMCONTROL	E1: ATOM-01 E2: ATOM-02 E3: 定制	FOGO: 无视觉 FXGX: 有视觉
	1200		A2: KEBA CONTROL		

## ● Model and Symbol



Robot type	Type	Load Type	Control Type	Control Cabinet	Vision Type
D5	800	P2: 2kg	A1: ATOMCONTROL	E1: ATOM-01 E2: ATOM-02 E3: Custom	FOGO: Without vision FXGX: With vision
	1200		A2: KEBA CONTROL		

## D5-800-P2

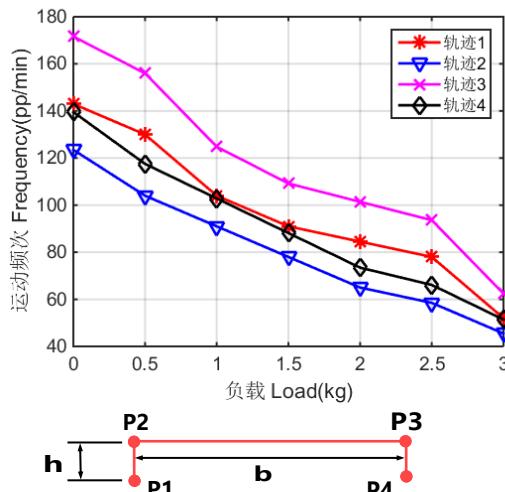


**高速度** High speed  
**高精度** High precision  
**高稳定性** High stability  
**高自由度** More degrees  
**小巧、敏捷** Small and Agile

- ◆ 具备3+2自由度，轻松满足复杂摆放场景。  
With 3+2-DOF movement in three-dimensional space, robot can be used for more complicated handling operations
- ◆ 标准循环时间小于0.5s, 满足追求最高速度和最小体积需求  
The standard cycle time is less than 0.5s, meeting your pursuit for the maximum speed and the minimum volume.
- ◆ 特殊旋转轴铰链设计，轻松应对高强度高频次重复运动需求  
Advanced design of Hooke joint in the rotational axis, enables the robot to easily cope with the high-intensity repetitive operation.
- ◆ 非常适于狭小空间内作业、3C制造等行业的高速高精密生产作业，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.

型号 Type		D5-800-P2
轴数 Axes		3+2
最大负载 Payload		2kg
机器人本体 Manipulator	重量 Weight	85kg
	工作空间直径 Diameter	800mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.1°
旋转范围 Rotation range		±360°
俯仰范围 Vertical rotation range		±90°
允许负载最大旋转惯量 (水平旋转) 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	36.5°
	下摆 Down	70.5°
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	2.7kw	
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	

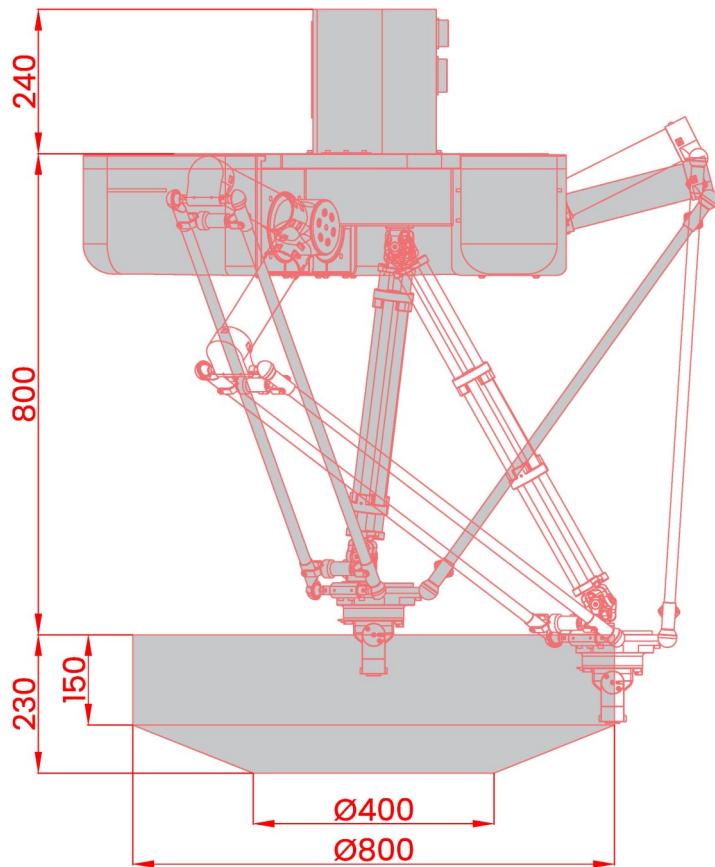
## ● 负载-频次 Load-Frequency



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，并且未包含俯仰运动，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)



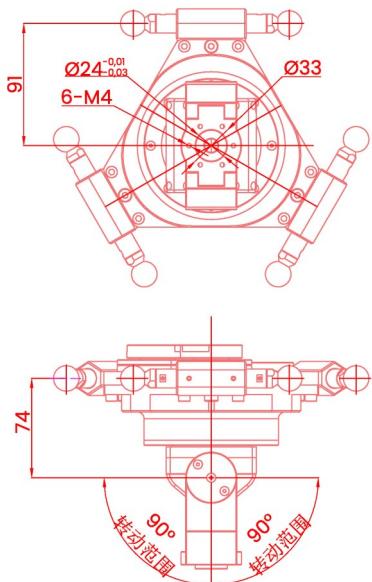
## 说明:

图示下部灰色工作空间代表末端俯仰转轴的中心点所能到达的区域。

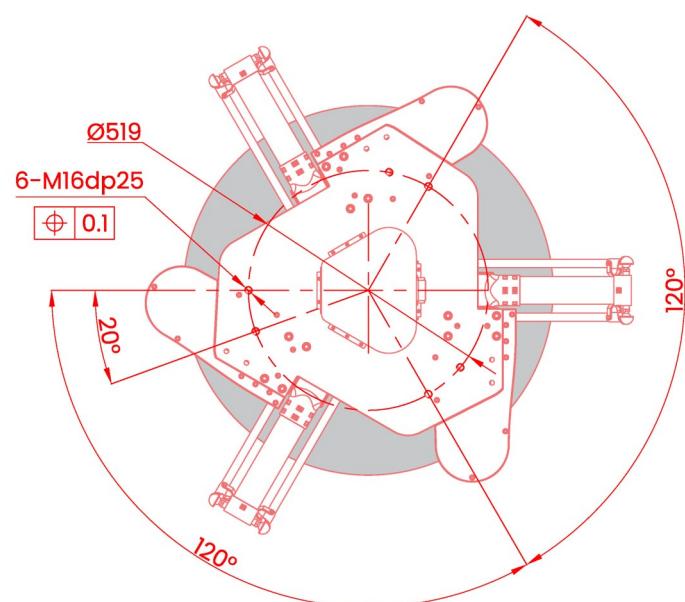
## Instruction:

The bottom gray workspace in the figure represents the area that can be reached by the center point of the end pitch axis.

法兰 Flange (mm)



基座安装 Base installation (mm)



## D5-1200-P2



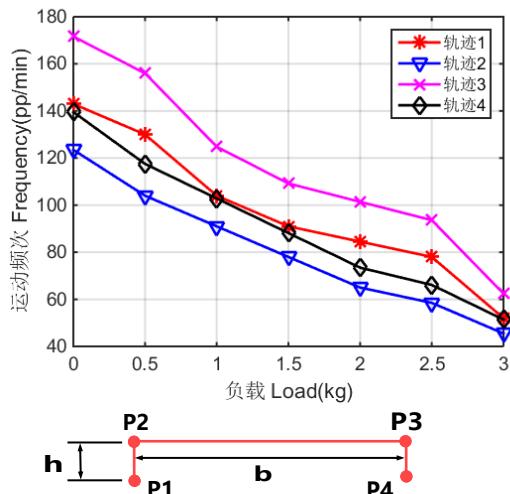
型号 Type		D5-1200-P2
轴数 Axes		3+2
最大负载 Payload		2kg
机器人本体 Manipulator	重量 Weight	90kg
	工作空间直径 Diameter	1200mm
重复定位精度 repeatability	位置 Position	0.05mm
	旋转 Rotation	0.1°
旋转范围 Rotation range		±360°
俯仰范围 Vertical rotation range		±90°
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防护等级 Protection	IP55	

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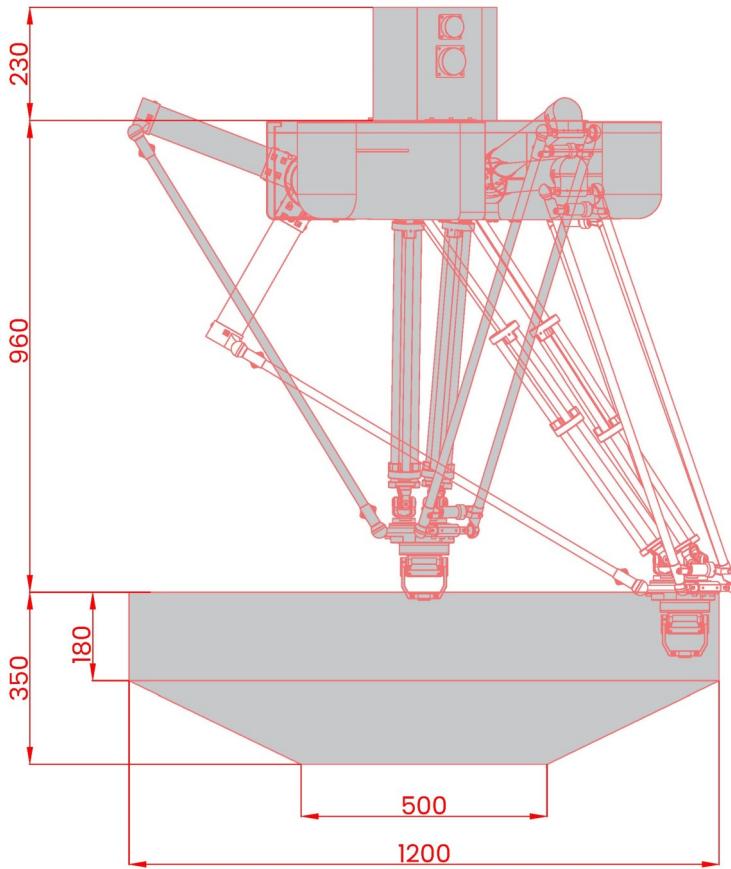
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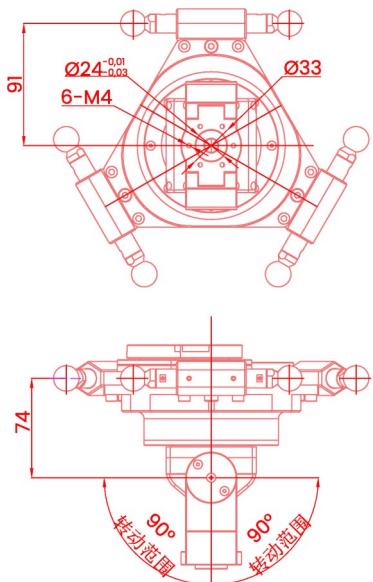
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Outline dimensions and Working range (mm)



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