

2-JAW PARALLEL GRIPPERS

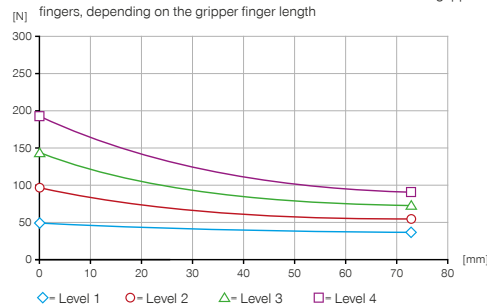
HRC-03-126902

▶ PRODUCT SPECIFICATIONS



▶ Gripping force diagram

Shows the arithmetic total of the individual forces that occur on the gripper fingers, depending on the gripper finger length



▶ Forces and moments

Displays static forces and moments that can also have an effect, besides the gripping force.



Mr [Nm]	7
Mx [Nm]	7
My [Nm]	5.5
Fa [N]	200

▶ TECHNICAL DATA

Order no.	HRC-03-126902
Suitable for robot type	ISO TK 50**
MRK design according to ISO/TS 15066	Yes
HRC form	collaborative
Cable management	external
Type of drive	electrical
Control	IO-Link
Integrated position sensing	Using process data
Stroke per jaw [mm]	10
Self locking mechanism	mechanical
Gripping force in closing (adjustable) max. [N]	190
Gripping force in opening (adjustable) max. [N]	190
Gripping force in accordance with ISO/TS 15066 [N]*	<140
Closing time [s]	0.19
Opening time [s]	0.19
Control time [s]	0.03
Dead weight of mounted gripper finger max. [kg]	0.1
Length of the gripper fingers max. [mm]	80
Repetition accuracy +/- [mm]	0.05
Operating temperature [°C]	5 ... +50
Voltage [V]	24
Current consumption max. [A]	1
Minimum positioning path per jaw [mm]	0.5
Protection to IEC 60529	IP40
Weight [kg]	0.73

* Value based on the parameters described in the ISO/TS 15066, determined with a force measuring device certified by the DGUV (German Social Accident Insurance)

** Mechanical assembly compatible to all robots with standard ISO PCD 50 mm. Electrical connection via standard IO-Link M12-5 female connector.

▶ TECHNICAL DRAWINGS

- ① Gripper attachment
- ② Energy supply
- ③ Fixing for gripper finger
- ④ Emergency release
- ⑥ Status display

