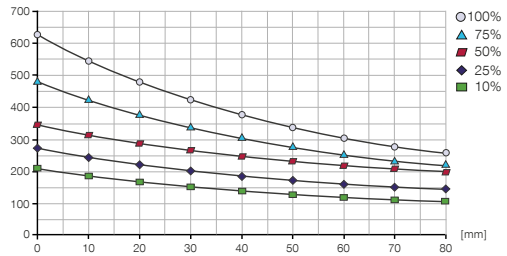
2-JAW PARALLEL GRIPPERS WITH LONG STROKE
HRC-01-102270

▶ 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 and the set gripping force



▶ Forces and moments

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

Mr [Nm]	25
Mx [Nm]	25
My [Nm]	25
Fa [N]	500

▶ TECHNICAL DATA

Order no.	HRC-01-102270
Suitable for robot type	ISO TK 50* *
MRK design according to ISO/TS 15066	Yes
HRC form	cooperative
Cable management	external
Safety function	STO
Type of drive	electrical
Control	IO-Link
Integrated position sensing	Using process data
Stroke per jaw [mm]	40
Stroke per jaw, adjustable [mm]	40
Self locking mechanism	mechanical
Gripping force min. [N]	120
Nominal gripping force [N]	620
Gripping force in accordance with ISO/TS 15066 [N]*	>140
Control time [s]	0.1
Dead weight of mounted gripper finger max. [kg]	0.3
Length of the gripper fingers max. [mm]	80
Jaw speed in force mode max. [mm/s]	50
Jaw speed in positioning mode max. [mm/s]	60
Repetition accuracy +/- [mm]	0.05
Operating temperature [°C]	5 ... +50
Voltage [V]	24
Current consumption max. [A]	7.5
Minimum positioning path per jaw [mm]	3
Protection to IEC 60529	IP40
Weight [kg]	1.6

*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