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

