

2-JAW PARALLEL GRIPPERS

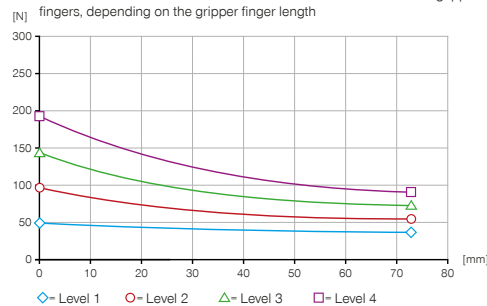
HRC-03-151986

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-03-151986
Suitable for robot type	ABB CRB 15000 GoFa
MRK design according to ISO/TS 15066	Yes
HRC form	collaborative
Robot adaptation	directly on robot flange (adapter plate integrated)
Adapter plate type	Robot flange to ISO TK
Cable management	internal
Type of drive	electrical
Control	I/O
Position sensing	integrated
Position query magnetic field	Yes
Switching output	PNP
Stroke per jaw [mm]	10
Self locking mechanism	mechanical
Nominal gripping force [N]	190
Gripping force in accordance with ISO/TS 15066 [N]*	<140
Grip direction	External / internal gripping
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]	0.68

*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)

TECHNICAL DRAWINGS

