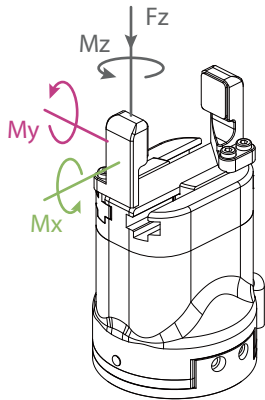


PGC-50-35

Collaborative parallel gripper



Allowable vertical load (static)

Fz: 150 N

Allowable vertical load (static)

Mx: 2.5 N·m

My: 2 N·m

Mz: 3 N·m

DH-ROBOTICS

Gripping force

15~50 N

Stroke

35 mm

Mechanical specifications

Recommended workpiece weight* 1 kg

Repeat accuracy (positioning) ± 0.03 mm

Opening/closing time 0.7 s/0.7 s

Driving method Precise planetary gears + Rack and pinion + T-slot guide

Weight 0.5 kg

Noise emission < 50 dB

Electrical specifications

Communication Standard: Modbus RTU (RS485), Digital I/O interface Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT

Rated voltage 24 V DC ± 10%

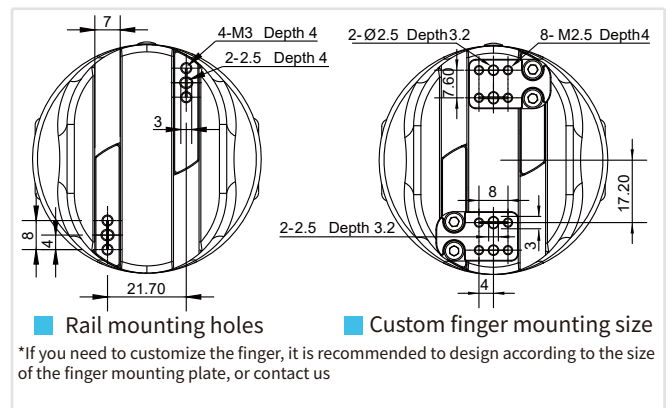
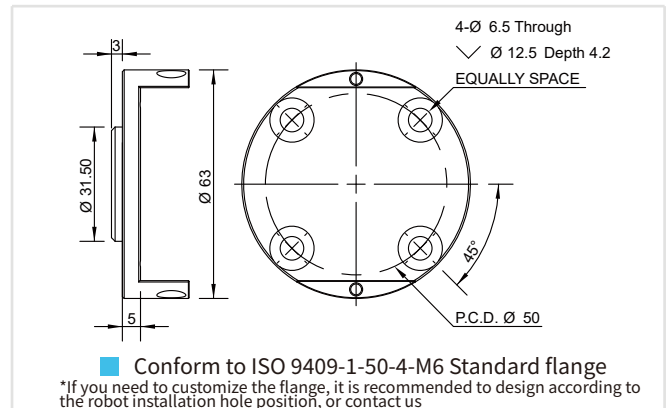
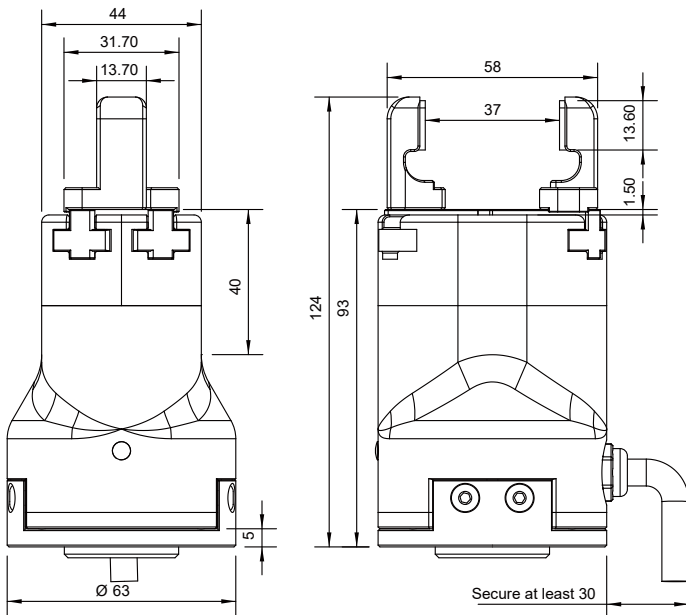
Rated current 0.25 A

Peak current 0.5 A

IP class IP 54

Recommended environment 0~40°C, under 85% RH

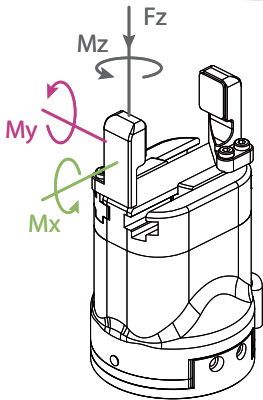
*It depends on the shape of the grasping object, the material and friction of the contact surface, and the acceleration of the motion, if you have any questions, please contact us.



PGC-140-50

DH-ROBOTICS

Collaborative parallel gripper



Allowable vertical load (static)

Fz: 300 N

Allowable vertical load (static)

Mx: 7 N·m

My: 7 N·m

Mz: 7 N·m

Gripping force

40~140 N

Stroke

50 mm

Mechanical specifications

Recommended workpiece weight* 3 kg

Repeat accuracy (positioning) ± 0.03 mm

Opening/closing time 0.6 s/0.6 s

Driving method Precise planetary gears + Rack and pinion + T-slot guide

Weight 1 kg

Noise emission < 50 dB

Electrical specifications

Communication Standard: Modbus RTU (RS485), Digital I/O interface Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT

Rated voltage 24 V DC ± 10%

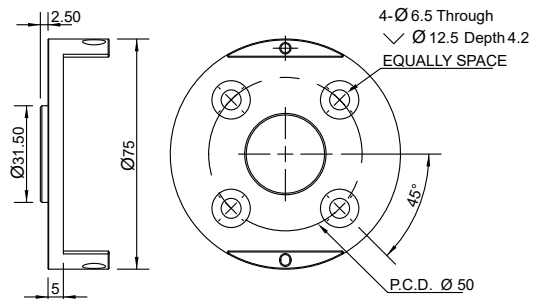
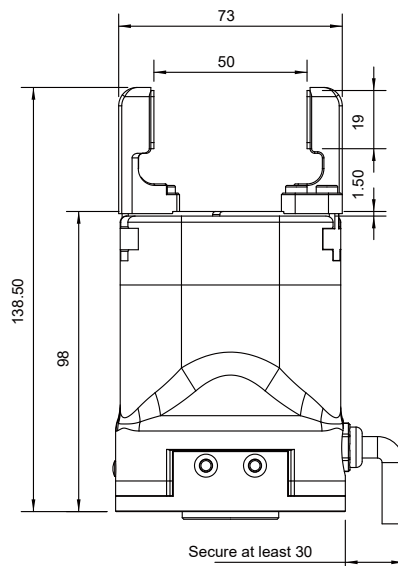
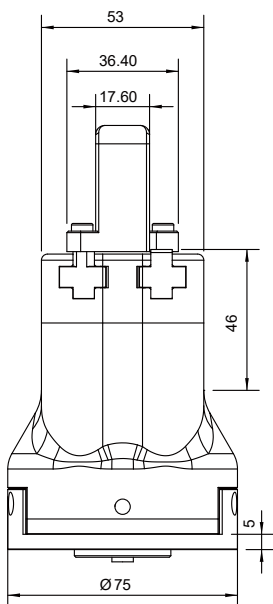
Rated current 0.4 A

Peak current 1 A

IP class IP 67

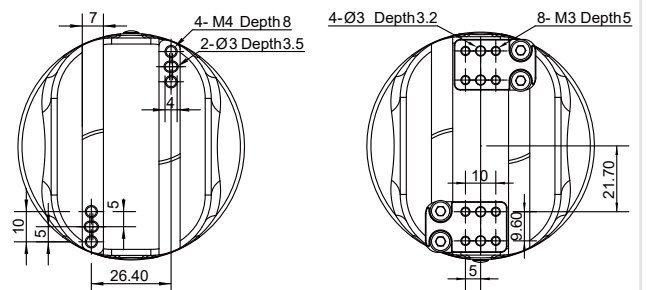
Recommended environment 0~40°C, under 85% RH

*It depends on the shape of the grasping object, the material and friction of the contact surface, and the acceleration of the motion, if you have any questions, please contact us.



Conform to ISO 9409-1-50-4-M6 Standard flange

*If you need to customize the flange, it is recommended to design according to the robot installation hole position, or contact us



Rail mounting holes

Custom finger mounting size

*If you need to customize the finger, it is recommended to design according to the size of the finger mounting plate, or contact us

