

Servo Electric Grippers

EN-2024.03



DH-ROBOTICS

DH-Robotics is a high-tech company which focus on providing core components for industrial intelligent manufacturing scenarios. Based on the self-developed precision force control direct drive technology, we provide customers in various industries around the world with diversified electric grippers and precision motion products to reduce production costs, improve production efficiency, and achieve intelligent manufacturing.

Our Support System



R&D System



New Technology



Innovation



R&D



Engineering Management



Sales Network



Projects Assessment



Training



Quality Supervision



After-sales Service



Manufacturing



Quality System



Stock Management



Supply Management



Manufacturing

CONTENTS

| | |
|---------------------------|---|
| Applications | 4 |
| Selection Reference | 7 |
| Products Brief Parameters | 9 |

PGE Series Slim-type Electric Parallel Gripper



| | |
|------------|----|
| PGE-2-12 | 16 |
| PGE-5-26 | 17 |
| PGE-8-14 | 20 |
| PGE-15-10 | 22 |
| PGE-15-26 | 24 |
| PGE-50-26 | 26 |
| PGE-50-40 | 28 |
| PGE-100-26 | 30 |

PGSE Series Slim-type Electric Parallel Gripper



| | |
|-----------|----|
| PGSE-15-7 | 34 |
|-----------|----|

RGI Series Electric Rotary Gripper



| | |
|-------------|----|
| RGI-100-14 | 39 |
| RGI-100-22 | 40 |
| RGI-100-30 | 41 |
| RGIC-35-12 | 42 |
| RGIC-100-35 | 44 |

RGD Series Electric Direct Drive Rotary Gripper



| | |
|-----------|----|
| RGD-5-14 | 48 |
| RGD-5-30 | 48 |
| RGD-35-14 | 51 |
| RGD-35-30 | 51 |

PGI Series

Electric Parallel Gripper



PGI-140-80 56

PGHL Series

**Heavy-Load Long-Stroke
Electric Parallel Gripper**



PGHL-400-80 58

PGS Series

**Miniature Electro Magnetic
Gripper**



PGS-5-5 64

PGC Series

**Electric Collaborative
Parallel Gripper**



PGC-50-35 68
PGC-140-50 70
PGC-300-60 72

AG Series

Electric Adaptive Gripper



AG-160-95 76
AG-105-145 78
DH-3 80

CG Series

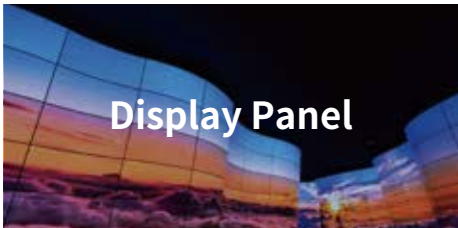
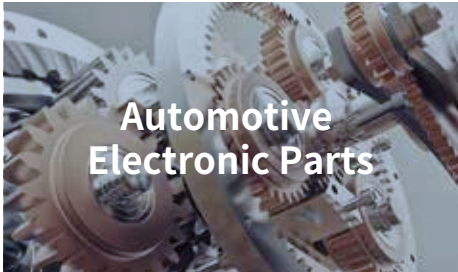
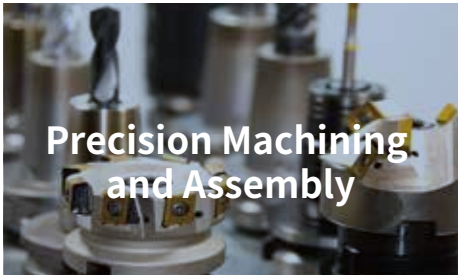
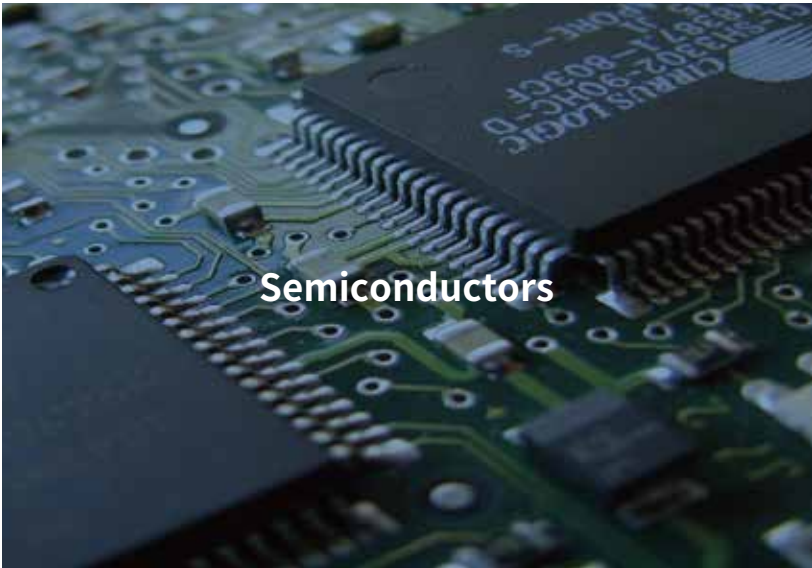
Electric Centric Gripper



CGE-10-10 84
CGI-100-170 86
CGC-80-10 88

Applications in Cutting-edge Industries

More solutions and applications, please visit www.dh-robotics.com



Application cases



PGE-8-14 Automatic Application

One collabotative robot with two electric grippers to complete the loading and unloading.



PGE-8-14 Electronics

Handling and positioning of very small workpieces.



RGI-35-14 Medical Automation

The automatic sub-cup processing system, through ABB' s Scara robotic arm and DH-Robotics electric gripper, can automatically complete the operation of sample tube opening, scanning, information entry, pipetting, turning plate, and closing lid.



PGE-15-26 Medical Automation

Double-channel scan code to read the information, and unscrew the tube cover. Participate in automatic cup sharing process.

Application cases



PGC-50-35 Automation

Two PGC-50-35 grippers were applied with UR robot to pick& place the work-pieces on production line.



AG-160-95 Automotive

AG-160-95 electric gripper was applied with a collaborative robot to complete the clamping and assembly of needle roller bearings.



PGC-140-50 Robot New Retail

The PGC-140-50 was applied with DOOSAN robot to complete a show in CHANEL stores located in 20 countries to celebrate the 100th anniversary of CHANEL No. 5 perfume.



AG-160-95 Machining

The AG-160-95 electric gripper was applied with AGV and COBOT to complete machine tool loading and unloading and machine tool equipment management.







Short wire correspondence table

Our gripper can directly connect to the end interface of each brand of collaborative robot through a short wire.
(The serial number represent the short wire type.)

| Support electric gripper models | UR CB Series | UR E Series | Elite CS Series | SIASUN | Hanwha A Series | ROKAE CR Series | DOBOT CR Series | DOBOT Nova Series | Aubo | Elephant | Jaka | ECHMAN | ROKAE SR Series | ROKAE ER Series | DOBOT MG400 | UR E Series | Doosan A Series | Doosan M Series | Elite EC Series | Han's Robot | Neuromeka | FAIRINO | Hanwha HCR | UF xArm | ROKAE CR |
|--|--------------|-------------|-----------------|--------|-----------------|-----------------|-----------------|-------------------|------|----------|------|--------|-----------------|-----------------|-------------|-------------|-----------------|-----------------|-----------------|-------------|-----------|---------|------------|---------|----------|
| Small current electric gripper (Peak current ≤ 0.6A) | 01 | | | | | | | | | | | | | | | | | | | | | | | | |
| Small current electric gripper (Peak current < 1.5A) | | 01 | 01 | 01 | 01 | | | | 02 | 03 | 04 | 05 | 06 | 06 | 07 | | | | | | | | | | |
| High current electric claw (Peak current > 1.5A) | | | | | | | | | | | | | | | | 08 | | | | | | | | | |
| In common (Support large and small current electric gripper) | | | | | | 01 | 01 | 01 | | | | | | | | | 09 | 10 | 11 | 12 | 13 | 14 | 15 | 16 | 17 |






DH-Robotics' Gripper and Cylinder Communication Protocol Conversion Box

The communication within DH-Robotics' Servo Gripper and Servo Electric Cylinder defaults to Modbus RTU (RS485) and a small number of I/O. If customers choose other communication protocols, they will need to use the communication protocol conversion box. The following communication protocol conversion boxes are available for selection:

| | Communication Protocol Conversion Box Name | Ordering Model | | Communication Protocol Conversion Box Name | Ordering Model |
|---|--|--|--|--|----------------|
|  | EtherCAT 1-1 | M2E-B1-1 |  | TCP/IP 1-1 | M2T-B1-1-YBT |
|  | EtherCAT 1-4 | M2E-B1-4 |  | PROFINET 1-2 | M2P2-B1-2-HJ |
|  | EtherCAT转 I/O 1-More | Please contact our technical staff confirm the specific parameters |  | PROFINET 1-11 | M2P-B1-11-9 |

Quick Selection Reference

According to the following five conditions, you can quickly and initially select the matching gripper model; or you can also consult sales for detailed understanding and selection.

| Condition 1 Application | Condition 2 Workpiece weight | Condition 3 Gripping stroke | Condition 4 Feature selection | Condition 5 Environmental requirements |
|---|--|---|--|--|
|  |  |  |  |  |
| <input type="checkbox"/> Collaborative robot <input type="radio"/> Load <input type="radio"/> Peak current <input type="checkbox"/> Industrial robot <input type="checkbox"/> Automation module | <input type="checkbox"/> Workpiece shape <input type="checkbox"/> Workpiece material <input type="checkbox"/> Friction <input type="checkbox"/> ... | <input type="checkbox"/> Workpiece size <input type="checkbox"/> Parallel / centric <input type="checkbox"/> Outer clip, inner support <input type="checkbox"/> Fingertip design <input type="checkbox"/> ... | <input type="checkbox"/> Rotary <input type="checkbox"/> Self-locking <input type="checkbox"/> Envelope grab <input type="checkbox"/> ... | <input type="checkbox"/> IP class <input type="checkbox"/> Temperature conditions <input type="checkbox"/> ... |

Precautions on Model Selection

Note 1: Confirm the required gripping force and workpiece quality

When the workpiece is clamped by the friction force generated by the clamping force, the required clamping force is calculated as follows:

- F: Clamping force (N)
- μ : Friction coefficient
- m: Workpiece quality (kg)
- g: Acceleration due to gravity (9.8m/s^2)
- mg: Workpiece weight (N)

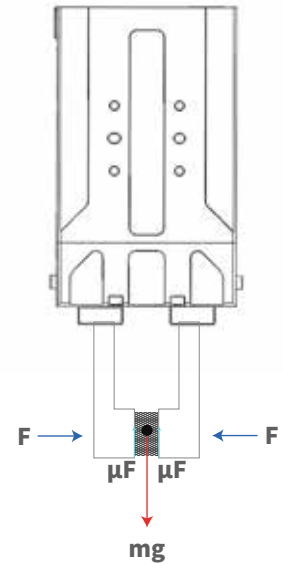
Clamped workpiece, The condition that the workpiece will not fall is

number of gripper fingers \uparrow
 $2 \times \mu F > mg$

Thus: $F > \frac{mg}{2 \times \mu}$

| Friction coefficient μ | Fingertip and workpiece material (benchmark) |
|----------------------------|--|
| 0.1 | Metal(Surface roughness under Rz3.2) |
| 0.2 | Metal |
| Over 0.2 | Rubber, resin |

(Reference) The friction coefficient(μ) varies depending on the usage environment, surface pressure, workpiece shape, etc.



Note 2: Confirm gripper stroke and fingertip

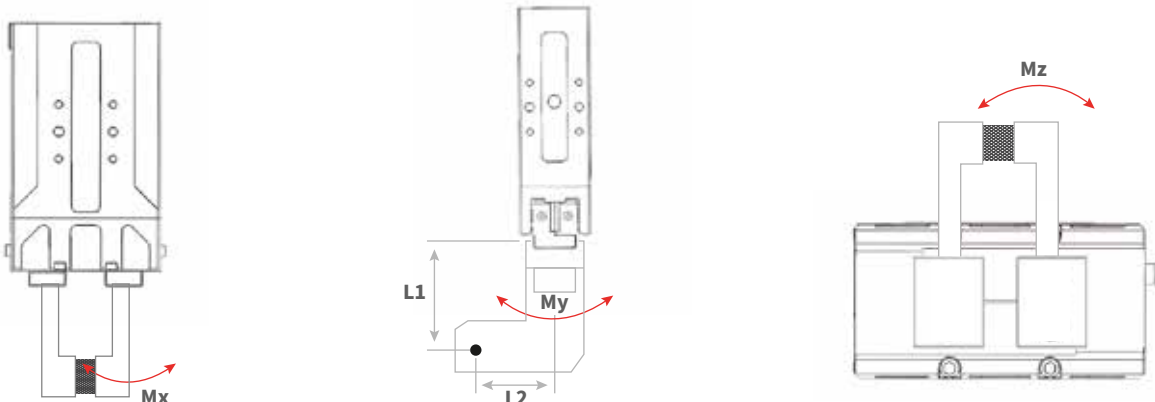
- The stroke of the gripper needs to be greater than the difference between the maximum and minimum dimensions of the workpiece.
- Choose the right fingertip: The fingertip is too long, too big, and the weight is too heavy, the inertia force or bending moment when opening and closing will affect the gripper, which may cause the performance of the gripper to decrease or shorten the service life.

Note 3: Check the external force exerted on the gripper

- The vertical load borne by the clamping jaw must be within the allowable load.
- The moment the clamping jaws bear must be within the maximum allowable load moment.

· Allowable load F(N) = $\frac{M(\text{Load allowable moment}) (N \cdot m)}{L(\text{mm}^2) \times 10}$

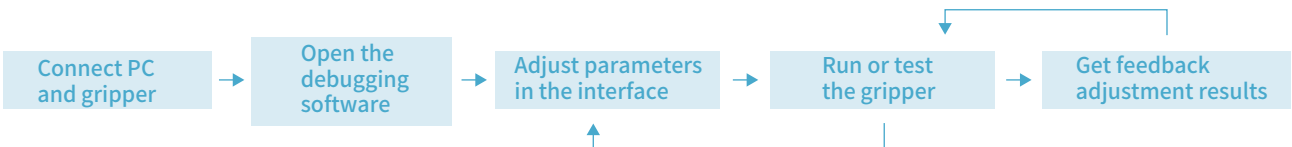
Note: Mx and My are calculated by L1, and Mz is calculated by L2. Confirm whether the calculated gripper can withstand the external force (based on the smaller F value calculated from Mx, My, Mz).



Host Computer Debugging Software (PC Side)

User-friendly

The host computer debugging software was self-developed by DH-Robotics, it can help customers easily and quickly complete various function parameters adjustments, testing and initialization setting on the PC side. At the meaning time, various status information is provided in real time, which can save a lot of production line setup time and reduce the difficulty of operation and maintenance for on-site engineers.

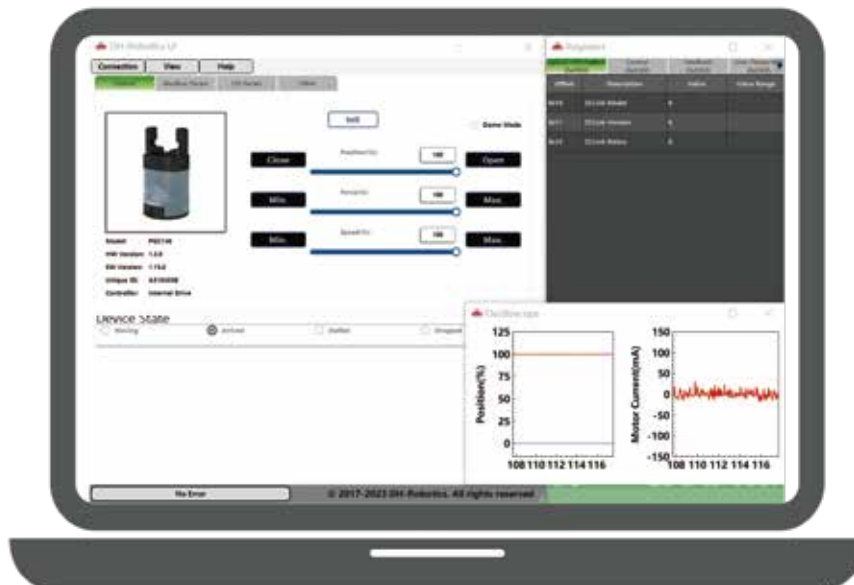


Parameters Adjustable

- gripping force
- fingertip position
- gripping speed
- rotation angle*
- rotation speed*
- rotation force(torque force)*

Real-time feedback

- four gripping states
 - ① movement status
 - ② in place
 - ③ clamp state
 - ④ dropped state
- location versus time graph
- clamping current as a function of time



Example: DH-Robotics PC software

* Please consult sales person for specific applicable models

Products Brief Parameters

PGE Series Slim-type Electric Parallel Gripper

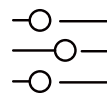
Precision
force control

Small Size

Fast
Response



All-in-one
Design



Adjustable
Parameters



Intelligent
Feedback



Replaceable
Fingertip



Self-locking
Mechanism



PGE-2-12



PGE-5-26



PGE-8-14



PGE-15-10



PGE-15-26



PGE-50-26



PGE-50-40



PGE-100-26

| | Gripping Force (N) | Recommended workpiece weight(kg) | Stroke (mm) | Opening/closing time(s) | IP Class |
|------------|--------------------|----------------------------------|-------------|-------------------------|----------|
| PGE-2-12 | 0.8~2 | 0.05 | 12 | 0.15 | IP40 |
| PGE-5-26 | 0.8~5 | 0.1 | 26 | 0.3 | IP40 |
| PGE-8-14 | 2~8 | 0.1 | 14 | 0.3 | IP40 |
| PGE-15-10 | 6~15 | 0.25 | 10 | 0.3 | IP40 |
| PGE-15-26 | 6~15 | 0.25 | 26 | 0.5 | IP40 |
| PGE-50-26 | 15~50 | 1 | 26 | 0.45/0.45 | IP40 |
| PGE-50-40 | 15~50 | 1 | 40 | 0.6/0.6 | IP40 |
| PGE-100-26 | 30~100 | 2 | 26 | 0.5 | IP40 |

PGSE Series Slim-type Electric Parallel Gripper

Small Size

Fast
Response



All-in-one
Design




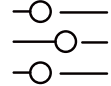


Replaceable
Fingertip



PGSE-15-7

| | Gripping Force (N) | Recommended workpiece weight(kg) | Stroke (mm) | Opening/closing time(s) | IP Class |
|-----------|--------------------|----------------------------------|-------------|-------------------------|----------|
| PGSE-15-7 | 6~15 | 0.25 | 7 | 0.15 | IP40 |


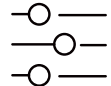



RGI Series Electric Rotary Gripper

| | | |
|--|--|--|
| Infinite Rotation | Dual Servo System | Compact Type |
|  All-in-one Design |  Adjustable Parameters |  Intelligent Feedback |
| | |  Replaceable Fingertip |



| | Gripping Force (N) | Recommended workpiece weight(kg) | Stroke (mm) | Opening/closing time(s) | IP Class |
|-------------|--------------------|----------------------------------|-------------|-------------------------|----------|
| RGI-100 | 30~100 | 1.5 | 14/22/30 | 0.6/0.65/0.7 | IP40 |
| RGIC-35-12 | 13~35 | 0.5 | 12 | 0.6 | IP40 |
| RGIC-100-35 | 40~100 | 1 | 35 | 0.9 | IP40 |


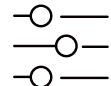



RGD Series Electric Direct Drive Rotary Gripper

| | | |
|--|--|---|
| Zero Backlash | Infinite Rotation | Precise Positioning |
|  All-in-one Design |  Adjustable Parameters |  Intelligent Feedback |
| | |  Replaceable Fingertip |
| | |  Self-locking Mechanism |



| | Gripping Force (N) | Recommended workpiece weight(kg) | Stroke (mm) | Opening/closing time(s) | IP Class |
|--------|--------------------|----------------------------------|-------------|-------------------------|----------|
| RGD-5 | 2~5.5 | 0.05 | 14/30 | 0.5 | IP40 |
| RGD-35 | 10~35 | 0.35 | 14/30 | 0.5/0.7 | IP40 |

PGI Series Electric Parallel Gripper

| | | |
|--|--|---|
| High Load | High Protection Grade | Long Stroke |
|  All-in-one Design |  Adjustable Parameters |  Intelligent Feedback |
| | |  Replaceable Fingertip |
| | |  Self-locking Mechanism |



| | Gripping Force (N) | Recommended workpiece weight(kg) | Stroke (mm) | Opening/closing time(s) | IP Class |
|------------|--------------------|----------------------------------|-------------|-------------------------|----------|
| PGI-140-80 | 40~140 | 3 | 80 | 1.1 | IP54 |

PGHL Series Heavy-Load Long-Stroke Electric Parallel Gripper

High Load

High Protection Grade

Long Stroke



All-in-one Design



Adjustable Parameters



Intelligent Feedback



Replaceable Fingertip



Self-locking Mechanism



PGHL-400-80

| | Gripping Force (N) | Recommended workpiece weight(kg) | Stroke (mm) | Opening/closing time(s) | IP Class |
|-------------|--------------------|----------------------------------|-------------|-------------------------|----------|
| PGHL-400-80 | 140~400 | 8 | 80 | 1.0/1.1 | IP40 |

PGS Series Miniature Electro-magnetic Gripper

Small Size

High Frequency

Easy Operation



Replaceable Fingertip



Self-locking Mechanism



PGS-5-5

| | Gripping Force (N) | Recommended workpiece weight(kg) | Stroke (mm) | Opening/closing time(s) | IP Class |
|---------|--------------------|----------------------------------|-------------|-------------------------|----------|
| PGS-5-5 | 3~5.5 | 0.05 | 5 | 0.03 | IP40 |

PGC Series Electric Collaborative Parallel Gripper

Plug and Play

High Protection Grade

High Load



All-in-one Design



Adjustable Parameters



Intelligent Feedback



Replaceable Fingertip



Self-locking Mechanism



PGC-50-35



PGC-140-50



PGC-300-60

| | Gripping Force (N) | Recommended workpiece weight(kg) | Stroke (mm) | Opening/closing time(s) | IP Class |
|------------|--------------------|----------------------------------|-------------|-------------------------|----------|
| PGC-50-35 | 15~50 | 1 | 37 | 0.7 | IP54 |
| PGC-140-50 | 40~140 | 3 | 50 | 0.6 | IP67 |
| PGC-300-60 | 80~300 | 6 | 60 | 0.8 | IP67 |

AG Series Electric Collaborative Parallel Gripper

Plug and Play

High Protection
Grade

High Load



All-in-one
Design



Adjustable
Parameters



Intelligent
Feedback



Replaceable
Fingertip



Self-locking
Mechanism



AG-160-95



AG-105-145



DH-3

| | Gripping Force (N) | Recommended workpiece weight(kg) | Stroke (mm) | Opening/closing time(s) | IP Class |
|------------|--------------------|----------------------------------|----------------------------|-------------------------|----------|
| AG-160-95 | 45~160 | 3 | 95 | 0.9 | IP54 |
| AG-105-145 | 35~105 | 2 | 145 | 0.9 | IP54 |
| DH-3 | 10~65 | 1.8 | 106(parallel)/122(centric) | 0.7 | IP40 |

CG Series Electric Centric Gripper

Centric
Gripping



All-in-one
Design



Adjustable
Parameters



Intelligent
Feedback



Replaceable
Fingertip



Self-locking
Mechanism



CGE-10-10



CGI-100-170



CGC-80-10

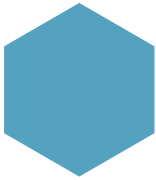
| | Gripping Force (N) | Recommended workpiece weight(kg) | Stroke (mm) | Opening/closing time(s) | IP Class |
|-------------|--------------------|----------------------------------|--|-------------------------|----------|
| CGE-10-10 | 3~10 | 0.1 | 10 (Single jaw) | 0.3 | |
| CGI-100-170 | 30~100 | 1.5 | $\phi 40 \sim \phi 170$ (Inward work piece diameter) | 1.35 | IP40 |
| CGC-80-10 | 20~80 | 1.5 | 10 (Single jaw) | 0.2 | IP67 |

PGE Series Slim-type Electric Parallel Gripper

PGE-2-12
PGE-5-26
PGE-8-14
PGE-15-10
PGE-15-26
PGE-50-26
PGE-50-40
PGE-100-26

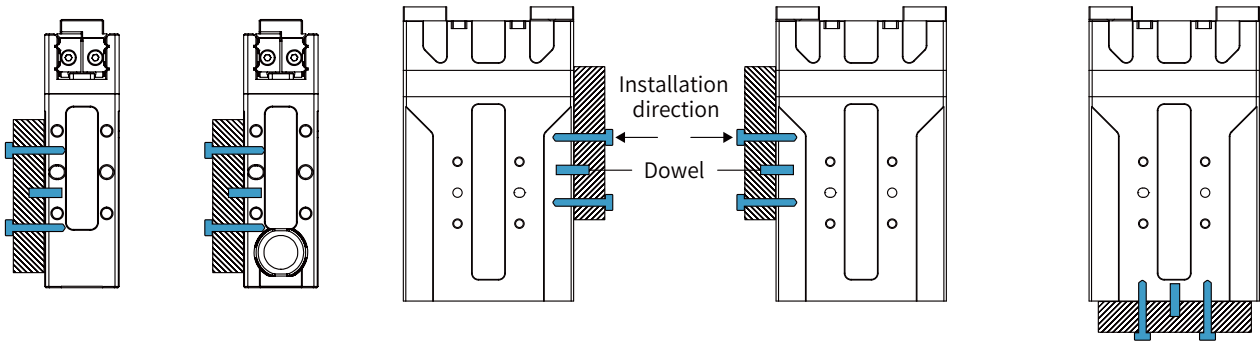


The PGE series is an industrial slim-type electric parallel gripper. With its precise force control, compact size and highly working speed, it has become a “Hot sell product” in the field of industrial electric gripper.



Installation

1. Front installation: use front screw holes for installation
2. Rear installation: use rear screw holes for installation
3. Right installation: use right screw holes for installation
4. Left installation: use left screw holes for installation
5. Bottom installation : use bottom screw holes for installation



Product Features

● Small size Flexible Installation

The thinnest size is 18 mm with compact structure, supports at least five flexible installation methods to meet the needs of clamping tasks & saves design space.

● High Working Speed

The fastest opening and closing time can reach 0.15 s / 0.15 s, which can meet the high-speed and stable clamping requirements of the production line.

● Precise Force Control

With special driver design and driving algorithm compensation, the gripping force is continuously adjustable, and the force repeat ability could reach 0.1 N.

Application

For scenarios requiring force control or flexibility, such as assembly, sorting and loading and unloading in semiconductor, 3C electronics, medical automation and other industries.



PGE-2-12

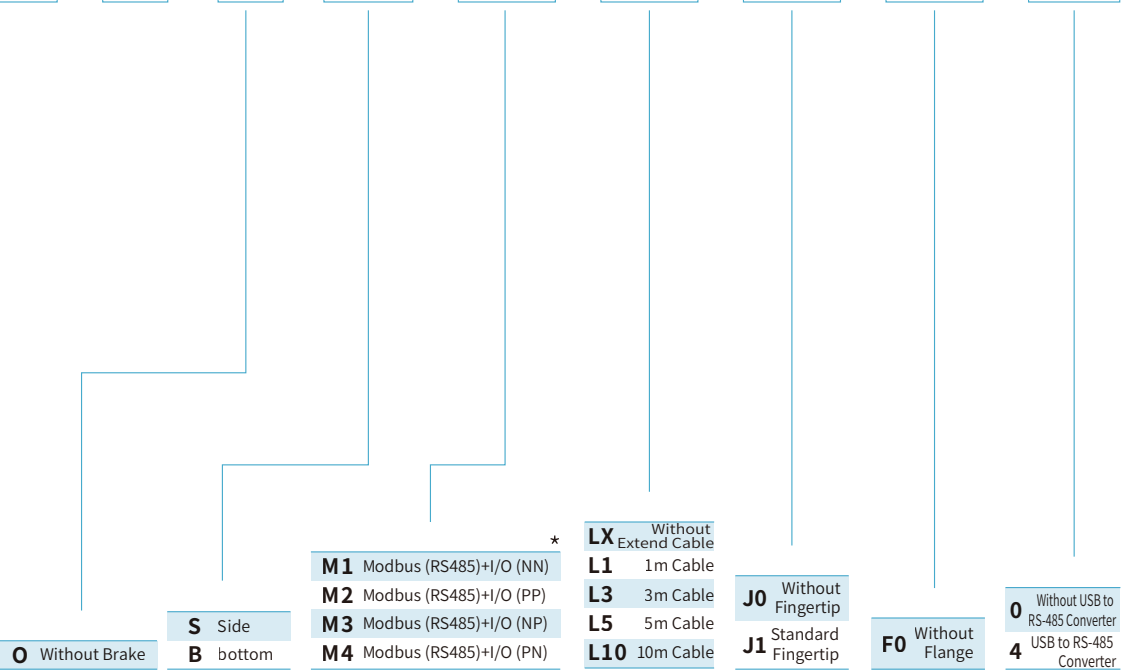
Slim-type Electric Parallel Gripper



Selection Method

| Serie | Gripping Force | Stroke | Brake | Cable Direction | Communication Protocol | Cable Selection | Fingertip Selection | Flange selection | Other |
|------------|----------------|-----------|----------|-----------------|------------------------|-----------------|---------------------|------------------|----------|
| PGE | 2 | 12 | O | S | M1 | L5 | J0 | F0 | 0 |

* Note:
 I/O(NN): NPN/NPN
 I/O(PP): PNP/PNP
 I/O(NP): NPN/PNP
 I/O(PN): PNP/NPN

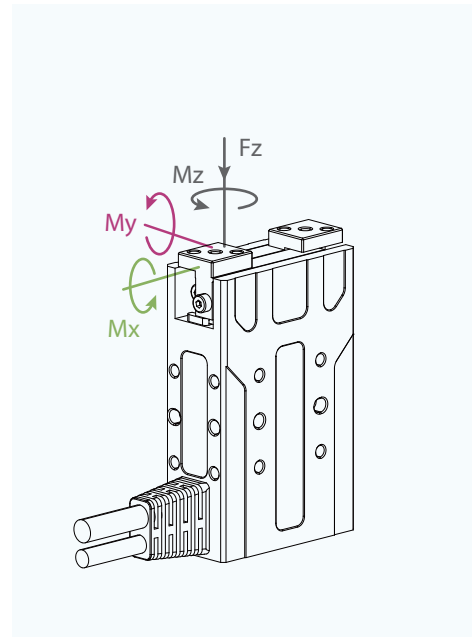


Parameters

| Product Parameter | |
|---------------------------------|---|
| Gripping force (per jaw) | 0.8~2 N |
| Stroke | 12 mm |
| Recommended workpiece weight *① | 0.05 kg |
| Opening/closing time | 0.15 s/0.15 s |
| Repeat accuracy (position) | ± 0.02 mm |
| Noise emission | < 50 dB |
| Weight | 0.15 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | Gripper Size:65 mm x 39 mm x 18 mm Controller Size:78 mm x 52.4 mm x 27.2 mm |

| Working Environment | |
|-------------------------|---|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT *② |
| Rated voltage | 24 V DC \pm 10% |
| Rated current | 0.2 A |
| Peak current | 0.5 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, 85% RH 以下 |
| Certification | CE, FCC, RoHS |

| | | | | | |
|-------------------------------------|-------------------------------------|-------------------------------------|-------------------------------------|-------------------------------------|-------------------------------------|
| <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> |
| Built-in Controller | Gripping Force Adjustable | Position Adjustable | Speed Adjustable | Drop Detection | Self-locking Mechanism |

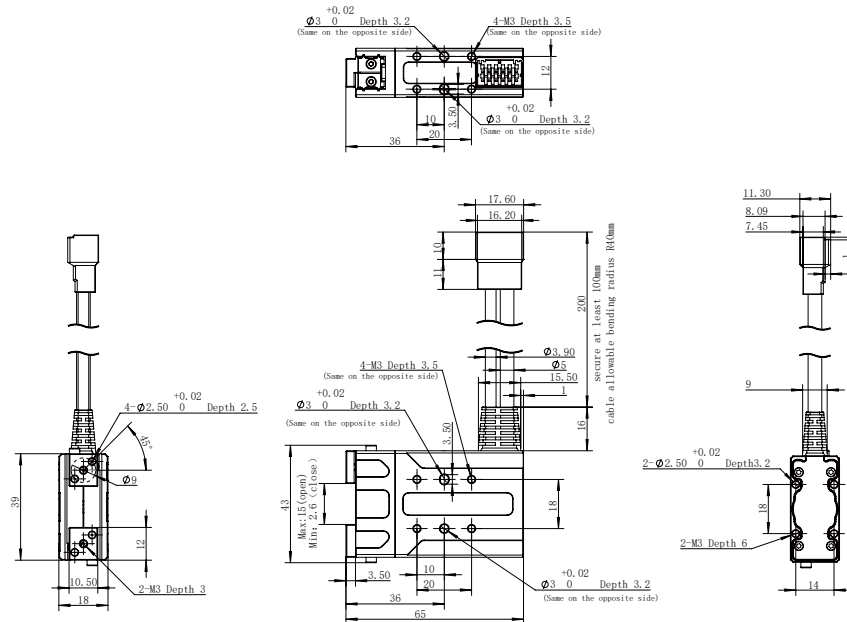


| Static Vertical Allowable Load | |
|--------------------------------|------|
| Fz | 35 N |

| Allowable Loading Moment | |
|--------------------------|----------|
| Mx | 0.2 N·m |
| My | 0.17 N·m |
| Mz | 0.2 N·m |

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

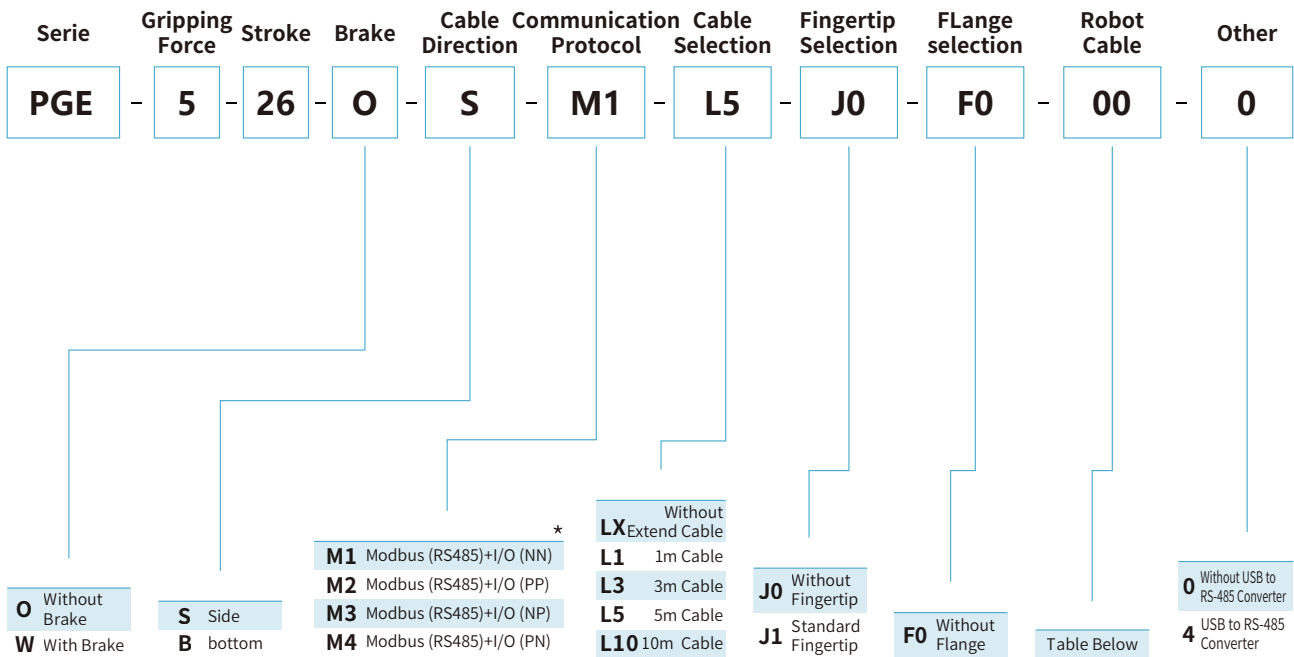


PGE-5-26

Slim-type Electric Parallel Gripper



Selection Method



* Note:

I/O(NN): NPN/NPN
I/O(PP): PNP/PNP
I/O(NP): NPN/PNP
I/O(PN): PNP/NPN

| | | | | | | | | | | | |
|-------------------------------|-----------------------------|----------------------------|------------------------|--------------------------------------|-------------------------------------|--|--|---------------------------------------|--|--------------------|--|
| 00 Without Robot Cable | 01 Elite CS UR CB | SIASUN Hanwha A UR E | DOBOT CR DOBOT Nova | 02 AUBO 03 ELEPHANT | 04 JAKA 05 TECHMAN | 06 ROKAE SR ROKAE ER 07 DOBOT MG400 | 09 Doosan A 10 Doosan M | 11 Elite EC 12 Han's | 13 Neuromeka 14 FAIRINO | 16 UF x Arm | 15 Hanwha HCR 17 ROKAE CR |
|-------------------------------|-----------------------------|----------------------------|------------------------|--------------------------------------|-------------------------------------|--|--|---------------------------------------|--|--------------------|--|

Parameters

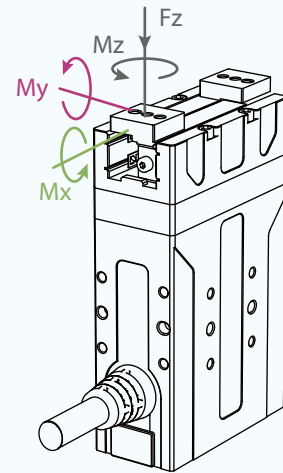
Product Parameter

| | |
|---------------------------------|--|
| Gripping force (per jaw) | 0.8~5 N |
| Stroke | 26 mm |
| Recommended workpiece weight *① | 0.1 kg |
| Opening/closing time | 0.3 s/0.3 s |
| Repeat accuracy (position) | ± 0.02 mm |
| Noise emission | < 50 dB |
| Weight | 0.4 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | 95 mm x 55 mm x 26 mm (without brake) 113.5 mm x 55 mm x 30 mm (with brake) |

Working Environment

| | |
|-------------------------|---|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT *② |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.4 A |
| Peak current | 0.7 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, 85% RH 以下 |
| Certification | CE, FCC, RoHS |

| | | | | | |
|--|--|--|---|---|---|
|  Build-in Controller |  Gripping Force Adjustable |  Position Adjustable |  Speed Adjustable |  Drop Detection |  Self-locking Mechanism |
|--|--|--|---|---|---|



Static Vertical Allowable Load

| | |
|----|------|
| Fz | 50 N |
|----|------|

Allowable Loading Moment

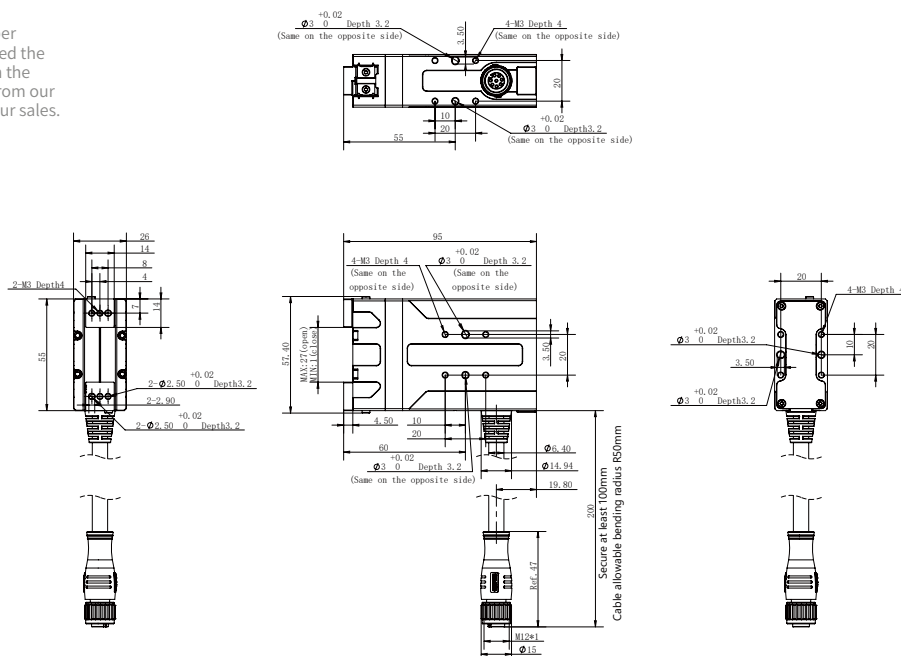
| | |
|----|----------|
| Mx | 0.3 N·m |
| My | 0.25 N·m |
| Mz | 0.3 N·m |

*① 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.

*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

This drawing is for the gripper without the brake. If you need the drawing for the gripper with the brake, please download it from our official website or contact our sales.

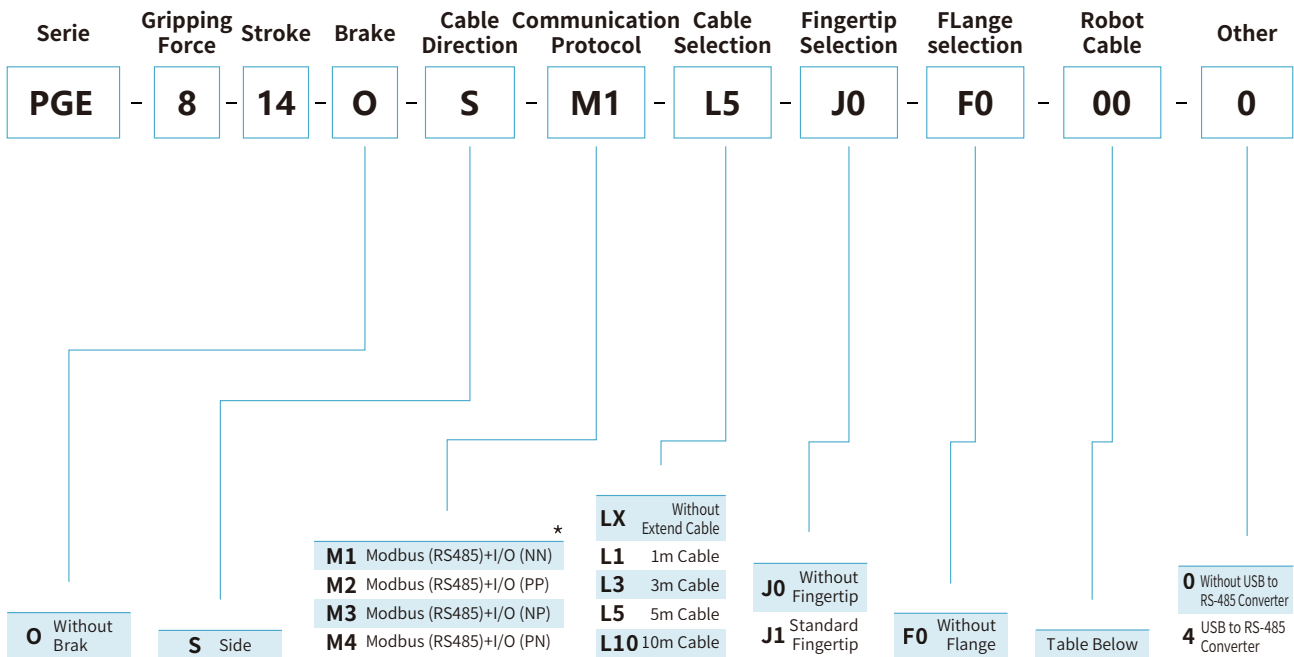


PGE-8-14

Slim-type Electric Parallel Gripper



Selection Method



* Note:

I/O(NN): NPN/NPN
 I/O(PP): PNP/PNP
 I/O(NP): NPN/PNP
 I/O(PN): PNP/NPN

| | | | | | | | | | | |
|-------------------------------|---------------------------------|------------------------|--------------------|-------------------|-----------------------------|--------------------|--------------------|---------------------|----------------------|--------------------|
| 00 Without Robot Cable | 01 SIASUN Elite CS UR CB | DOBOT CR Hanwha A UR E | 02 AUBO | 04 JAKA | 06 ROKAE SR ROKAE ER | 09 Doosan A | 11 Elite EC | 13 Neuromeka | 15 Hanwha HCR | |
| | | | 03 ELEPHANT | 05 TECHMAN | 07 DOBOT MG400 | 10 Doosan M | 12 Han's | 14 FAIRINO | 16 UF x Arm | 17 ROKAE CR |


Parameters

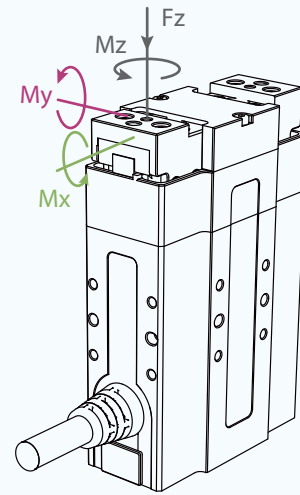
Product Parameter

| | |
|---------------------------------|---|
| Gripping force (per jaw) | 2~8 N |
| Stroke | 14 mm |
| Recommended workpiece weight *① | 0.1 kg |
| Opening/closing time | 0.3 s/0.3 s |
| Repeat accuracy (position) | ± 0.02 mm |
| Noise emission | < 50 dB |
| Weight | 0.4 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | 97 mm x 62 mm x 31 mm |

Working Environment

| | |
|-------------------------|---|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT *② |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.4 A |
| Peak current | 0.7 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | |
|--|--|--|---|---|---|
|  Build-in Controller |  Gripping Force Adjustable |  Position Adjustable |  Speed Adjustable |  Drop Detection |  Self-locking Mechanism |
|--|--|--|---|---|---|



Static Vertical Allowable Load

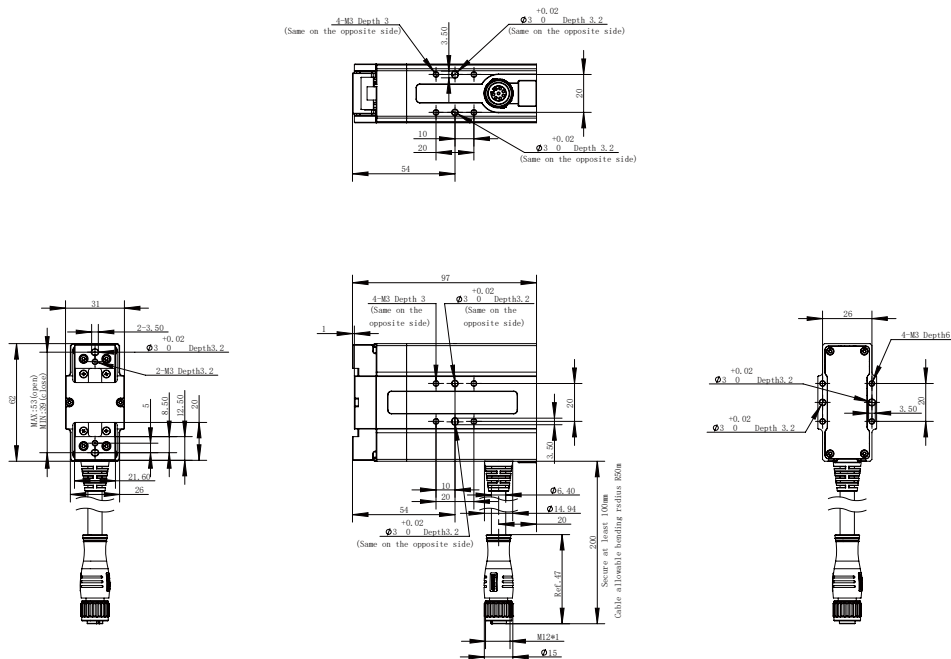
| | |
|----|------|
| Fz | 90 N |
|----|------|

Allowable Loading Moment

| | |
|----|----------|
| Mx | 0.55 N·m |
| My | 0.45 N·m |
| Mz | 0.55 N·m |

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings



PGE-15-10

Slim-type Electric Parallel Gripper



Selection Method

| Serie | Gripping Force | Stroke | Brake | Cable Direction | Communication Protocol | Cable Selection | Fingertip Selection | Flange selection | Other |
|------------|----------------|-----------|----------|-----------------|------------------------|-----------------|---------------------|------------------|----------|
| PGE | 15 | 10 | O | S | M1 | L5 | J0 | F0 | 0 |

| | | | | | | |
|-------------------------------|--|--|---|---|---------------------------------|--|
| <p>O Without Brake</p> | <p>S Side B bottom</p> | <p>M1 Modbus (RS485)+I/O (NN) M2 Modbus (RS485)+I/O (PP) M3 Modbus (RS485)+I/O (NP) M4 Modbus (RS485)+I/O (PN)</p> | <p>LX Without Extend Cable L1 1m Cable L3 3m Cable L5 5m Cable L10 10m Cable</p> | <p>J0 Without Fingertip J1 Standard Fingertip</p> | <p>F0 Without Flange</p> | <p>0 Without USB to RS-485 Converter 4 USB to RS-485 Converter</p> |
|-------------------------------|--|--|---|---|---------------------------------|--|

* Note:
I/O(NN): NPN/NPN
I/O(PP): PNP/PNP
I/O(NP): NPN/PNP
I/O(PN): PNP/NPN

Parameters

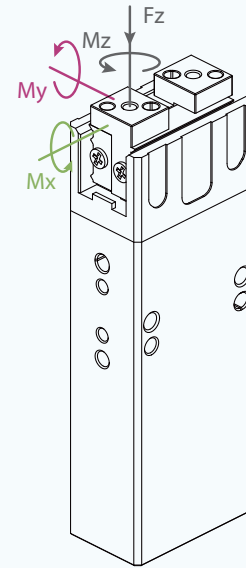
Product Parameter

| | |
|---------------------------------|---|
| Gripping force (per jaw) | 6~15 N |
| Stroke | 10 mm |
| Recommended workpiece weight *① | 0.25 kg |
| Opening/closing time | 0.3 s/0.3 s |
| Repeat accuracy (position) | ± 0.02 mm |
| Noise emission | < 50 dB |
| Weight | 0.155 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | Gripper Size: 89 mm x 30 mm x 18 mm Controller Size: 78 mm x 52.4 mm x 27.2 mm |

Working Environment

| | |
|-------------------------|---|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT *② |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.1 A |
| Peak current | 0.22 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | |
|---|---|---|--|--|--|
| <input checked="" type="checkbox"/> Build-in Controller | <input checked="" type="checkbox"/> Gripping Force Adjustable | <input checked="" type="checkbox"/> Position Adjustable | <input checked="" type="checkbox"/> Speed Adjustable | <input checked="" type="checkbox"/> Drop Detection | <input checked="" type="checkbox"/> Self-locking Mechanism |
|---|---|---|--|--|--|



Static Vertical Allowable Load

Fz 35 N

Allowable Loading Moment

Mx 0.45 N·m

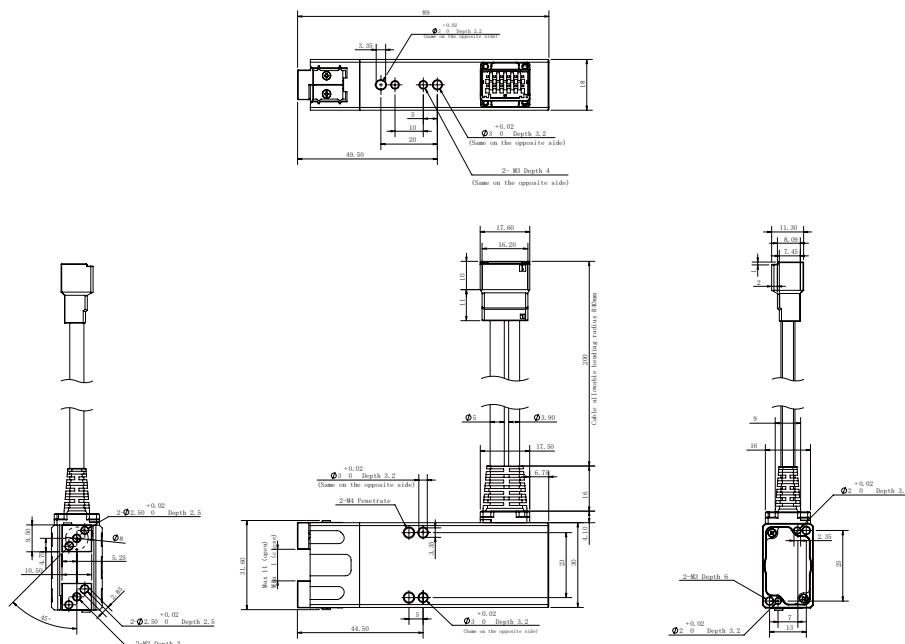
My 0.4 N·m

Mz 0.45 N·m

*① 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.

*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

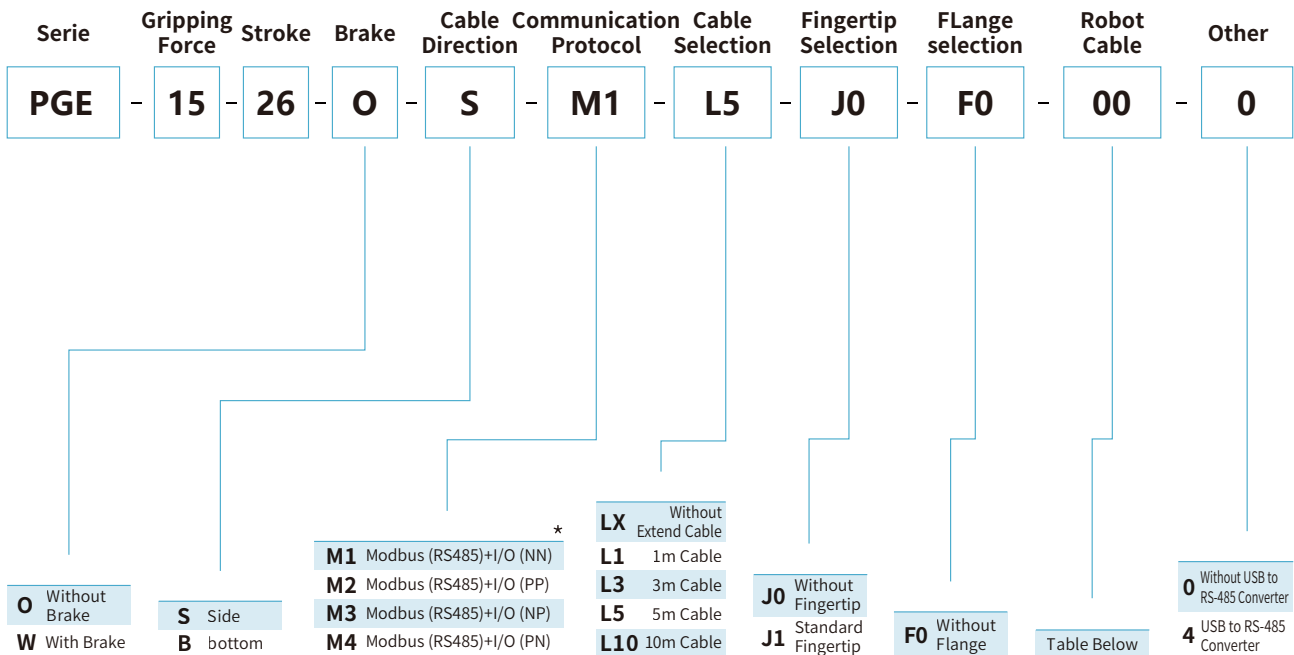


PGE-15-26

Slim-type Electric Parallel Gripper



Selection Method



* Note:

I/O(NN): NPN/NPN
I/O(PP): PNP/PNP
I/O(NP): NPN/PNP
I/O(PN): PNP/NPN

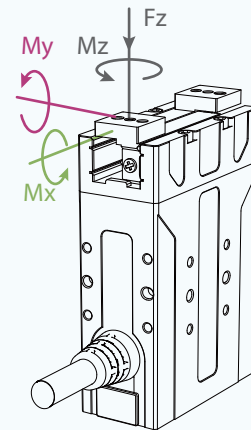
| | | | | | | | | | | | |
|-------------------------------|--------------------------|----------------------|---------------------|--------------------|-------------------|-----------------------------|--------------------|--------------------|---------------------|----------------------|--------------------|
| 00 Without Robot Cable | 01 Elite CS UR CB | SIASUN Hanwha A UR E | DOBOT CR DOBOT Nova | 02 AUBO | 04 JAKA | 06 ROKAE SR ROKAE ER | 09 Doosan A | 11 Elite EC | 13 Neuromeka | 15 Hanwha HCR | |
| | | | | 03 ELEPHANT | 05 TECHMAN | 07 DOBOT MG400 | 10 Doosan M | 12 Han's | 14 FAIRINO | 16 UF x Arm | 17 ROKAE CR |

Parameters

| Product Parameter | |
|--|--|
| Gripping force (per jaw) | 6~15 N |
| Stroke | 26 mm |
| Recommended workpiece weight ^{*①} | 0.25 kg |
| Opening/closing time | 0.5 s/0.5 s |
| Repeat accuracy (position) | ± 0.02 mm |
| Noise emission | < 50 dB |
| Weight | 0.33 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | 86.5 mm x 55 mm x 26 mm(without brake) 107.5 mm x 55 mm x 26 mm(with brake) |

| Working Environment | |
|-------------------------|--|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT ^{*②} |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.25 A |
| Peak current | 0.5 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | |
|---------------------|---------------------------|---------------------|------------------|----------------|------------------------|
| Build-in Controller | Gripping Force Adjustable | Position Adjustable | Speed Adjustable | Drop Detection | Self-locking Mechanism |
|---------------------|---------------------------|---------------------|------------------|----------------|------------------------|



Static Vertical Allowable Load

| | |
|----|------|
| Fz | 70 N |
|----|------|

Allowable Loading Moment

| | |
|----|-----------|
| Mx | 0.9 N · m |
|----|-----------|

| | |
|----|------------|
| My | 0.75 N · m |
|----|------------|

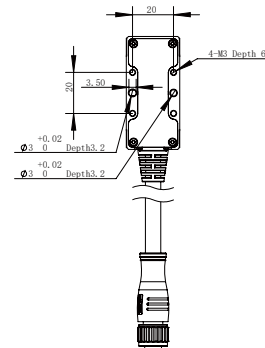
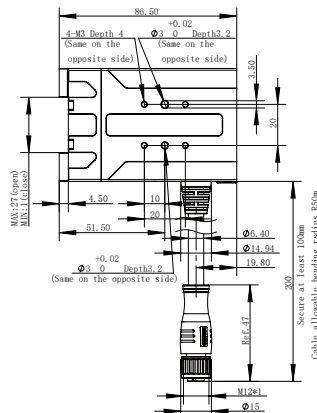
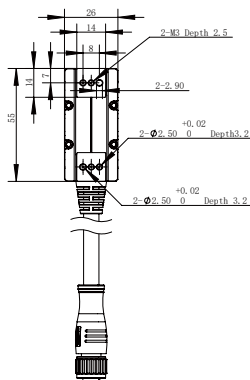
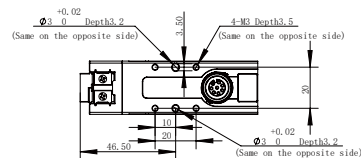
| | |
|----|-----------|
| Mz | 0.9 N · m |
|----|-----------|

^{*①} 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.

^{*②} Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

This drawing is for the gripper without the brake. If you need the drawing for the gripper with the brake, please download it from our official website or contact our sales.

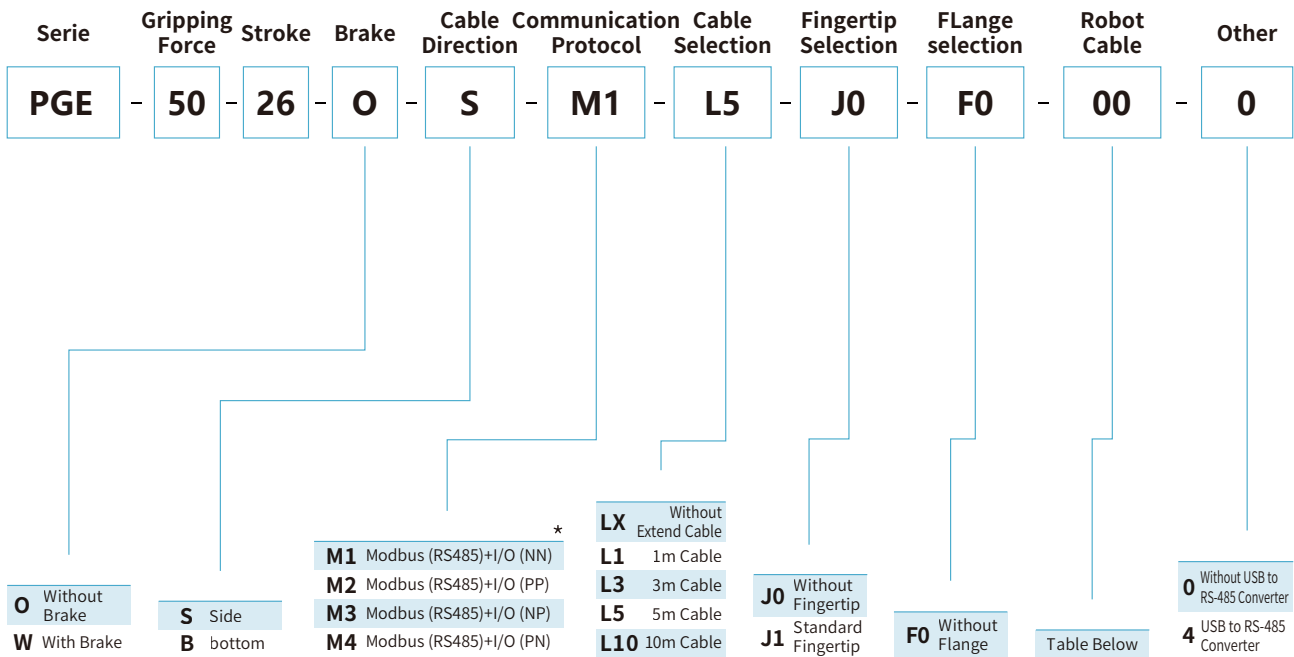


PGE-50-26

Slim-type Electric Parallel Gripper



Selection Method



* Note:







I/O(NN): NPN/NPN
I/O(PP): PNP/PNP
I/O(NP): NPN/PNP
I/O(PN): PNP/NPN

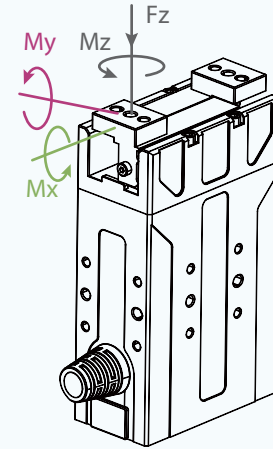
| | | | | | | | | | | |
|-------------------------------|------------------------------------|------------------------------|------------|--------------------|-------------------|--------------------------------|--------------------|--------------------|---------------------|--|
| 00 Without Robot Cable | 01 SIASUN Elite CS UR CB | DOBOT CR Hanwha A UR E | DOBOT Nova | 02 AUBO | 04 JAKA | 06 ROKAE SR ROKAE ER | 09 Doosan A | 11 Elite EC | 13 Neuromeka | 15 Hanwha HCR |
| | | | | 03 ELEPHANT | 05 TECHMAN | 07 DOBOT MG400 | 10 Doosan M | 12 Han's | 14 FAIRINO | 16 UF x Arm 17 ROKAE CR |

Parameters

| Product Parameter | |
|---------------------------------|--|
| Stroke | 26 mm |
| Gripping force (per jaw) | 15~50 N |
| Recommended workpiece weight *① | 1 kg |
| Opening/closing time | 0.45 s/0.45 s |
| Repeat accuracy (position) | ± 0.02 mm |
| Noise emission | < 50 dB |
| Weight | 0.4 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | 97 mm x 55 mm x 29 mm (without brake) 118 mm x 55 mm x 29 mm (with brake) |

| Working Environment | |
|-------------------------|---|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT *② |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.25 A |
| Peak current | 0.5 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | |
|--|--|--|---|---|---|
|  Build-in Controller |  Gripping Force Adjustable |  Position Adjustable |  Speed Adjustable |  Drop Detection |  Self-locking Mechanism |
|--|--|--|---|---|---|



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

Mx 2.5 N·m

My 2 N·m

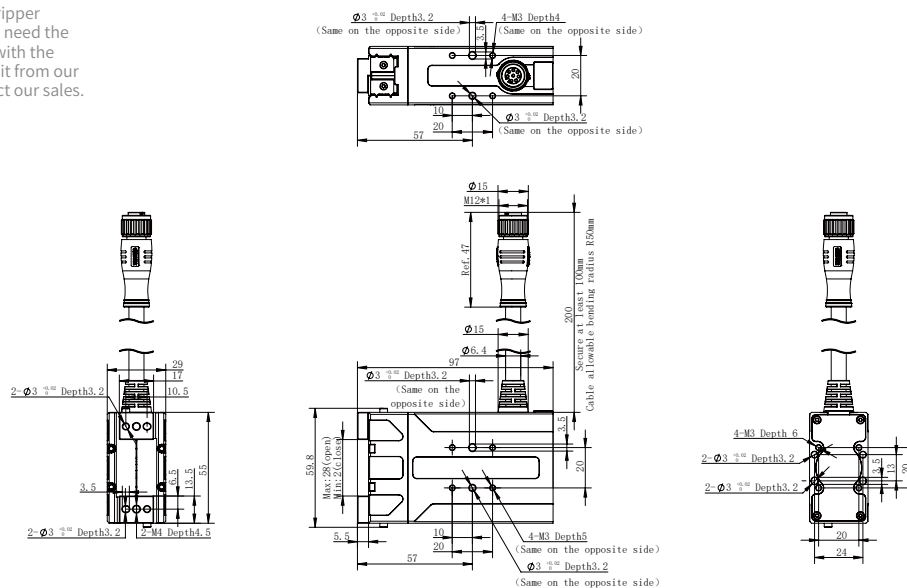
Mz 3 N·m

*① 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.

*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

This drawing is for the gripper without the brake. If you need the drawing for the gripper with the brake, please download it from our official website or contact our sales.

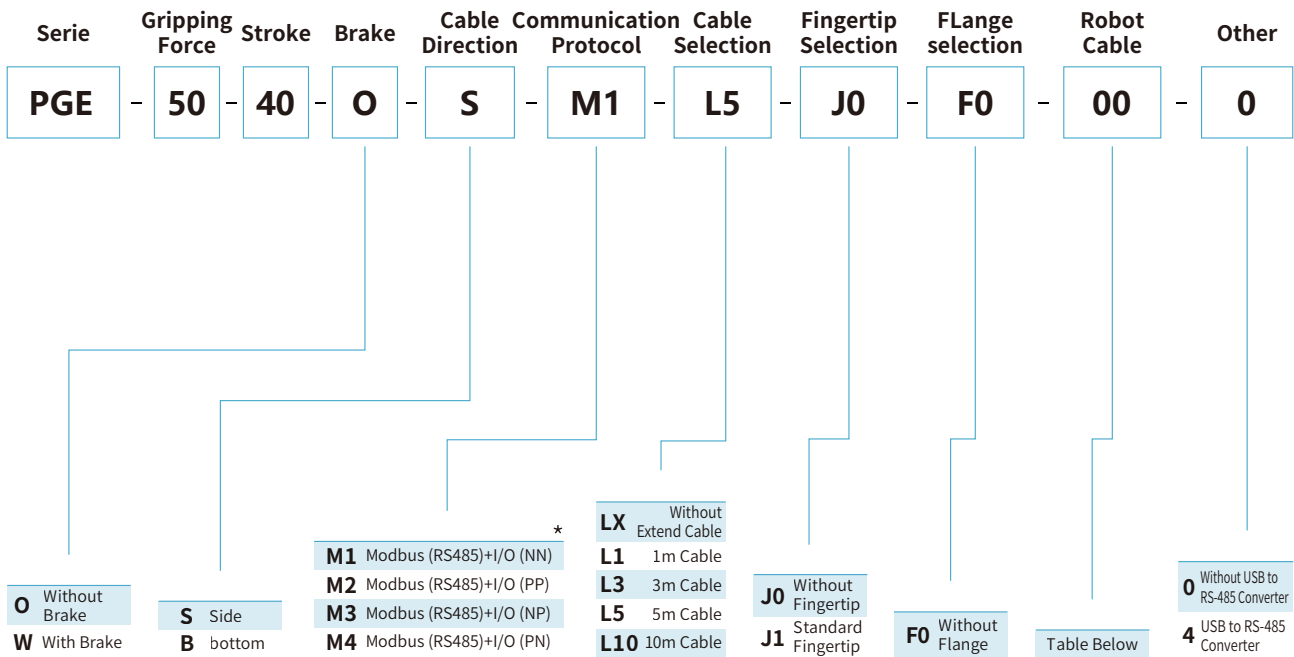


PGE-50-40

Slim-type Electric Parallel Gripper



Selection Method



* Note:







I/O(NN): NPN/NPN
I/O(PP): PNP/PNP
I/O(NP): NPN/PNP
I/O(PN): PNP/NPN

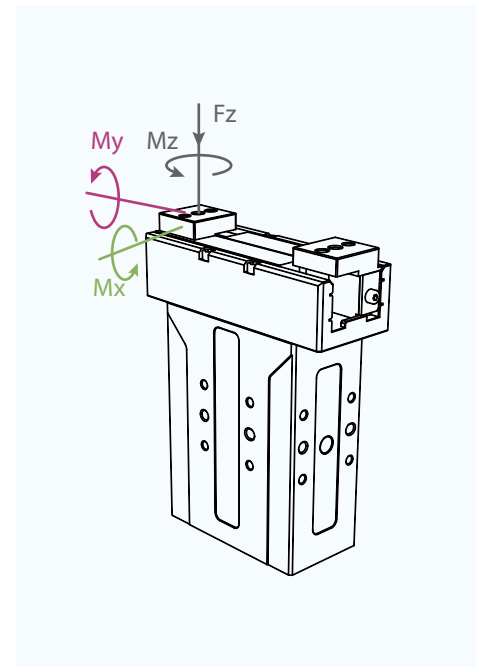
| | | | | | | | | | | | |
|-------------------------------|--------------------------|----------------------|---------------------|--------------------|-------------------|-----------------------------|--------------------|--------------------|---------------------|----------------------|--------------------|
| 00 Without Robot Cable | 01 Elite CS UR CB | SIASUN Hanwha A UR E | DOBOT CR DOBOT Nova | 02 AUBO | 04 JAKA | 06 ROKAE SR ROKAE ER | 09 Doosan A | 11 Elite EC | 13 Neuromeka | 15 Hanwha HCR | |
| | | | | 03 ELEPHANT | 05 TECHMAN | 07 DOBOT MG400 | 10 Doosan M | 12 Han's | 14 FAIRINO | 16 UF x Arm | 17 ROKAE CR |

Parameters

| Product Parameter | |
|--|--|
| Stroke | 40 mm |
| Gripping force (per jaw) | 15~50 N |
| Recommended workpiece weight ^{*①} | 1 kg |
| Opening/closing time | 0.6 s/0.6 s |
| Repeat accuracy (position) | ± 0.02 mm |
| Noise emission | < 50 dB |
| Weight | 0.51 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | 97 mm x 78 mm x 29 mm (without brake) 118 mm x 78 mm x 29 mm (with brake) |

| Working Environment | |
|-------------------------|--|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT ^{*②} |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.25 A |
| Peak current | 0.5 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | |
|--|--|--|---|---|---|
|  Build-in Controller |  Gripping Force Adjustable |  Position Adjustable |  Speed Adjustable |  Drop Detection |  Self-locking Mechanism |
|--|--|--|---|---|---|



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

Mx 4.5 N·m

My 5 N·m

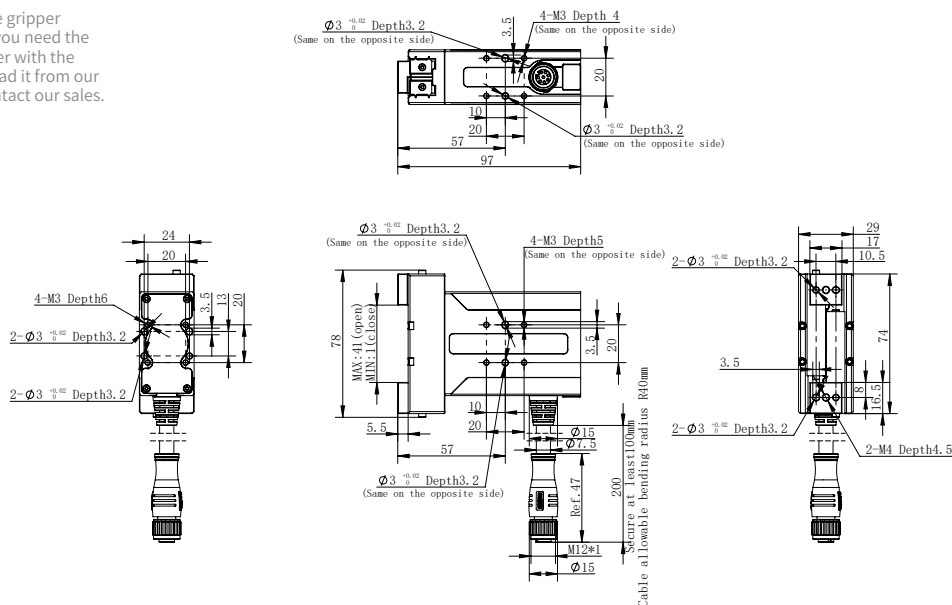
Mz 7 N·m

*① 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.

*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

This drawing is for the gripper without the brake. If you need the drawing for the gripper with the brake, please download it from our official website or contact our sales.

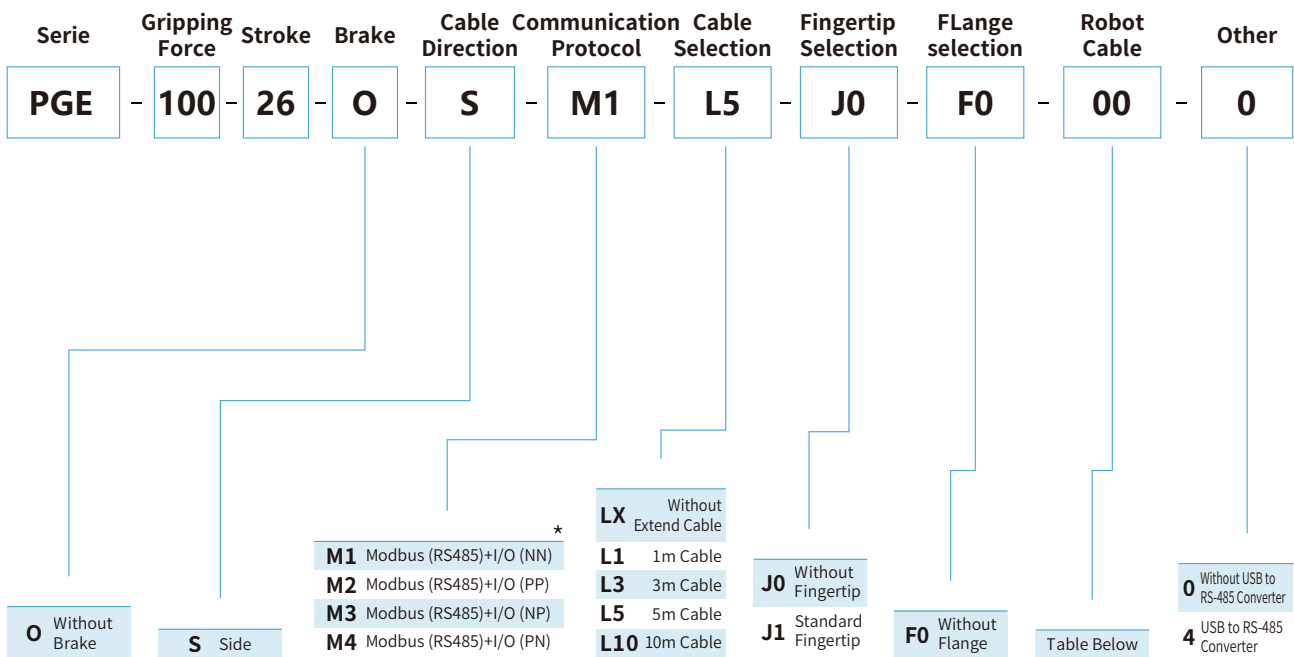


PGE-100-26

Slim-type Electric Parallel Gripper



Selection Method



* Note:

I/O(NN): NPN/NPN
 I/O(PP): PNP/PNP
 I/O(NP): NPN/PNP
 I/O(PN): PNP/NPN

| | | | | | | | | | | | |
|-------------------------------|--------------------------|----------------------|---------------------|--------------------|-------------------|-----------------------------|--------------------|--------------------|---------------------|----------------------|--------------------|
| 00 Without Robot Cable | 01 Elite CS UR CB | SIASUN Hanwha A UR E | DOBOT CR DOBOT Nova | 02 AUBO | 04 JAKA | 06 ROKAE SR ROKAE ER | 09 Doosan A | 11 Elite EC | 13 Neuromeka | 15 Hanwha HCR | |
| | | | | 03 ELEPHANT | 05 TECHMAN | 07 DOBOT MG400 | 10 Doosan M | 12 Han's | 14 FAIRINO | 16 UF x Arm | 17 ROKAE CR |

Parameters

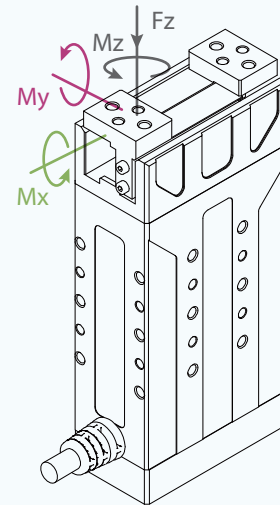
Product Parameter

| | |
|---|---|
| Gripping force (per jaw) | 30~100 N |
| Stroke | 26 mm |
| Recommended workpiece weight * ^① | 2 kg |
| Opening/closing time | 0.5 s/0.5 s |
| Repeat accuracy (position) | ± 0.02 mm |
| Noise emission | < 50 dB |
| Weight | 0.55 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| 尺寸 | 125 mm x 57 mm x 30 mm |

Working Environment

| | |
|-------------------------|---|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT * ^② |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.3 A |
| Peak current | 1.2 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | |
|---|---|---|--|--|--|
| <input checked="" type="checkbox"/> Build-in Controller | <input checked="" type="checkbox"/> Gripping Force Adjustable | <input checked="" type="checkbox"/> Position Adjustable | <input checked="" type="checkbox"/> Speed Adjustable | <input checked="" type="checkbox"/> Drop Detection | <input checked="" type="checkbox"/> Self-locking Mechanism |
|---|---|---|--|--|--|



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

Mx 2.5 N·m

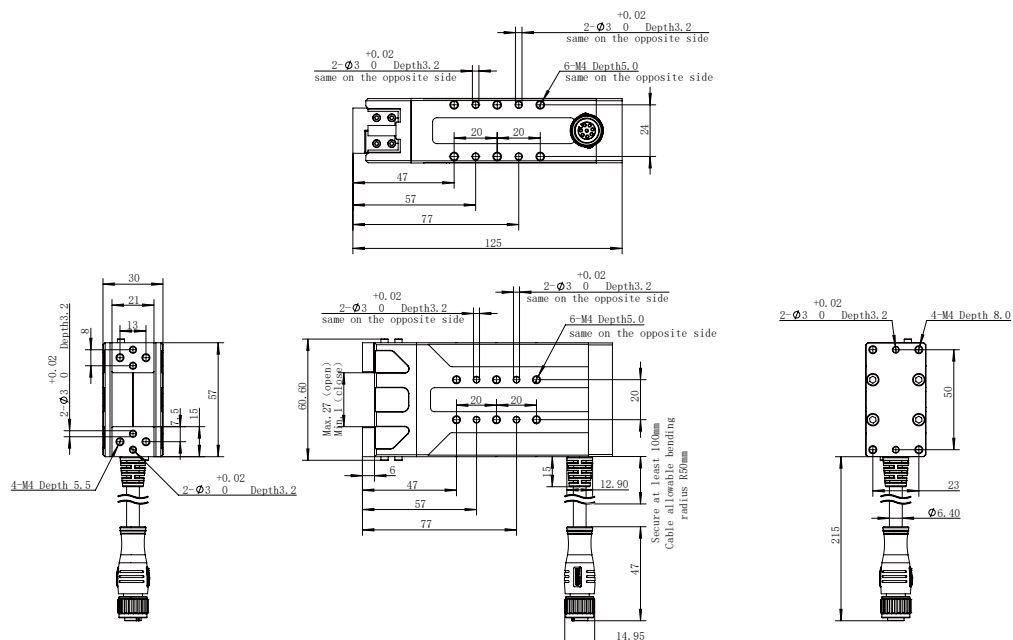
My 3 N·m

Mz 4 N·m

*^① 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.

*^② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

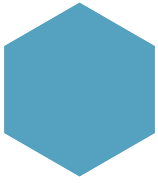


PGSE Series Slim-type Electric Parallel Gripper

PGSE-15-7

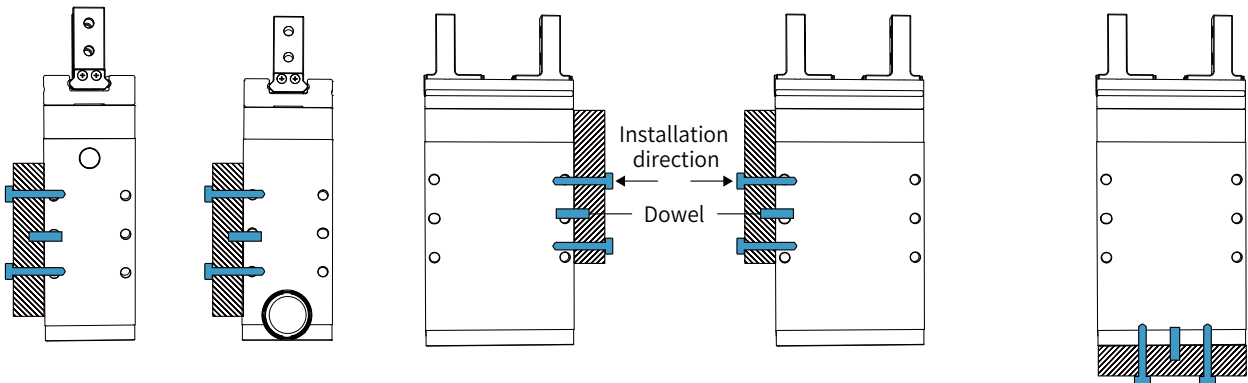


The PGSE Industrial Parallel Gripper is a miniature electric gripper specifically designed to meet the demand for quick grasping in narrow and compact installation spaces in industrial settings.



Installation

1. Front installation: use front screw holes for installation
2. Rear installation: use rear screw holes for installation
3. Right installation: use right screw holes for installation
4. Left installation: use left screw holes for installation
5. Bottom installation : use bottom screw holes for installation



Product Features

● Ultimate Slimness

The PGSE gripper features a compact and intricate design, with dimensions of only 85.6 x 38 x 23.2 mm (length x width x height), making it extremely slim and compact.

● High-Speed Response

The PGSE gripper offers rapid opening and closing times, with a minimum response time of as fast as 0.15 seconds for both opening and closing actions. This allows for quick grasping cycles, meeting the high-speed gripping requirements of production lines.

● Flexible Installation

The gripper body of the PGSE model provides multiple mounting options, allowing for versatile installation in compact spaces. Coupled with its compact size, it facilitates easy installation in tight spaces.

Application

The PGSE gripper is suitable for compact production environments, such as the semiconductor and 3C electronics industries, where it can be utilized for gripping, sorting, loading, and unloading of small-sized components.

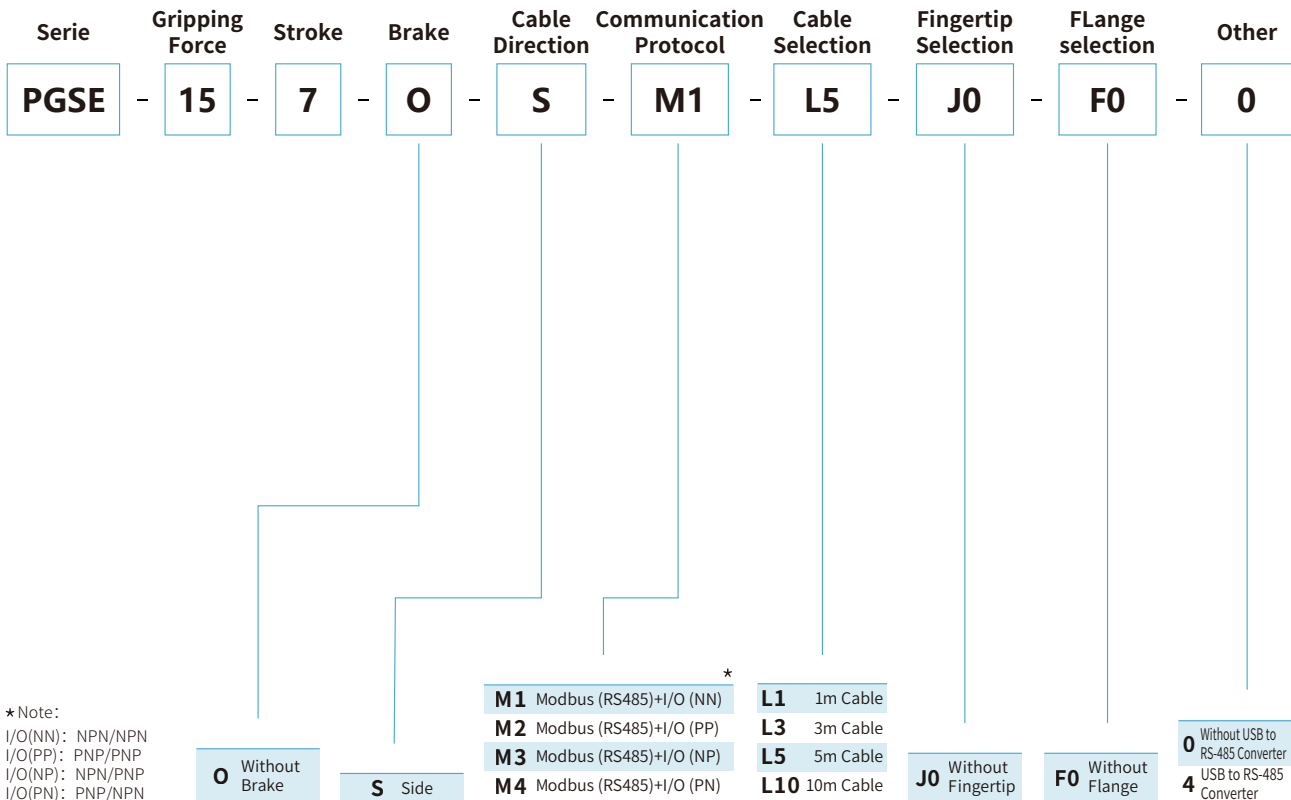


PGSE-15-7

Slim-type Electric Parallel Gripper



Selection Method



Parameters

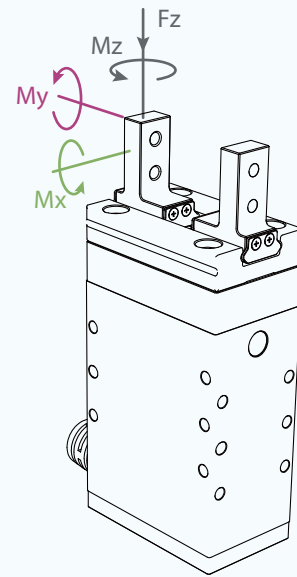
Product Parameter

| | |
|---------------------------------|---|
| Gripping force (per jaw) | 6~15 N |
| Stroke | 7 mm |
| Recommended workpiece weight *① | 0.25 kg |
| Opening/closing time | 0.15 s/0.15 s |
| Noise emission | < 50 dB |
| Weight | 0.15 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | 85.6 mm x 38 mm x 23.2 mm |

Working Environment

| | |
|-------------------------|-----------------------------------|
| Communication interface | Modbus RTU (RS485)、Digital I/O *② |
| Rated voltage | 24 V DC \pm 10% |
| Rated current | 0.15 A |
| Peak current | 0.8 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | |
|---|---|---|--|--|--|
| <input checked="" type="checkbox"/> Build-in Controller | <input checked="" type="checkbox"/> Gripping Force Adjustable | <input checked="" type="checkbox"/> Position Adjustable | <input checked="" type="checkbox"/> Speed Adjustable | <input checked="" type="checkbox"/> Drop Detection | <input checked="" type="checkbox"/> Self-locking Mechanism |
|---|---|---|--|--|--|



Static Vertical Allowable Load

Fz 70 N

Allowable Loading Moment

Mx 0.9 N·m

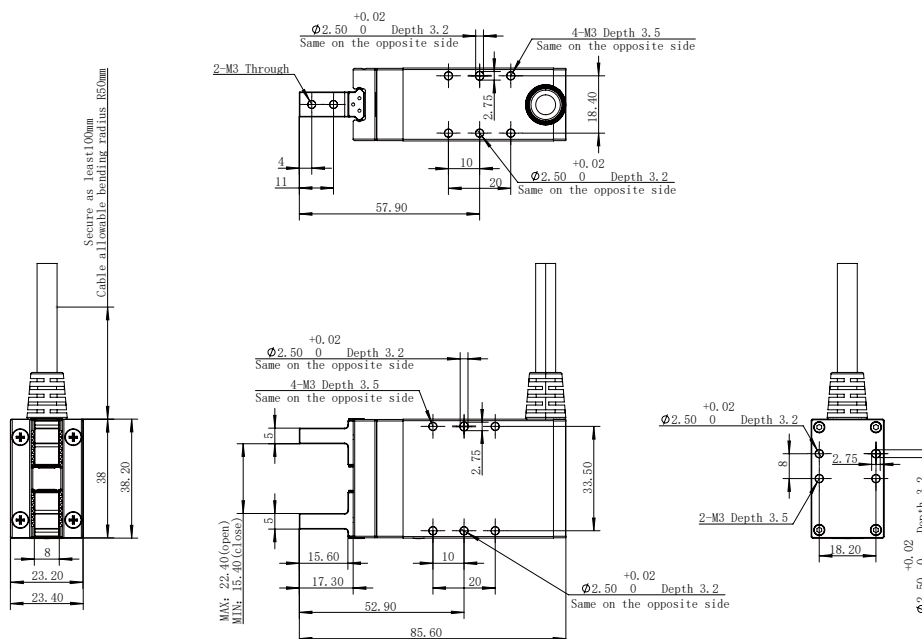
My 0.75 N·m

Mz 0.9 N·m

*① 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.

*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings



RGI Series Electric Rotary Gripper

RGI (Standard)

RGI-100-14

RGI-100-22

RGI-100-30

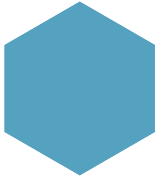
RGIC (Compact)

RGIC-35-12

RGIC-100-35

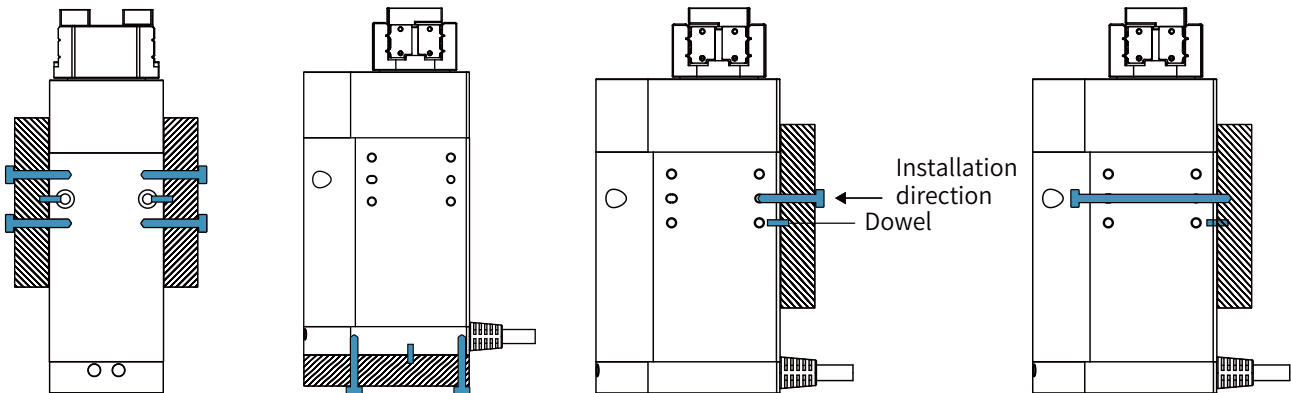


RGI series is the first fully self-developed infinite rotating gripper with a compact and precise structure on the market. It is widely applied in medical automation industry to grip and rotate the test tubes as well as other industries like electronics and New energy industry.



Installation

1. Side installation: use side screw holes for installation
2. Bottom installation : use bottom screw holes for installation
3. Rear installation: use rear screw holes for installation
4. Front installation: Install with front screw holes



Product Feature

● Gripping & Infinite Rotation

The unique structural design in the industry can realize the simultaneous gripping and infinite rotation on one electric gripper, and solve the winding problem in non-standard design and rotation.

● Compact Double Servo System

Dual servo systems are creatively integrated in a thin machine body, which is compact in design and can be adapted to many industrial scenes.

● High Gripping Force and Torque

The maximum single-sided gripping force is 100N, and the maximum torque is $1.5N \cdot m$. Though precise force control and position control, the RGI gripper can more stably complete the grasping and rotating tasks.

Application

Medical automation reagents, blood samples, nucleic acids and other sample processing scenarios such as opening and closing covers, scanning code detection, etc.; RGI-100 series comes standard with fingertips and can be adapted to 10 mix 1 and 20 mix 1 size tubes to meet the needs of large-scale nucleic acid sampling.



RGI-100

Electric Rotary Gripper



Selection Method

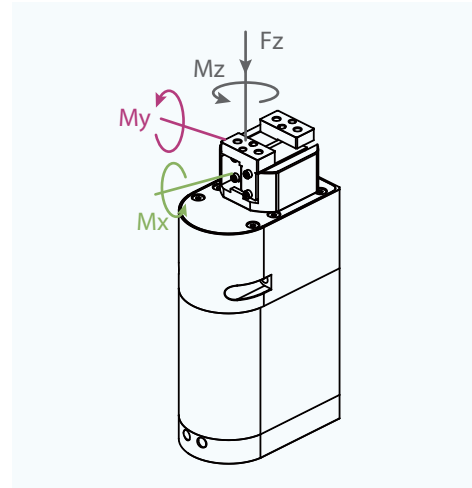
| Serie | Gripping Force | Stroke | Brake | Cable Direction | Communication Protocol | Cable Selection | Fingertip Selection | FLange selection | Other |
|------------|----------------|----------------|------------------------|----------------------------------|--|--|---|--------------------------|--|
| RGI | 100 | 14 | O | S | M1 | L5 | J0 | F0 | 0 |
| | | 14 22 30 | | | | | | | |
| | | | O Without Brake | S Side B bottom | M1 Modbus (RS485)+I/O (NN) M2 Modbus (RS485)+I/O (PP) M3 Modbus (RS485)+I/O (NP) M4 Modbus (RS485)+I/O (PN) | LX Without Extend Cable L1 1m Cable L3 3m Cable L5 5m Cable L10 10m Cable | J0 Without Fingertip J1 Standard Fingertip | F0 Without Flange | 0 Without USB to RS-485 Converter 4 USB to RS-485 Converter |

* Note:
I/O(NN): NPN/NPN
I/O(PP): PNP/PNP
I/O(NP): NPN/PNP
I/O(PN): PNP/NPN

RGI-100-14 Parameters

| Product Parameter | |
|--|--|
| Stroke | 14 mm |
| Gripping force (per jaw) | 30~100 N |
| Rated torque | 0.5 N·m |
| Peak torque | 1.5 N·m |
| Rotary range | Infinite Rotating |
| Recommended workpiece weight* ^① | 1.5 kg |
| Max. rotation speed | 2160 °/s |
| Repeat accuracy (swiveling) | ± 0.05 ° |
| Repeat accuracy (position) | ± 0.02 mm |
| Opening/closing time | 0.6 s/0.6 s |
| Weight | 1.28 kg |
| Size | 158 x 75.5 x 47 mm Rotary Diameter: 47.1 mm |

| Working Environment | |
|-------------------------|--|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, CAN2.0A, PROFINET, EtherCAT** |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 1.0 A |
| Peak current | 4.0 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

Mx 2.5 N·m

My 3 N·m

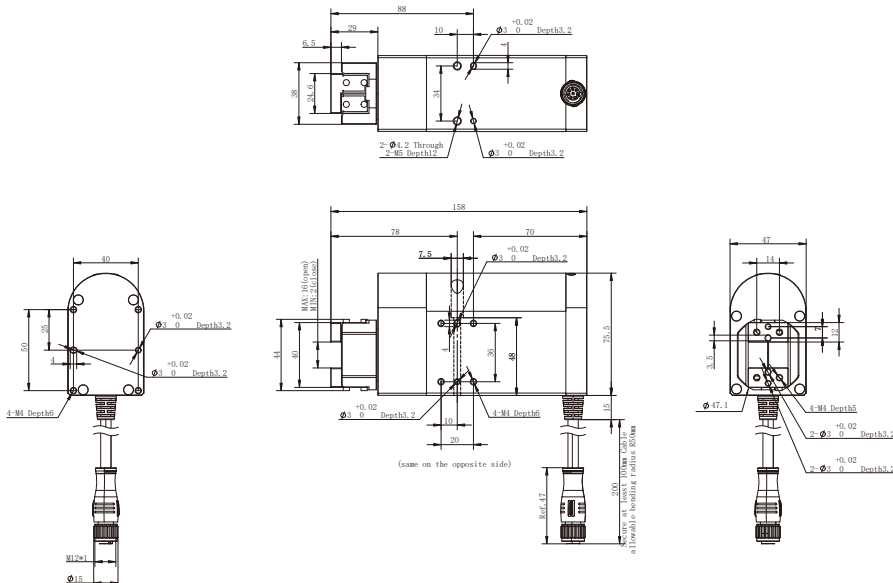
Mz 4 N·m

| | | | |
|-------------------------------------|-------------------------------------|-------------------------------------|-------------------------------------|
| <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> |
| Build-in Controller | Gripping Force Adjustable | Position Adjustable | Speed Adjustable |
| <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> | |
| Drop Detection | Rotary Adjustable | Self-locking Mechanism | |

*① 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.

**② Use optional communication, need external communication conversion box, please consult the sales staff for details.

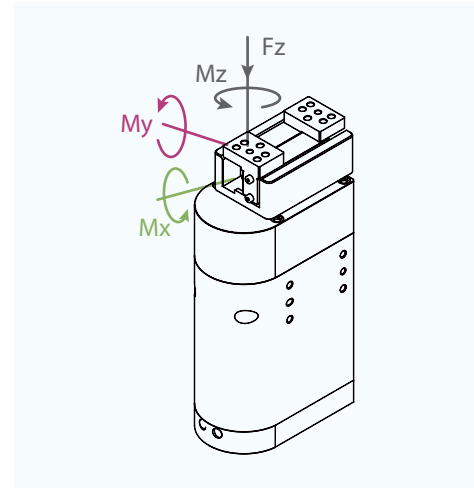
Technical Drawings



RGI-100-22 Parameters

| Product Parameter | |
|--|--|
| Stroke | 22 mm |
| Gripping force (per jaw) | 30~100 N |
| Rated torque | 0.5 N·m |
| Peak torque | 1.5 N·m |
| Rotary range | Infinite Rotating |
| Recommended workpiece weight* ^① | 1.5 kg |
| Max. rotation speed | 2160 °/s |
| Repeat accuracy (swiveling) | ± 0.05 ° |
| Repeat accuracy (position) | ± 0.02 mm |
| Opening/closing time | 0.65 s/0.65 s |
| Weight | 1.28 kg |
| Size | 158 x 75.5 x 47 mm Rotaty Diameter: 67.1 mm |

| Working Environment | |
|-------------------------|--|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, CAN2.0A, PROFINET, EtherCAT** |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 1.0 A |
| Peak current | 4.0 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |



Static Vertical Allowable Load

Fz 200 N

Allowable Loading Moment

Mx 3.5 N·m

My 4 N·m

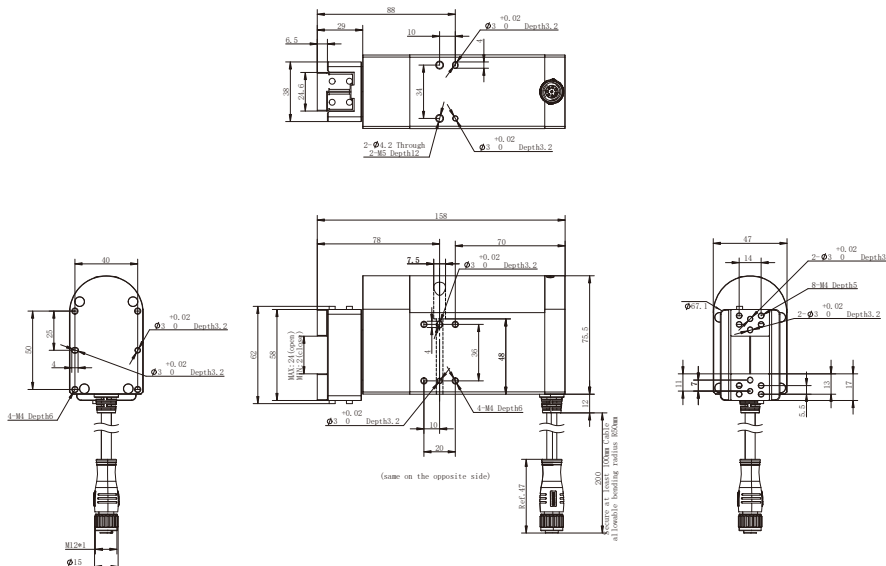
Mz 5.5 N·m

| | | | |
|-------------------------------------|-------------------------------------|-------------------------------------|-------------------------------------|
| <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> |
| Build-in Controller | Gripping Force Adjustable | Position Adjustable | Speed Adjustable |
| <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> | <input checked="" type="checkbox"/> | |
| Drop Detection | Rotary Adjustable | Self-locking Mechanism | |

*^① 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.

*^② Use optional communication, need external communication conversion box, please consult the sales staff for details.

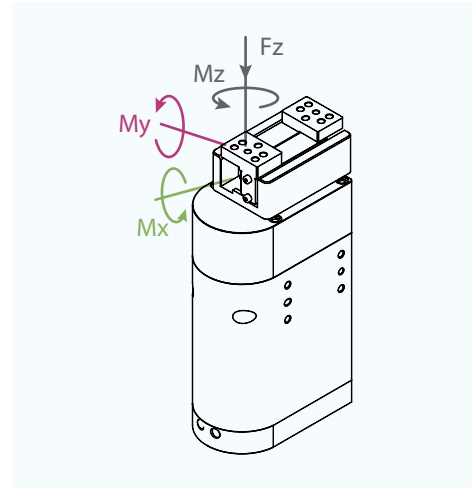
Technical Drawings



RGI-100-30 Parameters

| Product Parameter | |
|--|--|
| Stroke | 30 mm |
| Gripping force (per jaw) | 30~100 N |
| Rated torque | 0.5 N·m |
| Peak torque | 1.5 N·m |
| Rotary range | Infinite Rotating |
| Recommended workpiece weight* ^① | 1.5 kg |
| Max. rotation speed | 2160 °/s |
| Repeat accuracy (swiveling) | ± 0.05 ° |
| Repeat accuracy (position) | ± 0.02 mm |
| Opening/closing time | 0.7 s/0.7 s |
| Weight | 1.28 kg |
| Size | 158 x 75.5 x 47 mm Rotary Diameter: 84.8 mm |

| Working Environment | |
|-------------------------|--|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, CAN2.0A, PROFINET, EtherCAT** |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 1.0 A |
| Peak current | 4.0 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |



Static Vertical Allowable Load

Fz 250 N

Allowable Loading Moment

Mx 4.5 N·m

My 5 N·m

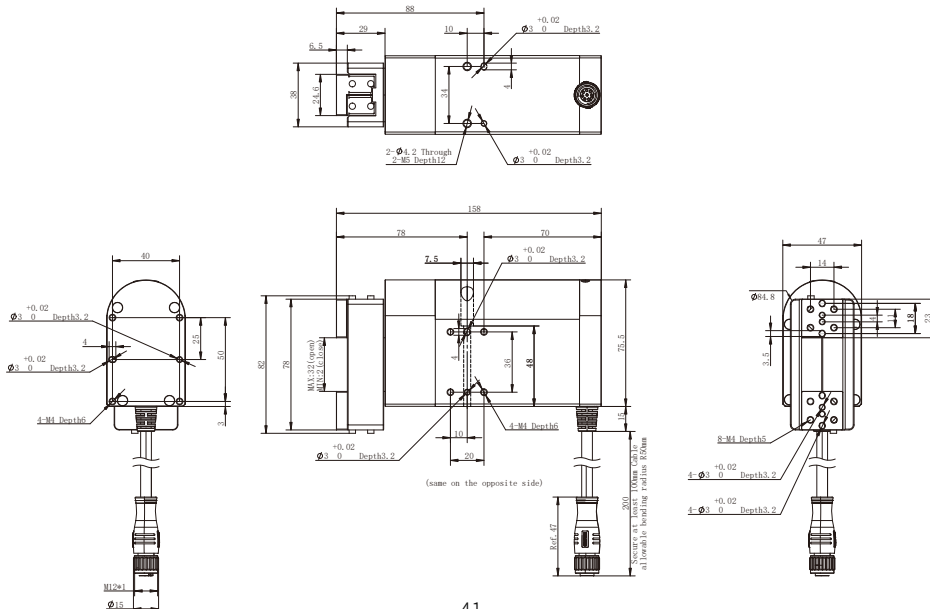
Mz 7 N·m

| | | | |
|---|---|--|--|
| <input checked="" type="checkbox"/> Build-in Controller | <input checked="" type="checkbox"/> Gripping Force Adjustable | <input checked="" type="checkbox"/> Position Adjustable | <input checked="" type="checkbox"/> Speed Adjustable |
| <input checked="" type="checkbox"/> Drop Detection | <input checked="" type="checkbox"/> Rotary Adjustable | <input checked="" type="checkbox"/> Self-locking Mechanism | |

*^① 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.

*^② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings



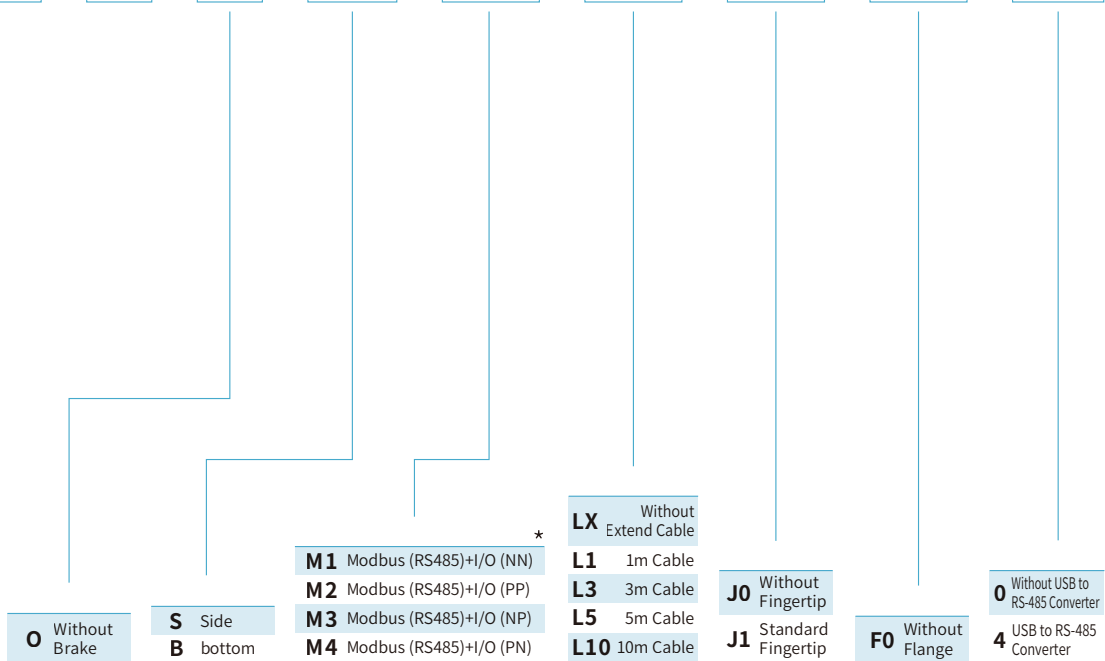
RGIC-35-12

Electric Rotary Gripper



Selection Method

| Serie | Gripping Force | Stroke | Brake | Cable Direction | Communication Protocol | Cable Selection | Fingertip Selection | FLange selection | Other |
|-------------|----------------|-----------|----------|-----------------|------------------------|-----------------|---------------------|------------------|----------|
| RGIC | 35 | 12 | O | S | M1 | L5 | J0 | F0 | 0 |



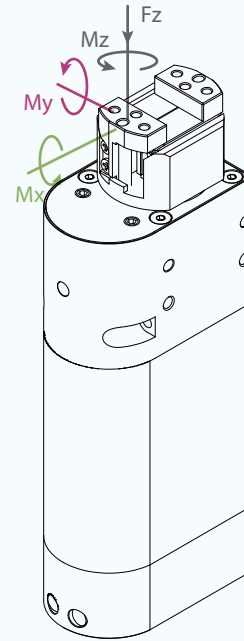
*Note:
I/O(NN): NPN/NPN
I/O(PP): PNP/PNP
I/O(NP): NPN/PNP
I/O(PN): PNP/NPN

Parameters

| Product Parameter | |
|---------------------------------|---|
| Gripping force (per jaw) | 13~35 N |
| Stroke | 12 mm |
| Rated torque | 0.2 N·m |
| Peak torque | 0.5 N·m |
| Rotary range | Infinite Rotating |
| Recommended workpiece weight *① | 0.5 kg |
| Max. rotation speed | 2160 °/s |
| Repeat accuracy (swiveling) | ± 0.05 ° |
| Repeat accuracy (position) | ± 0.02 mm |
| Opening/closing time | 0.6 s/0.6 s |
| Weight | 0.64 kg |
| Size | 150 mm x 53 mm x 34 mm Rotary Diameter: 33mm |

| Working Environment | |
|-------------------------|---|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, CAN2.0A, PROFINET, EtherCAT *② |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 1.7 A |
| Peak current | 2.5 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | | |
|---|---|---|--|--|---|--|
| <input checked="" type="checkbox"/> Build-in Controller | <input checked="" type="checkbox"/> Gripping Force Adjustable | <input checked="" type="checkbox"/> Position Adjustable | <input checked="" type="checkbox"/> Speed Adjustable | <input checked="" type="checkbox"/> Drop Detection | <input checked="" type="checkbox"/> Rotary Adjustable | <input checked="" type="checkbox"/> Self-locking Mechanism |
|---|---|---|--|--|---|--|



Static Vertical Allowable Load

Fz 100 N

Allowable Loading Moment

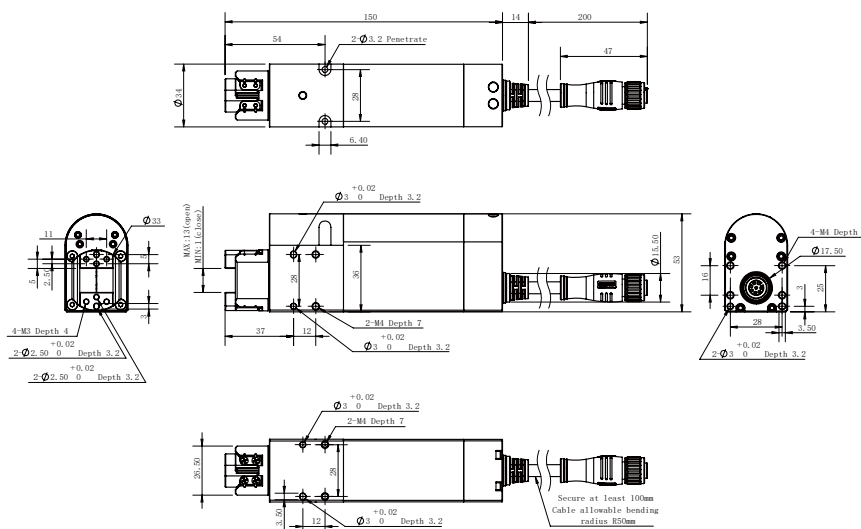
Mx 1.5 N·m

My 1.1 N·m

Mz 2.1 N·m

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

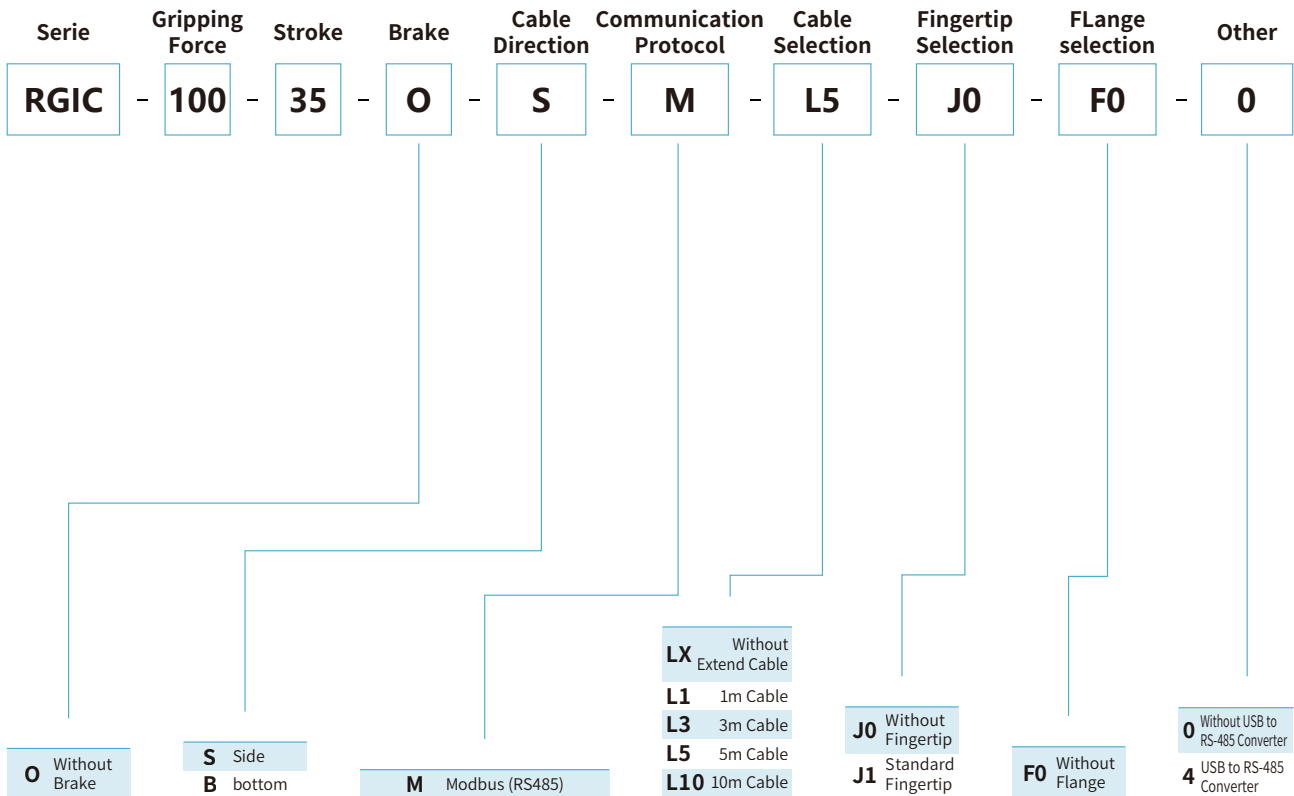


RGIC-100-35

Electric Rotary Gripper



Selection Method

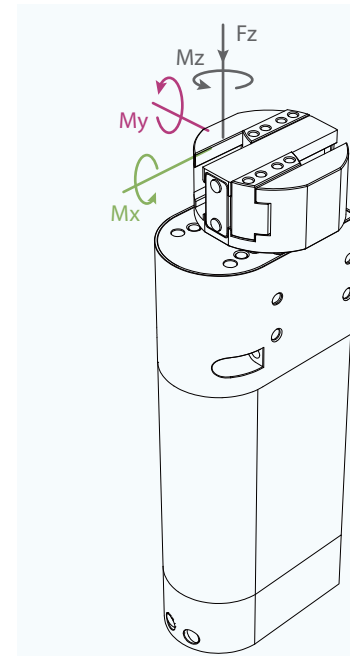


Parameters

| Product Parameter | |
|--|--|
| Gripping force (per jaw) | 40~100 N |
| Stroke | 35 mm |
| Rated torque | 0.35 N·m |
| Peak torque | 1.5 N·m |
| Rotary range | Infinite Rotating |
| Recommended workpiece weight ^{*①} | 1 kg |
| Max. rotation speed | 1400 °/s |
| Repeat accuracy (position) | ± 0.02 mm |
| Opening/closing time | 0.9 s/0.9 s |
| Weight | 0.65 kg |
| Size | 159 mm x 53 mm x 34 mm Rotary Diameter: 41 mm |

| Working Environment | |
|-------------------------|--|
| Communication interface | Standard: Modbus RTU (RS485) Optinal: TCP/IP, CAN2.0A, PROFINET, EtherCAT ^{*②} |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 2.0 A |
| Peak current | 5.0 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | | |
|---|---|---|--|--|---|--|
| <input checked="" type="checkbox"/> Build-in Controller | <input checked="" type="checkbox"/> Gripping Force Adjustable | <input checked="" type="checkbox"/> Position Adjustable | <input checked="" type="checkbox"/> Speed Adjustable | <input checked="" type="checkbox"/> Drop Detection | <input checked="" type="checkbox"/> Rotary Adjustable | <input checked="" type="checkbox"/> Self-locking Mechanism |
|---|---|---|--|--|---|--|



Static Vertical Allowable Load

Fz 100 N

Allowable Loading Moment

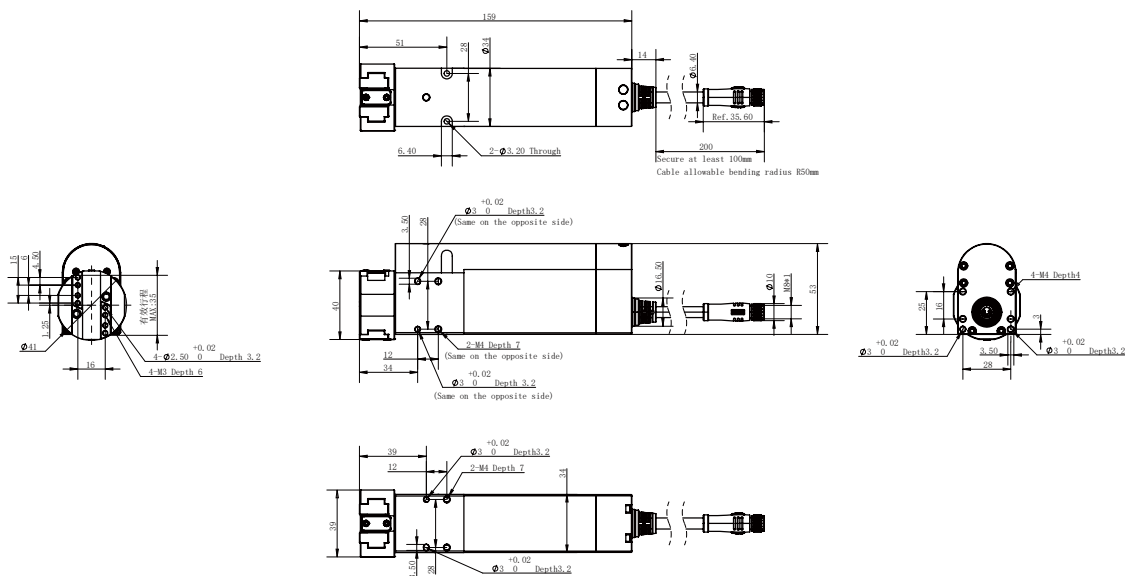
Mx 1.5 N·m

My 1.1 N·m

Mz 2.1 N·m

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings



RGD Series Electric Direct Drive Rotary Gripper

RGD-5-14

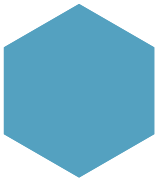
RGD-5-30

RGD-35-14

RGD-35-30

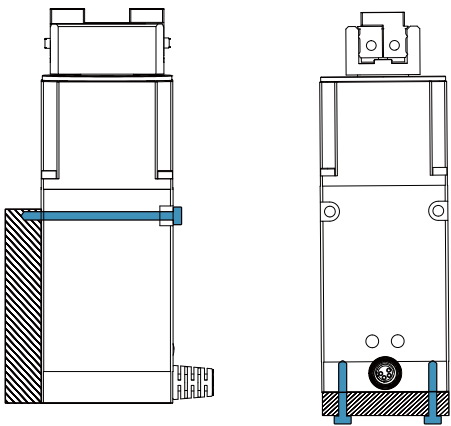


The RGD direct-drive electric rotary gripper of DH-Robotics adopts a direct-drive backlash-free rotation module to improve therotary accuracy, and thus is perfectly suited for high-precision manufacturing applications.



Installation

1. Front installation: use front screw holes for installation
2. Bottom installation: use bottom screw holes for installation



Product Features

● Zero Rotary Backlash High Repeatability

The RGD series adopts direct-drive rotary motors to realize zero rotary backlash and a rotary resolution of up to 0.01°, which applies to rotary positioning scenarios in semiconductor production.

● High Dynamic Response High-speed Stability

The precision direct-drive technology, coupled with DH-Robotics' excellent drive control, realizes perfect control of gripping and rotation. The rotation speed is up to 1500° per second.

● All-in-one Design Power-off Protection

The gripper adopts the design of integrating the dual servo system of gripping and rotation with the drive control module, which is smaller and more compact, and applies to more scenarios. Brakes are optional to meet the requirements of various applications.

Application

With the direct-drive technology, the RGD gripper can provide greatly improved rotary accuracy, which can be used in scenarios such as the high-precision positioning assembly, transport, and deflection correction of 3C electronics and semiconductors.

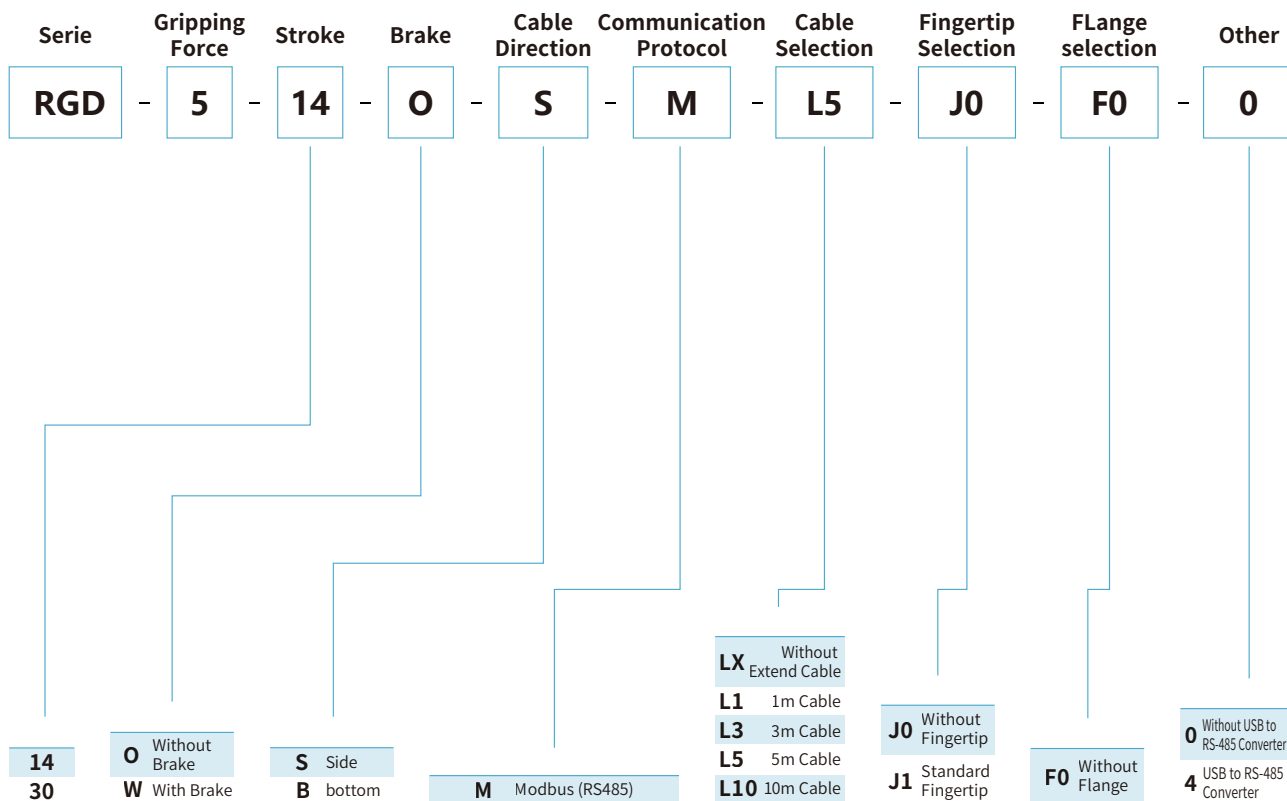


RGD-5

Direct Drive
Rotary Gripper



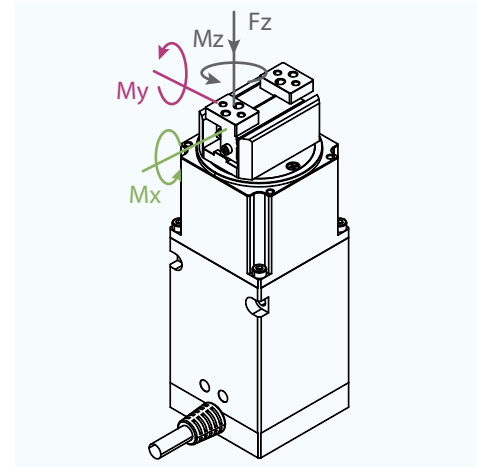
Selection Method



RGD-5-14 Parameters

| Product Parameter | |
|--|--|
| Stroke | 14 mm |
| Gripping force (per jaw) | 2-5.5 N |
| Rated torque | 0.1 N·m |
| Peak torque ^{**} | 0.25 N·m |
| Rotary range | Infinite Rotating |
| Recommended workpiece weight ^{*②} | 0.05 kg |
| Max. rotation speed | 1500 °/s |
| Rotary backlash | Zero backlash |
| Repeat accuracy (swiveling) | ± 0.1 ° |
| Repeat accuracy (position) | ± 0.02 mm |
| Opening/closing time | 0.5 s/0.5 s |
| Noise emission | < 60 dB |
| Weight | 0.86 kg(without brake) 0.88 kg(with brake) |
| Size | 149 mm x 50 mm x 50 mm Rotary Diameter: 47 mm |

| Working Environment | |
|-------------------------|--|
| Communication interface | Modbus RTU (RS485) Optional: TCP/IP, EtherCAT ^{*③} |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 1.2 A |
| Peak current | 2.5 A ^{*④} |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

Mx 2 N·m

My 1.5 N·m

Mz 2.5 N·m

| | | | |
|---|---|--|--|
| <input checked="" type="checkbox"/> Build-in Controller | <input checked="" type="checkbox"/> Gripping Force Adjustable | <input checked="" type="checkbox"/> Position Adjustable | <input checked="" type="checkbox"/> Speed Adjustable |
| <input checked="" type="checkbox"/> Drop Detection | <input checked="" type="checkbox"/> Rotary Adjustable | <input checked="" type="checkbox"/> Self-locking Mechanism | |

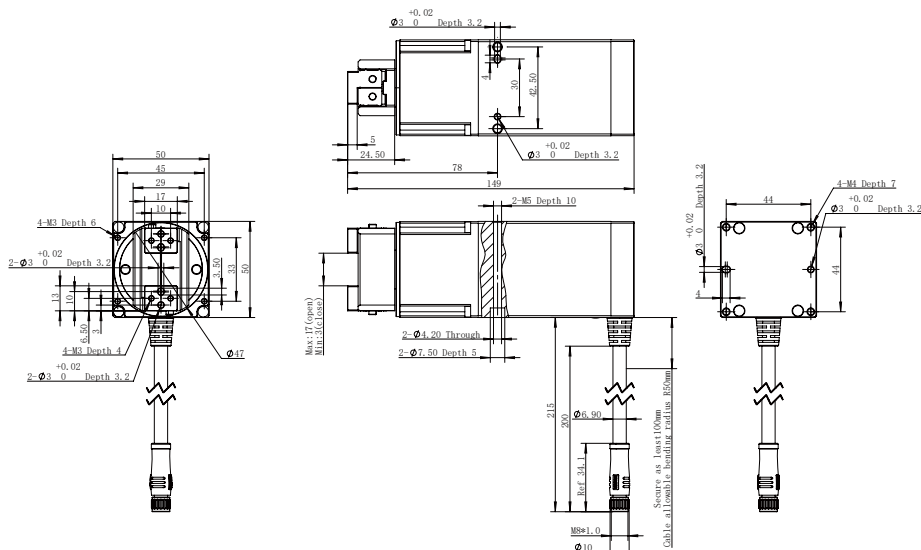
^{**} The peak torque can be increased to a maximum of 0.5 N·m. For specific details, please consult with technical support personnel.

^{*②} The gripping force on objects depends on factors such as the shape of the object, the material and friction of the contact surface, and the acceleration of movement. The displacement of the center of gravity of the grasped object can also affect the load. If you have any questions, please contact us.

^{*③} When using the optional communication protocol, an external communication box is required. For details, you can consult with our sales representatives.

^{*④} It is recommended to power the device with a power supply that matches the peak current. In cases where the power supply is insufficient, there is a possibility of unintentional triggering of the brake.

Technical Drawings



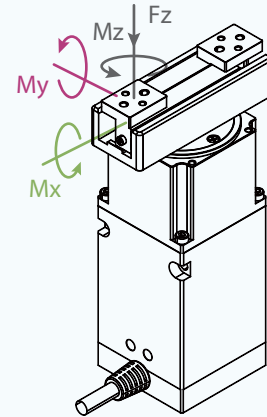
RGD-5-30 Parameters

Product Parameter

| | |
|--|--|
| Stroke | 30 mm |
| Gripping force (per jaw) | 2-5.5 N |
| Rated torque | 0.1 N·m |
| Peak torque** | 0.25 N·m |
| Rotary range | Infinite Rotating |
| Recommended workpiece weight* [®] | 0.05 kg |
| Max. rotation speed | 1500 °/s |
| Rotary backlash | Zero backlash |
| Repeat accuracy (swiveling) | ± 0.1 ° |
| Repeat accuracy (position) | ± 0.02 mm |
| Opening/closing time | 0.5 s/0.5 s |
| Noise emission | < 60 dB |
| Weight | 1 kg(without brake) 1.02 kg(with brake) |
| Size | 149 mm x 50 mm x 50 mm Rotary Diameter: 83.6 mm |

Working Environment

| | |
|-------------------------|--|
| Communication interface | Modbus RTU (RS485) Optional: TCP/IP, EtherCAT* ^③ |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 1.2 A |
| Peak current | 2.5 A* ^④ |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |



Static Vertical Allowable Load

| | |
|----|-------|
| Fz | 150 N |
|----|-------|

Allowable Loading Moment

| | |
|----|---------|
| Mx | 2 N·m |
| My | 1.5 N·m |
| Mz | 2.5 N·m |

| | | | |
|---|---|--|--|
| <input checked="" type="checkbox"/> Build-in Controller | <input checked="" type="checkbox"/> Gripping Force Adjustable | <input checked="" type="checkbox"/> Position Adjustable | <input checked="" type="checkbox"/> Speed Adjustable |
| <input checked="" type="checkbox"/> Drop Detection | <input checked="" type="checkbox"/> Rotary Adjustable | <input checked="" type="checkbox"/> Self-locking Mechanism | |

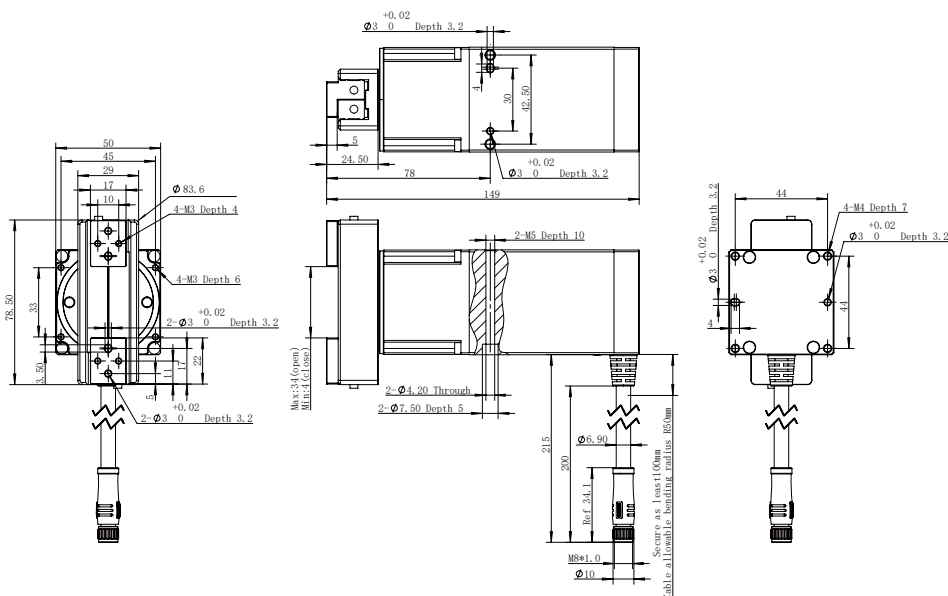
*The peak torque can be increased to a maximum of 0.5 N·m. For specific details, please consult with technical support personnel.

**The gripping force on objects depends on factors such as the shape of the object, the material and friction of the contact surface, and the acceleration of movement. The displacement of the center of gravity of the grasped object can also affect the load. If you have any questions, please contact us.

*When using the optional communication protocol, an external communication box is required. For details, you can consult with our sales representatives.

**It is recommended to power the device with a power supply that matches the peak current. In cases where the power supply is insufficient, there is a possibility of unintentional triggering of the brake.

Technical Drawings



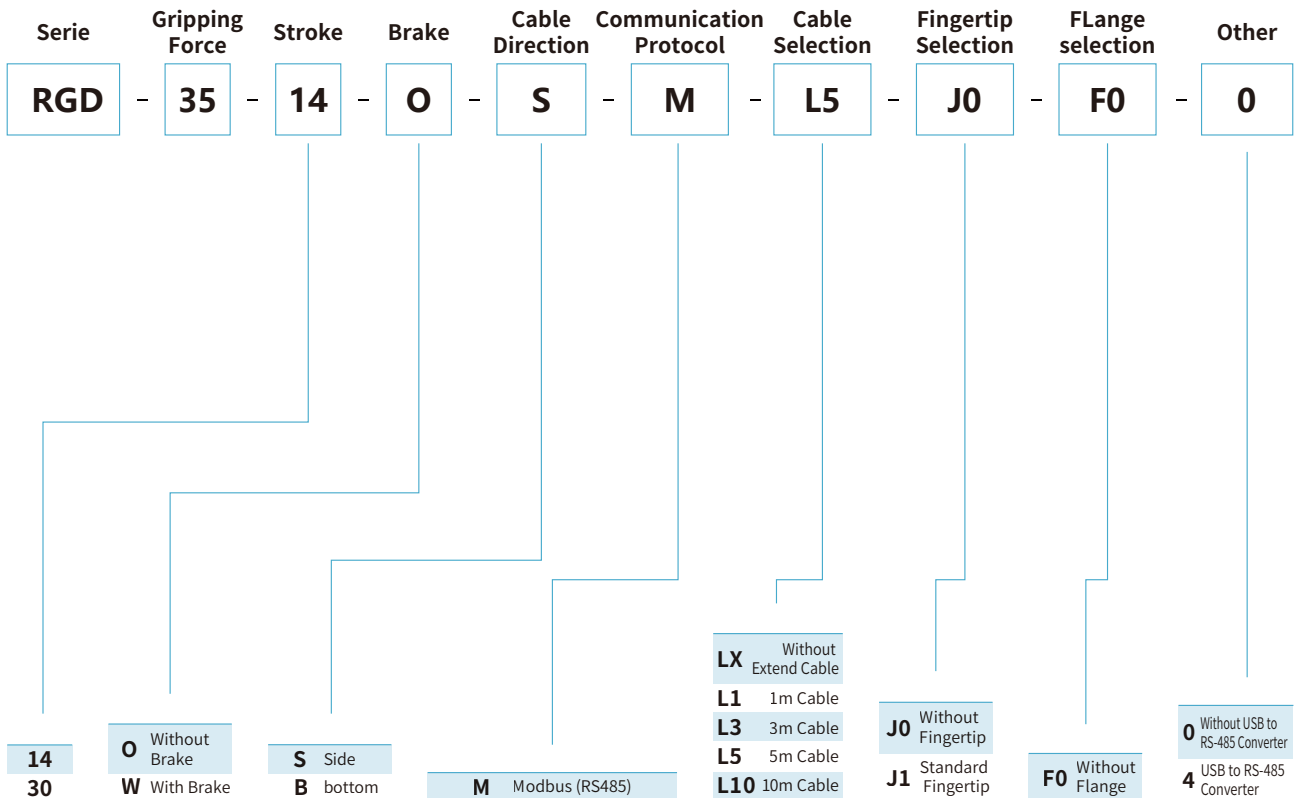
RGD-35

Direct Drive
Rotary Gripper



PGE Series
PGSE Series
RGI Series
RGD Series
PGI Series
PGHL Series
PGS Series
PGC Series
AG Series
CG Series

Selection Method



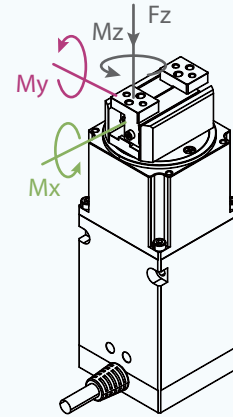
RGD-35-14 Parameters

Product Parameter

| | |
|--|--|
| Stroke | 14 mm |
| Gripping force (per jaw) | 10-35 N |
| Rated torque | 0.1 N·m |
| Peak torque* ^① | 0.25 N·m |
| Rotary range | Infinite Rotating |
| Recommended workpiece weight* ^② | 0.35 kg |
| Max. rotation speed | 1500 °/s |
| Rotary backlash | Zero backlash |
| Repeat accuracy (swiveling) | ± 0.1 ° |
| Repeat accuracy (position) | ± 0.02 mm |
| Opening/closing time | 0.5 s/0.5 s |
| Noise emission | < 60 dB |
| Weight | 0.86 kg(without brake) 0.88 kg(with brake) |
| Size | 159 mm x 50 mm x 50 mm Rotary Diameter: 47 mm |

Working Environment

| | |
|-------------------------|--|
| Communication interface | Modbus RTU (RS485) Optional: TCP/IP, EtherCAT* ^③ |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 1.2 A |
| Peak current | 2.5 A* ^④ |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

Mx 2 N·m

My 1.5 N·m

Mz 2.5 N·m

| | | | |
|---|---|---|--|
| <input checked="" type="checkbox"/> Build-in Controller | <input checked="" type="checkbox"/> Gripping Force Adjustable | <input checked="" type="checkbox"/> Position Adjustable | <input checked="" type="checkbox"/> Speed Adjustable |
| <input checked="" type="checkbox"/> Drop Detection | <input checked="" type="checkbox"/> Rotary Adjustable | <input type="checkbox"/> Self-locking Mechanism | |

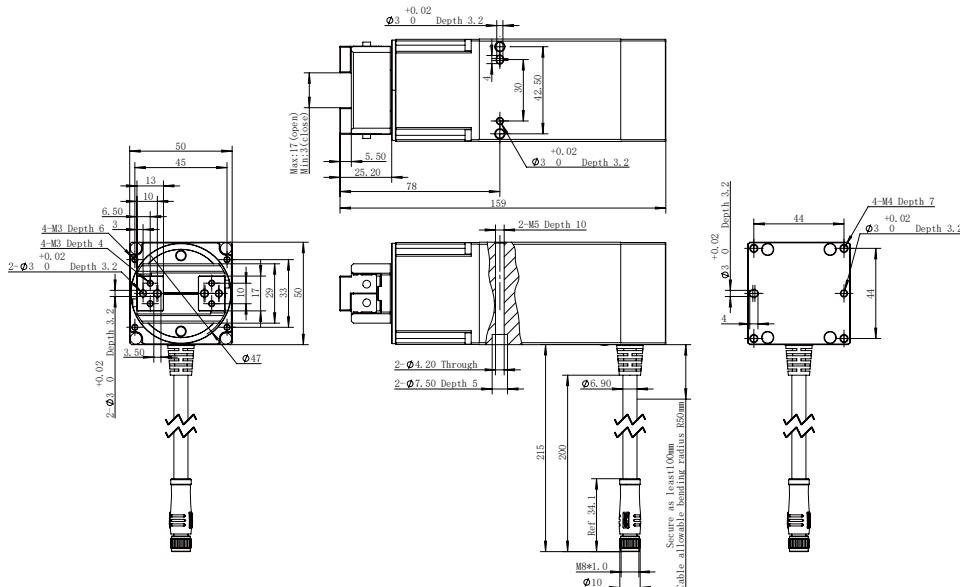
*^① The peak torque can be increased to a maximum of 0.5 N·m. For specific details, please consult with technical support personnel.

*^② The gripping force on objects depends on factors such as the shape of the object, the material and friction of the contact surface, and the acceleration of movement. The displacement of the center of gravity of the grasped object can also affect the load. If you have any questions, please contact us.

*^③ When using the optional communication protocol, an external communication box is required. For details, you can consult with our sales representatives.

*^④ It is recommended to power the device with a power supply that matches the peak current. In cases where the power supply is insufficient, there is a possibility of unintentional triggering of the brake.

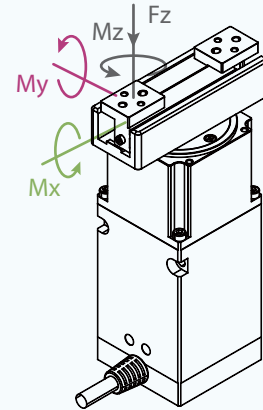
Technical Drawings



RGD-35-30 Parameters

| Product Parameter | |
|--|--|
| Stroke | 30 mm |
| Gripping force (per jaw) | 10-35 N |
| Rated torque | 0.1 N·m |
| Peak torque* ^① | 0.25 N·m |
| Rotary range | Infinite Rotating |
| Recommended workpiece weight* ^② | 0.35 kg |
| Max. rotation speed | 1500 °/s |
| Rotary backlash | Zero backlash |
| Repeat accuracy (swiveling) | ± 0.1 ° |
| Repeat accuracy (position) | ± 0.02 mm |
| Opening/closing time | 0.7 s/0.7 s |
| Noise emission | < 60 dB |
| Weight | 1 kg(without brake) 1.02 kg(with brake) |
| Size | 159 mm x 50 mm x 50 mm Rotary Diameter: 83.6 mm |

| Working Environment | |
|-------------------------|--|
| Communication interface | Modbus RTU (RS485) Optional: TCP/IP, EtherCAT* ^③ |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 1.2 A |
| Peak current | 2.5 A* ^④ |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

Mx 2 N·m

My 1.5 N·m

Mz 2.5 N·m

| | | | |
|---|---|---|--|
| <input checked="" type="checkbox"/> Build-in Controller | <input checked="" type="checkbox"/> Gripping Force Adjustable | <input checked="" type="checkbox"/> Position Adjustable | <input checked="" type="checkbox"/> Speed Adjustable |
| <input checked="" type="checkbox"/> Drop Detection | <input checked="" type="checkbox"/> Rotary Adjustable | <input type="checkbox"/> Self-locking Mechanism | |

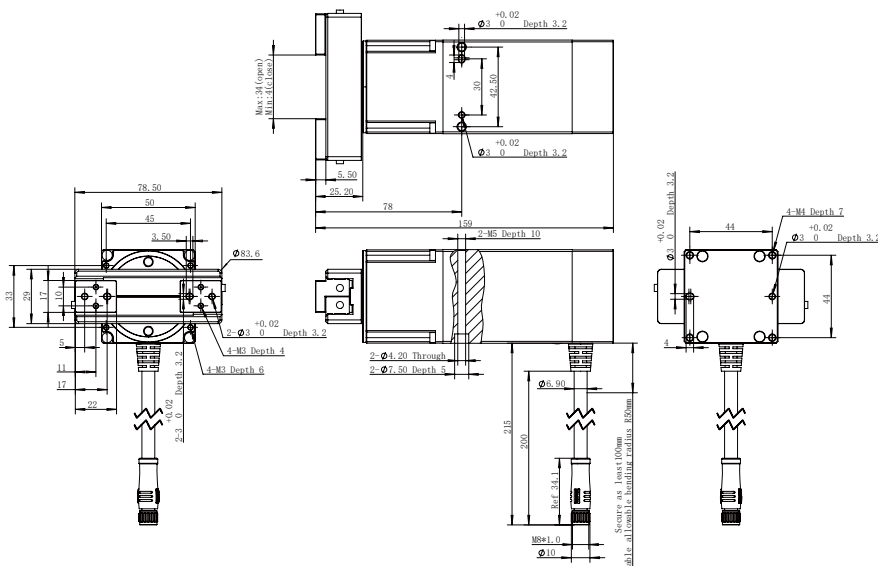
*^①The peak torque can be increased to a maximum of 0.5 N·m. For specific details, please consult with technical support personnel.

*^②The gripping force on objects depends on factors such as the shape of the object, the material and friction of the contact surface, and the acceleration of movement. The displacement of the center of gravity of the grasped object can also affect the load. If you have any questions, please contact us.

*^③When using the optional communication protocol, an external communication box is required. For details, you can consult with our sales representatives.

*^④It is recommended to power the device with a power supply that matches the peak current. In cases where the power supply is insufficient, there is a possibility of unintentional triggering of the brake.

Technical Drawings

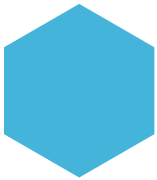


PGI Series Electric Parallel Gripper

PGI-140-80

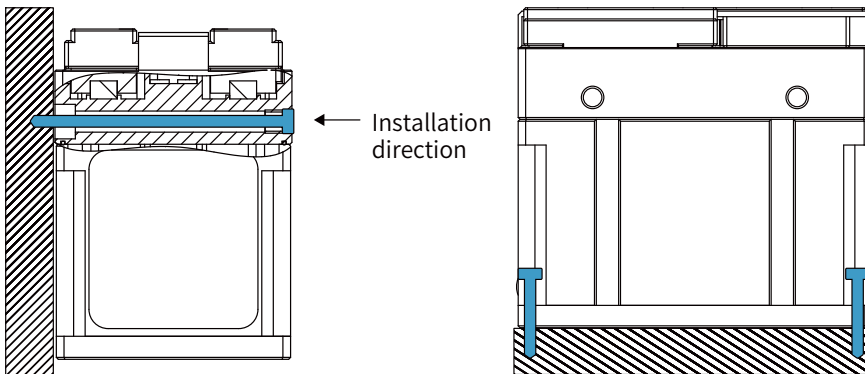


Based on the industrial requirements of “long stroke, high load, and high protection level” , DH-Robot ics independently developed the PGI series of industrial electric parallel gripper. The PGI series is widely used in various industrial scenarios with positive feedback.



Installation

1. Front and rear installation: use front and rear screw holes for installation
2. Bottom installation : use bottom screw holes for installation



Product Features

● Long Stroke

Long stroke reach to 80 mm. With the customization fingertips, it can stably grasp the medium and large objects below 3kg and suitable for lots of industrial scenes.

● High Protection Level

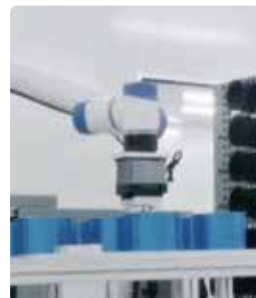
The protection level of PGI-140-80 reaches to IP54, which is able to work under harsh environment with dust and liquid splash.

● High Load

The maximum single-sided gripping force of PGI-140-80 is 140 N, and the maximum recommended load is 3 kg, which can meet more diverse gripping needs.

Application

In industrial scenarios, it is used for gripping, handling and assembly of heavy workpieces. Mostly used in new energy, auto parts, machining, 3C electronics and other industries.

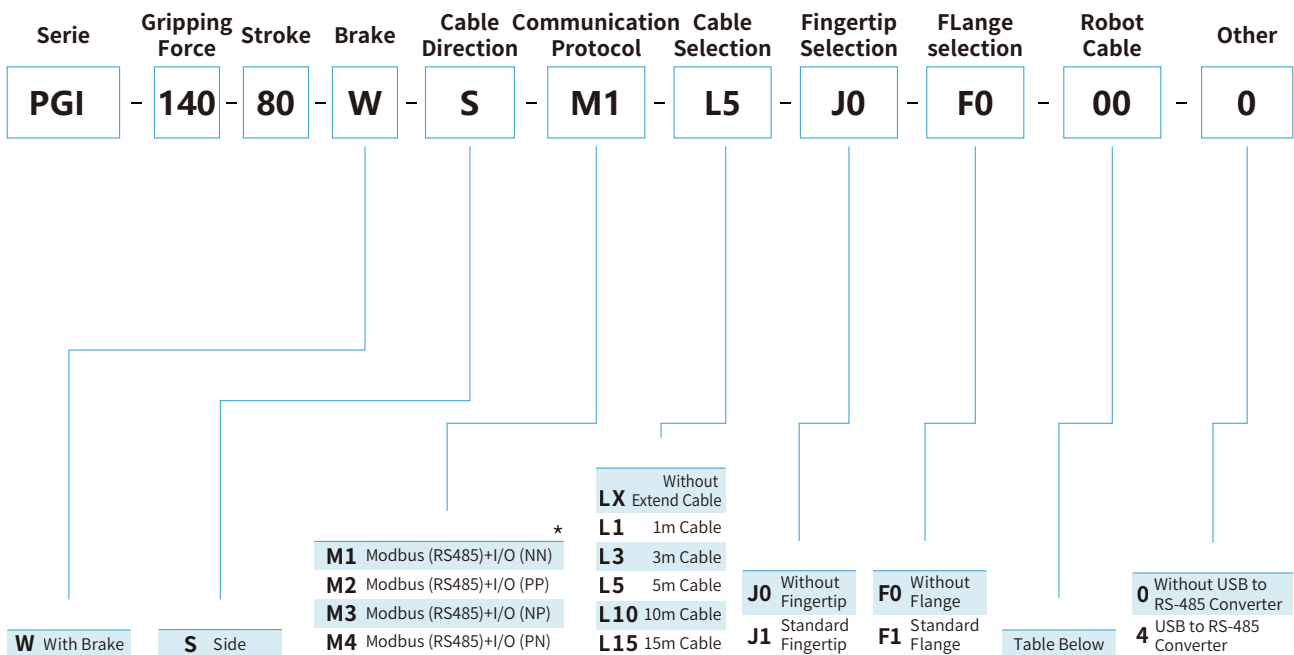


PGI-140-80

Electric Parallel Gripper



Selection Method



* Note:







I/O(NN): NPN/NPN
 I/O(PP): PNP/PNP
 I/O(NP): NPN/PNP
 I/O(PN): PNP/NPN

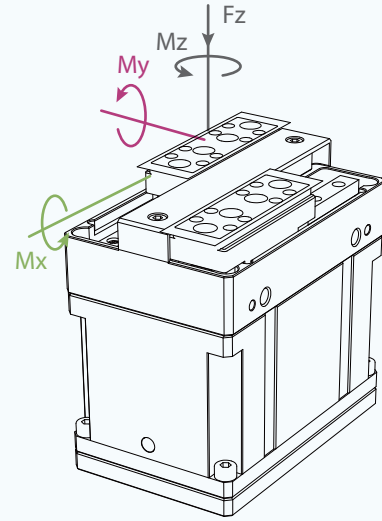
| | | | | | | | | | | | | | | | |
|-------------------------------|---------------------------------|-------------------------------|-------------------------|------------------------|-----------------------------|-----------------------|--------------------|--------------------|--------------------|-----------------|-------------------|--------------------|---------------------|--------------------|----------------------|
| 00 Without Robot Cable | 01 SIASUN Elite CS UR CB | 02 DOBOT CR DOBOT Nova | 03 AUBO ELEPHANT | 04 JAKA TECHMAN | 05 ROKAE SR ROKAE ER | 06 DOBOT MG400 | 07 Doosan A | 08 Doosan M | 09 Elite EC | 10 Han's | 11 FAIRINO | 12 UF x Arm | 13 Neuromeka | 14 ROKAE CR | 15 Hanwha HCR |
|-------------------------------|---------------------------------|-------------------------------|-------------------------|------------------------|-----------------------------|-----------------------|--------------------|--------------------|--------------------|-----------------|-------------------|--------------------|---------------------|--------------------|----------------------|

Parameters

| Product Parameter | |
|------------------------------------|---|
| Gripping force (per jaw) | 40~140 N |
| Stroke | 80 mm |
| Recommended workpiece weight | 3 kg |
| Opening/closing time* ^① | 1.1 s/1.1 s |
| Repeat accuracy (position) | ± 0.03 mm |
| Noise emission | < 50 dB |
| Weight | 1 kg (exclude fingers) |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | 95 mm x 61.7 mm x 86 mm |

| Working Environment | |
|-------------------------|---|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP、USB2.0、CAN2.0A、PROFINET、EtherCAT * ^② |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.5 A |
| Peak current | 1.2 A |
| IP class | IP 54 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | |
|--|--|--|---|---|---|
|  Build-in Controller |  Gripping Force Adjustable |  Position Adjustable |  Speed Adjustable |  Drop Detection |  Self-locking Mechanism |
|--|--|--|---|---|---|



Static Vertical Allowable Load

Fz 300 N

Allowable Loading Moment

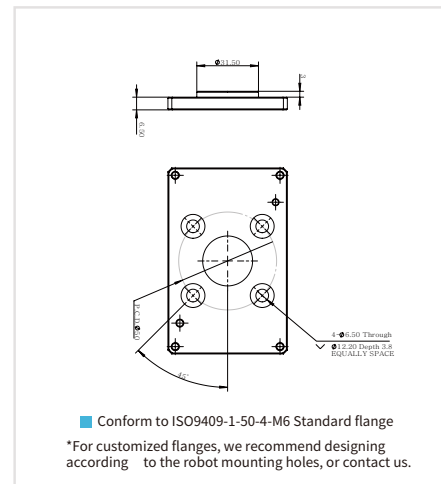
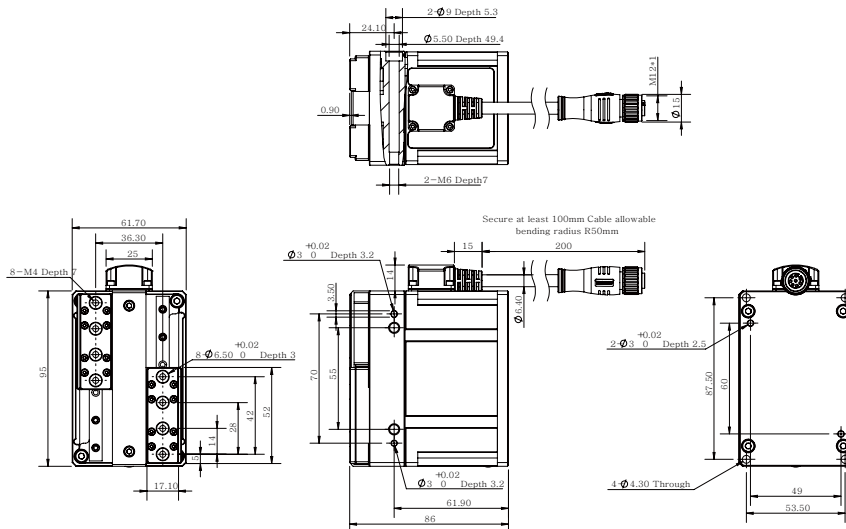
Mx 7 N·m

My 7 N·m

Mz 7 N·m

*^① 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.
*^② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings



PGHL Series Heavy-Load Long-Stroke Electric Parallel Gripper

PGHL-400-80

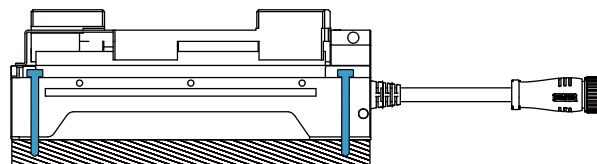
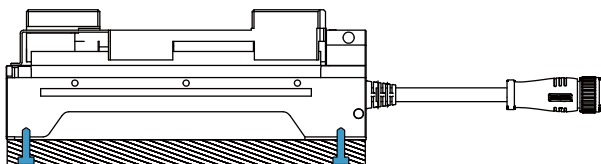


PGHL series is an industrial flat electric gripper developed and produced by DH-Robotics. With its compact design, heavy load and high force control accuracy, it can be applied to heavier load clamping requirements and more application scenarios.



Installation

Bottom installation: use bottom screw holes for installation



Product Features

● Flat Electric Gripper High Energy density

PGHL-400-80 industrial flat electric gripper, the structure of which is delicate and meticulous. The length, width and height dimensions is only 194 × 73 × 70mm. This model can provide large clamping force and fast clamping beat, coming with mechanical self-locking mechanism, challenge the limit of large load and thin size.

● High Force Control Accuracy

The force repeatability is $\pm 40N(\pm 10\%)$. Far better than ordinary products in the market by $\pm 10\% \sim \pm 20\%$ of force control accuracy.

● Quick Response Intelligent planning speed

Opening/closing time up to 1.0s/1.1s, with speed control optimization and mechanical self-locking mechanism function, it can meet fast and stable gripping needs of the production line.

Application

Applied in industrial production of large weight and large volume workpieces gripping and handling, such as lithium batteries in the new energy industry package gripping, large machined parts in automobile assembly production in automotive assembly.

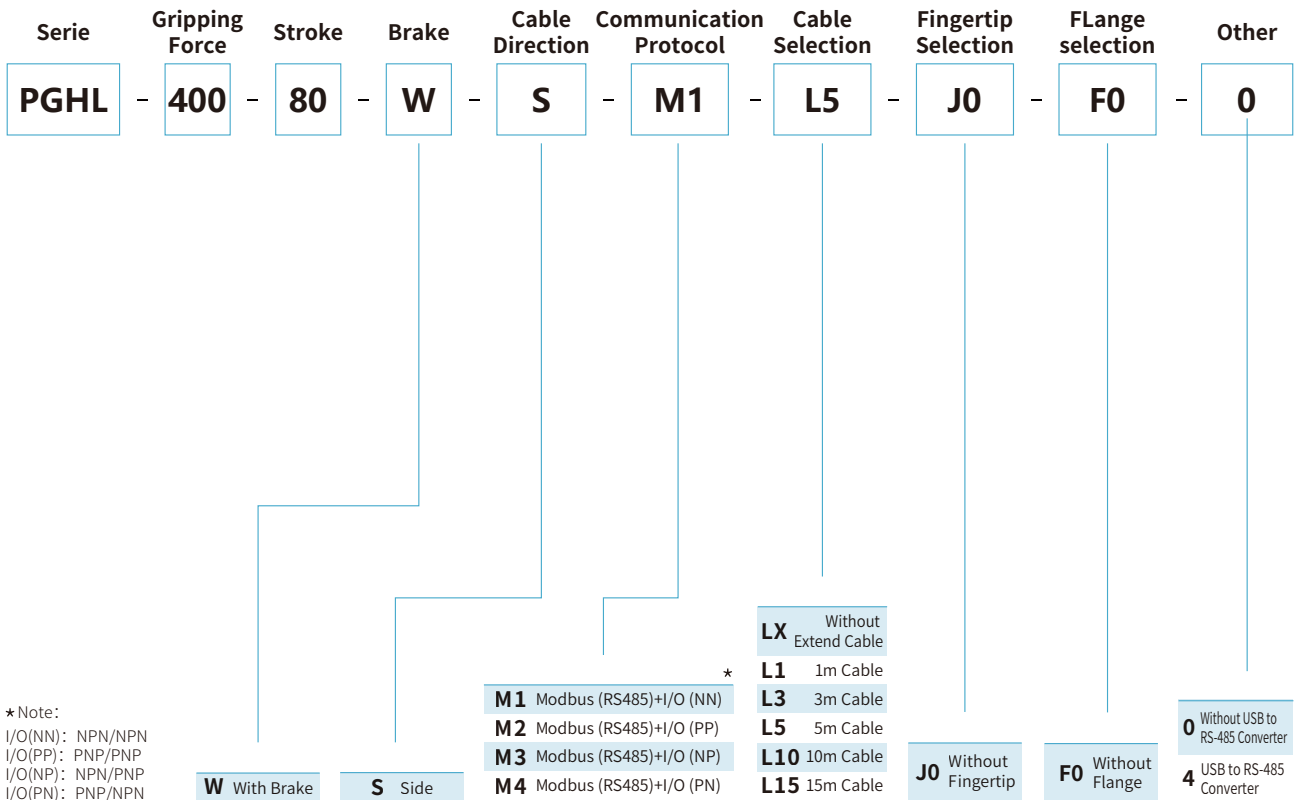


PGHL-400-80

Heavy-Load Long-Stroke
Electric Parallel Gripper









Selection Method

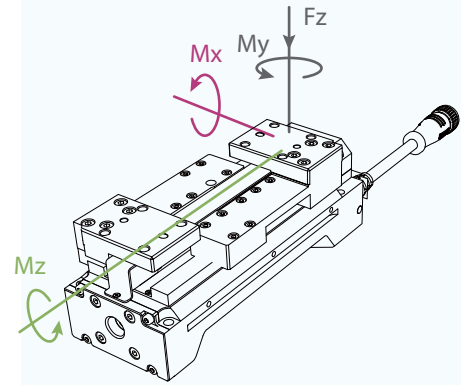


Parameters

| Product Parameter | |
|--|--|
| Gripping force (per jaw) | 140~400 N |
| Stroke | 80 mm |
| Recommended workpiece weight ^{*①} | 8 kg |
| Opening/closing time | 1.0 s/1.1 s |
| Repeat accuracy (position) | ± 0.02 mm |
| Noise emission | < 60 dB |
| Weight | 2.2 kg |
| Driving method | Precise planetary gears+ Tshaped lead screw+Rack and pinion |
| Size | 194 mm x 73 mm x 70 mm |

| Working Environment | |
|-------------------------|---|
| Communication interface | Standard: Modbus RTU (RS485)、Digital I/O Optional: TCP/IP、USB2.0、CAN2.0A、PROFINET、EtherCAT ^{*②} |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 1.0 A |
| Peak current | 3.0 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, 85% RH 以下 |
| Certification | CE, FCC, RoHS |

| | | | | | |
|--|--|--|---|---|---|
|  Build-in Controller |  Gripping Force Adjustable |  Position Adjustable |  Speed Adjustable |  Drop Detection |  Self-locking Mechanism |
|--|--|--|---|---|---|



Static Vertical Allowable Load

Fz 1000 N

Allowable Loading Moment

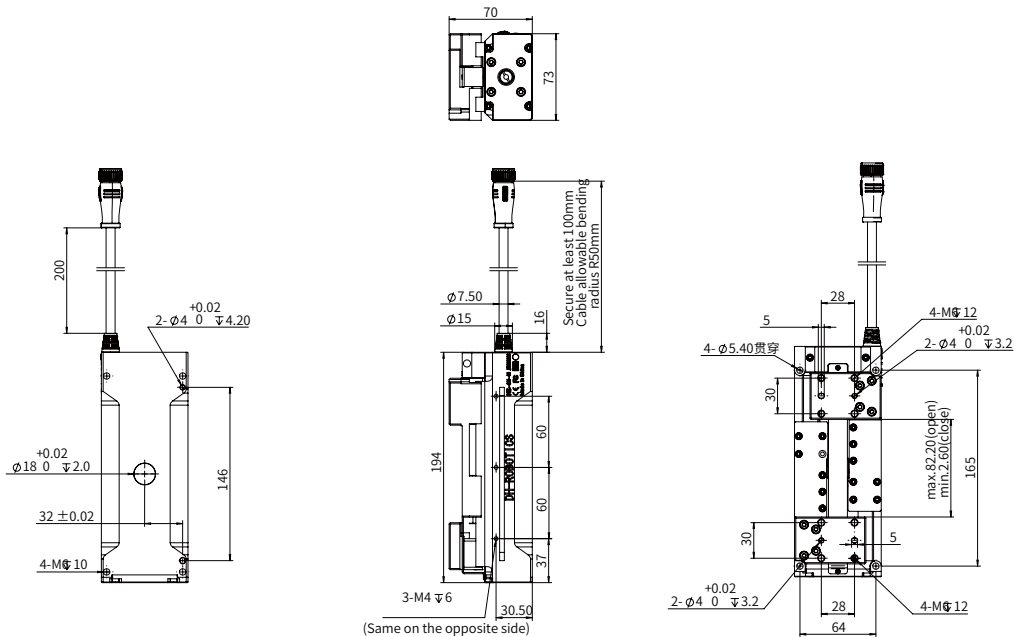
Mx 50 N·m

My 50 N·m

Mz 15 N·m

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings



PGS Series Miniature Electro-magnetic Gripper

PGS-5-5

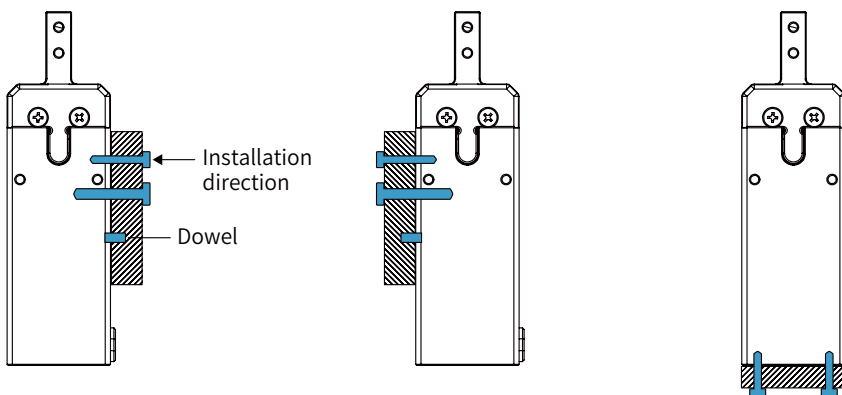


The PGS series is a miniature electromagnetic gripper with high working frequency. Based on a split design, the PGS series could be applied in space-limited environment with the ultimate compact size and simple configuration.



Installation

1. Front and rear installation: use front and rear screw holes for installation
2. Bottom installation : use bottom screw holes for installation



Product Features

● Small Size

Compact size with 20×26 mm, it can be deployed in a relatively small environment.

● High Frequency

The opening/closing time could reach 0.03s to meet the needs of fast grasping.

● Easy to Use

The configuration is simple with the Digital I/O communication protocol.

Application

High-frequency fast capture, detection, adjustment and other scenarios in 3C electronics, medical automation, semiconductor and other industries.

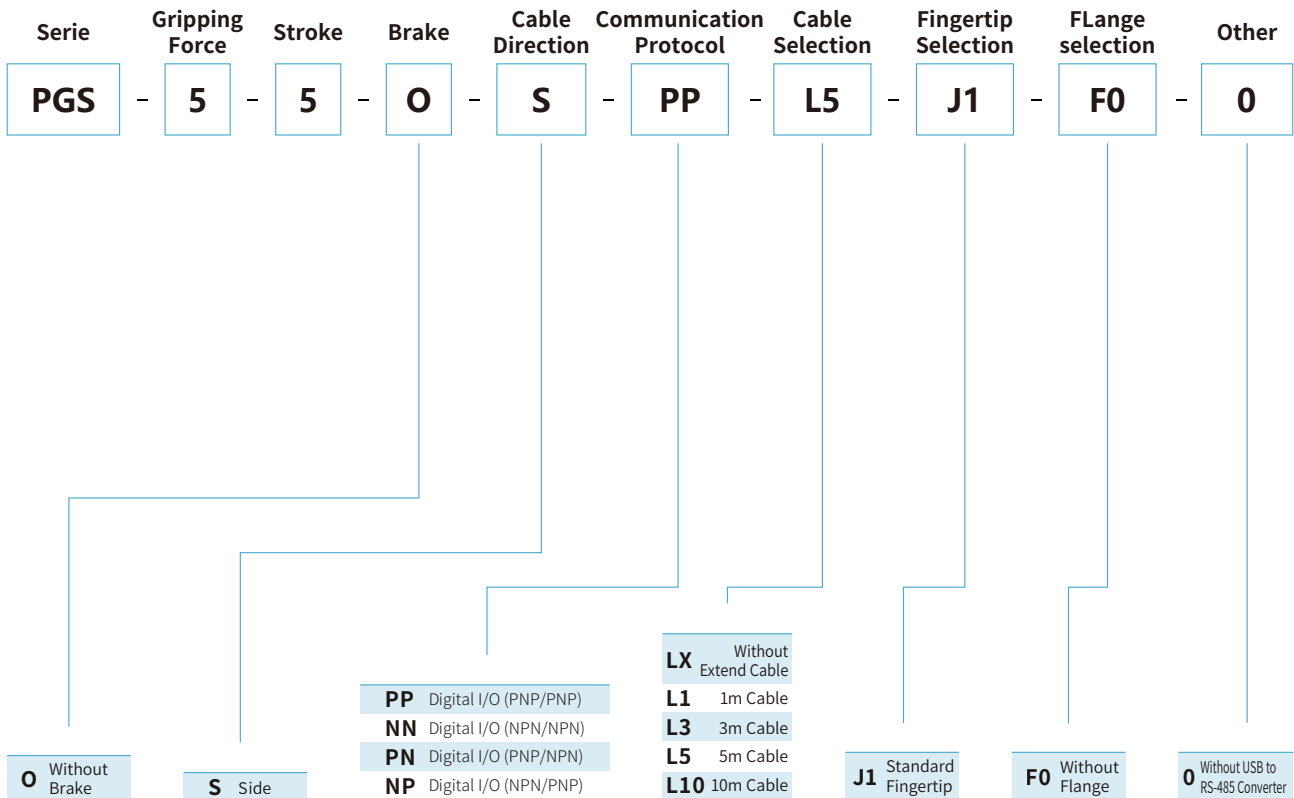


PGS-5-5

Miniature Electro-magnetic Gripper









Selection Method

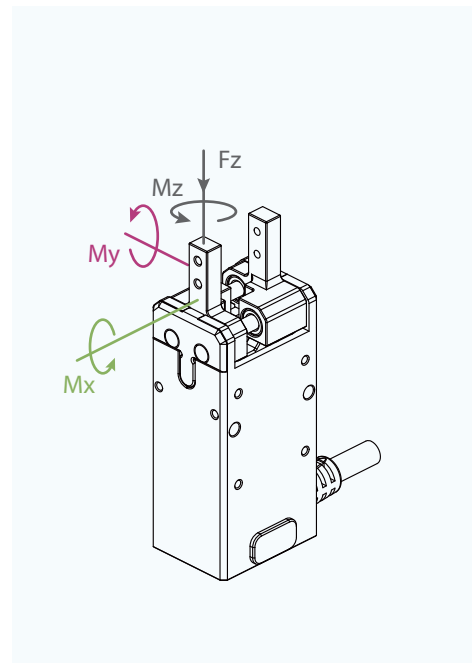


Parameters

| Product Parameter | |
|-------------------------------|---|
| Gripping force (per jaw) | 3.5-5 N |
| Stroke | 5 mm |
| Recommended workpiece weight* | 0.05 kg |
| Opening/closing time | 0.03 s/0.03 s |
| Repeat accuracy (position) | ± 0.01 mm |
| Noise emission | < 60 dB |
| Weight | 0.2 kg |
| Driving method | Electromagnet + Spring |
| Size | Gripper Size: 68.5 mm x 26 mm x 20 mm Controller Size: 67.7 mm x 66.8 mm x 29.6 mm |

| Working Environment | |
|-------------------------|----------------------|
| Communication interface | Digital I/O |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.1 A |
| Peak current | 3.0 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | |
|---|---|---|---|---|---|
|  |  |  |  |  |  |
| Build-in Controller | Gripping Force Adjustable | Position Adjustable | Speed Adjustable | Drop Detection | Self-locking Mechanism |



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

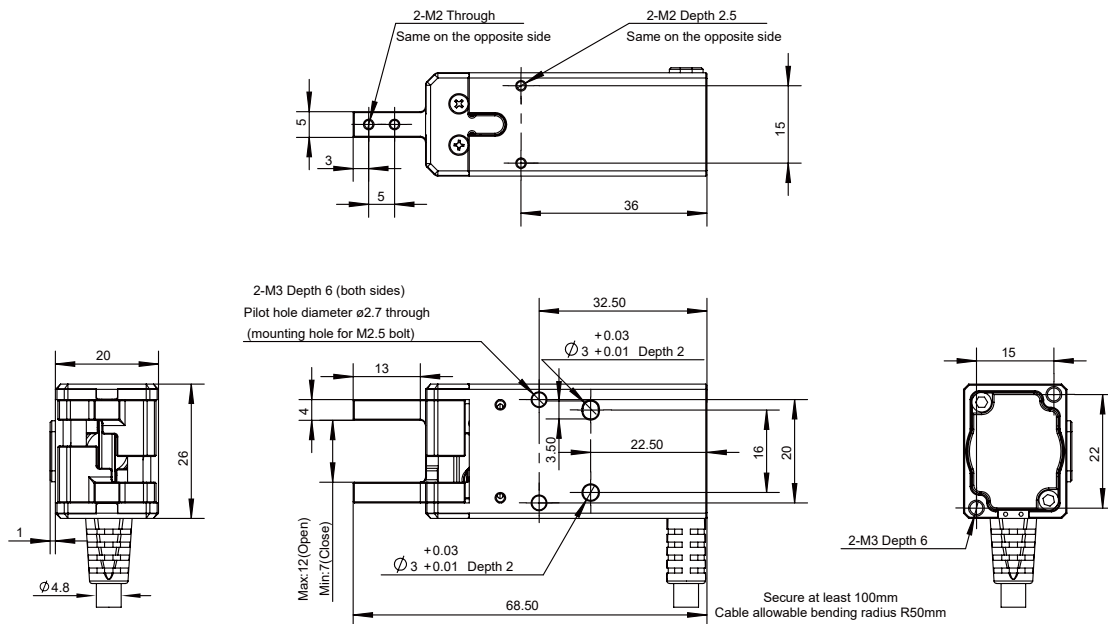
Mx 0.62 N · m

My 0.62 N · m

Mz 0.62 N · m

*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.

Technical Drawings



PGC Series Electric Collaborative Parallel Gripper



PGC-50-35
PGC-140-50
PGC-300-60

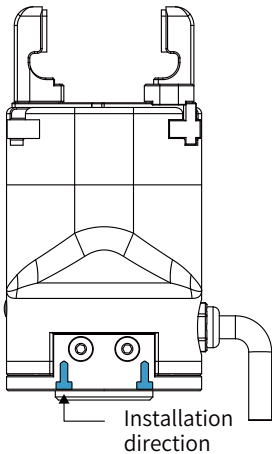


DH-Robotics PGC series of collaborative parallel electric grippers is an electric gripper mainly used in cooperative manipulators. It has the advantages of high protection level, plug and play, large load and so on. The PGC series combines precision force control and industrial aesthetics. In 2021, it won two industrial design awards, the Red Dot Award and the IF Award.



Installation

1. Bottom installation : use bottom screw holes for installation



Product Features

● High protection level

The protection level of PGC series is up to IP67, so the PGC series is able to work under harsh conditions such as machine tending environment.

● Plug & Play

PGC series supports plug & play with most collaborative robot brands on the market which is easier to control and program.

● High Load

The gripping force of the PGC series could reach 300 N, and the maximum load can reach 6 kg, which can meet more diverse gripping needs.

Application

With collaborative robots, it can complete a series of complex processes including gripping, handling, and assembly in scenarios such as medical automation, 3C electronics, new energy, and new robot retail.

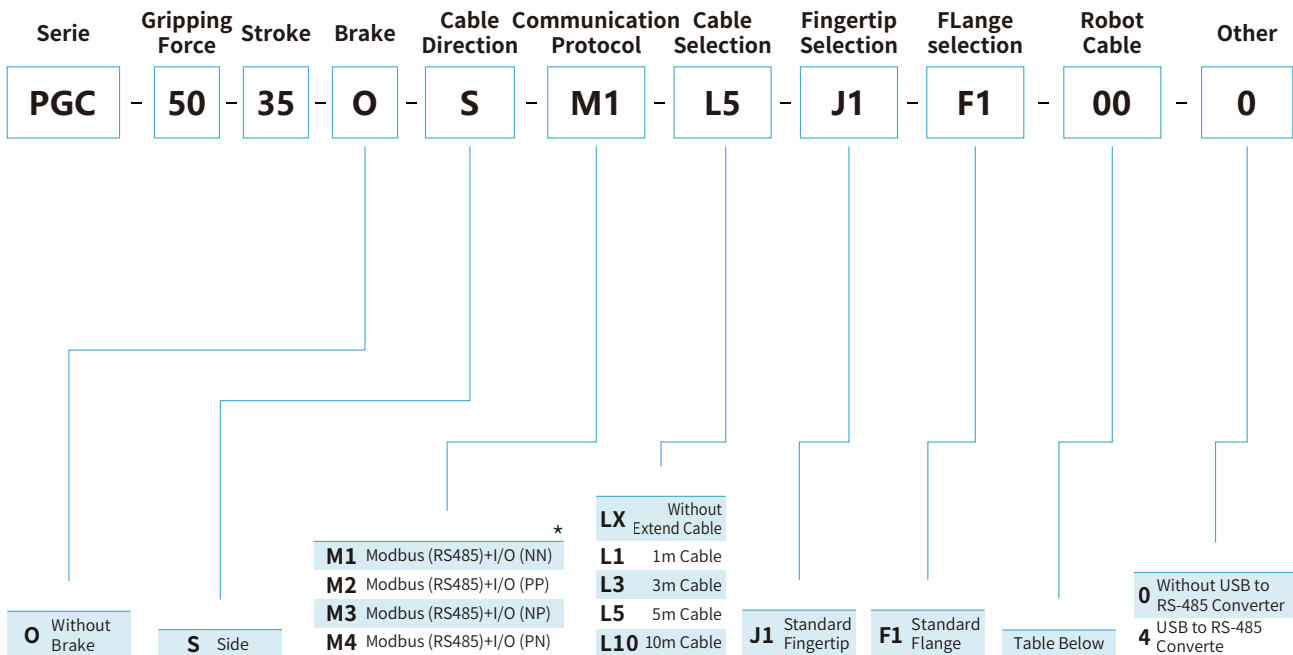


PGC-50-35

Electric Collaborative
Parallel Gripper



Selection Method



* Note:

I/O(NN): NPN/NPN
I/O(PP): PNP/PNP
I/O(NP): NPN/PNP
I/O(PN): PNP/NPN

| | | | | | | | | | | | |
|-------------------------------|--------------------------|----------------------|---------------------|--------------------|-------------------|-----------------------------|--------------------|--------------------|---------------------|----------------------|--------------------|
| 00 Without Robot Cable | 01 Elite CS UR CB | SIASUN Hanwha A UR E | DOBOT CR DOBOT Nova | 02 AUBO | 04 JAKA | 06 ROKAE SR ROKAE ER | 09 Doosan A | 11 Elite EC | 13 Neuromeka | 15 Hanwha HCR | |
| | | | | 03 ELEPHANT | 05 TECHMAN | 07 DOBOT MG400 | 10 Doosan M | 12 Han's | 14 FAIRINO | 16 UF x Arm | 17 ROKAE CR |

Parameters

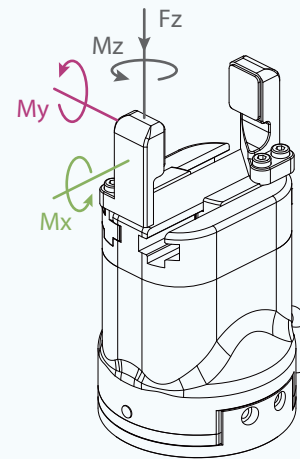
Product Parameter

| | |
|--|---|
| Gripping force (per jaw) | 15~50 N |
| Stroke | 37 mm |
| Recommended workpiece weight ^{*①} | 1 kg |
| Opening/closing time | 0.7 s/0.7 s |
| Repeat accuracy (position) | ± 0.03 mm |
| Noise emission | < 50 dB |
| Weight | 0.5 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | 124 mm x 63 mm x 63 mm |

Working Environment

| | |
|-------------------------|--|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT ^{*②} |
| 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 |
| Certification | CE, FCC, RoHS |

| | | | | | | |
|---|---|---|--|--|---|--|
|  Build-in Controller |  Gripping Force Adjustable |  Position Adjustable |  Speed Adjustable |  Drop Detection |  Plug & Play |  Self-locking Mechanism |
|---|---|---|--|--|---|--|



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

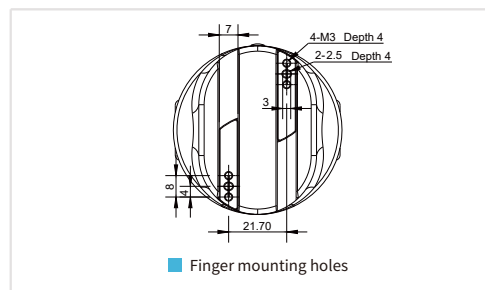
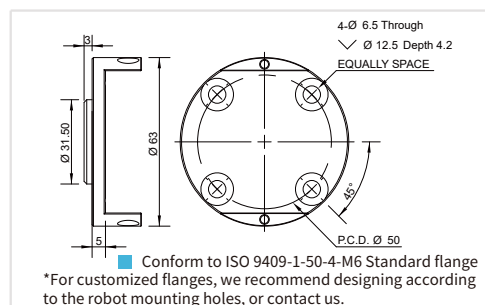
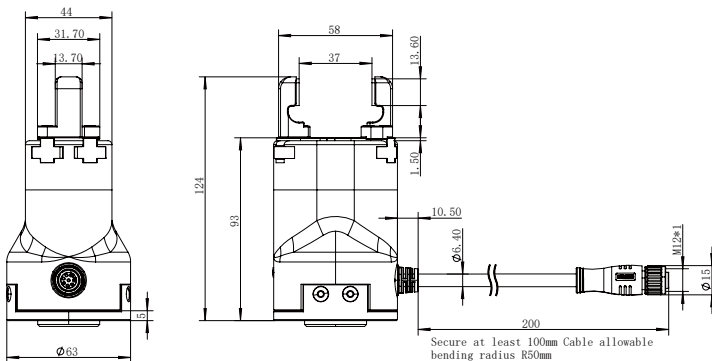
Mx 2.5 N·m

My 2 N·m

Mz 3 N·m

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

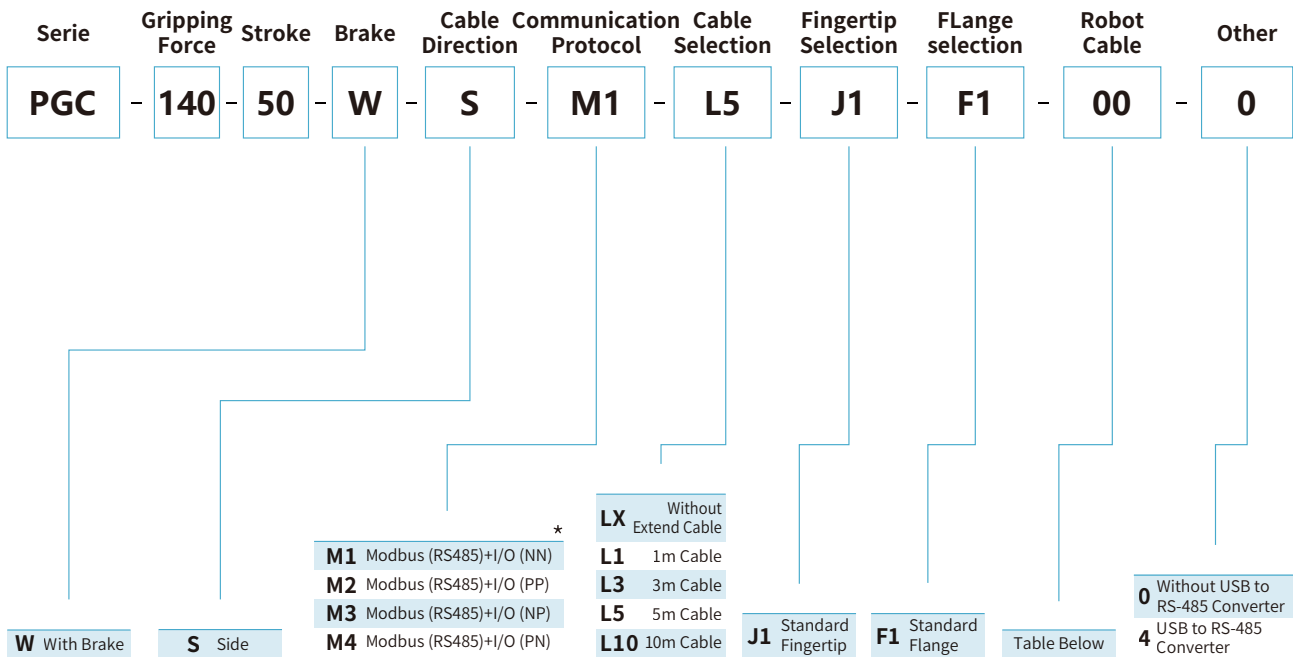


PGC-140-50

Electric Collaborative
Parallel Gripper



Selection Method



* Note:








I/O(NN): NPN/NPN
 I/O(PP): PNP/PNP
 I/O(NP): NPN/PNP
 I/O(PN): PNP/NPN

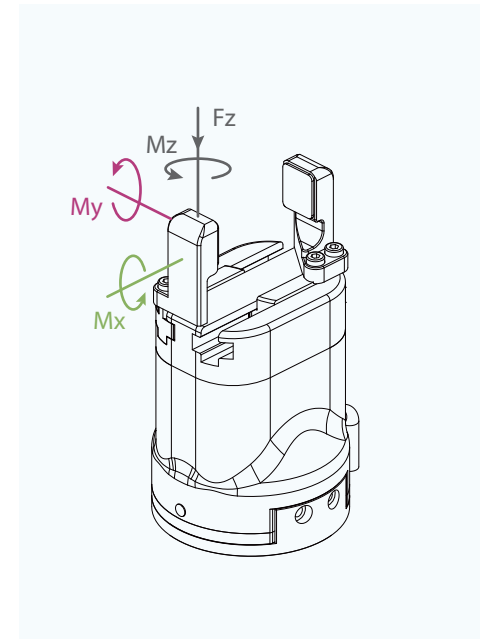
| | | | | | | | | | | | |
|-------------------------------|--------------------------|----------------------|---------------------|--------------------|-------------------|-----------------------------|--------------------|--------------------|---------------------|----------------------|--------------------|
| 00 Without Robot Cable | 01 Elite CS UR CB | SIASUN Hanwha A UR E | DOBOT CR DOBOT Nova | 02 AUBO | 04 JAKA | 06 ROKAE SR ROKAE ER | 09 Doosan A | 11 Elite EC | 13 Neuromeka | 15 Hanwha HCR | |
| | | | | 03 ELEPHANT | 05 TECHMAN | 07 DOBOT MG400 | 10 Doosan M | 12 Han's | 14 FAIRINO | 16 UF x Arm | 17 ROKAE CR |

Parameters

| Product Parameter | |
|--|---|
| Gripping force (per jaw) | 40~140 N |
| Stroke | 50 mm |
| Recommended workpiece weight ^{*①} | 3 kg |
| Opening/closing time | 0.6 s/0.6 s |
| Repeat accuracy (position) | ± 0.03 mm |
| Noise emission | < 50 dB |
| Weight | 1 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | 138.5 mm x 75 mm x 75 mm |

| Working Environment | |
|-------------------------|--|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT ^{*②} |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.4 A |
| Peak current | 1.0 A |
| IP class | IP 67 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | | |
|---|---|---|--|--|---|--|
|  Build-in Controller |  Gripping Force Adjustable |  Position Adjustable |  Speed Adjustable |  Drop Detection |  Plug & Play |  Self-locking Mechanism |
|---|---|---|--|--|---|--|



Static Vertical Allowable Load

Fz 300 N

Allowable Loading Moment

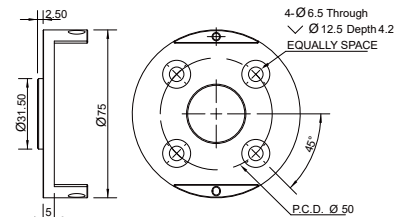
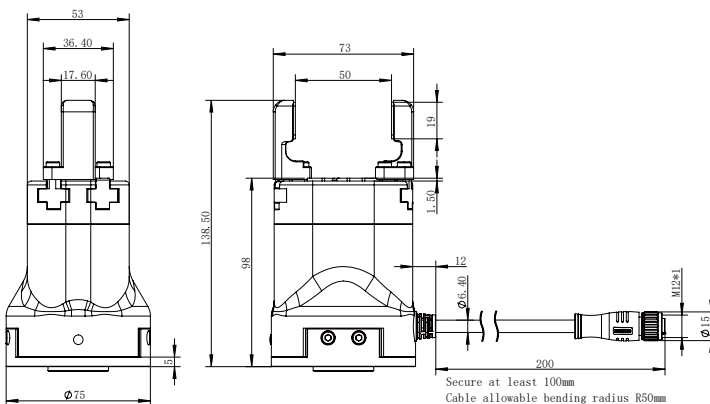
Mx 7 N·m

My 7 N·m

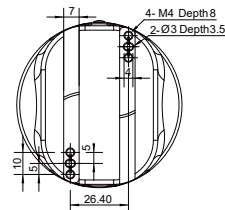
Mz 7 N·m

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings



■ Conform to ISO 9409-1-50-4-M6 Standard flange
*For customized flanges, we recommend designing according to the robot mounting holes, or contact us.



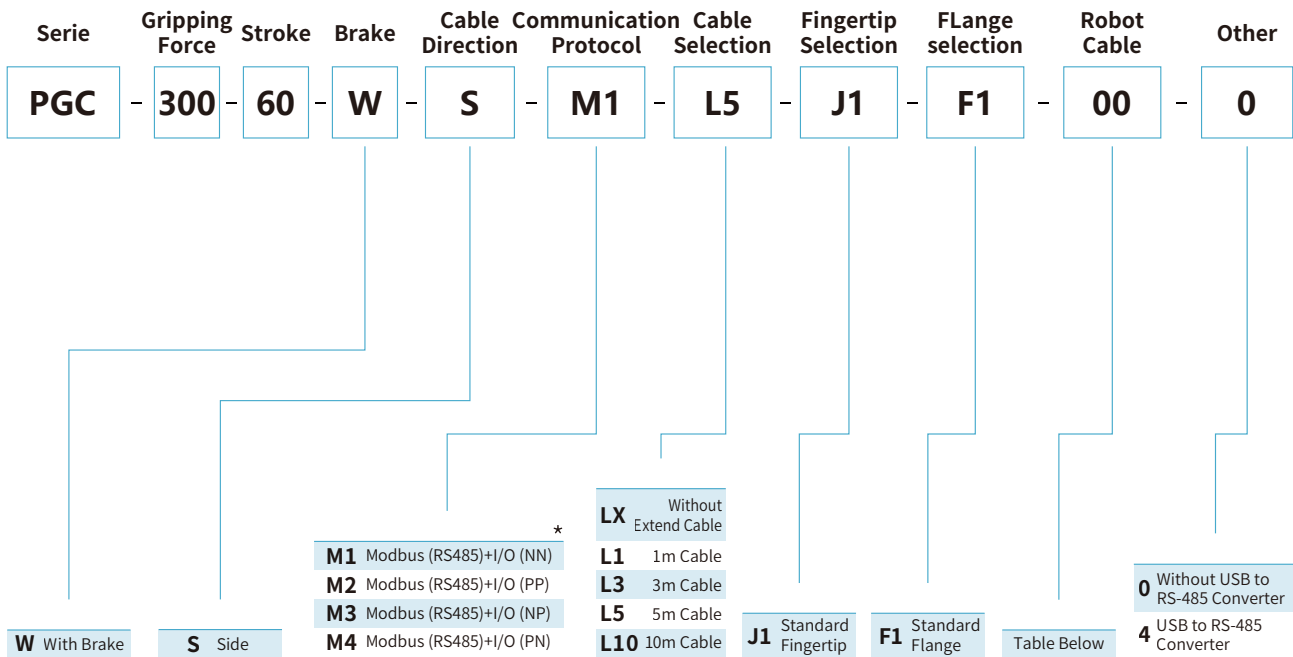
■ Finger mounting holes

PGC-300-60

Electric Collaborative
Parallel Gripper



Selection Method



* Note:

I/O(NN): NPN/NPN
 I/O(PP): PNP/PNP
 I/O(NP): NPN/PNP
 I/O(PN): PNP/NPN

| | | | | | | | | | | |
|-------------------------------|---------------------------------------|------------------------------------|--|---|--|--|--|--|---|--|
| 00 Without Robot Cable | 01 Elite CS UR CB SIASUN | Hanwha A DOBOT CR DOBOT Nova | 02 AUBO 03 ELEPHANT | 04 JAKA 05 TECHMAN | 06 ROKAE SR ROKAE ER 07 DOBOT MG400 | 08 UR E 09 Doosan A | 10 Doosan M 11 Elite EC | 12 Han's 13 Neuromeka | 14 FAIRINO 15 Hanwha HCR | 16 UF x Arm 17 ROKAE CR |
|-------------------------------|---------------------------------------|------------------------------------|--|---|--|--|--|--|---|--|

Parameters

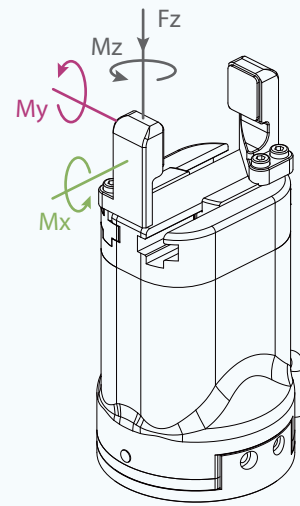
Product Parameter

| | |
|--|---|
| Gripping force (per jaw) | 80~300 N |
| Stroke | 60 mm |
| Recommended workpiece weight ^{*①} | 6 kg |
| Opening/closing time | 0.8 s/0.8 s |
| Repeat accuracy (position) | ± 0.03 mm |
| Noise emission | < 50 dB |
| Weight | 1.5 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | 178 mm x 90 mm x 90 mm |

Working Environment

| | |
|-------------------------|--|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT ^{*②} |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.4 A |
| Peak current | 2.0 A |
| IP class | IP 67 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | | |
|---------------------|---------------------------|---------------------|------------------|----------------|-------------|------------------------|
| | | | | | | |
| Build-in Controller | Gripping Force Adjustable | Position Adjustable | Speed Adjustable | Drop Detection | Plug & Play | Self-locking Mechanism |



Static Vertical Allowable Load

Fz 600 N

Allowable Loading Moment

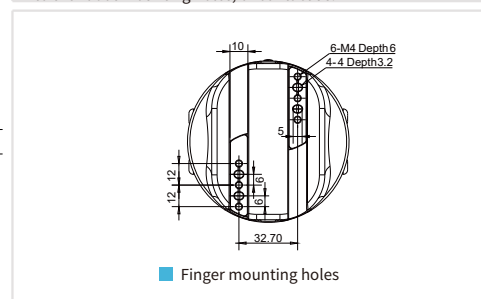
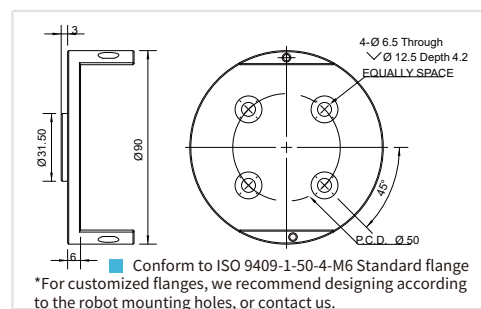
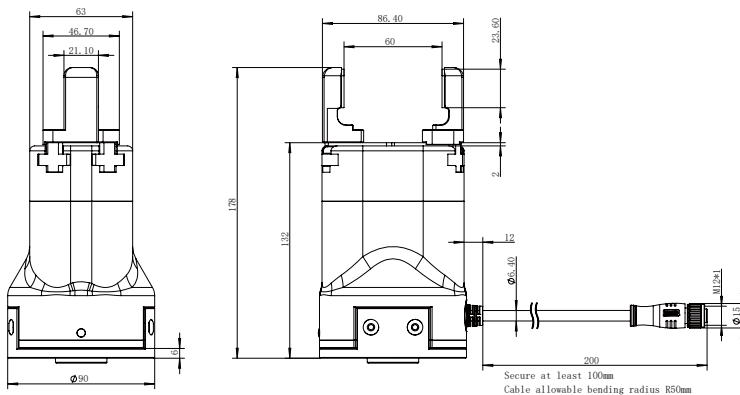
Mx 15 N·m

My 15 N·m

Mz 15 N·m

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings



AG Series

Electric Adaptive Gripper



AG-160-95
AG-105-145
DH-3

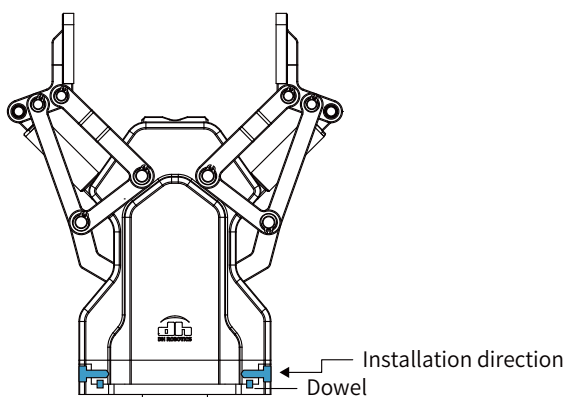


The AG series is a linkage-type adaptive electric gripper which is independently developed by DH-Robotics. With Plug& Play software many and exquisite structural design , AG series is a perfect solution to be applied with collabrative robots to grip work-pieces with different shapes in different industries.



Installation

1. Bottom installation : use bottom screw holes for installation



Product Features

● Envelope Adaptive Capture

The gripper linkage mechanism supports envelope adaptive grasping, which is more stable to grip round, spherical or special-shaped objects.

● Plug & Play

It supports plug & play with most collaborative robot brands on the market which is easier to control and program.

● Long Stroke

The biggest stroke of the AG series is up to 145 mm. One gripper can meet the grasping needs of objects of different sizes with good compatibility.

Application

Cooperate with collaborative robot or industrial robot to complete material handling, loading and unloading, assembly, testing, sorting and other tasks in auto parts, automation equipment, new energy and other industries.

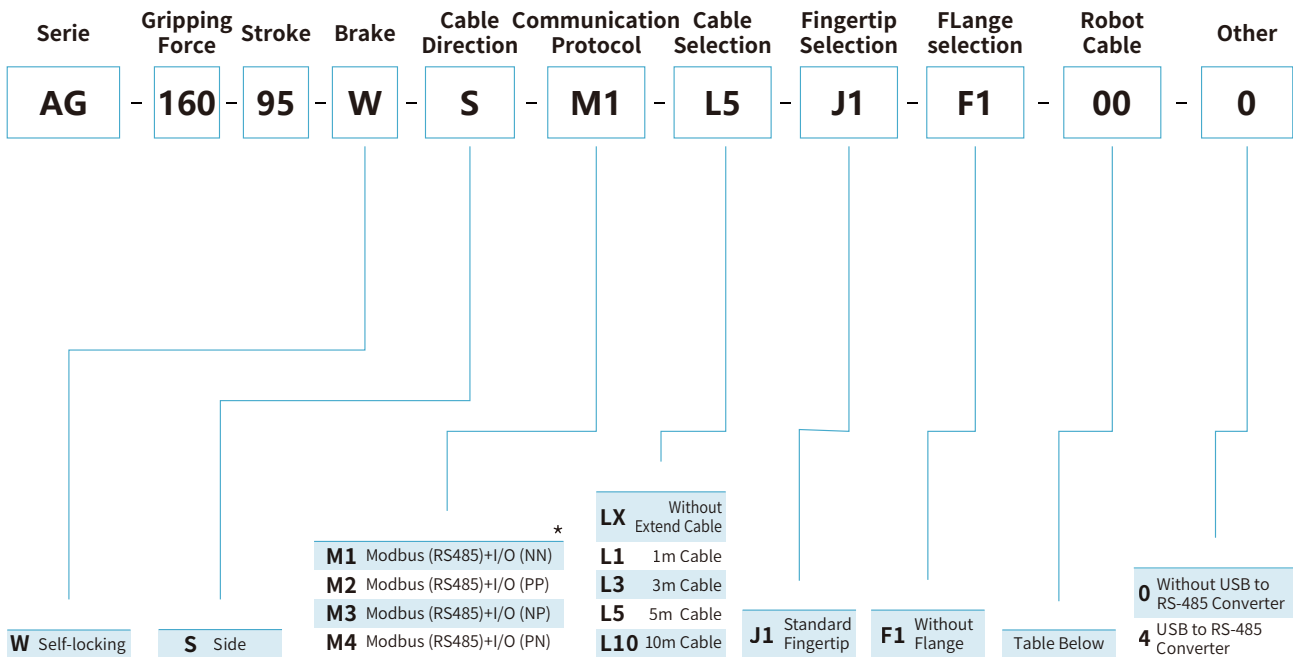


AG-160-95

Electric Adaptive Gripper



Selection Method



* Note:

I/O(NN): NPN/NPN
 I/O(PP): PNP/PNP
 I/O(NP): NPN/PNP
 I/O(PN): PNP/NPN

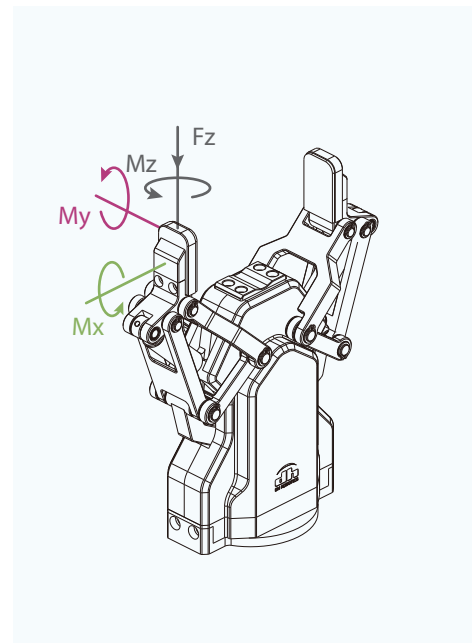
| | | | | | | | | | | | |
|-------------------------------|--------------------------|----------------------|---------------------|--------------------|-------------------|-----------------------------|--------------------|--------------------|---------------------|----------------------|--------------------|
| 00 Without Robot Cable | 01 Elite CS UR CB | SIASUN Hanwha A UR E | DOBOT CR DOBOT Nova | 02 AUBO | 04 JAKA | 06 ROKAE SR ROKAE ER | 09 Doosan A | 11 Elite EC | 13 Neuromeka | 15 Hanwha HCR | |
| | | | | 03 ELEPHANT | 05 TECHMAN | 07 DOBOT MG400 | 10 Doosan M | 12 Han's | 14 FAIRINO | 16 UF x Arm | 17 ROKAE CR |

Parameters

| Product Parameter | |
|--|------------------------------|
| Gripping force (per jaw) | 45~160 N |
| Stroke | 95 mm |
| Recommended workpiece weight ^{*①} | 3 kg |
| Opening/closing time | 0.9 s/0.9 s |
| Repeat accuracy (position) | ± 0.03 mm |
| Noise emission | < 60 dB |
| Weight | 1 kg |
| Driving method | Screw drive + Linkage system |
| Size | 184.6 mm x 162.3 mm x 67 mm |

| Working Environment | |
|-------------------------|--|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT ^{★②} |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.8 A |
| Peak current | 1.5 A |
| IP class | IP 54 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | | |
|---|---|---|--|--|---|--|
| <input checked="" type="checkbox"/> Build-in Controller | <input checked="" type="checkbox"/> Gripping Force Adjustable | <input checked="" type="checkbox"/> Position Adjustable | <input checked="" type="checkbox"/> Speed Adjustable | <input checked="" type="checkbox"/> Drop Detection | <input checked="" type="checkbox"/> Plug & Play | <input checked="" type="checkbox"/> Self-locking Mechanism |
|---|---|---|--|--|---|--|



Static Vertical Allowable Load

Fz 300 N

Allowable Loading Moment

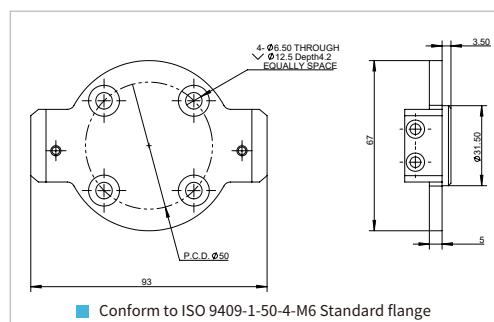
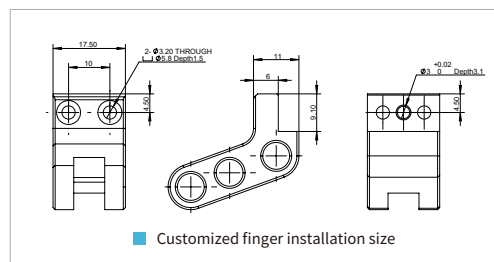
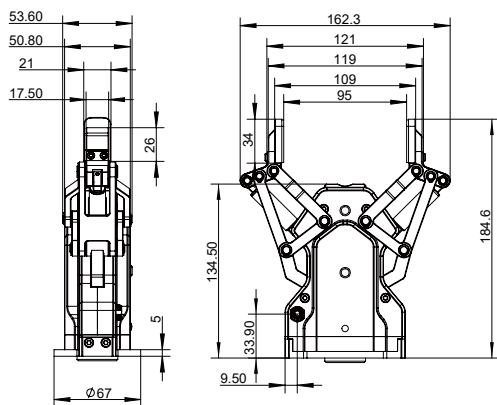
Mx 4.75 N · m

My 4.75 N · m

Mz 4.75 N · m

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

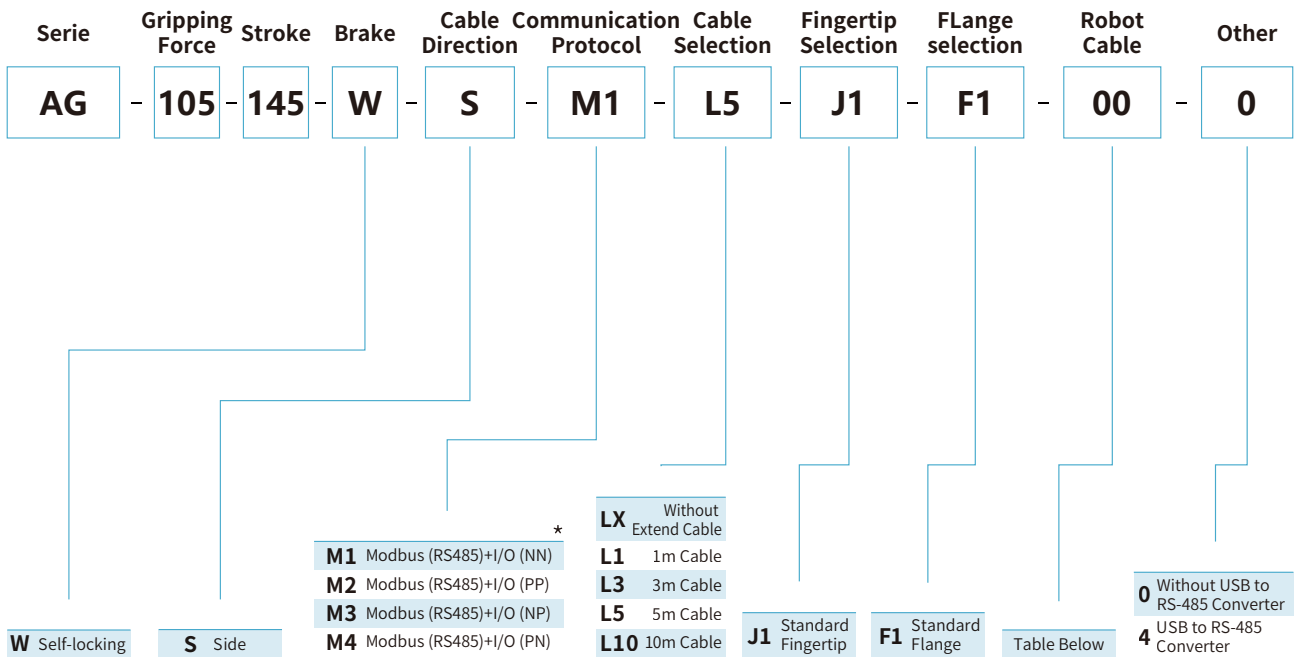


AG-105-145

Electric Adaptive Gripper



Selection Method



* Note:








I/O(NN): NPN/NPN
 I/O(PP): PNP/PNP
 I/O(NP): NPN/PNP
 I/O(PN): PNP/NPN

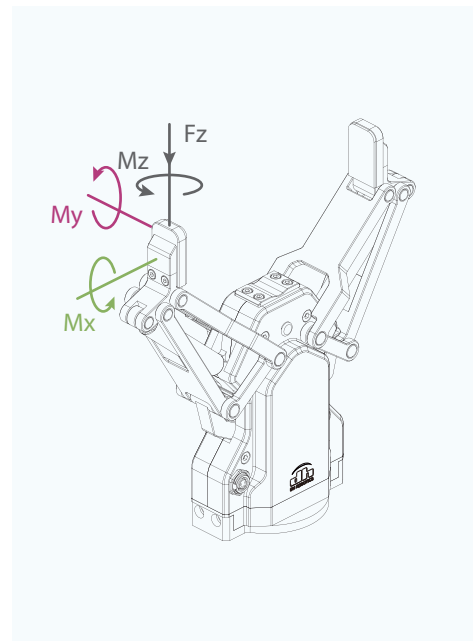
| | | | | | | | | | | | |
|-------------------------------|--------------------------|----------------------|---------------------|--------------------|-------------------|-----------------------------|--------------------|--------------------|---------------------|----------------------|--------------------|
| 00 Without Robot Cable | 01 Elite CS UR CB | SIASUN Hanwha A UR E | DOBOT CR DOBOT Nova | 02 AUBO | 04 JAKA | 06 ROKAE SR ROKAE ER | 09 Doosan A | 11 Elite EC | 13 Neuromeka | 15 Hanwha HCR | |
| | | | | 03 ELEPHANT | 05 TECHMAN | 07 DOBOT MG400 | 10 Doosan M | 12 Han's | 14 FAIRINO | 16 UF x Arm | 17 ROKAE CR |

Parameters

| Product Parameter | |
|--|------------------------------|
| Gripping force (per jaw) | 35~105 N |
| Stroke | 145 mm |
| Recommended workpiece weight ^{*①} | 2 kg |
| Opening/closing time | 0.9 s/0.9 s |
| Repeat accuracy (position) | ± 0.03 mm |
| Noise emission | < 60 dB |
| Weight | 1.3 kg |
| Driving method | Screw drive + Linkage system |
| Size | 203.9 mm x 212.3 mm x 67 mm |

| Working Environment | |
|-------------------------|---|
| Communication interface | 标配: Modbus RTU (RS485)、Digital I/O 选配: TCP/IP、USB2.0、CAN2.0A、PROFINET、EtherCAT ^{*②} |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.8 A |
| Peak current | 1.5 A |
| IP class | IP 54 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | | |
|---|---|---|--|--|---|--|
|  Build-in Controller |  Gripping Force Adjustable |  Position Adjustable |  Speed Adjustable |  Drop Detection |  Plug & Play |  Self-locking Mechanism |
|---|---|---|--|--|---|--|



Static Vertical Allowable Load

Fz 300 N

Allowable Loading Moment

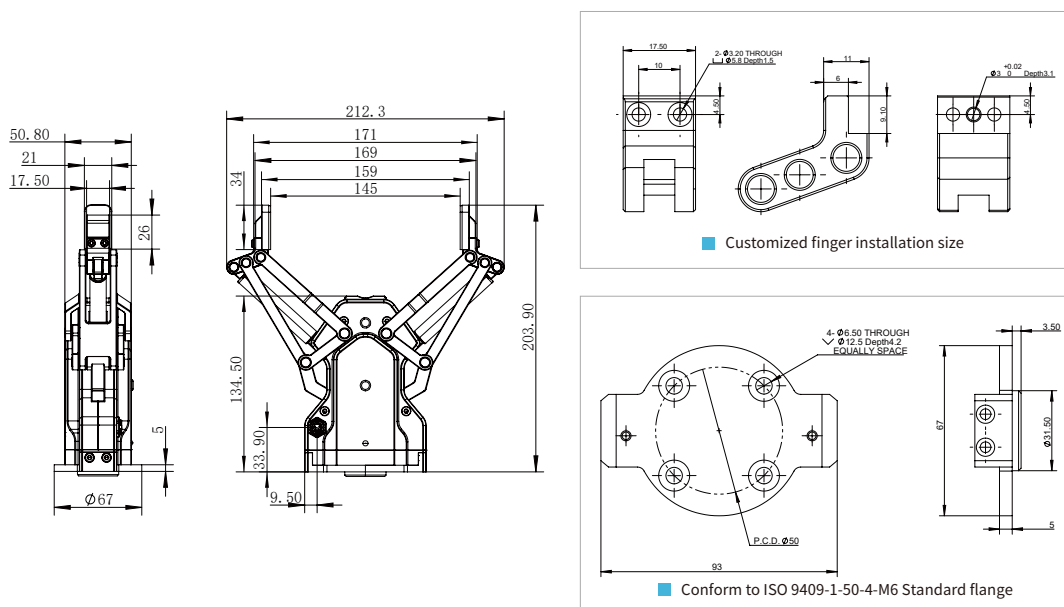
Mx 1.95 N·m

My 1.95 N·m

Mz 1.95 N·m

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

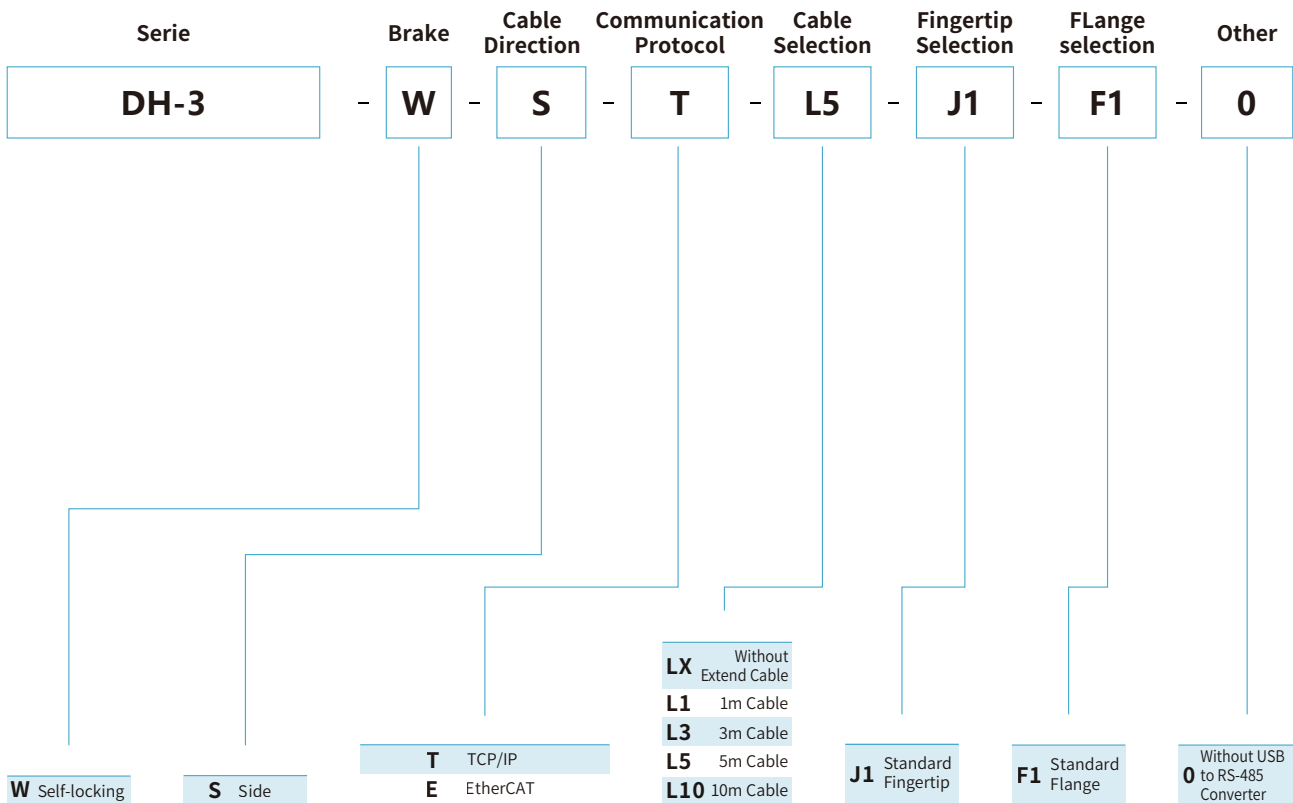


DH-3

Electric Adaptive Gripper



Selection Method



Parameters

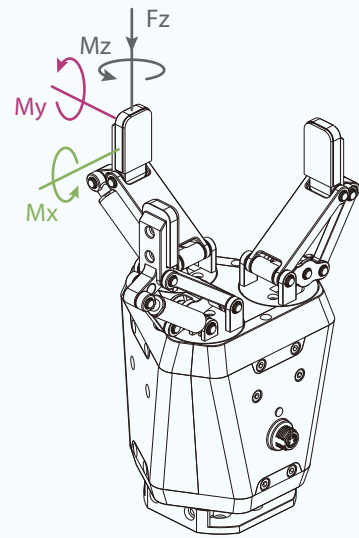
Product Parameter

| | |
|--|--|
| Gripping force (per jaw) | 10~65 N |
| Stroke | 106 mm (parallel) 122 mm (centric) |
| Recommended workpiece weight ^{*①} | 1.8 kg |
| Opening/closing time | 0.7 s/0.7 s |
| Repeat accuracy (position) | ± 0.03 mm |
| Noise emission | < 60 dB |
| Weight | 1.68 kg |
| Driving method | Screw nut+ gear drive + linkage mechanism |
| Size | 213.5 mm x 170 mm x 118 mm |

Working Environment

| | |
|-------------------------|---|
| Communication interface | Standard: TCP/IP, USB2.0, CAN2.0A Optional: EtherCAT ^{*②} |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.5 A |
| Peak current | 1 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | | |
|---|---|---|--|--|---|--|
|  Build-in Controller |  Gripping Force Adjustable |  Position Adjustable |  Speed Adjustable |  Drop Detection |  Plug & Play |  Self-locking Mechanism |
|---|---|---|--|--|---|--|



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

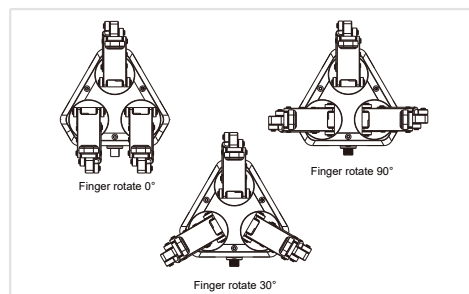
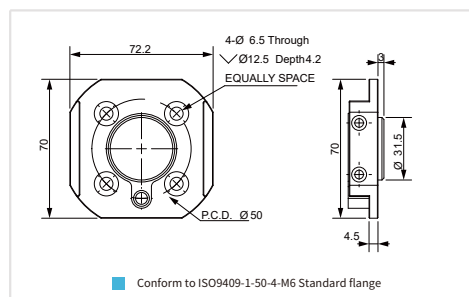
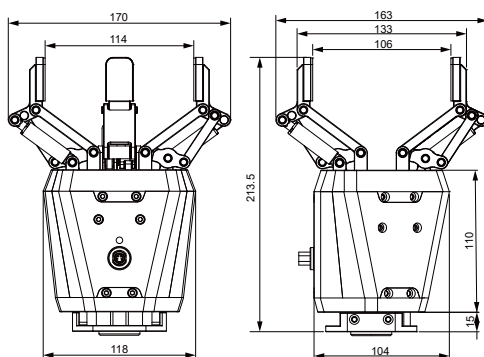
Mx 2.5 N·m

My 2 N·m

Mz 3 N·m

^{*①} 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.
^{*②} Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings



CG Series

Electric Centric Gripper

CGE-10-10

CGI-100-170

CGC-80-10

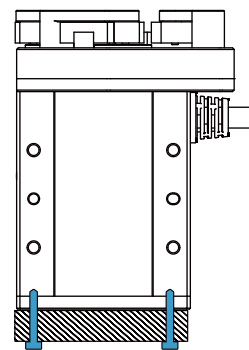
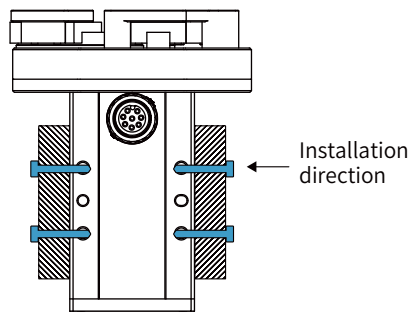
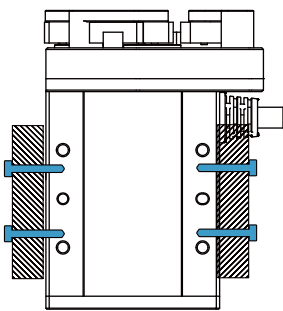


The CG series is a three-finger centric gripper independently developed by DH-Robotics. The three-finger gripping method can better cope with the grasping task of cylindrical workpieces. The CG series is available in a variety of models for a variety of scenarios, stroke and end devices.



Installation

1. Front and rear installation: use front and rear screw holes for installation
2. Side installation: use side screw holes for installation
3. Bottom installation : use bottom screw holes for installation



Product Features

● High Performance

Realize high-precision centering and grasping, the process structure meets the requirements of high rigidity, and the energy density exceeds that of similar products.

● Long Lifetime

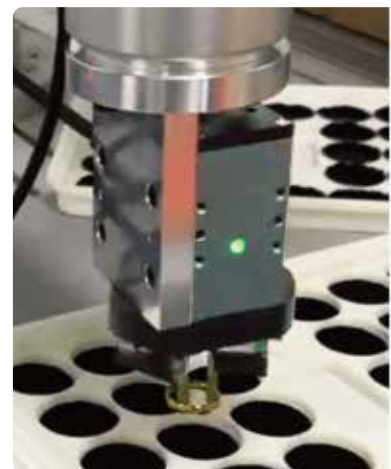
Continuous and stable work above 10 millions times without maintenance.

● Overload Protection

The high-performance servo motor can provide instantaneous overload protection.

Application

Accurate and stable grasping of cylindrical workpieces in the fields of auto parts, automation equipment, precision machining and assembly, etc.

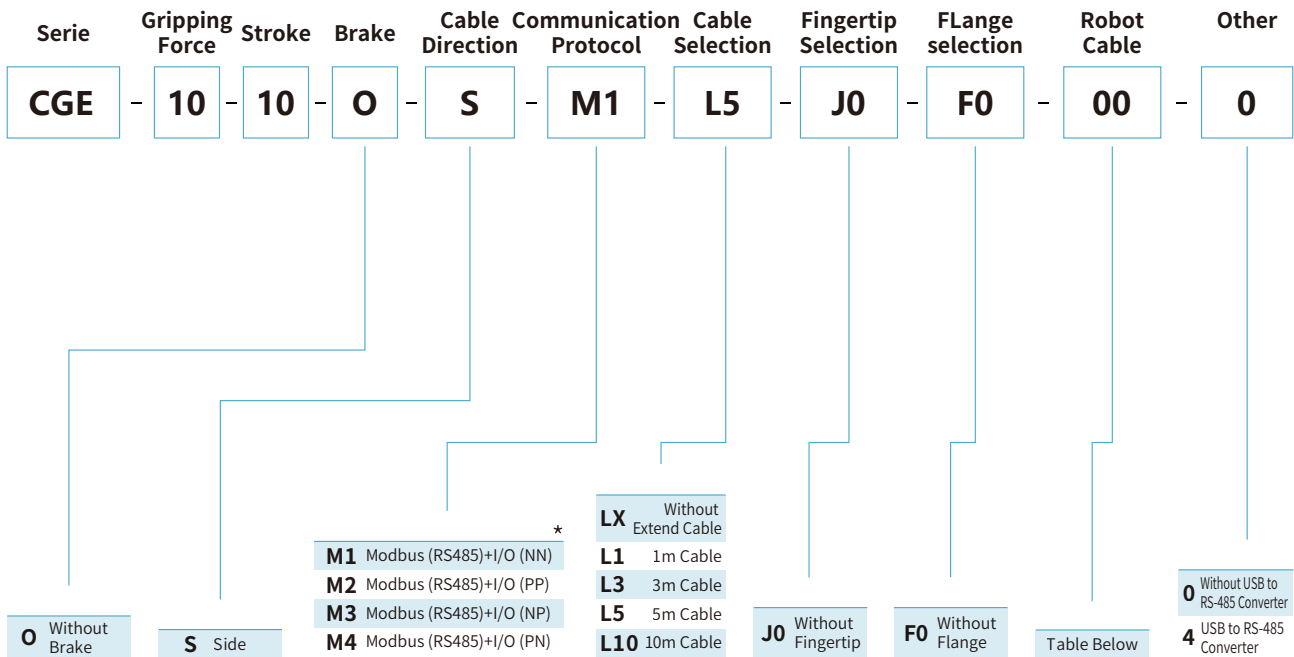


CGE-10-10

Electric Centric Gripper



Selection Method



* Note:

I/O(NN): NPN/NPN
I/O(PP): PNP/PNP
I/O(NP): NPN/PNP
I/O(PN): PNP/NPN

| | | | | | | | | | | | |
|-------------------------------|--------------------------|----------------------|---------------------|--------------------|-------------------|-----------------------------|--------------------|--------------------|---------------------|----------------------|--------------------|
| 00 Without Robot Cable | 01 Elite CS UR CB | SIASUN Hanwha A UR E | DOBOT CR DOBOT Nova | 02 AUBO | 04 JAKA | 06 ROKAE SR ROKAE ER | 09 Doosan A | 11 Elite EC | 13 Neuromeka | 15 Hanwha HCR | |
| | | | | 03 ELEPHANT | 05 TECHMAN | 07 DOBOT MG400 | 10 Doosan M | 12 Han's | 14 FAIRINO | 16 UF x Arm | 17 ROKAE CR |

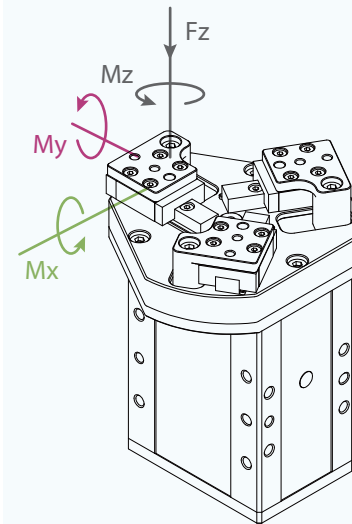
Parameters

Product Parameter

| | |
|--|--|
| Gripping force (per jaw) | 3~10 N |
| Stroke | 10 mm |
| Recommended workpiece weight ^{*①} | 0.1 kg |
| Opening/closing time | 0.3 s/0.3 s |
| Repeat accuracy (position) | ± 0.03 mm |
| Noise emission | < 50 dB |
| Weight | 0.43 kg |
| Driving method | Precise planetary gear reducer + Rack and pinion |
| Size | 94 mm x 53.5 mm x 38 mm |

Working Environment

| | |
|-------------------------|--|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT ^{*②} |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.3 A |
| Peak current | 0.6 A |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

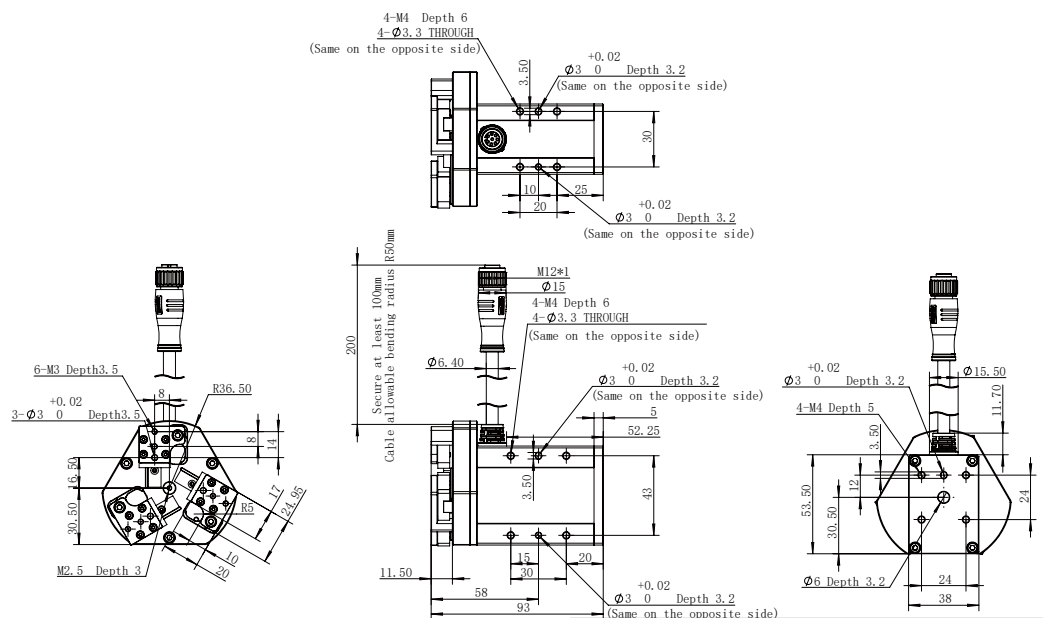
Mx 0.62 N·m

My 0.62 N·m

Mz 0.62 N·m

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

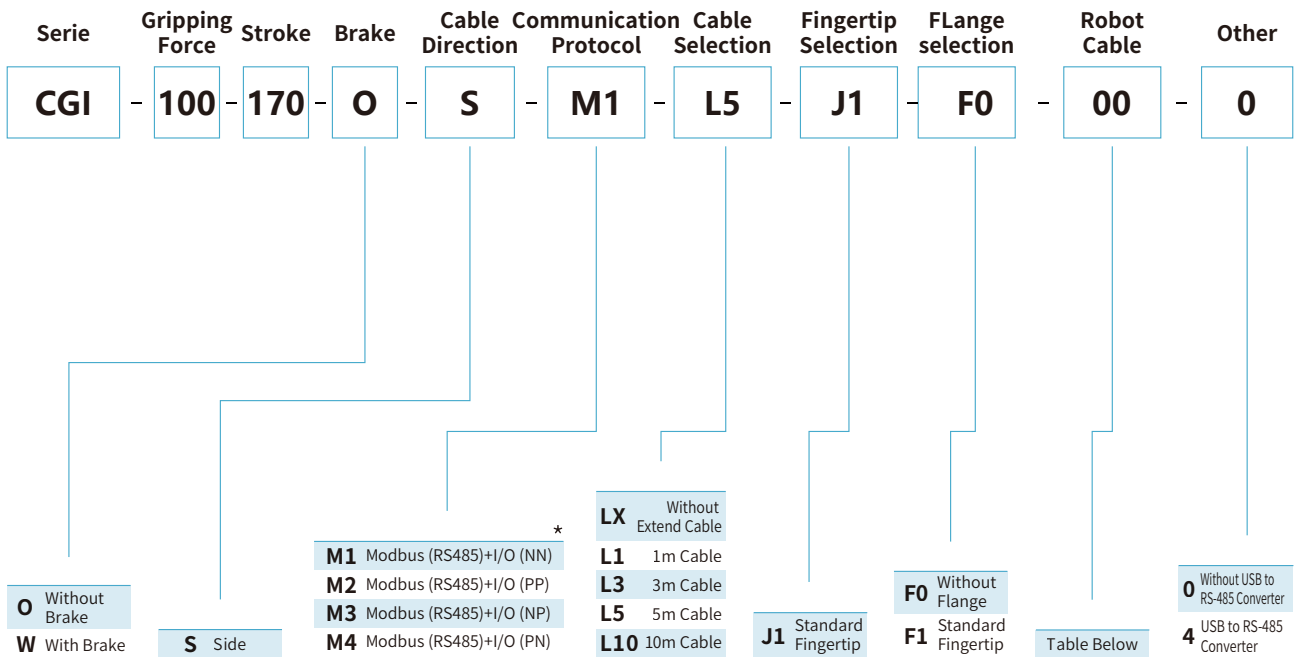


CGI-100-170

Electric Centric Gripper



Selection Method



* Note:

I/O(NN): NPN/NPN
I/O(PP): PNP/PNP
I/O(NP): NPN/PNP
I/O(PN): PNP/NPN

| | | | | | | | | | | | |
|-------------------------------|--------------------------|----------------------|---------------------|--------------------|-------------------|-----------------------------|--------------------|--------------------|---------------------|----------------------|--------------------|
| 00 Without Robot Cable | 01 Elite CS UR CB | SIASUN Hanwha A UR E | DOBOT CR DOBOT Nova | 02 AUBO | 04 JAKA | 06 ROKAE SR ROKAE ER | 09 Doosan A | 11 Elite EC | 13 Neuromeka | 15 Hanwha HCR | |
| | | | | 03 ELEPHANT | 05 TECHMAN | 07 DOBOT MG400 | 10 Doosan M | 12 Han's | 14 FAIRINO | 16 UF x Arm | 17 ROKAE CR |

Parameters

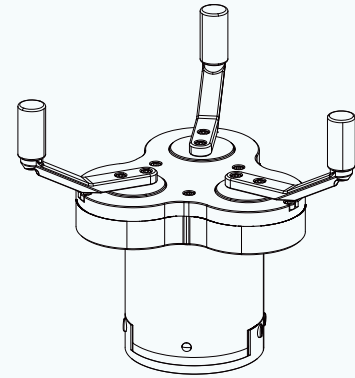
Product Parameter

| | |
|---|---|
| Gripping force (per jaw) | 30~100 N |
| Recommended workpiece diameter (inward) | Φ40~Φ170 mm |
| Recommended workpiece weight *① | 1.5 kg |
| Opening/closing time | 1.35 s |
| Repeat accuracy (position) | ± 0.03 mm |
| Noise emission | < 50 dB |
| Weight | 1.5 kg |
| Driving method | Precise planetary gears + Rack and pinion |
| Size | 158.4 mm x 124.35 mm x 116 mm (without brake/with brake, same size) |

Working Environment

| | |
|-------------------------|---|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT *② |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.4 A |
| Peak current | 1 A |
| IP class | IP 40 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

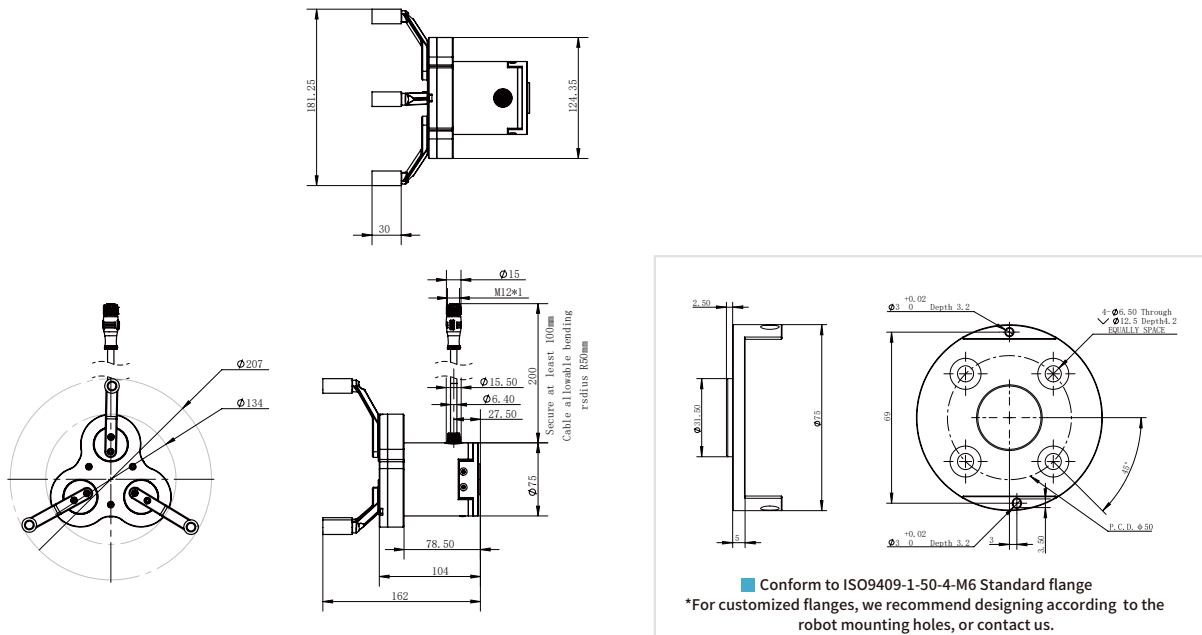
| | | | | | |
|--|--|--|---|---|---|
|  Build-in Controller |  Gripping Force Adjustable |  Position Adjustable |  Speed Adjustable |  Drop Detection |  Self-locking Mechanism |
|--|--|--|---|---|---|



This type of gripper is recommended to use the standard finger.
If you need to replace it in the application, please contact us for confirmation.

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings

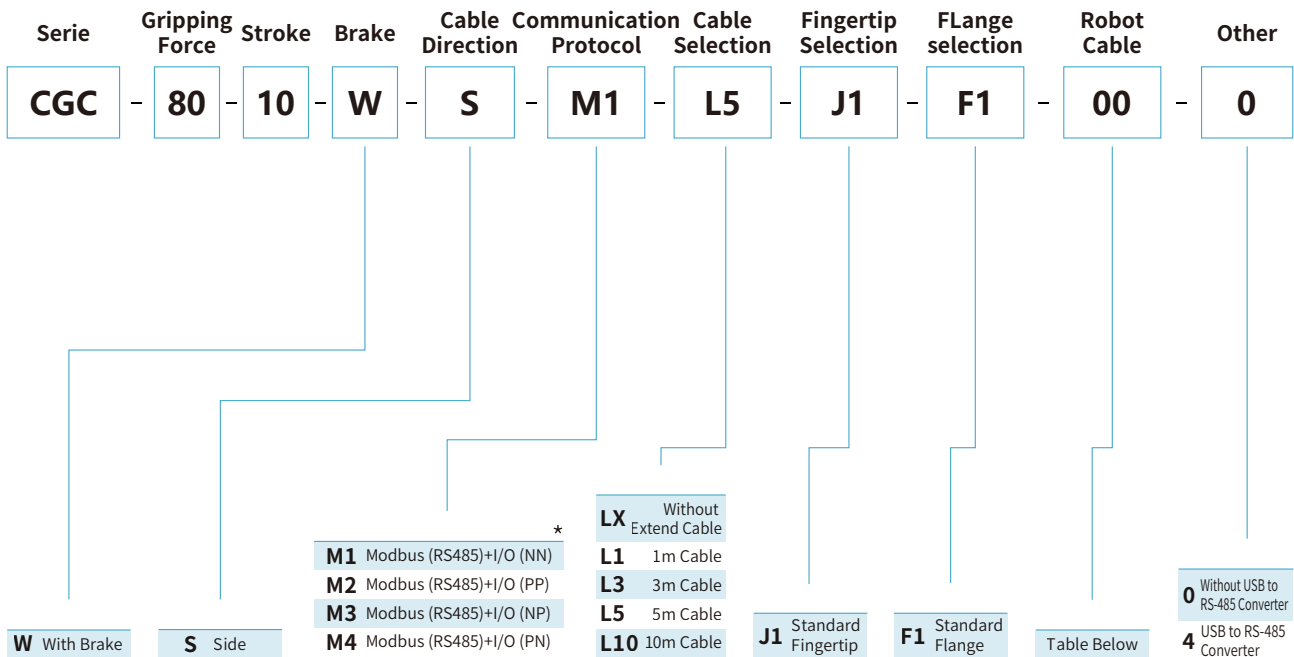


CGC-80-10

Electric Collaborative Centric Gripper



Selection Method



* Note:
 I/O(NN): NPN/NPN
 I/O(PP): PNP/PNP
 I/O(NP): NPN/PNP
 I/O(PN): PNP/NPN

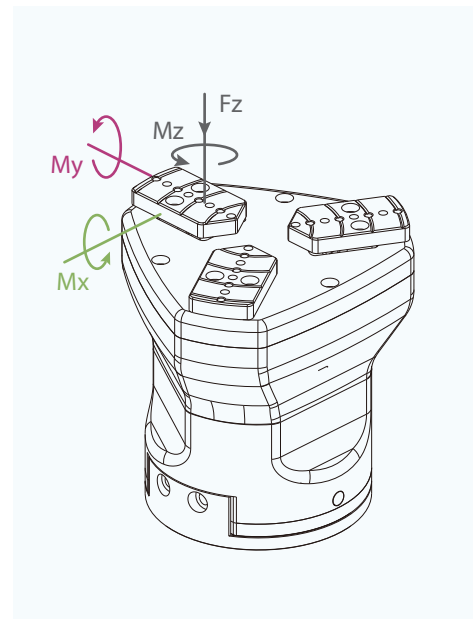
| | | | | | | | |
|-------------------------------|--------------------|-------------------|--------------------------------|--------------------|--------------------|---------------------|----------------------|
| 00 Without Robot Cable | 02 AUBO | 04 JAKA | 06 ROKAE SR ROKAE ER | 09 Doosan A | 11 Elite EC | 13 Neuromeka | 15 Hanwha HCR |
| | 03 ELEPHANT | 05 TECHMAN | 07 DOBOT MG400 | 10 Doosan M | 12 Han's | 14 FAIRINO | 16 UF x Arm |

Parameters

| Product Parameter | |
|--|--|
| Gripping force (per jaw) | 20~80 N |
| Single jaw | 10 mm |
| Recommended workpiece weight ^{*①} | 1.5 kg |
| Opening/closing time | 0.2 s/0.2 s |
| Repeat accuracy (position) | ± 0.03 mm |
| Noise emission | < 50 dB |
| Weight | 1.5 kg |
| Driving method | Precise planetary gear reducer + Rack and pinion |
| Size | 141 mm x 103 mm x 75 mm |

| Working Environment | |
|-------------------------|--|
| Communication interface | Standard: Modbus RTU (RS485), Digital I/O Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT ^{*②} |
| Rated voltage | 24 V DC ± 10% |
| Rated current | 0.3 A |
| Peak current | 1 A |
| IP class | IP 67 |
| Recommended environment | 0~40°C, under 85% RH |
| Certification | CE, FCC, RoHS |

| | | | | | | |
|---------------------|---------------------------|---------------------|------------------|----------------|-------------|------------------------|
| | | | | | | |
| Build-in Controller | Gripping Force Adjustable | Position Adjustable | Speed Adjustable | Drop Detection | Plug & Play | Self-locking Mechanism |



Static Vertical Allowable Load

Fz 200 N

Allowable Loading Moment

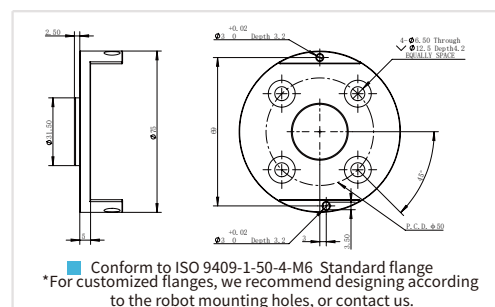
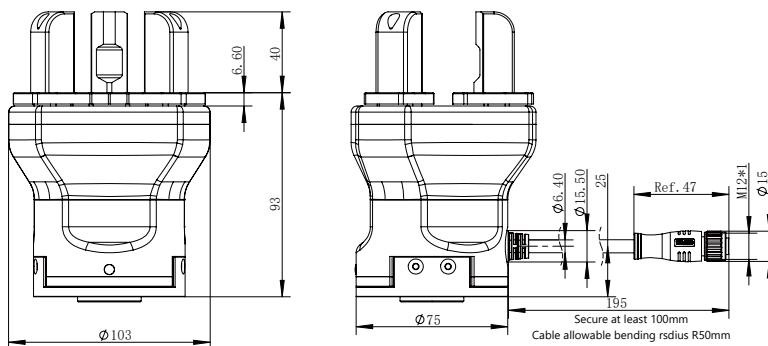
Mx 2.5 N·m

My 2 N·m

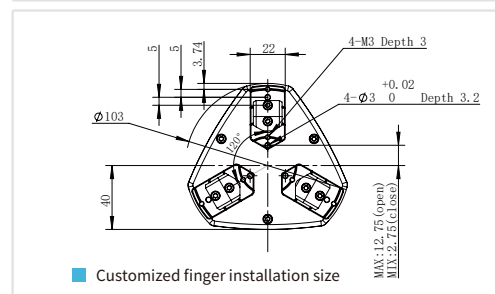
Mz 3 N·m

*① 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.
*② Use optional communication, need external communication conversion box, please consult the sales staff for details.

Technical Drawings



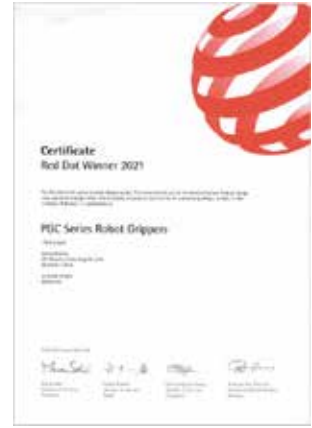
■ Conform to ISO 9409-1-50-4-M6 Standard flange
*For customized flanges, we recommend designing according to the robot mounting holes, or contact us.



■ Customized finger installation size

Honors and Certificates

– Some of Our Certificates



1

2

3

4



5

6

7

1. CE Certificate
2. IP Class Certificate
3. RoHS Certificate
4. EMC Certificate
5. FCC Certificate
6. Low Temperature Test Report
7. Intellectual Property Management System Certification

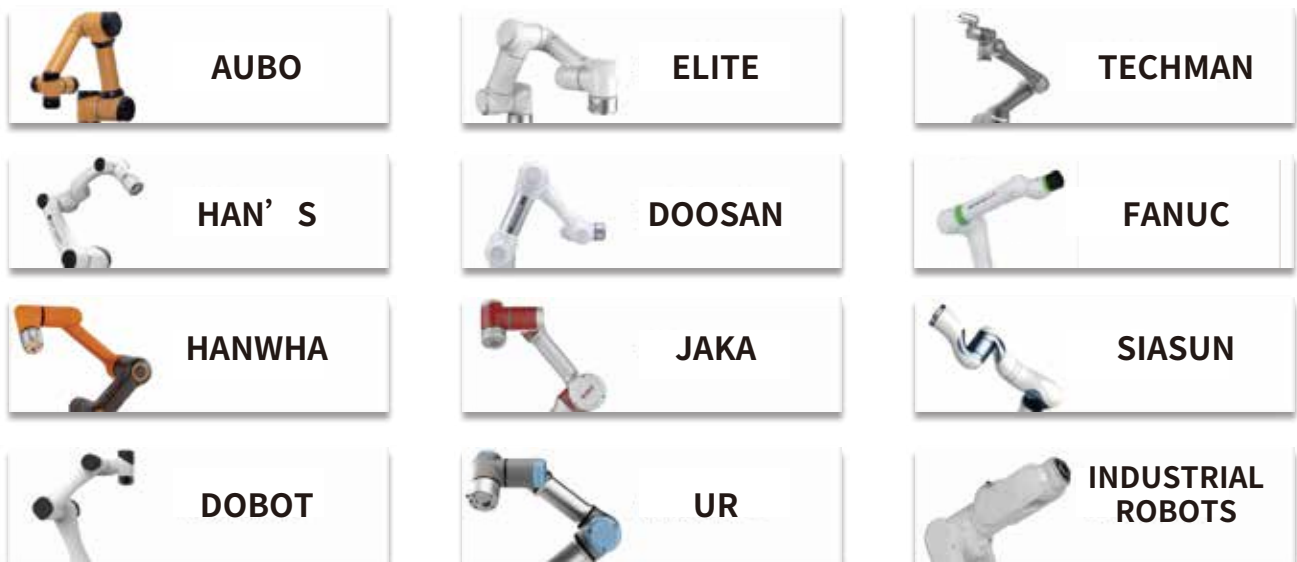
Our Customers

More than 800 customers around the world are using DH-Robotics products
The number of customers continues to grow rapidly...



Our Eco-Partners

DH-Robotics is a high-quality partner of global collaborative robots



DH-ROBOTICS

is committed to provide first-class
core components of precision motion control.



Version Change Log

| Revision Date | Released Version | Change Log |
|---------------|------------------|---|
| 2024.03 | CN.2403 | <ul style="list-style-type: none">· Update CGI-100-17 with a new open/close time of 1.35s.· Remove cable configuration option LX from PGSE-15-7.· Update the short line sequence number of the Lushi robot CR series to 17. |

Due to continuous product upgrades, content changes may occur without prior notice.
All rights reserved © DH-Robotics Technology Co., Ltd.



DH-Robotics Technology Co.,Ltd.

Linked  |  **YouTube** [Search DH-Robotics](#)

en.dh-robotics.com
info@dh-robotics.com

14th Floor, Building A4, Nanshan Intelligence Park, No. 1001 Xueyuan Avenue,
Taoyuan Street, Nanshan District, Shenzhen City, Guangdong Province, China