

Sealed 180° Angular Gripper - Design W10 -

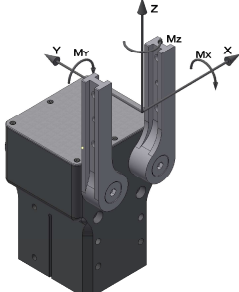
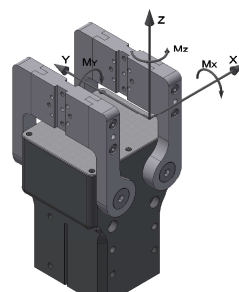
Characteristic:

- High Gripping Force
- Short Cycle Time
- Completely capsuled mechanics
- User defines installation position
- Maintenance free up to 10 million movements
- Compact design
- Multiple position monitoring through proximity switch, optional
- built-in end position damping when opening

By using the given torque M [Nm], the necessary air pressure P can be computed with the following formula in position where fingers are closed:

$$0,5 \text{ bar} \leq P_{\text{erf.}} = \frac{M}{76,7 \text{ Nm}} \text{ bar} \leq 6 \text{ bar}$$

Technical Data

Type		 W110	 W210
Drive		pneumatic	
max. Gripping Force (at 6 bar) *		2500 N	3000 N
max. Torque (at 6 bar) **		460 Nm	
Operating Air Pressure		1 to 6 bar	
Cycle Time	Open	1 s	
	Close	1 s	
Repeat Accuracy		0,1 mm	
Energy Consumption per cycle		2,4 liter	
Operating Temperature		-30 to +80°C	
Mass		10 kg	11,5 kg
Loading Capacity* per Finger with Gripping Mass and Acceleration	$Mx_{\text{max.}}$	150 Nm	250 Nm
	$My_{\text{max.}}$ (Gripping)	435 Nm	435 Nm
	$Fz_{\text{max.}}$	25,000 N	50,000 N
	$Mz_{\text{max.}}$	50 Nm	150 Nm

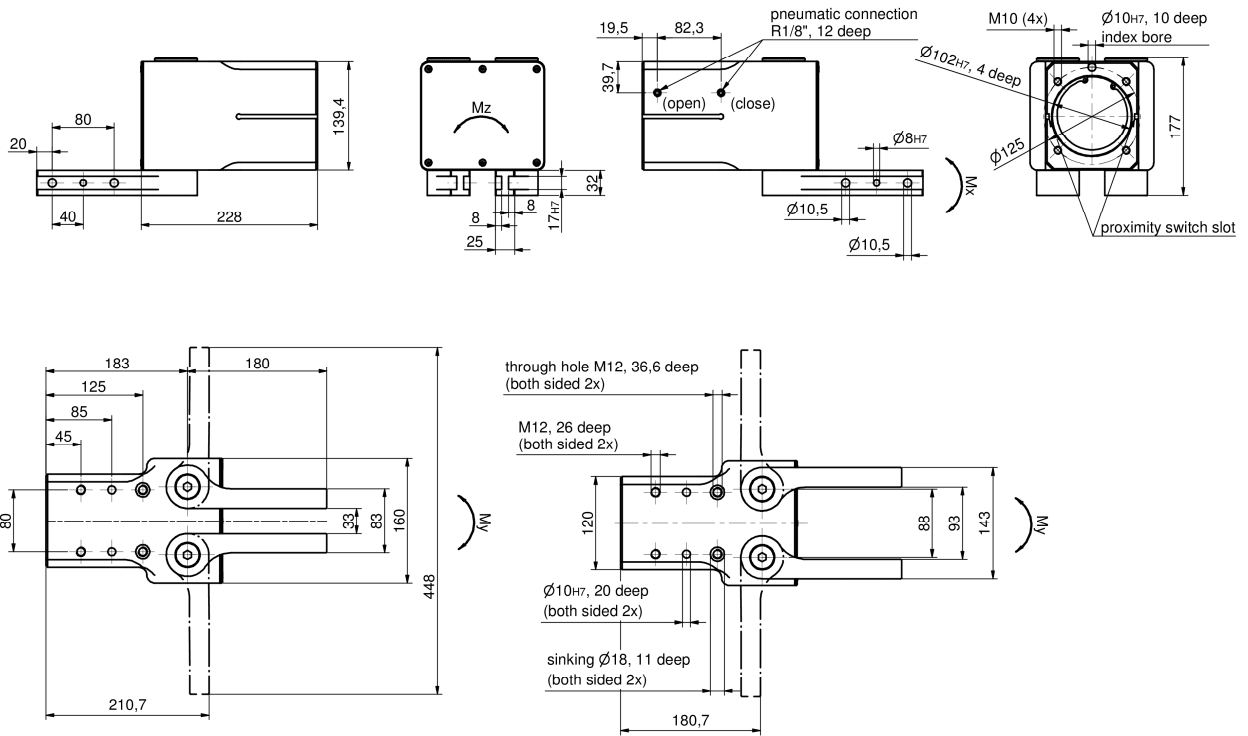
* At fingers outer edge when standard fingers' (180mm / 150mm) position closed

** Gripping force per finger is half of this torque divided by length of finger

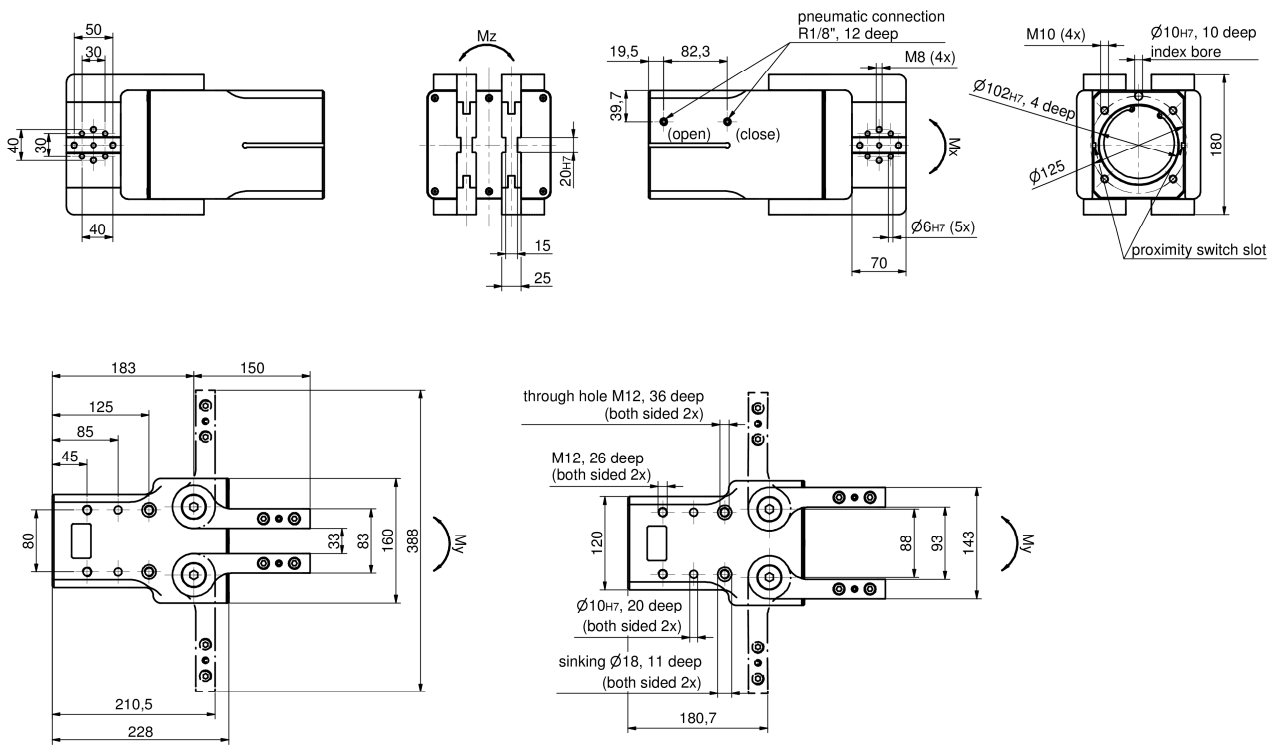


W10

Type W110 (Single Finger)



Type W210 (Double Finger)



address:
GMG – Gesellschaft fuer modulare
Greifersysteme mbH
Coesterweg 45c
D-59494 Soest
Germany

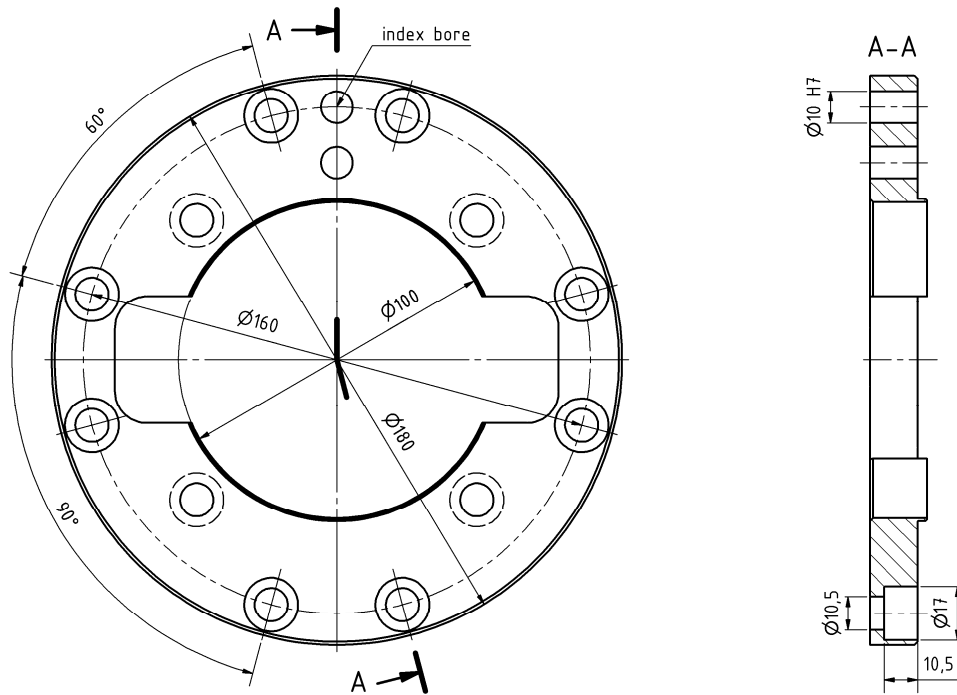
phone:
+49 (0)2921 - 4062
fax:
+49 (0)2921 - 4042

e-mail:
info@gmg-system.com
homepage:
http://www.gmg-system.com



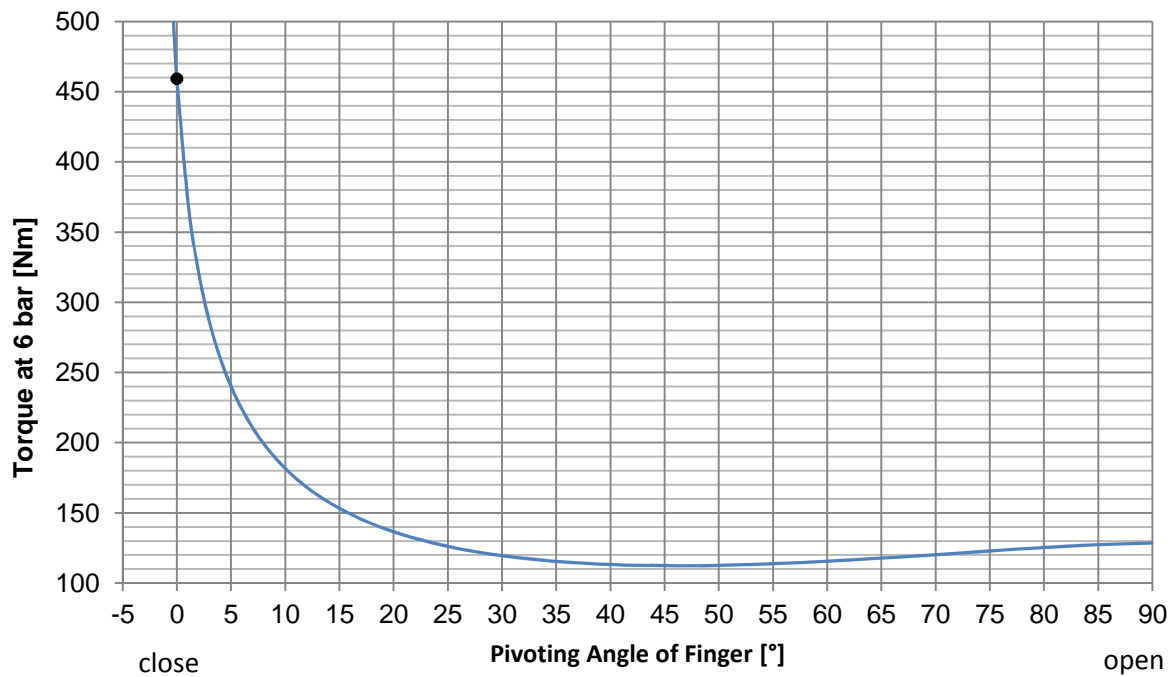
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Flange



Used to mount the gripper to a robot

Diagram



Torque curve also available in mirrored version upon request.



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e-mail:
info@gmg-system.com
homepage:
<http://www.gmg-system.com>



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Finger Position

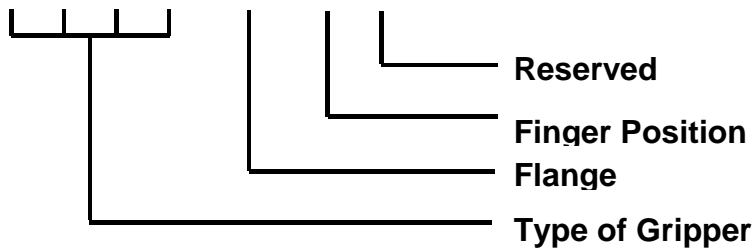
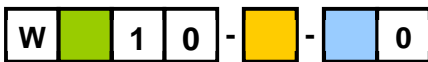


Inside Fingers



Outside Fingers

Order Number



Type of Gripper	
Style	Ident.
Single Finger W110	1
Double Finger W 210	2

Flange	
Style	Ident.
With Flange	N
Without Flange	O

Finger Position	
Style	Ident.
Inside Fingers	I
Outside Fingers	A



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 D-59494 Soest
 Germany

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 fax:
 +49 (0)2921 - 4042

e-mail:
 info@gmg-system.com
 homepage:
 http://www.gmg-system.com