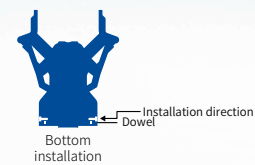


Electric Adaptive Gripper



Serie	Gripping Force	Stroke	Brake	Cable Direction	Communication Protocol	Cable Selection	Fingertip Selection	Flange Selection	Robot Cable
AG	160	95	W	S	M1	L5	J1	F1	00

[illegible]

①:															
I/O(NN): NPN/NPN	00 Without Robot Cable	01 Elite CS UR CB	SIASUN	DOBOT CR	02 AUBO	04 JAKA	06 ROKAE SR ROKAE ER	09 Doosan A	11 Elite EC	13 Neuromeka	15 Hanwha HCR				
I/O(PP): PNP/PNP			Hanwha A	DOBOT Nova											
I/O(NP): NPN/PNP			UR E												
I/O(PP): PNP/PNP					03 ELEPHANT	05 TECHMAN	07 DOBOT MG400	10 Doosan M	12 Han's	14 FAIRINO	16 UF x Arm	17 ROKAE CR			

The Modbus RTU (RS485) to USB module will no longer be provided for free. Please place a separate order if needed.

A 3D line drawing of a robotic gripper. A coordinate system is overlaid on the gripper: a vertical arrow labeled F_z points downwards, a curved arrow labeled M_z indicates rotation around the vertical axis, a curved arrow labeled M_y indicates rotation around the horizontal axis, and a curved arrow labeled M_x indicates rotation around the gripper's longitudinal axis.

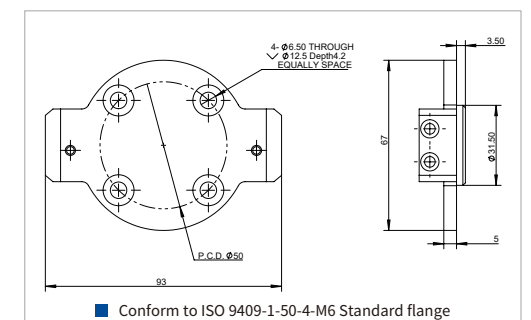
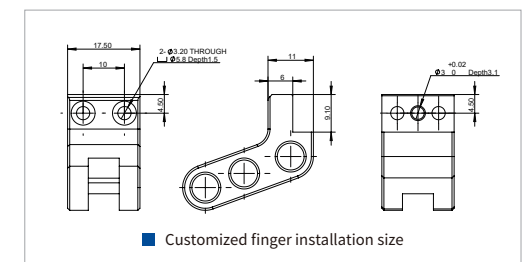
F_z	300 N
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Mx	4.75 N · m
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My 4.75 N · m

Mz 4.75 N · m

*④ When selecting the power supply, please select according to the peak current. If the current is lower than the parameter, it will cause the product can not work normally.



Gripping force (per jaw)	45~160 N
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Gripping force (per jaw)	45~160 N
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Recommended workpiece weight *②	3 kg
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Stroke 95 mm

Full stroke opening/closing time	0.9 s/0.9 s
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Repeat accuracy (position) ± 0.03 mm

Weight	1 kg
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Size	184.6 mm x 162.3 mm x 67 mm
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Noise emission < 60 dB

Driving method	Screw drive + Linkage system
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Communication interface	Standard: Modbus RTU (RS485)、Digital I/O(2 inputs 2 outputs) Optional: TCP/IP、USB2.0、CAN2.0A、PROFINET、EtherCAT *③
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Rated voltage	24 V DC $\pm$ 10%
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Current	0.8 A(Rated)/ 1.5 A(Peak) ^{*④}
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Rated power	19.2 W
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IP class	IP 54
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Recommended environment	0~40°C, under 85% RH
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Certification	CE, FCC, RoHS
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