CGC-80-10

Electric Collaborative Centric Gripper

Selection Method

Serie	Gripping Force	Stroke	Brake	Cable Direction	Communication Protocol	Cable Selection	Fingertip Selection	Flange Selection	Robot Cable
CGC	80	10	W	S	M1	L5	J1	F1	00

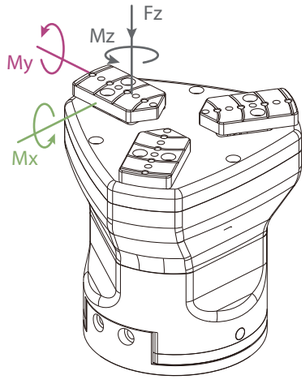
W	With Brake
S	Side
M1	Modbus (RS485)+I/O (NN)
M2	Modbus (RS485)+I/O (PP)
M3	Modbus (RS485)+I/O (NP)
M4	Modbus (RS485)+I/O (PN)
LX	Without Extend Cable
L1	1m Cable
L3	3m Cable
L5	5m Cable
L10	10m Cable
J1	Standard Fingertip
F1	Standard Flange
Table Below	

*①:
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

*⑤ It is recommended that no more than 4units of DH-Robotics products be accessed on a single 485 bus, otherwise 485 communication anomalies may occur.
If you need to access more than 4 devices, it is recommended to contact the sales staff for product adjustment.
The Modbus RTU (RS485) to USB module will no longer be provided for free. Please place a separate order if needed.

TECHNICAL SPECIFICATIONS



Static Vertical Allowable Load	
Fz	200 N

Allowable Loading Moment	
Mx	2.5 N·m
My	2 N·m
Mz	3 N·m

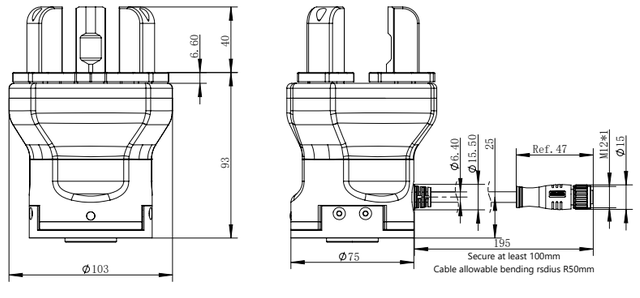
*② The recommended load calculation is based on pure friction force gripping, with a friction coefficient of 0.2 and a safety factor of 4. The center of gravity shift of the gripped object will also affect the load. If you have any questions, please consult us.
*③ Requires external communication convertor or customization, pleass contact sales or technical support.
*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.

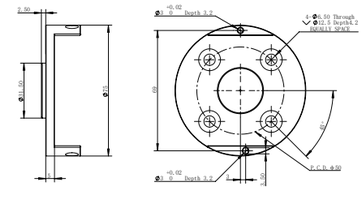
Product Parameter	
Gripping force (per jaw)	20~80 N
Recommended workpiece weight *②	1.5 kg
Single jaw	10 mm
Full stroke opening/closing time	0.5 s/0.5 s
Repeat accuracy (position)	± 0.03 mm
Weight	1.5 kg
Size	141 mm x 103 mm x 75 mm
Noise emission	< 50 dB
Driving method	Precise planetary gear reducer + Rack and pinion

Working Environment	
Communication interface	Standard: Modbus RTU (RS485)、Digital I/O(2 inputs 2 outputs) Optional: TCP/IP、USB2.0、CAN2.0A、PROFINET、EtherCAT *③
Rated voltage	24 V DC ± 10%
Current	0.5 A(Rated)/ 1.2 A(Peak) *④
Rated powert	12 W
IP class	IP 67
Recommended environment	0~40°C, under 85% RH
Certification	CE, FCC, RoHS

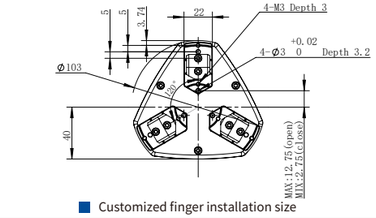
Build-in Controller · Gripping Force Adjustable · Position Adjustable · Speed Adjustable · Drop Detection · Plug & Play · Self-locking Mechanism

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