

PGE-5-26

Slim-type Electric Parallel Gripper



Selection Method

Serie	Gripping Force	Stroke	Brake	Cable Direction	Communication Protocol	Cable Selection	Fingertip Selection	Flange Selection	Robot Cable
PGE	5	26	O	S	M1	L5	JO	F0	00

O	Without Brake	S	Side	M1	Modbus (RS485)+I/O (NN)	LX	Without Extend Cable	JO	Without Fingertip	F0	Without Flange	Table Below
				M2	Modbus (RS485)+I/O (PP)	L1	1m Cable					
B	bottom	S	Side	M3	Modbus (RS485)+I/O (NP)	L3	3m Cable	J1	Standard Fingertip	F0	Without Flange	Table Below
				M4	Modbus (RS485)+I/O (PN)	L5	5m Cable					
						L10	10m Cable					
						L15	15m Cable					

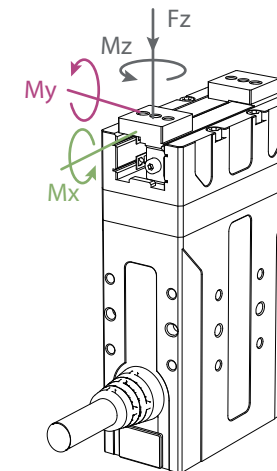
★①:		00	01	SIASUN	DOBOT CR	02	AUBO	04	JAKA	06	ROKAE SR	09	Doosan A	11	Elite EC	13	Neuromeka	15	Hanwha HCR
I/O(NN): NPN/NPN		Without Robot Cable	Elite CS	Hanwha A	DOBOT Nova						ROKAE ER								
I/O(PP): PNP/PNP			UR CB	UR E							DOBOT MG400								
I/O(NP): NPN/PNP												10	Doosan M	12	Han's	14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

★⑤ It is recommended that no more than 4 units 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 50 N

Allowable Loading Moment

Mx 0.3 N · m

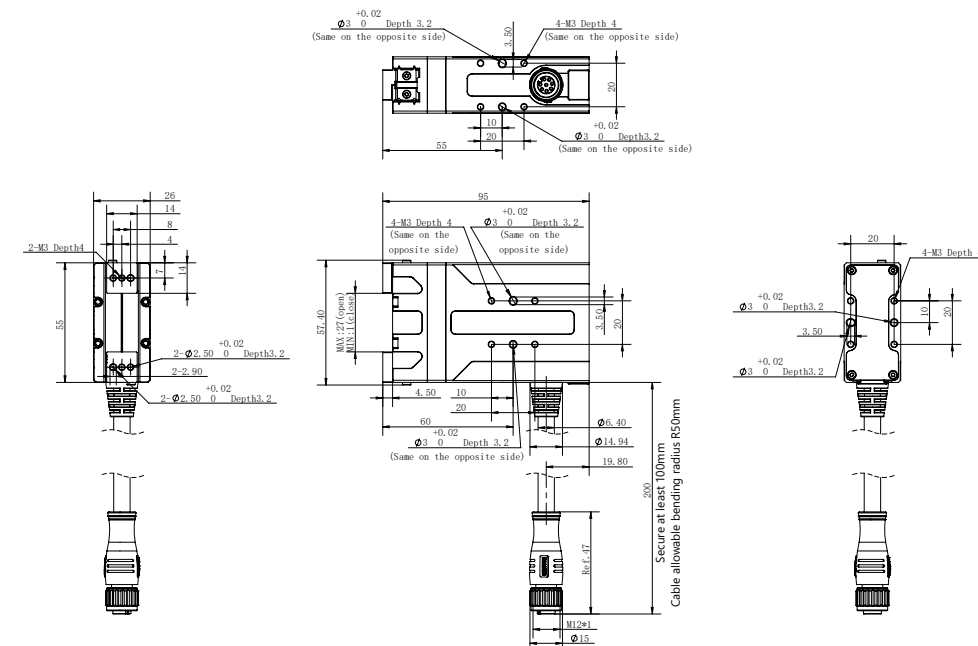
My 0.25 N · m

Mz 0.3 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, please 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 to not work normally.

Technical Drawings



Product Parameter

Gripping force (per jaw) 0.8~5 N

Recommended workpiece weight *③ 0.1 kg

Stroke 26 mm

Full stroke opening/closing time 0.3 s/0.3 s

Repeat accuracy (position) ± 0.02 mm

Weight 0.4 kg

Size 95 mm x 55 mm x 26 mm

Noise emission < 50 dB

Driving method Precise planetary gears + 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 0.4 A(Rated)/ 0.7 A(Peak) *④

Rated power 9.6 W

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