

PGE-8-14

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	8	14	O	S	M1	L5	J0	F0	00
			O Without Brak	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 L15 15m Cable	J0 Without Fingertip J1 Standard Fingertip	F0 Without Flange	Table Below

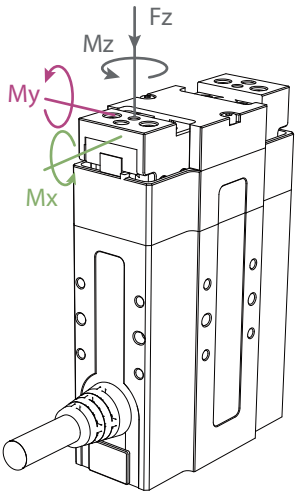
★①:

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												
I/O(PN): PNP/NPN												
					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 90 N

Allowable Loading Moment

Mx 0.55 N · m

My 0.45 N · m

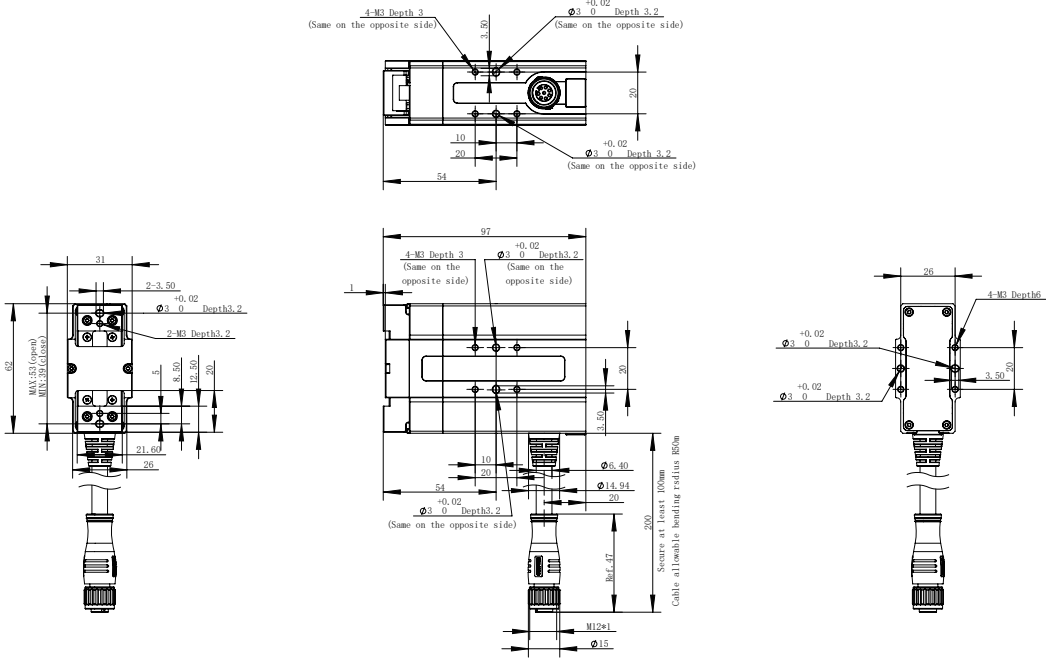
Mz 0.55 N · m

*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 can not work normally.

Technical Drawings



Product Parameter

Gripping force (per jaw)	2~8 N
Recommended workpiece weight*②	0.1 kg
Stroke	14 mm
Full stroke opening/closing time	0.3 s/0.3 s
Repeat accuracy (position)	± 0.02 mm
Weight	0.4 kg
Size	97 mm x 62 mm x 31 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
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