

Parameter Table of Rotational Time in Place for Different Inertia Loads

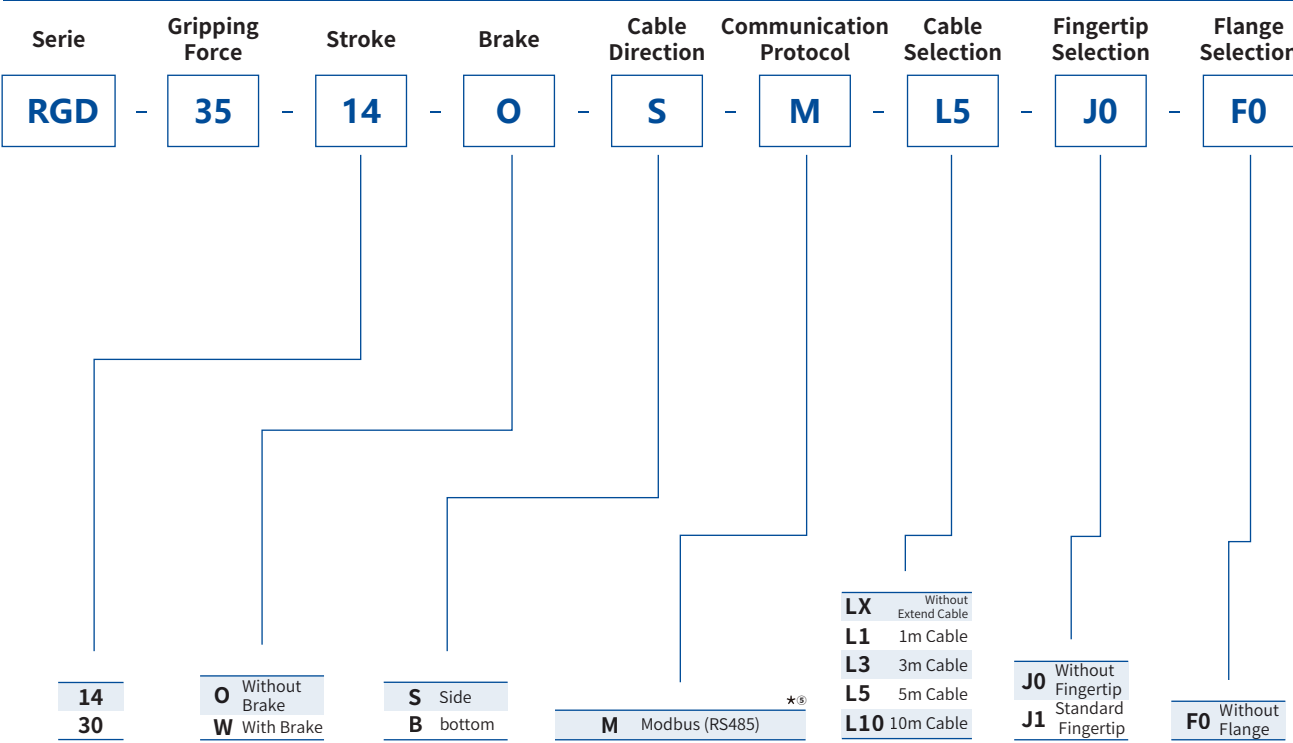
Reference Size/mm	Material	Weight/g	Corresponding Inertia/Kg · mm ²	Actual Rotation Angle/°	Reference Correction Tme/ms
Unload	-	0	0	45	200
				90	200
				180	400
				360	500
				720	700
20*80*25	Aluminum Block	57	61	45	200
				90	300
				180	400
				360	500
				720	700
74.7*80*25	Aluminum Block	387	402	45	300
				90	350
				180	400
				360	550
				720	750
96.7*80*25	Aluminum Block	503	685	45	400
				90	450
				180	500
				360	650
				720	850
111.3*80*25	Aluminum Block	582	941	45	850
				90	1000
				180	1200
				360	1450
				720	1650
126*80*25	Aluminum Block	662	1263	45	1350
				90	1550
				180	1850
				360	1950
				720	2450

RGD-35

Direct Drive Rotary Gripper



Selection Method



*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.

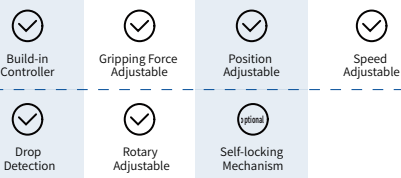
A 3D schematic of a 6-DOF force/torque sensor. The sensor consists of a base and a top plate. A coordinate system is defined with the Z-axis pointing upwards. The force components are labeled: F_z (axial force), F_x (lateral force), and F_y (lateral force). The moment components are labeled: M_z (torque about the Z-axis), M_x (torque about the X-axis), and M_y (torque about the Y-axis). The sensor is shown with a cable connector at the bottom.

F_z	150 N
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M_x	$2 \text{ N} \cdot \text{m}$
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My 1.5 N · m

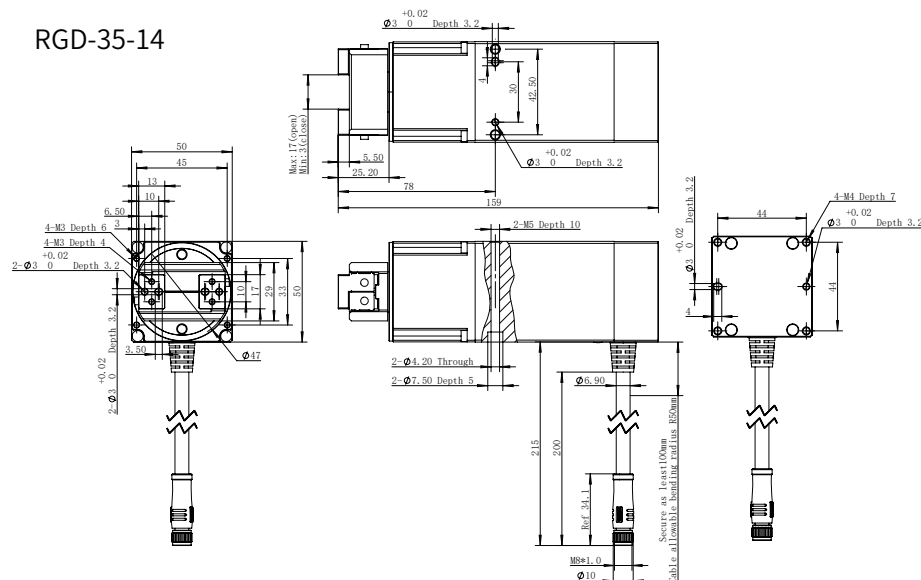
Mz 2.5 N · m



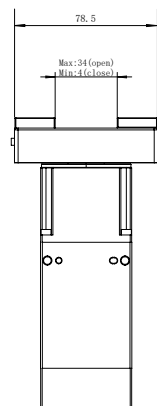
- *① The peak torque can be increased to a maximum of 0.5 N·m. For specific details, please consult with technical support personnel.
- *② The recommended load calculation is based on pure friction force gripping, with a friction coefficient of 0.2 and a safety factor of 4. The center of gravity shift of the gripped object will also affect the load. If you have any questions, please consult us.
- *③ Requires external communication converter 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

RGD-35-14



RGD-35-30



Reference Size/mm	Material	Weight/g	Corresponding Inertia/Kg · mm ²	Actual Rotation Angle/°	Reference Correction Time/ms
Unload	-	0	0	45	200
				90	200
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				360	500
				720	700
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