

Rectangular Design B02

- Two- to Six-Finger Gripper -

Characteristics:

- centric, linear and parallel or swiveling finger movement, can also be combined
- adjustable in finger length, amount and position.
- inside and outside gripper
- lubrication and maintenance free slide bearings
- self-locking free
- multiple position monitoring through proximity switch, optional

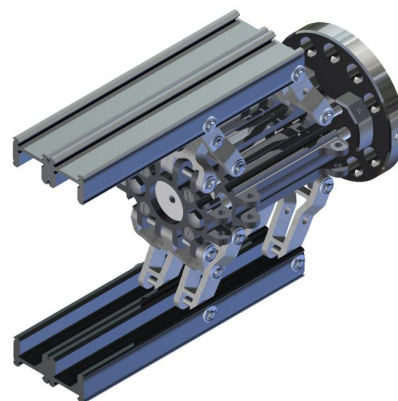


Illustration: type B102-400080-A-PNO-00

Technical Data						
Type B02		Finger Length (F)				
		0 mm	20 mm	40 mm	60 mm	80 mm
Finger Movement A (parallel open / parallel close)	Stroke [mm]	30				
	Gripping Width* [mm]	111 to 141 (136 to 166)				
	Gripping Force*** [N]	208 to 1.075				
Finger Movement B** (parallel open / swiveling close)	Stroke [mm]	32	39	46	53	61
	Gripping Width* [mm]	109 to 141 (134 to 166)	102 to 141 (127 to 166)	95 to 141 (120 to 166)	88 to 141 (113 to 166)	80 to 141 (105 to 166)
	Gripping Force*** [N]	205 to 1.004	176 to 684	154 to 519	137 to 418	123 to 350
Finger Movement C** (swiveling open / swiveling close)	Stroke [mm]	32	43	54	64	80
	Gripping Width* [mm]	109 to 141 (134 to 166)	104 to 147 (128 to 171)	98 to 152 (122 to 176)	92 to 156 (116 to 180)	85 to 165 (109 to 189)
	Gripping Force*** [N]	201 to 965	165 to 527	140 to 362	122 to 276	107 to 223
Drive		pneumatic			electrical*	
Operating Air Pressure / Voltage		1,5 to 6 bar			24V (DC)	
Cycle Time (undamped)		0,25 s			-	
Energy Consumption per Cycle		0,15 liter (at 6 bar)			-	
Operating Temperature		-30 to +80°C				
Mass	Operating Unit	490 g			740 g	
	per Finger Mechanism	max. 100 g				
Loading Capacity** per Finger with Gripping Mass and Acceleration	Mx _{max.}	1 Nm ⇒ (Fy _{max.} : 12,5 N at finger length F = 80mm)				
	My _{max.}	2 Nm ⇒ (Fx _{max.} : 25 N at finger length F = 80mm)				
	Mz _{max.}	2 Nm				
	Fz _{max.}	100 N				

* two gripping widths result due to the rectangular design, data referring to fingers' outer edge

** larger strokes through adjustment of gripping width and pivoting angle on request

*** higher gripping force always at finger position "open" (data referring to 6 bar air pressure)

* on request

** loading capacity autonomous of gripping force



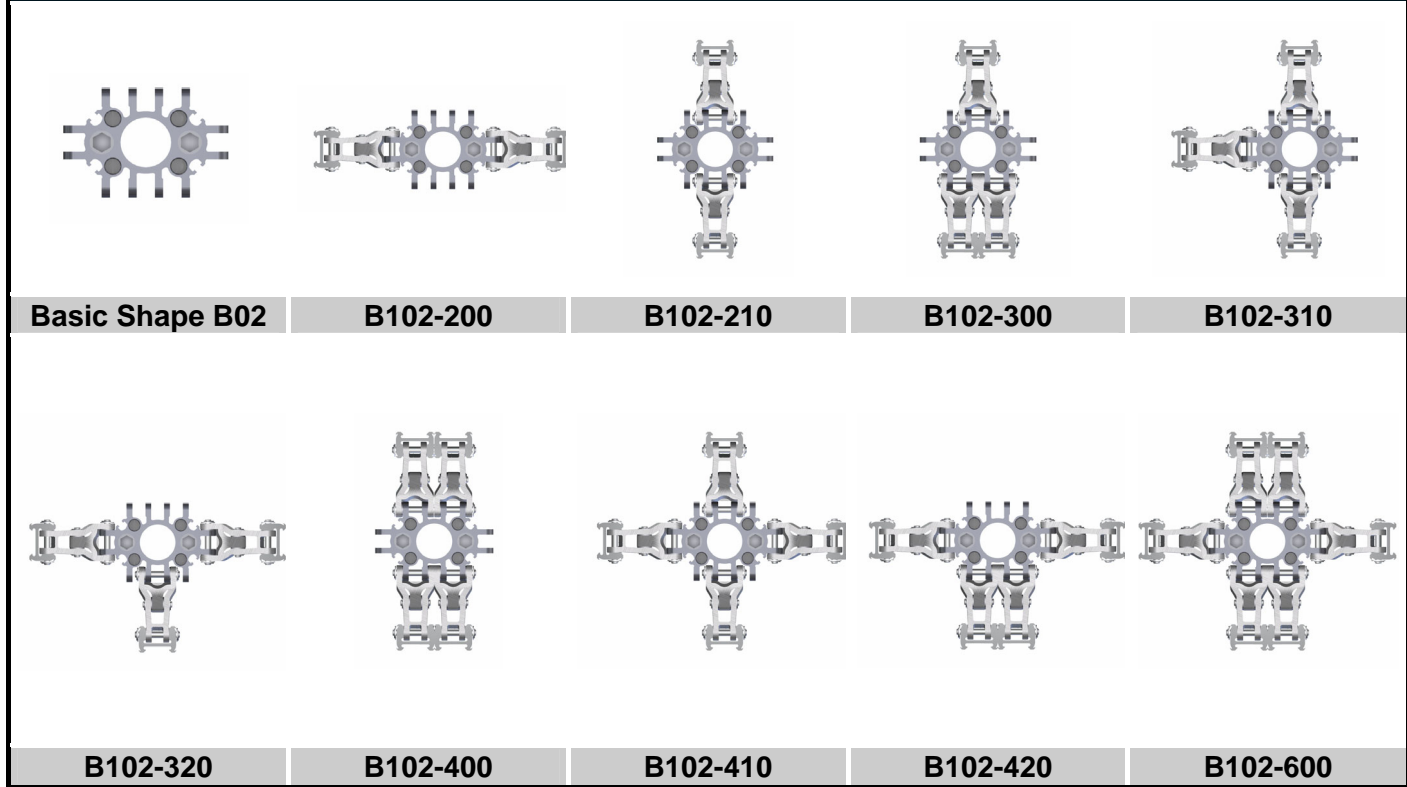
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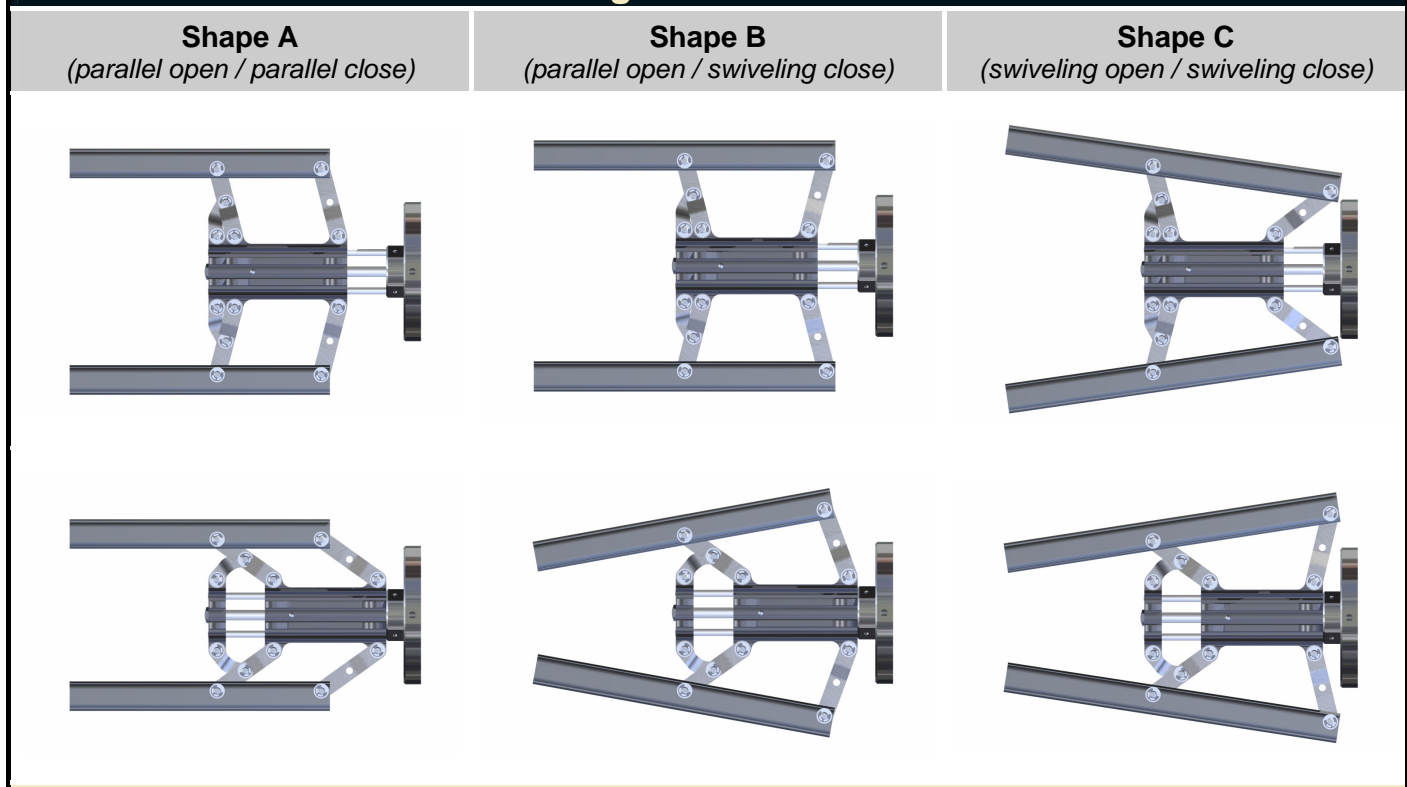
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Quantity and Position of Fingers



Finger Movement



Special Movement through combining shapes are possible upon request!



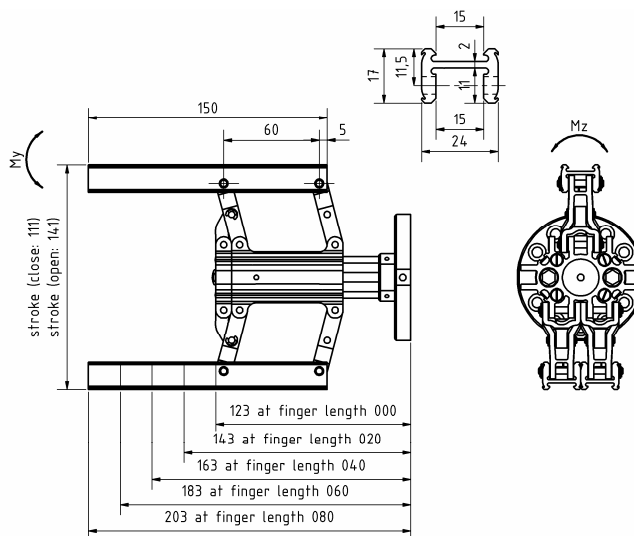
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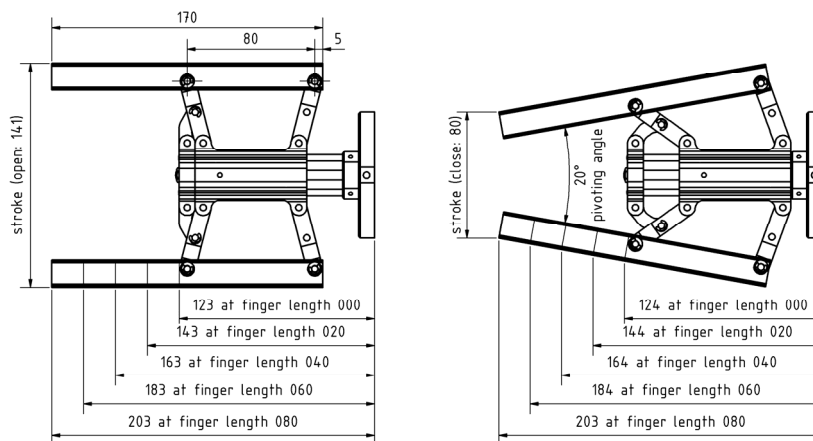
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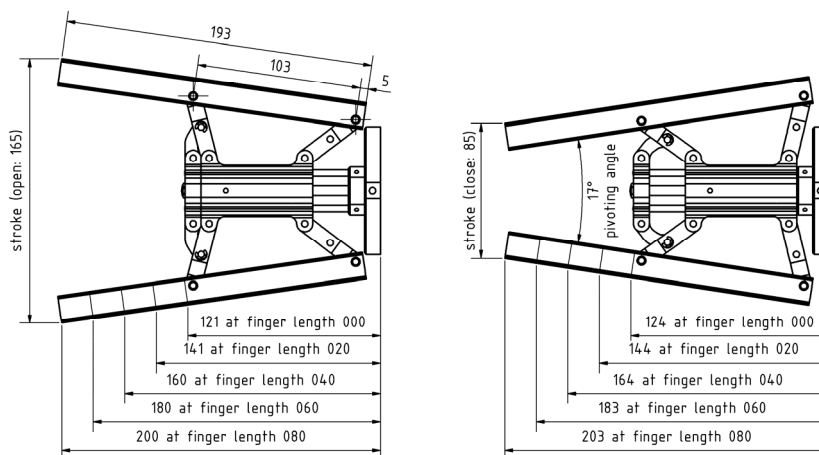
Finger Movement A



Finger Movement B



Finger Movement C



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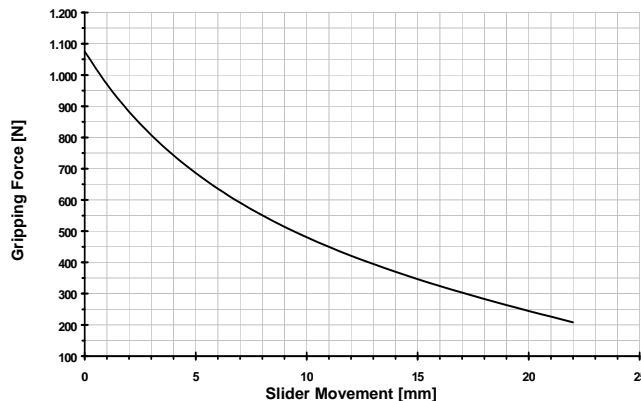
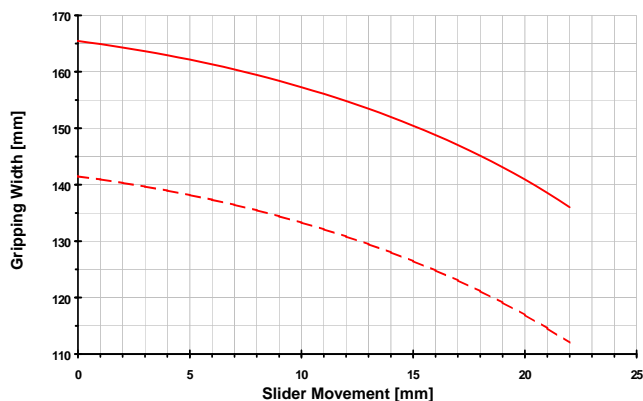
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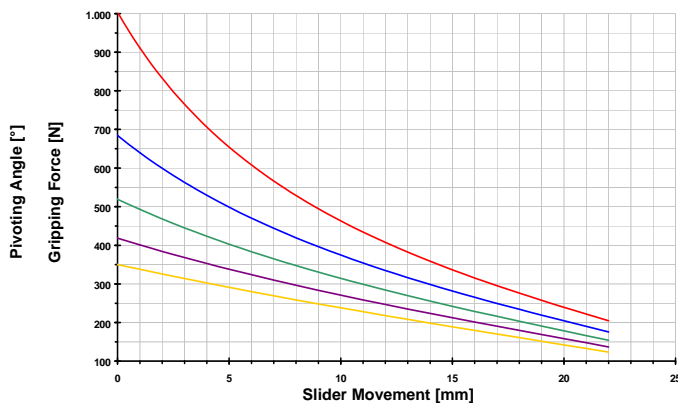
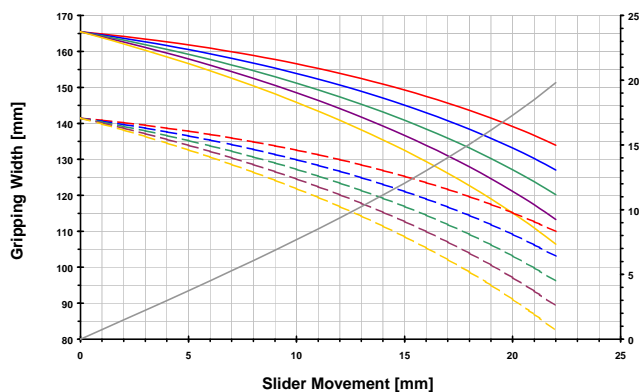
B02

Force- and Gripping-Width-Diagram

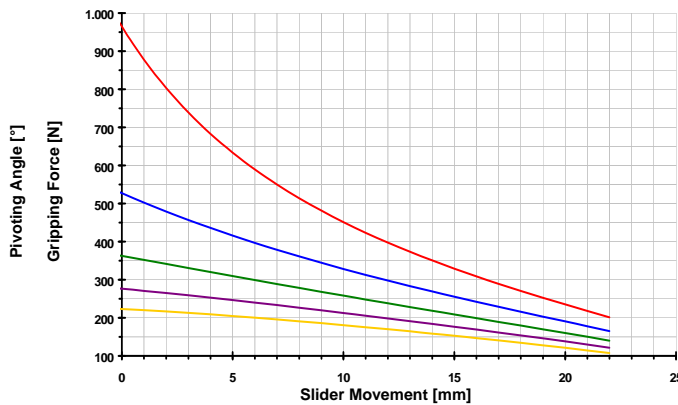
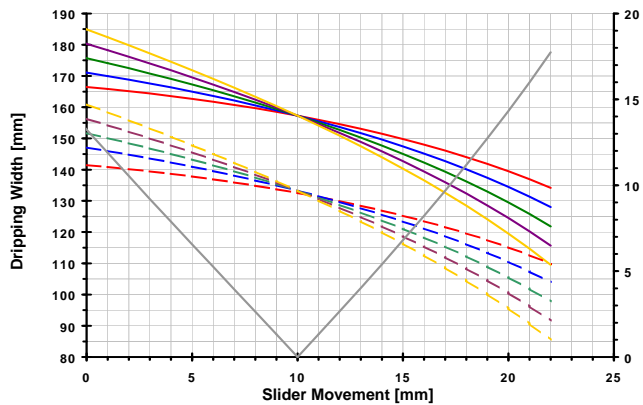
Finger Movement A



Bewegungsform B



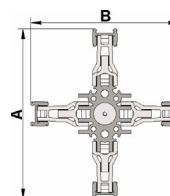
Finger Movement C



— 0 mm
 — 20 mm
 — 40 mm
 — 60 mm
 — 80 mm
 — Pivoting Angle

— (full line) Gripping Width A

- - - (dashed line) Gripping Width B



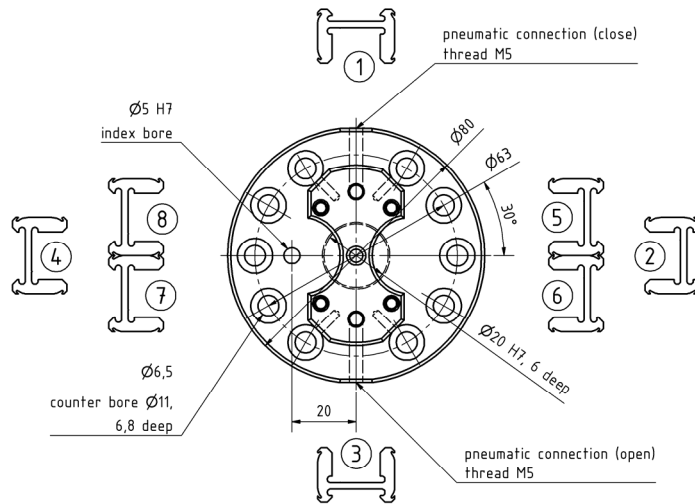
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Finger Position referring to Grippers Flange

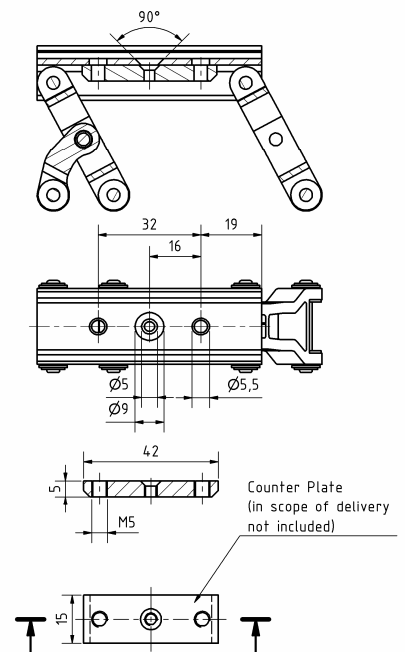


Front View

Finger Quantity	Position								Ident.
	1	2	3	4	5	6	7	8	
2	X		X						200
		X		X					210
3				X	X	X			300
		X					X	X	301
		X	X	X					310
	X	X		X					311
	X		X	X					320
	X	X	X						321
					X	X	X	X	400
4	X	X	X	X					410
	X		X		X	X			420
	X	X					X	X	421
	X		X		X	X	X	X	600

Standard Style

Standard – Bore - Plan



Order Number Counter Plate:
1007-B102-GP03

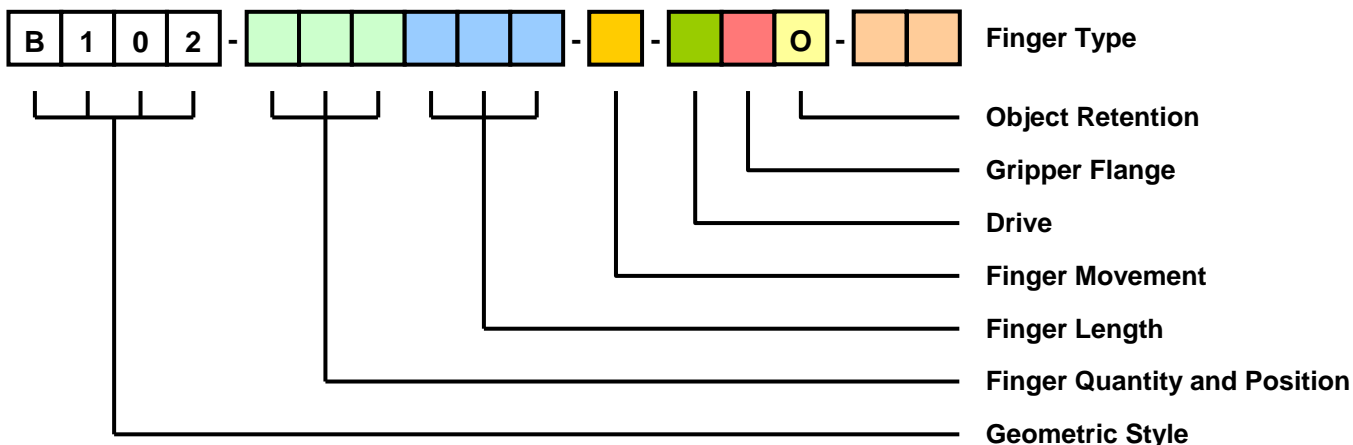
Only for Finger Length F = 0mm



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**Order Number**

<i>Finger Quantity and Position</i>
View table previous page

<i>Finger Length</i>		
	<i>Length (F)</i>	<i>Ident.</i>
Standard	0 mm	000
	20 mm	020
	40 mm	040
	60 mm	060
	80 mm	080
	Special Length	Declaration in mm

<i>Finger Movement</i>	
<i>Style</i>	<i>Ident.</i>
parallel open parallel close	A
parallel open swiveling close	B
swiveling open swiveling close	C
Combination of Finger Movement Styles*	K

<i>Gripper Flange</i>	
<i>Style</i>	<i>Ident.</i>
Normal	N
Rotary Feedthrough (in flange integrated)	D

* on request

<i>Drive</i>	
<i>Style</i>	<i>Ident.</i>
Pneumatic	P
Electrical	E

<i>Object Retention at Blackout</i>	
<i>Style</i>	<i>Ident.</i>
Without Object Retention	O

<i>Finger Type</i>	
<i>Style</i>	<i>Ident.</i>
Without Bore	00
With Bore	01



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