

Sealed 180° Angular Gripper - Design W06 -



Characteristic:

- High Gripping Force
- Short Cycle Time
- Completely capsuled Mechanics
- User defined installation position
- Maintenance free up to 10 million movements
- Compact Design
- Modular Design
- multiple position monitoring through proximity switch, optional
- built-in end position damping when opening

By using the given torque M [Nm], the necessary air pressure P can be computed with the following formula in position where fingers are closed:

$$0,5 \text{ bar} \leq P_{\text{erf.}} = \frac{M \text{ bar}}{30 \text{ Nm}} \leq 6 \text{ bar}$$

Technical Data

Type		 W106	 W206
Drive		pneumatic	
max. Gripping Force (at 6 bar) *		2250 N	
max. Torque (at 6 bar) **		180 Nm	
Operating Air Pressure		0,5 to 6 bar	
Cycle Time	Open	0,25 s	
	Close	0,25 s	
Repeat Accuracy		0,1 mm	
Energy Consumption per Cycle		1,2 liter	
Operating Temperature		-30 to +80°C	
Mass		2,1 kg	2,5 kg
Loading Capacity* per Finger with Gripping Mass and Acceleration	Mx _{max.}	40 Nm	100 Nm
	My _{max.} (Gripping)	180 Nm	180 Nm
	Fz _{max.}	10.000 N	20.000 N
	Mz _{max.}	30 Nm	100 Nm

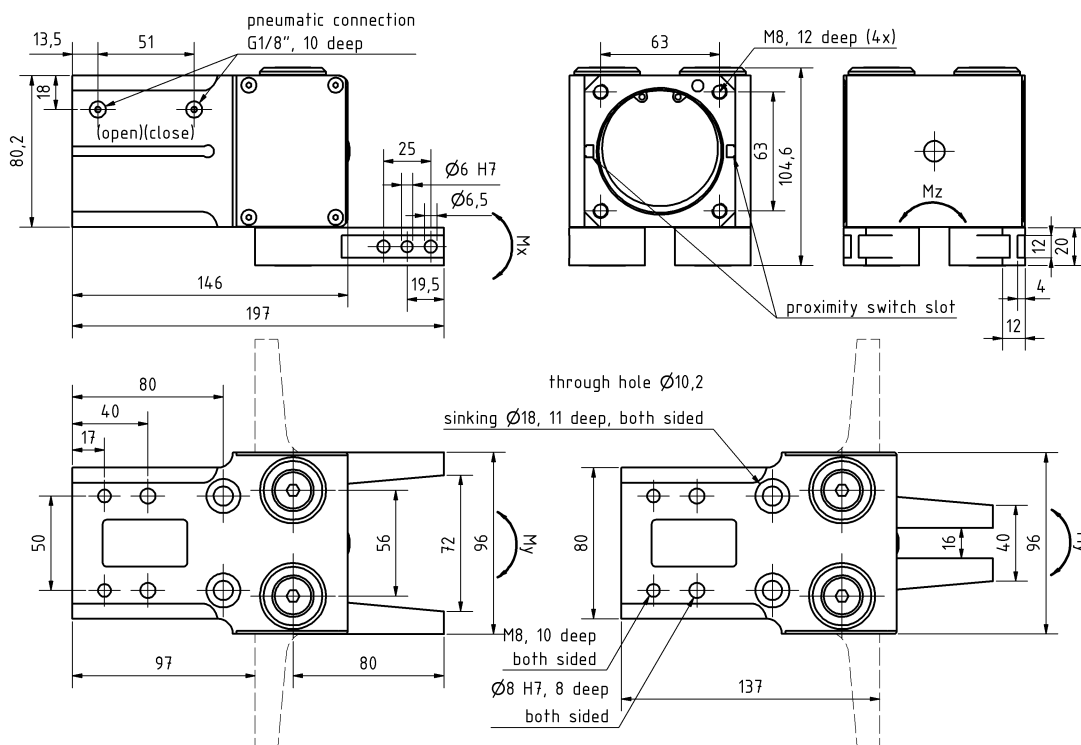
* At fingers outer edge when standard fingers´ (80mm) position closed

** Gripping force per finger is half of this torque divided by length of finger

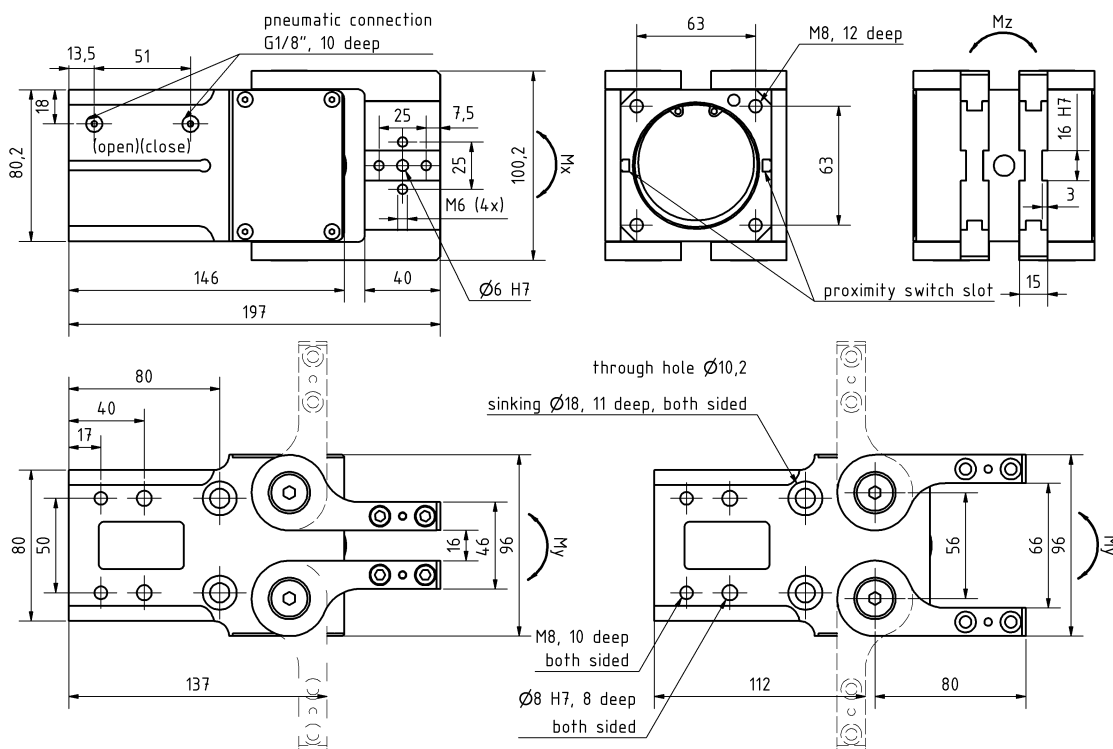


W06

Type W106 (Single Finger)



Type W206 (Double Finger)



address:
GMG – Gesellschaft fuer modulare
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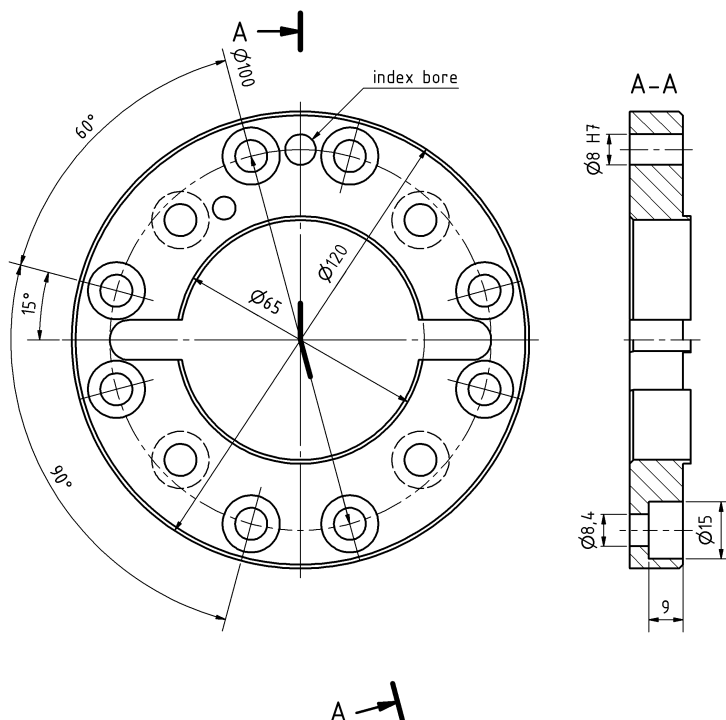
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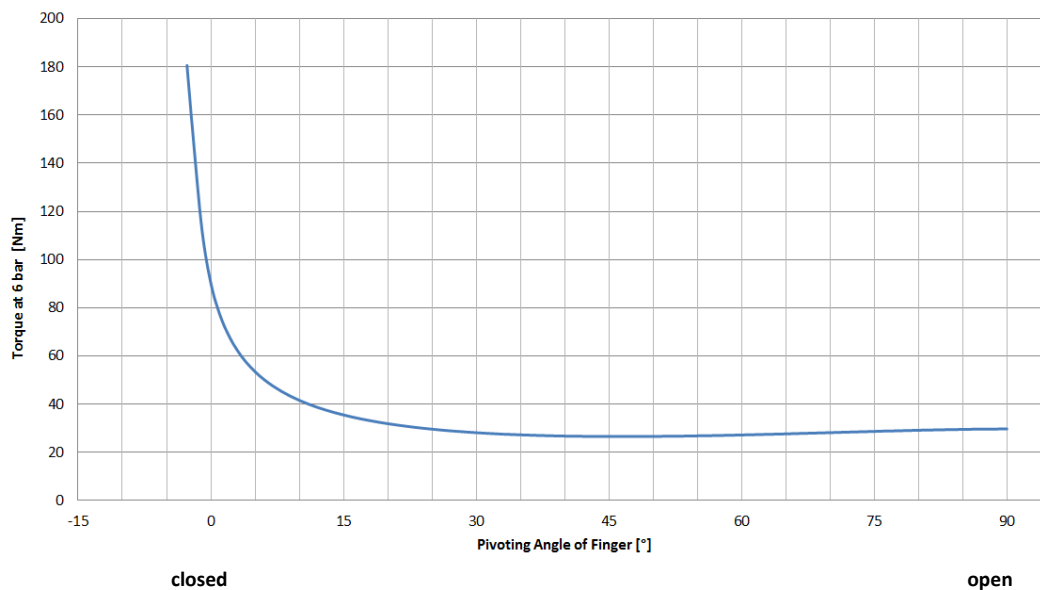
W06

Flange



Used to mount the gripper to a robot

Diagram



Torque curve also available in mirrored version upon request.

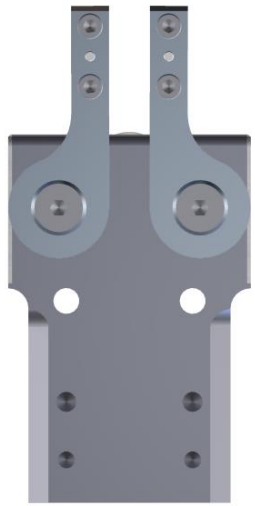


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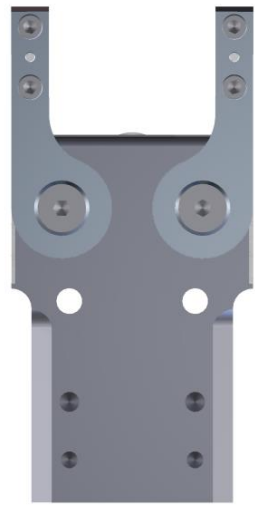
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Finger Position

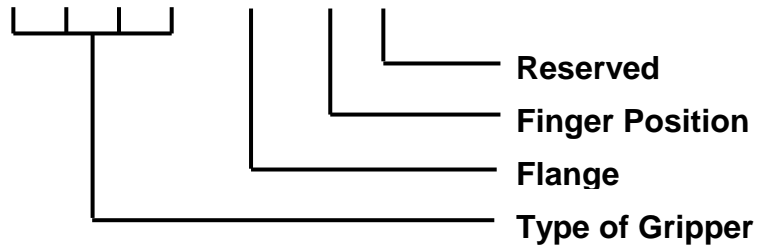
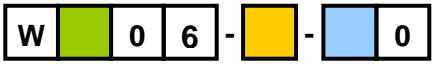


Inside Fingers



Outside Fingers

Order Number



Type of Gripper	
Style	Ident.
Single Finger W106	1
Single Finger W 206	2

Flange	
Style	Ident.
With Flange	N
Without Flange	O

Finger Position	
Style	Ident.
Inside Fingers	I
Outside Fingers	A



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