technical data

**TECHNICAL**

- **MECHANICAL**
  - wrist mounting range
  - wrist mounting resolution
  - power grasp payload
  - pinch grasp payload
  - hanging payload
  - full closing time
- **INERTIAL**
  - center of mass
- **ENVIRONMENTAL**
  - operating temperature
  - storage temperature
- **ELECTRICAL**
  - operating voltage
  - power consumption
- **CONTROL**
  - communication protocols

**FEATURES**

- plug-and-play
- soft, human-like fingers
- adjustable wrist mounting position
- splash, water, and dust resistance: IP65
- interchangeable gloves for special applications

**NORMAL COMPLIANCE**

- ISO 12100
- ISO/TS 15066
- ISO 13849-1/-2
- ISO 10210-1/-2
- ISO/TR 20218-1
- IEC 60529
- IEC 61000-6-1/-6-2
- ISO 9409-1-50-4-M6

**CONTROL**

- communication protocols: EtherCAT, UDP, Digital I/Os

**ELECTRICAL UNIT NOMINAL MIN MAX**

- operating voltage [V]
- power consumption [W]

**OPERATING TEMPERATURE**

- °C

**STORAGE TEMPERATURE**

- °C

**ELECTRICAL CONNECTIONS**

- power supply unit
- robot controller
- external driver

**CONNECTOR PIN-OUT**

- 1
- 2
- 3
- 4
- 5
- 6
- 7
- 8

**MAXIMUM PAYLOAD CHART NOTES**

- shapes: sphere, cylinder, mass M
- friction factor: 0.8±0.1
- safe limit is intended w.r.t. ISO/TS 15066
- maximum stopping acceleration = 30m/s²
- restricted objects are detailed in the user manual
- *restricted objects are detailed in the user manual*

**WRIST MOUNTING WORKSPACE**

- R172
- 90°

**FINGERS WORKSPACE**

- 5°
- 156
- 86
- 92
- 81
- 63

**KINEMATICS**

- 15°

**MAXIMUM PAYLOAD CHART**

- payload [kg]
- shape diameter [mm]

- 0.5
- 1.0
- 1.5
- 2.0
- 2.5
- 3.0
- 3.5
- 4.0
- 4.5

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