Collaborative Parallel Grippers ECG2-25140 2-Finger

- ECG is a collaborative 2-finger parallel gripper that is equipped with symmetrically parallel Advantages

 Compact design

 Smooth body with rounded edges ideal for collaborative applications

 Grip control: force and position adjustment

 Quick open/close time with speed adjustment

 Grip feedback and part detection: gripper status can be read at the PLC/Controller and visualized on the unit via LED's

 Plug and play: mechanical and software interface for major cobot manufacturers

 Multiple communication modes: the gripper supports Modbus RTU protocol and IO mode control. Other protocols such as USB and ETHERNET can be implemented through a protocol converter.

- ROS compatible
 Designed for harsh environments
 Grip actuation via embedded controller.



SPECIFICATIONS

Model	Stroke per Jaw	Gripping Force per Jaw	Total Gripping Force	Opening/ Closing Time	Nominal Voltage	Nominal Current	Max Current	Repeatability (Positioning)	Recommended Workpiece Weight*	Weight
ECG2-25140	25 mm	40 - 140 N	80 - 280 N	0.6/0.6 s	24 V DC ± 10%	0.40 A	1.00 A	± 0.03 mm	3.0 kg	1.00 kg
	0.98 in	8.99 - 31.47 lb	17.98 - 62.95 lb					± 0.001 in	6.61 lb	2.20 lb

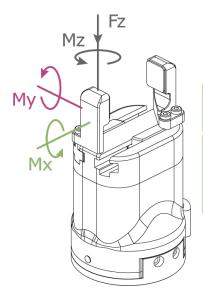
^{*} Recommended workpiece weight depends on the shape of the part, the material and friction of the contact surface and the acceleration of the motion.

Communication Interface Standard: Modbus RTU (RS485), Digital I/O
Optional: TCP/IP, USB2.0, CAN2.0A, PROFINET, EtherCAT

IP Protection Class IP 67

Noise Emission (Sound Pressure) ≤ 40 dB(A) in any direction
Recommended operating environment 0-40 °C (32-104 °F), < 85% RH

For this type of gripper the use of the standard fingers is recommended.

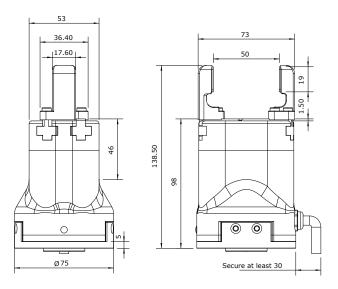


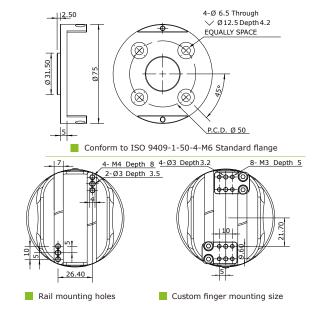
Allowable vertical load (static)								
Fz	300 N (67.44 lb)							
Allowable moment (static)								
Mx	7 Nm (61.96 in-lb)							
Му	7 Nm (61.96 in-lb)							
Mz	7 Nm (61.96 in-lb)							



PRODUCT INFORMATION

ECG2-25140 2-Finger







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