

CGE-10-10

Electric Centric Gripper



Selection Method

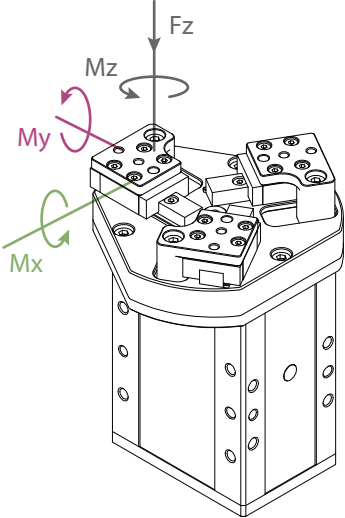
Serie	Gripping Force	Stroke	Brake	Cable Direction	Communication Protocol	Cable Selection	Fingertip Selection	Flange Selection	Robot Cable
CGE	10	10	O	S	M1	L5	J0	F0	00
			O Without Brake	S Side	★① ★⑤ M1 Modbus (RS485)+I/O (NN) M2 Modbus (RS485)+I/O (PP) M3 Modbus (RS485)+I/O (NP) M4 Modbus (RS485)+I/O (PN)	LX Without Extend Cable L1 1m Cable L3 3m Cable L5 5m Cable L10 10m Cable	J0 Without Fingertip	F0 Without Flange	Table Below

①: I/O(NN): NPN/NPN I/O(PP): PNP/PNP I/O(NP): NPN/PNP I/O(PN): PNP/NPN	00	01	SIASUN	DOBOT CR	02	04	06	09	11	13	15	
	Without	Elite CS	Hanwha A	DOBOT Nova	AUBO	JAKA	ROKAE SR ROKAE ER	Doosan A	Elite EC	Neuromeka	Hanwha HCR	
	Robot	UR CB	UR E									
	Cable				03	05	07	10	12	14	16	17
					ELEPHANT	TECHMAN	DOBOT MG400	Doosan M	Han's	FAIRINO	UF x Arm	ROKAE CR

★⑤ It is recommended that no more than 4 units 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.

TECHNICAL SPECIFICATIONS



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

Mx 0.62 N·m

My 0.62 N·m

Mz 0.62 N·m

★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 convertor 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.

Product Parameter

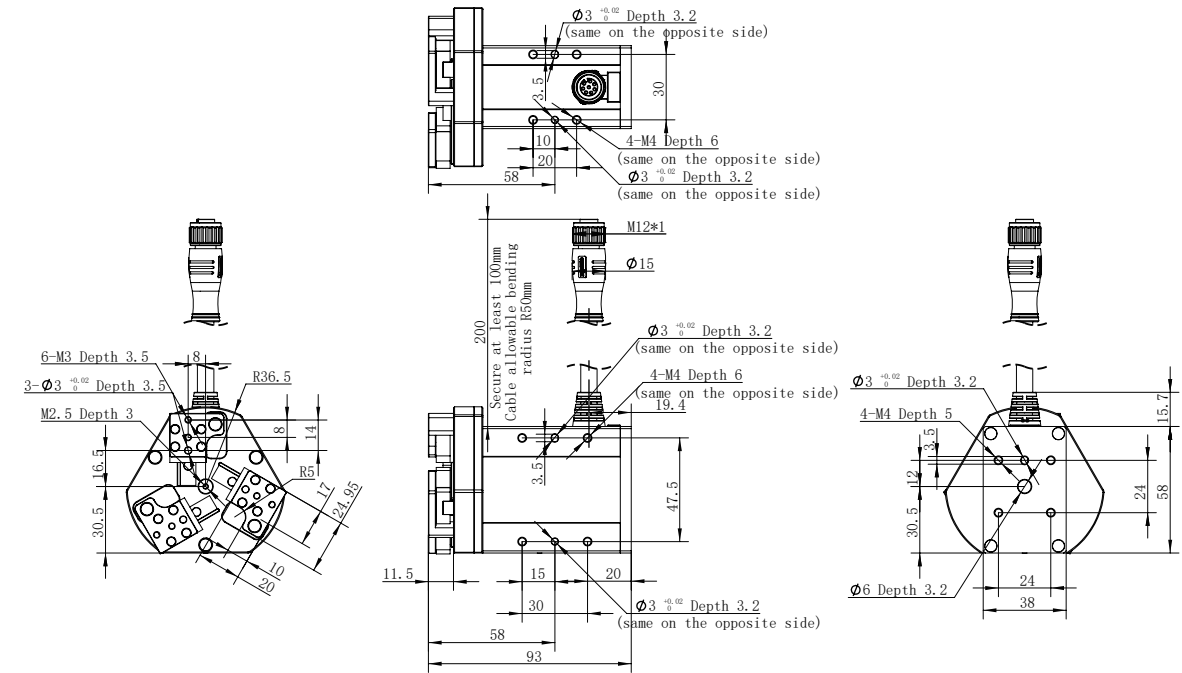
Gripping force (per jaw)	3~10 N
Recommended workpiece weight ★②	0.1 kg
Stroke	10 mm
Full stroke opening/closing time	0.3 s/0.3 s
Repeat accuracy (position)	± 0.03 mm
Weight	0.43 kg
Size	94 mm x 53.5 mm x 38 mm
Noise emission	< 50 dB
Driving method	Precise planetary gear reducer + Rack and pinion

Working Environment

Communication interface	Standard: Modbus RTU (RS485)、Digital I/O(2 inputs 2 outputs) Optional:TCP/IP、USB2.0、CAN2.0A、PROFINET、EtherCAT ★③
Rated voltage	24 V DC ± 10%
Current	0.3 A(Rated)/ 0.6 A(Peak) ★④
Rated power	7.2 W
Recommended environment	0~40°C, under 85% RH
Certification	CE, FCC, RoHS

Build-in Controller	Gripping Force Adjustable	Position Adjustable	Speed Adjustable	Drop Detection	Self-locking Mechanism
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Technical Drawings



Electric Centric Gripper



Series	Gripping Force	Stroke	Brake	Cable Direction	Communication Protocol	Cable Selection	Fingertip Selection	Flange Selection	Robot Cable
CGI	100	170	O	S	M1	L5	J1	F1	00

O Without Brake

W With Brake

S Side

M1 Modbus (RS485)+I/O (NN)

M2 Modbus (RS485)+I/O (PP)

M3 Modbus (RS485)+I/O (NP)

M4 Modbus (RS485)+I/O (PN)

LX Without Extend Cable

L1 1m Cable

L3 3m Cable

L5 5m Cable

L10 10m Cable

J1 Standard Fingertip

F1 Standard Flange

Table Below

00 Without Robot Cable	01 Elite CS UR CB	SIASUN Hanwha A UR E	DOBOT CR DOBOT Nova	02 AUBO	04 JAKA	06 ROKAE SR ROKAE ER	09 Doosan A	11 Elite EC	13 Neuromeka	15 Hanwha HCR
				03 ELEPHANT	05 TECHMAN	07 DOBOT MG400	10 Doosan M	12 Han's	14 FAIRINO	16 UF x Arm

The Modbus RTU (RS485) to USB module will no longer be provided for free. Please place a separate order if needed.

A technical line drawing of a mechanical component. It features a central cylindrical base with a flange. On top of the flange is a four-lobed star-shaped plate. From the center of each lobe, a vertical rod extends upwards. Additionally, from the outer edge of each lobe, a horizontal rod extends outwards. The drawing is a perspective view, showing the top and side of the component.

*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.

Gripping force (per jaw)	30~100 N
Recommended workpiece weight *②	1.5 kg
Recommended workpiece diameter (inward)	Φ40~Φ170 mm
Full stroke opening/closing time	1.35 s
Repeat accuracy (position)	± 0.03 mm
Weight	1.5 kg
Size	158.4mmx124.35mmx116mm (without brake/with brake,same size)
Noise emission	< 50 dB
Driving method	Precise planetary gears + Rack and pinion

Communication interface	Standard: Modbus RTU (RS485)、Digital I/O(2 inputs 2 outputs) Optional: TCP/IP、USB2.0、CAN2.0A、PROFINET、EtherCAT *③
Rated voltage	24 V DC $\pm$ 10%
Current	0.4 A(Rated)/ 1 A(Peak) *④
Rated power	9.6 W
IP class	IP 40
Recommended environment	0~40°C, under 85% RH
Certification	CE, FCC, RoHS

