

DH-3

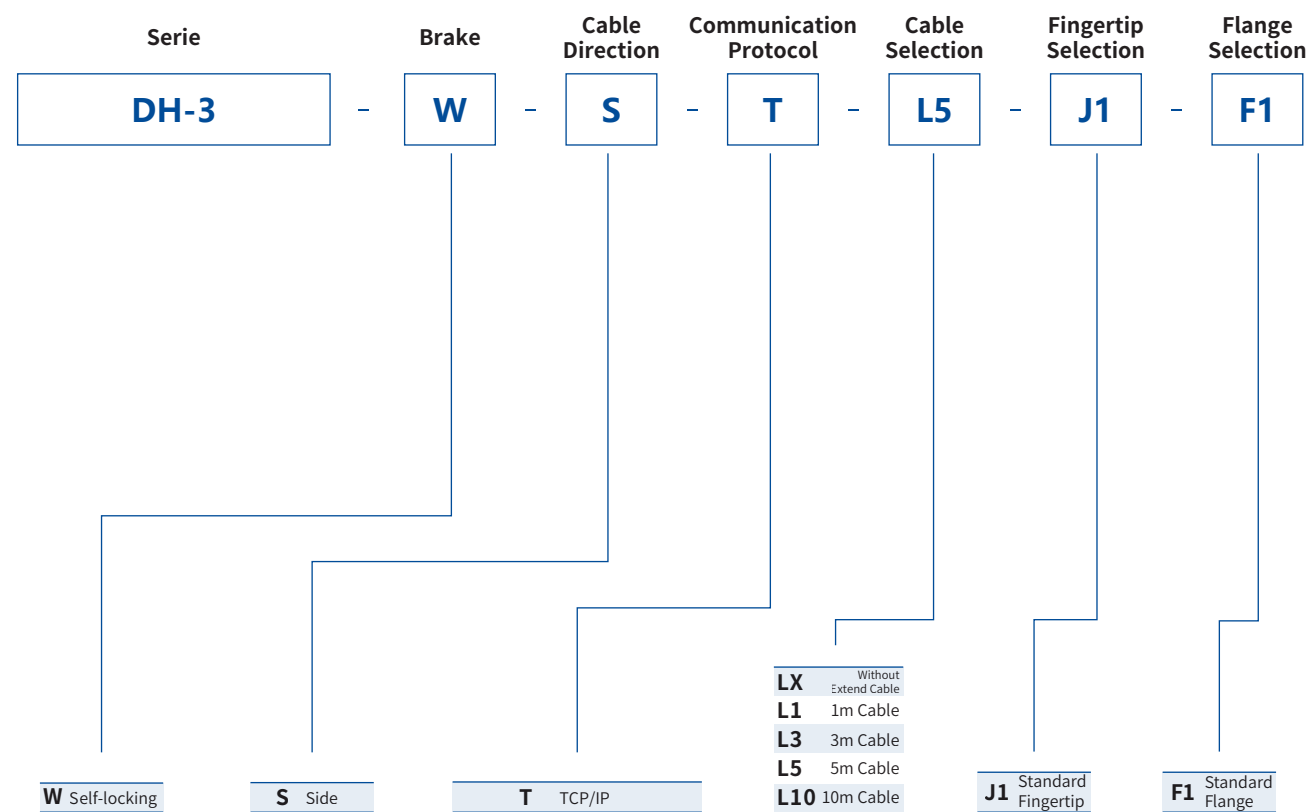
Electric Adaptive Gripper

reddot award 2020
winner

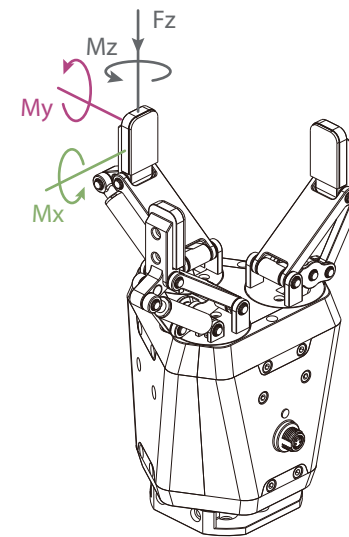


Bottom
installation

Selection Method



TECHNICAL SPECIFICATIONS



Static Vertical Allowable Load

Fz 150 N

Allowable Loading Moment

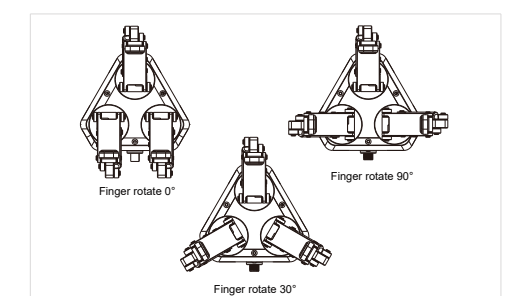
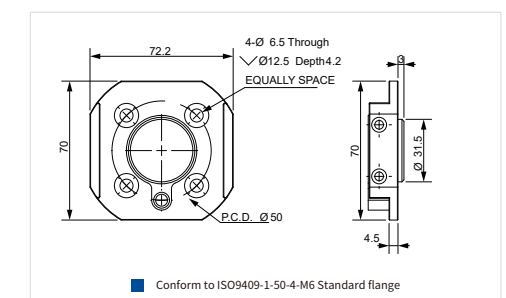
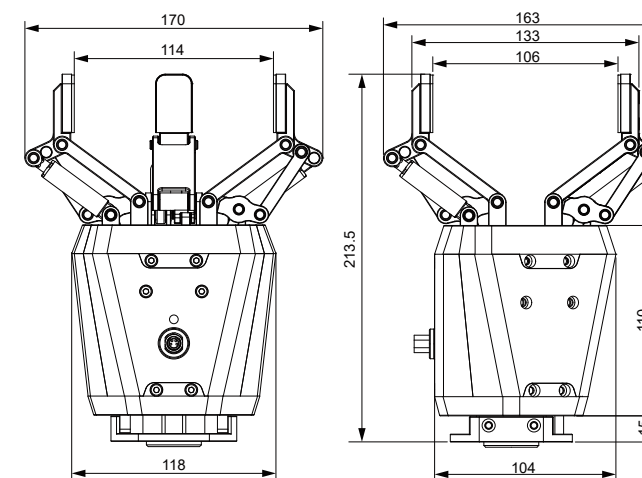
Mx 2.5 N·m

My 2 N·m

Mz 3 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.

Technical Drawings



Product Parameter

Gripping force (per jaw)	10~65 N
Recommended workpiece weight *①	1.8 kg
Stroke	106 mm (parallel) 122 mm (centric)
Full stroke opening/closing time	0.7 s/0.7 s
Repeat accuracy (position)	± 0.03 mm
Weight	1.68 kg
Size	213.5 mm x 170 mm x 118 mm
Noise emission	< 60 dB
Driving method	Screw nut + gear driv + linkage mechanism

Working Environment

Communication interface	Standard: TCP/IP, USB2.0, CAN2.0A
Rated voltage	24 V DC ± 10%
Current	0.5 A(Rated)/ 1 A(Peak)*③
Rated power	12 W
IP class	IP 40
Recommended environment	0~40°C, under 85% RH
Certification	CE, FCC, RoHS



Build-in Controller



Gripping Force Adjustable



Position Adjustable



Speed Adjustable



Drop Detection



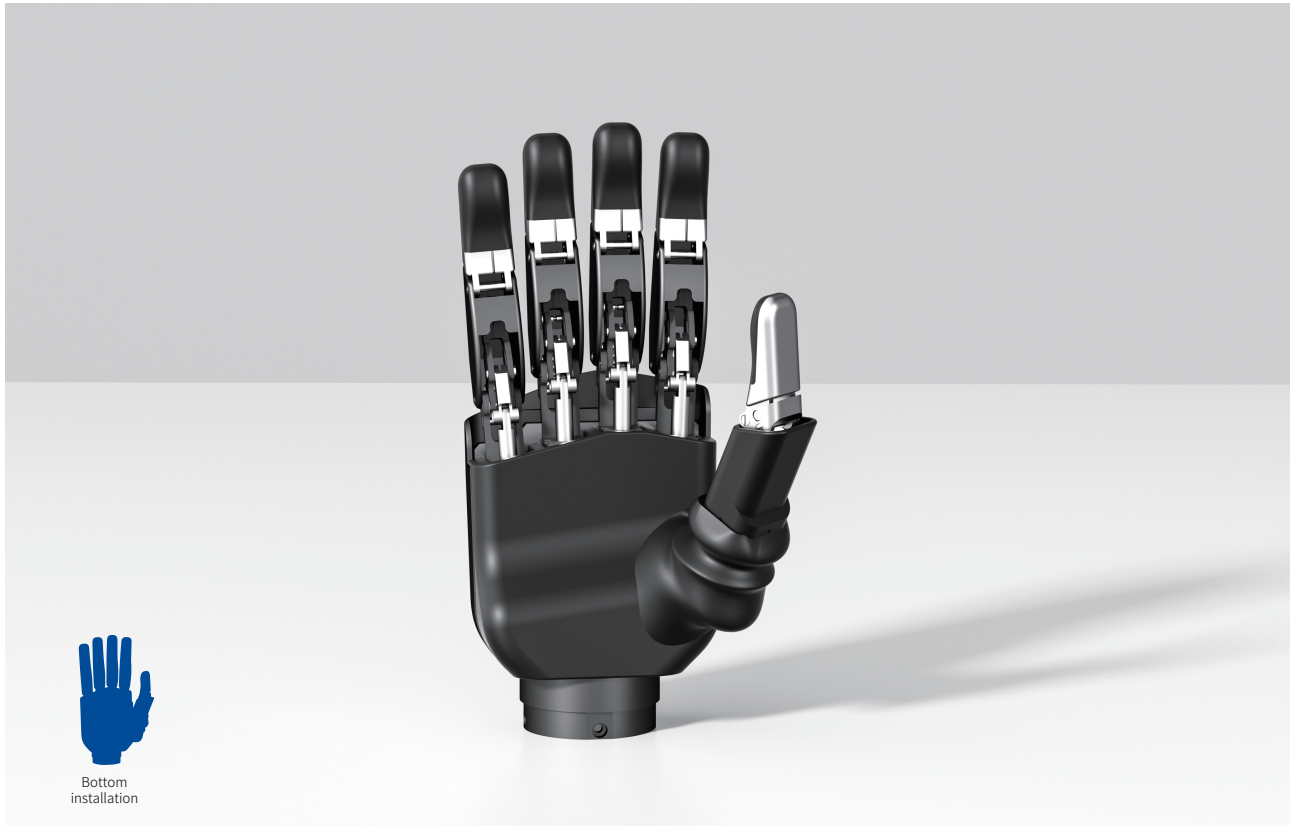
Plug & Play



Self-locking Mechanism

DH-5-6

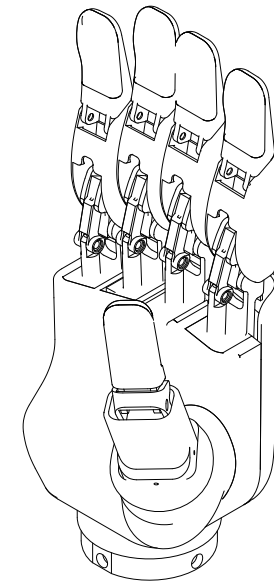
Dexterous Hand



Selection Method

Serie	Number of Fingers	Hand Shape	Active Degrees of Freedom	Degrees of Freedom	Wrist Interface	Cable Direction	Sensors	Cable Configuration	Mounting Flange
DH	5	L	6	11	N	M3	C0	L3	Z0
3 3 Fingers	L Left Hand	6 Degrees of Freedom	11 Joint	N Standard interface	M3 MODBUS-RTU			L1 Extension Cable 1m	
5 5 Fingers	R Right Hand			F Quick-release interface	M4 Custom communication protocol over RS485		C0 Without Sensor	L3 Extension Cable 3m	
								L5 Extension Cable 5m	
								L10 Extension Cable 10m	
									Z0 Standard Flange without Adapter
									Z1 With Adapter Flange 1 (Mounting PCD Ø50 mm / Locating Boss Ø31.5 mm)
									Z2 With Adapter Flange 2 (Mounting PCD Ø49 mm / Locating Boss Ø18mm)
									Z3 Others

TECHNICAL SPECIFICATIONS



Build-in Controller	Gripping Force Adjustable	Position Adjustable	Speed Adjustable
Plug & Play			

Product Parameter	
Total degrees of freedom	11
Active degree of freedom	6
Working speed	0.8 s
Four-finger bending angle	83°+87°
Thumb bending angle	38°+7°
Thumb lateral swing angle	85°
Single fingertip force	25 N
Recommended maximum friction load	2 kg
Recommended maximum structural lifting load	4 kg
Hand grip strength	80 N
Lifting load	10 kg
Weight	790 g
Sensors	Multi-point Tactile Sensing (Optional)
Safety features	Anti-collision Buffering for Inward Grasping
Driving method	Coreless motor + planetary reducer + ball screw + linkage
Size	236 mm*116 mm*96 mm
Working Environment	
Communication interface	Modbus-RTU/Custom communication protocol over RS485
Rated voltage	24 V DC ± 10%

Technical Drawings

