

**PW206**

Sealed 2-Finger-Parallel-Angular-Gripper

- Design PW206 -

Characteristics:

- parallel finger movement
- fingers move out of gripping area
- enormous stroke
- high gripping force
- short cycle time
- completely capsuled mechanics
- user defines installation position
- maintenance free up to 10 million movements
- compact design
- multiple position monitoring through proximity switch, optional

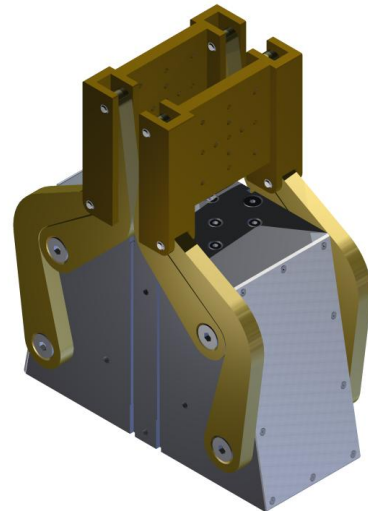


Illustration: PW206-OO-00

Technical Data		
Type	PW206	
Stroke	660 mm	
Gripping Width	132 mm – 792mm	
Gripping Force per finger (at 6 bar) *	208 N – 1.500 N	
Drive	pneumatic	
Operating Pressure	2,5 to 6 bar	
Cycle time	Open	1,5 s
	Close	1,5 s
Energy consumption per cycle (at 6bar)	2,3 liter	
Operating Temperature	-30 to +80°C	
Mass	31,5 kg	
Loading capacity* per finger with gripping mass and Acceleration	Mx max.	250 Nm
	My max. (gripping)	170 Nm **
	Fz max.	50.000 N
	Mz max.	150 Nm

* Rectangular force on shoe support

** At closed fingerposition



Hausanschrift:

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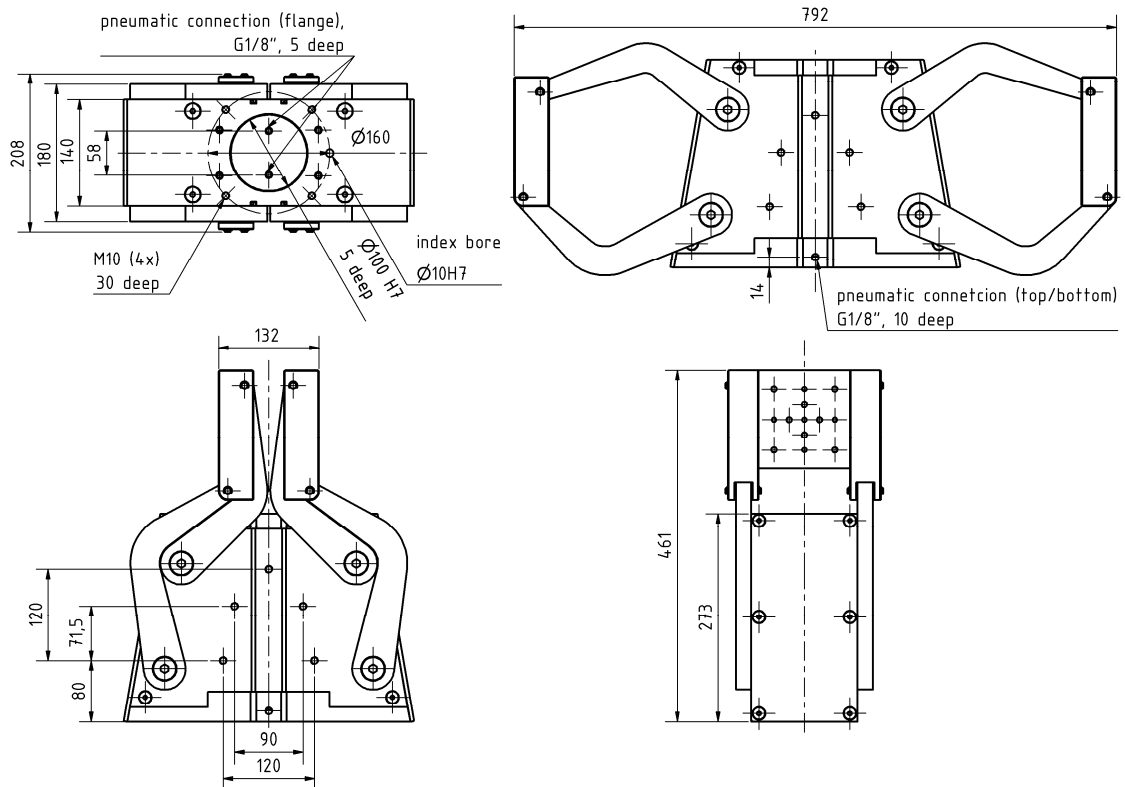
info@gmg-system.com

Internet:

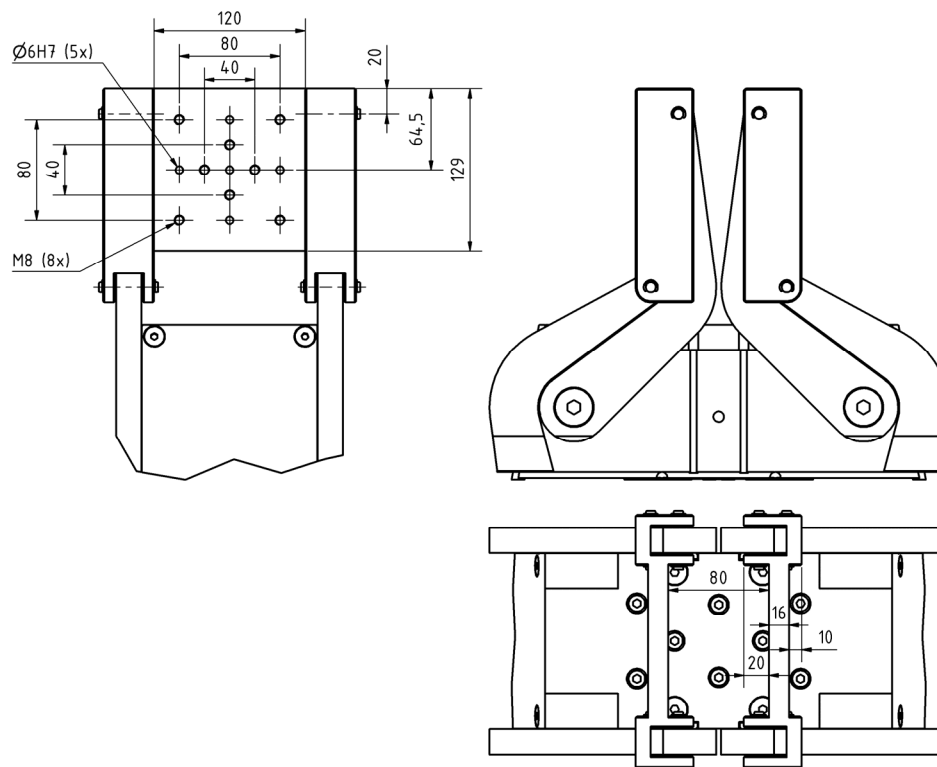
http://www.gmg-system.com



Dimension Sheet



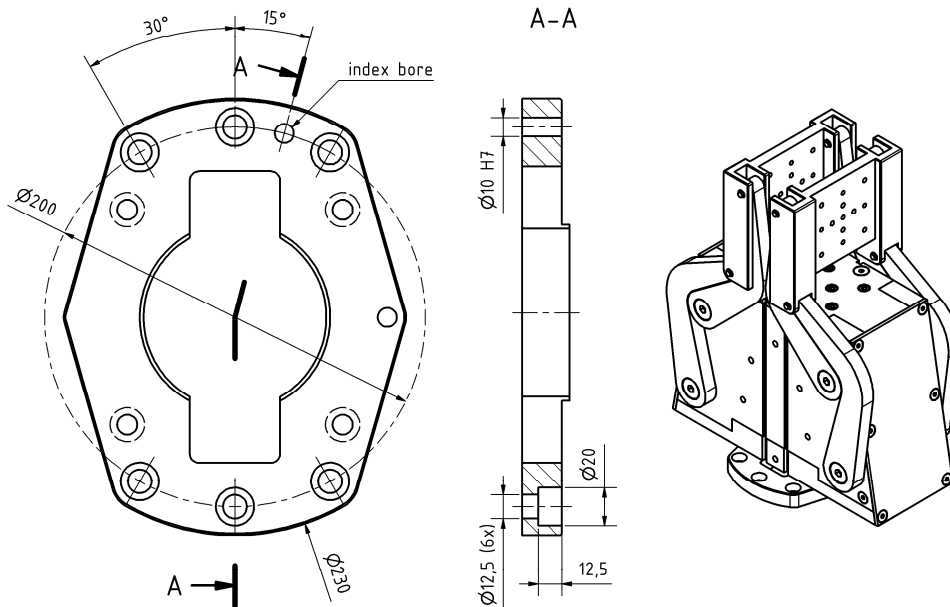
Shoe Support





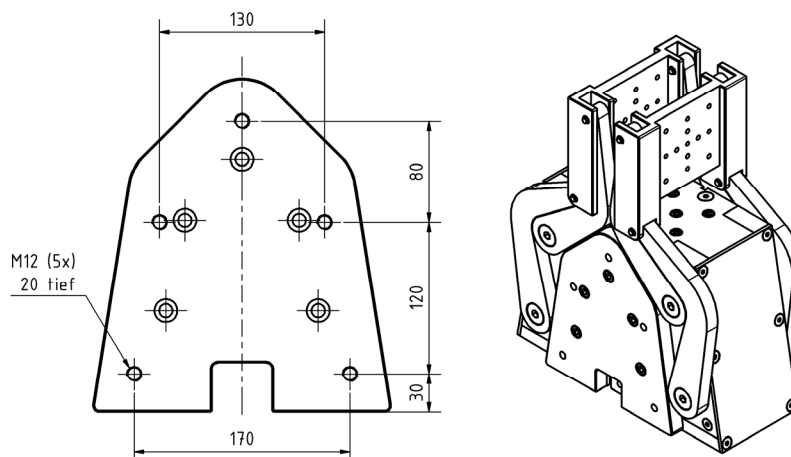
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Flange



Used to mount the gripper to a industrial robot

Side flange



To mount the gripper sideways



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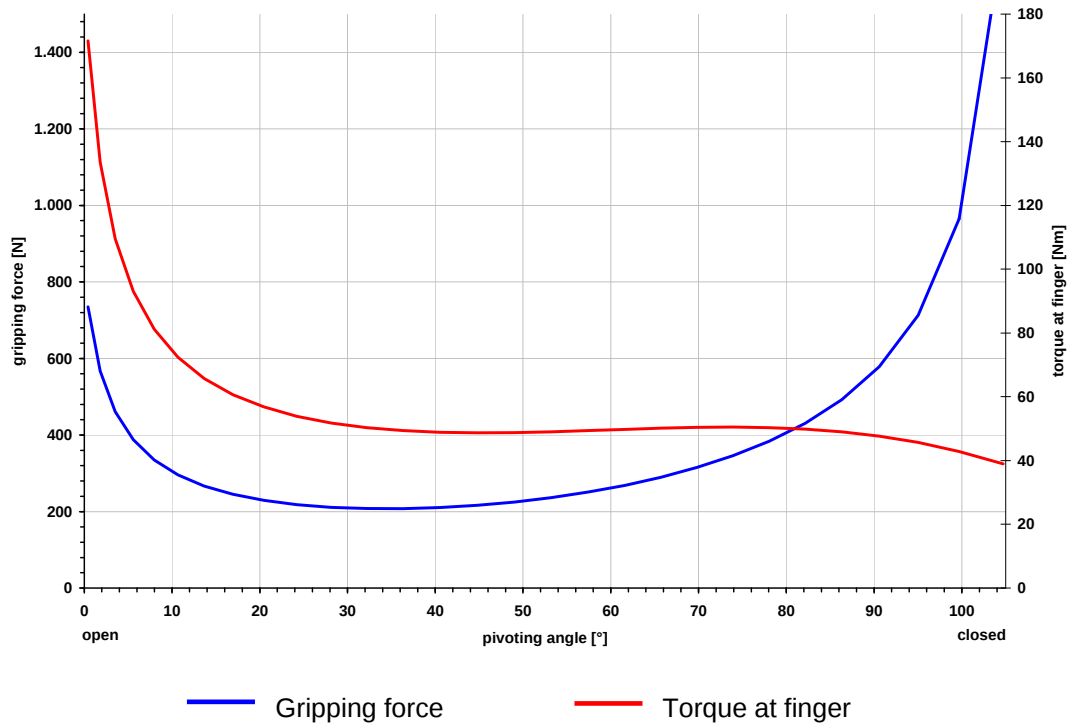
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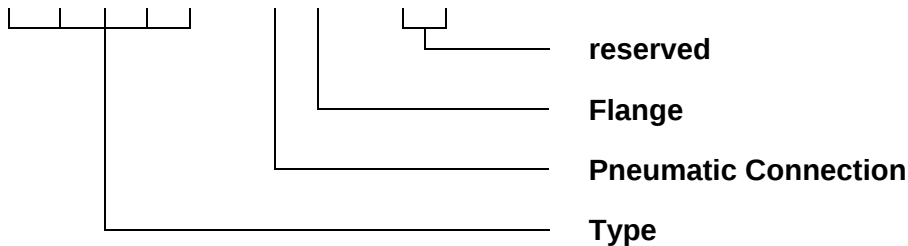
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Diagram



Order Number

P W 2 0 6 - **O** **N** - **0 0**



Pneumatic Connection	
Style	Ident.
Pneumatic Connection Top/Bottom	O
Pneumatic Connection at Bottom Plate (Flange)	F

Flange	
Style	Ident.
Without Flange	O
With Flange	N
With Side Flange	S
With 2 Side Flange	2



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