

## Sealed Clamshell Bucket Gripper - Type SG10 -

### Characteristics:

- ideal for gripping bulk good like granules or standard parts
- radial bucket movement
- short cycle time
- completely sealed mechanics
- user defined installation position
- maintenance free up to 10 million movements
- compact design
- modular design
- multiple position checks through proximity switches (optional)
- customized buckets available on request



### Technical Specifications

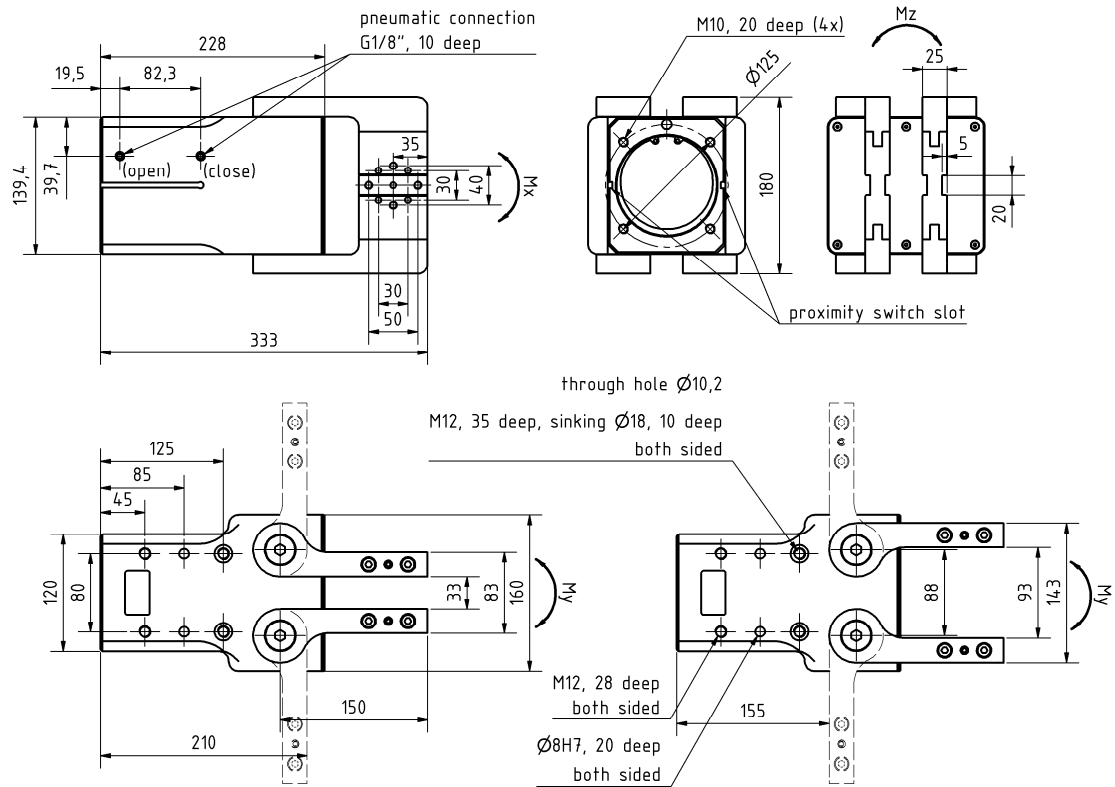
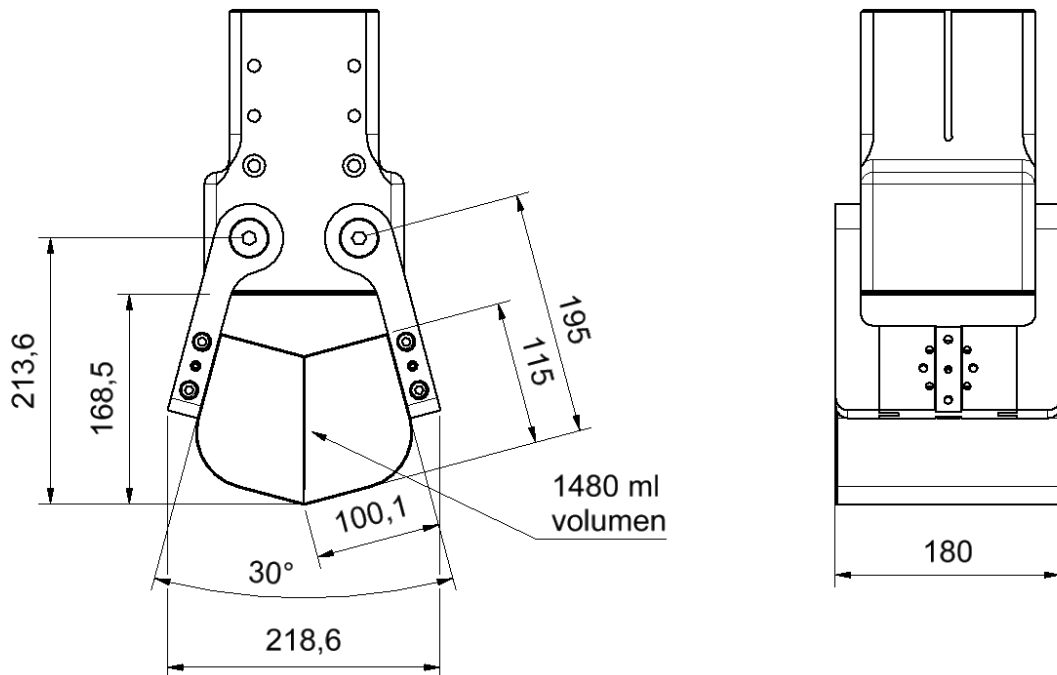
<b>Type</b>		<b>SG10</b>
<b>Drive</b>		pneumatic
<b>max. Grip Force (at 6 bar) *</b>		660 N
<b>max. Torque (at 6 bar) **</b>		144 Nm
<b>Operating Air Pressure</b>		0,5 to 6 bar
<b>Cycle Time</b>	<b>Open</b>	0,15 s
	<b>Close</b>	0,15 s
<b>Repeat Accuracy</b>		0.1 mm
<b>Energy Consumption per Cycle</b>		0.1 liter (at 6 bar)
<b>Operating Temperature</b>		-30 to +80°C
<b>Mass</b>		12 kg
<b>Loading Capacity* per bucket with Gripping Mass and Acceleration</b>	$Mx_{max.}$	250 Nm
	$My_{max.}$ (Gripping)	144 Nm
	$Fz_{max.}$	20000 N
	$Mz_{max.}$	150 Nm

\* At buckets outer edge in completely closed position

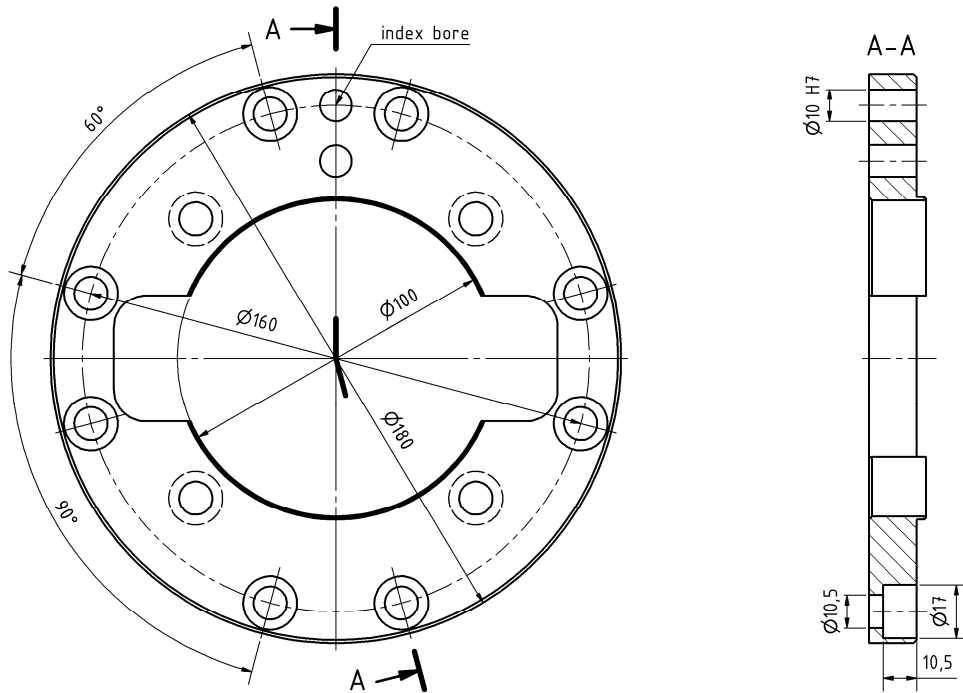
\*\* Grip force per bucket is half of this torque divided by distance to the axis

By using the given torque M [Nm], the necessary air pressure  $p_{req}$  can be calculated with the following formula when the buckets are closed:

$$0,5 \text{ bar} \leq p = \frac{M}{24 \text{ Nm}} \leq 6 \text{ bar}$$

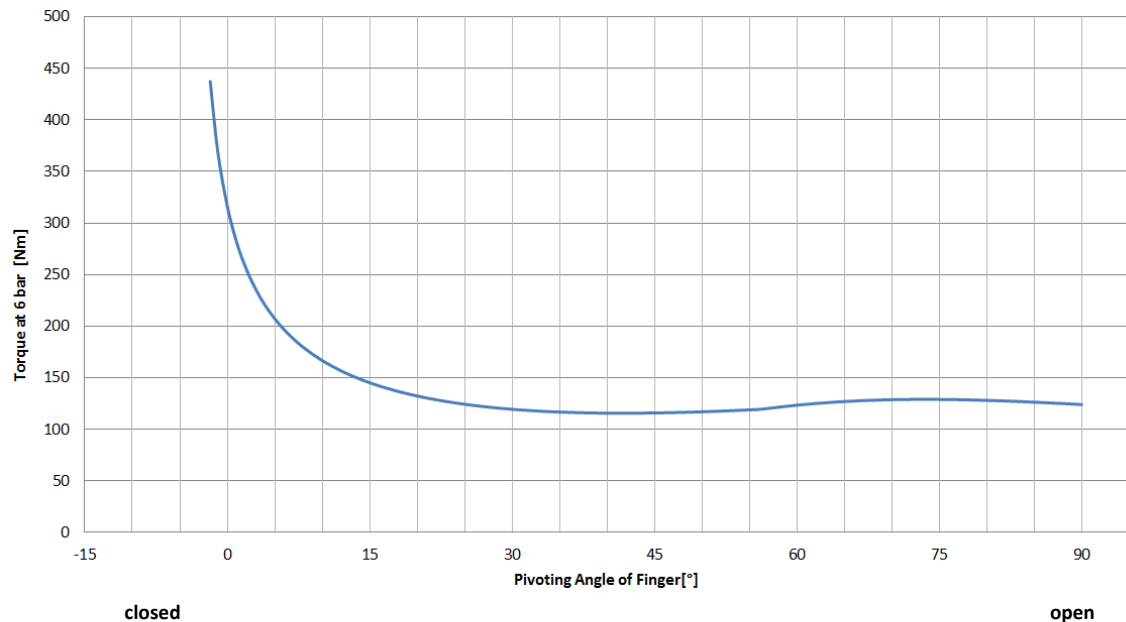
**Type SG10 (Body + Doublefinger)**

**Type SG10 (Standard Buckets)**


## Flange



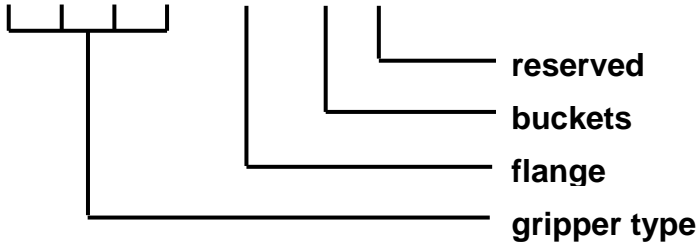
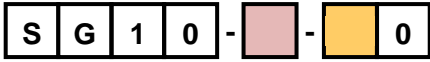
Used to mount the gripper to a robot

## Diagram



Torque curve also available in mirrored version upon request.

## Order Number



Flange	
style	ident
with flange	N
without flange	O

Bucket	
style	ident
with standard bucket	S
without standard bucket	O