

RCP2CR-GRSS

Cleanroom ROBO Cylinder, 2-Finger Gripper, Mini Slider Type, Actuator Width 42mm, Pulse Motor

Model Specification Items	RCP2CR — GRSS — I — 20P — 30 — 8 — — —
	Series — Type — Encoder type — Motor type — Deceleration Ratio — Stroke — Applicable controller — Cable length — Options
	I: Incremental * The Simple absolute encoder is also considered type "I". 20P: Pulse motor, 20□ size 30: 1/30 deceleration ratio 8: 8mm (4mm per side) P1: PCON-PL/PO/SE PSEL P3: PCON-CA PMEC/PSEP MSEP N: None P: 1m S: 3m M: 5m X□□: Custom Length See Options below.

* See page Pre-47 for details on the model descriptions.



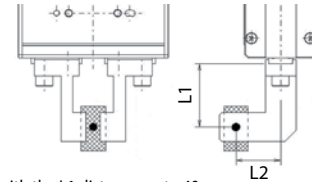
Technical References Appendix P.5



- (1) The maximum opening/closing speed indicates the operating speed on one side. The relative operating speed is twice this value.
- (2) The maximum gripping force is the sum of the gripping forces of both fingers, at a gripping point where there is no offset or overhanging distance. The work piece weight that can be actually moved depends on the friction coefficient between the gripper fingers and the work piece, as well as on the shape of the work piece. As a rough guide, a work piece's weight should not exceed 1/10 to 1/20 of the gripping force. (See page A-86 for details.)
- (3) The rated acceleration while moving is 0.3G.

■ Gripping Force vs. Current Limit

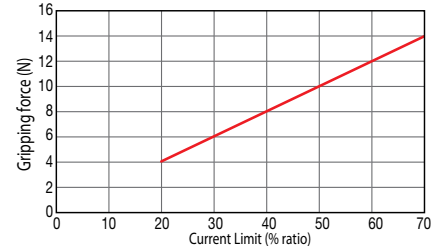
The gripping (pushing) force can be adjusted freely within the range of current limits of 20% to 70%.



* Operate with the L1 distance up to 40mm.

* The gripping force value in the graph below is when both L1 and L2 are at 0 mm. (For gripping force reference per L1 distance, see page A-87.)

The gripping force value is the sum of gripping forces of both fingers.



* The gripping force graph above shows the number of references. Please allow margins up to ± 15%.

* Please note that, when gripping (pushing), the speed is fixed at 5mm/s.

Actuator Specifications

■ Lead and Payload

Model number	Deceleration Ratio	Maximum Gripping Force (N)	Stroke (mm)
RCP2CR-GRSS-I-20P-30-8-①-②-③	30	14 (7 per side)	8 (4 per side)

Code explanation ① Applicable Controller ② Cable length ③ Options

■ Stroke and Max. Speed/Suction Volume

Deceleration ratio	Stroke	Suction Volume (Nℓ/min)
	8 (mm)	
30	78	10

(Unit: mm/s)

Stroke

Stroke (mm)	Standard price
8	—

② Cable Length

Type	Cable symbol	Standard price
Standard (Robot Cables)	P (1m)	—
	S (3m)	—
	M (5m)	—
Special length	X06 (6m) ~ X10 (10m)	—
	X11 (11m) ~ X15 (15m)	—
	X16 (16m) ~ X20 (20m)	—
		—

* The standard cable is the motor-encoder integrated robot cable.

* See page A-59 for cables for maintenance.

③ Options

Name	Option code	See page	Standard price
Non-motor end specification	NM	→ A-52	—
Flange bracket	FB	→ A-43	—
Shaft bracket	SB	→ A-55	—

Actuator Specifications

Item	Description
Drive System	Worm gear + helical gear + helical rack
Positioning repeatability	±0.01mm
Backlash	0.2mm or less per side (constantly pressed out by a spring)
Lost motion	0.05mm or less per side
Guide	Linear guide
Allowable static load moment	Ma: 0.5 N·m, Mb: 0.5 N·m, Mc: 1.5 N·m
Weight	0.2kg
Cleanliness	Class 10 (0.1μm)
Ambient operating temperature, humidity	0 to 40°C, 85% RH or less (Non-condensing)

