

RCP2CR-GRS

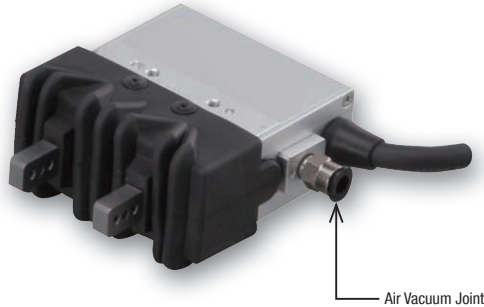
Cleanroom ROBO Cylinder, 2-finger Gripper, Small Slider Type, 74mm Width, Pulse Motor

RCP2W-GRS

Dust-proof ROBO Cylinder, 2-finger Gripper, Small Slider Type, 74mm Width, Pulse Motor

Model Specification Items	RCP2CR RCP2W Series	GRS Type	I Encoder	20P Motor	1 Deceleration Ratio	10 Opening/ Closing Stroke	Applicable Controllers	Cable Length	Options
	RCP2CR: Cleanroom RCP2W : Dust-proof		I: Incremental	20P: Pulse motor 20□size	1: Deceleration ratio 1/1	10: 10mm (5mm per finger)	P1: PCON-PL/PO/SE PSEL P3: PCON-CA PMEC/PSEP MSEP	N: None P: 1m S: 3m M: 5m X□□ : Custom R□□ : Robot cable	FB: Flange bracket SB: Shaft bracket VL: L-shaped vacuum joint specification

RoHS



Air Vacuum Joint

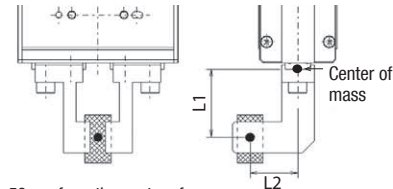
* The figure above shows the Cleanroom Type.
There is no air vacuum joint equipped on the Dust-proof Type.

POINT
Note on selection

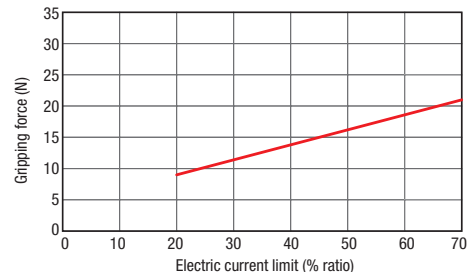
- (1) The maximum opening/closing speed indicates the operating speed on one side. The relative operating speed is twice this value.
- (2) The maximum gripping force is the sum of the gripping forces of both fingers, at a gripping point where there is no offset or overhang distance. The work part weight that can be actually moved depends on the friction coefficient between the gripper fingers and the work part, as well as on the shape of the work part. As a rough guide, a work part's weight should not exceed 1/10 to 1/20 of the gripping force.
* The gripping point O should be the center of mass in the drawing.
- (3) Refer to "How to Select Gripper" at the end of the ROBO Cylinder General Catalog for how to select a gripper.
- (4) The rated acceleration while moving is 0.3G.

Correlation Diagram of Gripping Force and Electric Current Limit

By pressing motion, the gripping (pushing) force can be adjusted freely within the range of electric current limits of 20% to 70%.



- * Keep L1 within 50mm from the center of mass.
- * The gripping force in the graph below assumes that L1 and L2 in the figure above are zero. Also note that the gripping force is a sum of gripping forces of both fingers.



* The gripping force graph above shows reference numbers. Please allow margins up to ±15%.

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

Actuator Specifications

Max. Gripping Force and Stroke

Model Number	Deceleration Ratio	Max. Gripping Force (N)	Stroke (mm)
RCP2CR-GRS-I-20P-1-10-①-②-③	1	21	10
RCP2W-GRS-I-20P-1-10-①-②-③		(10.5 per finger)	(5 per finger)

Legend: ① Applicable controllers ② Cable length ③ Options

Stroke and Max. Opening/Closing Speed / Suction Amount

Deceleration Ratio	Stroke	10 (mm)	Suction Amount (*)
1		33.3mm/s (Per finger)	10Nℓ/min

* For Cleanroom Type

Stroke

Stroke (mm)	Specification	Standard Price
10	Cleanroom	—
	Dust-proof	—

② Cable Length

Type	Cable Code	Standard Price	
		Applicable Controller Code	
		P3	P1
Standard Type	P (1m)	—	—
	S (3m)	—	—
	M (5m)	—	—
Special Length	X06 (6m) ~ X10 (10m)	—	—
	X11 (11m) ~ X15 (15m)	—	—
	X16 (16m) ~ X20 (20m)	—	—
Robot Cable	R01 (1m) ~ R03 (3m)	—	Robot cable is standard for P1
	R04 (4m) ~ R05 (5m)	—	
	R06 (6m) ~ R10 (10m)	—	
	R11 (11m) ~ R15 (15m)	—	
	R16 (16m) ~ R20 (20m)	—	
		—	

③ Options

Name	Option Code	Standard Price
Flange Bracket	FB	—
Shaft Bracket	SB	—
L-shaped Vacuum Joint Specification (Cleanroom Only)	VL	—

<Option Code>

FB...Bracket only: RCP2-FB-GRS

SB...Bracket only: RCP2-SB-GRS

* Check the size of the bracket in the option explanation at the end of the ROBO Cylinder General Catalog.

Actuator Specifications

Item	Description	
	Cleanroom	Dust-proof
Drive System	Timing belt + trapezoidal screw (1.5 lead)	
Positioning Repeatability	±0.01mm	
Backlash	0.15mm or less per finger (constantly pressed out by a spring)	
Lost Motion	0.1mm or less per finger	
Allowable Static Load Moment	Ma: 6.3N·m Mb: 6.3N·m Mc: 7.0N·m	
Guide	Cross roller guide	
Cleanliness	Class 10 (0.1μm)	
IP Code	— IP50	
Weight	0.42kg	
Operating Environment	Temperature 0~40°C Humidity 20~85% RH or less (non-condensing)	

