Air Gripper Unit

for Collaborative Robots

Compliant with the UR (e) Series

UNIVERSAL ROBOTS

collaborative robot

Plug and Play

configuration for immediate use

URCap Easy programming

UNIVERSAL ROBOTS+ Certified

JMHZ2-X7400B

More information can be viewed here.

Plug and Play

Air Gripper Unit for Collaborative Robots

UNIVERSAL ROBOTS

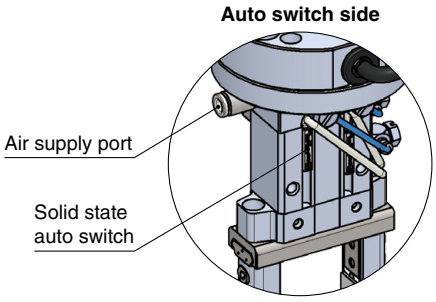
For use with: UR3(e), UR5(e), UR10(e), UR16e series

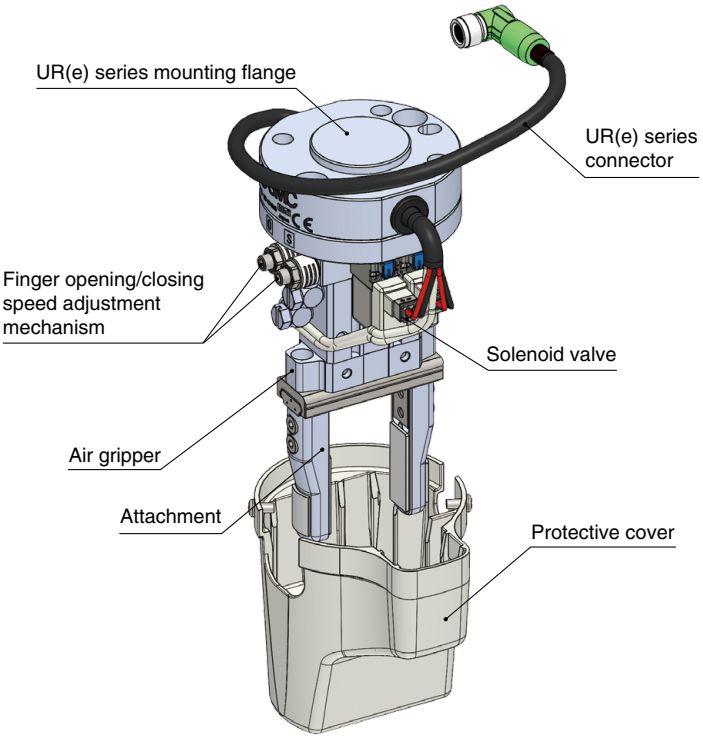
- **Compact, lightweight product with high gripping force due to air operation**
- **An air gripper that realizes high rigidity and high precision due to its guide-integrated construction**

With high-precision linear guide
Repeatability: ±0.01 mm

Linear guide of the higher rigidity and precision is used.
Higher rigidity (Compared with the same size of the existing MHZ2)

- **Operate by simply connecting 1 air supply tube and an electrical wiring M8 connector.**
- **Integrated solenoid valve, speed adjustment mechanism, and auto switch**
- **URCap**
- **Component Parts**





How to Order

CE RoHS

JMHZ2-16D-X7400B

Specifications

Bore size [mm]		16
Fluid		Air
Action		Double acting
Operating pressure [MPa]		0.1 to 0.7
Repeatability [mm]		±0.01
Gripping force Effective value per finger [N]	External	32.7
	Internal	43.5
Opening/Closing (Both sides) [mm]		10
Weight [g]		430
Standards		ISO9409-1-50-4-M6
Auto switch model		D-M9P-5
Connector type		M8 8-pin connector (Socket)

Included parts: Mounting bolt, Positioning pin, Piping tube (ø4 x 2 m)

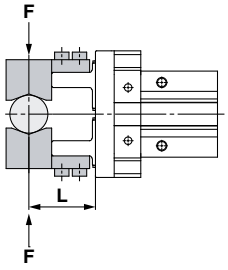
Characteristics

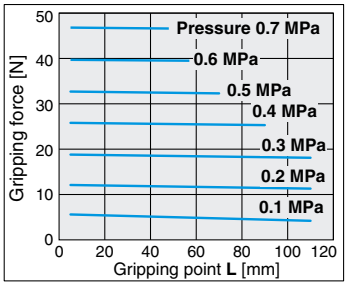
Gripping force

● **Indication of effective gripping force**

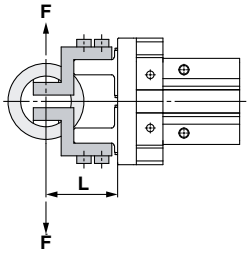
The gripping force shown in the graphs below represents the gripping force of one finger when all fingers and attachments are in contact with the workpiece. **F** = One finger thrust

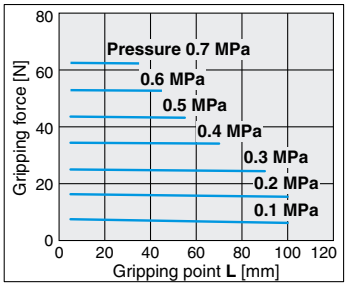
External gripping force





Internal gripping force



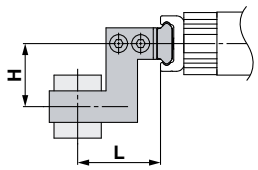


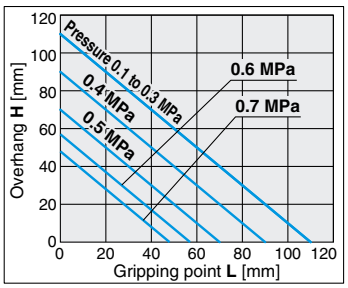
Gripping point

● The air gripper should be operated so that the workpiece gripping point “L” and the amount of overhang “H” stay within the range shown for each operating pressure given in the graphs below.

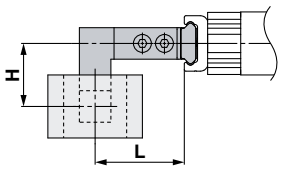
● If the workpiece gripping point goes beyond the range limits, this will have an adverse effect on the life of the air gripper.

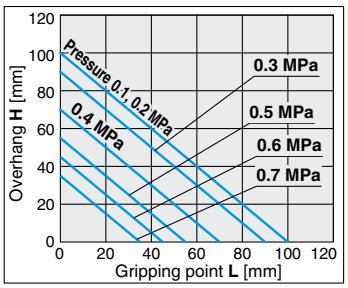
External grip



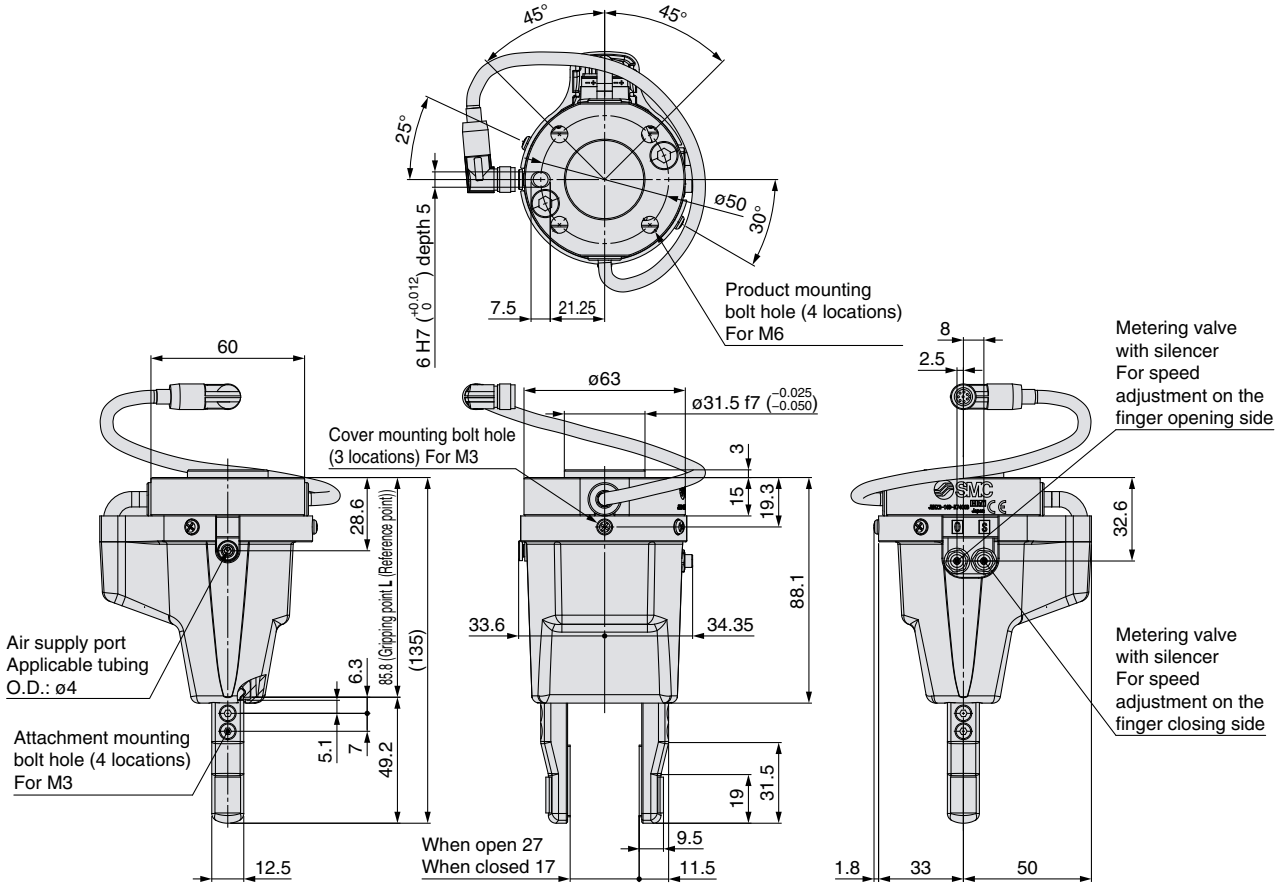


Internal grip





Dimensions



URCap

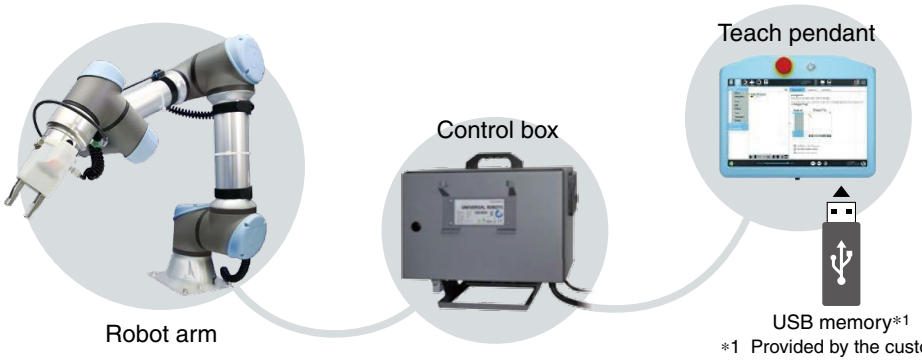
More information on the URCap software can be viewed here.

Easy programming

By using the dedicated software certified for Universal Robots, URCap, the teaching pendant can conduct various operations intuitively, allowing for sensor signals to be easily incorporated.

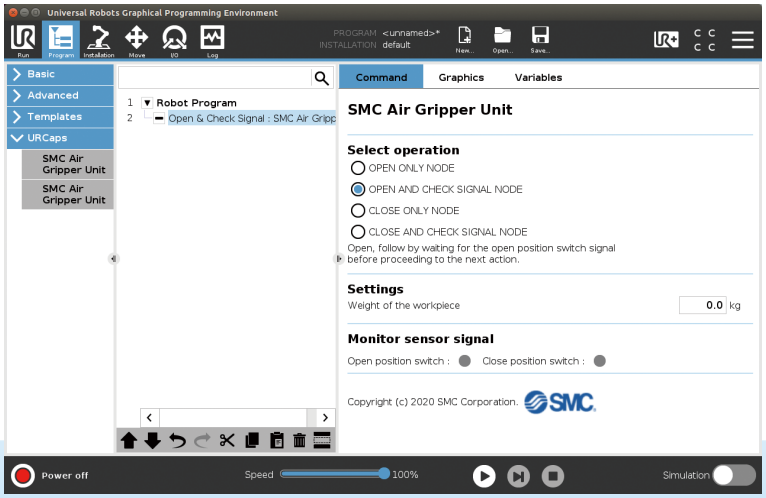
Save a copy of the URCap software to a USB memory and insert it into the teaching pendant to easily install the software.

∗ Please download the URCap software from the website, and save it to a USB memory.



∗1 Provided by the customer
(Saved copy of URCap software)

Air gripper unit program screen



UNIVERSAL ROBOTS+
Certified

⚠ Safety Instructions Be sure to read the “Handling Precautions for SMC Products” (M-E03-3) and “Operation Manual” before use.