RCP6-GRT7A

2-Finger Gripper | Slim Slide Type | Body Width 66 mm | 24V Pulse Motor

■ Model Specification Items

RCP6 — GRT7A — WA — 28P — 1 — 30 — ☐ — ☐ — ☐ — ☐

Series	Type	Encoder Type	Motor Type	Gear Ratio Pattern	Stroke	Applicable Controllers	Cable Length	Options
		WA: Battery-less Absolute	28P: Pulse Motor 28□ Size	1: Lead Screw 1.5mm Pulley Reduction Ratio 1.5	30: 30mm	P3: PCON MCON MSEL P5: RCM-P6PC (Coming soon)	N: None P: 1m S: 3m M: 5m X□□: Specified Length	Please refer to the option price list below. * Be sure to fill in one of the following options for the cable exit direction.

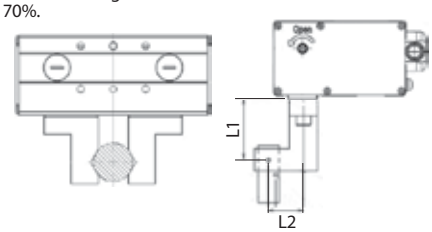
* Does not include a controller.
* Please refer to P.2 for more information about the model specification items.

CE RoHS

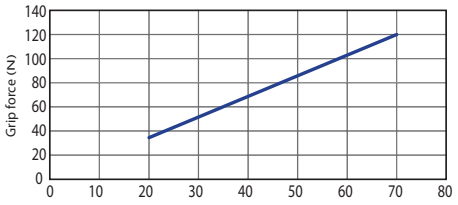
Horizontal | Vertical | Side | Ceiling

■ Gripping Force vs. Electric Current Limit

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



* For L1 and L2, please refer to the gripper selection method on P.9.
* The gripping force in the graph below assumes that L1 and L2 the figure above are zero. (Refer to p.10 for the rough guide gripping force at each distance of L1.) Also note that the gripping force is the sum of the gripping forces of both fingers.



* Grip force is the sum of both fingers

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

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

POINT Selection Notes

(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 workpiece weight that can be actually moved depends on the friction coefficient between the gripper fingers and the workpiece, as well as on the shape of the workpiece. As a rough guide, a workpiece 's weight should not exceed 1/10 to 1/20 of the gripping force. (See page 9 for details.)
(3) The rated acceleration while moving is 0.3 G.

Actuator Specifications

Model specification items	Gear ratio pattern	Max grip force (N)	Stroke (mm)
RCP6-GRT7A-WA-28P-1-30-①-②-③	1	120 (one side 60)	30 (one side 15)

Legend: ① Applicable Controllers ② Cable Length ③ Options

■ Stroke and Max Opening/Closing Speed

Gear ratio pattern \ Stroke	30 (mm)
1	75

(Unit: mm/s)

Cable Length

Type	Cable code
Standard type	**P**(1m)
	S(3m)
	M(5m)
Specified length	**X06** (6m) ~ **X10** (10m)
	X11 (11m) ~ **X15** (15m)
	X16 (16m) ~ **X20** (20m)*
Robot cable	**R01** (1m) ~ **R03** (3m)
	R04 (4m) ~ **R05** (5m)
	R06 (6m) ~ **R10** (10m)
	R11 (11m) ~ **R15** (15m)
	R16 (16m) ~ **R20** (20m)*

Cable between actuator and controller.
* When changing the actuator cable length as an option, make sure the total cable length between the actuator and the controller is within 20m.

Actuator Specifications

Item	Description
Drive system	Timing belt + left/right trapezoidal screw ø8
Positioning repeatability	±0.01mm
Backlash	One side 0.2mm or less
Lost motion	One side 0.2mm or less
Allowable static moment	Ma: 3.6N·m Mb: 3.6N·m Mc: 10.2N·m
Mass	0.46kg
Ambient operating temperature/humidity	0~40°C, 85% RH or less (non-condensing)

Options *

* Be sure to select a symbol for the cable exit direction.

Name	Option code	Reference page
Actuator cable length 1 m specification	**AC1**	P. 8
Actuator cable length 2 m specification	**AC2**	P. 8
Actuator cable length 3 m specification	**AC3**	P. 8
Rear cable exit direction (top)	**CJTB**	P. 8
Rear cable exit direction (left)	**CJLB**	P. 8
Rear cable exit direction (right)	**CJRB**	P. 8

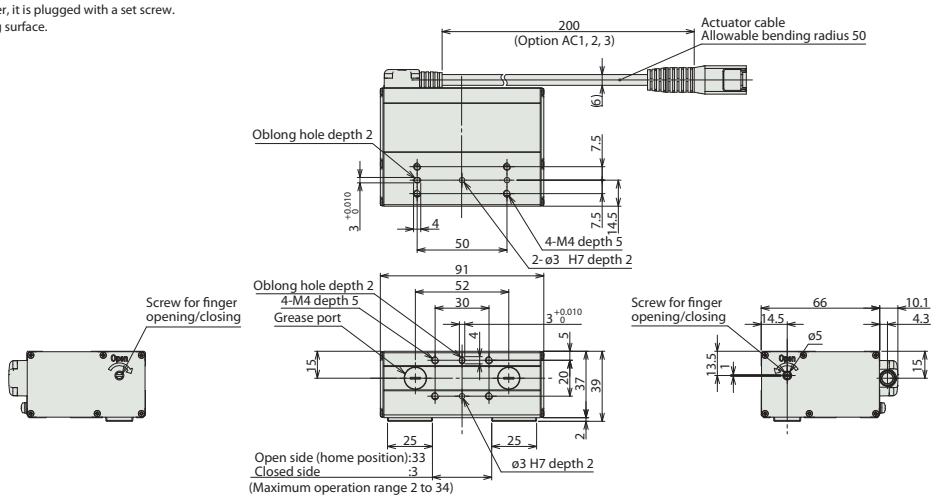
Name	Option code	Reference page
Rear cable exit direction (bottom)	**CJBB**	P. 8
Side cable exit direction (top)	**CJTS**	P. 8
Side cable exit direction (left)	**CJLS**	P. 8
Side cable exit direction (right)	**CJRS**	P. 8
Side cable exit direction (bottom)	**CJBS**	P. 8
Non-motor end specification	**NM**	P. 8

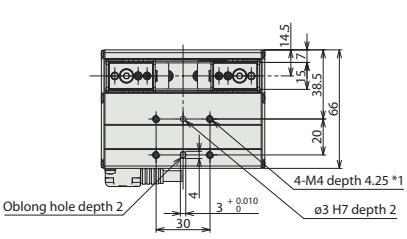
Dimensions

CAD drawings can be downloaded from our website.
www.robocylinder.de

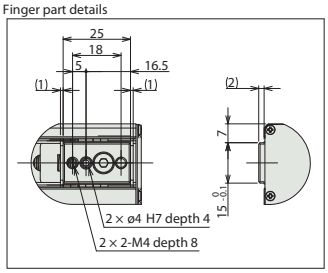
2D CAD 3D CAD

* The open side of the finger is at home position.
*1 To prevent intrusion of foreign matter, it is plugged with a set screw.
Remove when using it as a mounting surface.

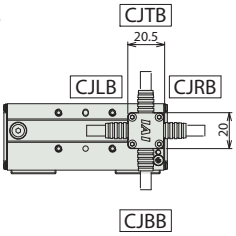


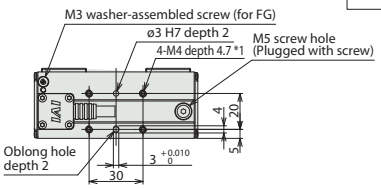


Finger part details

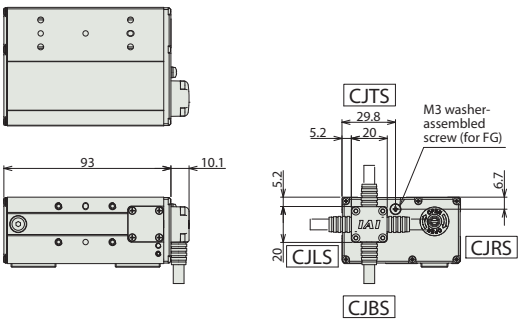


For CJ*B





For CJ*S



Applicable Controllers

The RCP6 series actuators can be operated by the controllers indicated below. Please select the type depending on your intended use.

Name	External view	Max. number of connectable axes	Power supply voltage	Control method				Maximum number of positioning points	Reference page
				Positioner	Pulse-train	Program	Network * I/O type selection		
PCON-CYB/PLB/POB (Coming soon)		1	24VDC	● * Controller type selection	● * Controller type selection	–	Network cannot be selected	64	Plea see the dedicated catalog or manual.
PCON-CB/CGB		1		● * I/O type selection	● * I/O type selection	–	DeviceNet, CC-Link, PROFIBUS, CompoNet, EtherCAT, EtherNet/IP	512 (768 for network spec.)	
MCON-C/CG		8		This model is network-compatible only.				256	
MCON-LC/LCG (Coming soon)		6		–	–	●		256	
MSEL-PC/PG		4	Single phase 100~230VAC	–	–	●	Note: · The type of compatible networks will vary depending on the controller. Please refer to reference page for more information.	30000	
RCM-P6PC (Coming soon)		1	Can be used within the RCP6S Gateway system.					768	Refer to the RCP6S fieldnetwork manual.