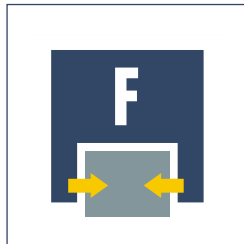




**Sizes**  
29 .. 140



**Weight**  
0.025 kg .. 2.55 kg



**Gripping force**  
30 N .. 1180 N

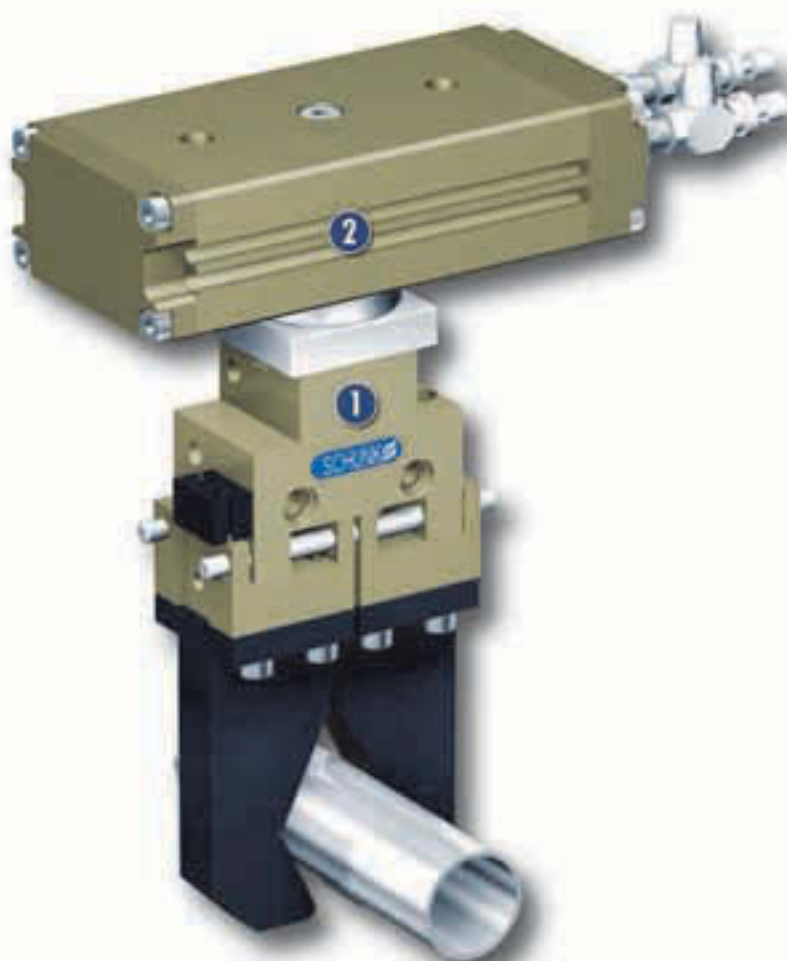


**Stroke per finger**  
2 mm .. 15 mm



**Workpiece weight**  
0.15 kg .. 5.9 kg

### Application example



Reversing unit for the economical reorientation of cylindrical bar material



**PGM 50 2-Finger Parallel Gripper with workpiece-specific gripper fingers**



**MRU 14.1-E-0 Miniature Rotary Actuator**

## Universal Gripper

Universal, economical 2-finger parallel gripper

### Area of application

for universal use in clean environments

### Your advantages and benefits

#### Economical gripper series

for material handling

#### Rod guide for base jaws

for excellent guidance characteristics

#### Cylinder rod guidance

for versatility and a long tool life

#### Compact design

for minimal interfering contours in the application



### General information on the series

#### Working principle

Internal wedge-hook kinematics

#### Housing material

Aluminum alloy, hard-anodized

#### Guide

Steel guide, ground and hardened

#### Actuation

Pneumatic, with filtered compressed air (10 µm): Dry, lubricated or non-lubricated

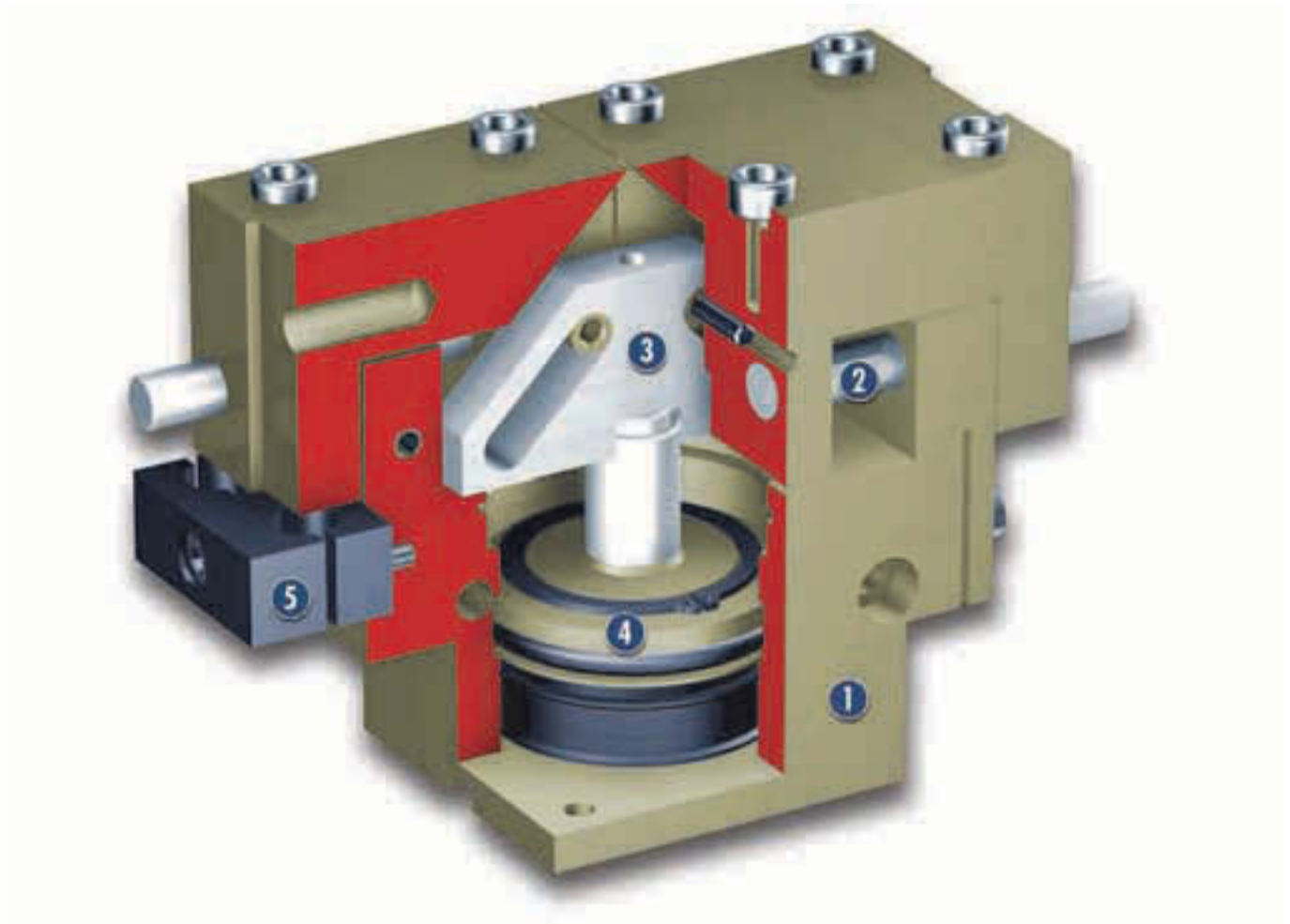
#### Warranty

24 months

#### Scope of delivery

Brackets for proximity switches, centering sleeves, assembly and operating manual with manufacturer's declaration

### Sectional diagram



- 1 Housing**  
weight-reduced through the use of a hard-anodized, high-strength aluminum alloy
- 3 Kinematics**  
internal, power transmission via line contact
- 5 Sensor system**  
mounting brackets for inductive proximity switches
- 2 Rod guide**  
simple yet resilient
- 4 Drive**  
using tried and tested pneumatic piston drive

### Function description

The piston is moved up and down by compressed air. The wedge hook, together with the transverse rods of the base jaws, transforms the piston motion into synchronized opening and closing.

### Options and special information

The PGM series is a product line with an important cost/benefit ratio.

## Accessories

SCHUNK accessories — the suitable complement for the highest level of functionality, reliability and controlled production of all automation modules.

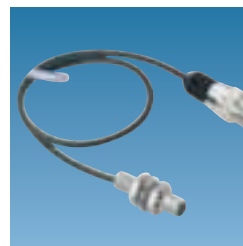
Centering sleeves



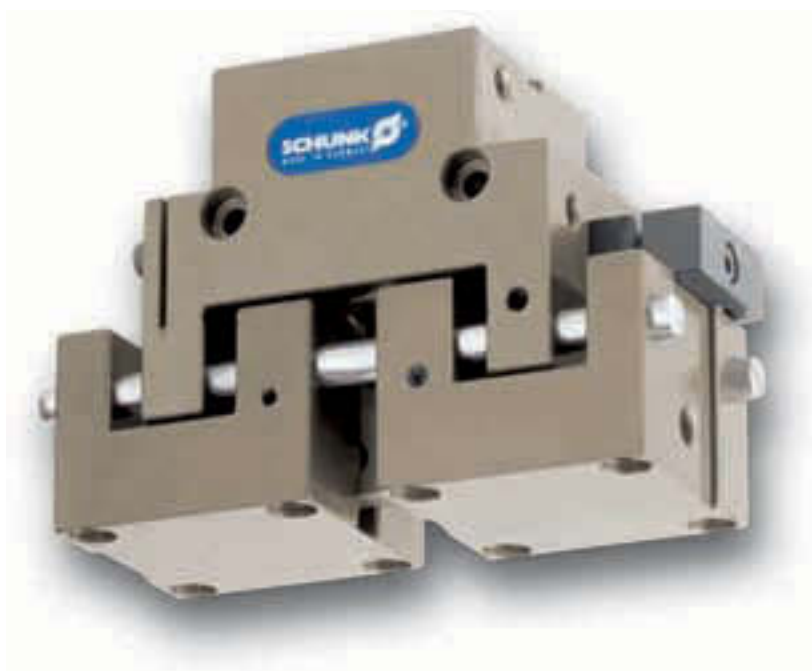
Fittings



IN inductive proximity switches



W/WK/KV/GK sensor cables



V sensor distributors



SDV-P pressure maintenance valves



① For the exact size of the required accessories, availability of this size and the designation and ID, please refer to the additional views at the end of the size in question. You can find more detailed information on our accessory range in the "Accessories" catalog section.

## General information on the series

### Gripping force

is the arithmetic total of the gripping force applied to each base jaw at distance P (see illustration), measured from the upper edge of the gripper.

### Finger length

is measured from the upper edge of the gripper housing in the direction of the main axis.

### Repeat accuracy

is defined as the spread of the limit position after 100 consecutive strokes.

### Workpiece weight

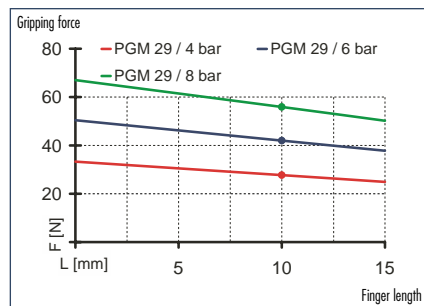
The recommended workpiece weight is calculated for a force-type connection with a coefficient of friction of 0.1 and a safety factor of 2 against slippage of the workpiece on acceleration due to gravity g. Considerably heavier workpiece weights are permitted with form-fit clamping.

### Closing and opening times

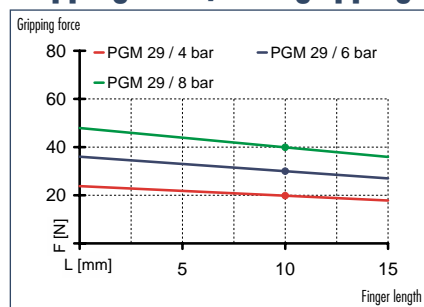
Closing and opening times are purely the times that the base jaws or base fingers are in motion. Valve switching times, hose filling times or PLC reaction times are not included in the above times and must be taken into consideration when determining cycle times.



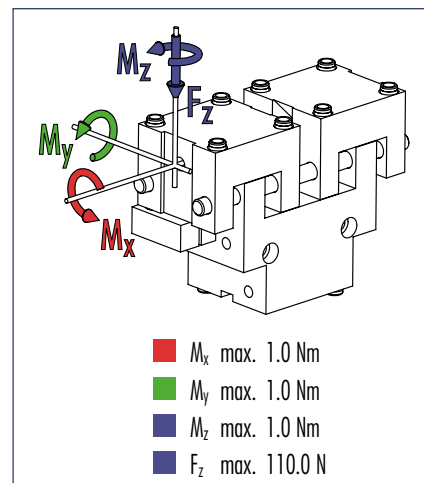
### Gripping force, I.D. gripping



### Gripping force, O.D. gripping



### Finger load

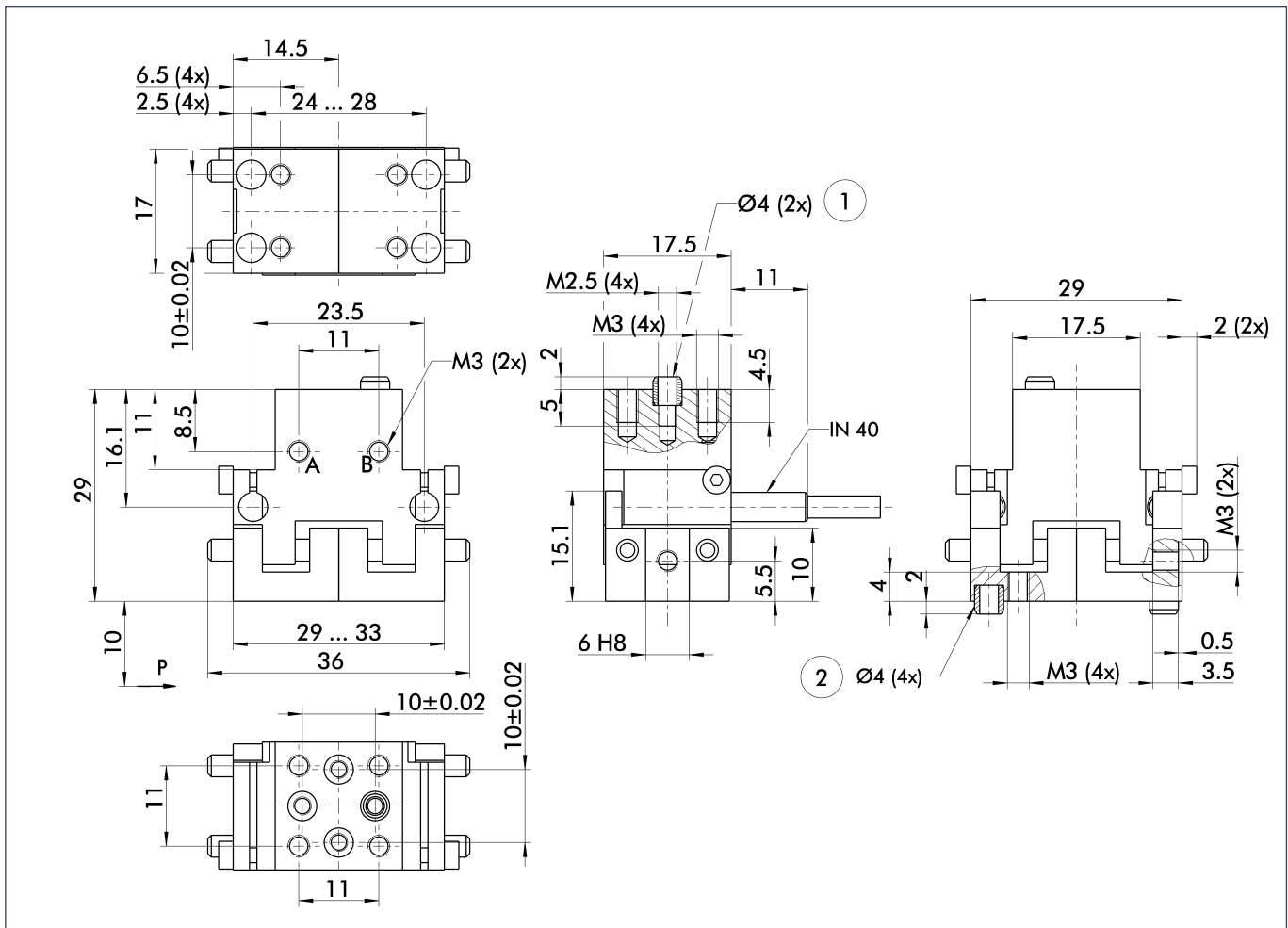


① Moments and forces apply per base jaw and may occur simultaneously.  $M_y$  may arise in addition to the moment generated by the gripping force itself. If the max. permitted finger weight is exceeded, it is imperative to throttle the air pressure so that the jaw movement occurs without any hitting or bouncing. Service life may be reduced.

## Technical data

Description	PGM 29
	<b>0302680</b>
Stroke per finger	[mm] 2.0
Closing force	[N] 30.0
Opening force	[N] 40.0
Weight	[kg] 0.025
Recommended workpiece weight	[kg] 0.15
Air consumption per double stroke	[cm <sup>3</sup> ] 0.16
Nominal pressure	[bar] 6.0
Minimum pressure	[bar] 2.0
Maximum pressure	[bar] 8.0
Closing time	[s] 0.03
Opening time	[s] 0.03
Max. permitted finger length	[mm] 15.0
Max. permitted weight per finger	[kg] 0.01
IP rating	30
Min. ambient temperature	[°C] -10.0
Max. ambient temperature	[°C] 90.0
Repeat accuracy	[mm] 0.02

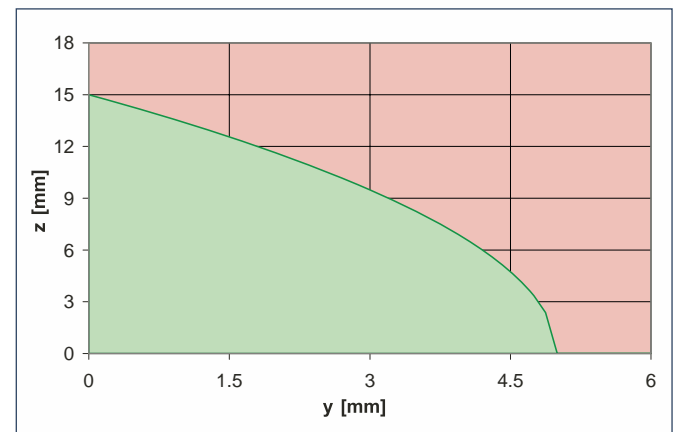
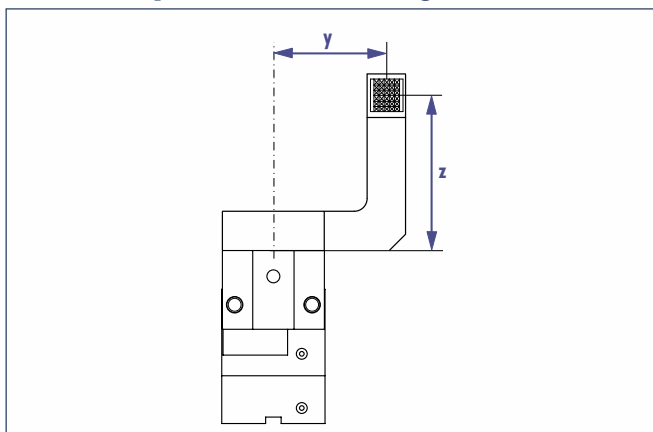
### Main views



The drawing shows the gripper in the basic version with closed jaws, the dimensions do not include the options described below.

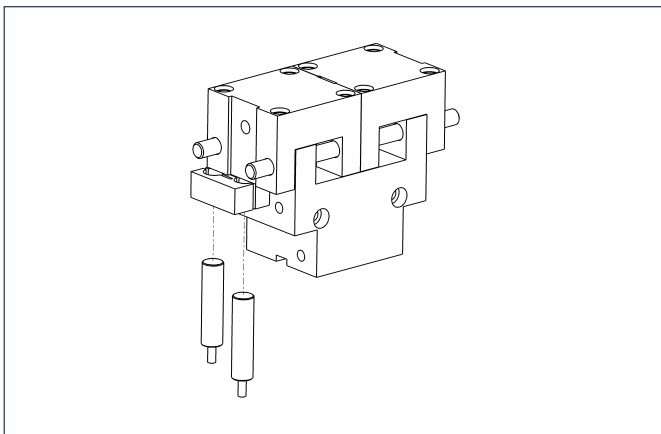
- A,a Main/direct connection, gripper opening
- B,b Main/direct connection, gripper closing
- ① Gripper connection
- ② Finger connection

### Maximum permitted overhang



- Permitted range
- Non-permissible range

### Sensor system



#### End position monitoring:

Inductive proximity switches, for direct mounting

Description	ID	Recommended product
IN 40/S-M12	0301574	
IN 40/S-M8	0301474	•
INK 40/S	0301555	

- ① Two sensors (NO contacts) are required for each gripper, plus extension cables as an option.

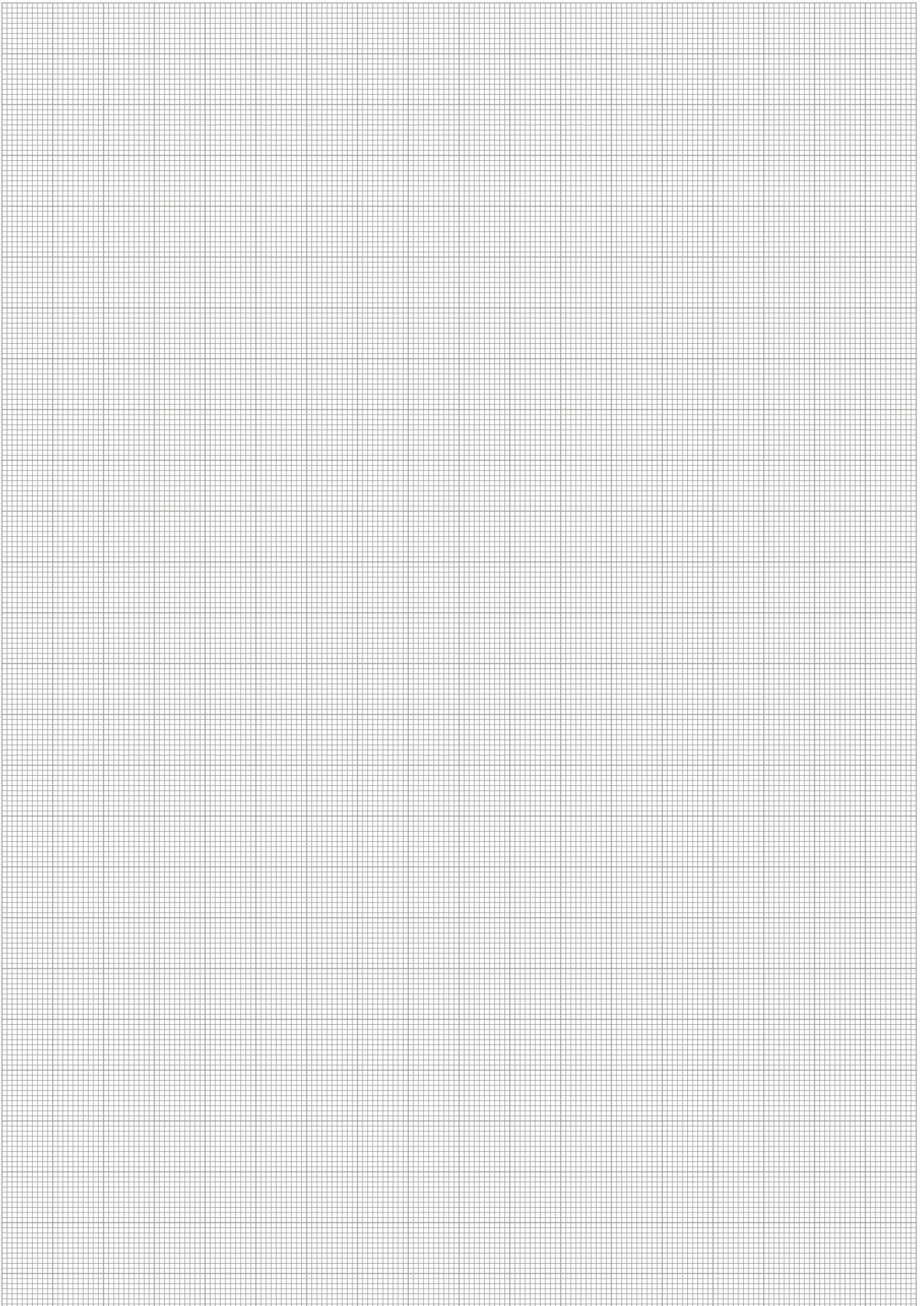
#### Extension cables for proximity switches/magnetic switches

Description	ID
GK 3-M8	0301622
KV 10-M12	0301596
KV 10-M8	0301496
KV 20-M12	0301597
KV 20-M8	0301497
KV 3-M12	0301595
KV 3-M8	0301495
W 3-M12	0301503
W 5-M12	0301507
WK 3-M8	0301594
WK 5-M8	0301502

- ① Please note the minimum permitted bending radii for the sensor cables, which are generally 35 mm.



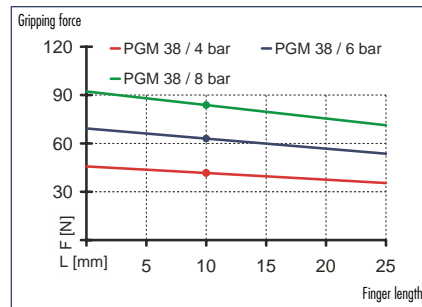
You can find more detailed information and individual parts of the above-mentioned accessories in the “Accessories” catalog section.



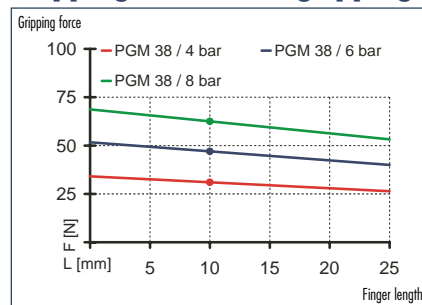




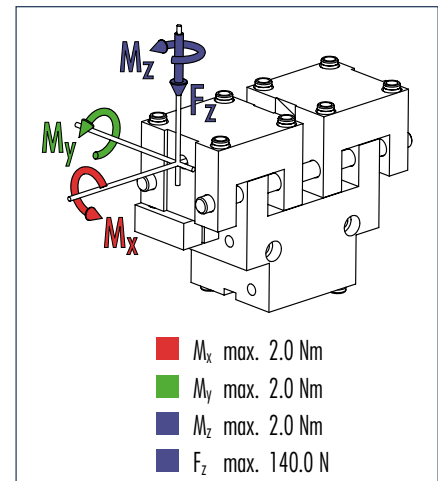
### Gripping force, I.D. gripping



### Gripping force, O.D. gripping



### Finger load



① Moments and forces apply per base jaw and may occur simultaneously.  $M_y$  may arise in addition to the moment generated by the gripping force itself. If the max. permitted finger weight is exceeded, it is imperative to throttle the air pressure so that the jaw movement occurs without any hitting or bouncing. Service life may be reduced.

## Technical data

Description	PGM 38
	0302681
Stroke per finger	[mm] 3.0
Closing force	[N] 47.0
Opening force	[N] 63.0
Weight	[kg] 0.05
Recommended workpiece weight	[kg] 0.235
Air consumption per double stroke	[cm <sup>3</sup> ] 0.34
Nominal pressure	[bar] 6.0
Minimum pressure	[bar] 2.0
Maximum pressure	[bar] 8.0
Closing time	[s] 0.03
Opening time	[s] 0.03
Max. permitted finger length	[mm] 25.0
Max. permitted weight per finger	[kg] 0.017
IP rating	30
Min. ambient temperature	[°C] -10.0
Max. ambient temperature	[°C] 90.0
Repeat accuracy	[mm] 0.02

Technical drawing of a 4/3-way solenoid valve, showing three views: front, side, and top, along with detailed cross-sections A and B.

**Dimensions:**

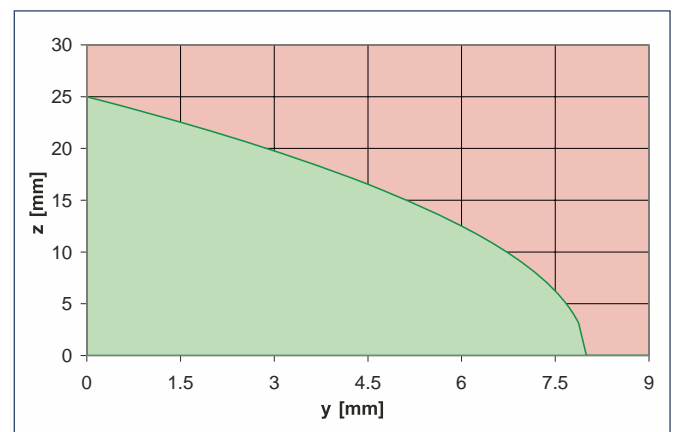
- Top view: 19 (width), 6 (flange offset), 26 ... 32 (body length), 18.5 (height), 11 ± 0.02 (flange thickness).
- Front view: 40 (total height), 26 (height to top of coil), 21.5 (height to top of body), 13 (height to top of solenoid), 10 (height to bottom of coil), 38 ... 44 (width to center of ports), 45 (width to center of solenoid), 11 ± 0.02 (flange thickness).
- Side view: 30 (height to top of coil), 19 (width to center of ports), 7.5 (height to top of solenoid), 2 (height to bottom of solenoid), 0.5 (height to bottom of coil), 5.5 (height to bottom of body).
- Port dimensions: 19 (width), 6 H8 (height to center of port), 4.5 (height to top of port), 3.5 (height to bottom of port), 16.8 (height to top of solenoid), 4.5 (height to top of body), 2 (height to bottom of solenoid), 2 (height to bottom of body).
- Port diameters: Ø6 (2x) (port diameter), Ø3 (2x) (port diameter), Ø5 (2x) (solenoid diameter), Ø5 (4x) (solenoid diameter).
- Thread dimensions: M5 (2x) (solenoid thread), M3 (4x) (solenoid thread), M3 (2x) (solenoid thread), M3 (4x) (solenoid thread).

**Callouts:**

- 1: Ø5 (2x) (solenoid diameter)
- 2: Ø5 (4x) (solenoid diameter)
- A: Section A (solenoid)
- B: Section B (solenoid)

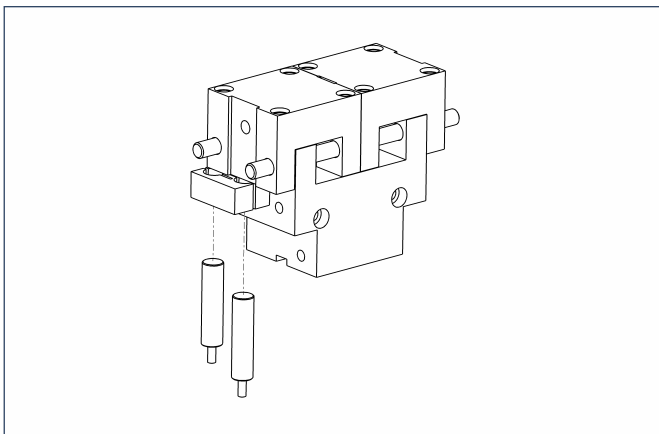
A,a Main/direct connection, gripper opening  
B,b Main/direct connection, gripper closing  
① Gripper connection  
② Finger connection

A technical drawing of a mechanical assembly. The assembly consists of a base plate with several circular features (holes or pins) and a vertical component attached to its right side. The vertical component has a rectangular section at the top with a grid pattern. Dimension lines indicate the width of the vertical component as  $y$  and the height of the grid section as  $z$ .



■ Permitted range  
■ Non-permissible range

### Sensor system



#### End position monitoring:

Inductive proximity switches, for direct mounting

Description	ID	Recommended product
IN 40/S-M12	0301574	
IN 40/S-M8	0301474	•
INK 40/S	0301555	

- ① Two sensors (NO contacts) are required for each gripper, plus extension cables as an option.

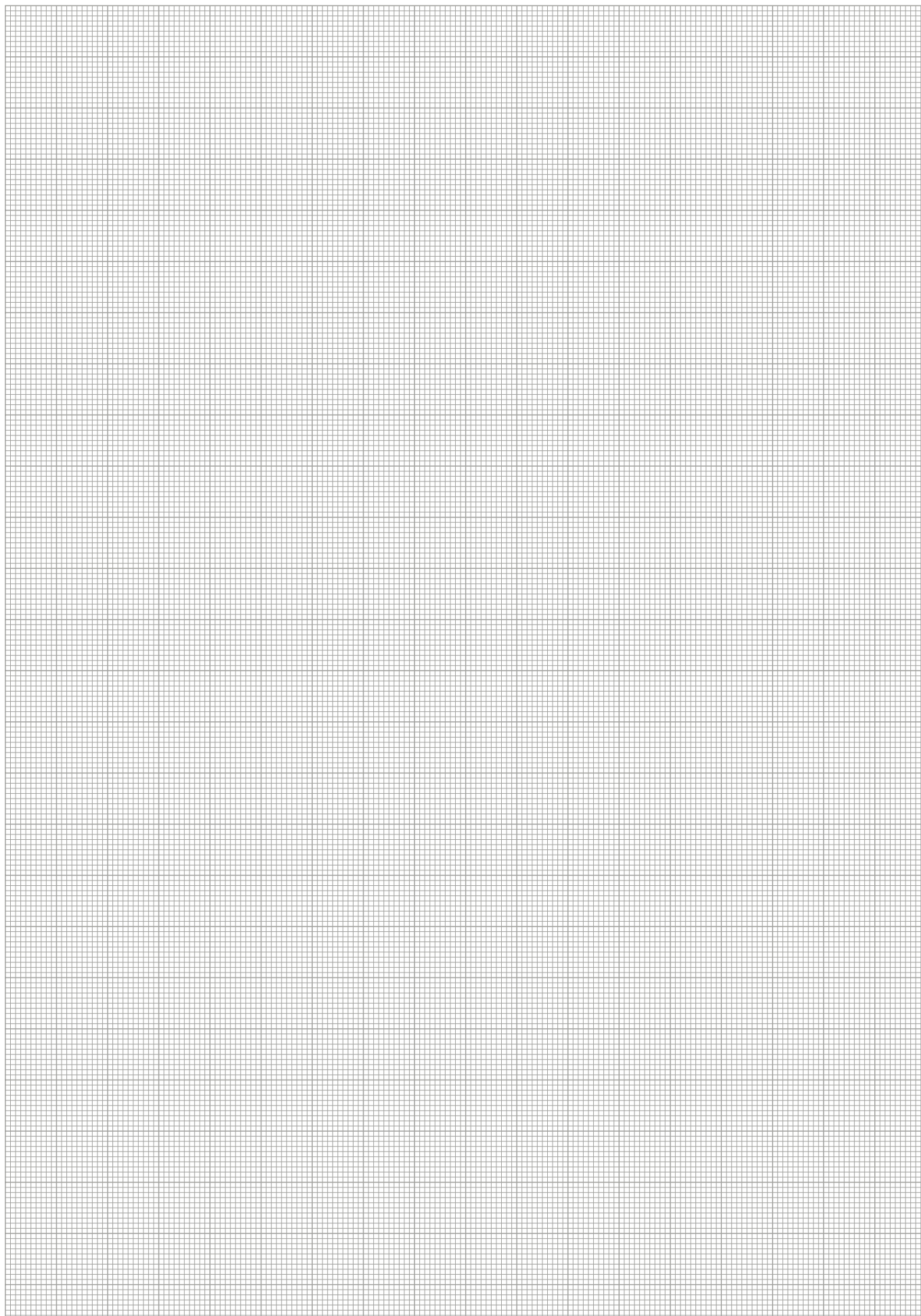
#### Extension cables for proximity switches/magnetic switches

Description	ID
GK 3-M8	0301622
KV 10-M12	0301596
KV 10-M8	0301496
KV 20-M12	0301597
KV 20-M8	0301497
KV 3-M12	0301595
KV 3-M8	0301495
W 3-M12	0301503
W 5-M12	0301507
WK 3-M8	0301594
WK 5-M8	0301502

- ① Please note the minimum permitted bending radii for the sensor cables, which are generally 35 mm.

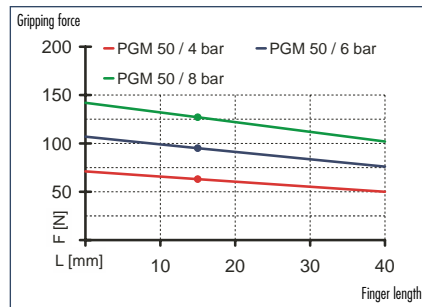


You can find more detailed information and individual parts of the above-mentioned accessories in the “Accessories” catalog section.

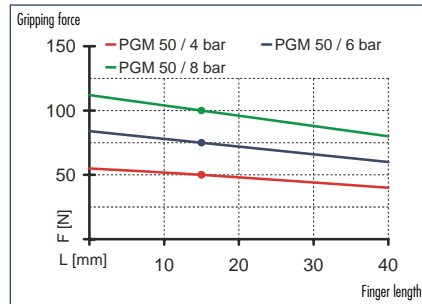




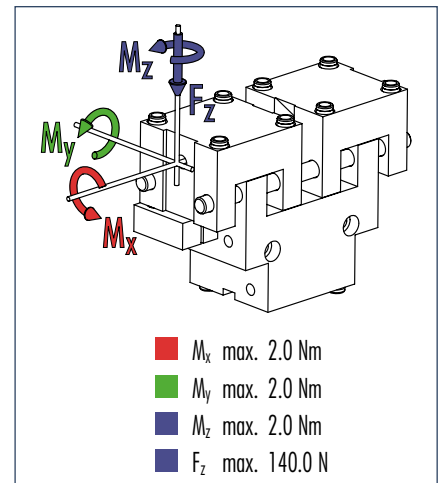
### Gripping force, I.D. gripping



### Gripping force, O.D. gripping



### Finger load



① Moments and forces apply per base jaw and may occur simultaneously.  $M_y$  may arise in addition to the moment generated by the gripping force itself. If the max. permitted finger weight is exceeded, it is imperative to throttle the air pressure so that the jaw movement occurs without any hitting or bouncing. Service life may be reduced.

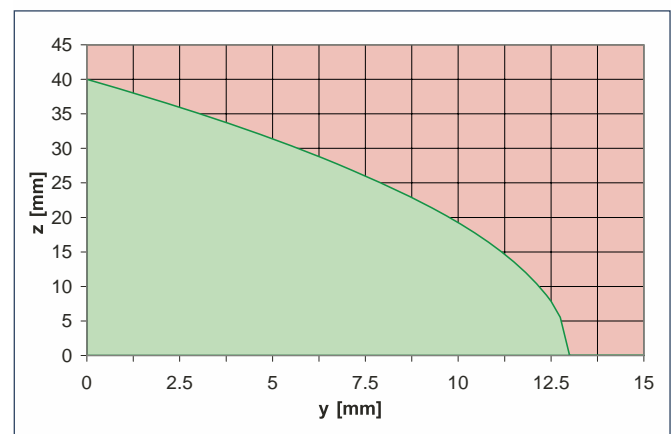
## Technical data

Description	PGM 50
	<b>0302682</b>
Stroke per finger	[mm] 4.0
Closing force	[N] 75.0
Opening force	[N] 95.0
Weight	[kg] 0.105
Recommended workpiece weight	[kg] 0.375
Air consumption per double stroke	[cm <sup>3</sup> ] 0.8
Nominal pressure	[bar] 6.0
Minimum pressure	[bar] 2.0
Maximum pressure	[bar] 8.0
Closing time	[s] 0.04
Opening time	[s] 0.04
Max. permitted finger length	[mm] 40.0
Max. permitted weight per finger	[kg] 0.035
IP rating	30
Min. ambient temperature	[°C] -10.0
Max. ambient temperature	[°C] 90.0
Repeat accuracy	[mm] 0.02

[illegible]

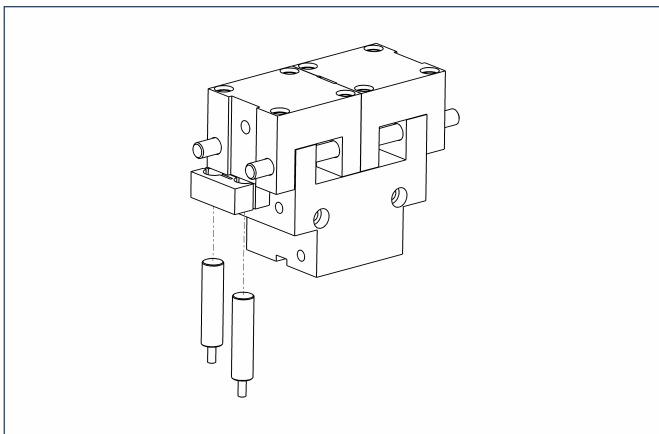
A,a Main/direct connection, gripper opening  
B,b Main/direct connection, gripper closing  
① Gripper connection  
② Finger connection

A technical diagram of a mechanical assembly. The assembly consists of a base plate with several circular features (holes or pins) and a vertical component attached to its right side. The vertical component has a rectangular section at the top with a grid pattern. Dimension lines indicate the width of the vertical component as  $y$  and the height of the grid section as  $z$ .



■ Permitted range  
■ Non-permissible range

### Sensor system



#### End position monitoring:

Inductive proximity switches, for direct mounting

Description	ID	Recommended product
IN 40/S-M12	0301574	
IN 40/S-M8	0301474	•
INK 40/S	0301555	

- ① Two sensors (NO contacts) are required for each gripper, plus extension cables as an option.

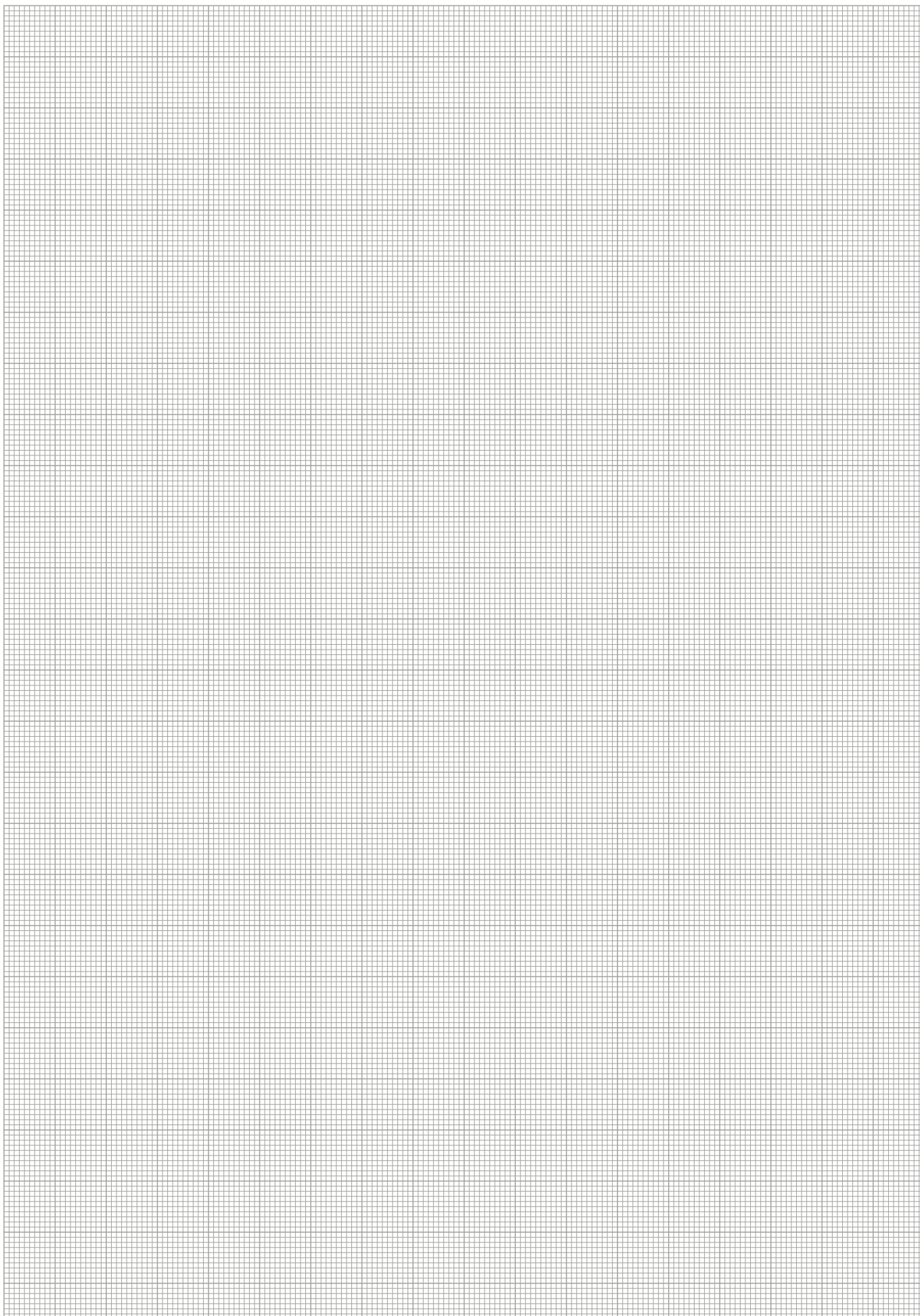
#### Extension cables for proximity switches/magnetic switches

Description	ID
GK 3-M8	0301622
KV 10-M12	0301596
KV 10-M8	0301496
KV 20-M12	0301597
KV 20-M8	0301497
KV 3-M12	0301595
KV 3-M8	0301495
W 3-M12	0301503
W 5-M12	0301507
WK 3-M8	0301594
WK 5-M8	0301502

- ① Please note the minimum permitted bending radii for the sensor cables, which are generally 35 mm.



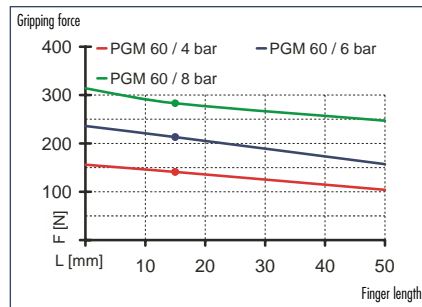
You can find more detailed information and individual parts of the above-mentioned accessories in the “Accessories” catalog section.



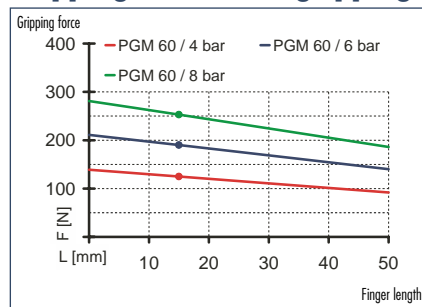




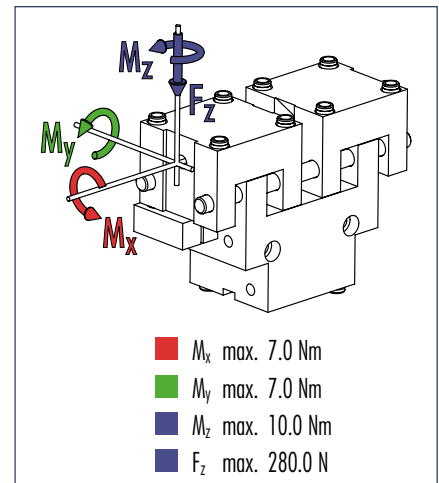
### Gripping force, I.D. gripping



### Gripping force, O.D. gripping



### Finger load



① Moments and forces apply per base jaw and may occur simultaneously.  $M_y$  may arise in addition to the moment generated by the gripping force itself. If the max. permitted finger weight is exceeded, it is imperative to throttle the air pressure so that the jaw movement occurs without any hitting or bouncing. Service life may be reduced.

## Technical data

Description	PGM 60
	<b>0302683</b>
Stroke per finger	[mm] 5.0
Closing force	[N] 190.0
Opening force	[N] 210.0
Weight	[kg] 0.21
Recommended workpiece weight	[kg] 0.95
Air consumption per double stroke	[cm <sup>3</sup> ] 2.5
Nominal pressure	[bar] 6.0
Minimum pressure	[bar] 2.0
Maximum pressure	[bar] 8.0
Closing time	[s] 0.05
Opening time	[s] 0.05
Max. permitted finger length	[mm] 50.0
Max. permitted weight per finger	[kg] 0.07
IP rating	30
Min. ambient temperature	[°C] -10.0
Max. ambient temperature	[°C] 90.0
Repeat accuracy	[mm] 0.02

Technical drawing of a mechanical assembly, showing three views: top, front, and side. The drawing includes dimensions and part labels.

**Top View:**

- Overall width: 30
- Distance between mounting holes:  $20 \pm 0.02$
- Distance from edge to mounting hole: 5
- Distance between central features: 10 ... 20
- Overall height:  $27.5$
- Distance from edge to central feature:  $20 \pm 0.02$

**Front View:**

- Overall height: 56
- Distance from top edge to mounting hole: 38
- Distance from top edge to central feature: 33.5
- Distance from top edge to bottom edge: 20
- Overall width: 60 ... 70
- Distance between mounting holes: 32  $\pm 0.02$
- Distance from edge to mounting hole: 15
- Distance from edge to central feature: 70
- Distance from edge to bottom edge: 15  $\pm 0.02$
- Distance between central features: 26  $\pm 0.02$
- Overall width: 29
- Distance between mounting holes: 31.5

**Side View:**

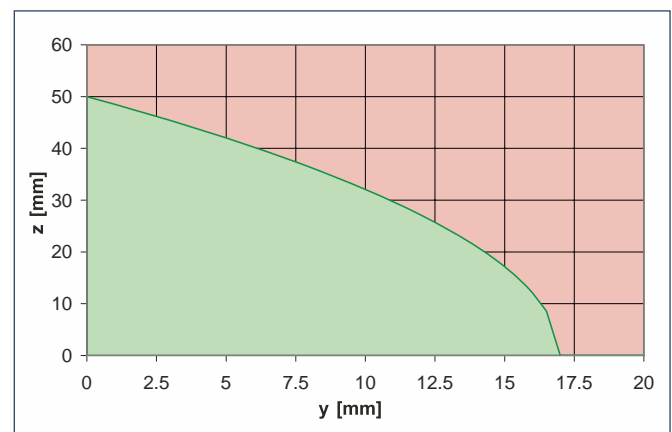
- Overall width: 51
- Distance between mounting holes: 34
- Distance from edge to mounting hole: 9.5
- Overall height: 29.5
- Distance from top edge to mounting hole: 8
- Distance from top edge to central feature: 2.5
- Distance from top edge to bottom edge: 10
- Overall width: 8
- Distance between mounting holes: 2.5
- Distance from edge to mounting hole: 1
- Distance from edge to central feature: 10
- Distance from edge to bottom edge: 15
- Distance between central features: 26  $\pm 0.02$
- Overall width: 29
- Distance between mounting holes: 31.5

**Labels and Dimensions:**

- M4 (2x)
- M5 (2x)
- $\varnothing 6$  (2x)
- $\varnothing 7.5$  (2x)
- $\varnothing 4.3$  (2x)
- 12 H8
- 28
- 5
- 3.2
- 5 (2x)
- 2.5
- 10
- 7
- 10
- 2.5
- 2.5
- 8
- 2.5
- M4 (8x)
- M5 (2x)
- $\varnothing 6$  (4x)
- 1
- 2

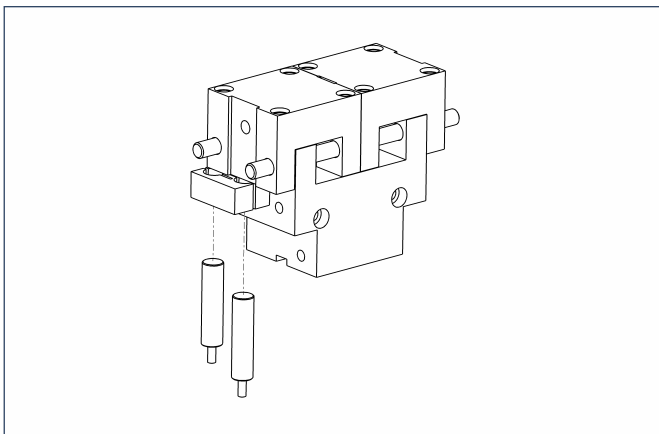
A,a Main/direct connection, gripper opening  
B,b Main/direct connection, gripper closing  
① Gripper connection  
② Finger connection

A technical drawing of a mechanical assembly. The assembly consists of a base plate with several circular features (holes or pins) and a vertical component attached to its right side. The vertical component has a rectangular section at the top with a grid pattern. Dimension lines indicate the width of the vertical component as  $y$  and the height of the grid section as  $z$ .



■ Permitted range  
■ Non-permissible range

### Sensor system



#### End position monitoring:

Inductive proximity switches, for direct mounting

Description	ID	Recommended product
IN 40/S-M12	0301574	
IN 40/S-M8	0301474	•
INK 40/S	0301555	

- ① Two sensors (NO contacts) are required for each gripper, plus extension cables as an option.

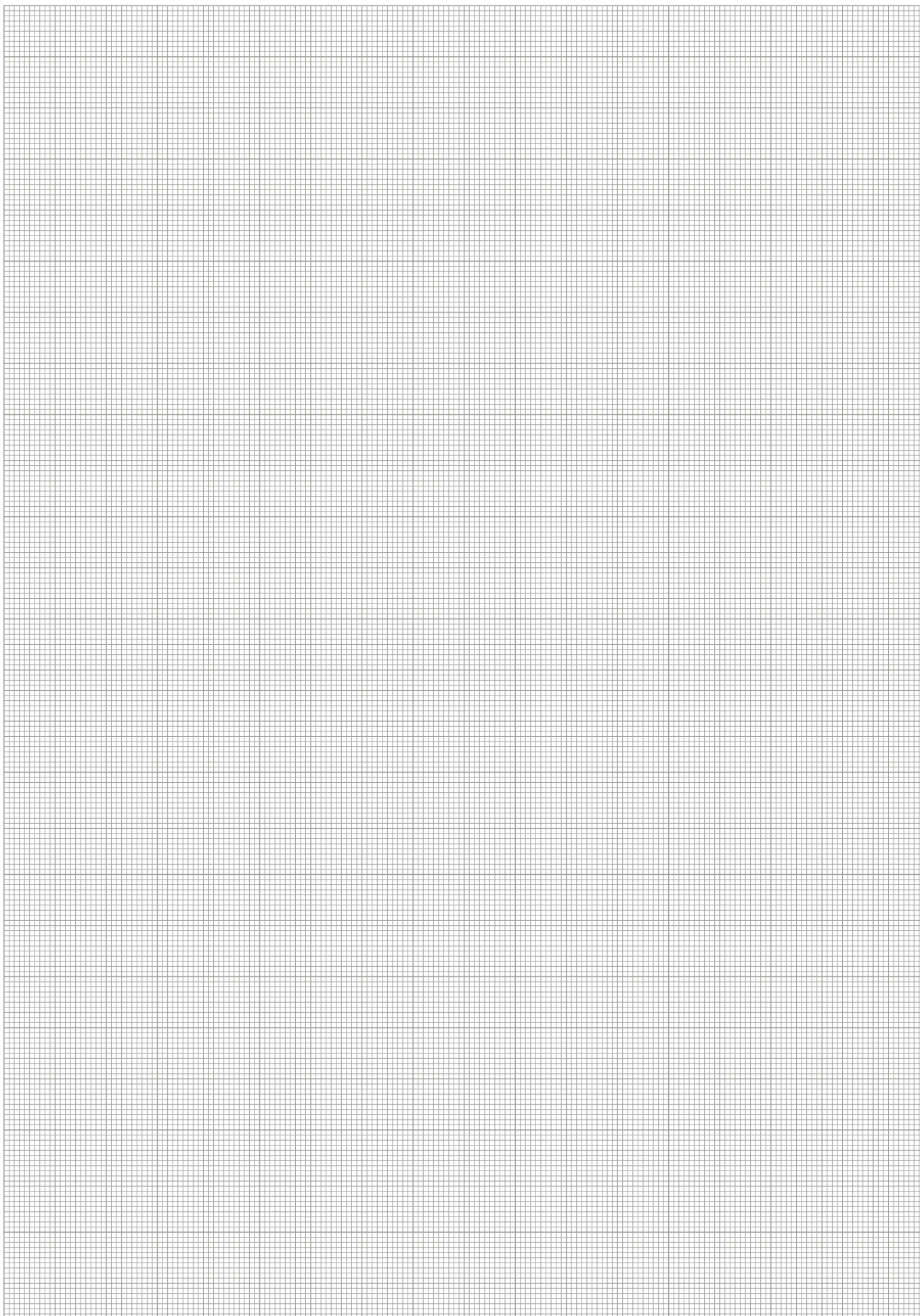
#### Extension cables for proximity switches/magnetic switches

Description	ID
GK 3-M8	0301622
KV 10-M12	0301596
KV 10-M8	0301496
KV 20-M12	0301597
KV 20-M8	0301497
KV 3-M12	0301595
KV 3-M8	0301495
W 3-M12	0301503
W 5-M12	0301507
WK 3-M8	0301594
WK 5-M8	0301502

- ① Please note the minimum permitted bending radii for the sensor cables, which are generally 35 mm.

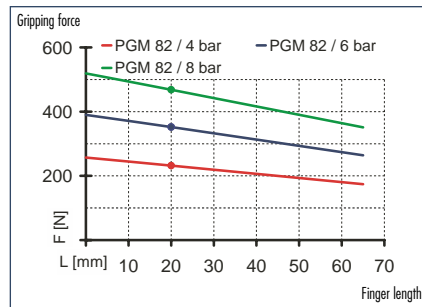


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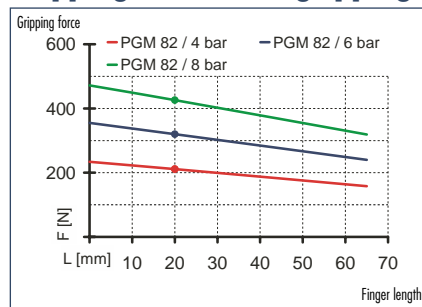




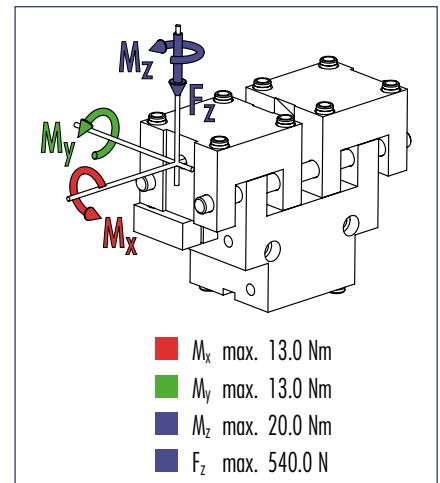
### Gripping force, I.D. gripping



### Gripping force, O.D. gripping



### Finger load



① Moments and forces apply per base jaw and may occur simultaneously.  $M_y$  may arise in addition to the moment generated by the gripping force itself. If the max. permitted finger weight is exceeded, it is imperative to throttle the air pressure so that the jaw movement occurs without any hitting or bouncing. Service life may be reduced.

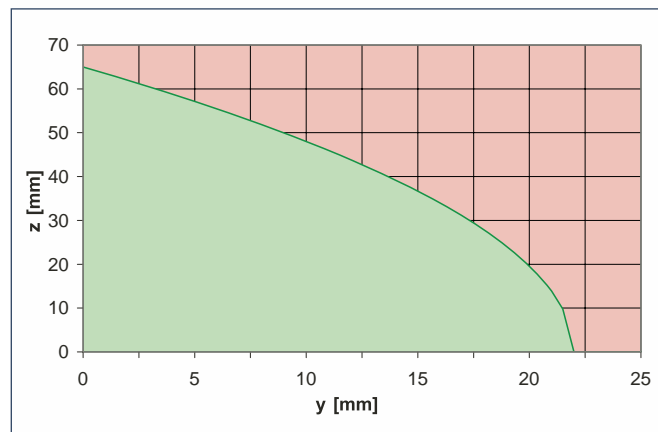
## Technical data

Description	PGM 82
	<b>0302684</b>
Stroke per finger	[mm] 10.0
Closing force	[N] 320.0
Opening force	[N] 350.0
Weight	[kg] 0.6
Recommended workpiece weight	[kg] 1.6
Air consumption per double stroke	[cm <sup>3</sup> ] 8.0
Nominal pressure	[bar] 6.0
Minimum pressure	[bar] 2.0
Maximum pressure	[bar] 8.0
Closing time	[s] 0.07
Opening time	[s] 0.07
Max. permitted finger length	[mm] 65.0
Max. permitted weight per finger	[kg] 0.17
IP rating	30
Min. ambient temperature	[°C] -10.0
Max. ambient temperature	[°C] 90.0
Repeat accuracy	[mm] 0.03

[illegible]

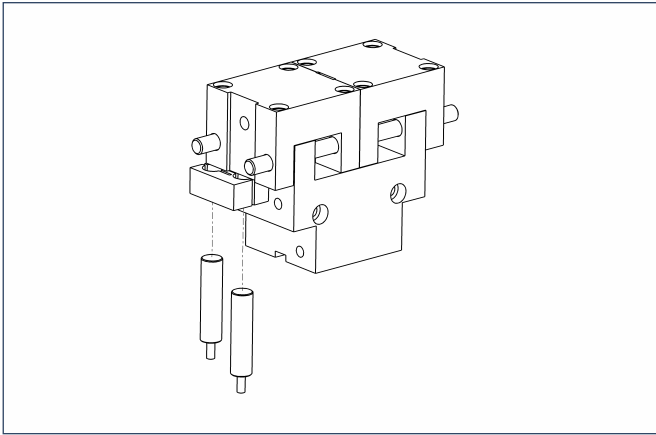
A,a Main/direct connection, gripper opening  
B,b Main/direct connection, gripper closing  
① Gripper connection  
② Finger connection

Technical drawing of a mechanical part. The part consists of a base with a central rectangular section and two side sections. The central section has a circular hole. The side sections have circular holes. The base has a small rectangular notch on the left side. A vertical section on the right side of the part is shown in cross-section, with a hatched pattern. Dimension  $y$  is indicated by a horizontal double-headed arrow, representing the width of the central section. Dimension  $z$  is indicated by a vertical double-headed arrow, representing the height of the vertical section.



■ Permitted range  
■ Non-permissible range

### Sensor system



End position monitoring:

Inductive proximity switches, for direct mounting

Description	ID	Recommended product
IN 80/S-M12	0301578	
IN 80/S-M8	0301478	•
INK 80/S	0301550	

- ① Two sensors (NO contacts) are required for each gripper, plus extension cables as an option.

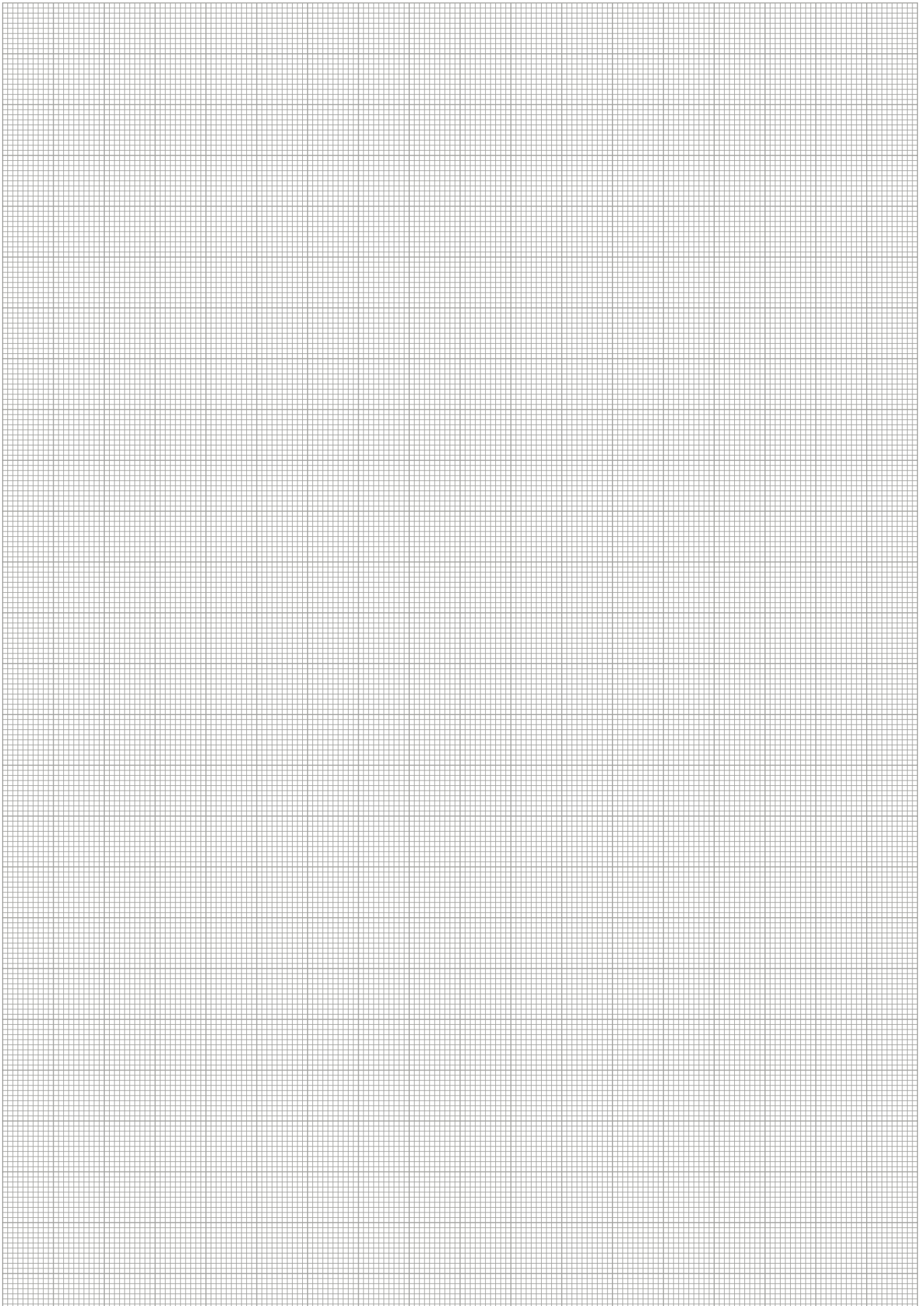
### Extension cables for proximity switches/magnetic switches

Description	ID
GK 3-M8	0301622
KV 10-M12	0301596
KV 10-M8	0301496
KV 20-M12	0301597
KV 20-M8	0301497
KV 3-M12	0301595
KV 3-M8	0301495
W 3-M12	0301503
W 5-M12	0301507
WK 3-M8	0301594
WK 5-M8	0301502

- ① Please note the minimum permitted bending radii for the sensor cables, which are generally 35 mm.



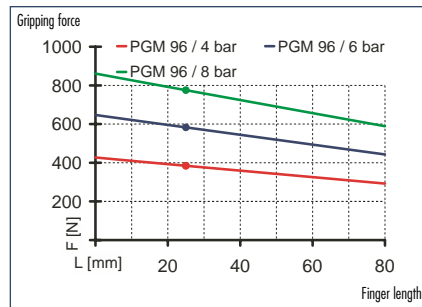
You can find more detailed information and individual parts of the above-mentioned accessories in the “Accessories” catalog section.



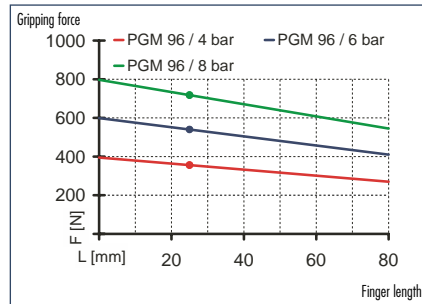




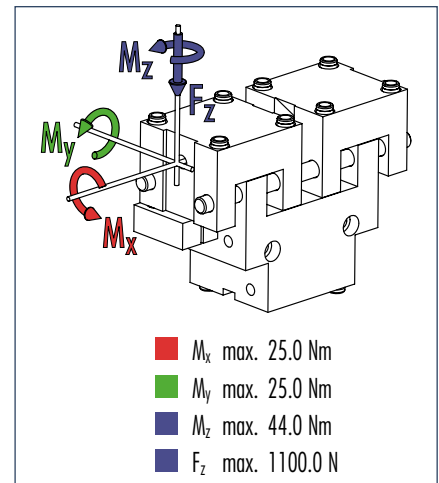
### Gripping force, I.D. gripping



### Gripping force, O.D. gripping



### Finger load

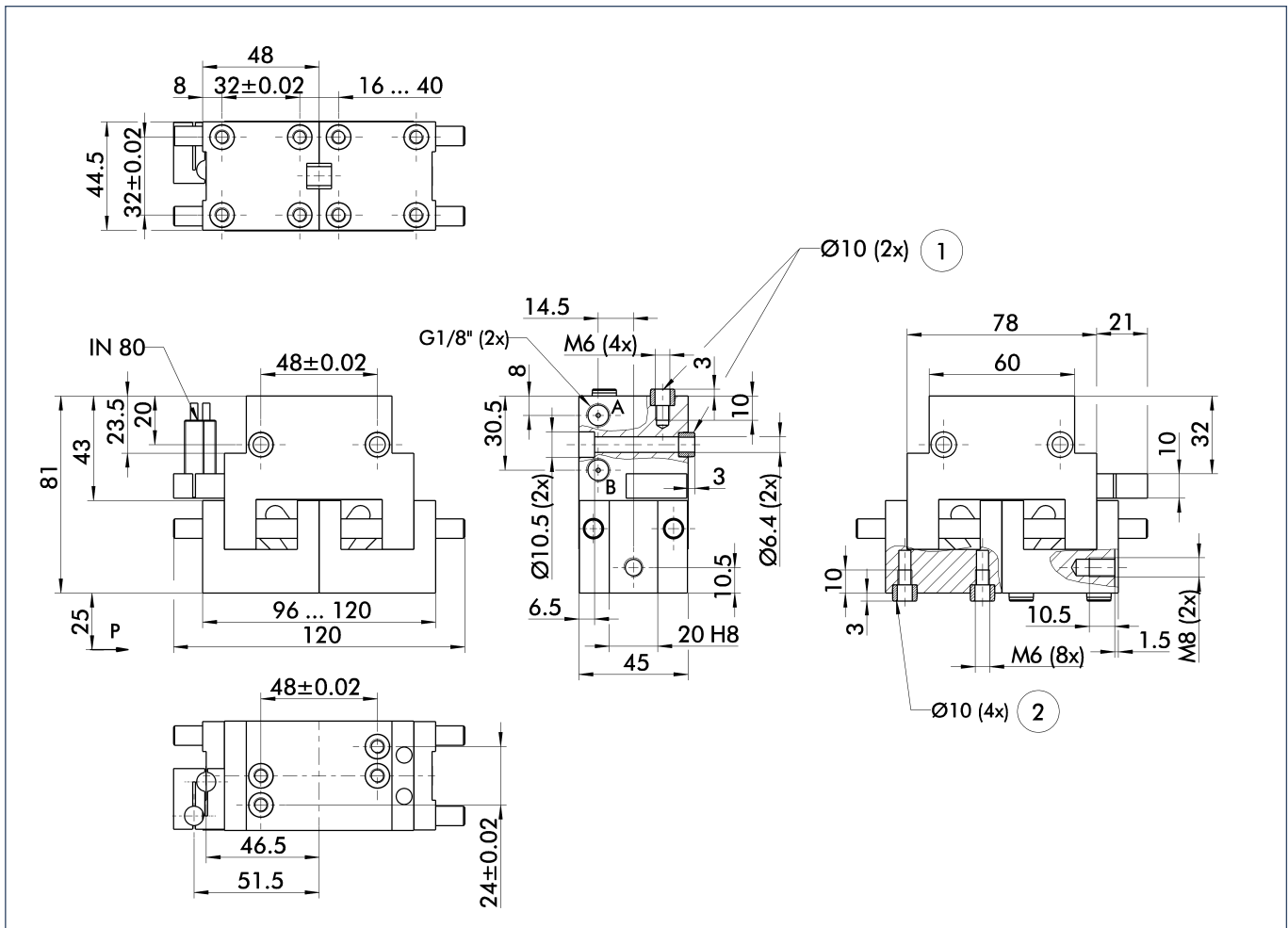


① Moments and forces apply per base jaw and may occur simultaneously.  $M_y$  may arise in addition to the moment generated by the gripping force itself. If the max. permitted finger weight is exceeded, it is imperative to throttle the air pressure so that the jaw movement occurs without any hitting or bouncing. Service life may be reduced.

### Technical data

Description	PGM 96
	<b>0302685</b>
Stroke per finger	[mm] 12.0
Closing force	[N] 540.0
Opening force	[N] 580.0
Weight	[kg] 0.84
Recommended workpiece weight	[kg] 2.7
Air consumption per double stroke	[cm <sup>3</sup> ] 15.1
Nominal pressure	[bar] 6.0
Minimum pressure	[bar] 2.0
Maximum pressure	[bar] 8.0
Closing time	[s] 0.08
Opening time	[s] 0.08
Max. permitted finger length	[mm] 80.0
Max. permitted weight per finger	[kg] 0.28
IP rating	30
Min. ambient temperature	[°C] -10.0
Max. ambient temperature	[°C] 90.0
Repeat accuracy	[mm] 0.03

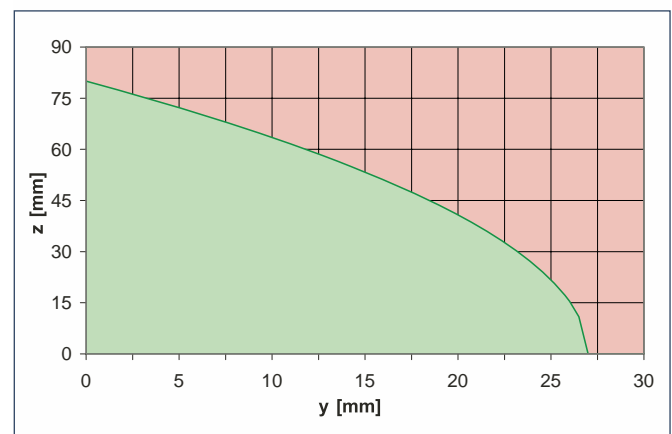
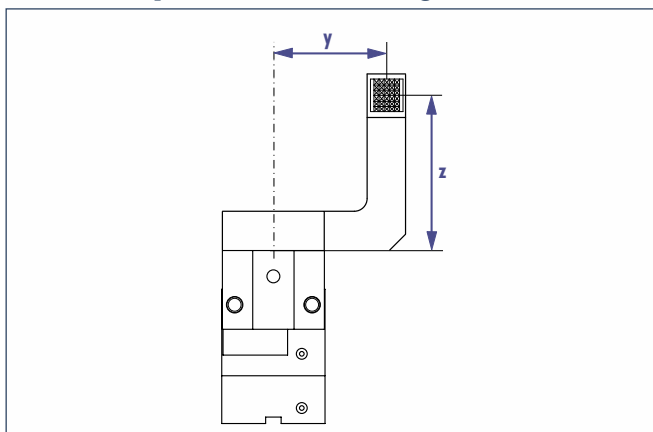
## Main views



The drawing shows the gripper in the basic version with closed jaws, the dimensions do not include the options described below.

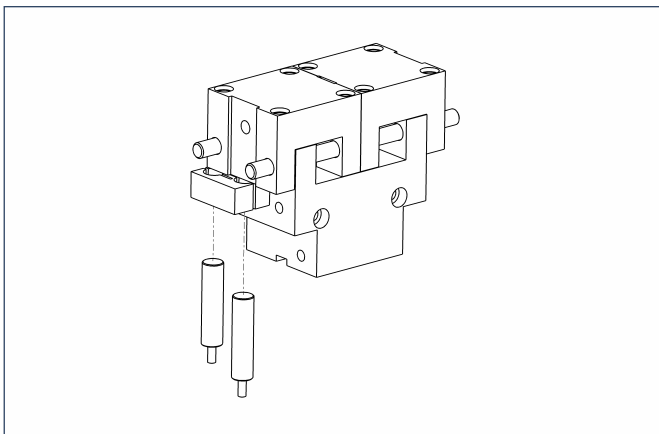
- A,a Main/direct connection, gripper opening  
B,b Main/direct connection, gripper closing  
① Gripper connection  
② Finger connection

### Maximum permitted overhang



- Permitted range  
■ Non-permissible range

### Sensor system



#### End position monitoring:

Inductive proximity switches, for direct mounting

Description	ID	Recommended product
IN 80/S-M12	0301578	
IN 80/S-M8	0301478	•
INK 80/S	0301550	

- ① Two sensors (NO contacts) are required for each gripper, plus extension cables as an option.

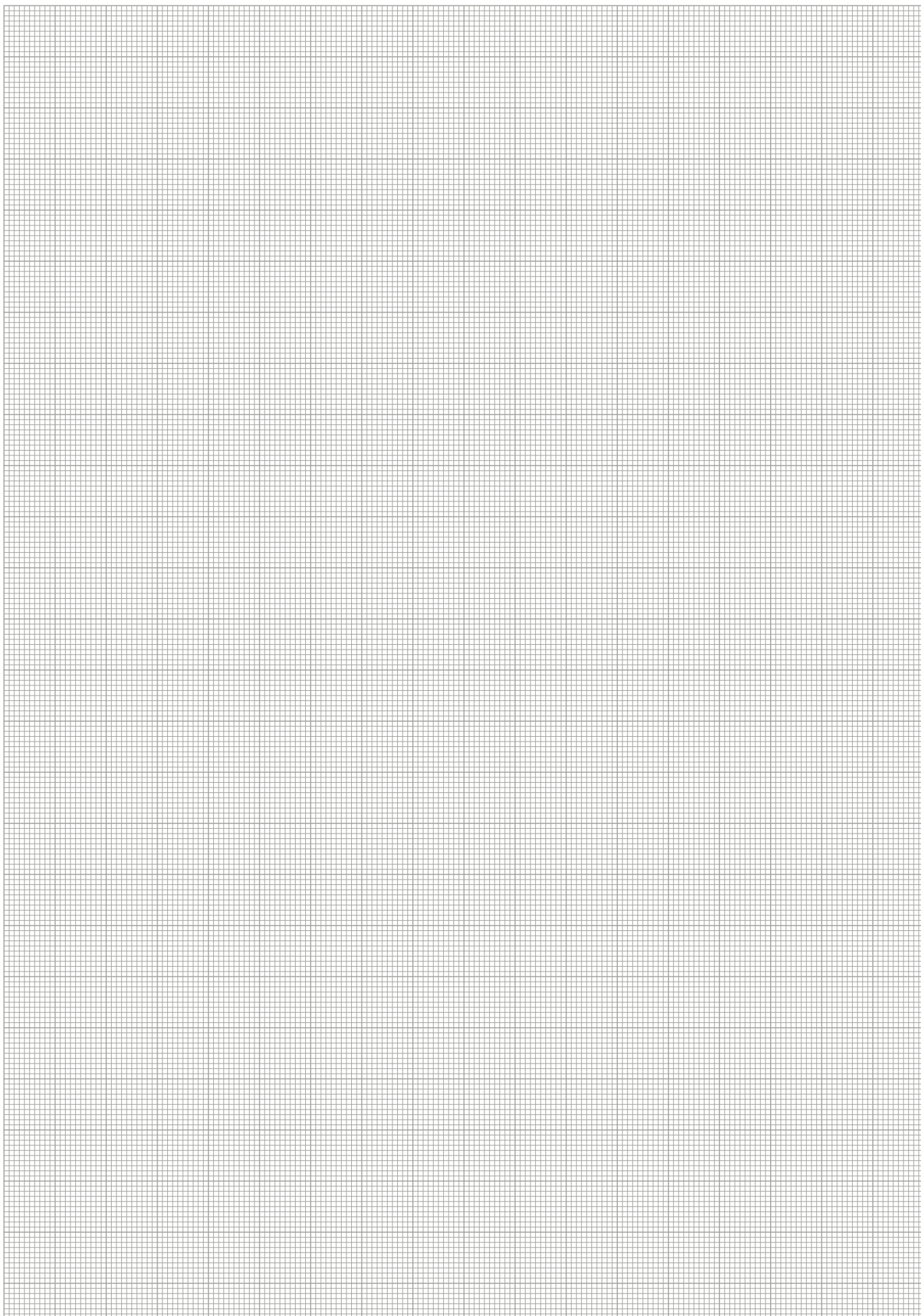
#### Extension cables for proximity switches/magnetic switches

Description	ID
GK 3-M8	0301622
KV 10-M12	0301596
KV 10-M8	0301496
KV 20-M12	0301597
KV 20-M8	0301497
KV 3-M12	0301595
KV 3-M8	0301495
W 3-M12	0301503
W 5-M12	0301507
WK 3-M8	0301594
WK 5-M8	0301502

- ① Please note the minimum permitted bending radii for the sensor cables, which are generally 35 mm.

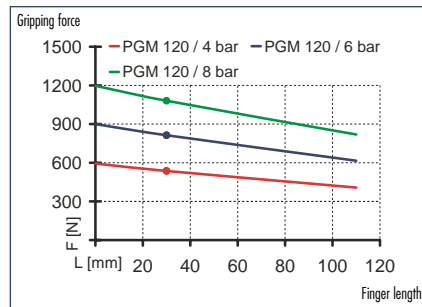


You can find more detailed information and individual parts of the above-mentioned accessories in the “Accessories” catalog section.

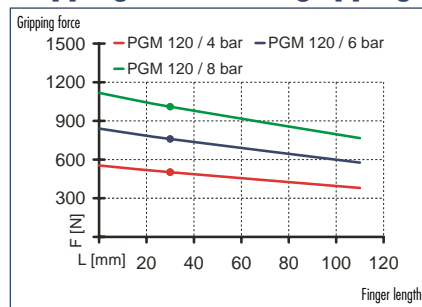




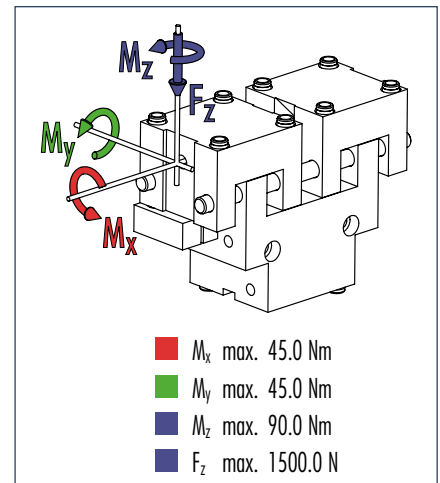
### Gripping force, I.D. gripping



### Gripping force, O.D. gripping



### Finger load



① Moments and forces apply per base jaw and may occur simultaneously.  $M_y$  may arise in addition to the moment generated by the gripping force itself. If the max. permitted finger weight is exceeded, it is imperative to throttle the air pressure so that the jaw movement occurs without any hitting or bouncing. Service life may be reduced.

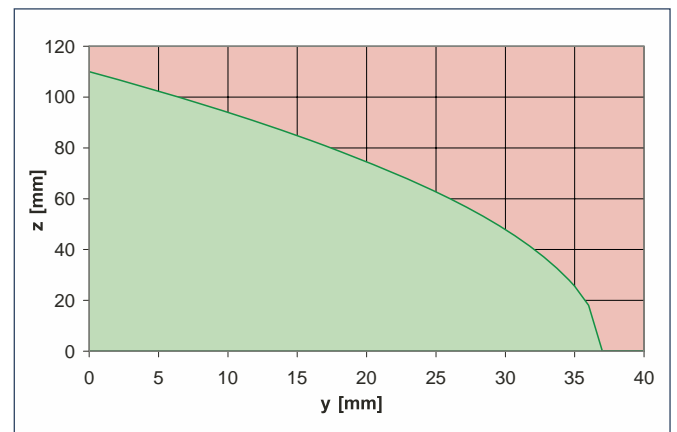
### Technical data

Description	PGM 120
	<b>0302686</b>
Stroke per finger	[mm] 12.0
Closing force	[N] 760.0
Opening force	[N] 810.0
Weight	[kg] 1.26
Recommended workpiece weight	[kg] 3.8
Air consumption per double stroke	[cm <sup>3</sup> ] 23.6
Nominal pressure	[bar] 6.0
Minimum pressure	[bar] 2.0
Maximum pressure	[bar] 8.0
Closing time	[s] 0.1
Opening time	[s] 0.1
Max. permitted finger length	[mm] 110.0
Max. permitted weight per finger	[kg] 0.58
IP rating	30
Min. ambient temperature	[°C] -10.0
Max. ambient temperature	[°C] 90.0
Repeat accuracy	[mm] 0.03

[illegible]

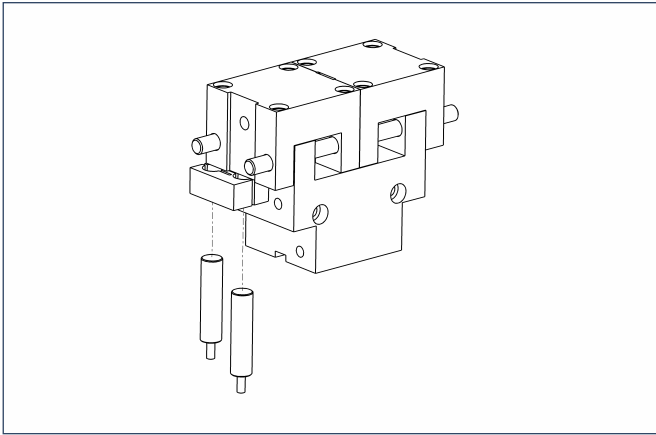
A,a Main/direct connection, gripper opening  
B,b Main/direct connection, gripper closing  
① Gripper connection  
② Finger connection

A technical drawing of a mechanical assembly. The assembly consists of a base plate with several circular features (holes or pins) and a vertical component attached to its right side. The vertical component has a rectangular section at the top with a grid pattern. Dimension lines indicate the width of the vertical component as  $y$  and the height of the grid section as  $z$ .



■ Permitted range  
■ Non-permissible range

### Sensor system



#### End position monitoring:

Inductive proximity switches, for direct mounting

Description	ID	Recommended product
IN 80/S-M12	0301578	
IN 80/S-M8	0301478	•
INK 80/S	0301550	

- ① Two sensors (NO contacts) are required for each gripper, plus extension cables as an option.

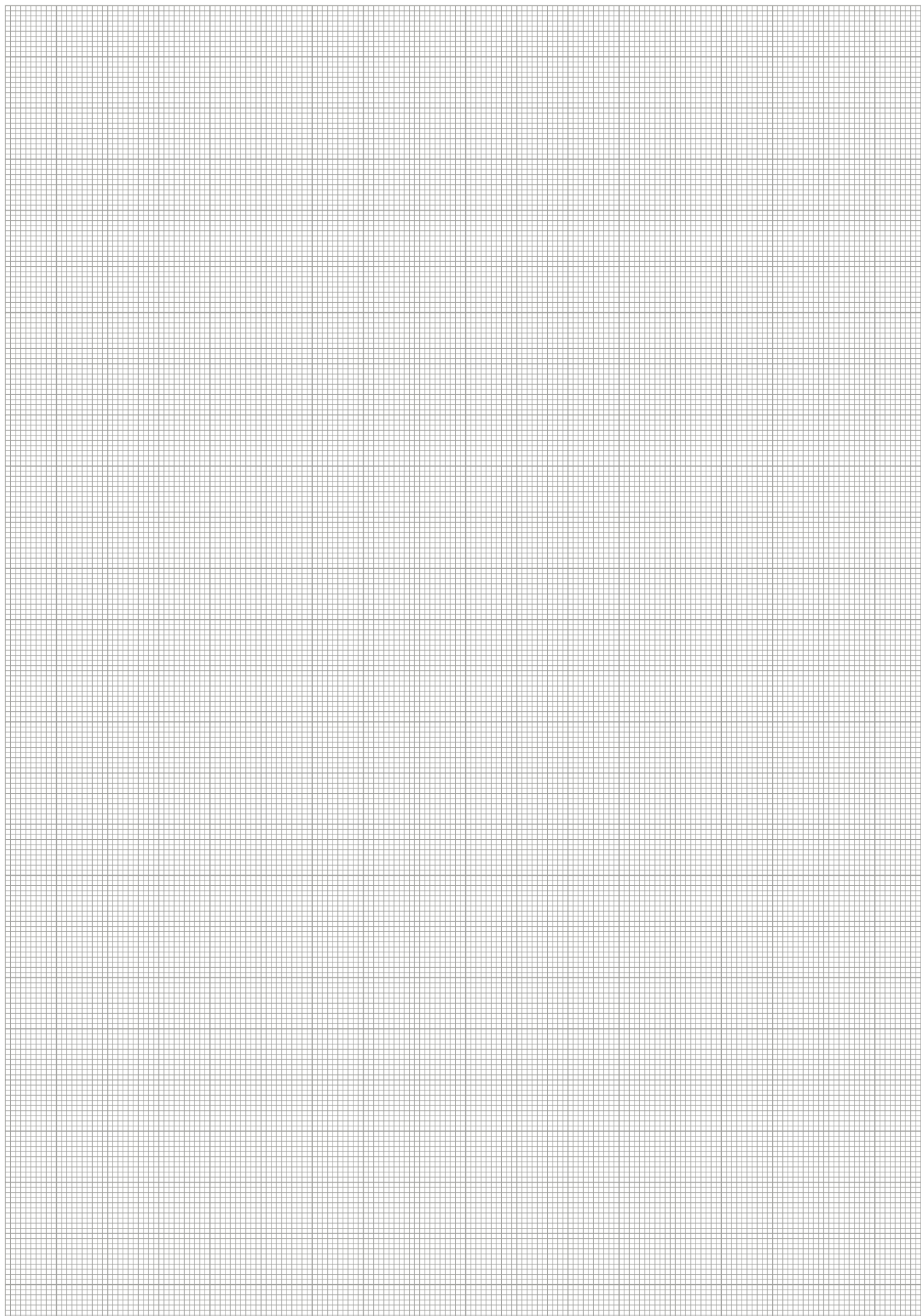
#### Extension cables for proximity switches/magnetic switches

Description	ID
GK 3-M8	0301622
KV 10-M12	0301596
KV 10-M8	0301496
KV 20-M12	0301597
KV 20-M8	0301497
KV 3-M12	0301595
KV 3-M8	0301495
W 3-M12	0301503
W 5-M12	0301507
WK 3-M8	0301594
WK 5-M8	0301502

- ① Please note the minimum permitted bending radii for the sensor cables, which are generally 35 mm.



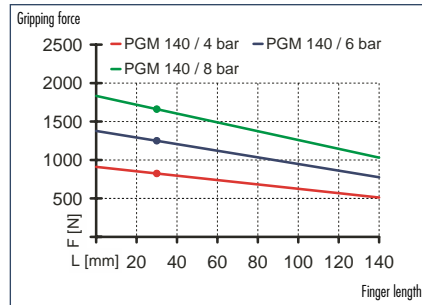
You can find more detailed information and individual parts of the above-mentioned accessories in the “Accessories” catalog section.



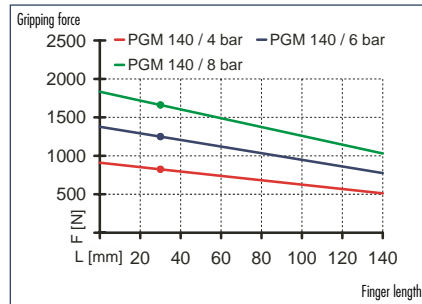




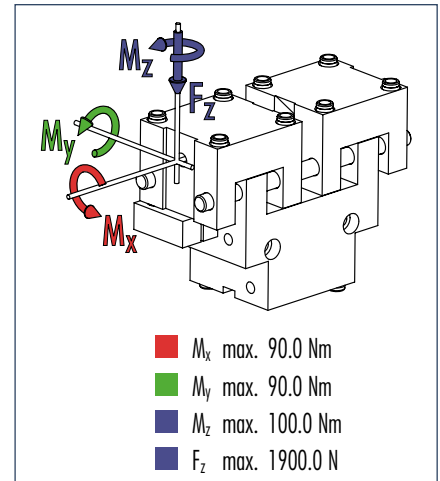
### Gripping force, I.D. gripping



### Gripping force, O.D. gripping



### Finger load

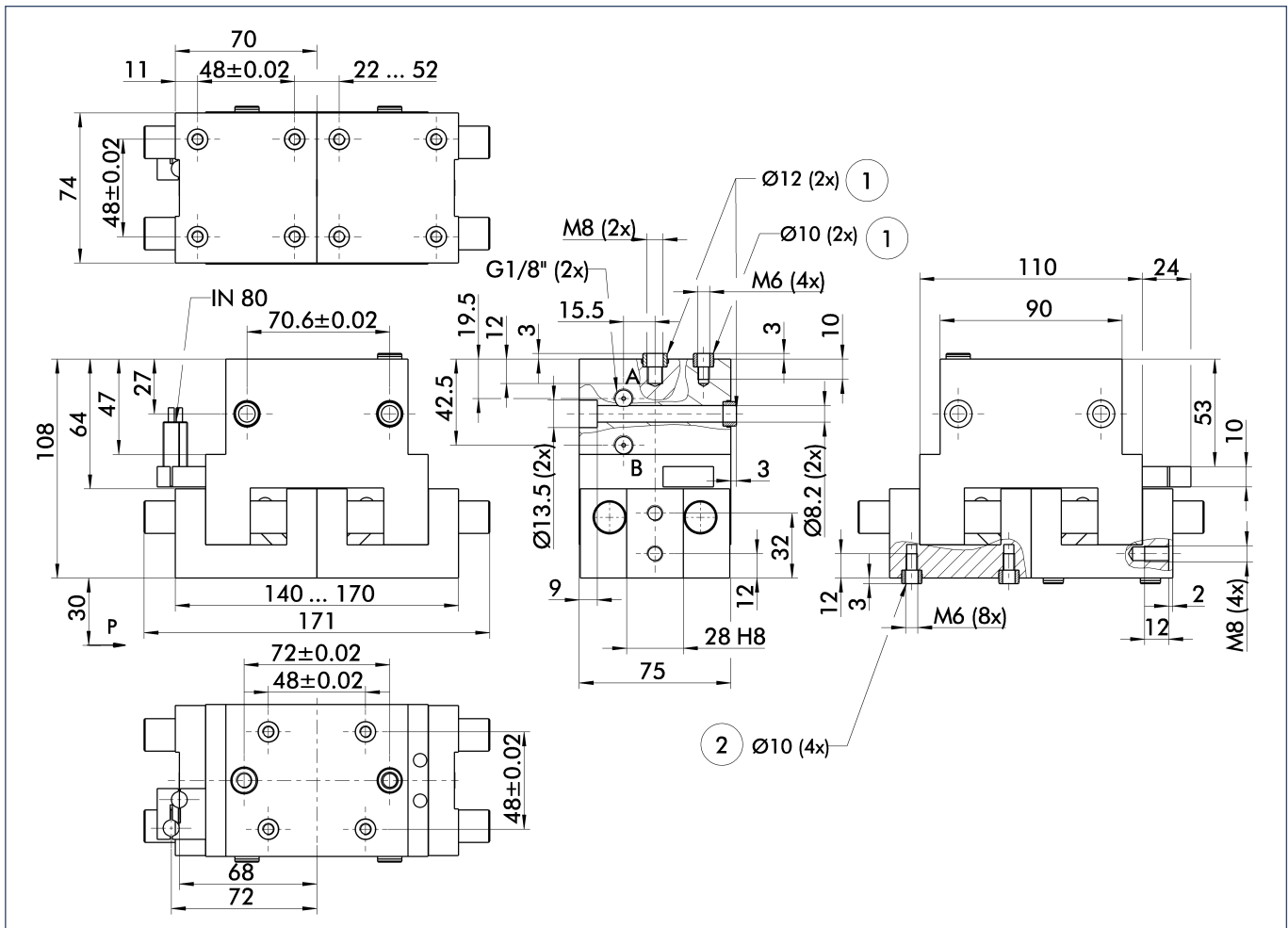


① Moments and forces apply per base jaw and may occur simultaneously.  $M_y$  may arise in addition to the moment generated by the gripping force itself. If the max. permitted finger weight is exceeded, it is imperative to throttle the air pressure so that the jaw movement occurs without any hitting or bouncing. Service life may be reduced.

## Technical data

Description	PGM 140
	<b>0302687</b>
Stroke per finger	[mm] 15.0
Closing force	[N] 1180.0
Opening force	[N] 1250.0
Weight	[kg] 2.55
Recommended workpiece weight	[kg] 5.9
Air consumption per double stroke	[cm <sup>3</sup> ] 46.8
Nominal pressure	[bar] 6.0
Minimum pressure	[bar] 2.0
Maximum pressure	[bar] 8.0
Closing time	[s] 0.12
Opening time	[s] 0.12
Max. permitted finger length	[mm] 140.0
Max. permitted weight per finger	[kg] 1.0
IP rating	30
Min. ambient temperature	[°C] -10.0
Max. ambient temperature	[°C] 90.0
Repeat accuracy	[mm] 0.03

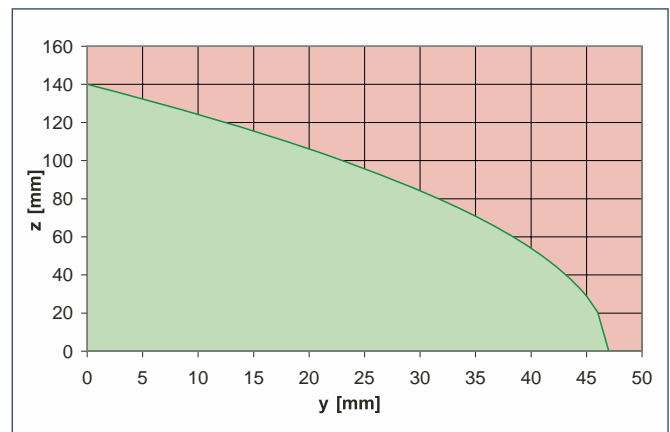
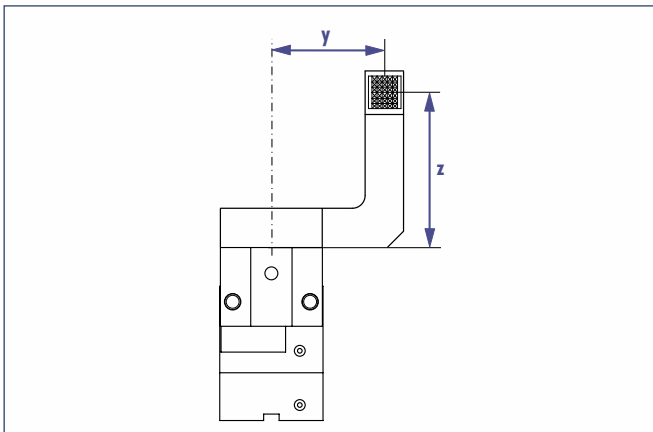
## Main views



The drawing shows the gripper in the basic version with closed jaws, the dimensions do not include the options described below.

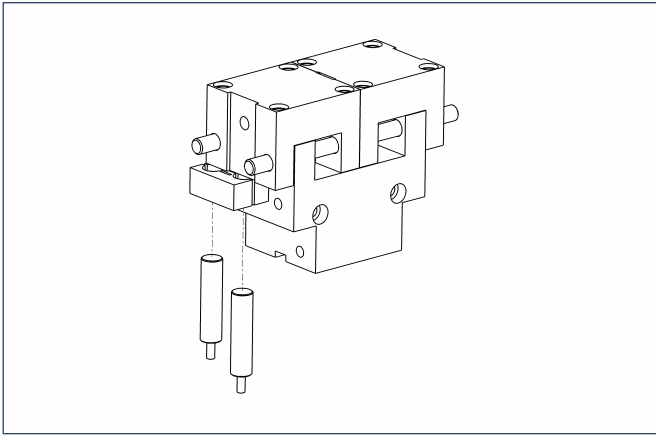
- A,a Main/direct connection, gripper opening  
B,b Main/direct connection, gripper closing  
① Gripper connection  
② Finger connection

### Maximum permitted overhang



■ Permitted range  
■ Non-permissible range

### Sensor system



#### End position monitoring:

Inductive proximity switches, for direct mounting

Description	ID	Recommended product
IN 80/S-M12	0301578	
IN 80/S-M8	0301478	•
INK 80/S	0301550	

- ① Two sensors (NO contacts) are required for each gripper, plus extension cables as an option.

#### Extension cables for proximity switches/magnetic switches

Description	ID
GK 3-M8	0301622
KV 10-M12	0301596
KV 10-M8	0301496
KV 20-M12	0301597
KV 20-M8	0301497
KV 3-M12	0301595
KV 3-M8	0301495
W 3-M12	0301503
W 5-M12	0301507
WK 3-M8	0301594
WK 5-M8	0301502

- ① Please note the minimum permitted bending radii for the sensor cables, which are generally 35 mm.



You can find more detailed information and individual parts of the above-mentioned accessories in the “Accessories” catalog section.

