



- Swivelling and gripping in one unit
- Cushioning concepts:  
Elastomer cushioning or  
hydraulic cushioning
- Quick, precise and light

# Swivel/gripper units HGDS

Key features

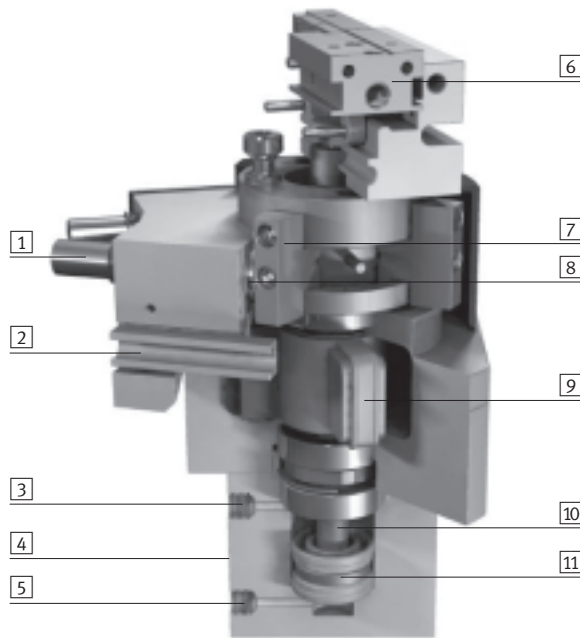
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## At a glance

### Combination of parallel gripper and swivel module

The power transmission from the linear motion to the gripper motion takes place via the piston rod, which opens and closes the gripper jaws housed in the gripper housing via 2 reversing levers.

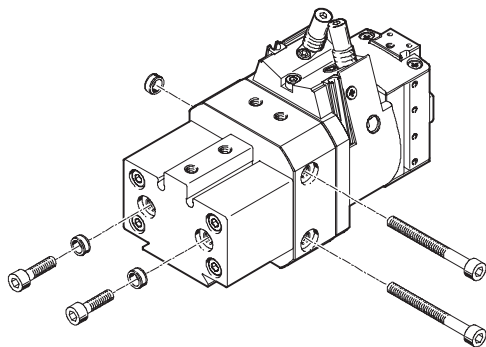
The swivel motion takes place via a swivel drive. It can be adjusted almost infinitely via 2 stops (max. 210°). The rotary motion is cushioned either via a flexible cushioning buffer or a hydraulic shock absorber. The swivel angle can be finely adjusted by means of a precision adjustment facility.



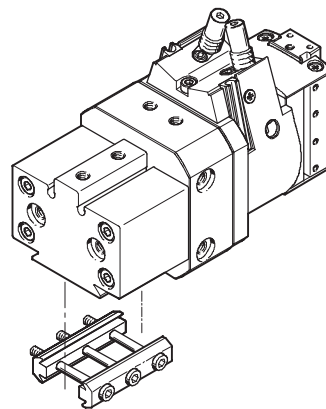
- 1 Flexible cushioning or hydraulic shock absorbers
- 2 Slot for proximity sensor SME/SMT-10 for sensing the swivel position
- 3 Gripper compressed air connection, closing
- 4 Slot for proximity sensor SME/SMT-10 for sensing the gripper position
- 5 Gripper compressed air connection, opening
- 6 Gripper jaw
- 7 Adjustable stop plates for the swivel motion, with magnet
- 8 Precise end stop with flexible cushioning or integrated shock absorber
- 9 Rotary vane
- 10 Piston rod for gripping motion
- 11 Piston with magnet

## Mounting options

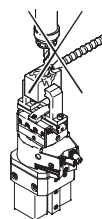
### Direct mounting



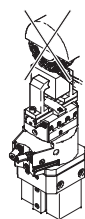
### Dovetail connection



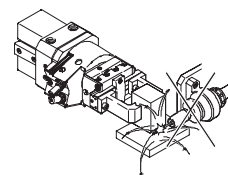
**Note**  
Swivel/gripper units are not suitable for the following or similar applications:



- Machining
- Aggressive media



- Grinding dust



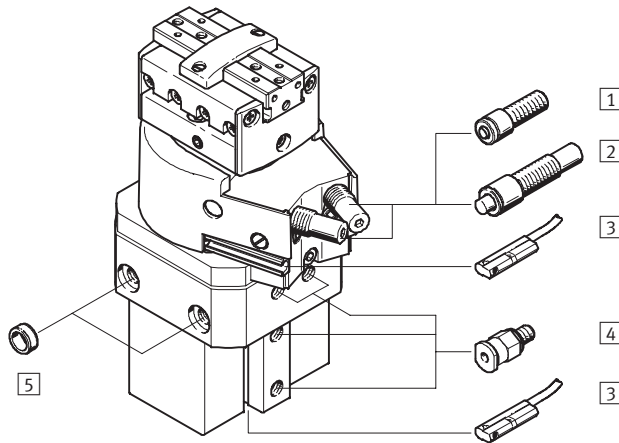
- Welding spatter

# Swivel/gripper units HGDS

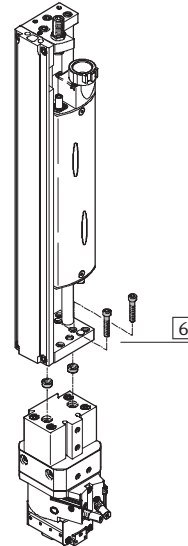
Peripherals overview and type codes

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## Peripherals overview



## System product for handling and assembly technology



Accessories			
Type	Brief description		→ Page
1 Cushioning P	Non-adjustable, flexible cushioning. Is used for smaller loads		–
2 Cushioning YSRT	Self-adjusting, hydraulic shock absorber		–
3 Proximity sensor SME/SMT-10	For sensing the gripper and rotary vane position		1 / 7.8-12
4 Push-in fitting QS	For connecting compressed air tubing with standard external diameters		Volume 3
5 Centring sleeve ZBH	For centring the gripper when mounting (2 included in scope of delivery)		1 / 7.8-12
6 –	Drive/gripper connections		Volume 5

		HGDS	–	PP	–	16	–	YSRT	–	A
<b>Type</b>										
HGDS	Swivel/gripper unit									
<b>Gripper function</b>										
PP	Parallel gripping									
<b>Size</b>										
<b>Cushioning</b>										
P	Flexible cushioning									
YSRT	Hydraulic cushioning									
<b>Position sensing</b>										
A	For proximity sensing									

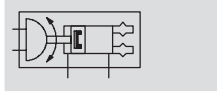
# Swivel/gripper units HGDS

Technical data

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Function

Swivelling/Gripping



- Ø - Size  
12, 16, 20
- I - Stroke  
5, 9, 14 mm



General technical data			
Size	12	16	20
Design	Semi-rotary drive Parallel gripper with drive		
Mode of operation	Double-acting		
Pneumatic connection	M5		
Type of mounting	With threaded hole and centring hole Via through-holes Clamped in dovetail slot		
Fitting position	Any		
Relubrication intervals of guide	10 million switching cycles		
Product weight	[g]	465	660
			1120

Operating and environmental conditions			
Operating pressure	[bar]	3 ... 8	
Operating medium		Filtered compressed air, lubricated or unlubricated	
Ambient temperature <sup>1)</sup>	[°C]	+5 ... +60	
Corrosion resistance class CRC <sup>2)</sup>		2	

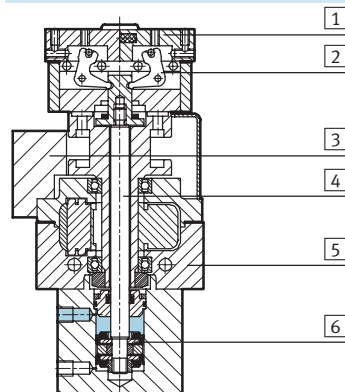
1) Note operating range of proximity sensors

2) Corrosion resistance class 2 according to Festo standard 940 070

Components requiring moderate corrosion resistance. Externally visible parts with primarily decorative surface requirements which are in direct contact with a normal industrial environment or media such as coolants or lubricating agents

## Materials

Sectional view



Swivel/gripper unit		
1	Gripper jaw	Wrought aluminium alloy, nickel-plated
2	Lever	Hardened steel
3	Stop	Wrought aluminium alloy, hard-anodised
4	Piston rod	Stainless steel
5	Housing	Wrought aluminium alloy, hard-anodised
6	Piston	Nitrile rubber, polyurethane
-	Rubber buffer	Nitrile rubber

# Swivel/gripper units HGDS

Technical data

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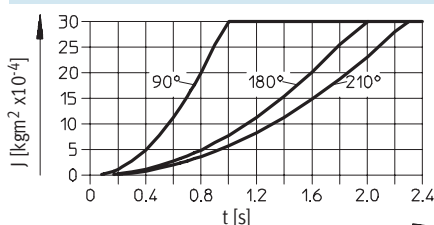
## Technical data – Swivelling

Size			12	16	20	
Swivel angle			[°]	0 ... 210 ➔ 1 / 7.8-10		
Theoretical torque <sup>1)</sup>			[Nm]	0.85	1.25	2.5
Repetition accuracy <sup>1)</sup>	P cushioning	[°]	< 0.2			
	YSRT cushioning	[°]	< 0.02			
Cushioning			➔ 1 / 7.8-6			
Max. swivelling frequency <sup>1)</sup>	P cushioning	[Hz]	2			
	YSRT cushioning	[Hz]	1.5			
Position sensing			For proximity sensing			

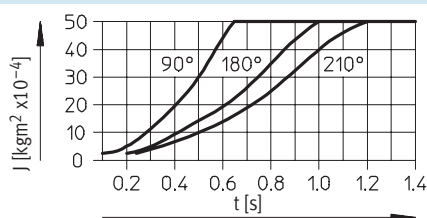
1) At 6 bar

## Mass moments of inertia J at 6 bar as a function of swivel time t and swivel angle

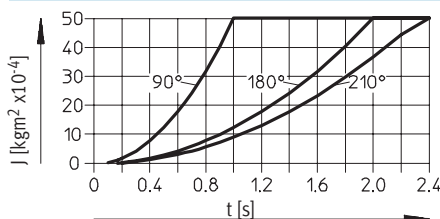
HGDS-PP-12-P-A



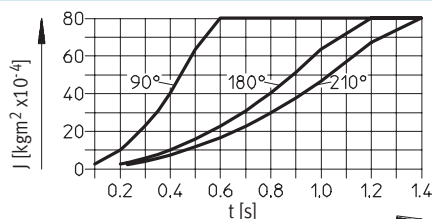
HGDS-PP-12-YSRT-A



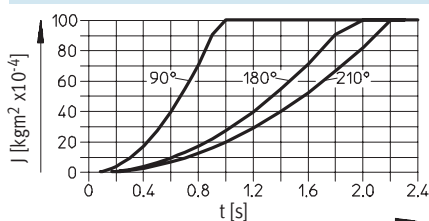
HGDS-PP-16-P-A



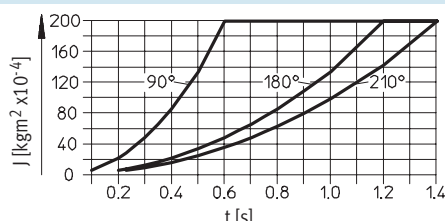
HGDS-PP-16-YSRT-A



HGDS-PP-20-P-A



HGDS-PP-20-YSRT-A



## Dependency between operating pressure and swivel time

When the operating pressure of the gripper drive is reduced, the permissible swivel time at the same mass moment of inertia must be increased by 15% per bar of operating pressure.

Example:

Given:

$$J = 40 \text{ kgm}^2 \times 10^{-4}$$

Operating pressure 4 bar (gripper drive)

Swivel time at 6 bar = 0.4 s, see graph opposite

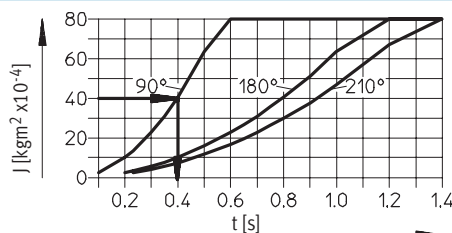
This yields a swivel time at 4 bar:

$$t = 0.4 + 2 \times 15\% = 0.52 \text{ s}$$

Cushioning time of the shock absorber = 0.1 s

This yields a swivel time of

$$t_{\text{tot.}} = 0.52 \text{ s} + 0.1 \text{ s} = 0.62 \text{ s}$$



# Swivel/gripper units HGDS

Technical data

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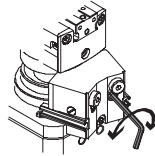
## Precision adjustment of the swivel angle

The swivel angle can be adjusted roughly by means of two stop plates → 1 / 7.8-2. The precision adjustment works as follows:  
Variants P and YSRT differ in only one component. The retainer and the fine

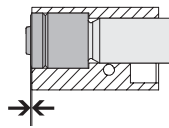
adjustment are identical. In both variants, the rotary vane travels to a metallic stop, which can be adjusted with great accuracy via the adjustable sleeve for P cushioning or the shock absorber for YSRT cushioning.

Size			12	16	20
Precision adjustment range	P cushioning	[°]	-6		
	YSRT cushioning	[°]	-2.5		
Swivel angle adjuster per revolution		[°]	3.1	2.8	2.2

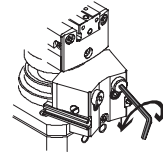
- 1) Loosen the locking screw underneath the cushioning element



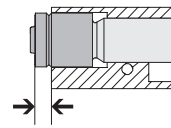
Min. setting range, to the inner stop



- 2) Adjust the cushioning element as required. Observe the minimum and maximum settings.



Max. setting range, to the notch



# Swivel/gripper units HGDS

Technical data

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## Technical data – Gripping

Size	12	16	20
Gripper function	Parallel		
Number of gripper fingers	2		
Max. applied load per external gripper finger <sup>1)</sup> [N]	0.3	0.5	1.0
Stroke per gripper jaw [mm]	2.5	4.5	7
Max. gripper jaw backlash [mm]	0		
Max. gripper jaw angular backlash [°]	0		
Repetition accuracy [mm]	< 0.02		
Max. operating frequency [Hz]	4		
Position sensing	Via proximity sensor		

1) Valid for unthrottled operation

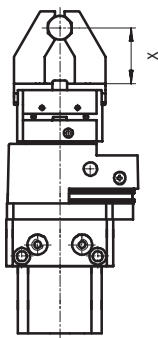
## Gripping force [N] at 6 bar

Size	12	16	20
Gripping force per gripper jaw			
Opening	29	56.5	85
Closing	26	45	65
Total gripping force			
Opening	58	113	170
Closing	52	90	130

## Gripping force $F_{Grip}$ per gripper jaw as a function of operating pressure p

Gripping forces related to operating pressure and lever arm can be determined for the various sizes using the following graphs.

The characteristic curves apply for external and internal gripping.

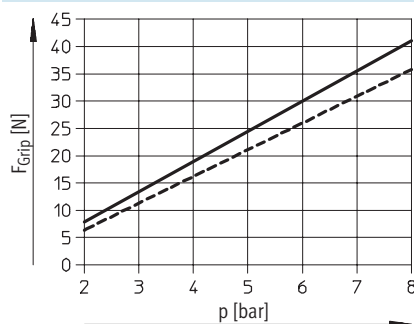


Note

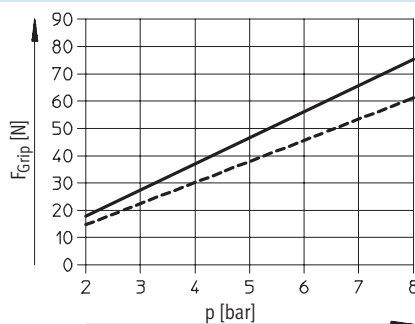
The gripping force is practically independent of the lever arm. Fluctuation at max. lever arm and max. operating pressure approx. 10%.

for unthrottled operation:

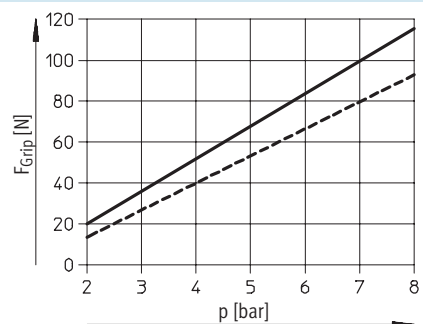
HGDS-12 (max. lever arm x 40 mm)



HGDS-16 (max. lever arm x 50 mm)



HGDS-20 (max. lever arm x 70 mm)



— Opening  
- - - Closing

# Swivel/gripper units HGDS

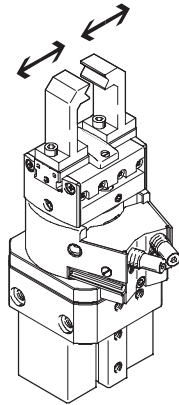
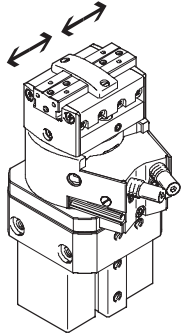
Technical data

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## Opening and closing times [ms] at 6 bar

With gripper jaws

With additional gripper fingers



The indicated opening and closing times [ms] have been measured at room temperature and at 6 bar operating pressure with horizontally mounted gripper without external

gripper fingers. The grippers must be throttled for greater applied loads. Opening and closing times must then be adjusted correspondingly.

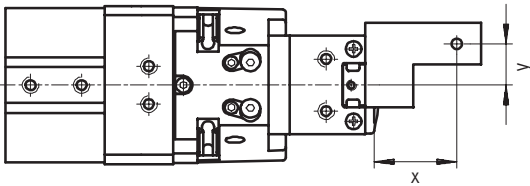
## with additional gripper fingers as a function of applied load

Size		12	16	20
Max. applied load		0.3 N	0.5 N	1.0 N
HGDS-...-A unthrottled	Opening	20	50	70
	Closing	30	50	100

## with additional gripper fingers as a function of applied load

Size	12		16		20		
Applied load	1.0 N	2.0 N	1.0 N	2.0 N	1.0 N	2.0 N	
HGDS-...-A throttled	Closing	100	150	100	200	100	250

## Eccentricity y as a function of lever arm x



The dependency on the lever arm and the maximum permissible off-centre point of force application can be determined for the various sizes using the following graphs.

The gripping forces apply, see above.

It is vital that you adhere to the mass moment of inertia  $\rightarrow 1 / 7.8-5$  when making your selection.

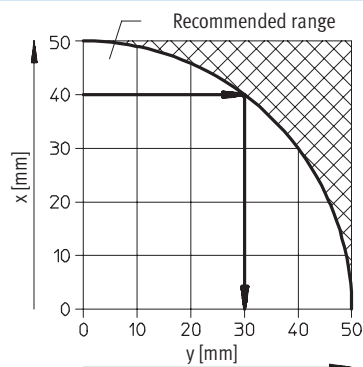
## Calculation example

Lever arm  $x = 40 \text{ mm}$

To be found: Eccentricity  $y$

- Move along the horizontal axis to the point of intersection
- Then move vertically downwards until you intersect the scale
- Read the eccentricity

Max. eccentricity = 30 mm





# Swivel/gripper units HGDS

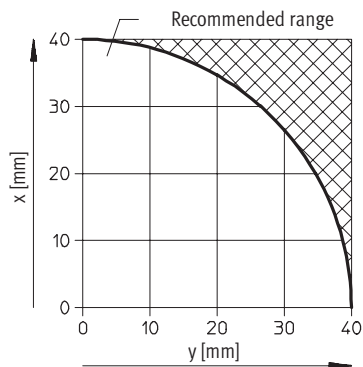
Technical data

FESTO

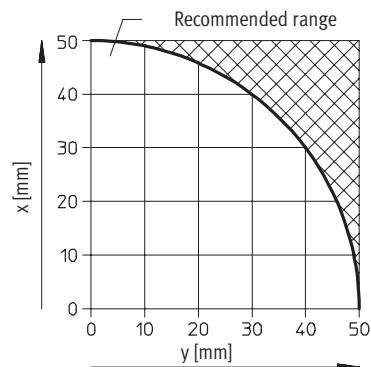
## Eccentricity $y$ as a function of lever arm $x$

for unthrottled operation:

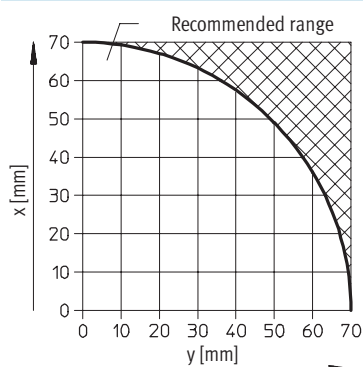
HGDS-12 (max. lever arm 40 mm)



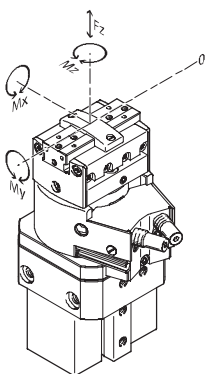
HGDS-16 (max. lever arm 50 mm)



HGDS-20 (max. lever arm 70 mm)



## Characteristic load values per gripper jaw



The indicated permissible forces and torques refer to a single gripper jaw. The indicated values include the lever arm, additional applied loads caused by the workpiece or external gripper fingers, as well as forces which occur during movement.

The zero coordinate line (gripper finger guide) must be taken into consideration for the calculation of torques.

Size	12	16	20
Max. permissible force $F_z$ [N]	20	30	60
Max. permissible torque $M_x$ [Nm]	1.5	4	8
Max. permissible torque $M_y$ [Nm]	1.5	4	8
Max. permissible torque $M_z$ [Nm]	1.5	4	8

# Swivel/gripper units HGDS

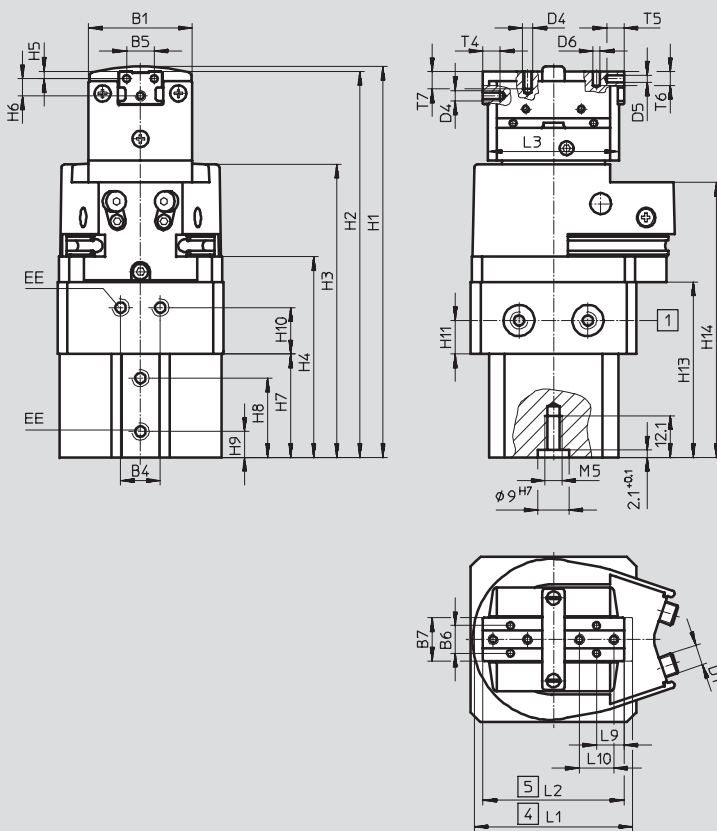
Technical data

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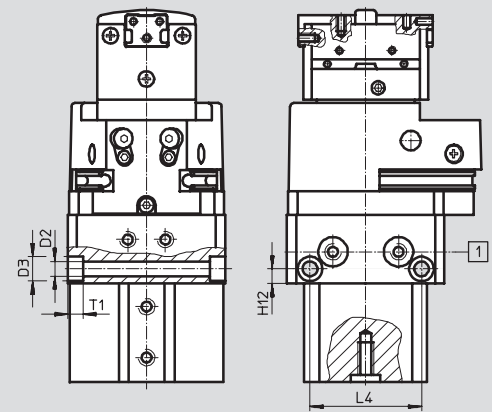
## Dimensions

Download CAD data → [www.festo.com/en/engineering](http://www.festo.com/en/engineering)

### Size 16/20

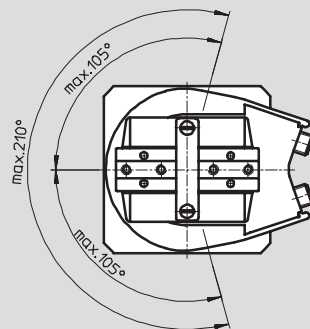


### Size 12



- 1 Cross-section through mounting holes → 1 / 7.8-11
- 2 For dovetail joint with HAVB-3
- 3 Sensor slot for SME-/SMT-10
- 4 Gripper jaws open
- 5 Gripper jaws closed
- 6 Shock absorber YSRT

## Swivel angle



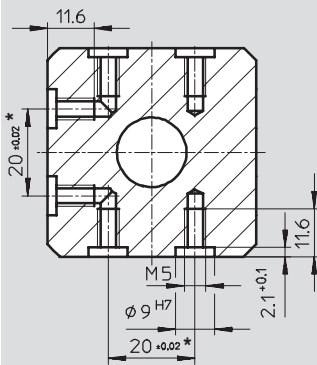
# Swivel/gripper units HGDS

Technical data

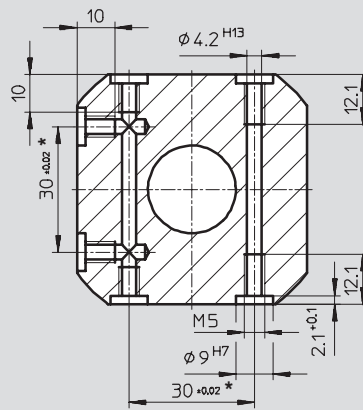
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Cross-section at 1 → 1 / 7.8-10

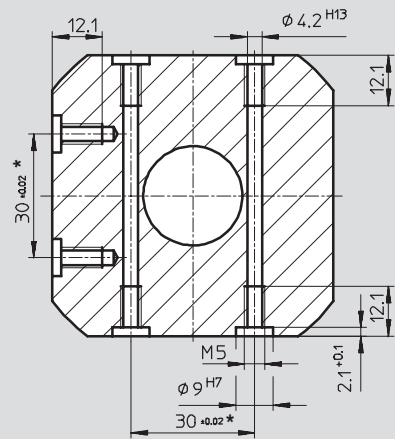
Size 12



Size 16



Size 20



Size	B1	B2	B3	B4	B5	B6	B7	D1	D2 Ø	D3 Ø	D4	D5 Ø
[mm]		±0.03	±0.02*		±0.02	±0.02	±0.1		H13	H13		H8
12	30	48	20	11.5	8	8	12.5	M6x0.5	4.5	7.5	M3	2
16	34	55	30	13	10	10	16	M8x1	–	–	M3	2
20	40	68	30	16	12	12	20	M10x1	–	–	M4	2.5

Size	D6 Ø	EE	H1	H2	H3	H4	H5	H6	H7	H8	H9
[mm]	H8		+1/-0.6	+0.8/-0.4	+1.3/-0.2	+0.8/-0.2	±0.02	±0.12	±0.1	±0.1	
12	2	M5	113.4	111.9	85.1	58.2	2	5	30	23	7.5
16	2	M5	121.7	120.1	92.1	64.3	3	5	34.5	26	8.3
20	2.5	M5	154.8	152.8	112.3	81.7	3	7	43	34.6	8.3

Size	H10	H11	H12	H13	H14	L1	L2	L3	L4	L5	L6
[mm]		-0.1		+1/-0.2	+1/-0.2	±0.5	±0.5	±0.5	±0.1		±0.05
12	13.5	9.7	4.5	51.3	79.8	46	41	38	34	36	24
16	14	8	–	58.2	86.7	58	49	47	–	40.5	27.5
20	19	9	–	73.1	105.6	78	64	61	–	40.5	34

Size	L7	L8 ±1		L9	L10	T1	T4	T5	T6	T7
[mm]	±0.03	P	YSRT	±0.02			min.			min.
12	48	59.5	69.3	8	10	4.6	5	5	4	5
16	55	68.5	80.5	8	10	–	6.5	6	5	5
20	68	85.4	96.4	12	14	–	10	8	7	7

\* Tolerance valid for centring hole Ø 9<sup>H7</sup>

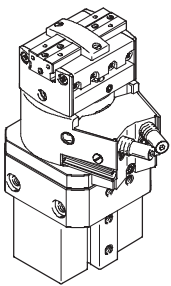
Handling units  
Swivel grippers

7.8


# Swivel/gripper units HGDS

Technical data and accessories

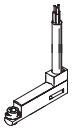
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Ordering data				
	Size	With flexible P cushioning		With hydraulic YSRT cushioning
	[mm]	Part No.	Type	Shock absorber Part No. Type
	12	534 278	HGDS-PP-12-P-A <sup>1)</sup>	534 279 HGDS-PP-12-YSRT-A <sup>1)</sup>
	16	534 280	HGDS-PP-16-P-A <sup>1)</sup>	534 281 HGDS-PP-16-YSRT-A <sup>1)</sup>
	20	534 282	HGDS-PP-20-P-A <sup>1)</sup>	534 283 HGDS-PP-20-YSRT-A <sup>1)</sup>

1) Two centring sleeves are included in the scope of delivery

Ordering data – Accessories				Technical data → 1 / 10.1-3	
	For size	Weight	Part No.	Type	PU <sup>1)</sup>
	[mm]	[g]			
Centring sleeve					
	12, 16, 20	1	150 927	ZBH-9	10

1) Packaging unit quantity

Ordering data – Proximity sensors for C-slot, connecting cable at right angles					Technical data → 1 / 10.2-57	
	Electrical connection		Cable length	Part No.	Type	
	Cable	Plug M8				
			[m]			
	NO contact, magneto-resistive					
	3-core	–	2.5	526 674	SMT-10F-PS-24V-K2,5Q-OE	
	–	3-pin	0.3	526 675	SMT-10F-PS-24V-K0,3Q-M8D	
	NO contact, magnetic reed					
	3-core	–	2.5	526 670	SME-10F-DS-24V-K2,5Q-OE	
	–	3-pin	0.3	526 671	SME-10F-DS-24V-K0,3Q-M8D	

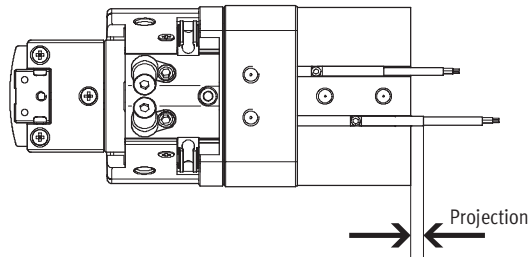
## Swivel/gripper units HGDS


Accessories







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If the swivel/gripper unit is mounted **on the front**, proximity sensors with the connecting cable **at right angles** should be used.

When proximity sensors with in-line connecting cables are used, the sensors project beyond the swivel/gripper unit after the switching point has been set.



Ordering data – Proximity sensors for C-slot, in-line connecting cable							Technical data➔ 1 / 10.2-60	
	Electrical connection		Cable length [m]	Projection at HGDS in [mm]			Part No.	Type
	Cable	Plug M8		Ø 12	Ø 16	Ø 20		
	NO contact, magneto-resistive							
	3-core	–	2.5	8.3	7.1	4.4	525 915	SMT-10F-PS-24V-K2,5L-OE
	2-core						526 677	SMT-10F-ZS-24V-K2,5L-OE
	–	3-pin	0.3				525 916	SMT-10F-PS-24V-K0,3L-M8D
	NO contact, magnetic reed							
	3-core	–	2.5	2.7	2.1	–	525 913	SME-10F-DS-24V-K2,5L-OE
	2-core						526 672	SME-10F-ZS-24V-K2,5L-OE
	–	3-pin	0.3				525 914	SME-10F-DS-24V-K0,3L-M8D

Ordering data – Plug sockets with cable							Technical data➔ 1 / 10.2-114	
	Assembly	Switch output		Connection	Cable length [m]	Part No.	Type	
		PNP	NPN					
Straight socket								
	Union nut M8			3-pin	2.5	159 420	SIM-M8-3GD-2,5-PU	
					5	159 421	SIM-M8-3GD-5-PU	
Angled socket								
	Union nut M8			3-pin	2.5	159 422	SIM-M8-3WD-2,5-PU	
					5	159 423	SIM-M8-3WD-5-PU	

