

- Sturdy
- Gripping forces of up to 825 N
- Reliable thanks to gripping force retention
- Splash-proof through use of sealing air

# Parallel grippers HGPT, robust

Key features



## At a glance

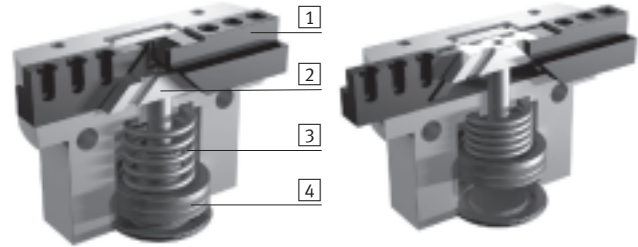
The force generated by the linear motion is translated into the gripper jaw movement via a wedge mechanism with guided motion sequence. This also guarantees synchronous movement of the gripper jaw. The virtually backlash-free slideway is realised using ground-in gripper jaws.

Flexible range of applications

- Double-acting gripper
- Compression spring for supplementary or retaining gripping forces
- For use as a single-acting gripper with only one compressed air connection
- Suitable for external and internal gripping

Gripper closed

Gripper open



- 1 Gripper jaw
- 2 Wedge with restricted guidance
- 3 Spring
- 4 Piston with magnet

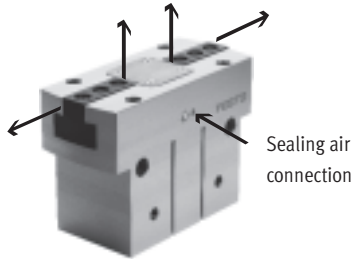


Gripper selection software  
[www.festo.com/en/engineering](http://www.festo.com/en/engineering)

## Sealing air connection

Compressed air flows past the gripper jaw when sealing air (max. 0.5 bar) is connected.

This prevents, for example, particles and soluble cutting oil from entering the gripper jaw guides.



## Versatile compressed air connections

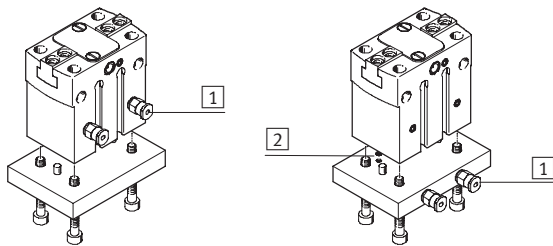
Direct from the front

Via adapter plate from underneath

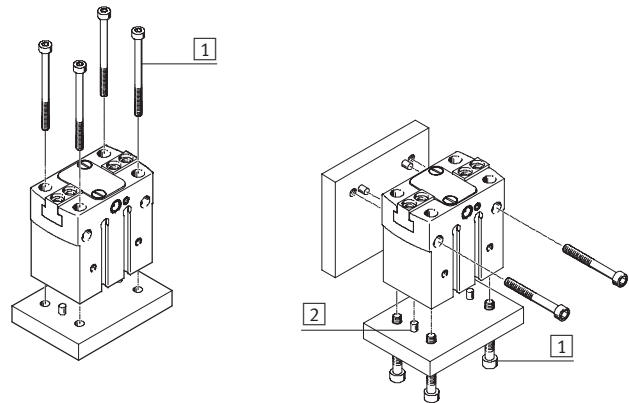
## Mounting options

Direct mounting from above

from underneath and from the side



- 1 Compressed air connections
- 2 O-rings

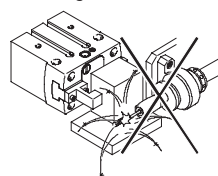


- 1 Mounting screws
- 2 Centring pins

- - Note

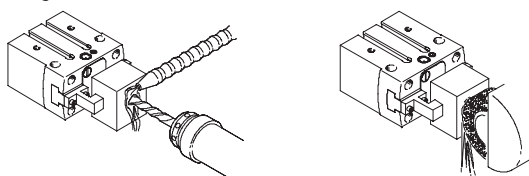
These grippers are not designed for the following application examples or only under limited conditions:

Not designed for



- Welding spatter

Designed for but under limited conditions

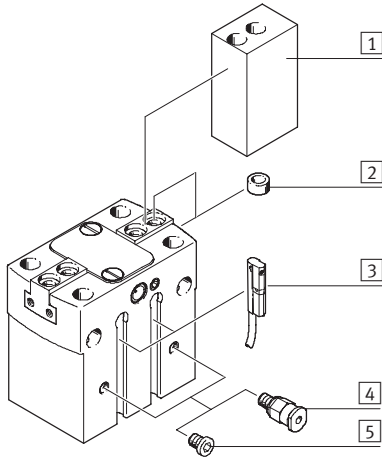


- Machining with sealing air possible
- Aggressive media only possible after consulting Festo

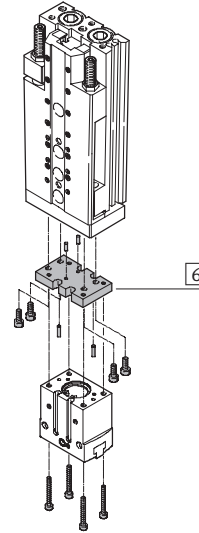
# Parallel grippers HGPT, robust

Peripherals overview and type codes

## Peripherals overview



## System product for handling and assembly technology



Accessories			
Type	Brief description	→ Page	
1	Unmachined gripper finger BUB-HGPT	Unmachined part specially matched to the gripper jaws for custom building of gripper fingers	1 / 7.7-14
2	Centring sleeve ZBH	For centring when attaching gripper fingers	1 / 7.7-15
3	Proximity sensor SME/SMT-10	For sensing the piston position	1 / 7.7-15
4	Push-in fitting QS	For connecting compressed air tubing with standard external diameters	Volume 3
5	Blanking plug B	For sealing compressed air connections when using air connections at the front	1 / 7.7-15
6	-	Drive/gripper connections	Volume 5

## Type codes

HGPT – 16 – A – G1

Type	
HGPT	Parallel gripper

Size	
16	

Position sensing	
A	For proximity sensing

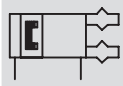
Gripping force retention	
G1	Open
G2	Closed



# Parallel grippers HGPT, robust

Technical data

FESTO

Function  
Double-acting  
HGPT-...-A



 Size  
16 ... 63 mm  
 Stroke  
6 ... 32 mm



Single-acting or  
with gripping force retention ...  
... open HGPT-...-G1



... closed HGPT-...-G2



General technical data							
Size	16	20	25	35	40	50	63
Design	Wedge mechanism Guided motion sequence						
Mode of operation	Double-acting						
Gripper function	Parallel						
Number of gripper jaws	2						
Max. applied load per external gripper finger <sup>1)</sup> [N]	0.5	1	1.5	2	2.5	3	4
Stroke per gripper jaw [mm]	3	4	6	8	10	12	16
Pneumatic connection	M3	M3	M5	M5	M5	G $\frac{3}{8}$	G $\frac{3}{8}$
Pneumatic connection Sealing air	M3	M3	M5	M5	M5	M5	M5
Repetition accuracy <sup>2)</sup> [mm]	< 0.03	< 0.04	< 0.05				
Max. interchangeability [mm]	0.2						
Max. gripper jaw backlash <sup>3)</sup> [mm]	0.02						
Max. gripper jaw angular backlash [°]	0.1						
Max. operating frequency [Hz]	3					2	
Rotational symmetry [mm]	< $\varnothing$ 0.2						
Position sensing	For proximity sensing						
Type of mounting	Via through-hole and dowel pin Via female thread and dowel pin						
Fitting position	Any						

- 1) Valid for unthrottled operation  
 2) End-position drift under constant conditions of use with 100 consecutive strokes in the direction of movement of the gripper jaws  
 3) In the direction of the gripper jaw movement  
 -  $\varnothing$  Note: This product conforms with the ISO 1179-1 standard and the ISO 228-1 standard.

Operating and environmental conditions			
Min. operating pressure	HGPT-...-A	[bar]	3
	HGPT-...-G...	[bar]	5
Max. operating pressure		[bar]	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

# Parallel grippers HGPT, robust

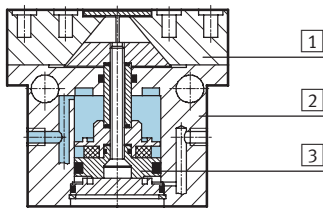
Technical data



Weight [g]							
Size	16	20	25	35	40	50	63
HGPT-...-A	102	183	361	625	1209	1984	3633
HGPT-...-G1	104	186	371	645	1252	2102	3763
HGPT-...-G2	104	186	371	645	1252	2102	3763

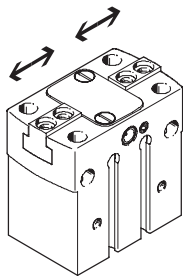
## Materials

Sectional view



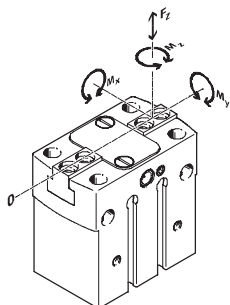
Parallel gripper		
1	Gripper jaw	Hardened steel
2	Housing	Aluminium, coated with CompCote
3	Piston	Gunmetal (red brass)
-	Seals	Nitrile rubber
Note on materials		Free of copper, PTFE and silicone

## Gripping force [N] at 6 bar



Size	16	20	25	35	40	50	63
Gripping force per gripper jaw							
Opening	42	75	110	250	300	480	825
Closing	36	70	100	230	270	440	770
Total gripping force							
Opening	84	150	220	500	600	960	1650
Closing	72	140	200	460	540	880	1540

## Characteristic load values at the gripper jaws



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.

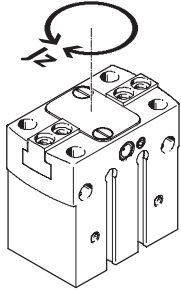
Size	16	20	25	35	40	50	63	
Max. permissible force $F_z$	[N]	200	300	500	900	1500	2500	4000
Max. permissible torque $M_x$	[Nm]	10	15	30	50	80	100	140
Max. permissible torque $M_y$	[Nm]	7	10	25	40	60	90	120
Max. permissible torque $M_z$	[Nm]	5	8	15	30	40	60	80

# Parallel grippers HGPT, robust

Technical data



## Mass moment of inertia [kgm<sup>2</sup>x10<sup>-4</sup>]



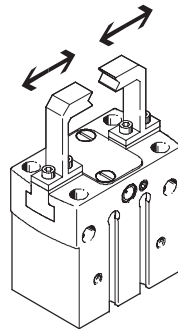
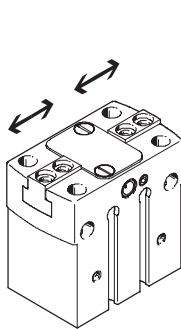
Mass moment of inertia [kgm<sup>2</sup>x10<sup>-4</sup>]  
for parallel grippers in relation to the  
central axis with no load.

Size	16	20	25	35	40	50	63
HGPT-...-A	0.177	0.391	1.263	3.383	9.673	25.147	74.991
HGPT-...-G1	0.178	0.392	1.272	3.411	9.786	25.460	75.409
HGPT-...-G2	0.178	0.392	1.272	3.411	9.786	25.460	75.409

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

without external gripper fingers

with external 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.

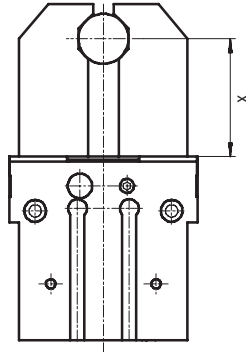
Size		16	20	25	35	40	50	63
without external gripper fingers								
HGPT-...-A	Opening	20	31	30	40	66	85	150
	Closing	21	31	33	40	61	76	135
HGPT-...-G1	Opening	10	26	30	39	57	65	123
	Closing	44	51	64	92	130	150	282
HGPT-...-G2	Opening	41	52	50	78	100	130	260
	Closing	21	31	30	39	61	70	130
with external gripper fingers as a function of applied load								
HGPT-...	1 N	100	-	-	-	-	-	-
	2 N	200	150	100	-	-	-	-
	3 N	300	250	200	150	100	-	-
	4 N	-	350	300	250	200	150	-
	5 N	-	-	400	350	300	250	200
	6 N	-	-	-	450	400	300	250
	8 N	-	-	-	-	-	450	400
	10 N	-	-	-	-	-	-	500

# Parallel grippers HGPT, robust

Technical data

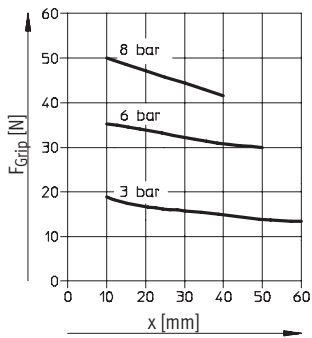
## Gripping force $F_{Grip}$ per gripper jaw as a function of operating pressure and lever arm $x$

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

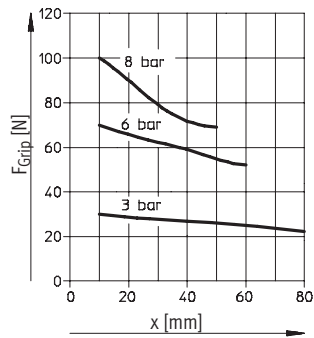


### As external gripper: Closing operation

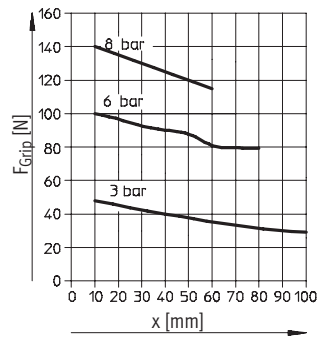
HGPT-16-A



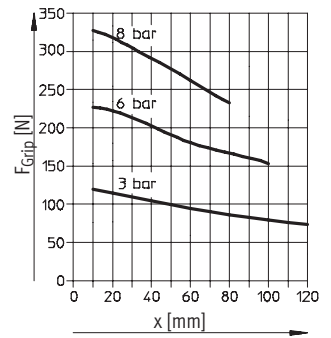
HGPT-20-A



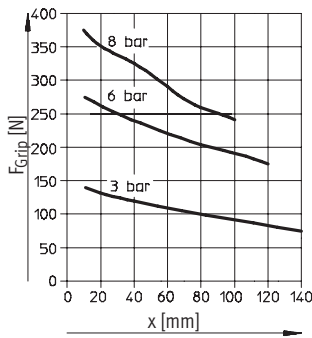
HGPT-25-A



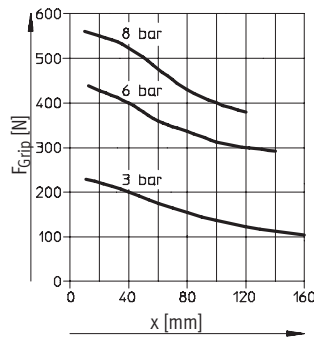
HGPT-35-A



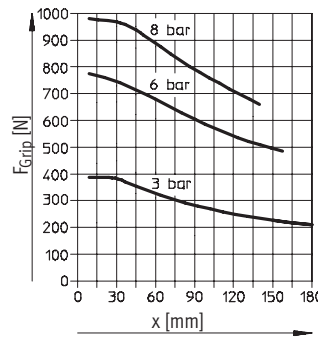
HGPT-40-A



HGPT-50-A



HGPT-63-A



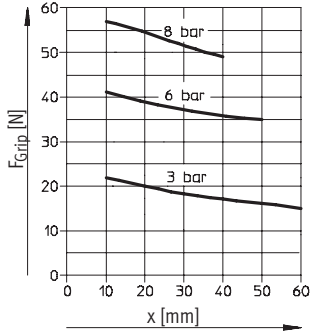
# Parallel grippers HGPT, robust

Technical data

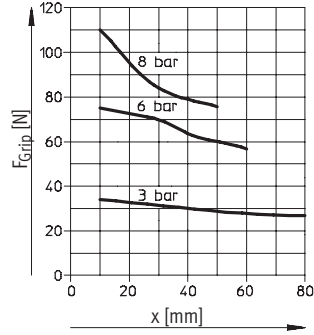


Gripping force  $F_{Grip}$  per gripper jaw as a function of operating pressure and lever arm  $x$   
As internal gripper: Opening operation

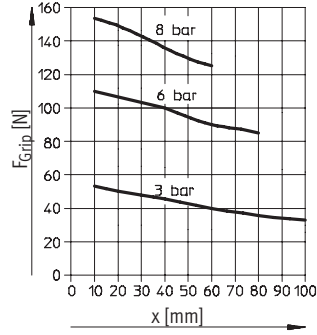
HGPT-16-A



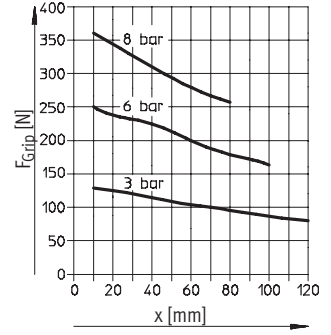
HGPT-20-A



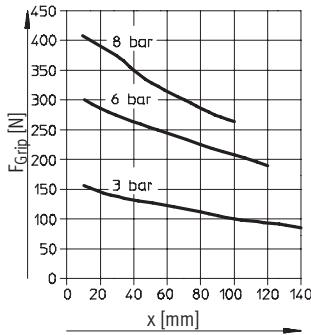
HGPT-25-A



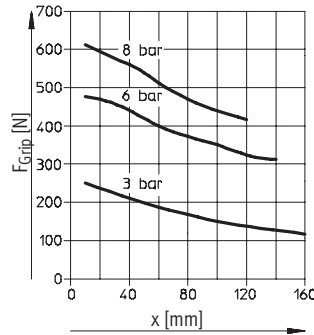
HGPT-35-A



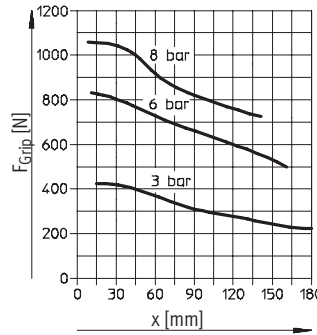
HGPT-40-A



HGPT-50-A



HGPT-63-A





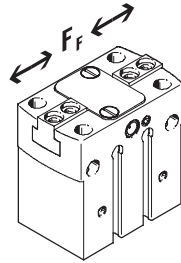
# Parallel grippers HGPT, robust

Technical data

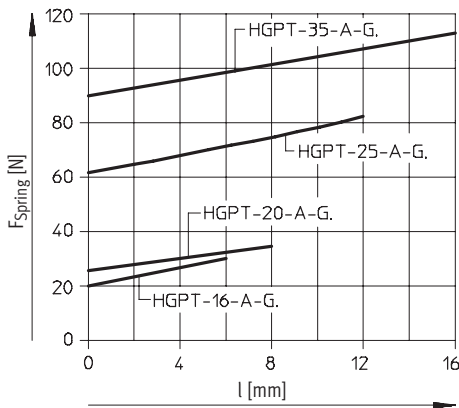
## Spring force $F_{Spring}$ as a function of gripper size and overall stroke $l$

Gripping force retention for HGPT-...-G...

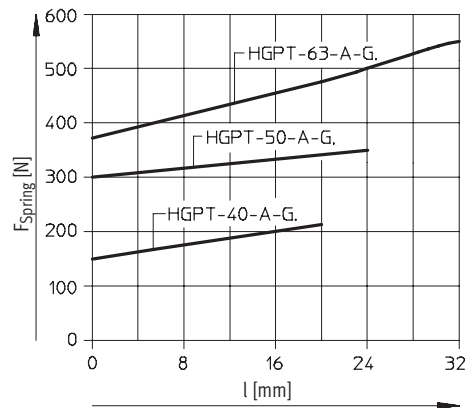
Spring forces  $F_{Spring}$  as a function of gripper size and overall stroke  $l$  can be determined for the various gripper types (HGPT-...-G...) using the following graphs.



Size 16 ... 35



Size 40 ... 63



The lever arm  $x$  must be taken into consideration when determining the actual spring force  $F_{Stotal}$ .

The formulae for calculating the spring force are provided in the table opposite.

Size	$F_{Stotal} =$
16	$-0.2 * x + 0.8 * F_{Spring}$
20	$-0.375 * x + 0.8 * F_{Spring}$
25	$-0.25 * x + 0.8 * F_{Spring}$
35	$-1 * x + 0.8 * F_{Spring}$
40	$-0.9 * x + 0.8 * F_{Spring}$
50	$-1.36 * x + 0.8 * F_{Spring}$
63	$-2.2 * x + 0.8 * F_{Spring}$

## Determination of the actual gripping forces $F_{Gr}$ for HGPT-...-G1 and HGPT-...-G2 depending on the application

Parallel grippers with integrated spring type HGPT-...-G1 (opening gripping force retention) and HGPT-...-G2 (closing gripping force retention) can be used as:

- single-acting grippers
- grippers with supplementary gripping force and
- grippers with gripping force retention depending on requirements.

In order to calculate available gripping forces  $F_{Gr}$  (per gripper jaw), the gripping force ( $F_{Grip}$ ) and spring

force ( $F_{Stotal}$ ) must be combined accordingly.

### Application

Single-acting

- Gripping with spring force:  
 $F_{Gr} = F_{Stotal}$
- Gripping with pressure force:  
 $F_{Gr} = F_{Grip} - F_{Stotal}$

Supplementary gripping force

- Gripping with pressure and spring force:  
 $F_{Gr} = F_{Grip} + F_{Stotal}$

Gripping force retention

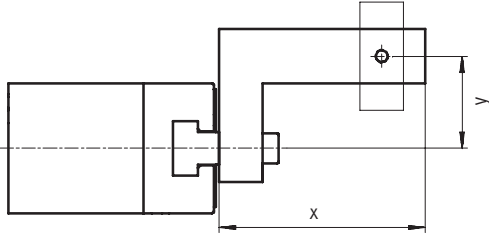
- Gripping with spring force:  
 $F_{Gr} = F_{Stotal}$

# Parallel grippers HGPT, robust

Technical data



## Gripping force $F_H$ per gripper jaw at 6 bar as a function of lever arm $x$ and eccentricity $y$



Gripping forces at 6 bar dependent upon eccentric application of force and the maximum permissible off-centre point of force application can be determined for the various sizes using the following graphs.

### Calculation example

Given:

Lever arm  $x = 40$  mm

Eccentricity  $y = 45$  mm

To be found:

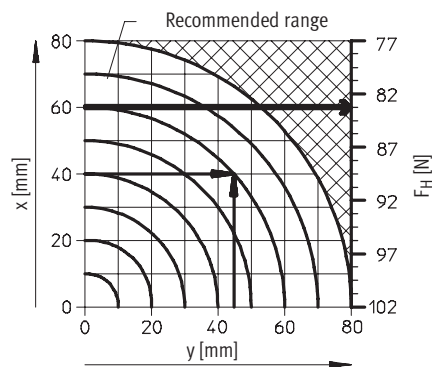
Gripping force at 6 bar

Procedure:

- Determine the intersection  $xy$  between lever arm  $x$  and eccentricity  $y$  in the graph for HGPT-25-A-...
- Draw an arc (with centre at origin) through intersection  $xy$
- Determine the intersection between the arc and the X axis
- Read the gripping force

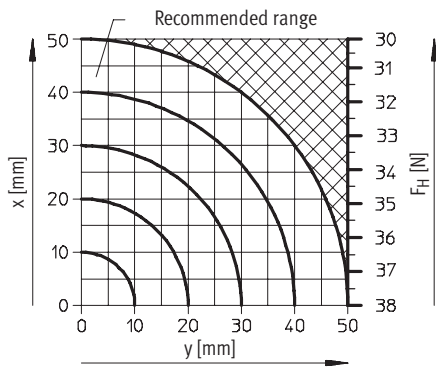
Result:

Gripping force = approx. 83 N

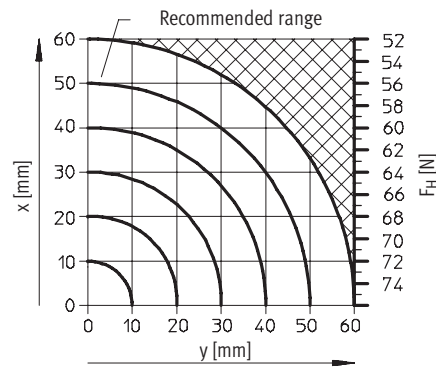


### As external gripper: Closing operation

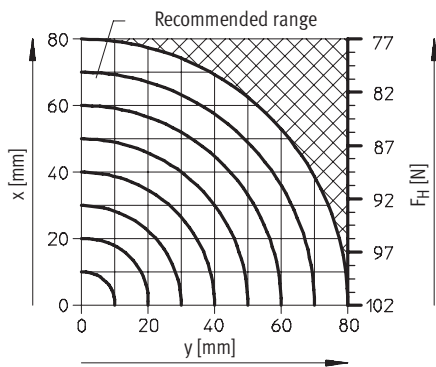
HGPT-16-A



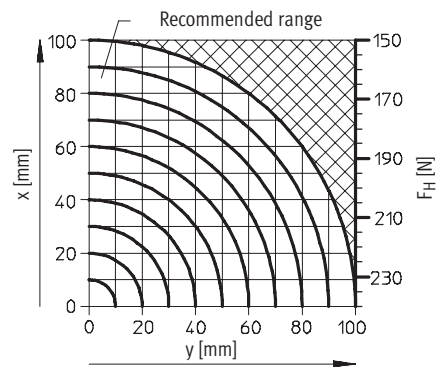
HGPT-20-A



HGPT-25-A



HGPT-35-A

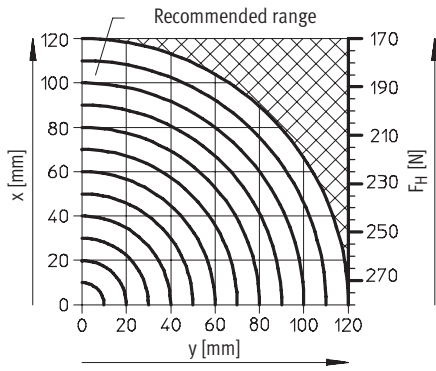


# Parallel grippers HGPT, robust

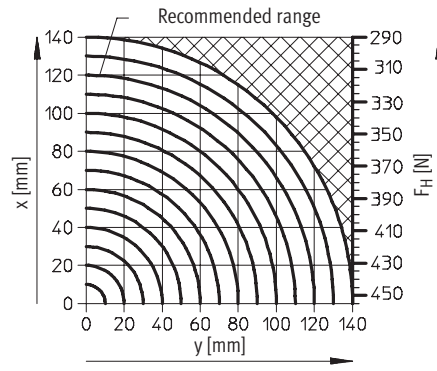
Technical data

## Gripping force $F_H$ per gripper jaw at 6 bar as a function of lever arm $x$ and eccentricity $y$

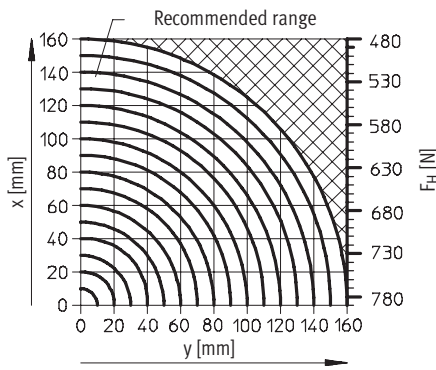
HGPT-40-A



HGPT-50-A

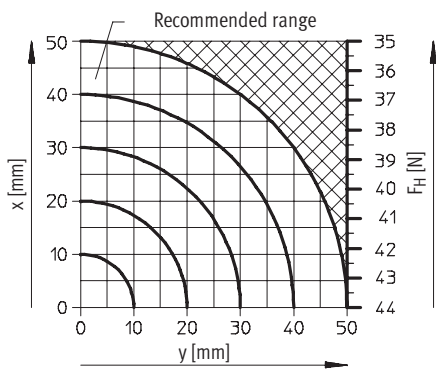


HGPT-63-A

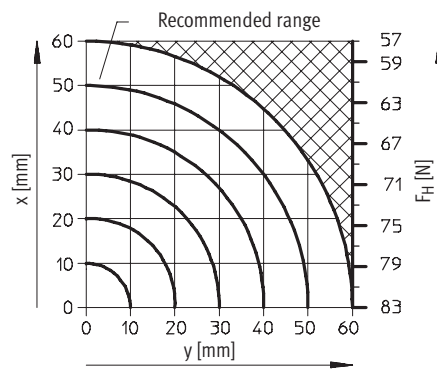


## As internal gripper: Opening operation

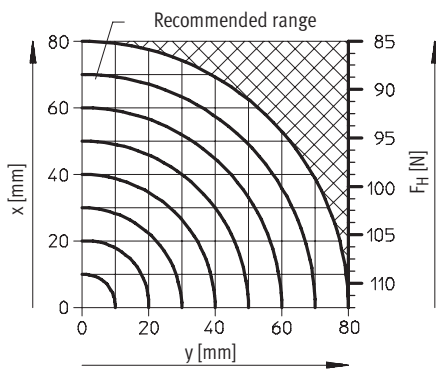
HGPT-16-A



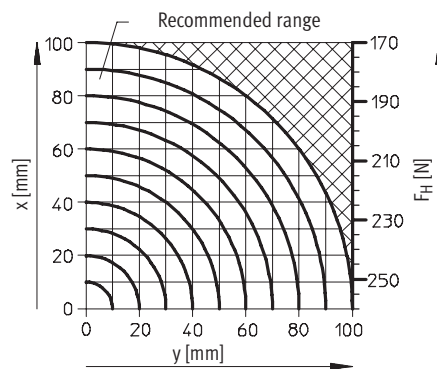
HGPT-20-A



HGPT-25-A



HGPT-35-A



# Parallel grippers HGPT, robust

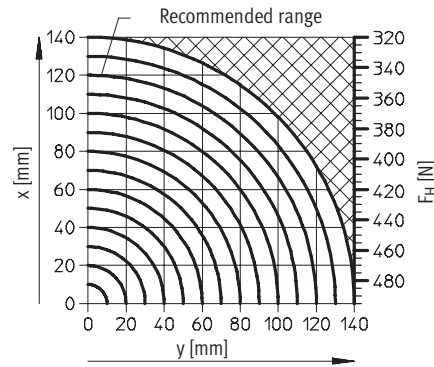
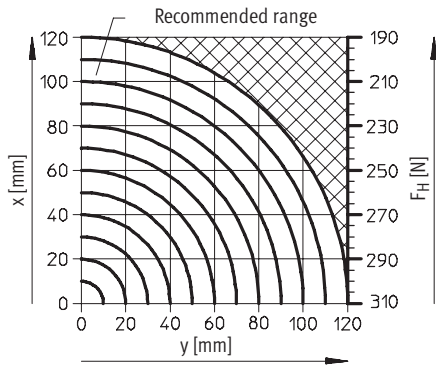
Technical data



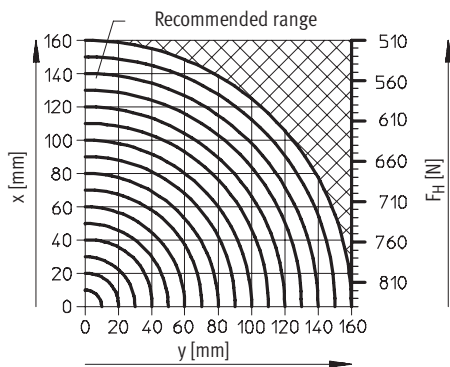
## Gripping force $F_H$ per gripper jaw at 6 bar as a function of lever arm $x$ and eccentricity $y$

HGPT-40-A

HGPT-50-A

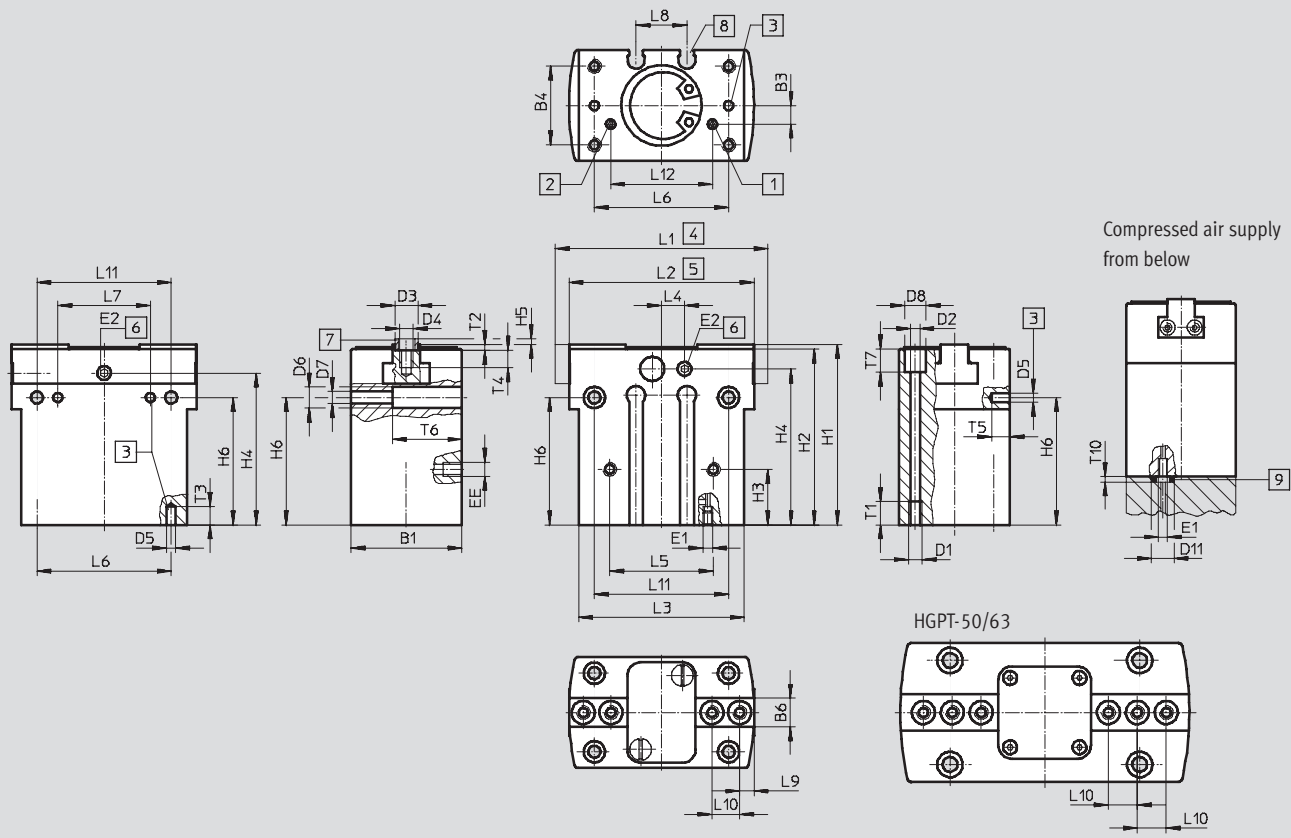


HGPT-63-A



## Dimensions

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



# Parallel grippers HGPT, robust

Technical data

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1) Compressed air connection opening, either on the side or bottom (bottom connection sealed on delivery)	3) Hole for dowel pin (not included in scope of delivery)	7) Centring sleeves ZBH (4 included in scope of delivery)	9) O-ring for parallel grippers HGPT-16: Ø 2x1.5 HGPT-20: Ø 3x1.5 HGPT-25: Ø 3x1.5 HGPT-35: Ø 4x1.5 HGPT-40: Ø 5x1.5 HGPT-50: Ø 5x1.5 HGPT-63: Ø 5x1.5
2) Compressed air connection closing, either on the side or bottom (bottom connection sealed on delivery)	4) Gripper jaw open	8) Slot for proximity sensor	
	5) Gripper jaw closed		
	6) Sealing air connection (sealed on delivery)		

Size	B1	B3	B4	B6	D1	D2	D3	D4	D5	D6	D7
[mm]	±0.05	±0.1	±0.1	-0.05 -0.1		Ø	Ø		Ø	Ø	Ø
16	24	4	17	6	M3	2.6	5	M3	2	4.6+0.1	2.6
20	28	7	22	6.5	M4	3.2	5	M3	3	6+0.2	3.2
25	36	10	27	10	M5	4.2	7	M4	4	8+0.3	4.2
35	42	9	32	12	M5	4.2	9	M6	4	10+0.3	5.3
40	50	13	38	14	M6	5.1	9	M6	5	11+0.3	6.4
50	60	14	45	15.5	M8	6.4	9	M6	6	13.5+0.3	8.4
63	72	12	56	20	M8	6.4	12	M8	6	13.5+0.3	8.4

Size	D8	D11	EE	E1	E2	H1	H2	H3	H4	H5	H6
[mm]	Ø					±0.05	±0.05	±0.1		-0.3	±0.02 <sup>1)</sup> ±0.1 <sup>2)</sup>
16	4.6+0.1	5	M3	M2	M3	39	38	12	33.7	1.2	27.5
20	6+0.2	6	M3	M3	M3	46	45	15	37	1.2	24
25	8+0.3	6	M5	M3	M5	57	56	20	46	1.4	34
35	8+0.3	7	M5	M4	M5	67	66	28	53	1.9	38
40	9+0.3	8	M5	M5	M5	83	82	36	68	1.9	53
50	11+0.3	8	G1/8	M5	M5	97	96	30	78	1.9	61
63	11+0.3	8	G1/8	M5	M5	117	116	26	92	2.4	67

Size	L1	L2	L3	L4	L5	L6	L7	L8	L9	L10
[mm]	±0.5	±0.5	±0.1		±0.1	±0.02 <sup>1)</sup> ±0.1 <sup>2)</sup>	±0.02	+0.1	±0.02 <sup>1)</sup> ±0.1 <sup>2)</sup>	±0.02 <sup>1)</sup> ±0.1 <sup>2)</sup>
16	46	40	35.8	3.8	22.4	29	20	11	3	6
20	58	50	44	0	28	35	24	18	4	8
25	76	64	52	0	28	42	20	17	5	12
35	96	80	64	0	40	52	40	24	6	15
40	120	100	80	0	48	66	50	32	10	18
50	149	125	100	0	56	82	60	32	10	12.5
63	192	160	125	0	74	100	76	34	10	18

Size	L11	L12	T1	T2	T3	T4	T5	T6	T7	T10
[mm]	±0.1	±0.1	min.	+0.1	min.	min.	min.		+0.2	
16	29	22	5	1.3	4	5	4	15	24	1.2
20	35	24	6	1.3	4	5	4	19	11	1.2
25	42	28	10	1.6	4	5	4	24	16	1.2
35	52	40	10	2.1	6	10	4	27	19	1.2
40	66	44	12	2.1	6	10	6	33	20	1.2
50	82	56	12	2.1	8	10	8	43	23	1.2
63	100	70	12	2.6	10	12	10	55	35	1.2

1) For centring

2) For through-and threaded hole

- | - Note: This product conforms with the ISO 1179-1 standard and the ISO 228-1 standard.

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Technical data and accessories

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Ordering data						
Size [mm]	Double-acting without compression spring		Single-acting or with gripping force retention			
	Part No.	Type	open Part No.	Type	closed Part No.	Type
16	535 858	HGPT-16-A	535 859	HGPT-16-A-G1	535 860	HGPT-16-A-G2
20	535 861	HGPT-20-A	535 862	HGPT-20-A-G1	535 863	HGPT-20-A-G2
25	535 864	HGPT-25-A	535 865	HGPT-25-A-G1	535 866	HGPT-25-A-G2
35	535 867	HGPT-35-A	535 868	HGPT-35-A-G1	535 869	HGPT-35-A-G2
40	535 870	HGPT-40-A	535 871	HGPT-40-A-G1	535 872	HGPT-40-A-G2
50	535 873	HGPT-50-A	535 874	HGPT-50-A-G1	535 875	HGPT-50-A-G2
63	535 876	HGPT-63-A	535 877	HGPT-63-A-G1	535 878	HGPT-63-A-G2

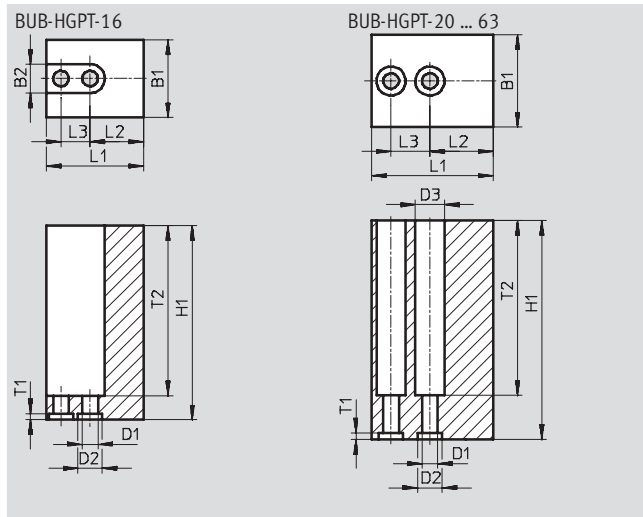
## Accessories

### Unmachined gripper finger

#### BUB-HGPT

(Scope of delivery: 2 pcs.)

Material:  
Aluminium



Dimensions and ordering data							
For size	B1	B2	D1	D2	D3	H1	L1
[mm]	±0.05	+0.22	∅ H13	∅ H8	∅ +0.22	±0.05	±0.05
16	16	6	3.2	5	-	40	20
20	19	-	3.2	5	6	45	25
25	24	-	4.3	7	8	60	32
35	28	-	6.4	9	11	70	40
40	34	-	6.4	9	11	75	50
50	40	-	6.4	9	11	100	62.5
63	50	-	8.4	12	13.5	120	80



For size	L2	L3	T1	T2	Weight per unmachined gripper finger [g]	Part No.	Type
[mm]	±0.02 <sup>1)</sup> ±0.1 <sup>2)</sup>	±0.01 <sup>1)</sup> ±0.1 <sup>1)</sup>	+0.1				
16	11	6	1.3	35	28	537 198	BUB-HGPT-16
20	13	8	1.3	36	53	537 199	BUB-HGPT-20
25	15	12	1.6	51	112	537 200	BUB-HGPT-25
35	19	15	2.1	61	182	537 201	BUB-HGPT-35
40	22	18	2.1	71	312	537 202	BUB-HGPT-40
50	27.5	25	2.1	91	638	537 203	BUB-HGPT-50
63	34	36	2.6	110	1 230	537 204	BUB-HGPT-63

1) For centring  
2) For through-hole



# Parallel grippers HGPT, robust



Accessories



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Ordering data						
	For size [mm]	Remarks	Weight [g]	Part No.	Type	PU <sup>1)</sup>
Centring sleeve ZBH			Technical data → 1 / 10.1-3			
	16, 20	For centring unmachined gripper jaws/gripper fingers on the gripper jaws	1	<b>189 652</b>	<b>ZBH-5</b>	10
	25		1	<b>186 717</b>	<b>ZBH-7</b>	10
	35, 40, 50		1	<b>150 927</b>	<b>ZBH-9</b>	10
	63		1	<b>189 653</b>	<b>ZBH-12</b>	10
	20, 25	For lateral centring of gripper fingers on the gripper jaws	1	<b>189 652</b>	<b>ZBH-5</b>	10
	35, 40, 50, 63		1	<b>186 717</b>	<b>ZBH-7</b>	10
Blanking plug B			Technical data → Volume 4			
	16, 20	For sealing the compressed air connections	0.6	<b>30 979</b>	<b>B-M3-S9</b>	10
	25, 35, 40		1	<b>174 308</b>	<b>B-M5-B</b>	10
	50, 63		5	<b>3 568</b>	<b>B-1/8</b>	10

1) Packaging unit quantity

Ordering data – Proximity sensors for C-slot, magneto-resistive					Technical data → <a href="http://www.festo.com/catalogue/sm">www.festo.com/catalogue/sm</a>	
	Type of mounting	Switch output	Electrical connection, connection direction	Cable length [m]	Part No.	Type
N/O contact						
	Insertable in the slot from above, flush with cylinder profile	PNP	Cable, 3-wire, in-line	2.5	<b>525 915</b>	<b>SMT-10F-PS-24V-K2,5L-OE</b>
			Plug M8x1, 3-pin, in-line	0.3	<b>525 916</b>	<b>SMT-10F-PS-24V-K0,3L-M8D</b>
			Cable, 3-wire, lateral	2.5	<b>526 674</b>	<b>SMT-10F-PS-24V-K2,5Q-OE</b>
			Plug M8x1, 3-pin, lateral	0.3	<b>526 675</b>	<b>SMT-10F-PS-24V-K0,3Q-M8D</b>
	Insertable in the slot lengthwise	PNP	Plug M8x1, 3-pin, in-line	0.3	<b>173 220</b>	<b>SMT-10-PS-SL-LED-24</b>
			Cable, 3-wire, in-line	2.5	<b>173 218</b>	<b>SMT-10-PS-KL-LED-24</b>

Ordering data – Proximity sensors for C-slot, magnetic reed					Technical data → <a href="http://www.festo.com/catalogue/sm">www.festo.com/catalogue/sm</a>	
	Type of mounting	Switch output	Electrical connection, connection direction	Cable length [m]	Part No.	Type
N/O contact						
	Insertable in the slot from above, flush with cylinder profile	Contacting	Plug M8x1, 3-pin, in-line	0.3	<b>525 914</b>	<b>SME-10F-DS-24V-K0,3L-M8D</b>
			Cable, 3-wire, in-line	2.5	<b>525 913</b>	<b>SME-10F-DS-24V-K2,5L-OE</b>
			Plug M8x1, 3-pin, lateral	0.3	<b>526 671</b>	<b>SME-10F-DS-24V-K0,3Q-M8D</b>
			Cable, 3-wire, lateral	2.5	<b>526 670</b>	<b>SME-10F-DS-24V-K2,5Q-OE</b>
	Insertable in the slot lengthwise	Contacting	Plug M8x1, 3-pin, in-line	0.3	<b>173 212</b>	<b>SME-10-SL-LED-24</b>
			Cable, 3-wire, in-line	2.5	<b>173 210</b>	<b>SME-10-KL-LED-24</b>

Ordering data – Connecting cables				Technical data → <a href="http://www.festo.com/catalogue/nebu">www.festo.com/catalogue/nebu</a>	
	Electrical connection, left	Electrical connection, right	Cable length [m]	Part No.	Type
	Straight socket, M8x1, 3-pin	Cable, open end, 3-wire	2.5	<b>541 333</b>	<b>NEBU-M8G3-K-2.5-LE3</b>
			5	<b>541 334</b>	<b>NEBU-M8G3-K-5-LE3</b>
	Angled socket, M8x1, 3-pin	Cable, open end, 3-wire	2.5	<b>541 338</b>	<b>NEBU-M8W3-K-2.5-LE3</b>
			5	<b>541 341</b>	<b>NEBU-M8W3-K-5-LE3</b>

