

Parallel grippers HGPT-B, heavy-duty

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Parallel grippers HGPT-B, heavy-duty

Key features

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Advantages compared with the parallel gripper HGPT

- **Space-optimised:**
Choice of shorter housing without gripping force retention or longer housing with gripping force retention
- **Increased gripping force/
high-force variant:**
Gripping force increased by 30% by means of oval piston.
High-force variant also available: half the stroke, twice the force
- **Reduced weight:**
Systematic use of lighter and higher performance materials
- **4 sensor slots:**
Proximity sensors no longer project past the bottom of the housing.
Up to four positions can be sensed with the proximity sensors

At a glance

General information

Sturdy and precise kinematic system for maximum torque absorption and long service life.
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 jaws.
The virtually backlash-free plain-bearing guide is realised using ground-in gripper jaws.

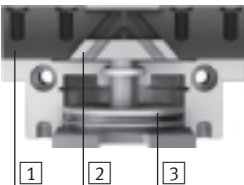
Flexible range of applications

A wide range of uses:

- Can be used as either a double-acting or single-acting gripper
- Compression spring for supplementary or retaining gripping forces
- Suitable for external and internal gripping
- Centring either via centring pins or centring sleeves

The technology in detail

Gripper closed



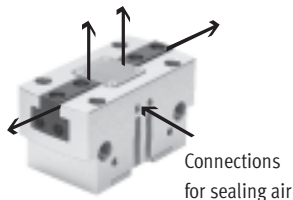
Gripper open



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

Additional connections

For sealing air



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

This prevents, for example, dust particles from entering the gripper jaw guides.

For lubrication



The connections can also be used for relubricating the guide.



Note

Gripper selection
sizing software
→ www.festo.com

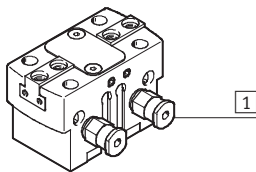
Parallel grippers HGPT-B, heavy-duty

Key features

Wide range of supply ports

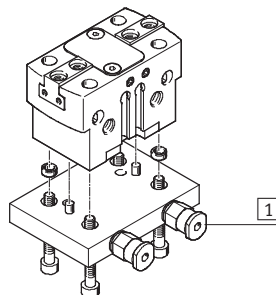
Direct

From the front



Via adapter plate

From underneath

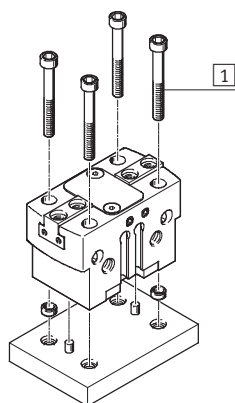


1 Supply ports

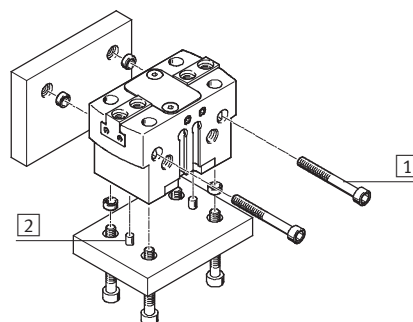
Mounting options

Direct mounting

From above



From underneath or from the side



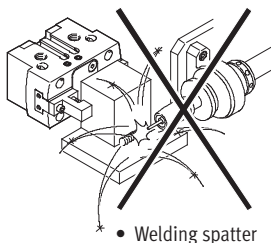
1 Mounting screws

2 Centring pins, centring sleeves

 **Note**

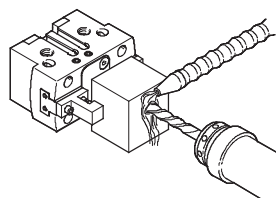
These grippers are not suitable or are of limited suitability for the following application examples:

Not suitable for:

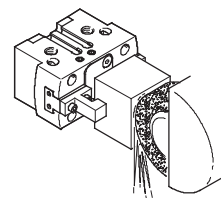


- Welding spatter

Of limited suitability for:



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

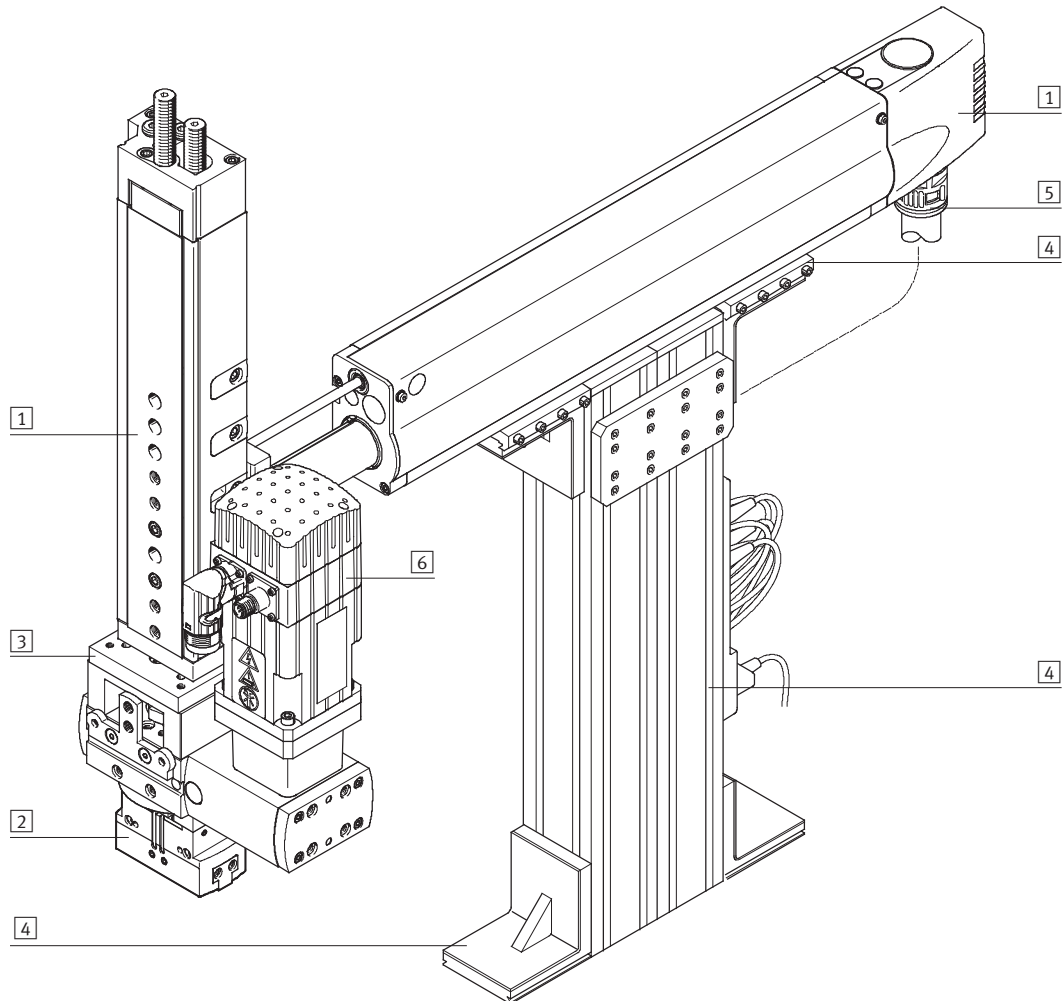


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Key features

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System product for handling and assembly technology



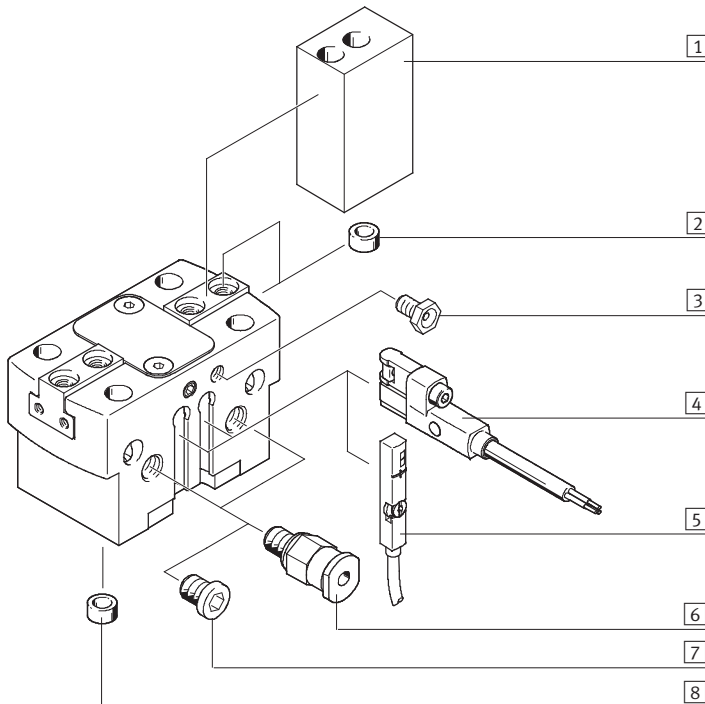
System components and accessories		
	Brief description	→ Page/Internet
1 Drives	Wide range of combinations possible within handling and assembly technology	drive
2 Grippers	Wide range of variations possible within handling and assembly technology	gripper
3 Adapters	For drive/drive and drive/gripper connections	adapter kit
4 Basic components	Profiles and profile connections as well as profile/drive connections	basic component
5 Installation components	For a clear, safe layout of electrical cables and tubing	installation component
6 Motors	Servo and stepper motors, with or without gearing	motor
– Axes	Wide range of combinations possible within handling and assembly technology	axis

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Peripherals overview

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Peripherals overview



Accessories			
Type	Brief description		→ Page/Internet
1 Gripper jaw blank BUB-HGPT	Blank specially matched to the gripper jaws for custom building of gripper fingers		19
2 Centring sleeve ZBH	- For centring gripper jaw blanks/gripper fingers on the gripper jaws - Centring sleeves are included in the scope of delivery of the gripper		20
3 Lubrication nipple	Included in the scope of delivery of the gripper		–
4 Proximity sensor SMT-8G/SMT-10G	- For sensing the piston position - Proximity sensor ends flush with the bottom of the housing		20
5 Position transmitters SMAT-8M	- Continuously senses the piston position. It has an analogue output with an output signal in proportion to the piston position - For size 40 ... 80		21
6 Push-in fitting QS	For connecting compressed air tubing with standard O.D.		quick star
7 Blanking plug B	For sealing supply ports when using the ports underneath		20
8 Centring sleeve ZBH	For centring the gripper when mounting		20
9 –	Drive/gripper connections		adapter kit

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Type codes

		HGPT	–	16	–	A	–	B	–	F	–	
Type												
HGPT	Parallel gripper											
Size												
Position sensing												
A	Via proximity sensor											
Variant												
B	B series											
Force variant												
F	High force											
Gripping force retention												
G1	Opening											
G2	Closing											

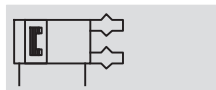
Parallel grippers HGPT-B, heavy-duty

Technical data

Function

Double-acting

HGPT-...



⌀ - Size
16 ... 80 mm

I - Total stroke
3 ... 50 mm

Function – Variants

Single-acting or
with gripping force retention ...

... opening HGPT-...-G1



... closing HGPT-...-G2



General technical data									
Size		16	20	25	35	40	50	63	80
Design		Wedge mechanism							
		Guided motion sequence							
Mode of operation		Double-acting							
Gripper function		Parallel							
Number of gripper jaws		2							
Max. weight force per external gripper finger ¹⁾ [N]		0.4	0.5	1.1	1.8	3.1	6.4	12.6	18.3
Stroke per gripper jaw	HGPT-...-A [mm]	3	4	6	8	10	12	16	25
	HGPT-...-A-F [mm]	1.5	2	3	4	5	6	8	12.5
Pneumatic connection		M3	M3	M5	M5	M5	G $\frac{1}{8}$	G $\frac{1}{8}$	G $\frac{1}{4}$
Pneumatic connection, sealing air		M3	M3	M5	M5	M5	M5	M5	M5
Repetition accuracy ²⁾ [mm]		±0.01	±0.02		±0.025				
Max. interchangeability [mm]		0.2							
Max. operating frequency [Hz]		3				2			
Rotational symmetry [mm]		< Ø 0.2							
Position sensing		Via proximity sensor, position transmitter							
Type of mounting		Via through-hole and locating pin/centring sleeve							
		Via female thread and locating pin/centring sleeve							
Mounting 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

• Note: This product conforms to ISO 1179-1 and to ISO 228-1

Operating and environmental conditions			
Min. operating pressure	HGPT-...-A	[bar]	3
	HGPT-...-A-G	[bar]	4
Max. operating pressure		[bar]	8
Operating pressure, sealing air		[bar]	0 ... 0.5
Operating medium	Filtered compressed air, lubricated or unlubricated		
Ambient temperature ¹⁾		[°C]	+5 ... +60
Corrosion resistance class CRC ²⁾	2		

1) Note operating range of proximity sensors.

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

Components subject to moderate corrosion stress. 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.

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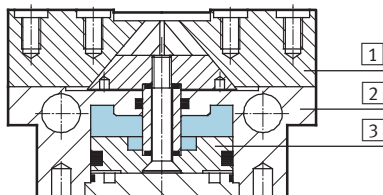
Technical data

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Weight [g]								
Size	16	20	25	35	40	50	63	80
HGPT-...-A	85	135	266	490	821	1,400	2,712	4,745
HGPT-...-A-F	85	135	266	490	821	1,400	2,712	4,745
HGPT-...-A-G	100	155	353	567	1,075	1,832	3,562	6,287

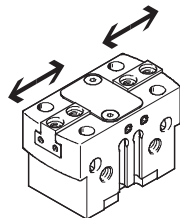
Materials

Sectional view



Parallel gripper	
1 Gripper jaw	Hardened steel
2 Housing	Hard anodised wrought aluminium alloy
3 Piston	Hard anodised aluminium
– Seals	Nitrile rubber
– Note on materials	Free of copper, PTFE and silicone
	RoHS-compliant

Gripping force [N] at 6 bar

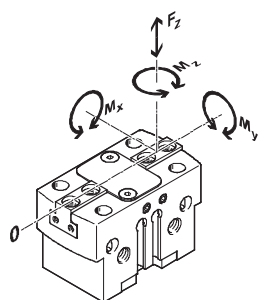


Size		16	20	25	35	40	50	63	80
Gripping force per gripper jaw									
HGPT-...-A	Opening	60	82	133	270	355	570	896	1,613
	Closing	53	77	124	252	331	535	851	1,551
HGPT-...-A-F	Opening	108	172	238	511	723	1,185	1,885	3,275
	Closing	96	161	221	478	674	1,113	1,791	3,150
Total gripping force									
HGPT-...-A	Opening	120	162	266	540	710	1,140	1,792	3,226
	Closing	106	154	248	504	662	1,070	1,702	3,102
HGPT-...-A-F	Opening	216	344	376	1,022	1,446	2,370	3,770	6,550
	Closing	192	322	442	956	1,328	2,226	3,522	6,300

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Technical data

Characteristic load values at the gripper jaws

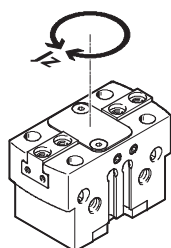


The indicated permissible forces and torques apply to a single gripper jaw. They include the lever arm, additional applied loads due to the workpiece or gripper fingers and acceleration

forces occurring during movement. The zero co-ordinate line (gripper jaw guide) must be taken into consideration for the calculation of torques.

Size		16	20	25	35	40	50	63	80
Max. permissible force F_z	[N]	200	700	1,200	1,800	2,500	3,200	5,000	7,000
Max. permissible torque M_x	[Nm]	10	15	50	80	100	120	160	180
Max. permissible torque M_y	[Nm]	12	15	45	60	90	120	180	220
Max. permissible torque M_z	[Nm]	6	8	35	50	75	100	140	170

Mass moment of inertia [$\text{kgm}^2 \times 10^{-4}$]

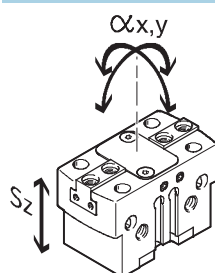


Requirements:

- The reference point is the central axis
- Without external gripper fingers
- In a load-free state

Size		16	20	25	35	40	50	63	80
HGPT-...-A		0.141	0.344	0.983	2.807	7.277	19.488	60.903	150.515
HGPT-...-A-G		0.163	0.445	1.479	3.974	10.990	29.423	93.034	238.336

Gripper jaw backlash



With grippers, backlash occurs between the gripper jaws and the housing due to the plain-bearing guide. The backlash values listed in the table have been calculated based on the traditional accumulative tolerance method.

Size		16	20	25	35	40	50	63	80
Max. gripper jaw backlash S_z	[mm]	0.02							
Max. gripper jaw angular backlash $\alpha_{x,y}$	[°]	0.1							

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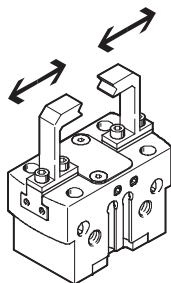
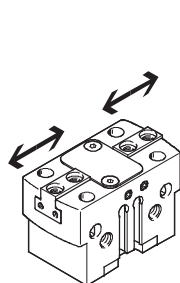
Technical data

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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 at an operating pressure of 6 bar with horizontally mounted gripper without additional

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

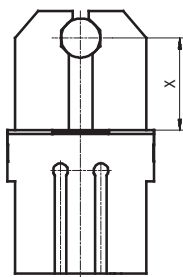
Size			16	20	25	35	40	50	63	80
Without external gripper fingers										
Standard	HGPT-...-A	Opening	9	22	26	33	56	80	150	214
		Closing	11	30	32	37	60	85	156	213
	HGPT-...-A-G1	Opening	13	13	24	31	67	70	146	182
		Closing	31	25	48	27	135	153	328	353
	HGPT-...-A-G2	Opening	22	35	40	50	122	151	294	379
		Closing	15	18	28	15	71	77	185	176
High force	HGPT-...-A-F	Opening	8	28	25	33	60	83	143	212
		Closing	10	31	32	36	64	82	152	211
	HGPT-...-A-F-G1	Opening	19	13	24	31	71	70	145	180
		Closing	30	25	45	28	143	143	315	340
	HGPT-...-A-F-G2	Opening	33	38	36	57	120	137	308	362
		Closing	17	14	28	10	72	80	154	178
With external gripper fingers (as a function of weight force)										
HGPT-...	0.5 N	10	–	–	–	–	–	–	–	–
	1 N	15	30	–	–	–	–	–	–	–
	2 N	21	42	35	–	–	–	–	–	–
	3 N	–	52	42	42	–	–	–	–	–
	4 N	–	–	49	49	63	–	–	–	–
	5 N	–	–	–	55	71	–	–	–	–
	6 N	–	–	–	–	78	–	–	–	–
	8 N	–	–	–	–	90	90	–	–	–
	10 N	–	–	–	–	–	95	–	–	–
	12 N	–	–	–	–	–	100	–	–	–
	15 N	–	–	–	–	–	–	164	–	–
	18 N	–	–	–	–	–	–	179	–	–
	20 N	–	–	–	–	–	–	189	223	–
	22 N	–	–	–	–	–	–	–	234	–
	24 N	–	–	–	–	–	–	–	244	–

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Technical data

Gripping force F_H per gripper jaw as a function of operating pressure and lever arm x

The gripping forces as a function of operating pressure and lever arm can be determined from the following graphs.



— 3 bar
- - - 6 bar
- · - 8 bar

 Note

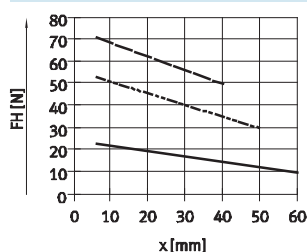
Gripper selection
sizing software

→ www.festo.com

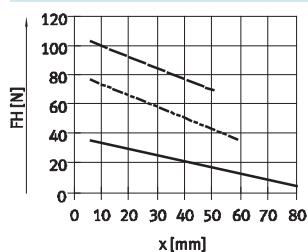
External gripping (closing)

Standard

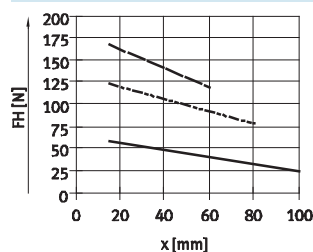
HGPT-16-A



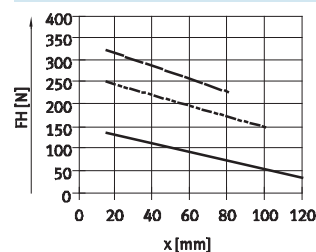
HGPT-20-A



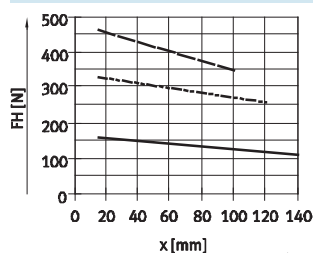
HGPT-25-A



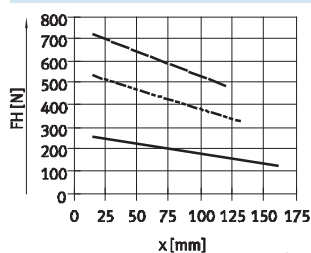
HGPT-35-A



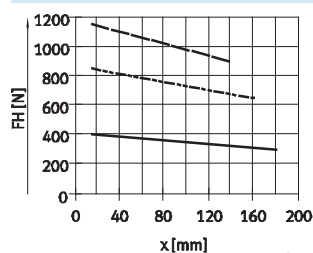
HGPT-40-A



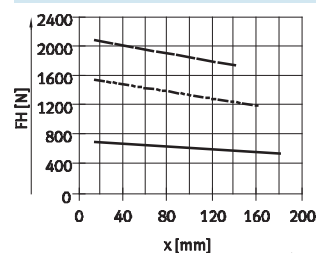
HGPT-50-A



HGPT-63-A

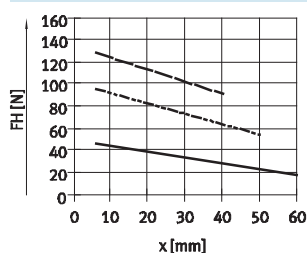


HGPT-80-A

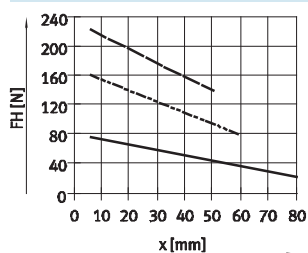


High force

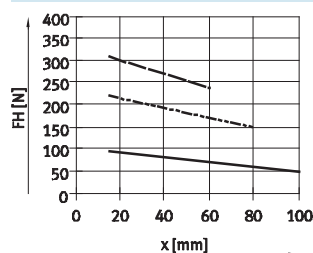
HGPT-16-A-F



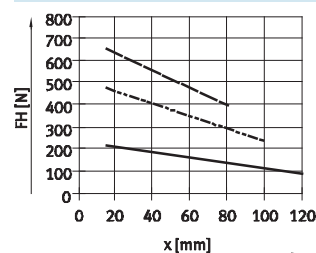
HGPT-20-A-F



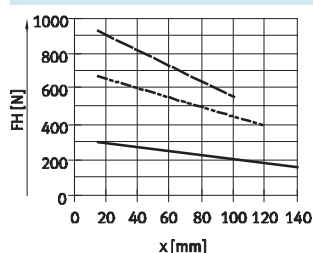
HGPT-25-A-F



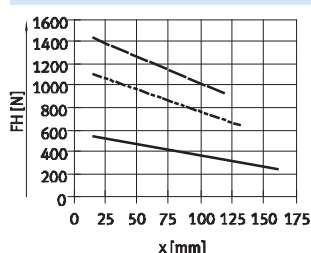
HGPT-35-A-F



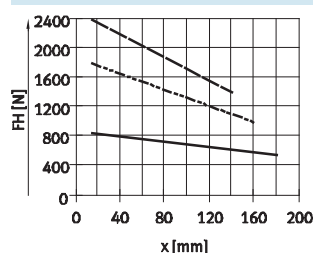
HGPT-40-A-F



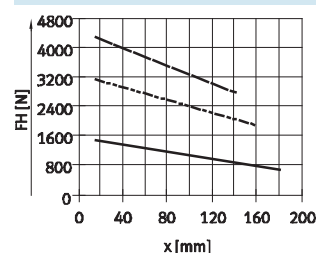
HGPT-50-A-F



HGPT-63-A-F



HGPT-80-A-F



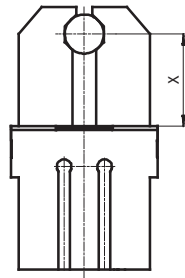
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Gripping force F_H per gripper jaw as a function of operating pressure and lever arm x

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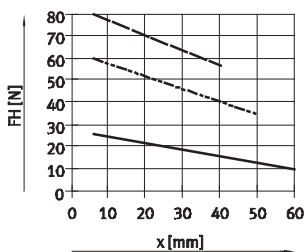
— 3 bar
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 **Note**
Gripper selection
sizing software
→ www.festo.com

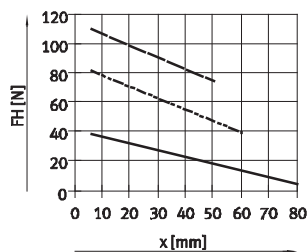
Internal gripping (opening)

Standard

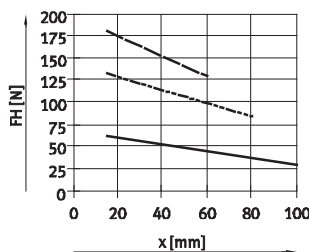
HGPT-16-A



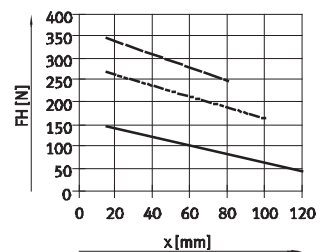
HGPT-20-A



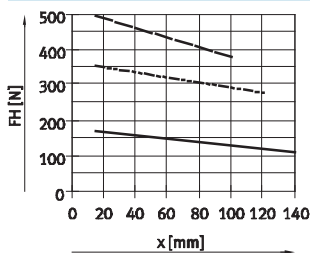
HGPT-25-A



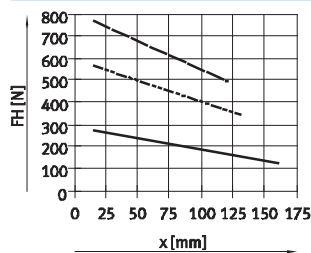
HGPT-35-A



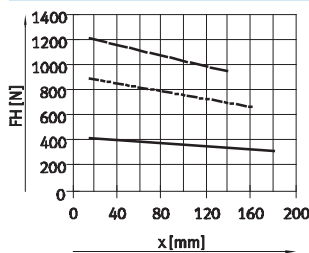
HGPT-40-A



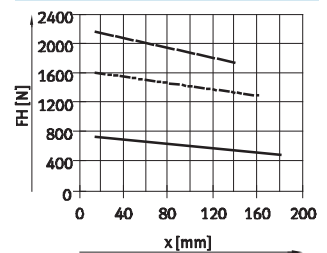
HGPT-50-A



HGPT-63-A

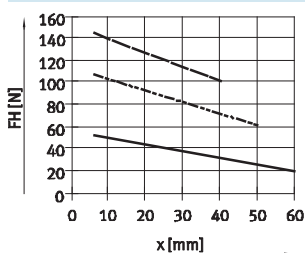


HGPT-80-A

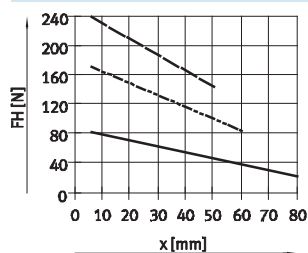


High force

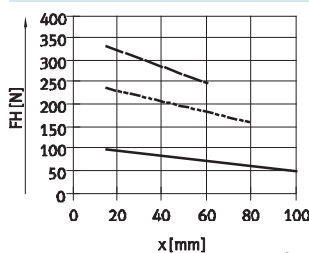
HGPT-16-A-F



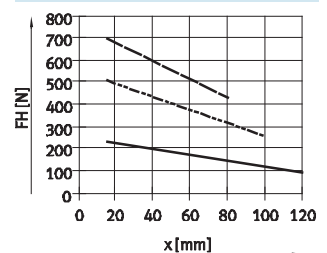
HGPT-20-A-F



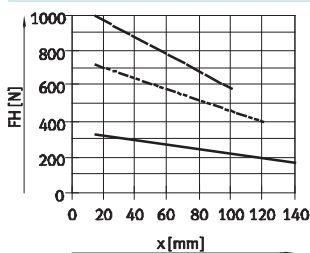
HGPT-25-A-F



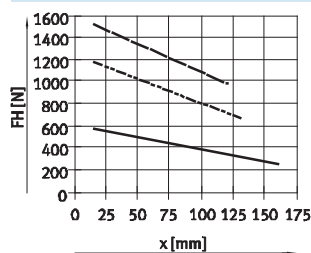
HGPT-35-A-F



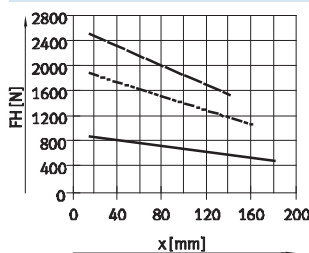
HGPT-40-A-F



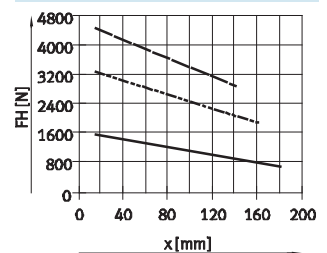
HGPT-50-A-F



HGPT-63-A-F



HGPT-80-A-F



Parallel grippers HGPT-B, heavy-duty

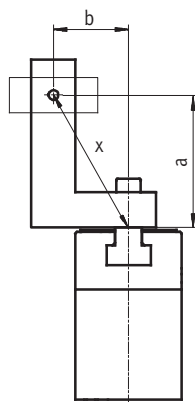
Technical data

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

The following formula must be used to calculate the lever arm x with eccentric gripping:

$$x = \sqrt{a^2 + b^2}$$

The gripping force F_H can then be read from the graphs (→ from 11) using the calculated value x .



Calculation example

Given:

Distance $a = 45$ mm

Distance $b = 40$ mm

To be calculated:

The gripping force at 6 bar,
with an HGPT-25,
used as an external gripper

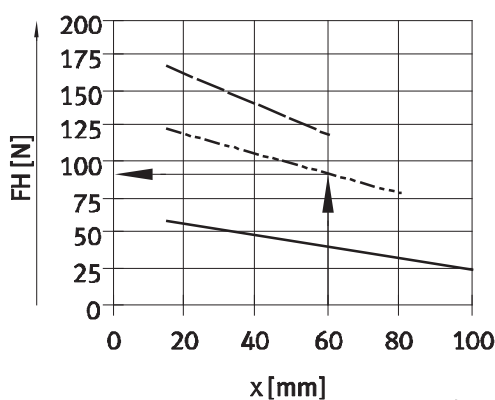
Procedure:

Calculate the lever arm x

$$x = \sqrt{45^2 + 40^2}$$

$$x = 60$$
 mm

The graph (→ 11) gives a value of F_H
= 89 N for the gripping force.



Parallel grippers HGPT-B, heavy-duty

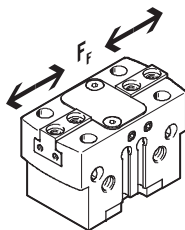
Technical data

FESTO

Spring force F_f as a function of size, gripper jaw stroke l

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

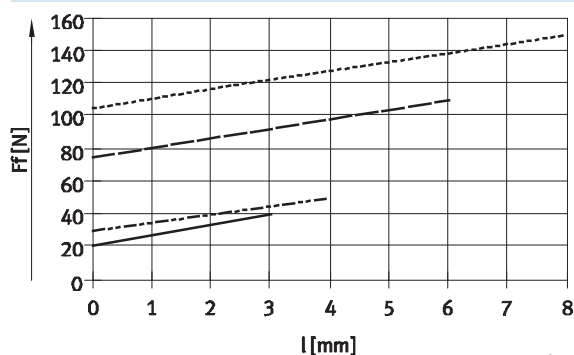
The spring forces F_f as a function of gripper jaw stroke l can be determined from the following graph.



Standard

HGPT-...-A-G

Size 16 ... 35

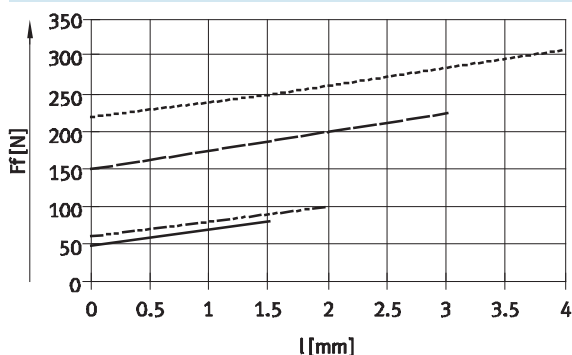


— HGPT-16-A-G
 - - - HGPT-20-A-G
 - · - HGPT-25-A-G
 ····· HGPT-35-A-G

High force

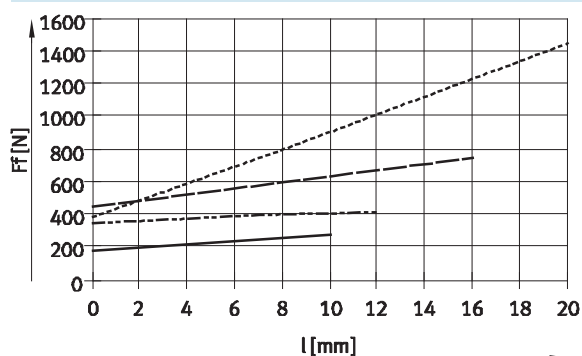
HGPT-...-A-F-G

Size 16 ... 35



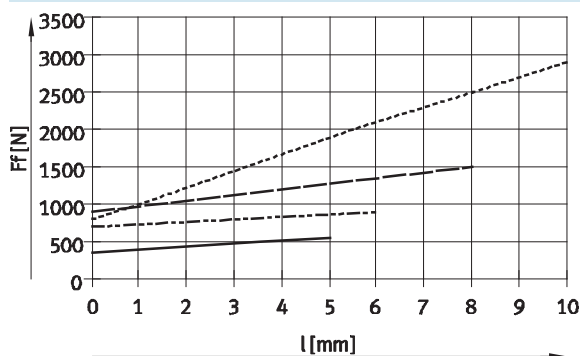
— HGPT-16-A-F-G
 - - - HGPT-20-A-F-G
 - · - HGPT-25-A-F-G
 ····· HGPT-35-A-F-G

Size 40 ... 80



— HGPT-40-A-G
 - - - HGPT-50-A-G
 - · - HGPT-63-A-G
 ····· HGPT-80-A-G

Size 40 ... 80



— HGPT-40-A-F-G
 - - - HGPT-50-A-F-G
 - · - HGPT-63-A-F-G
 ····· HGPT-80-A-F-G

Parallel grippers HGPT-B, heavy-duty

Technical data

Spring force F_F as a function of size, gripper jaw stroke l and lever arm x per gripper finger

The lever arm x must be taken into consideration when determining the actual spring force F_{Ftotal} .
The formulae for calculating the spring force are provided in the table below.

Standard – HGPT-...-A-G

Gripping force retention	Size	$F_{Ftotal} =$	Gripping force retention	Size	$F_{Ftotal} =$
G1	16	$-0.1 * x + 0.7 * F_F$	G2	16	$-0.2 * x + 0.7 * F_F$
	20	$-0.05 * x + 0.9 * F_F$		20	$-0.65 * x + 0.9 * F_F$
	25	$-0.7 * x + 0.7 * F_F$		25	$-0.55 * x + 0.7 * F_F$
	35	$-0.65 * x + 0.7 * F_F$		35	$-0.05 * x + 0.7 * F_F$
	40	$-1.05 * x + 0.8 * F_F$		40	$-1.05 * x + 0.8 * F_F$
	50	$-0.75 * x + 0.8 * F_F$		50	$-1.4 * x + 0.8 * F_F$
	63	$-2 * x + 0.8 * F_F$		63	$-1.2 * x + 0.8 * F_F$
	80	$-1.4 * x + 0.6 * F_F$		80	$-0.6 * x + 0.6 * F_F$

High force – HGPT-...-A-F-G

Gripping force retention	Size	$F_{Ftotal} =$	Gripping force retention	Size	$F_{Ftotal} =$
G1	16	$-0.6 * x + 0.6 * F_F$	G2	16	$-0.4 * x + 0.6 * F_F$
	20	$-0.7 * x + 0.75 * F_F$		20	$-0.95 * x + 0.75 * F_F$
	25	$-0.85 * x + 0.9 * F_F$		25	$-0.5 * x + 0.9 * F_F$
	35	$-0.4 * x + 0.55 * F_F$		35	$-0.4 * x + 0.55 * F_F$
	40	$-1.9 * x + 0.75 * F_F$		40	$-2.3 * x + 0.75 * F_F$
	50	$-2.5 * x + 0.7 * F_F$		50	$-1 * x + 0.7 * F_F$
	63	$-5.5 * x + 0.7 * F_F$		63	$-1 * x + 0.7 * F_F$
	80	$-5.65 * x + 0.8 * F_F$		80	$-0.5 * x + 0.8 * F_F$

Determination of the actual gripping forces F_{Gr} for HGPT-...-G1 and HGPT-...-G2 as a function of the application

The 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_H) and spring force (F_{Ftotal}) must be combined accordingly.

Application

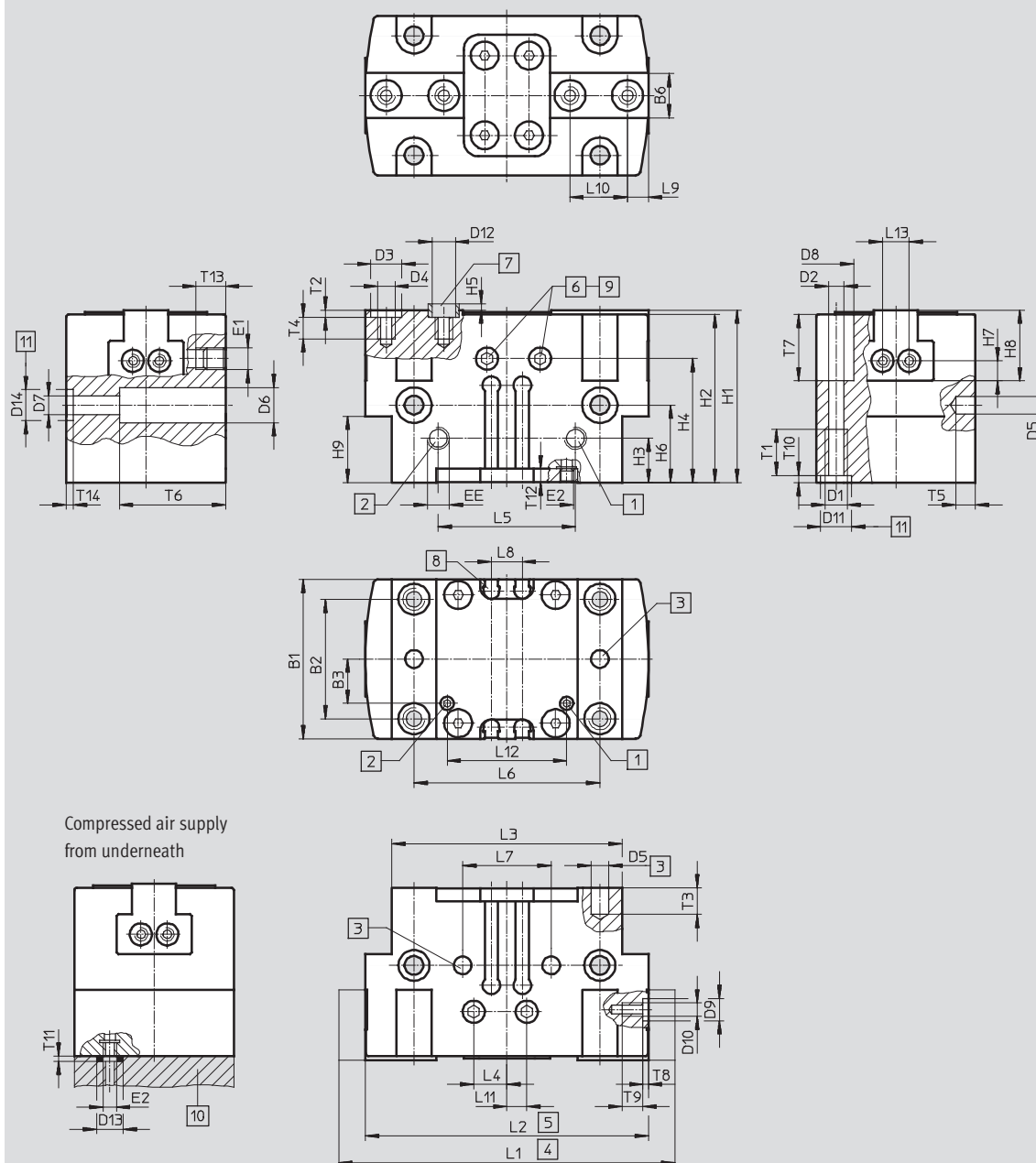
Single-acting	Supplementary gripping force	Gripping force retention
- Gripping with spring force: $F_{Gr} = F_{Ftotal}$ - Gripping with pressure force: $F_{Gr} = F_H - F_{Ftotal}$	Gripping with pressure and spring force: $F_{Gr} = F_H + F_{Ftotal}$	Gripping with spring force: $F_{Gr} = F_{Ftotal}$

Parallel grippers HGPT-B, heavy-duty

Technical data

Dimensions

Download CAD data → www.festo.com



- | | | | | | |
|----------|--|----------|--|-----------|---|
| 1 | Supply port opening, either on the side or underneath (bottom port sealed on delivery) | 3 | Hole for dowel pin (not included in the scope of delivery) | 8 | Slot for proximity sensor |
| 2 | Supply port closing, either on the side or underneath (bottom port sealed on delivery) | 4 | Gripper jaw open | 9 | Lubrication nipple (sealed on delivery) |
| | | 5 | Gripper jaw closed | 10 | O-ring for parallel gripper HGPT-16 ... 40: Ø 3x1.5 |
| | | 6 | Sealing air port (sealed on delivery) | | HGPT-50 ... 80: Ø 5x1.5 |
| | | 7 | Centring sleeves ZBH (4 included in the scope of delivery) | 11 | Hole for centring sleeve ZBH |

Parallel grippers HGPT-B, heavy-duty

Technical data

FESTO

Size	B1	B2 ¹⁾	B3	B6 -0.05 -0.1	D1	D2 Ø	D3 Ø H8/h7	D4	D5 Ø H8	D6 Ø ±0.1	D7 Ø	D8 Ø +0.3	D9 Ø H8	D10	D11 Ø H8	D12 Ø
[mm]	±0.05		±0.1													
16	24	17	4	6	M3	2.6	5	M3	2	4.6	2.6	4.6	-	M2	5	3.2
20	28	22	8.7	6.5	M4	3.3	5	M3	3	6	3.2	6	5	M3	5	3.2
25	36	27	11	10	M5	4.2	7	M4	4	8	4.2	8	5	M3	7	5.3
35	42	32	13	12	M5	4.2	9	M5	4	9.2	5.3	8	7	M5	7	6.4
40	50	38	17	14	M6	5.1	9	M6	5	11	6.4	9	7	M5	9	6.4
50	60	45	20	15.5	M8	6.8	9	M6	6	13.5	8.4	11	7	M5	12	6.4
63	72	56	24.5	20	M8	6.8	12	M10	6	13.5	8.4	11	7	M5	12	10.3
80	100	70	39.5	22	M10	8.5	15	M12	8	16.5	10.2	13.5	9	M6	12	12.4

Size	D13 Ø	D14 Ø H8/h7	EE	E1	E2	H1		H2		H3		H4		H5	H6 ¹⁾	
						±0.05	-G ±0.05	±0.05	-G ±0.05	±0.1	-G ±0.1		-G		-0.3	-G
16	6	-	M5	M3	M3	29	37	28	36	12	12	23.7	31.7	1.2	17.5	25.5
20	6	-	M5	M3	M3	31	38	30	37	10	15	23	30	1.2	14.5	21.5
25	6	7	M5	M5	M3	39	57	38	56	10	20	28	46	1.4	17.5	35.5
35	6	7	M5	M5	M3	49	67	48	66	12	30	36	54	1.9	20	38
40	6	9	M5	M5	M3	55	81	54	80	15	36	41	67	1.9	25	51
50	8	12	G ¹ / ₈	M5	M5	63	93	62	92	15	30	47	77	1.9	30	60
63	8	12	G ¹ / ₈	M5	M5	77	117	76	116	18	26	56	96	2.4	28	68
80	8	12	G ¹ / ₄	M5	M5	91	133	90	132	22	33	65	107	2.9	34	76

Size	H7 ¹⁾	H8	H9		L1		L2	L3	L4	L5	L6 ¹⁾	L7 ¹⁾	L8	L9 ¹⁾	L10 ¹⁾	L11
			±0.1	-G ±0.1	±0.5	-F ±0.5										
16	2.25	8.5	15	23	50	47	44	36	5.5	20	29	20	6	3	8	1
20	3	12	15	22	64	60	56	44	2.5	24	35	24	6	3.25	12	2.5
25	4.5	16	15	33	76	70	64	52	3.5	31	42	20	7	4.75	13	3.5
35	5.5	19	20	38	96	88	80	64	5.5	40	52	40	7	5.5	16	5.5
40	5.5	22	24	50	120	110	100	80	5.5	49	66	50	10	6.5	20	5.5
50	7.5	25.5	26	56	149	137	125	100	5.5	63	82	60	10	8	24	5.5
63	9	32	32	72	192	176	160	125	5.5	74	100	76	10	9.5	32	5.5
80	11	39	34	77	230	210	180	154	5.5	82	130	100	10	12	40	5.5

Size	L12	L13 ¹⁾	T1	T2	T3	T4	T5	T6	T7		T8	T9	T10	T11	T12	T13	T14
									+0.2	-G +0.2							
16	22	6	5.5	1.3	4	5	4	15	14	22	-	3	1.3	1.2	3	5.5	-
20	22.6	6	6.5	1.3	5	5.5	4	19	11	11	1.3	6	1.3	1.2	3	5.5	-
25	29	6	8.5	1.6	6	6.5	4.5	24	15	15	1.3	6	1.6	1.2	3	6.7	1.6
35	39	13	8.5	2.1	6	8.5	4.5	16	19	19	1.6	9	1.6	1.2	3	6.5	1.6
40	47.4	13	10.5	2.1	6	10.5	6	33	20	20	1.6	9	2.1	1.2	4	6.5	2.1
50	61	13	12.5	2.1	8	10.5	6	43	23	23	1.6	9	2.6	1.2	4	6.5	2.6
63	75	13	12.5	2.6	8	15.5	7	55	35	35	1.6	9	2.6	1.2	5	6.5	2.6
80	82	20	15	3.1	10	20	10	70	44	44	2.1	10	2.6	1.2	5.5	5	2.6

1) Tolerance for centring hole ±0.02 mm

Tolerance for thread ±0.1 mm

· || - Note: This product conforms to ISO 1179-1 and to ISO 228-1

Parallel grippers HGPT-B, heavy-duty

Technical data

FESTO

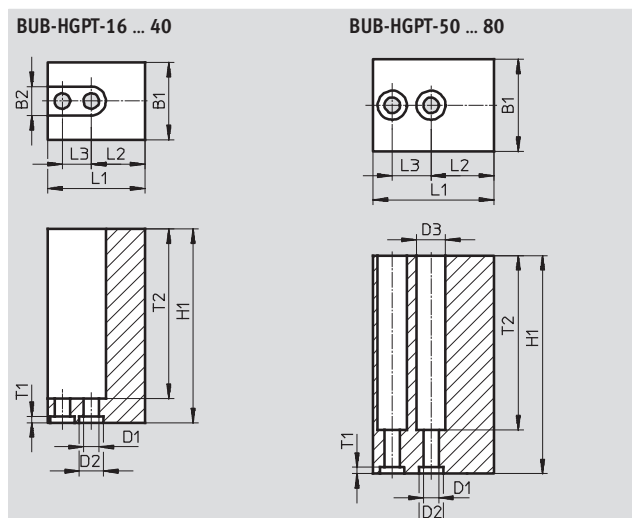
Ordering data						
Size [mm]	Double-acting without compression spring Part No. Type		Single-acting or with gripping force retention			
			Opening Part No. Type		Closing Part No. Type	
Standard						
16	560192	HGPT-16-A-B	560193	HGPT-16-A-B-G1	560194	HGPT-16-A-B-G2
20	560198	HGPT-20-A-B	560199	HGPT-20-A-B-G1	560200	HGPT-20-A-B-G2
25	560204	HGPT-25-A-B	560205	HGPT-25-A-B-G1	560206	HGPT-25-A-B-G2
35	560210	HGPT-35-A-B	560211	HGPT-35-A-B-G1	560212	HGPT-35-A-B-G2
40	560216	HGPT-40-A-B	560217	HGPT-40-A-B-G1	560218	HGPT-40-A-B-G2
50	560222	HGPT-50-A-B	560223	HGPT-50-A-B-G1	560224	HGPT-50-A-B-G2
63	560228	HGPT-63-A-B	560229	HGPT-63-A-B-G1	560230	HGPT-63-A-B-G2
80	560234	HGPT-80-A-B	560235	HGPT-80-A-B-G1	560236	HGPT-80-A-B-G2
High force						
16	560195	HGPT-16-A-B-F	560196	HGPT-16-A-B-F-G1	560197	HGPT-16-A-B-F-G2
20	560201	HGPT-20-A-B-F	560202	HGPT-20-A-B-F-G1	560203	HGPT-20-A-B-F-G2
25	560207	HGPT-25-A-B-F	560208	HGPT-25-A-B-F-G1	560209	HGPT-25-A-B-F-G2
35	560213	HGPT-35-A-B-F	560214	HGPT-35-A-B-F-G1	560215	HGPT-35-A-B-F-G2
40	560219	HGPT-40-A-B-F	560220	HGPT-40-A-B-F-G1	560221	HGPT-40-A-B-F-G2
50	560225	HGPT-50-A-B-F	560226	HGPT-50-A-B-F-G1	560227	HGPT-50-A-B-F-G2
63	560231	HGPT-63-A-B-F	560232	HGPT-63-A-B-F-G1	560233	HGPT-63-A-B-F-G2
80	560237	HGPT-80-A-B-F	560238	HGPT-80-A-B-F-G1	560239	HGPT-80-A-B-F-G2

Parallel grippers HGPT-B, heavy-duty

Accessories

Gripper jaw blank BUB-HGPT
(scope of delivery: 2 pieces)

Materials:
Aluminium



Dimensions and ordering data							
For size	B1	B2	D1	D2	D3	H1	L1
[mm]	±0.05	H13	Ø H13	Ø H8	Ø H13	±0.05	±0.05
16	16	6	3.2	5	–	40	21
20	19	6	3.2	5	–	45	27
25	24	8	4.3	7	–	60	31
35	28	10	5.3	9	–	70	39
40	34	11	6.4	9	–	75	49
50	40	–	6.4	9	11	100	61
63	50	–	10.3	12	17	120	79
80	58	–	12.4	15	20	140	88

For size	L2 ¹⁾	L3 ¹⁾	T1	T2	Weight per blank [g]	Part No.	Type
[mm]			+0.1				
16	10	8	1.3	35	29	560244	BUB-HGPT-16-B
20	11.75	12	1.3	36	53	560245	BUB-HGPT-20-B
25	13.25	13	1.6	51	98	560246	BUB-HGPT-25-B
35	17.5	16	2.1	61	161	560247	BUB-HGPT-35-B
40	22.5	20	2.1	66.5	280	560248	BUB-HGPT-40-B
50	29	24	2.1	91	622	560249	BUB-HGPT-50-B
63	37.5	32	2.6	110	1,213	560250	BUB-HGPT-63-B
80	36	40	3.1	125	1,738	560251	BUB-HGPT-80-B

1) Tolerance for centring hole ±0.02 mm
Tolerance for thread ±0.1 mm

Parallel grippers HGPT-B, heavy-duty

Accessories

FESTO

Ordering data						
	For size [mm]	Description	Weight [g]	Part No.	Type	PU ¹⁾
Centring sleeve ZBH Technical data → Internet: zbh						
	16, 20	For centring gripper jaw blanks/gripper fingers on the gripper jaws	1	189652	ZBH-5	10
	25		1	186717	ZBH-7	
	35, 40, 50		1	150927	ZBH-9	
	63		1	189653	ZBH-12	
	80		3	191409	ZBH-15	
	20, 25	For lateral centring of gripper fingers on the gripper jaws	1	189652	ZBH-5	
	35, 40, 50, 63		1	186717	ZBH-7	
	80		1	150927	ZBH-9	
	16, 20	For centring the gripper when mounting	1	189652	ZBH-5	
	25, 35		1	186717	ZBH-7	
	40		1	150927	ZBH-9	
	50, 63, 80		1	189653	ZBH-12	
Connecting sleeve ZBV Technical data → Internet: zbv						
	–	For compensating different centring diameters	1	571033	ZBV-6-5	1
			1	571034	ZBV-8-7	
			1	560253	ZBV-9-8	
			2	571035	ZBV-12-10	
			2	560255	ZBV-14-12	
Blanking plug B Technical data → Internet: blanking plug						
	16, 20	For sealing the supply ports	1	30979	B-M3-S9	10
	25, 35, 40		1	174308	B-M5-B	
	50, 63		5	3568	B-1/8	
	80		15	3569	B-1/4	

1) Packaging unit

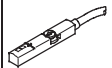
Proximity sensor for size 16 ... 35						
Ordering data – Proximity sensors for C-slot, magneto-resistive					Technical data → Internet: smt	
	Type of mounting	Switching output	Electrical connection, connection direction	Cable length [m]	Part No.	Type
N/O contact						
	Insertable in slot lengthwise	PNP	Cable, 3-wire, angled	2.5	547862	SMT-10G-24V-E-2,5Q-OE
			Plug M8x1, 3-pin, angled	0.3	547863	SMT-10G-24V-E-0,3Q-M8D

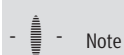
Proximity sensor for size 40 ... 80						
Ordering data – Proximity sensors for T-slot, magneto-resistive					Technical data → Internet: smt	
	Type of mounting	Switching output	Electrical connection, connection direction	Cable length [m]	Part No.	Type
N/O contact						
	Insertable in slot lengthwise	PNP	Cable, 3-wire, angled	2.5	547859	SMT-8G-24V-E-2,5Q-OE
			Plug M8x1, 3-pin, angled	0.3	547860	SMT-8G-24V-E-0,3Q-M8D

Parallel grippers HGPT-B, heavy-duty

Accessories

Proximity sensor for size 40 ... 80

Ordering data – Position transmitters for T-slot						Technical data → Internet: smat	
	Type of mounting	Analogue output [V]	Electrical connection, connection direction	Cable length [m]	Part No.	Type	
N/O contact							
	Insertable in slot from above	0 ... 10	Plug M8x1, 3-pin, angled	0.3	553744	SMAT-8M-U-E-0,3-M8D	



Note

Mode of operation:

The position transmitter continuously senses the piston position. It has an analogue output with an output signal in proportion to the piston position.

Measuring range:

The entire stroke can be measured with sizes 40 and 50.

A stroke of 13 mm (with the high-force variant 6.5 mm) can be measured with sizes 63 and 80.

Two position transmitters are required for sensing longer strokes.

Projection:

The position transmitter projects past the housing at the back with sizes 40 and 50.

Ordering data – Connecting cables					Technical data → Internet: nebu	
	Electrical connection, left	Electrical connection, right	Cable length [m]	Part No.	Type	
	Straight socket, M8x1, 3-pin	Cable, open end, 3-wire	2.5	541333	NEBU-M8G3-K-2.5-LE3	
			5	541334	NEBU-M8G3-K-5-LE3	
	Angled socket, M8x1, 3-pin	Cable, open end, 3-wire	2.5	541338	NEBU-M8W3-K-2.5-LE3	
			5	541341	NEBU-M8W3-K-5-LE3	

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