

## INDIVIDUAL SINGLE PIECE WITH OPTIMIZED DESIGN

With the help of a 3D model of the workpiece, the synthetic RRMG gripper is individually and perfectly adapted to the respective workpiece. Special jaws with free-form surfaces allow the secure gripping and clamping of every sensitive workpiece with complex geometries.

The particularly robust and resistant design of the new synthetic RRMG gripper makes a 30 % higher clamping force possible.

**RRMG**

**RÖHM  
Rapid  
Manufacturing  
Gripper**

**- 2**

**Sizes  
2-3**



Video Synthetic gripper



# SYNTHETIC GRIPPER

Whether round material, prismatic workpieces or free-form surfaces, the synthetic RRMG gripper from RÖHM is individually adapted to the workpiece and produced. Only a 3D model of the workpiece is required, and RÖHM will produce the individual synthetic RRMG gripper based on that. This customer-specific solution is therefore perfect for gripping and clamping sensitive workpieces with complex geometries.

## ADVANTAGES AT A GLANCE

- ⊕ Component-specific individual piece for sensitive workpieces with complex geometries
- ⊕ FEM-optimized design with 30 % higher clamping force for a greater range of use
- ⊕ Up to 16 million gripper cycles without required maintenance or signs of wear

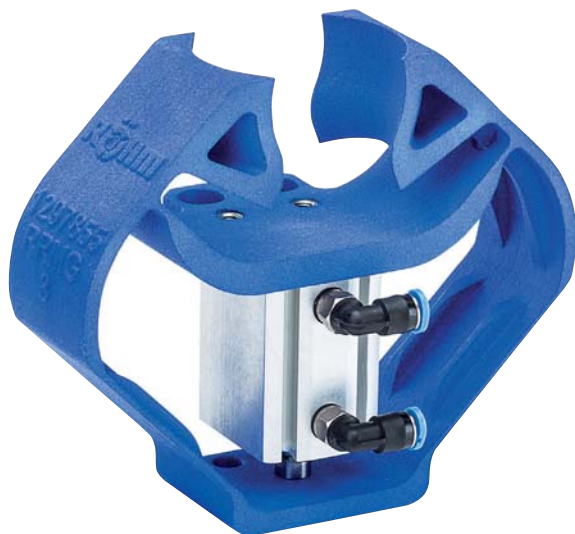


Synthetic gripper



Synthetic gripper RRMG

# RRMG



### APPLICATION

Synthetic gripper for light, sensitive workpieces with complex geometries.

### TYPE

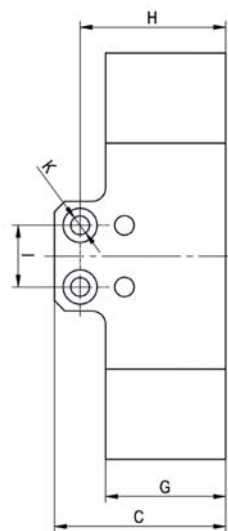
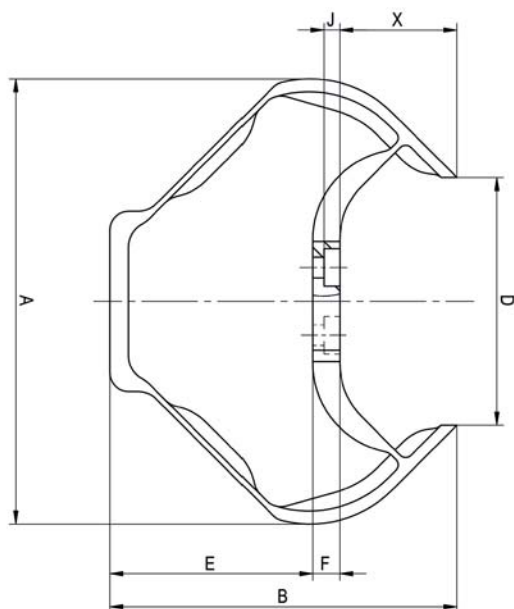
Synthetic gripper RRMG - customized and perfectly adapted jaws on the form of the workpiece.

### CUSTOMER BENEFITS

- ③ Part specific unique gripper for sensitive workpieces with complex geometries
- ③ FEM optimized structure with 30 % higher clamping force
- ③ Customized and perfectly adapted to the workpiece using the 3D-model
- ③ Application specific design of the flange for maximum flexibility
- ③ Up to 16 million gripping cycles without maintenance or wear and tear

### TECHNICAL FEATURES

- Synthetically built by selective laser sintering for short delivery times
- Especially robust and durable material polyamid with FEM-optimized structure
- Optional position monitoring by installable standard sensors
- Position monitoring by magnetic sensors possible
- Further designs and sizes on request (e.g. double gripper, internal gripper, etc.)



Synthetic gripper RRMG

### Synthetic gripper RRMG

	Size	Gripping force* N	Stroke* mm	Clamping point X	A mm	B mm	C mm	D mm	E mm	F mm	G mm	H mm	I mm	J mm	K Ø mm
RRMG	2	80	2,6	23,2	92	75,8	37	50	47	5,5	25	31	13	3,4	4,5
RRMG	3	152	4,3	31,2	118,6	92,4	50	66	54	7,2	35	42,5	18	4,2	5,5

\* At clamping point X



Synthetic gripper RRMG-MRK

# RRMG-MRK



## APPLICATION

Additive manufactured gripper with HRC-function for customer-specific and complex workpiece geometries. Rounding of edges and corners as well as the robust and durable design ensure protection of the worker from injury in accordance with the latest ISO 10218 and ISO/TS15066 standards by additional flexibility.

## TYPE

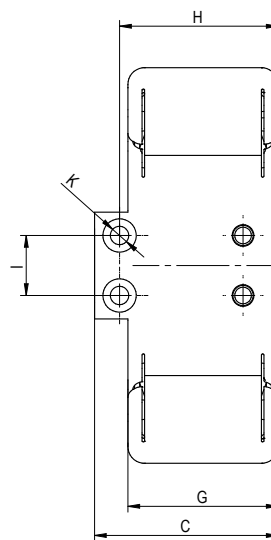
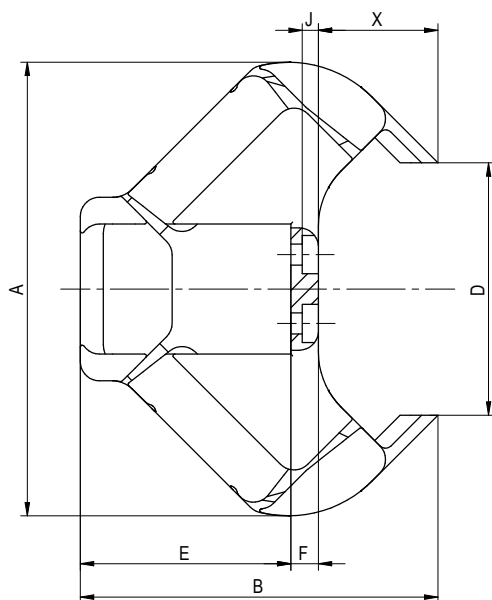
Additive manufactured gripper with customized and perfectly adapted jaws on the form of the workpiece.

## CUSTOMER BENEFITS

- ⊕ Accurate gripping of all conceivable workpiece shapes through form fitting adaption of the gripper fingers by additive manufacturing
- ⊕ Up to 120 N of gripping force, depending on the contour and surface of the workpiece
- ⊕ Maintenance-free for up to 10 million gripping cycles – with up to 100 gripping cycles per minute
- ⊕ Solid, durable design with extremely low net weight (300 g)

## TECHNICAL FEATURES

- The clamping position is comfortably reached by integrated sensors
- Gripping position can be changed by 90° with the flange
- Synthetically built by selective laser sintering for short delivery times
- Especially robust and durable material polyamid with FEM-optimized structure
- Optional position monitoring by installable standard sensors
- Position monitoring by magnetic sensors possible
- Further designs and sizes on request (e.g. double gripper, internal gripper, etc.)



### Synthetic gripper RRMG-MRK

	Gripping force* N	Stroke* mm	Clamping point X	A mm	B mm	C mm	D mm	E mm	F mm	G mm	H mm	I mm	J mm	K Ø mm
RRMG-MRK	120**	4,3	31,2	118,6	93,4	55	66	55	7,2	45	47,5	18	4,2	5,5

\* At clamping point X

\*\* Max. clamping force must be controlled by air pressure

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