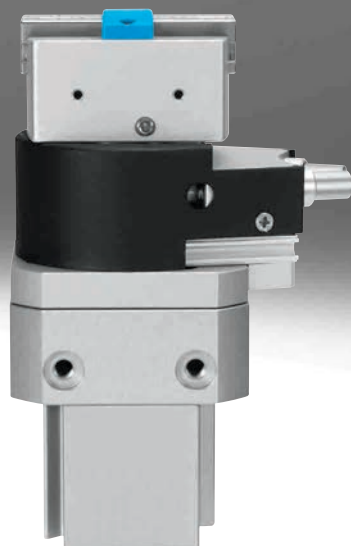


## Swivel/gripper units HGDS-B

**FESTO**

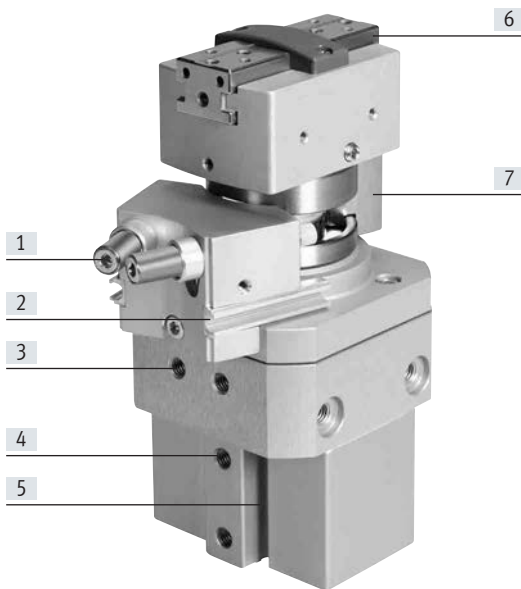


## Key features

### At a glance

- Combination of parallel gripper with T-slot guide and swivel module on the basis of swivel module DSM
- Infinitely adjustable swivel angle (max. 210°)
- Supply ports and position sensing outside the swivel range
- High performance (torque, mass moment of inertia)
- All connections accessible from one side
- Compact design and low weight

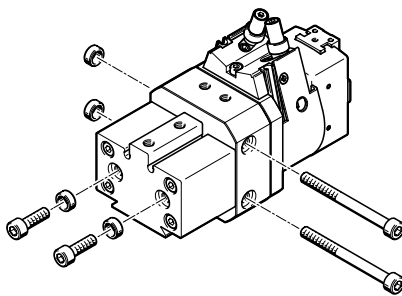
### The technology in detail



- [1] Three types of cushioning for swivel motion:
  - Elastic cushioning components (P)
  - Adjustable, elastic cushioning components with metal fixed stop (P1)
  - Shock absorbers with metal fixed stop (YSRT)
- [2] Slot for proximity switch SME-/SMT-10 for sensing the swivel position
- [3] Supply port for swivelling function
- [4] Supply port for gripping function
- [5] Slot for proximity switch SME-/SMT-10 for sensing the gripping position
- [6] Gripper jaw with T-slot guide
- [7] Adjustable stop cams for adjusting the swivel motion

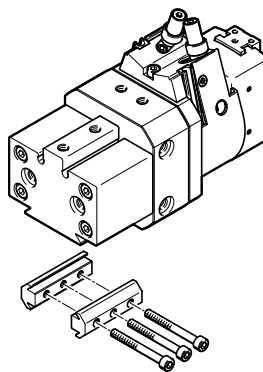
### Mounting options

#### Direct mounting



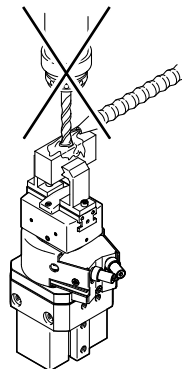
The swivel/gripper unit can be mounted on four sides.

#### Dovetail connection

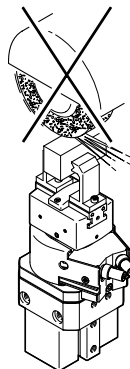


#### Note

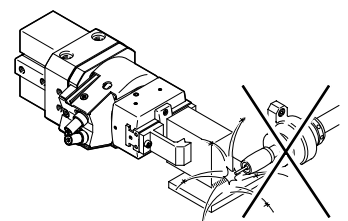
Swivel/gripper units are not suitable for the following or similar applications:



- Machining
- Aggressive media



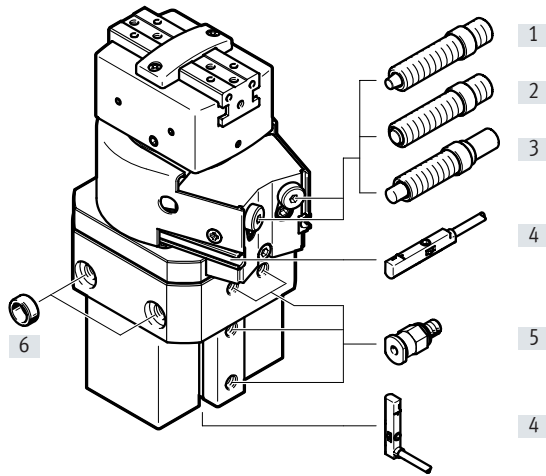
- Grinding dust



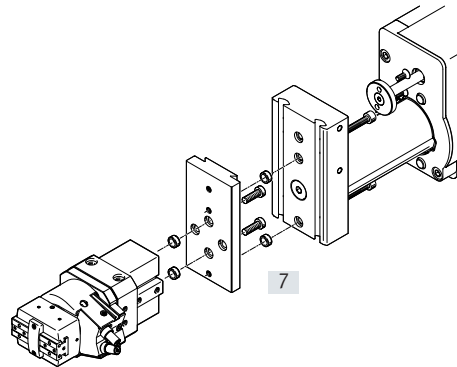
- Welding spatter

## Peripherals overview and type codes

## Peripherals overview



## System product for handling and assembly technology



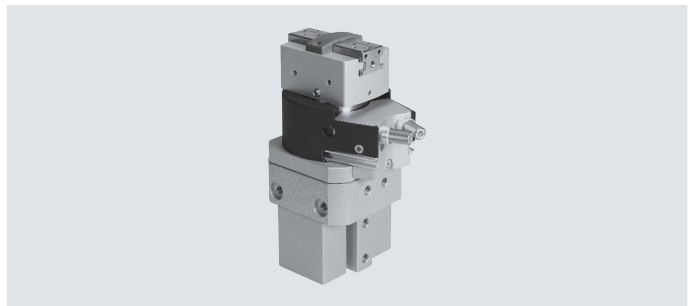
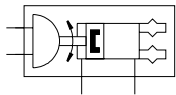
Accessories		
Type	Description	→ Page/Internet
[1] Cushioning P	Elastic cushioning components at both ends	16
[2] Cushioning P1	Elastic cushioning components at both ends, adjustable, with metal fixed stop	16
[3] Cushioning YSRT	Shock absorber at both ends, self-adjusting, with metal fixed stop	16
[4] Proximity switches SME/SMT-10	For sensing the gripping and swivelling position	16
[5] Push-in fitting QS	For connecting tubing with standard O.D.	qs
[6] Centring sleeve ZBH	For centring the gripper when mounting (2 included in the scope of delivery)	16
[7] Adapter kit HMSV	Drive/gripper connections	15

## Type codes

001	Series
HGDS	Swivel/gripper unit
002	Gripper version
PP	Parallel gripper
003	Size
12	12
16	16
20	20

004	Cushioning
P	Elastic cushioning rings/plates on both sides
P1	Elastomer cushioning, adjustable on both sides, with fixed stop
YSRT	Shock absorber, self-adjusting, linear, at both ends
005	Position sensing
A	For proximity sensor
006	Generation
B	Series B

Data sheet



- $\varnothing$  - Size  
12, 16, 20 mm
- $l$  - Stroke  
5, 9, 14 mm

General technical data			
Size	12	16	20
Design	Parallel gripper		
	Semi-rotary drive		
	Gripper module		
Mode of operation	Double-acting		
Pneumatic connection	M5		
Type of mounting	Via female thread and centring sleeve		
	Via through-hole and centring sleeve		
	Via dovetail slot		
Cushioning			
P cushioning	Elastic cushioning components at both ends		
P1 cushioning	Elastic cushioning components at both ends, adjustable		
YSRT cushioning	Shock absorber at both ends, self-adjusting		
Mounting position	Any		
Relubrication intervals of guide	10 million switching cycles		
Product weight [g]	505	730	1260
Technical data – Swivelling	→ Page 5		
Technical data Gripping	→ Page 8		

Operating and environmental conditions		
Operating pressure [bar]	3 ... 8	
Operating medium	Compressed air to ISO 8573-1:2010 [7:4:4]	
Note on the operating/pilot medium	Lubricated operation possible (in which case lubricated operation will always be required)	
Ambient temperature <sup>1)</sup> [°C]	+5 ... +60	
Corrosion resistance class CRC <sup>2)</sup>	2	

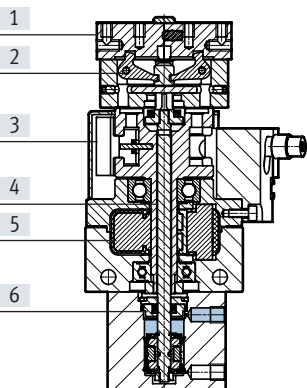
1) Note operating range of proximity sensors

2) Corrosion resistance class CRC 2 to Festo standard FN 940070

Moderate corrosion stress. Indoor applications in which condensation can occur. External visible parts with primarily decorative surface requirements which are in direct contact with a normal industrial environment.

Materials

Sectional view



Swivel/gripper unit		
[1]	Gripper jaw	Stainless steel
[2]	Lever	Hardened steel
[3]	Stop	Stainless steel
[4]	Piston rod	Stainless steel
[5]	Housing	Wrought aluminium alloy
[6]	Piston	NBR, polyurethane
-	Rubber buffer	NBR

## Data sheet

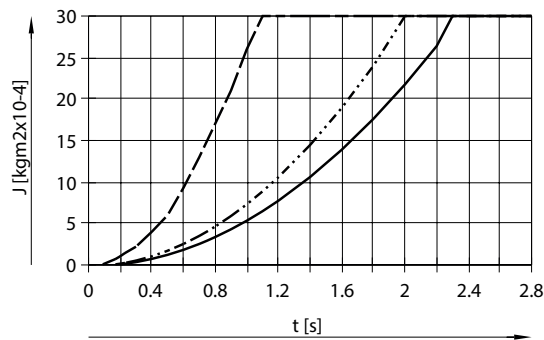
## Technical data – Swivelling

Size		12	16	20
Swivel angle	[°]	0 ... 210		
Theoretical torque <sup>1)</sup>	[Nm]	0.85	1.25	2.5
Repetition accuracy <sup>1)</sup>				
P cushioning	[°]	< 0.2		
P1 cushioning	[°]	< 0.02		
YSRT cushioning	[°]	< 0.02		
Max. swivel frequency <sup>1)</sup>				
P cushioning	[Hz]	2		
P1 cushioning	[Hz]	2		
YSRT cushioning	[Hz]	1.5		
Position sensing		Via proximity switch		

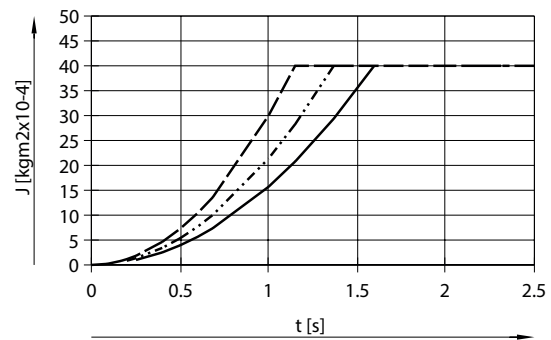
1) At an operating pressure of 6 bar

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

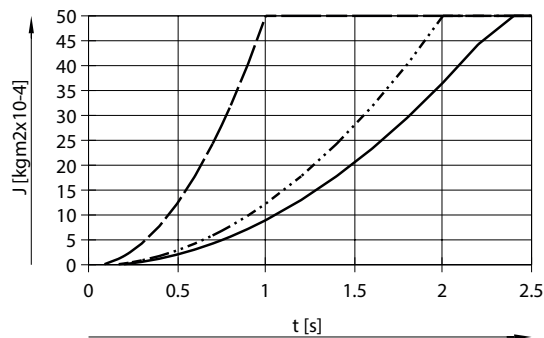
HGDS-PP-12-P-A-B



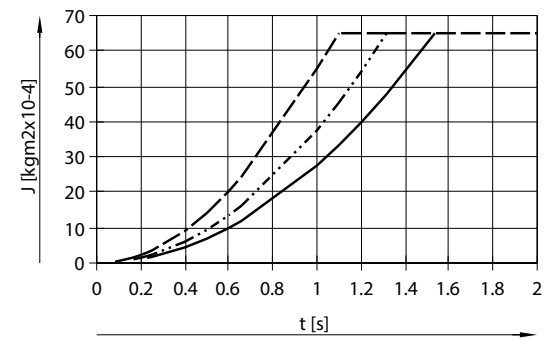
HGDS-PP-12-P1-A-B



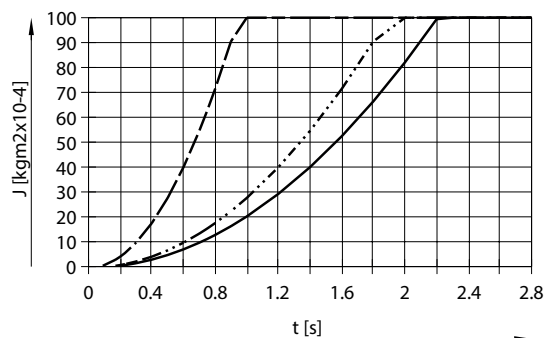
HGDS-PP-16-P-A-B



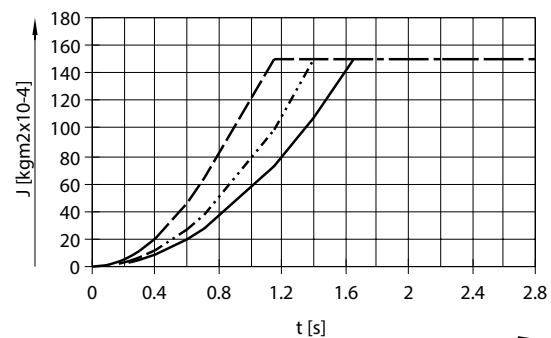
HGDS-PP-16-P1-A-B



HGDS-PP-20-P-A-B



HGDS-PP-20-P1-A-B

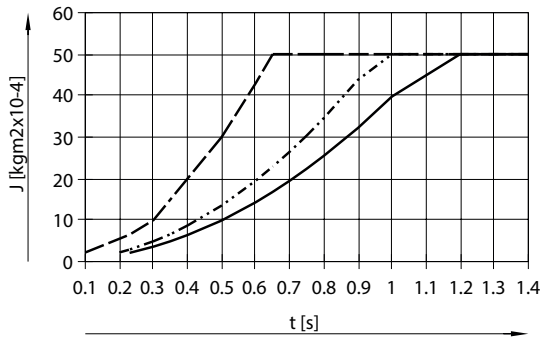


— Swivel angle 210°  
 ····· Swivel angle 180°  
 - - - Swivel angle 90°

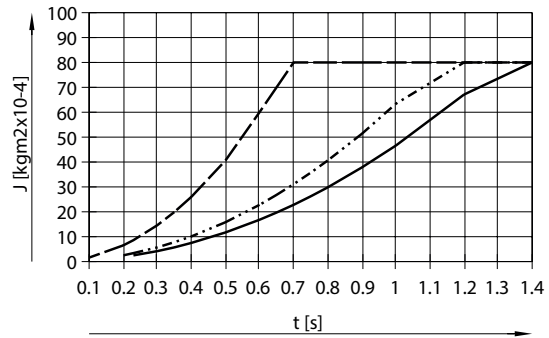
Data sheet

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

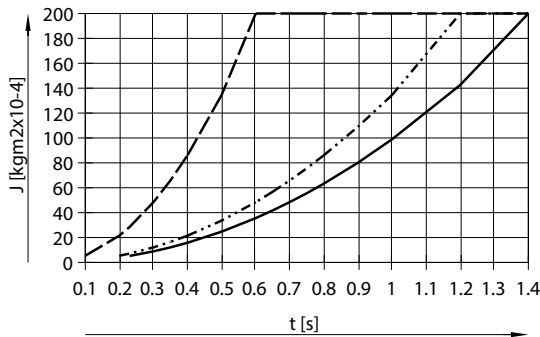
HGDS-PP-12-YSRT-A-B



HGDS-PP-16-YSRT-A-B



HGDS-PP-20-YSRT-A-B



- Swivel angle 210°
- Swivel angle 180°
- - - Swivel angle 90°

Dependency between operating pressure and swivel time

Reducing the operating pressure reduces the gripping force. To ensure that the grippers jaws do not open during swivelling, the swivel time must be increased by 15% per bar of operating pressure (with the same mass moment of inertia).

Swivel time at 6 bar = 0.5 s, see graph opposite

Swivel time at 4 bar:  
 $t = 0.5 + 2 \times 15\% = 0.65 \text{ s}$   
 Cushioning time of the shock absorber = 0.1 s

Example:

Assuming:

HGDS-PP-16-YSRT-A-B

Operating pressure 6 bar

Swivel angle 90°

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

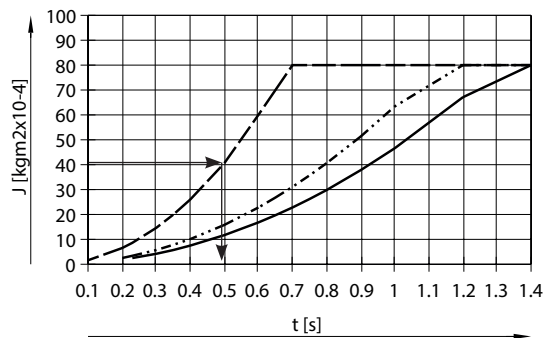
This yields a total swivel time of

$t_{\text{total}} = 0.65 \text{ s} + 0.1 \text{ s} = 0.75 \text{ s}$

To be calculated:

Swivel time at an operating pressure of

4 bar



## Data sheet

### Precision adjustment of the swivel angle

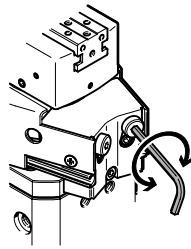
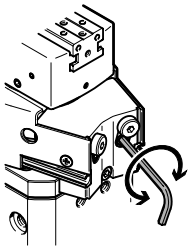
The swivel angle can be roughly adjusted by moving the cam stops → page 2.

The procedure for precision adjustment is the same for all cushioning variants (P, P1 and YSRT).

The swivel angle can be precisely adjusted by unscrewing or screwing in the cushioning component.

Swivelling to a metal stop enables high repetition accuracy.

- 1) Loosen the locking screw underneath the cushioning element.
- 2) Adjust the cushioning element as required. Note the adjustment range.



Size		12	16	20
<b>Precision adjustment range</b>				
P cushioning	[°]	-6		
P1 cushioning	[°]	-6		
YSRT cushioning	[°]	-2.5		
<b>Adjustment range of the cushioning component</b>				
P cushioning	[mm]	2	2.6	2.8
P1 cushioning	[mm]	2	2.6	2.8
YSRT cushioning	[mm]	1	1.3	1.4

Data sheet

Technical data – Gripping

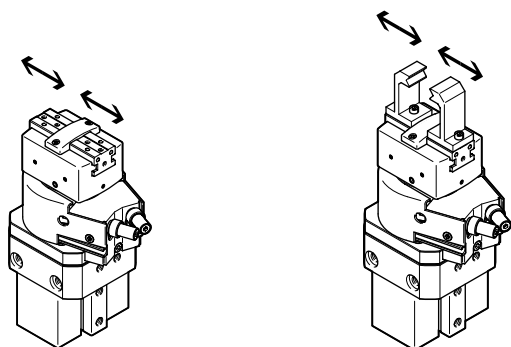
Size	12	16	20
Gripper function	Parallel		
Number of gripper jaws	2		
Max. mass per gripper finger <sup>1)</sup>	[g] 30	50	100
Stroke per gripper jaw	[mm] 2.5	4.5	7
Max. gripper jaw backlash	[mm] 0.02		
Max. gripper jaw angular backlash	[°] 0.1		
Repetition accuracy	[mm] ±0.01	±0.015	
Max. operating frequency	[Hz] 4		
Position sensing	Via proximity switch		

1) Applies to unthrottled operation

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 6 bar operating pressure with vertically mounted swivel/gripper unit without additional gripper fingers. The grippers must be throttled for larger masses [g]. Opening and closing times must then be adjusted accordingly.

With external gripper fingers (as a function of the mass per gripper finger)

Size	12	16	20
Max. mass	30 g	50 g	100 g
Unthrottled	Opening	40	60
	Closing	60	70

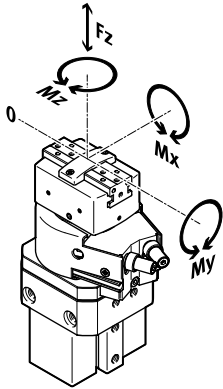
With external gripper fingers (as a function of the mass per gripper finger)

Size	12		16		20			
Mass	100 g	200 g	100 g	200 g	100 g	200 g		
Throttled	Closing		100	150	100	200	100	250



## Data sheet

## Static characteristic load values per gripper jaw



The indicated permissible forces and torques apply to a single gripper jaw.  
 The indicated values include the lever arm, additional weight forces caused by the workpiece or external gripper fingers, as well as forces which occur during movement.  
 The zero coordinate line (gripper jaw guide) must be taken into consideration when calculating torques.

Size		12	16	20
Max. permissible force $F_z$	[N]	90	150	250
Max. permissible torque $M_x$	[Nm]	6	11	22
Max. permissible torque $M_y$	[Nm]	6	11	22
Max. permissible torque $M_z$	[Nm]	6	11	22

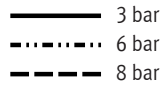
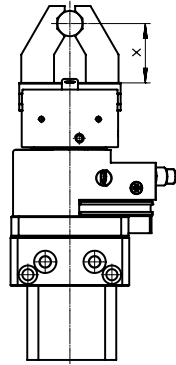
## Gripping force [N] at 6 bar with a lever arm of 25 mm

Size		12	16	20
<b>Gripping force per gripper jaw</b>				
Opening		42	58	96
Closing		37	51	84
<b>Total gripping force</b>				
Opening		84	116	192
Closing		74	102	168

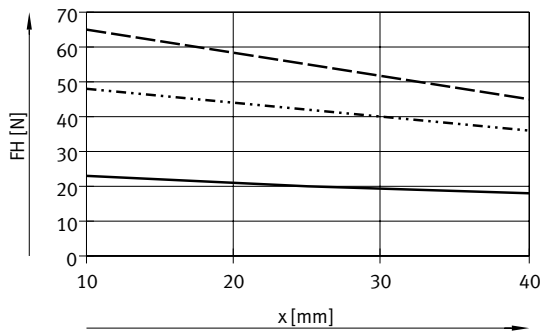
Data sheet

Gripping force  $F_H$  per gripper jaw as a function of operating pressure  $p$

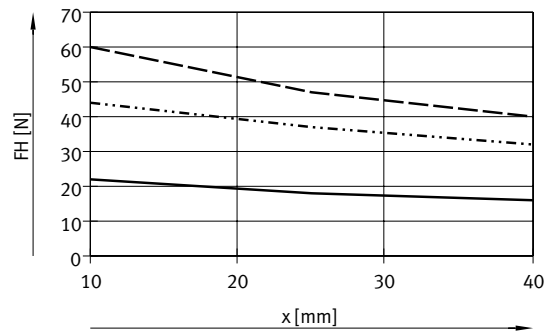
Gripping forces as a function of operating pressure and lever arm can be determined for the various sizes using the following graphs.



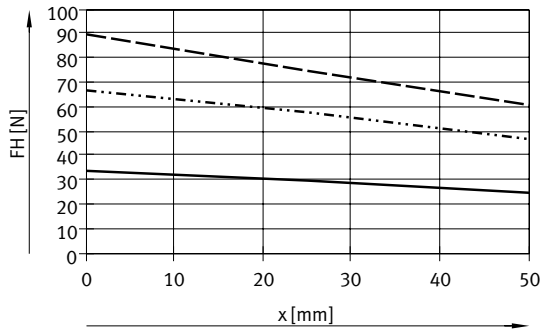
HGDS-12  
Opening



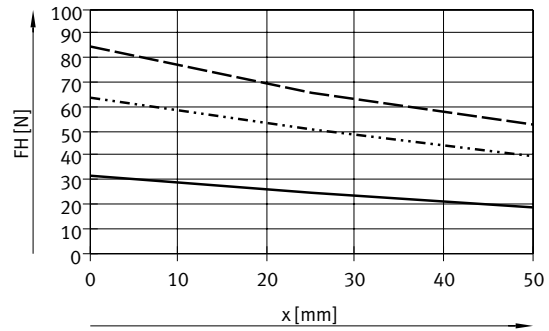
Closing



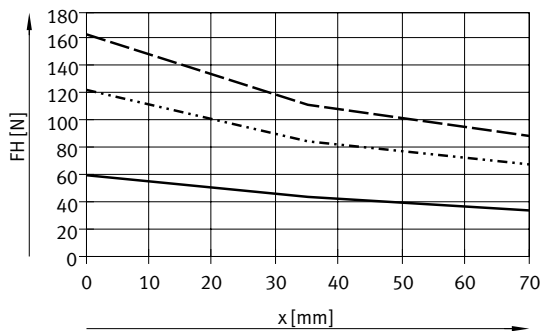
HGDS-16  
Opening



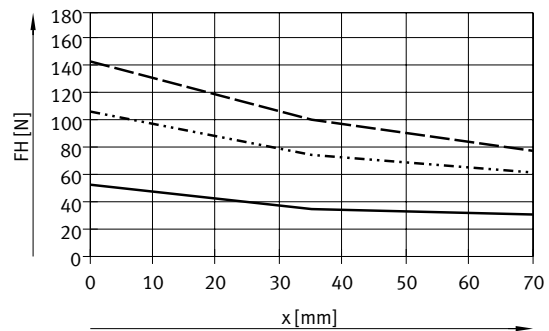
Closing



HGDS-20  
Opening



Closing



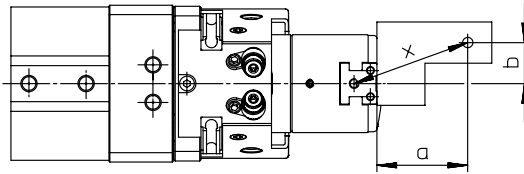
## Data sheet

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 be read from the graphs (→ page 10) using the calculated value  $x$ .



## Calculation example

Assuming:

Distance  $a = 25$  mm

Distance  $b = 20$  mm

To be calculated:

The gripping force at 6 bar with an HGDS-16, used as an external gripper

Procedure:

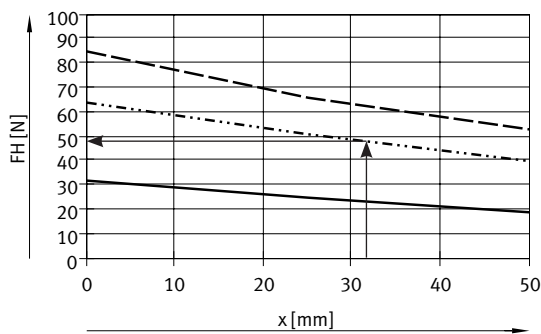
Calculating the lever arm  $x$

$$x = \sqrt{25^2 + 20^2}$$

$$x = 32$$
 mm

The graph (→ page 10) gives a

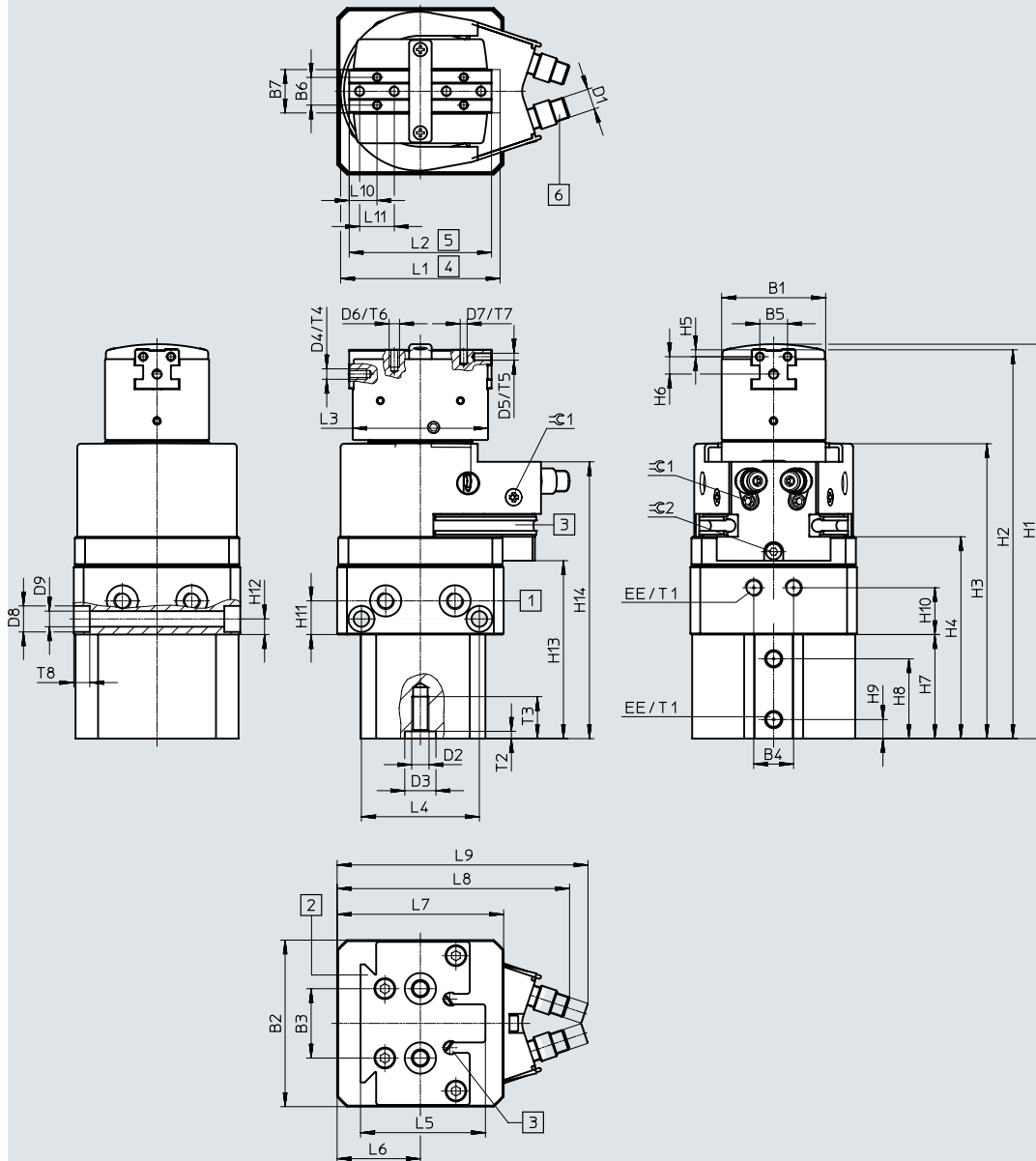
value of  $F_H = 47$  N for the gripping force.



Data sheet

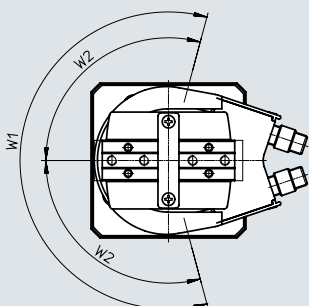
Dimensions

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



- [1] Cross-section through mounting holes → page 13
- [2] For dovetail connection with connecting adapter HAVB-3
- [3] Sensor slot for SME-/SMT-10
- [4] Gripper jaw open
- [5] Gripper jaw closed
- [6] Cushioning

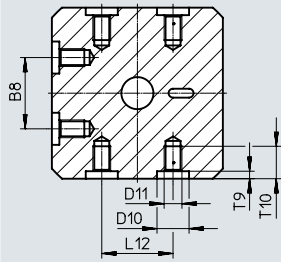
Swivel angle



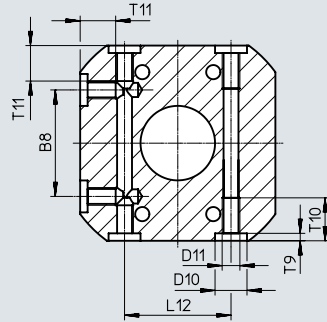
## Data sheet

Cross-section through [1]

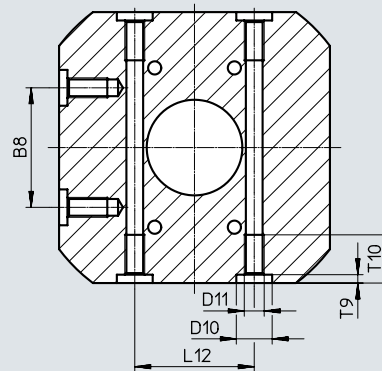
Size 12



Size 16



Size 20



Size	B1	B2	B3	B4	B5	B6	B7	B8 <sup>1)</sup>	D1	D2	D3 ∅ H7	D4
[mm]		±0.03	±0.02		±0.02	±0.02	±0.1					
12	30	48	20	11.5	8	8	12.5	20	M6x0.5	M5	9	M3
16	34	55	30	13	10	10	16	30	M8x1	M5	9	M3
20	40	67.4	30	16	12	12	20	30	M10x1	M5	9	M4

Size	D5 ∅ H8	D6	D7 ∅ H8	D8 ∅ H13	D9 ∅ H13	D10 ∅ H7	D11	EE	H1	H2	H3	H4
[mm]									+1/-0.6	+0.8/-0.4	+1.3/-0.2	+0.8/-0.2
12	2	M3	2	7.5	4.5	9	M5	M5	113.4	111.9	85	58.2
16	2	M3	2	-	4.2	9	M5	M5	121.7	120.1	92.3	64.3
20	2.5	M4	2.5	-	4.2	9	M5	M5	154.8	152.8	112.3	81.7

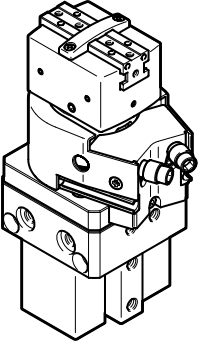
Size	H5	H6	H7	H8	H9	H10	H11	H12	H13	H14	L1	L2
[mm]	±0.02	±0.12	±0.1	±0.1								
12	2	5	30	23	7.5	13.5	9.7	4.5	51.3	79.8	46	41
16	3	5	34.5	26	6.3	14	8	-	58.2	86.7	58	49
20	3	7	43	34.6	5.3	19	9	-	73.1	105.6	78	64

Size	L3	L4	L5	L6	L7	L8 ±1 P	L9 ±1		L10	L11	L12 <sup>1)</sup>	T1
[mm]	±0.5	±0.1		±0.05	±0.03		P1	YSRT	±0.02			min.
12	39	34	36	24	48	67	72.4	72.4	8	10	20	5.3
16	47	-	40.5	27.5	55	80.2	81.6	81.6	8	10	30	5
20	61	-	40.5	34	67.4	93.3	97	97	12	14	30	6

Size	T2	T3	T4	T5	T6	T7	T8	T9	T10	T11	W1	W2	∠ 1	∠ 2
[mm]	+0.1		±0.4	max.	min.	max.		+0.1						
12	2.1	12.1	6	5	3.5	6	4.6	2.1	10	-	210°	105°	2	2
16	2.1	12.1	6	6	4.5	6	-	2.1	12.1	10	210°	105°	2.5	2.5
20	2.1	12.1	9	8	6	7.5	-	2.1	12.1	-	210°	105°	3	2.5

1) Tolerance for centring hole ∅9 H7,  
Tolerance for thread M5 ±0.1 mm

## Data sheet


Ordering data	Size [mm]	Part no.	Type
	<b>With cushioning P</b>		
	12 <sup>1)</sup>	1187955	HGDS-PP-12-P-A-B
	16 <sup>1)</sup>	1187958	HGDS-PP-16-P-A-B
	20 <sup>1)</sup>	1187961	HGDS-PP-20-P-A-B
	<b>With cushioning P1</b>		
	12 <sup>1)</sup>	1187956	HGDS-PP-12-P1-A-B
	16 <sup>1)</sup>	1187959	HGDS-PP-16-P1-A-B
	20 <sup>1)</sup>	1187962	HGDS-PP-20-P1-A-B
	<b>With cushioning YSRT</b>		
	12 <sup>1)</sup>	1187957	HGDS-PP-12-YSRT-A-B
	16 <sup>1)</sup>	1187960	HGDS-PP-16-YSRT-A-B
	20 <sup>1)</sup>	1187963	HGDS-PP-20-YSRT-A-B

1) Two centring sleeves are included in the scope of delivery of the swivel/gripper unit.

## Accessories

**Adapter kit**  
HMVA, HMSV, HAVB

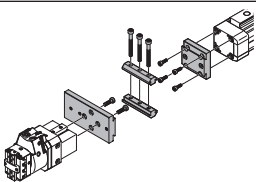


Material:  
Wrought aluminium alloy  
Free of copper and PTFE  
RoHS-compliant

 **Note**

The kit includes the individual mounting interface as well as the necessary mounting material.

## Permissible drive/gripper combinations with adapter kit




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

Combination	Drive	Gripper		Adapter kit			
	Size	Size	Mounting option		CRC <sup>1)</sup>	Part no.	Type
	DGPL-25	12, 16, 20			2	177653	HMSV-7
			534290	HMSV-38			
	DGPL-40	12, 16, 20	■	■		196788	HMVA-DLA1 8/25
						177653	HMSV-7
						534290	HMSV-38
						196790	HMVA-DLA40


1) Corrosion resistance class CRC 2 to Festo standard FN 940070

Moderate corrosion stress. Indoor applications in which condensation can occur. External visible parts with primarily decorative surface requirements which are in direct contact with a normal industrial environment.



## Accessories



Ordering data		For size	Brief description	Part no.	Type	PU <sup>1)</sup>
Cushioning kit for P/P1/YSRT cushioning						
	12	P cushioning: • Elastic cushioning component		1731537	HGDS-12-P-B	1
	16			1731540	HGDS-16-P-B	
	20			1731544	HGDS-20-P-B	
	12	P1 cushioning: • Elastic cushioning component • Adjustable • Via metal fixed stop		1731536	HGDS-12-P1-B	
	16			1731539	HGDS-16-P1-B	
	20			1731542	HGDS-20-P1-B	
	12	YSRT cushioning: • Shock absorbers • Self-adjusting • Via metal fixed stop		1731538	HGDS-12-YSRT-B	1
	16			1731541	HGDS-16-YSRT-B	
	20			1731545	HGDS-20-YSRT-B	



1) Packaging unit

Ordering data		For size	Weight [g]	Part no.	Type	PU <sup>1)</sup>	Data sheets → Internet: zbh
Centring sleeve ZBH							
	12, 16, 20		1	8137184	ZBH-9-B	10	

1) Packaging unit

Ordering data – Proximity sensor for C-slot, magneto-resistive		Type of mounting	Electrical connection, outlet direction of connection	Switching output	Cable length [m]	Part no.	Type	Data sheets → Internet: smt
N/O contact								
	Insertable in the slot from above	Cable, 3-wire, lengthwise	Plug M8x1, 3-pin, in-line	PNP	2.5	551373	SMT-10M-PS-24V-E-2.5-L-OE	
		Cable, 3-wire, lateral			0.3	551375	SMT-10M-PS-24V-E-0.3-L-M8D	
	Insertable in the slot from above	Cable, 3-wire, lateral	Plug M8x1, 3-pin, lateral	PNP	2.5	551374	SMT-10M-PS-24V-E-2.5-Q-OE	
		Cable, 2-wire, lateral			0.3	551376	SMT-10M-PS-24V-E-0.3-Q-M8D	

Ordering data – Proximity sensor for C-slot, magnetic reed		Type of mounting	Electrical connection, outlet direction of connection	Switching output	Cable length [m]	Part no.	Type	Data sheets → Internet: sme
N/O contact								
	Insertable in the slot from above	Cable, 3-wire, lengthwise	Plug M8x1, 3-pin, in-line	Contacting	2.5	551365	SME-10M-DS-24V-E-2.5-L-OE	
		Cable, 2-wire, lengthwise			2.5	551369	SME-10M-ZS-24V-E-2.5-L-OE	
		Cable, 3-wire, lateral			0.3	551367	SME-10M-DS-24V-E-0.3-L-M8D	
	Insertable in the slot from above	Cable, 3-wire, lateral	Plug M8x1, 3-pin, lateral	Contacting	2.5	551366	SME-10M-DS-24V-E-2.5-Q-OE	
		Cable, 2-wire, lateral			2.5	551370	SME-10M-ZS-24V-E-2.5-Q-OE	
		Cable, 2-wire, lateral			0.3	551368	SME-10M-DS-24V-E-0.3-Q-M8D	

Ordering data – Connecting cables		Electrical connection, left	Electrical connection, right	Cable length [m]	Part no.	Type	Data sheets → Internet: nebu
	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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