

ADAPTIVE GRIPPER 3-FINGER

GIVE TO YOUR ROBOT HAND-LIKE CAPABILITIES THROUGH A RUGGED AND AGILE GRIPPER.



FLEXIBLE

Handles a wide variety of part geometries and sizes.

POWERFUL CONTROL INTERFACE

Easy control of fingers' position, speed and force. Grip detection.

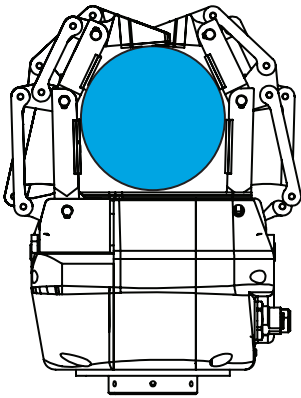
RUGGED AND RELIABLE

Designed for industrial environments.

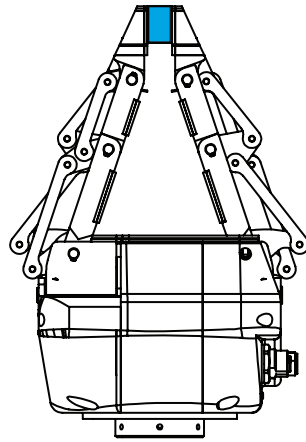


ADAPTIVE GRIPPER

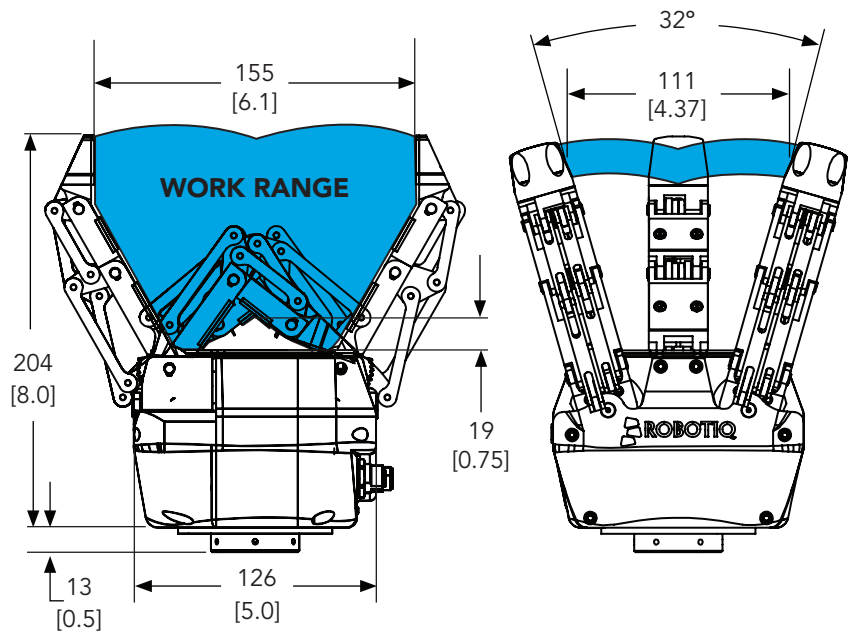
3-FINGER



ENCOMPASSING GRIP



FINGERTIP GRIP



*Figures not showing mechanical coupling to robot.

UNITS: mm
[in.]

TECHNICAL DATA

MECHANICAL SPECIFICATIONS

Gripper opening (see figure)	0 to 155 mm	0 to 6.1 in
Gripper weight	2.3 kg	5 lbs
Object diameter for encompassing	20 to 155 mm	0.79 to 6.1 in
Maximum recommended payload (encompassing grip)	10 kg	22 lbs
Maximum recommended payload (fingertip grip) 0.4 friction coefficient between finger rubber and steel part, safety factor of 2	2.5 kg	5.5 lbs
Grip force (fingertip grip)*	15 to 60 N	3.4 to 13.5 lbf
Closing speed (fingertip grip)	22 to 110 mm/s	0.87 to 4.33 in/s
Operating temperature	-10°C to 50°C	14°F to 122°F
Finger position repeatability (fingertip grip)	0.05 mm	0.002 in

* ±15%, varies with speed and force parameters

ELECTRICAL SPECIFICATIONS

Nominal supply voltage	24 V DC ±10%
Absolute maximum supply voltage	28 V DC
Quiescent power (minimum power consumption)	4.1 W
Peak power (at maximum gripping force)	36 W
2 x 5 m (16.4 ft) shielded high-flex cables included	

CONTROL

Communication protocol options	Modbus TCP, EtherNet/IP, PROFINET, EtherCAT, DeviceNet, CANopen
Communication by default	Modbus RTU (RS-485, half-duplex)
Programmable gripping parameters	Position, speed and force control of each finger Lateral finger position control
Status LEDs (on gripper)	Power, communication and error
Feedback	Grip detection, motor encoder position and motor current