

THANK YOU FOR CHOOSING ROBOTIQ

This step-by-step guide will allow you to **install** and **test** your **Hand-E Gripper** on Universal Robots with a robot controller version CB3 and later.



1. WHAT IS SUPPLIED?

Standard upon delivery of a Universal Robots kit:

Hand-E(HND-GRP-001)
 Gripper Coupling(GRP-CPL-062)
 Fingertip Starting Kit(HND-TIP-START-KIT)
 High-Flex Device Cable(CBL-COM-2065-10-HF)
 USB to RS485 Adapter(ACC-ADT-USB-RS485)
 USB Stick
 Necessary Hardware



2. TOOLS YOU NEED



3. GET THE LATEST

Visit: support.robotiq.com

- Get the up-to-date instruction manual (PDF or web browser).
- Get the latest **Robotiq_Grippers-X.X.X.urcap**.
- Download the .urcap file on a USB stick.

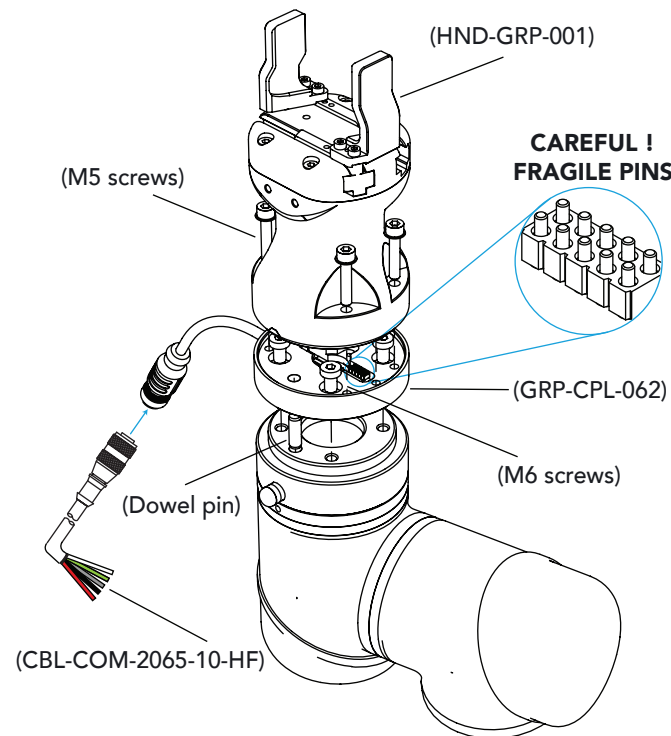


PLEASE READ THE INSTRUCTION MANUAL BEFORE OPERATING THE GRIPPER.



4. MOUNTING

- Mount the coupling (GRP-CPL-062) on your robot arm. Align with the provided dowel pin*.
- Fix using the provided M6 screws (use of threadlocker is recommended).
- Mount the Gripper (HND-GRP-001) on the coupling. Align with the dowel pin*.
- Fix using the provided M5 screws.
- Plug the device cable (CBL-COM-2065-10-HF) into the Gripper's pigtail cable and fix the cable along the robot arm using a cable routing system.



*The dowel pin is meant to have a tight fit on the robot side and a slip fit on the effector side of the assembly.

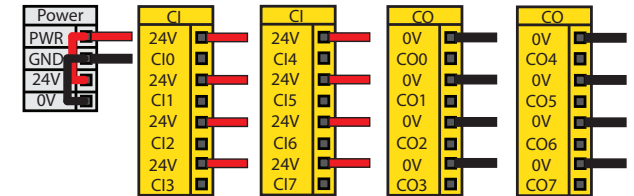


LEAVE ENOUGH EXCESS CABLE TO ALLOW FULL ROBOT MOVEMENT.



5. WIRING

- The red (24V) and black (0V) wires of the device cable (CBL-COM-2065-10-HF) provide power to the Gripper.
- Connect the red wire to a 24V pin.
- Connect the black wire to a 0V pin.



- Connect the communication wires in the USB converter (ACC-ADT-USB-RS485) as shown.



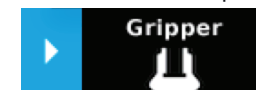
Pin	Signal Name	CBL-COM-2065-10-HF High-Flex Device Cable
1	485 + (A)	WHITE
2	485 - (B)	GREEN
3	485 GND	SHIELD

- Connect the USB converter to the UR controller.



6. SOFTWARE INSTALLATION

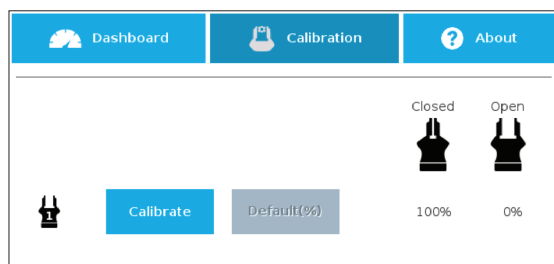
- Have a USB stick that contains the .urcap file (step 3).
- Insert the USB stick in the robot's teach pendant.
- Tap **Setup Robot** and then **URcaps Setup**.
- Tap the + sign.
- Open **Robotiq_Grippers-X.X.X.urcap**.
- Tap the **Restart** button to activate the URCap.
- The Gripper toolbar button will display a short time after the installation of the software is completed.





7. HOW TO CALIBRATE THE GRIPPER

- From a robot program, go to the **Installation** tab and select **Gripper** in the left pane.
- Tap the **Calibration** tab.
- Tap the **Calibrate** button next to the Gripper icon to start the Calibration wizard.

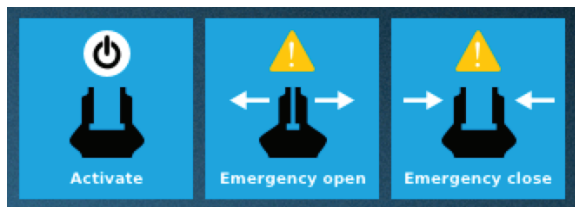


- The wizard prompts the user to fully **close** the Gripper, regardless of the type of fingers/fingertips used.
- Measure the distance between the fingers/fingertips and enter the measurement in the appropriate box.
- Tap the **Continue** button.
- The user is then asked to fully **open** the Gripper.
- Measure the distance between the fingers/fingertips and enter the measurement in the appropriate box.
- Tap the **Continue** button to complete the Calibration wizard.

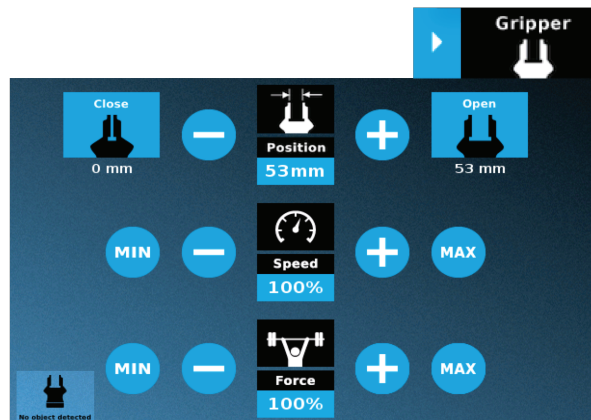


8. TEST AND JOG THE GRIPPER

- Tap the **Gripper** button to expand the Gripper toolbar.
- Tap **Activate** to initialize the Gripper and access the toolbar.



- The Gripper toolbar allows you to jog and test the Gripper. For more information, refer to the instruction manual.



- Depending on the PolyScope settings used, the Gripper position measurements can either display in metric or imperial units.



9. HOW TO PROGRAM THE GRIPPER

- From your robot program, go to the **Structure** tab.
- Go to the **URCaps** tab.
- Tap the **Gripper** button.
- Go to the **Command** tab to edit your Gripper's action.
- More information on how to program the Gripper using the URCap can be found in the instruction manual.

New product has a 1-year warranty from the above date.
Refer to your product instruction manual for details.

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HAND-E

QUICK START GUIDE

For installation on
Universal Robots

