

# **ADAPTIVE GRIPPER**

**2-FINGER 85** 

QUICKLY SETUP A NEW RUN BY USING A FLEXIBLE GRIPPER TO HANDLE ALL YOUR PARTS.



## EASY INTEGRATION

Compatible with all major industrial and collaborative robot manufacturers.



# 3 GRIPPING MODES

Parallel, encompassing and internal grip.



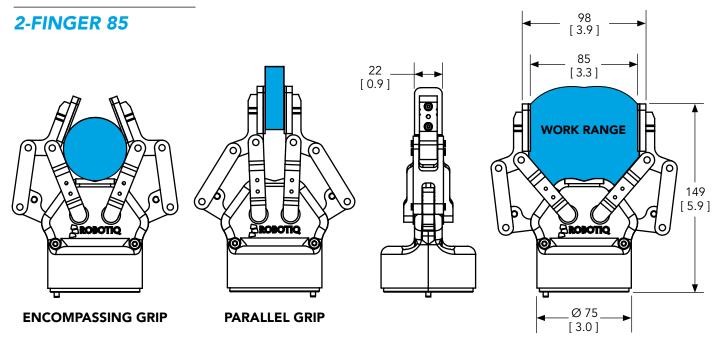
# POWERFUL CONTROL INTERFACE

Control position, speed and force. Grip detection.



robotiq.com T: 1.418.380.2788

# **ADAPTIVE GRIPPER**



# **TECHNICAL DATA**

## **MECHANICAL SPECIFICATIONS\***

Gripper opening (see figure)	0 to 85 mm	0 to 3.3 in
Object diameter for encompassing grip	43 to 85 mm	1.7 to 3.3 in
Gripper weight with mechanical coupling	850 g	1.9 lbs
Maximum recommended payload 0.3 friction coefficient between finger and steel part, safety factor of 2.4	5 kg	11 lbs
Grip force	60 to 200 N	13.5 to 45 lbf
Closing speed	20 to 150 mm/s	0.8 to 5.9 in/s
Operating temperature	-10°C to 50°C	14°F to 122°F
Parallel grip repeatability	0.05 mm	0.002 in

<sup>\*</sup>Using Flat Silicone Fingertips for 2-Finger 85 Adaptive Gripper

# **ELECTRICAL SPECIFICATIONS**

Nominal supply voltage	24 VDC ±10%
Absolute maximum supply voltage	28 VDC
Quiescent power (minimum power consumption)	<1 W
Peak current	1 A

#### **CONTROL**

Communication protocol	Modbus RTU (RS-485, Half-duplex)
Communication protocol options with controller	Ethernet/IP, TCP/IP, DeviceNet, CANopen, EtherCAT, Modbus RTU (USB)
Programmable gripping parameters	Position, speed and force control
Status LED	Power, communication and fault status
Feedback	Grip detection, gripper position and motor current

UNITS: mm

[ in. ]