



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.

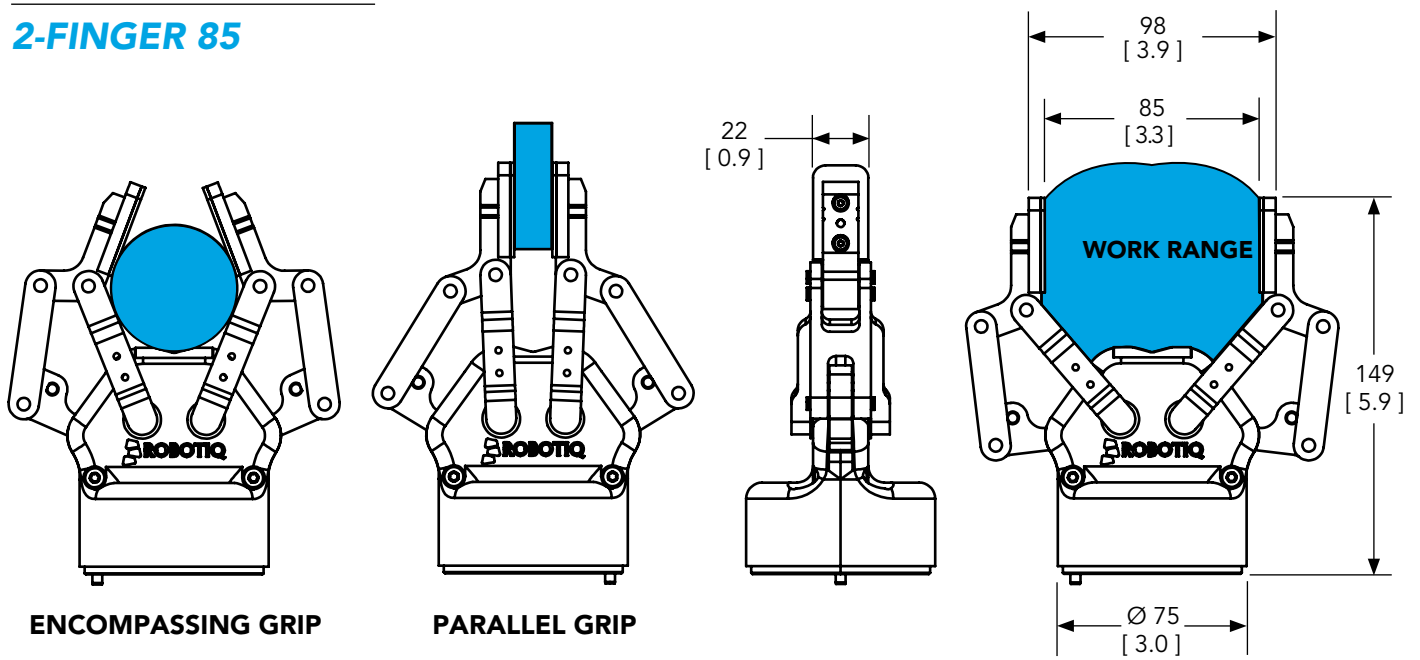
POWERFUL CONTROL INTERFACE

Control position, speed and force. Grip detection.



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UNITS: mm
[in.]

TECHNICAL DATA

MECHANICAL SPECIFICATIONS¹

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 ²	5 to 220 N	1.1 to 49.45 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

1 Using Flat Silicone Fingertips for 2-Finger 85 Adaptive Gripper

2 ± 10%, varies with speed and force parameters

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