



Gripper Grasp



User Guide

The Gripper Grasp app is used to grasp an object, and configure the End Effector with the new load weight.

Tab: Gripper Configuration

Configure the width that you want the gripper fingers to have, and the speed at which the fingers will move to the configured width. A visual representation of the gripper shows the actual gripper width as well as the configured gripper width. You can also configure the force used to grasp the object, as well as set the new load weight for the grasped object.

Info: Hand not initialised!

This information page will be shown if the gripper hand is not properly initialised. Go to the settings menu and in the 'End-Effector' tab, click on the 'Homing' button to re-initialise the hand.

Option: Target Width

Select a target width that the gripper fingers should move to. You can select the width by physically moving the gripper fingers on the robot, or by adjusting the slider in the app, or by entering a value in mm directly in the input box.

Option: Grasping Force

Select a grasping force in Newtons with which that the gripper fingers will grasp the object. You can select a value by adjusting the slider, clicking on the left and right arrows, or by entering a value in Newtons directly in the input box.

Option: Finger Speed

Select the speed in mm/s at which the gripper fingers will move to their configured width. Adjust the value by dragging the slider, clicking the left and right arrows, or entering a value directly in the input box.

Option: Load Weight

Configure the weight of the object that is to be grasped. An accurate load weight is necessary so that the End Effector position can be precisely calculated and controlled. You can also re-use the most recently used load weight by clicking on the load button to the right of the input box.