



Gripper Move



User Guide

The Gripper Move app is used to wait for a specified condition to be satisfied. The App is able to wait for a specified time, for a modbus signal to be detected, or for a user interaction.

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.

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: 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.