|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
| **Symbol** | **Axis**  **Direction** | **Geometric Meaning** | **Default**  **Value (mm)** | **Variable Name** | **Notes** |
| X | Length | External clearance at fingertip | 5 | x\_pg |  |
| C | Distance from TCP to finger base clearance | 40 | c\_pg | Base cle-arance: D |
| D | Gripper base clearance | 5 | d\_pg | Finger side |
| N | Finger length | 50 | n\_pg | = X+C+D |
| T | Gripper base bottom part length | 65 | t\_pg |  |
| U | Gripper base top part length | 50 | u\_pg |  |
| J | Gripper length (TCP to Robot) | 160 | j\_pg | = C+D+  T+U |
| S | Total Gripper length | 165 | s\_pg | = J+X |
| A | Width | Finger width | 10 | a\_pg |  |
| W | Internal clearance in finger width | 1.5 | w\_pg |  |
| V | External clearance in finger width | 5 | v\_pg |  |
| F | Finger open distance (max) | 100 | f\_pg |  |
| G | Finger close distance (min) | 20 | g\_pg |  |
| H | Gripper base bottom part width | 120 | h\_pg |  |
| K | External clearance of base bottom width | 5 | k\_pg | Both side |
| Q | Gripper base top part width | 80 | q\_pg |  |
| R | External clearance of base top width | 5 | r\_pg | Both side |
| E | Depth | Finger depth | 40 | e\_pg |  |
| I | External clearance of finger depth | 5 | i\_pg | Both side |
| L | Gripper base bottom part depth | 120 | l\_pg |  |
| M | External clearance of Gripper base bottom part depth | 5 | m\_pg | Both side |
| O | Gripper base top part depth | 70 | o\_pg |  |
| P | External clearance of Gripper base top part depth | 5 | p\_pg | Both side |
| Y | Maximum depth of Gripper | 130 | y\_pg | Include clearance |
| WR |  | Width of robot arm | 200 | w\_robot |  |
| LR |  | Length of robot arm | 300 | l\_robot |  |