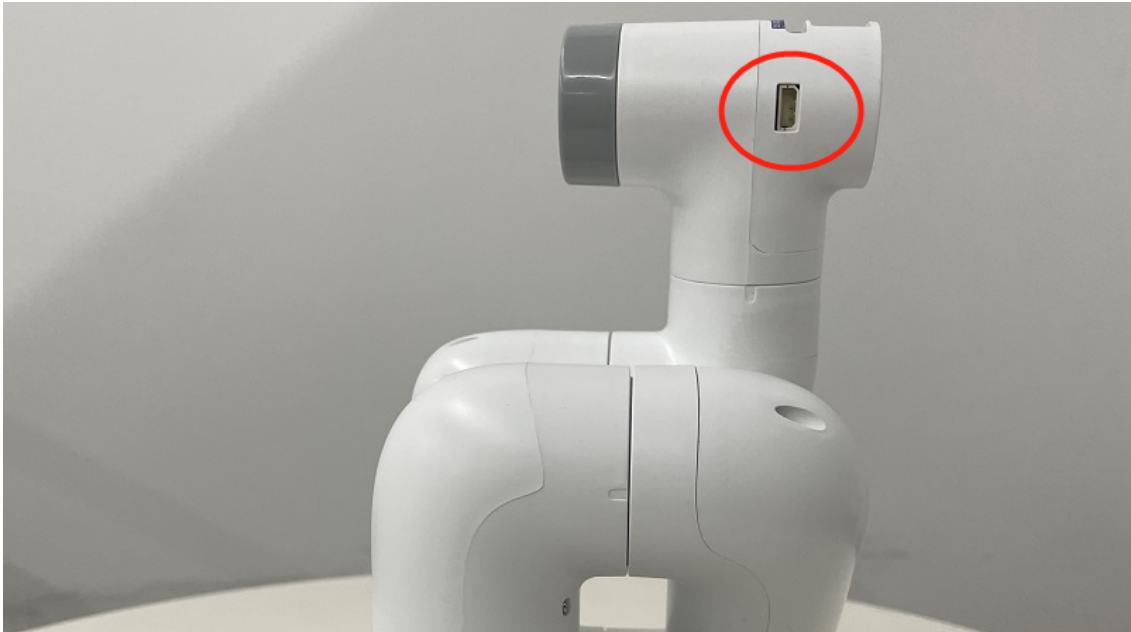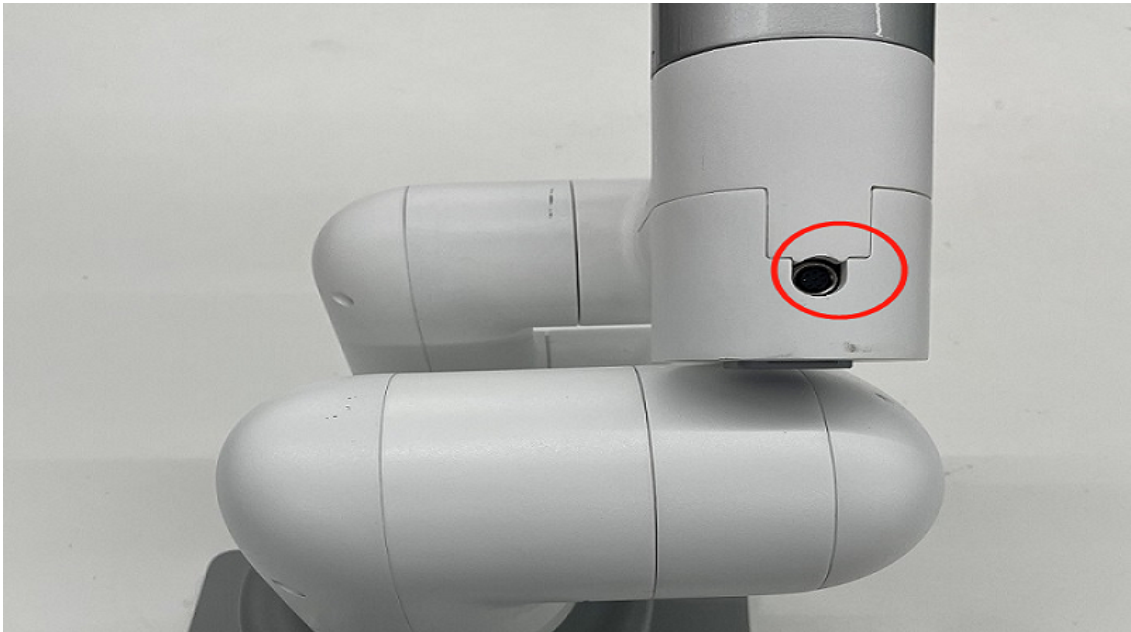# Gripper control

Installing the gripper:

- For an adaptive gripper, insert it on the pin on the atom, as shown in the following figure:

- For an electric gripper, insert it into the 485 interface on the top, as shown in the following figure:
  Notice: myCobot280 and myPalletizer 260 have no electric gripper, only myCobot320 has an electric gripper.

1 Adaptive gripper control

supports： **myCobot280, 320&&myPalletizer 260**
1.1 **setGripperValue(byte angle, byte speed)**
Return value: none
Parameter description: Parameter 1: gripper opening and closing angles (ranging from 0 to 100;
0–closed; 100-maximum open angle); Parameter 2: gripper opening and closing speeds (0-100)
Case:

```
mc.setGripperValue(0, 10);
Thread.Sleep(3000);
mc.setGripperValue(50, 100);
Thread.Sleep(3000);
```

1.2 **getGripperValue()**

Return value: int type, returning the gripper angle (0 - closed; 100 - maximum open angle)

Parameter description: none

Case:

```
Console.WriteLine(mc.getGripperValue());
```

2 Electric gripper control

Available for: **myCobot320**

2.1 **setEletricGripper(int state)**

Return value: none

Parameter description: gripper switch state (0-off; 1-on)

Case:

```
mc.setEletricGripper(0);
```

3 Complete use cases

```
using System;
using System.Threading;

namespace Mycobot.csharp
{
    class Test
    {
        static void Main(string[] args)
        {
            MyCobot mc = new MyCobot("COM57");
            mc.Open();
            Thread.Sleep(5000);

            //set gripper open or close 0--close 100-open max 0-100
            mc.setGripperValue(0, 10);
            Thread.Sleep(3000);
            mc.setGripperValue(50, 100);
            Thread.Sleep(3000);

            //set electric gripper
            mc.setEletricGripper(0);
            Thread.Sleep(100);
            mc.setEletricGripper(1);
            Thread.Sleep(100);

            //get gripper state 0--close 1--open
            Console.WriteLine(mc.getGripperValue());
            mc.Close();
```

```
            }
        }
}
```