The Use of Gripper

M5Stack series: Make sure the robot is connected with PC.

Other series: Make sure the robot is in normal status.

This section takes myPalletizer 260 M5Stack as an example to explain the use of gripper.

Purpose for this section

This section introduces instructions for using gripper.

Introduction to API

- `set_gripper_ini()`

- Applicable to myCobot 280 series, mechArm 270 series, and myPalletizer 260 series
- Function: Set the current position to zero
- `set_gripper_state(flag, speed)`

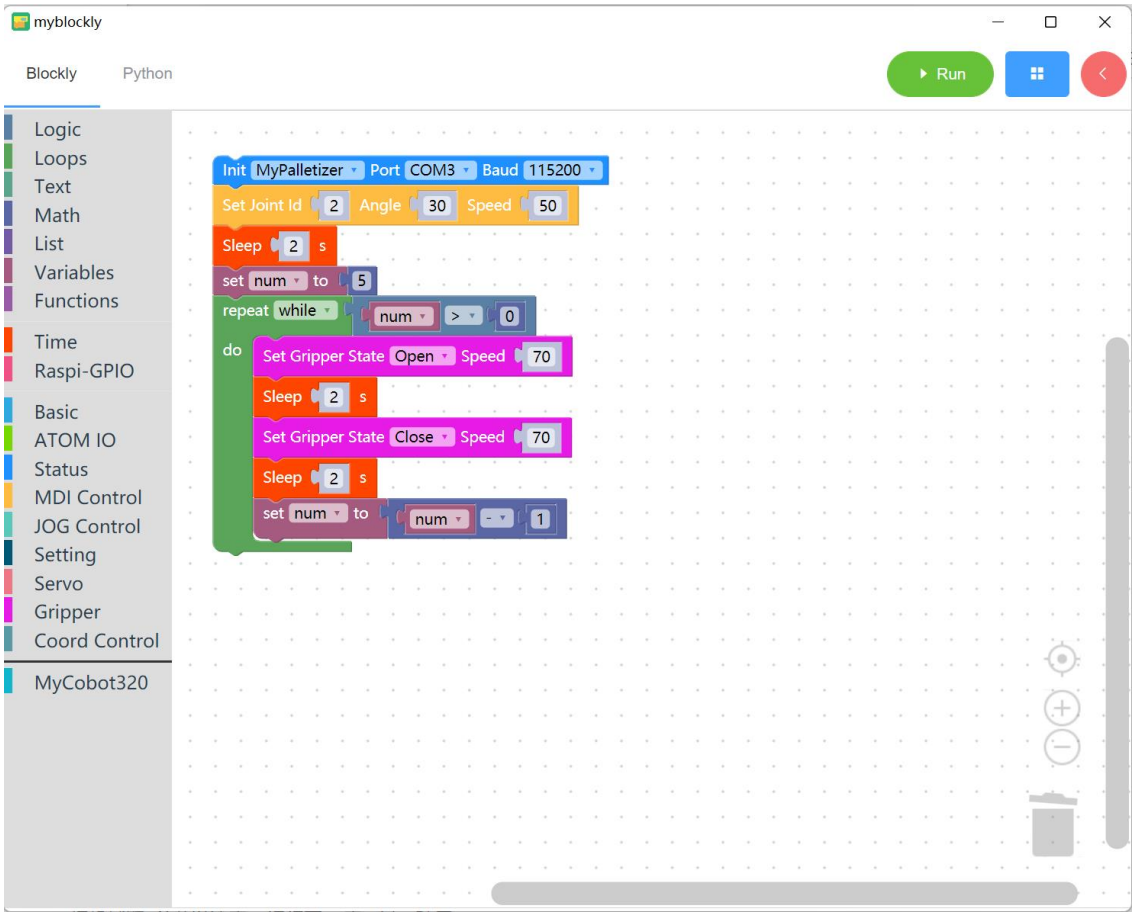
- Applicable to myCobot 280 series, mechArm 270 series, and myPalletizer 260 series
- Parameter:
  - flag (int): `0` means open, and `1` means close
  - speed (int): range from 0 to 100
- Function: set gripper switch state
- `set_gripper_value(value, speed)`

- Applicable to myCobot 280 series, mechArm 270 series, and myPalletizer 260 series
- Parameter:
  - `value()`: range from 0 to 100
  - `speed()`: range from 0 to 100
- Function: set gripper value
- `is_gripper_moving()`

- Applicable to myCobot 280 series, mechArm 270 series, and myPalletizer 260 series
- Function: Judge whether the gripper is moving or not

Simple Demo

- Program for display



- Motion:

  Joint 2 move to 30 degree at the speed of 50,

  after 2 seconds, gripper opens at the speed of 70,

  after 2 seconds, gripper closes at the speed of 70,

  the process loops 5 times.