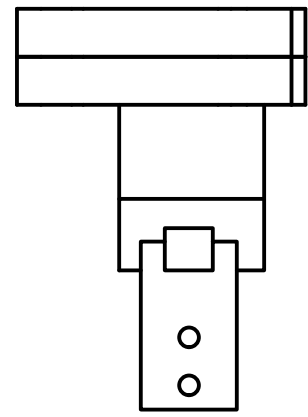
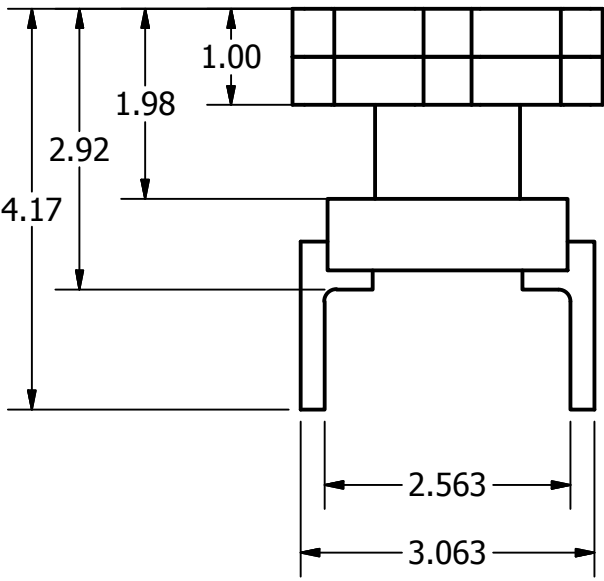
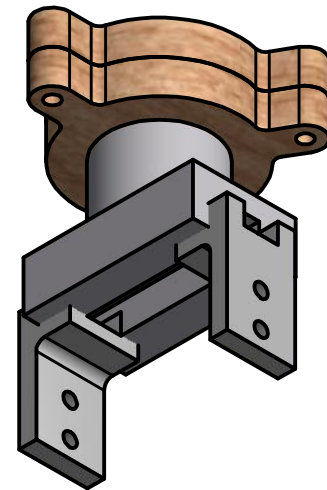
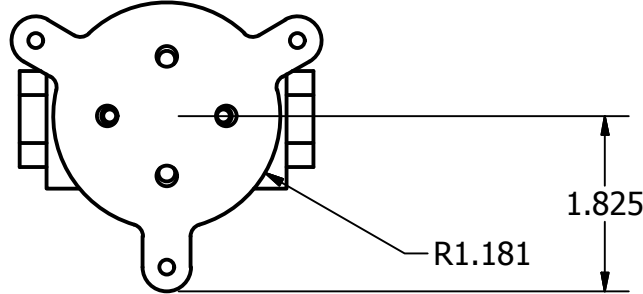


Gripper shown in open position.
In closed position, jaws are approximately 1.75" apart.



For this project, the IRB-120 was fitted with a parallel plate gripper. Although a more dexterous gripper, such as a BarrettHand, would have been desirable, one of the goals of this project was to create this robot as cheaply as possible. This pneumatically actuated parallel plate gripper has only two positions (open and closed), and is simply and cheaply constructed from aluminum and a single double-throw pneumatic piston. The pneumatic nature of the system makes the gripper jaws back-drivable, with a constant gripping force determined by the pneumatic system's adjustable regulator. The regulator can be set to any pressure up to the system's maximum pressure of 120 PSI.

Dimensions in inches

DRAWN Edward Venator (esv@cs.cmu.edu)	Parallel Plate Gripper		
CHECKED			
QA	TITLE		
MFG			
APPROVED	aBBY - A Mobile Robotic Manipulator		
	SIZE	DWG NO	REV
	A	robot	
	SCALE	SHEET 3 OF 3	