

FLEXIBLE ROBOT GRIPPERS DESIGNED FOR UNIVERSAL ROBOTS

PLUG + PLAY INTEGRATION



EASY INSTALLATION

Everything you'll need for a quick installation from hardware to software.

GET THE MOST OUT OF YOUR ROBOT

This adaptive gripper can pick objects of different sizes and shapes.

EASY PROGRAMMING

Program your robot in a few minutes with our Gripper URCap.







153 [6.0] **2-FINGER 85 2-FINGER 140** [5.5] 98 [3.9] WORK RANGE 85 [3.3] 22 [0.9] 209 [8.2] [3.0] [3.0] mm UNITS: PARALLEL GRIP **ENCOMPASSING GRIP** PARALLEL GRIP **ENCOMPASSING GRIP** [in.]

2-FING	GER 85	2-FING	ER 140
0 to 85 mm	0 to 3.3 in	0 to 140 mm	0 to 5.5 in
43 to 85 mm	1.7 to 3.3 in	90 to 140 mm	3.5 to 5.5 in
900 g	2 lbs	1000 g	2.2 lbs
5 kg	11 lbs	2.5 kg	5.5 lbs
20 to 235 N	1.1 to 49.45 lbf	10 to 125 N	2.2 to 24.7 lbf
20 to 150 mm/s	0.8 to 5.9 in/s	30 to 250 mm/s	1.2 to 9.8 in/s
-10°C to 50°C	14°F to 122°F	-10°C to 50°C	14°F to 122°F
0.05 mm	0.002 in	0.08 mm	0.003 in
	0 to 85 mm 43 to 85 mm 900 g 5 kg 20 to 235 N 20 to 150 mm/s -10°C to 50°C	43 to 85 mm 1.7 to 3.3 in 900 g 2 lbs 5 kg 11 lbs 20 to 235 N 1.1 to 49.45 lbf 20 to 150 mm/s 0.8 to 5.9 in/s -10°C to 50°C 14°F to 122°F	0 to 85 mm 0 to 3.3 in 0 to 140 mm 43 to 85 mm 1.7 to 3.3 in 90 to 140 mm 900 g 2 lbs 1000 g 5 kg 11 lbs 2.5 kg 20 to 235 N 1.1 to 49.45 lbf 10 to 125 N 20 to 150 mm/s 0.8 to 5.9 in/s 30 to 250 mm/s -10°C to 50°C 14°F to 122°F -10°C to 50°C

^{*} Using Flat Silicone Fingertips for 2-Finger 85 and 2-Finger 140 Adaptive Grippers

ELECTRICAL SPECIFICATIONS

Nominal supply voltage	24 V DC ±10%
Absolute maximum supply voltage	28 V DC
Quiescent power (minimum power consumption)	<1 W
Peak current	1 A

CONTROL

Communication protocol	Modbus RTU (RS-485, Half-duplex)
Communication protocol options with controller	Ethernet/IP, Modbus TCP, PROFINET, DeviceNet, CANopen, EtherCAT
Programmable gripping parameters	Position, speed and force control
Status LED	Power, communication and fault status
Feedback	Grip detection, gripper position and motor current

^{** ±15%,} varies with speed and force parameters