SOFT ROBOTICS

*m*Grip™
Parallel Gripper

QUICK START GUIDE
For 2, 4, and 6 finger
parallel configurations

SOFT ROBOTICS

Revolutionary Technology

The Soft Robotics *m*Grip modular gripping system is a suite of configurable gripper and controller products that enables reliable, high-speed picking of traditionally hard to grasp items in the food and beverage processing and consumer packaged goods industries.

For more information, visit:
softroboticsinc.com/mgrip

(1)

Install the Air Fitting onto the desired Parallel Hub. **Torque** to **6Nm**.
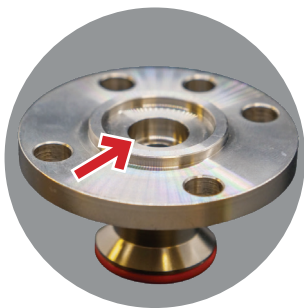
(2)

Install the Robot Adapter onto the Parallel Hub.

(3)

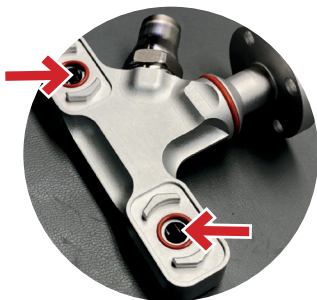**Insert** the M6 Screw to attach Robot Adapter through Parallel Hub. **Torque** this screw to **7.4Nm**.
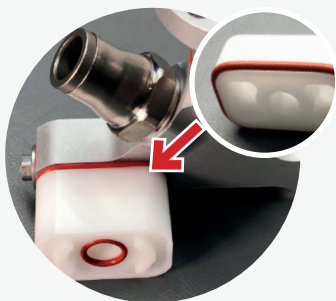
Note: We recommend Anti-Seize gel onto M6 screw before installation.

(4)

Ensure O-Rings are installed on the Parallel Hub and did not come loose during shipping.

5

Install the desired Spacer onto the Parallel Hub (if required) by aligning the features and pressing firmly.

6

Install Finger Module onto the Spacer by aligning features and pressing firmly.

Note: Fingers can be mounted directly to the hub if spacers are not being used.


7

Tighten the Hex Nut onto the tie rod (after anti-seize is applied) and then place through the installed finger module and spacer (if present) to attach to the hub.

Note: Use the Tie Rod and spacer chart (located on the right panel of this guide) to identify which tie rod is best for your gripper. We recommend Anti-Seize gel onto the Tie Rod before M4 Hex Nut is installed.

8

Install the second Spacer, if required, onto the opposite side of the Parallel Hub by passing the tie rod through the center of the spacer and pressing firmly against the Parallel Hub.
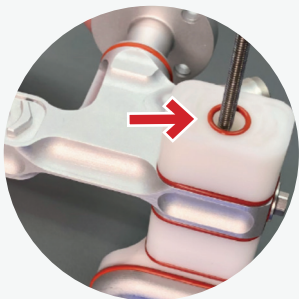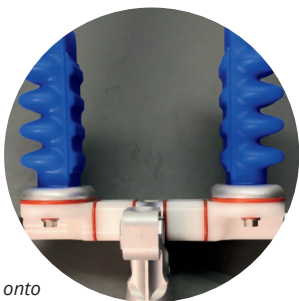
(9)

Install the second Finger Module onto Spacer and through the tie rod.

(10)

Install an M4 Sealing Cap Nut onto the end of the tie rod to secure the Spacers and Finger Modules in place. **Torque** Hex Nut to **2.2Nm**.
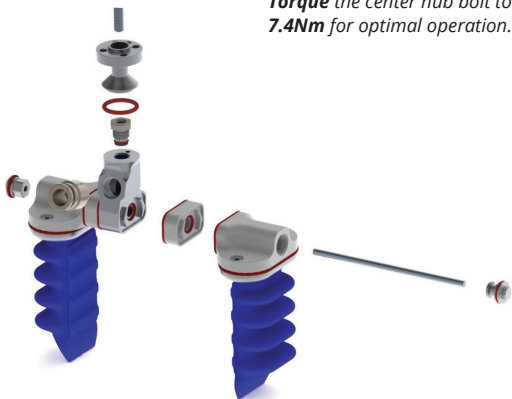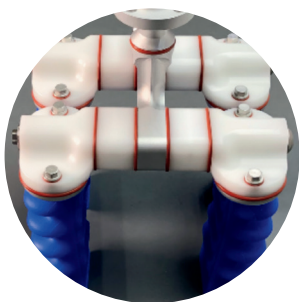
Note: We recommend Anti-Seize gel onto Tie Rod before M4 Cap Nut installation.

(11)

Repeat steps 5 through 10 to secure other Spacers and Finger Modules to the Parallel Hub *(for Parallel 4 and Parallel 6 EOATs)*

*Note: After the EOAT has been present in its operating environment for at least 8 hours, **Torque** the center hub bolt to **7.4Nm** for optimal operation.*

	Parallel EOAT			
	Traditional Finger Modules		**Compact Finger Modules**	
Grip Spacing	**Spacer Size**	**Tie Rod Size**	**Spacer Size**	**Tie Rod Size**
N/A	Blanking Plate	35	Blanking Plate	35
20	-	-	None	75
30	-	-	5	85
40	None	85	10	95
50	5	95	15	105
60	10	105	20	115
70	15	115	25	125
80	20	125	30	135
90	25	135	35	145
100	30	145	40	155
110	35	155	-	-
120	40	165	-	-