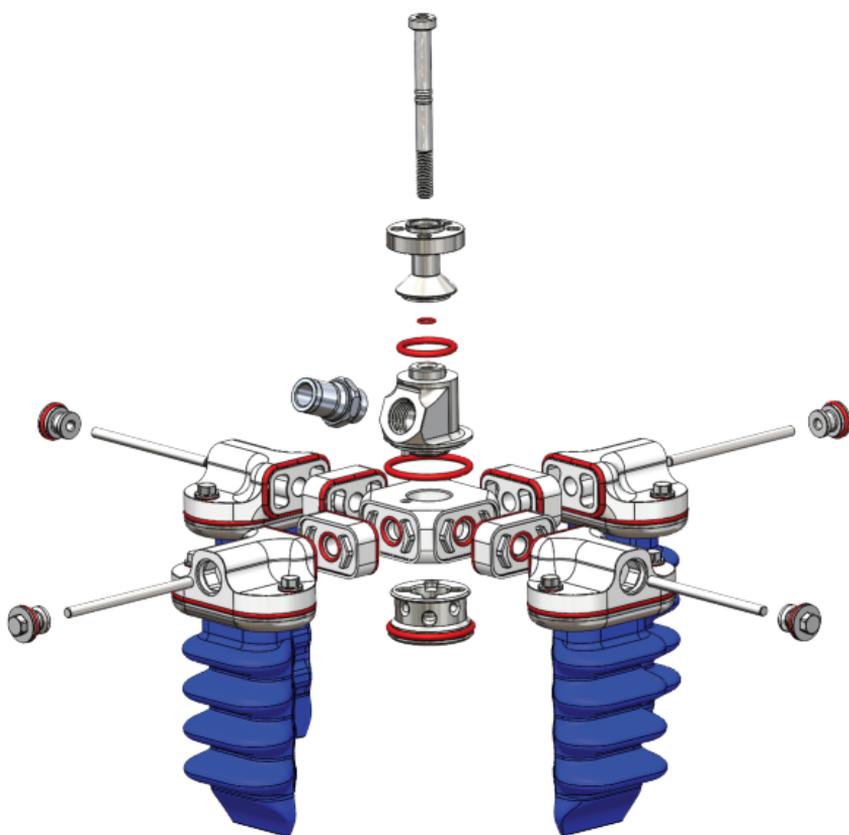




*mGrip*TM Circular Gripper

QUICK START GUIDE
For 3, 4, 5, and 6 finger
circular configurations





Revolutionary Technology

The Soft Robotics *mGrip* 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

*For 3 Finger Configuration,
Skip to Step 4.*

1

Install the Lower Hub Mount into Circular Hub if not already installed.



2

Install the Upper Hub Mount into the Circular Hub.

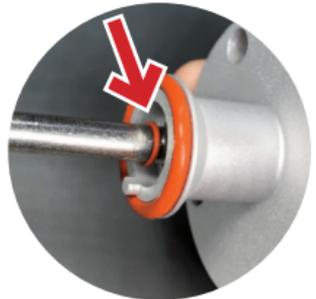
Ensure the mating surfaces are clean and dry.



3

Install the Circular Hub Screw into Robot Adapter.

Ensure the small O-Ring is installed properly on the Hub Screw after the screw is installed into the robot adapter.



***Note:** We recommend grease for the O-Ring and Anti-Seize gel for the screw.*

4

Install the Robot Adapter onto the Upper Hub Mount. **Torque** the Circular Hub Screw to **7.4Nm**. Ensure the mating surfaces are clean and dry.





5

Install the Air Fitting into the Upper Hub Mount and **Torque** to **6Nm**.

Note: This does not apply to 3-finger configuration.

6

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



7

Install the Finger Module onto the Spacer.

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

8

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.



9

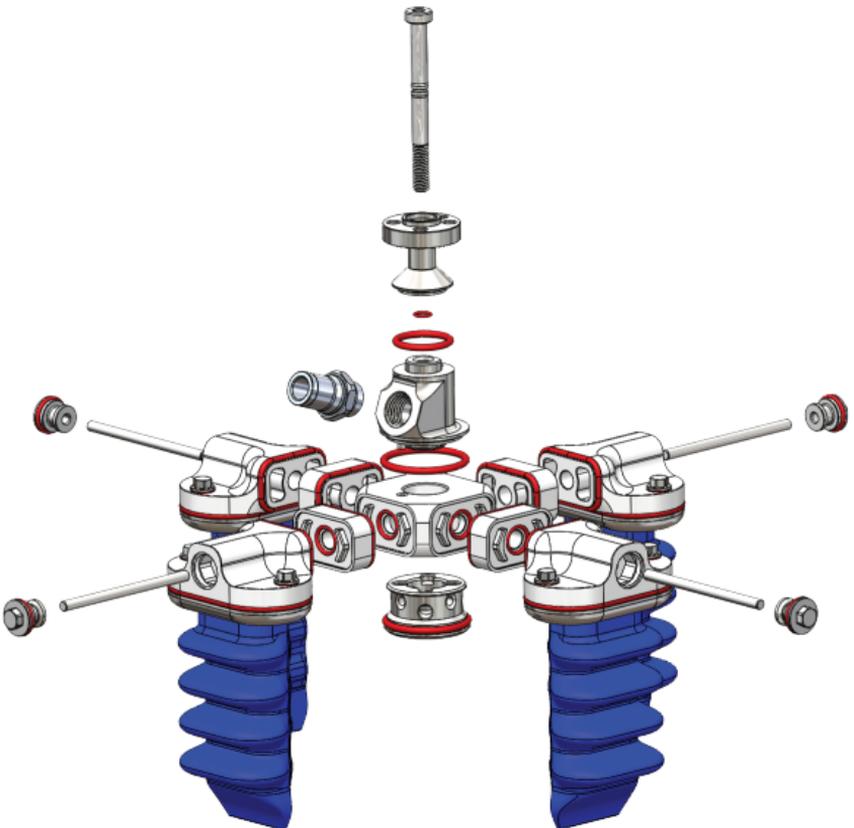
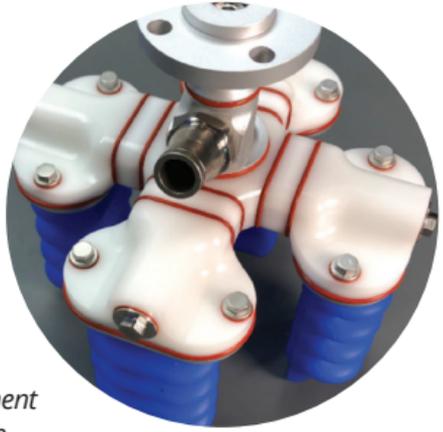
Torque the hex nut on the Tie Rod to **2.2Nm**.

If blanking plates are utilized, follow steps 6, 8, and 9.

10

Repeat steps 7 through 9 to secure other Finger Modules to the Circular Hub.

*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.*



Circular 3 Finger EOAT

Grip Spacing	Traditional Finger Modules		Compact Finger Modules	
	Spacer Size	Tie Rod Size	Spacer Size	Tie Rod Size
30	-	-	None	40
40	-	-	5	45
50	None	45	10	50
60	5	50	15	55
70	10	55	20	60
80	15	60	25	65
90	20	65	30	70
100	25	70	35	75
110	30	75	40	80
120	35	80	-	-
130	40	85	-	-

Circular 4 Finger EOAT

Grip Spacing	Traditional Finger Modules		Compact Finger Modules	
	Spacer Size	Tie Rod Size	Spacer Size	Tie Rod Size
N/A	Blanking Plate	25	Blanking Plate	25
45	-	-	None	45
55	-	-	5	50
65	None	50	10	55
75	5	55	15	60
85	10	60	20	65
95	15	65	25	70
105	20	70	30	75
115	25	75	35	80
125	30	80	40	85
135	35	85	-	-
145	40	90	-	-

Circular 5 Finger EOAT

Grip Spacing	Traditional Finger Modules		Compact Finger Modules	
	Spacer Size	Tie Rod Size	Spacer Size	Tie Rod Size
N/A	Blanking Plate	30	Blanking Plate	30
55	-	-	None	50
65	-	-	5	55
75	None*	55	10	60
85	5	60	15	65
95	10	65	20	70
105	15	70	25	75
115	20	75	30	80
125	25	80	35	85
135	30	85	40	90
145	35	90	-	-
155	40	95	-	-

* Only compatible with Traditional Mini Finger Module

Circular 6 Finger EOAT

Grip Spacing	Traditional Finger Modules		Compact Finger Modules	
	Spacer Size	Tie Rod Size	Spacer Size	Tie Rod Size
N/A	Blanking Plate	35	Blanking Plate	35
65	-	-	None**	-
75	-	-	5	60
85	None*	60	10	65
95	5*	65	15	70
105	10	70	20	75
115	15	75	25	80
125	20	80	30	85
135	25	85	35	90
145	30	90	40	95
155	35	95	-	-
165	40	100	-	-

* Only compatible with Traditional Mini Finger Module ** Not feasible