



MOUNTING INSTRUCTIONS: PNEU-CONNECT® WITH SINGLE GRIPPER

Part No.: 6441-758E

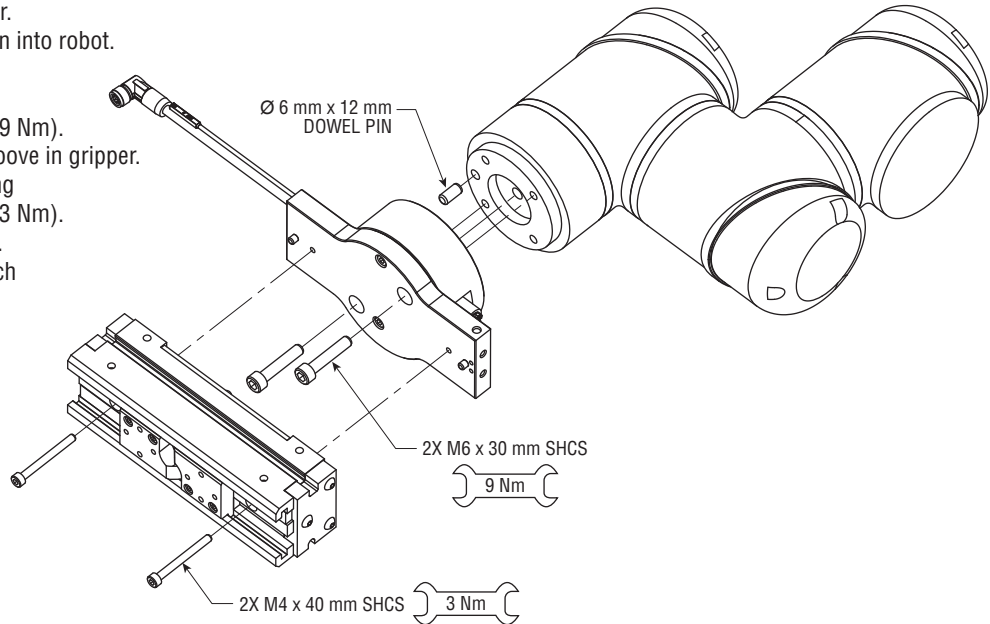
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GRH GRIPPER:

1. Remove 2X M4 x 40 mm SHCS and remove gripper from assembly.
(Gripper jaws must be in full close position to access SHCS.)
O-rings located between gripper and assembly should be retained and used when reattaching gripper.
2. Install \varnothing 6 mm x 12 mm dowel pin into robot.
3. Place assembly onto robot.
4. Fasten assembly to robot using 2X M6 x 30 mm SHCS (torque to 9 Nm).
5. Verify 2X O-rings are seated in groove in gripper.
6. Reattach gripper to assembly using 2X M4 x 40 mm SHCS (torque to 3 Nm).
7. Connect cable to I/O port of robot.
8. Connect air line (4 mm or 5/32 inch tubing) to air fitting.
9. Attach switches to gripper.

Configuration Values*

Payload = 1.22 kg
Center of gravity = 44.1 mm
Tool center point = 85.1 mm
*Values are without gripper tooling,
adjust values for added tooling.

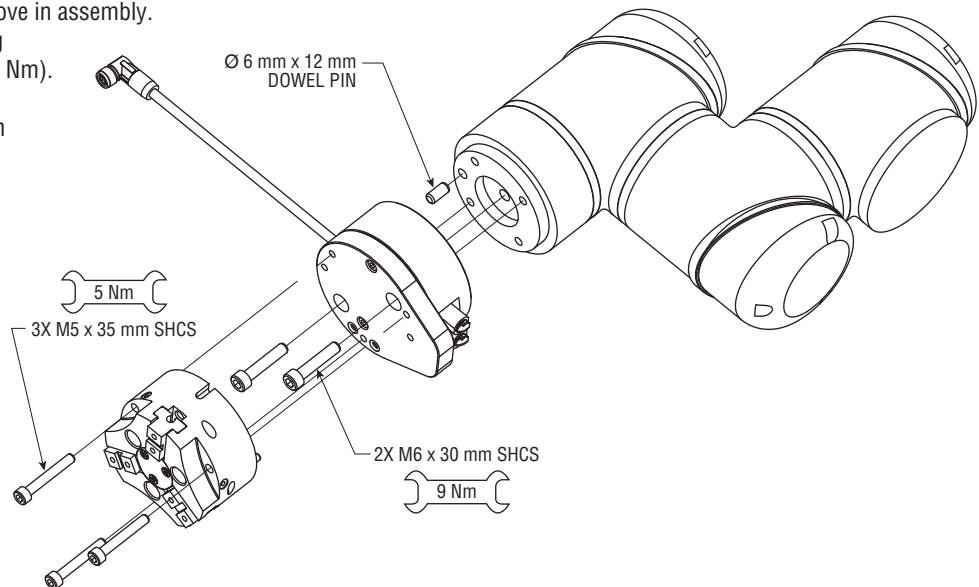


GRT GRIPPER:

1. Remove 3X M5 x 35 mm SHCS and remove gripper from assembly.
O-rings located between gripper and assembly should be retained and used when reattaching gripper.
2. Install \varnothing 6 mm x 12 mm dowel pin into robot.
3. Place assembly onto robot.
4. Fasten assembly to robot using 2X M6 x 30 mm SHCS (torque to 9 Nm).
5. Verify 2X O-rings are seated in groove in assembly.
6. Reattach gripper to assembly using 3X M5 x 35 mm SHCS (torque to 5 Nm).
7. Connect cable to I/O port of robot.
8. Connect air line (4 mm or 5/32 inch tubing) to air fitting.

Configuration Values*

Payload = 0.79 kg
Center of gravity = 44.5 mm
Tool center point = 83.1 mm
*Values are without gripper tooling,



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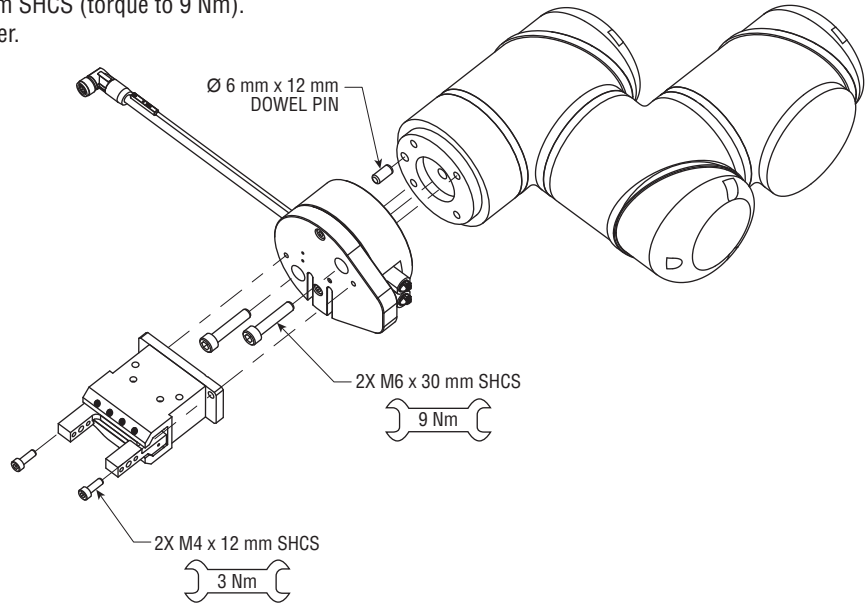
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GRA & GRV GRIPPERS:

1. Remove 2X M4 x 12 mm SHCS and remove gripper from assembly.
O-rings located between gripper and assembly should be retained and used when reattaching gripper.
2. Install \varnothing 6 mm x 12 mm dowel pin into robot.
3. Place assembly onto robot.
4. Fasten assembly to robot using 2X M6 x 30 mm SHCS (torque to 9 Nm).
5. Verify 2X O-rings are seated in groove in gripper.
6. Reattach gripper to assembly using 2X M4 x 12 mm SHCS (torque to 3 Nm).
7. Connect cable to I/O port of robot.
8. Connect air line (4 mm or 5/32 inch tubing) to air fitting.
9. Attach switches to gripper.

Configuration Values*

GRA Payload = 0.67 kg
 GRA Center of gravity = 42.9 mm
 GRA Tool center point = 93.6 mm
 GRV Payload = 0.64 kg
 GRV Center of gravity = 40.6 mm
 GRV Tool center point = 95.1 mm
 *Values are without gripper tooling,

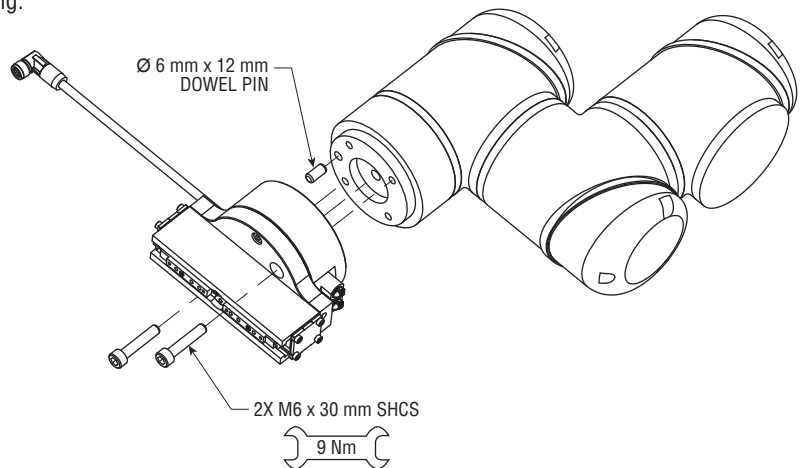


GRL GRIPPER:

1. Install \varnothing 6 mm x 12 mm dowel pin into robot.
2. Place assembly onto robot.
3. Fasten assembly to robot using 2X M6 x 30 mm SHCS (torque to 9 Nm).
4. Connect cable to I/O port of robot.
5. Connect air line (4 mm or 5/32 inch tubing) to air fitting.

Configuration Values*

Payload = 0.61 kg
 Center of gravity = 35.4 mm
 Tool center point = 72.5 mm
 *Values are without gripper tooling,
 adjust values for added tooling





ELECTRICAL SCHEMATICS: PNEU-CONNECT® WITH SINGLE GRIPPER

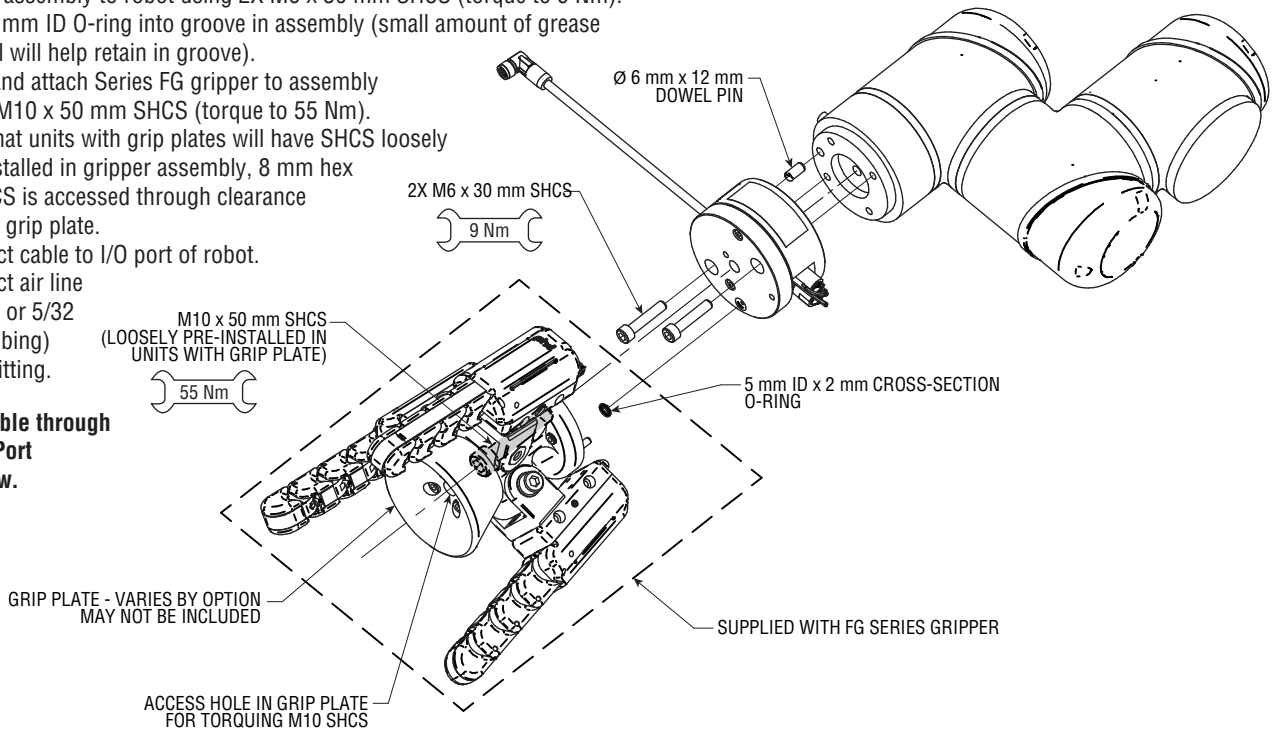
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FG FLEXION GRIPPER:

1. Install Ø 6 mm x 12 mm dowel pin into robot.
2. Place cuff and mounting plate assembly onto robot.
3. Fasten assembly to robot using 2X M6 x 30 mm SHCS (torque to 9 Nm).
4. Seat 5 mm ID O-ring into groove in assembly (small amount of grease on seal will help retain in groove).
5. Align and attach Series FG gripper to assembly using M10 x 50 mm SHCS (torque to 55 Nm).
Note that units with grip plates will have SHCS loosely pre-installed in gripper assembly, 8 mm hex of SHCS is accessed through clearance hole in grip plate.
6. Connect cable to I/O port of robot.
7. Connect air line (4 mm or 5/32 inch tubing) to air fitting.

Controllable through UR Tool Port
See below.



M8 FEMALE 8-PIN CONNECTOR

The pinout diagrams below provide the Pneu-Connect wire assignments for direct I/O control without the software interface.

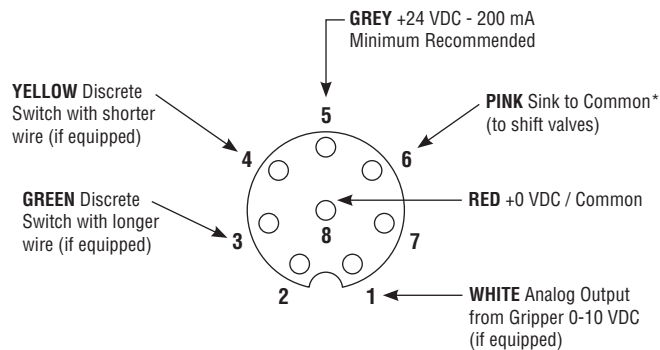
NOTE: A mating M8 8-Pin Male Cordset is required as a flying lead to the robot controller.

PNEU-CONNECT®

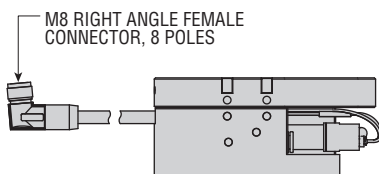
Operation: Pneu-Connect's internal circuitry uses a Digital Output to operate the gripper.

Requires three (3) connections to operate:

- 5 GREY +24 VDC
- 6 PINK "Sink" to Common to shift valves
- 8 RED +0 VDC / Common



*Sink Current is 5 mA with 24 V Supply



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