

## **ADAPTIVE GRIPPER**

### **2-FINGER 140**

**THE IDEAL  
FLEXIBLE GRIPPER  
FOR HIGH-MIX  
PICK AND PLACE**



#### **ADVANCED CONTROL**

Built-in part detection,  
can safely pick fragile and  
deformable objects.

#### **WIDE, PROGRAMMABLE STROKE**

0-140 mm stroke  
adjustable on the fly.

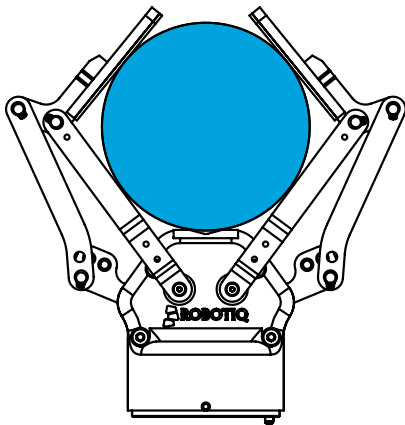
#### **EASY INTEGRATION**

Compatible with all major  
industrial and collaborative  
robot manufacturers.

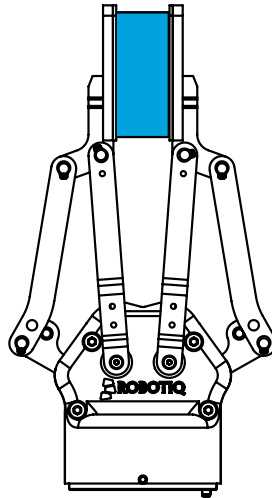


# ADAPTIVE GRIPPER

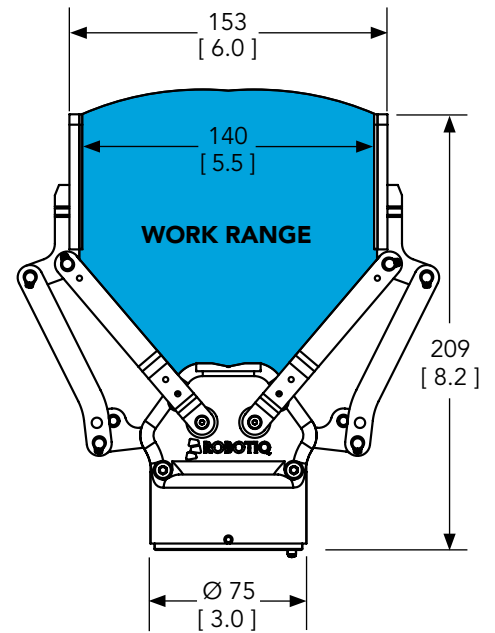
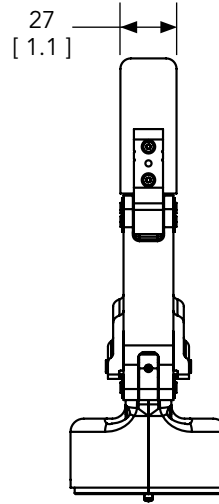
## 2-FINGER 140



ENCOMPASSING GRIP



PARALLEL GRIP



UNITS: mm  
[ in. ]

## TECHNICAL DATA

### MECHANICAL SPECIFICATIONS\*

Gripper opening (see figure)	0 to 140 mm	0 to 5.5 in
Object diameter for encompassing grip	90 to 140 mm	3.5 to 5.5 in
Gripper weight with mechanical coupling	1000 g	2.2 lbs
Maximum recommended payload	2.5 kg	5.5 lbs
0.3 friction coefficient between finger and steel part, safety factor of 2.6		
Grip force**	10 to 110 N	2.2 to 24.7 lbf
Closing speed	30 to 250 mm/s	1.2 to 9.8 in/s
Operating temperature	-10°C to 50°C	14°F to 122°F
Parallel grip repeatability	0.08 mm	0.003 in

\* Using Flat Silicone Fingertips for 2-Finger 140 Adaptive Gripper

\*\* ±10%, varies with speed and force parameters

### 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