



## THE FLEXIBLE ROBOT GRIPPER DESIGNED FOR **UNIVERSAL ROBOTS**

### **EASY INSTALLATION**

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



### **EASY PROGRAMMING**

Ready-made gripper  
programming templates  
for Universal Robots.

### **GET THE MOST OUT OF YOUR ROBOT**

This robot and gripper team thrives on  
fast set up runs and flexibility.



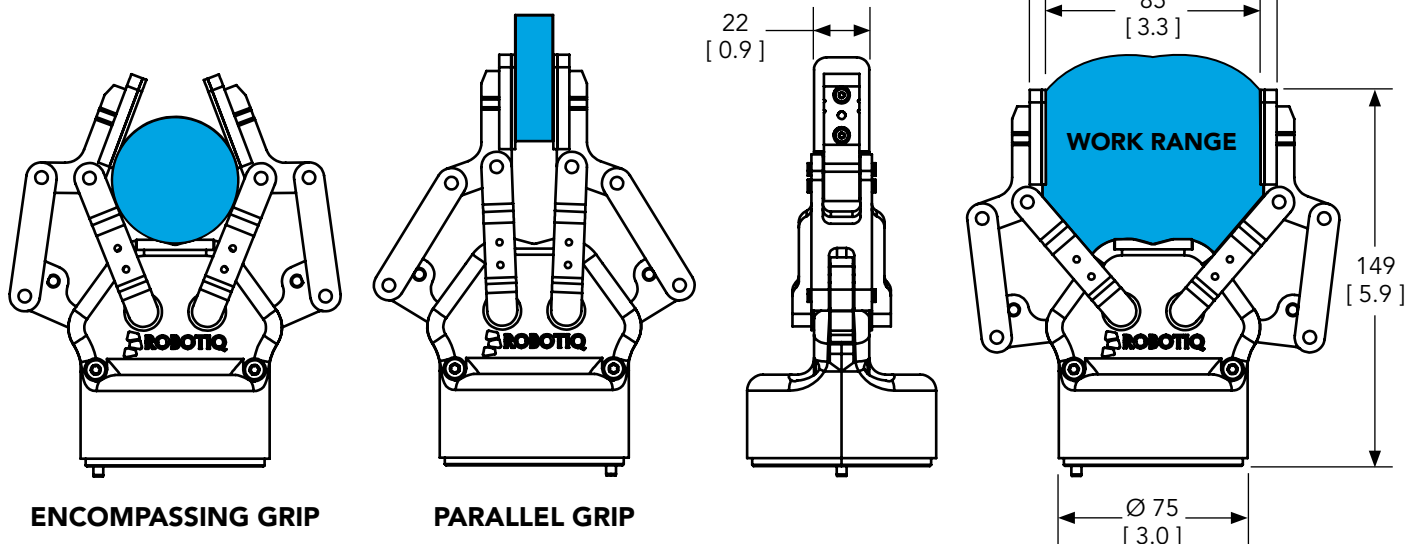
### **ADAPTIVE GRIPPER**

**2-FINGER 85**



# ADAPTIVE GRIPPER

## 2-FINGER 85



UNITS: mm  
[ in. ]

## TECHNICAL DATA

### MECHANICAL SPECIFICATIONS\*

Gripper opening (see figure)	0 to 85 mm	0 to 3.3 in
Object diameter for encompassing grip	43 to 85 mm	1.7 to 3.3 in
Gripper weight with mechanical coupling	850 g	1.9 lbs
Maximum recommended payload	5 kg	11 lbs
0.3 friction coefficient between finger and steel part, safety factor of 2.4		
Grip force	60 to 200 N	13.5 to 45 lbf
Closing speed	20 to 150 mm/s	0.8 to 5.9 in/s
Operating temperature	-10°C to 50°C	14°F to 122°F
Parallel grip repeatability	0.05 mm	0.002 in

\*Using Flat Silicone Fingertips for 2-Finger 85 Adaptive Gripper

### ELECTRICAL SPECIFICATIONS

Nominal supply voltage	24 VDC ±10%
Absolute maximum supply voltage	28 VDC
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, TCP/IP, DeviceNet, CANopen, EtherCAT, Modbus RTU (USB)
Programmable gripping parameters	Position, speed and force control
Status LED	Power, communication and fault status
Feedback	Grip detection, gripper position and motor current

總代理



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## **ROBOTIQ ADAPTIVE GRIPPER**

### **3-FINGER MODEL**

**GIVE TO YOUR ROBOT HAND-LIKE CAPABILITIES THROUGH A RUGGED AND AGILE GRIPPER.**



#### **FLEXIBLE**

Handles a wide variety of part geometries and sizes.

#### **POWERFUL CONTROL INTERFACE**

Easy control of fingers' position, speed and force. Grip detection.

#### **RUGGED AND RELIABLE**

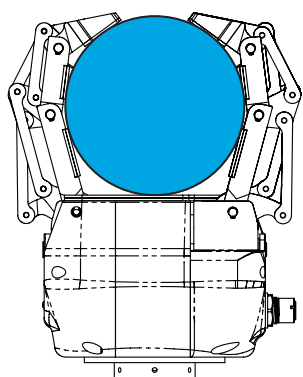
Designed for industrial environments.



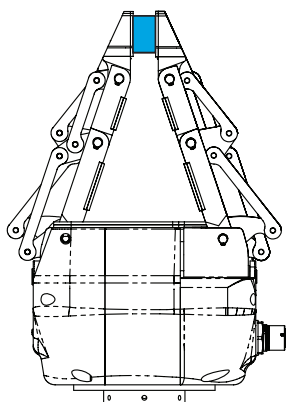
**GRIP IT ALL.**

# ROBOTIQ ADAPTIVE GRIPPER

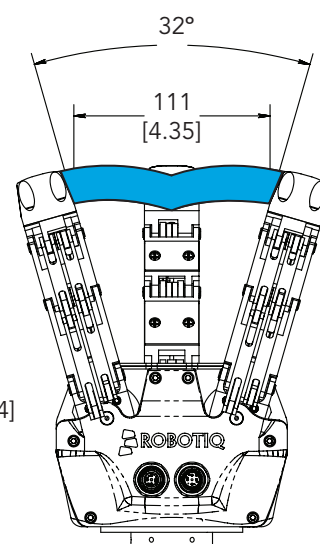
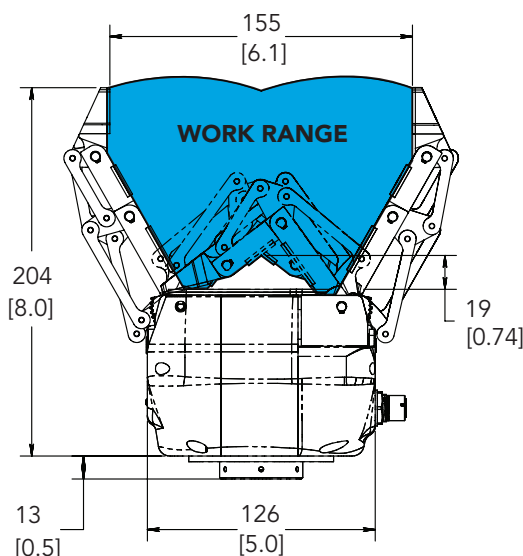
## 3-FINGER MODEL



ENCOMPASSING GRIP



FINGERTIP GRIP



\*Figures not showing adapter plate to robot.

UNITS: mm  
[ in. ]

## TECHNICAL DATA

### MECHANICAL SPECIFICATIONS

Gripper opening (see figure)	0 to 155 mm	0 to 6.1 in
Gripper weight	2.3 kg	5 lbs
Object diameter for encompassing	20 to 155 mm	0.79 to 6.1 in
Maximum recommended payload (encompassing grip)	10 kg	22 lbs
Maximum recommended payload (fingertip grip)	2.5 kg	5.5 lbs
0.4 friction coefficient between finger rubber and steel part, safety factor of 2		
Grip force (fingertip grip)	15 to 60 N	3.4 to 13.5 lbf
Closing speed (fingertip grip)	22 to 110 mm/s	0.87 to 4.33 in/s
Operating temperature	-10°C to 50°C	14°F to 122°F
Finger position repeatability (fingertip grip)	0.05 mm	0.002 in

### ELECTRICAL SPECIFICATIONS

Nominal supply voltage	24 V
Maximum total current	1.5 A
Quiescent power (minimum power consumption)	4.1 W
Peak power (at maximum gripping force)	36 W
2 x 5 m (16.4 ft) shielded high-flex cables included	

### CONTROL

Communication protocol options	EtherNet/IP, TCP/IP, DeviceNet, CANopen, EtherCAT, Modbus RTU
Programmable gripping parameters	Position, speed and force control of each finger Lateral finger position control
Status LEDs (on gripper)	Power, communication and error
Feedback	Grip detection, motor encoder position and motor current

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