



**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.

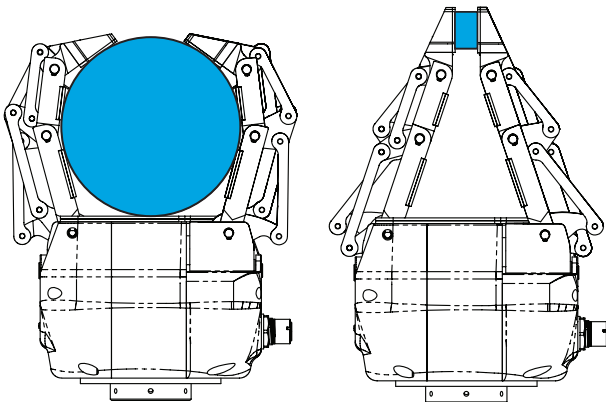
**RUGGED AND RELIABLE**

Designed for industrial environments.



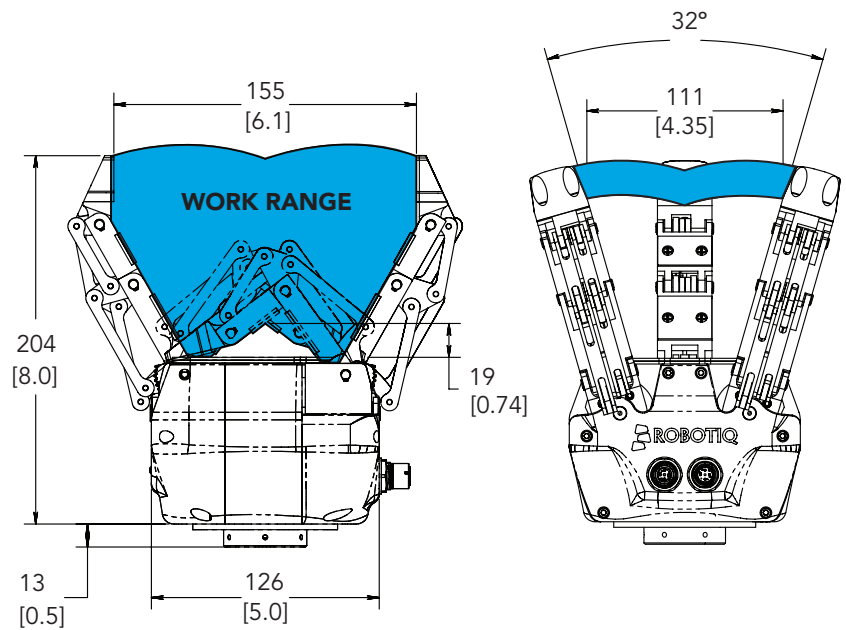
# ROBOTIQ ADAPTIVE GRIPPER

## 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) 0.4 friction coefficient between finger rubber and steel part, safety factor of 2	2.5 kg	5.5 lbs
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