Congratulations on your new RG6 Industrial Robot Gripper !

Scope of delivery for standard RG6 gripper

A RG6 Industrial Robot Gripper
B RG6 Single Bracket
C RG6 Fingertips
D USB Flash Drive
  - Software
  - User Manual
E Bag of screws:
  - M6x8 (4pcs)
  - M4x8 (6pcs)
F 3x Torx keys (T10, T25, T30)
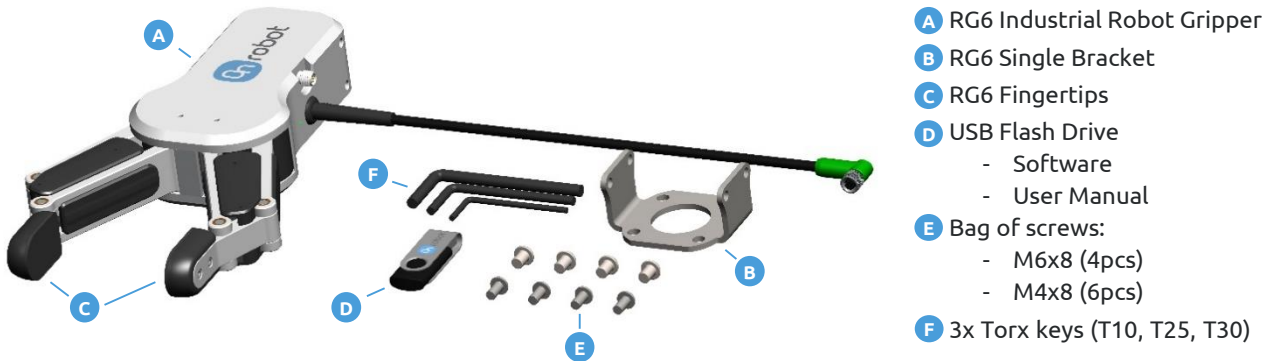
The **RG6 User Manual** is enclosed in the USB stick !

Getting started

- To get started follow the steps in page 2-3-4

⚠️ **WARNING**: It is important that the user/implementer of this product has understood the **RG6** and the Universal Robots User Manuals before connecting the gripper.

Update you RG6 functionalities

In the future, new functionalities will be released at www.onrobot.com/support/

- Get the latest RG6 Software Package
- Get the latest RG6 User Manual

1 Mount RG6
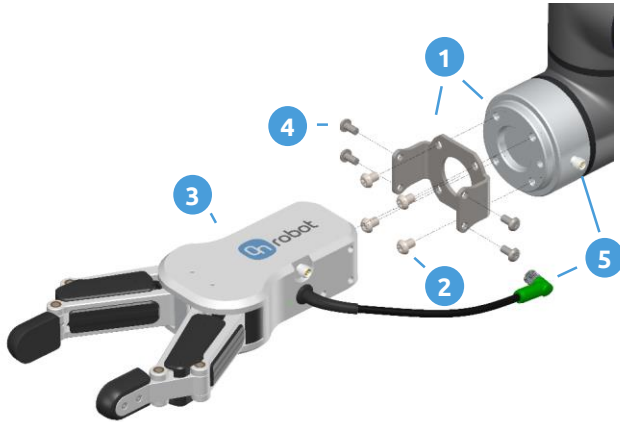
1. Place the bracket on the robot flange

2. Tighten M6 screws (4 pcs)

3. Place RG6 on the bracket with the desired angle

4. Tighten M4 screws (6pcs)

5. Plug RG6 cable in the robot's flange connector

2 Install RG6 Software Package

1. With the system powered on, insert the **USB stick** in the teach pendant

2. Wait for system to reboot

3. Press "**Go to initialization screen**"

4. Press "**ON**"

5. Press "**START**"

6. Press "**OK**"
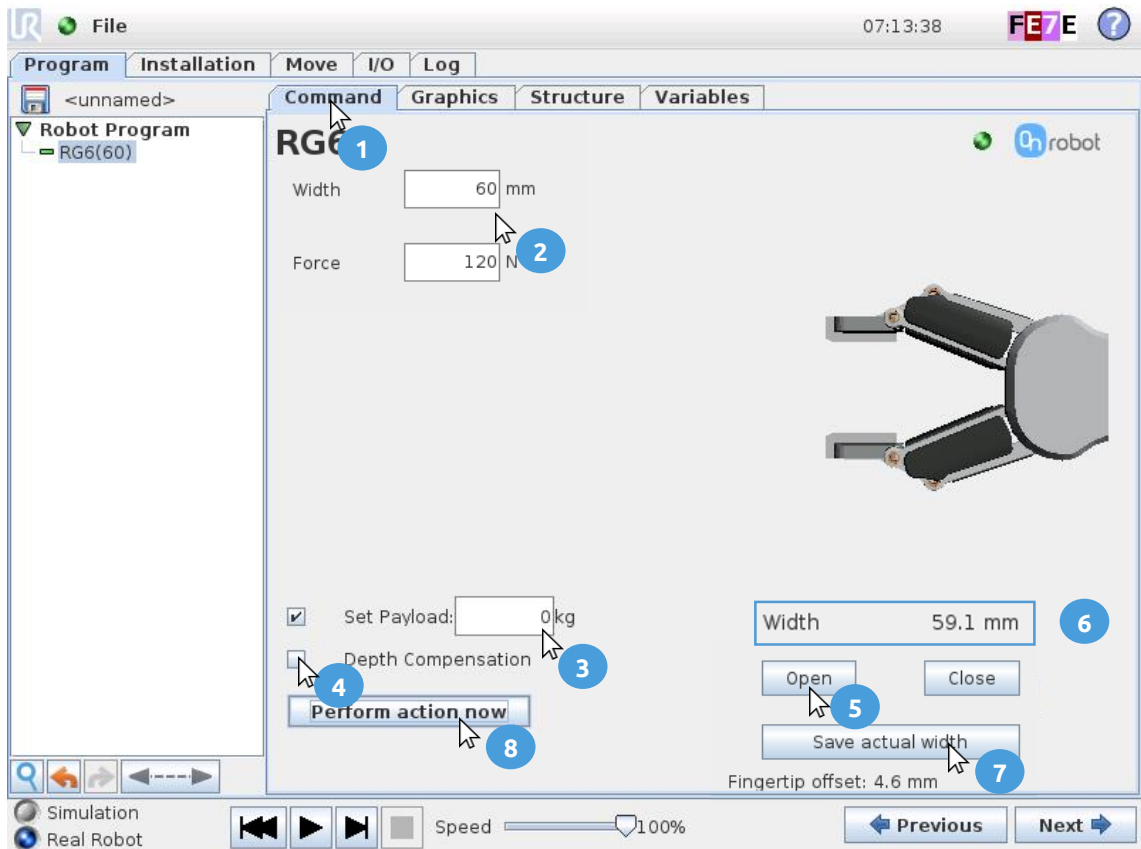
3 Configure RG6 Mount
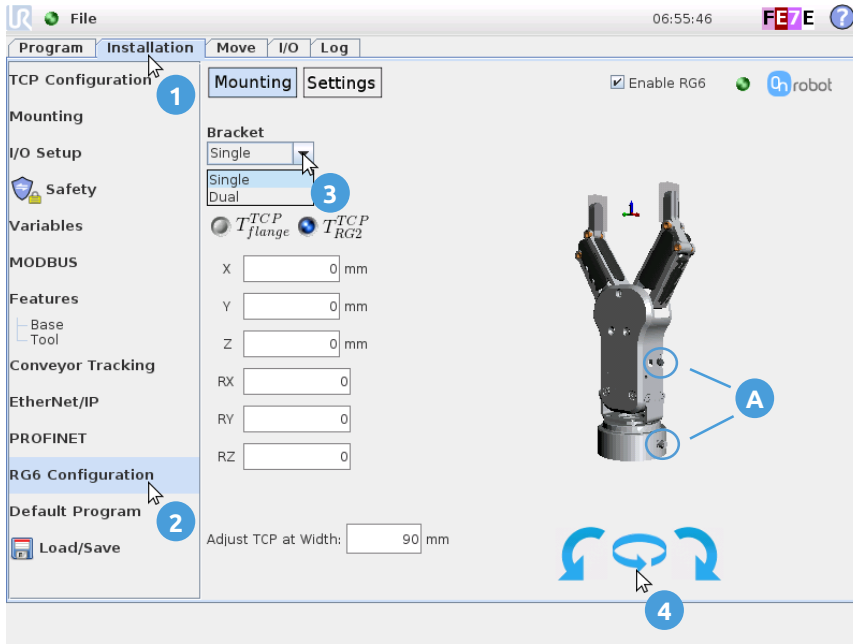
1. Press the "**Installation"** tab

2. Press "**RG Configuration"**

3. Select the "**Bracket"** type

4. Set the relative orientation for RG6 and the robot flange by pressing the **blue arrows** (use the pin guides Ⓐ as reference)

4 Add RG6 Node
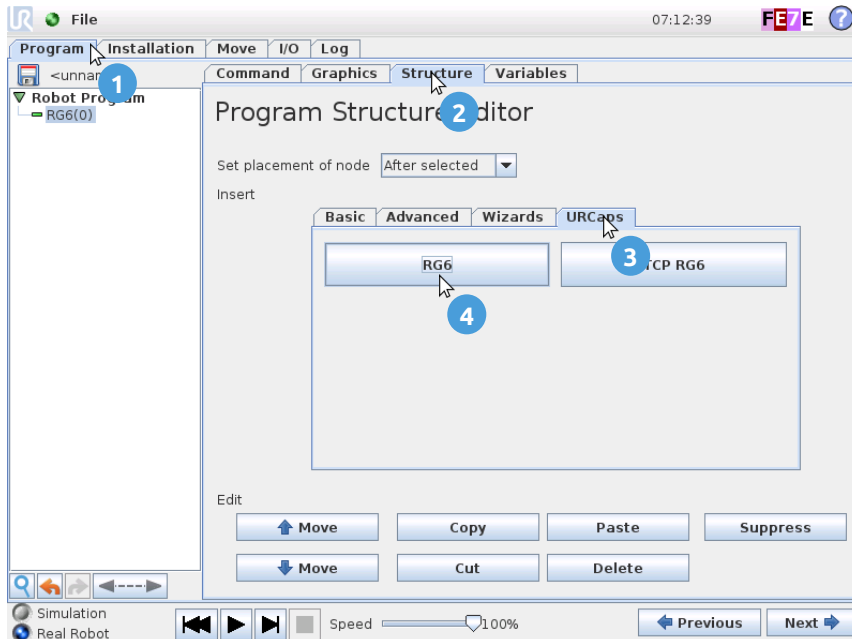
1. Press the "**Program**" tab

2. Press the "**Structure**" tab

3. Press the "**URCaps**" tab

4. Press "**RG6**"

5 Configure RG6 Node

1. Press the "**Command**" tab

2. Set the RG6 **Width** and **Force**

3. Set the **Payload** (workpiece weight)

4. Enable or disable **"Depth Compensation"**

5. "**Open**" and "**Close**" the RG6 by using the buttons (hold-to-run)

6. RG6 **Width** can be read online

7. "**Save actual width**" will save the width value **6** in this node

8. "**Perform action now**", the physical RG6 will move according to **2** and **4**

9. An "**Object detection**" image will appear when grasping an object