

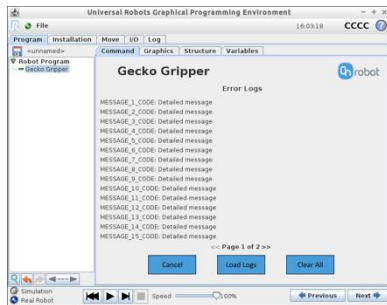
5 Perform Action



1. Select “Perform Action” to actuate the gripper and set parameters.

This step **must** be completed when using I/O comms to save the configuration to the SD card.

6 Other Features

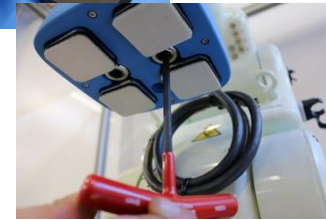


1. Retrieve Error Logs from the “Help” menu bar by clicking on “Error Logs.”
2. Click “Load Logs” for full error log information. By selecting “Save to File,” you can save error logs.



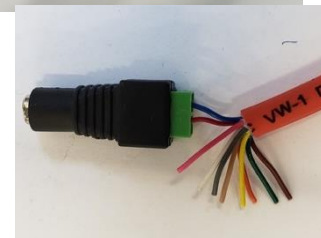
Gecko Gripper Quick Start Guide for Universal Robots

1 Mount Gripper



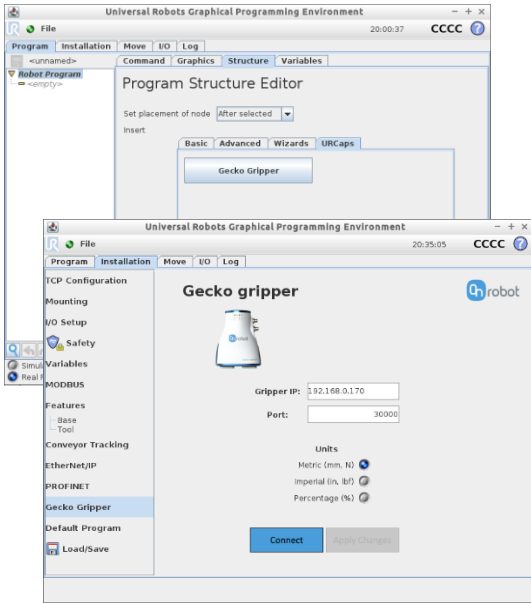
1. Insert the 4 Gecko pads by aligning the tab with the notch in the mounting plate.
2. Align two mounting holes between the gripper and robot. Insert the 2 mounting screws and tighten to 8 N-m with a 5mm hex key.

2 Connect Power and Comms



1. Plug in 10-pin power (24V via I/O cable). If using Ethernet, connect 8-pin cable as well. 4-pin is for optional cleaning system.
2. If using Digital I/O communication, wire flying leads to appropriate ports. If using Ethernet communication, plug in cable to appropriate port.
3. Pin 10 of the IO cable is Earth Ground – this must be properly grounded to ensure proper operation

3 Install Software



1. Plug in the OnRobot USB flash drive to the robot and install Gecko Gripper UR Cap. The program node can be found in the Program Structure Editor.
2. Enter the Gecko Gripper's IP address and port under the "Installation" tab to connect to the gripper. You are now ready to configure the gripper.

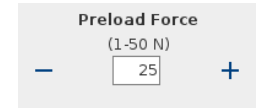
Navigate to the "Command" tab within the main "Program" tab within the UR GUI to display the Training Mode Screen.



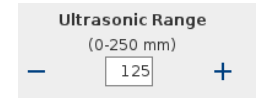
4 Define Gripper State

In the Training Mode Screen, the operator specifies several gripper parameters that collectively define a single gripper state.

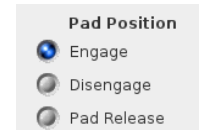
1. Set Preload Force.



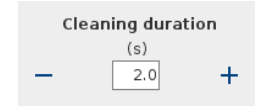
2. Set Ultrasonic Range for part sensor.



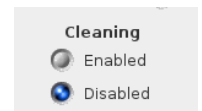
3. Select Pad Position.



4. Set Cleaning Duration for pad cleaning.



5. Choose to Enable or Disable Cleaning.



NOTE: The ultrasonic sensor has a 500 msec response time – account for this delay when robot programming