

Included CKD Pneumatic Gripper Software Operation Method

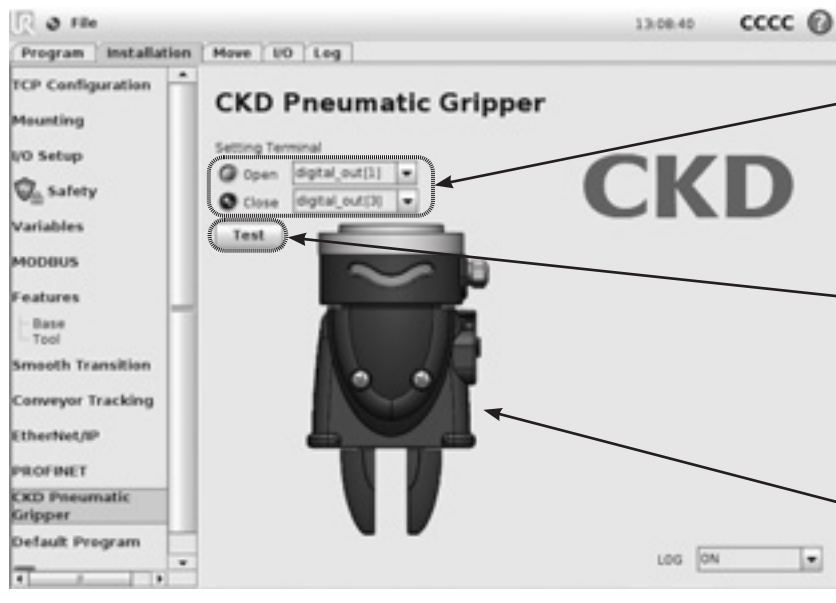
The following explains how to use the dedicated "CKD Pneumatic Gripper" software included with this product. For more details, refer to the UR Robot Manual and the instruction manual for this product. *When option "F" is selected

Software Installation

After inserting the included USB drive into the robot controller, go to the "Setup Robot" screen of the robot controller, select "URCaps," then select "CKD Pneumatic Gripper" and press the "Restart" button to begin installation.

Installation Settings Screen

Set the digital I/O for the directional control valve opening and closing the gripper. Setting is possible while checking the actual open/close status via the graphic display, enabling easy confirmation that the signals are not reversed. To prevent workpieces from falling when the directional control valve signal is shut OFF, use a two-position double solenoid.




Directional control valve digital I/O settings
Set the digital I/O for open/close and the activating directional control valve.

Test button
Open/close action and I/O setting accuracy can be confirmed.

Graphic display
The gripper open/close status and built-in cylinder switch operational status are displayed with color changes.

Program Registration Screen

This screen is for registering operation instructions to the gripper in the robot program. Enter the gripper operation direction, Payload (total mass of the gripper, attachment, and workpiece), barycentric coordinates (payload center of gravity), and the conditions for moving to the next operation.



Operating direction selection button
Selects the operating direction using the OPEN/CLOSE check buttons. Operation can be confirmed using the Test button.

Total mass and center of gravity setting
For "Payload," enter the total mass of the gripper, attachment, and workpiece, and for "Center of gravity," enter the center of gravity for the total mass using the XYZ coordinates.

Operating condition settings
Sets the conditions for moving to the next operation after gripper operation. Select the signal number for input signal waiting, and enter the waiting time for the timer setting.