

Attached Software "CKD Pneumatic Gripper" Operation Method

This is an overview of how to operate the dedicated software "CKD Pneumatic Gripper" included with this product. Refer to the UR Robot Manual and this product's Instruction Manual for details. * When option "F" is selected

Software Installation

Insert the included USB memory into the robot controller, navigate to the robot controller's "Setup Robot" screen, then sequentially select "URCaps" and "CKD Pneumatic Gripper", and press the "Restart" button to begin installation.

Setup Screen

Set the digital I/O of the directional control valve for opening/closing the gripper. Since the actual opening/closing status can be checked on the graphic display, it is easy to confirm if the signal is not reversed. Use a double solenoid 2-position valve for the directional control valve to prevent workpiece drop when the signal is interrupted.

Directional Control Valve Digital I/O Setting
Set the digital I/O for the directional control valve to actuate OPEN and CLOSE respectively.

Test Button
Check OPEN/CLOSE operation to confirm correct I/O settings.

Graphic Display
Displays the gripper's OPEN/CLOSE status and the operating status of the built-in cylinder switch with color changes.

Program Registration Screen

This screen registers gripper operation commands in the robot program. Enter gripper actuation direction, Payload (total weight of gripper, attachment, and workpiece), center of gravity coordinates (Payload center of gravity position), and conditions for proceeding to the next operation.

Operation Direction Selection Button
Select the operation direction with the OPEN/CLOSE checkbox. Confirm operation with the test button.

Total Weight and Center of Gravity Position Setting
For "Payload", enter the total weight of the gripper, attachment, and workpiece. For "Center of gravity", enter the center of gravity position of the total weight in XYZ coordinates.

Operation Condition Setting
Set conditions for proceeding to the next operation after gripper actuation. If waiting for an input signal, select the signal number; if setting a timer, enter the waiting time.

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