

## How to use the included "CKD Pneumatic Gripper" software

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.

### 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

Configure the digital I/O settings of the directional control valve that opens and closes the gripper. Settings can be configured while confirming the actual open/close status on the graphic display, so it is easy to confirm whether the signal is reversed. For the directional control valve, use a 2-position double solenoid valve to prevent workpieces from falling when the signal is cut off.

**Directional control valve digital I/O settings**  
Configures directional control valve digital I/O settings for OPEN/CLOSE.

**Test button**  
Confirms the OPEN/CLOSE operation to make sure the I/O settings are correct.

**Graphic display**  
The OPEN/CLOSE status of the gripper and the operating status of the built-in cylinder switch are indicated by a change in color.

### 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.