



ROBO Cylinder

RCP2 Actuator Gripper Type

Standard Specification

Instruction Manual

===== **Eleventh Edition** =====

Small Slim Two-finger Slide Type:	GRSS
Small Slim Two-finger Lever Type:	GRLS
Small and Medium Two-finger Type:	GRS / GRM
Two-finger Type with High Gripping Force:	GRHM / GRHB
Two-finger Long-stroke Type:	GRST
Three-finger Slide Type:	GR3SS / GR3SM
Three-finger Lever Type:	GR3LS / GR3LM

Please Read Before Use

Thank you for purchasing our product.

This instruction manual explains the handling methods, structure and maintenance of this product, providing the information you need in order to use the product safely.

Before using the product, be sure to read this manual and fully understand the contents explained herein to ensure safe use of the product.

Please download the user's manual from our website.

You can download it free of charge. User registration is required for the first time downloading.

URL : www.iai-robot.co.jp/data_dl/CAD_MANUAL/

When using the product, print out of the necessary portions of the relevant manual, or please display it on your computer, tablet terminal, etc. so that you can check it immediately.

After reading the instruction manual, keep it in a convenient place so that whoever is handling the product can refer to it quickly when necessary.

[Important]

- This instruction manual is an original document dedicated for this product.
- This product cannot be used in ways not shown in this instruction manual. IAI shall not be liable for any result whatsoever arising from the use of the product in any other way than what is noted in the manual.
- The information contained in this instruction manual is subject to change without notice for the purpose of product improvement.
- If any issues arise regarding the information contained in this instruction manual, contact our customer center or the nearest sales office.
- Use or reproduction of this instruction manual in full or in part without permission is prohibited.
- The company names, names of products and trademarks of each company shown in the text are registered trademarks.

RC ROBO CYLINDER

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Safety Guide

"Safety Guide" has been written to use the machine safely and so prevent personal injury or property damage beforehand. Make sure to read it before the operation of this product.

Safety Precautions for Our Products

The common safety precautions for the use of any of our robots in each operation.

No.	Operation Description	Description
1	Model Selection	• This product has not been planned and designed for the application where high level of safety is required, so the guarantee of the protection of human life is impossible. Accordingly, do not use it in any of the following applications. 1) Medical equipment used to maintain, control or otherwise affect human life or physical health. 2) Mechanisms and machinery designed for the purpose of moving or transporting people (For vehicle, railway facility or air navigation facility) 3) Important safety parts of machinery (Safety device, etc.) • Do not use the product outside the specifications. Failure to do so may considerably shorten the life of the product. • Do not use it in any of the following environments. 1) Location where there is any inflammable gas, inflammable object or explosive 2) Place with potential exposure to radiation 3) Location with the ambient temperature or relative humidity exceeding the specification range 4) Location where radiant heat is added from direct sunlight or other large heat source 5) Location where condensation occurs due to abrupt temperature changes 6) Location where there is any corrosive gas (sulfuric acid or hydrochloric acid) 7) Location exposed to significant amount of dust, salt or iron powder 8) Location subject to direct vibration or impact • For an actuator used in vertical orientation, select a model which is equipped with a brake. If selecting a model with no brake, the moving part may drop when the power is turned OFF and may cause an accident such as an injury or damage on the work piece.

No.	Operation Description	Description
2	Transportation	• When carrying a heavy object, do the work with two or more persons or utilize equipment such as crane. • When the work is carried out with 2 or more persons, make it clear who is to be the “leader” and who to be the “follower(s)” and communicate well with each other to ensure the safety of the workers. • When in transportation, consider well about the positions to hold, weight and weight balance and pay special attention to the carried object so it would not get hit or dropped. • Transport it using an appropriate transportation measure. The actuators available for transportation with a crane have eyebolts attached or there are tapped holes to attach bolts. Follow the instructions in the instruction manual for each model. • Do not step or sit on the package. • Do not put any heavy thing that can deform the package, on it. • When using a crane capable of 1t or more of weight, have an operator who has qualifications for crane operation and sling work. • When using a crane or equivalent equipments, make sure not to hang a load that weighs more than the equipment’s capability limit. • Use a hook that is suitable for the load. Consider the safety factor of the hook in such factors as shear strength. • Do not get on the load that is hung on a crane. • Do not leave a load hung up with a crane. • Do not stand under the load that is hung up with a crane.
3	Storage and Preservation	• The storage and preservation environment conforms to the installation environment. However, especially give consideration to the prevention of condensation. • Store the products with a consideration not to fall them over or drop due to an act of God such as earthquake.
4	Installation and Start	(1) Installation of Robot Main Body and Controller, etc. • Make sure to securely hold and fix the product (including the work part). A fall, drop or abnormal motion of the product may cause a damage or injury. Also, be equipped for a fall-over or drop due to an act of God such as earthquake. • Do not get on or put anything on the product. Failure to do so may cause an accidental fall, injury or damage to the product due to a drop of anything, malfunction of the product, performance degradation, or shortening of its life. • When using the product in any of the places specified below, provide a sufficient shield. 1) Location where electric noise is generated 2) Location where high electrical or magnetic field is present 3) Location with the mains or power lines passing nearby 4) Location where the product may come in contact with water, oil or chemical droplets

No.	Operation Description	Description
4	Installation and Start	(2) Cable Wiring • Use our company's genuine cables for connecting between the actuator and controller, and for the teaching tool. • Do not scratch on the cable. Do not bend it forcibly. Do not pull it. Do not coil it around. Do not insert it. Do not put any heavy thing on it. Failure to do so may cause a fire, electric shock or malfunction due to leakage or continuity error. • Perform the wiring for the product, after turning OFF the power to the unit, so that there is no wiring error. • When the direct current power (+24V) is connected, take the great care of the directions of positive and negative poles. If the connection direction is not correct, it might cause a fire, product breakdown or malfunction. • Connect the cable connector securely so that there is no disconnection or looseness. Failure to do so may cause a fire, electric shock or malfunction of the product. • Never cut and/or reconnect the cables supplied with the product for the purpose of extending or shortening the cable length. Failure to do so may cause the product to malfunction or cause fire. (3) Grounding • The grounding operation should be performed to prevent an electric shock or electrostatic charge, enhance the noise-resistance ability and control the unnecessary electromagnetic radiation. • For the ground terminal (PE) on the AC power cable of the controller and the grounding plate in the control panel, make sure for grounding work. For security grounding, it is necessary to select an appropriate wire thickness suitable for the load. Perform wiring that satisfies the specifications (electrical equipment standards and criteria). For detail, follow the description in [an instruction manual of each controller or controller built-in actuator]. • Conduct functional grounding on the FG terminal for a controller supplying 24V DC or a controller built-in type actuator. In order to minimize influence to mechanical operation given by electromagnetic interference (noise) to an electrical device or insulation failure, conduct grounding on a terminal or a conductor that is electrically stable. The reference impedance should be Type D (Former Class 3, ground resistance 100Ω or less).

No.	Operation Description	Description
4	Installation and Start	(4) Safety Measures • When the work is carried out with 2 or more persons, make it clear who is to be the “leader” and who to be the “follower(s)” and communicate well with each other to ensure the safety of the workers. • When the product is under operation or in the ready mode, take the safety measures (such as the installation of safety and protection fence) so that nobody can enter the area within the robot’s movable range. When the robot under operation is touched, it may result in death or serious injury. • Make sure to install the emergency stop circuit so that the unit can be stopped immediately in an emergency during the unit operation. • Take the safety measure not to start up the unit only with the power turning ON. Failure to do so may start up the machine suddenly and cause an injury or damage to the product. • Take the safety measure not to start up the machine only with the emergency stop cancellation or recovery after the power failure. Failure to do so may result in an electric shock or injury due to unexpected power input. • When the installation or adjustment operation is to be performed, give clear warnings such as “Under Operation; Do not turn ON the power!” etc. Sudden power input may cause an electric shock or injury. • Take the measure so that the work part is not dropped in power failure or emergency stop. • Wear protection gloves, goggle or safety shoes, as necessary, to secure safety. • Do not insert a finger or object in the openings in the product. Failure to do so may cause an injury, electric shock, damage to the product or fire. • When releasing the brake on a vertically oriented actuator, exercise precaution not to pinch your hand or damage the work parts with the actuator dropped by gravity.
5	Teaching	• When the work is carried out with 2 or more persons, make it clear who is to be the “leader” and who to be the “follower(s)” and communicate well with each other to ensure the safety of the workers. • Perform the teaching operation from outside the safety protection fence, if possible. In the case that the operation is to be performed unavoidably inside the safety protection fence, prepare the “Stipulations for the Operation” and make sure that all the workers acknowledge and understand them well. • When the operation is to be performed inside the safety protection fence, the worker should have an emergency stop switch at hand with him so that the unit can be stopped any time in an emergency. • When the operation is to be performed inside the safety protection fence, in addition to the workers, arrange a watchman so that the machine can be stopped any time in an emergency. Also, keep watch on the operation so that any third person can not operate the switches carelessly. • Place a sign “Under Operation” at the position easy to see. • When releasing the brake on a vertically oriented actuator, exercise precaution not to pinch your hand or damage the work parts with the actuator dropped by gravity. * Safety protection Fence : In the case that there is no safety protection fence, the movable range should be indicated.

No.	Operation Description	Description
6	Trial Operation	• When the work is carried out with 2 or more persons, make it clear who is to be the “leader” and who to be the “follower(s)” and communicate well with each other to ensure the safety of the workers. • After the teaching or programming operation, perform the check operation one step by one step and then shift to the automatic operation. • When the check operation is to be performed inside the safety protection fence, perform the check operation using the previously specified work procedure like the teaching operation. • Make sure to perform the programmed operation check at the safety speed. Failure to do so may result in an accident due to unexpected motion caused by a program error, etc. • Do not touch the terminal block or any of the various setting switches in the power ON mode. Failure to do so may result in an electric shock or malfunction.
7	Automatic Operation	• Check before starting the automatic operation or rebooting after operation stop that there is nobody in the safety protection fence. • Before starting automatic operation, make sure that all peripheral equipment is in an automatic-operation-ready state and there is no alarm indication. • Make sure to operate automatic operation start from outside of the safety protection fence. • In the case that there is any abnormal heating, smoke, offensive smell, or abnormal noise in the product, immediately stop the machine and turn OFF the power switch. Failure to do so may result in a fire or damage to the product. • When a power failure occurs, turn OFF the power switch. Failure to do so may cause an injury or damage to the product, due to a sudden motion of the product in the recovery operation from the power failure.

No.	Operation Description	Description
8	Maintenance and Inspection	• When the work is carried out with 2 or more persons, make it clear who is to be the “leader” and who to be the “follower(s)” and communicate well with each other to ensure the safety of the workers. • Perform the work out of the safety protection fence, if possible. In the case that the operation is to be performed unavoidably inside the safety protection fence, prepare the “Stipulations for the Operation” and make sure that all the workers acknowledge and understand them well. • When the work is to be performed inside the safety protection fence, basically turn OFF the power switch. • When the operation is to be performed inside the safety protection fence, the worker should have an emergency stop switch at hand with him so that the unit can be stopped any time in an emergency. • When the operation is to be performed inside the safety protection fence, in addition to the workers, arrange a watchman so that the machine can be stopped any time in an emergency. Also, keep watch on the operation so that any third person can not operate the switches carelessly. • Place a sign “Under Operation” at the position easy to see. • For the grease for the guide or ball screw, use appropriate grease according to the instruction manual for each model. • Do not perform the dielectric strength test. Failure to do so may result in a damage to the product. • When releasing the brake on a vertically oriented actuator, exercise precaution not to pinch your hand or damage the work parts with the actuator dropped by gravity. • The slider or rod may get misaligned OFF the stop position if the servo is turned OFF. Be careful not to get injured or damaged due to an unnecessary operation. • Pay attention not to lose the removed cover or screws, and make sure to put the product back to the original condition after maintenance and inspection works. Use in incomplete condition may cause damage to the product or an injury. * Safety protection Fence : In the case that there is no safety protection fence, the movable range should be indicated.
9	Modification and Dismantle	• Do not modify, disassemble, assemble or use of maintenance parts not specified based at your own discretion.
10	Disposal	• When the product becomes no longer usable or necessary, dispose of it properly as an industrial waste. • When removing the actuator for disposal, pay attention to drop of components when detaching screws. • Do not put the product in a fire when disposing of it. The product may burst or generate toxic gases.
11	Other	• Do not come close to the product or the harnesses if you are a person who requires a support of medical devices such as a pacemaker. Doing so may affect the performance of your medical device. • See Overseas Specifications Compliance Manual to check whether complies if necessary. • For the handling of actuators and controllers, follow the dedicated instruction manual of each unit to ensure the safety. • Using the devise in a way not indicated by IAI may lose the protection performance equipped to the device.

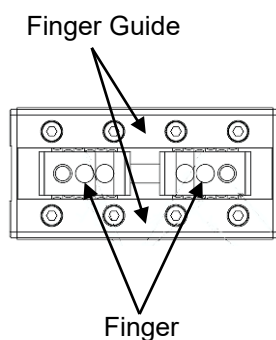
Alert Indication

The safety precautions are divided into “Danger”, “Warning”, “Caution” and “Notice” according to the warning level, as follows, and described in the instruction manual for each model.

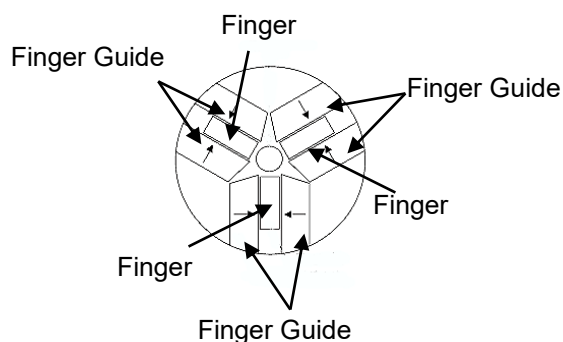
Level	Degree of Danger and Damage	Symbol
Danger	This indicates an imminently hazardous situation which, if the product is not handled correctly, will result in death or serious injury.	 Danger
Warning	This indicates a potentially hazardous situation which, if the product is not handled correctly, could result in death or serious injury.	 Warning
Caution	This indicates a potentially hazardous situation which, if the product is not handled correctly, may result in minor injury or property damage.	 Caution
Notice	This indicates lower possibility for the injury, but should be kept to use this product properly.	 Notice

Caution in Handling

1. **Make sure to follow the usage condition, environment and specification range of the product.**
In case it is not secured, it may cause a drop in performance or malfunction of the product.
2. **Do not attempt to have any handling or operation that is not stated in this instruction manual.**
3. **It is recommended to apply our products for the wiring between the actuator and the controller.**
4. **Do not attempt to establish the settings for the speed and acceleration/ deceleration above the allowable range.**
An operation with speed and acceleration/deceleration beyond the allowable range may cause an abnormal noise, vibration, malfunction or shortened life.
5. **Set the allowable moment within the allowable range.**
An operation with the load beyond the allowable moment may cause an abnormal noise, vibration, malfunction or shortened life. If it is extreme, flaking may occur on the guide.
6. **Make sure to attach the actuator properly by following this instruction manual.**
Using the product with the actuator not being certainly retained or affixed may cause abnormal noise, vibration, malfunction or shorten the product life.
7. **In case of removing the grease applied on the fingers and finger guides after delivery, make sure to implement a rust prevention treatment.**
Applicable models : GRSS, GRS, GRM, GR3SS, GR3SM
There is grease applied on the fingers and finger guides at the delivery for rust prevention treatment.
The fingers and finger guides may gather rust if the grease is wiped away.
Also, have grease or an anti-rust agent applied on the fingers and finger guides regularly.
[Refer to 5.4.1 Guide, Finger and Finger Guide in 5.4 Grease Supply for Two-Fingered Small Slim Type, Small Type and Medium Type, or 5.8.1 Greasing the Guide, Finger and Finger Guide in 5.8 Grease Supply for Three-Fingered Slide Type (GR3SS/GR3SM) for how to supply grease]



Two-Finger Type

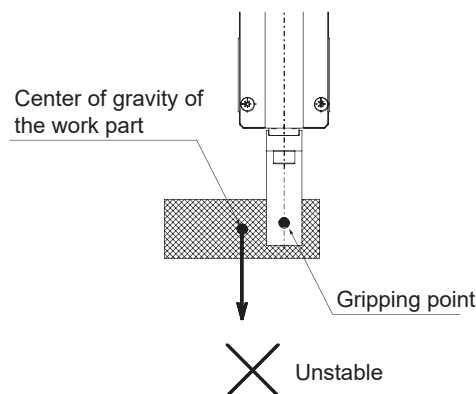


Three-Finger Type

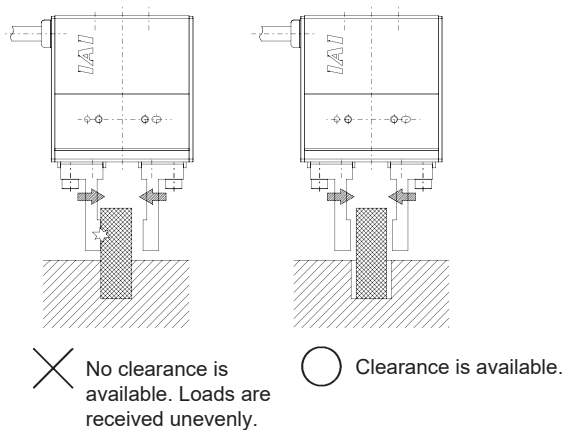
8. Make sure to follow the cautions listed below when transferring a work piece.

If the fingers receive a strong force or impact other than the gripping force when transferring work parts, the finger positions may deviate, looseness may occur or damage may result. Accordingly, pay due attention to the points listed below.

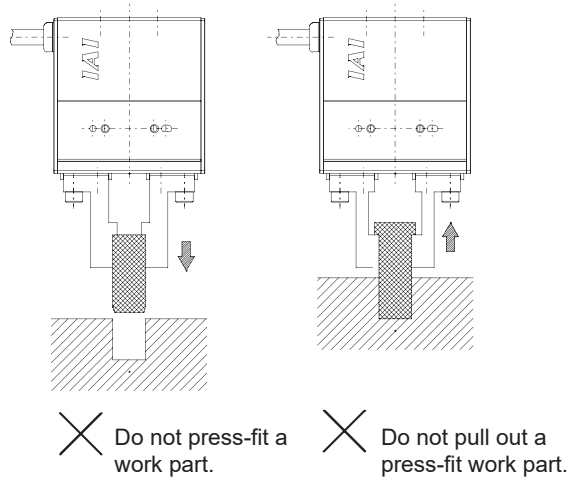
- ◆ Cause the center of gravity of the work part to match the gripping point as much as possible. If the two are not aligned, gravitational moments will force the work part to assume an unstable posture.



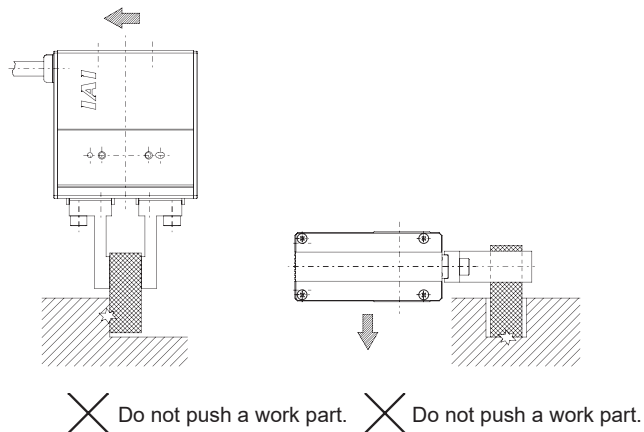
- ◆ While being gripped, the work part should have play (clearance) in the gripping direction. Also perform thorough alignment and avoid using the gripper in a manner where loads concentrate on one finger alone when a work part is gripped.



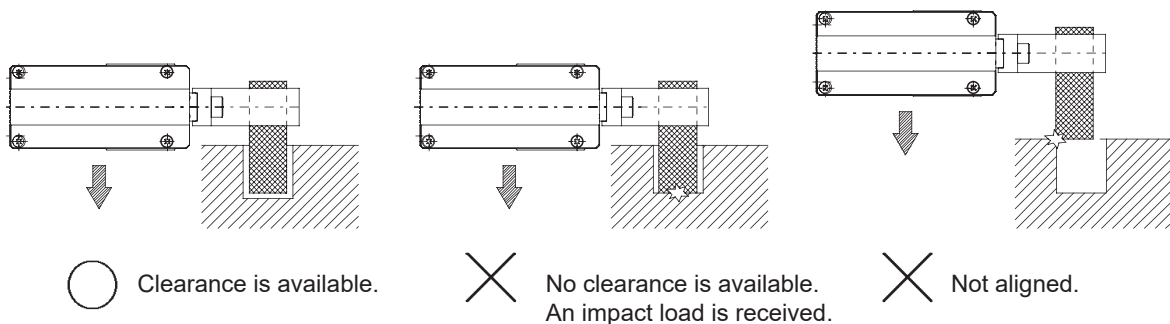
- ◆ Avoid using the gripper in a manner where it press-fits a gripped work part into a hole or pulls out a work part that has been press-fit.



- ◆ Avoid pushing a work part against a jig, etc., at the end of the movement stroke when the work part is moved or reversed.



- ◆ When inserting a work part into a hole, provide a sufficient clearance by anticipating positional variation. Also perform thorough alignment. (Pay attention to contact at the time of insertion.)



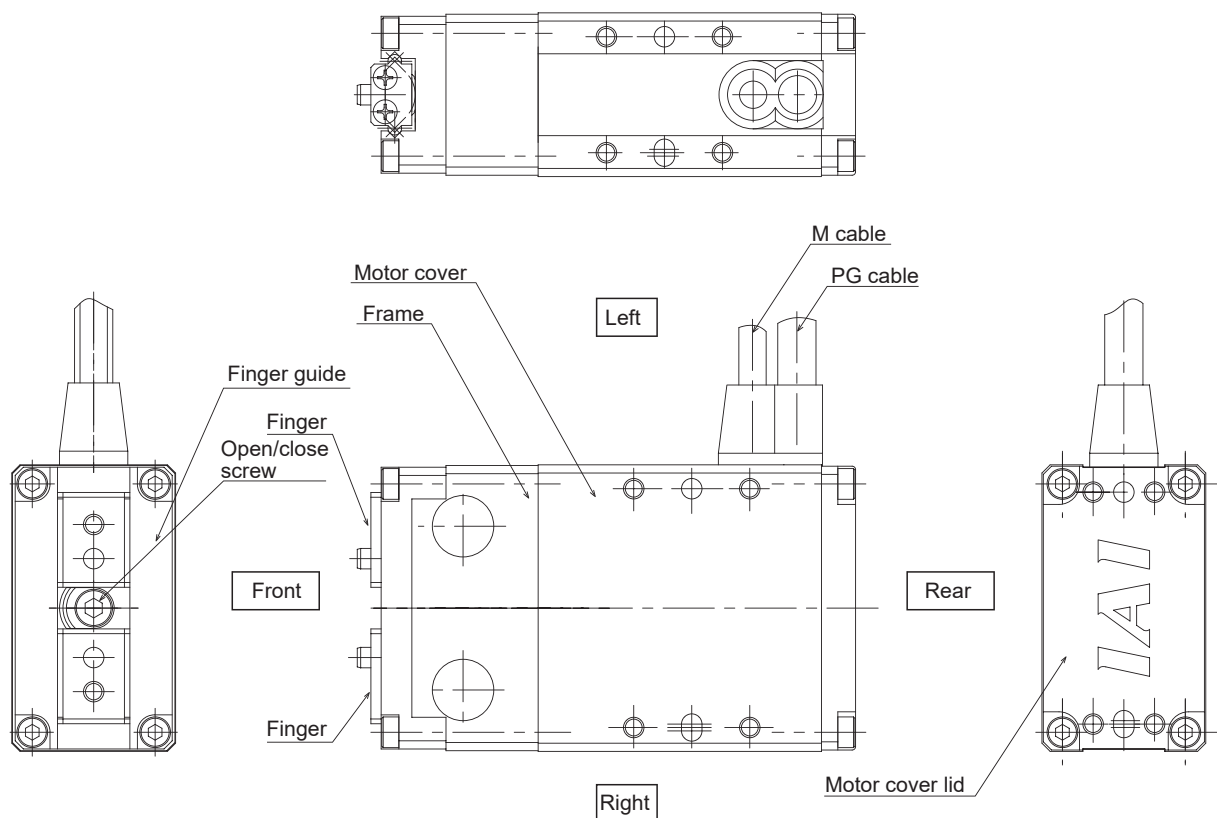
International Standards Compliances

This actuator complies with the following overseas standard.
Refer to Overseas Standard Compliance Manual (ME0287) for more detailed information.

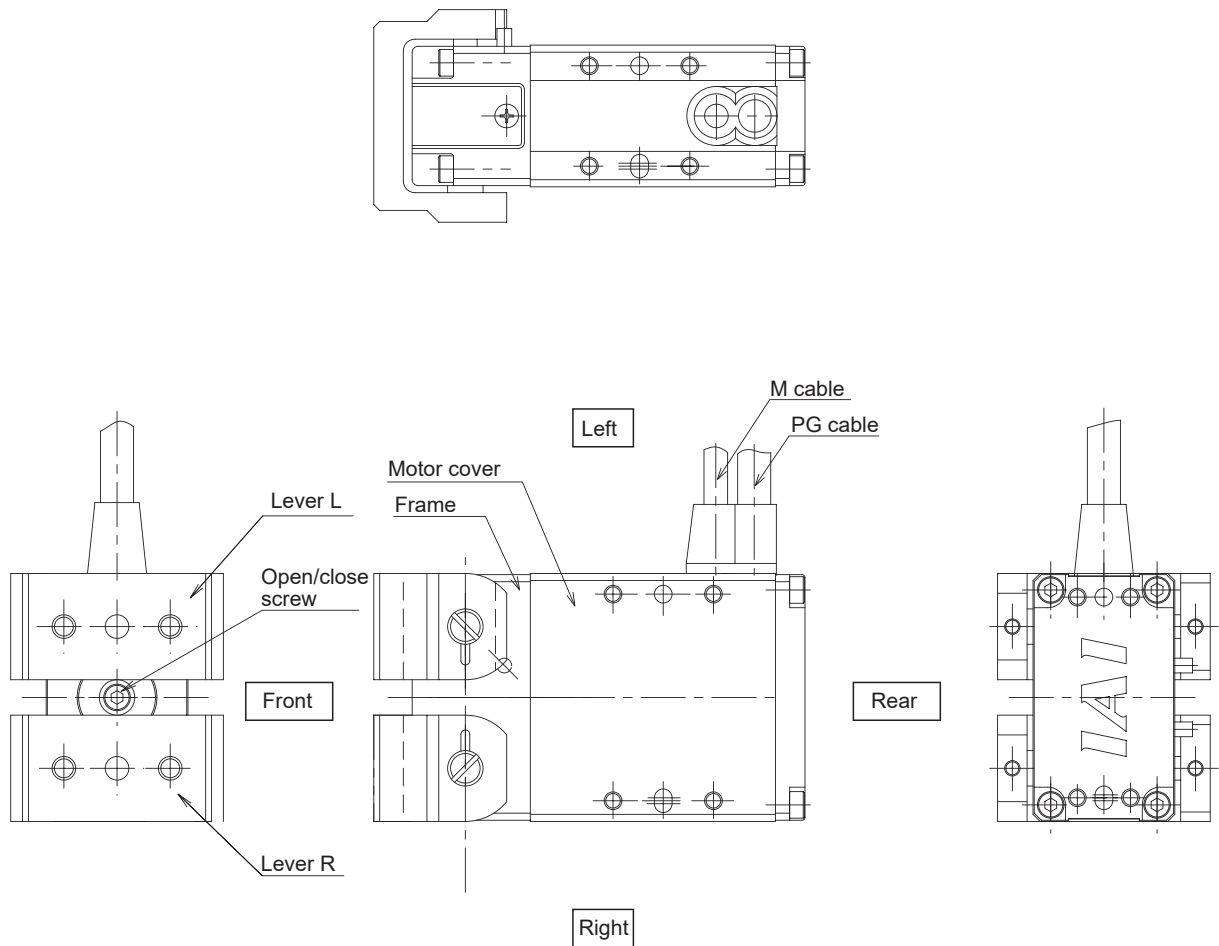
RoHS3 Directive	CE Marking
☐	☐

Names of the Parts

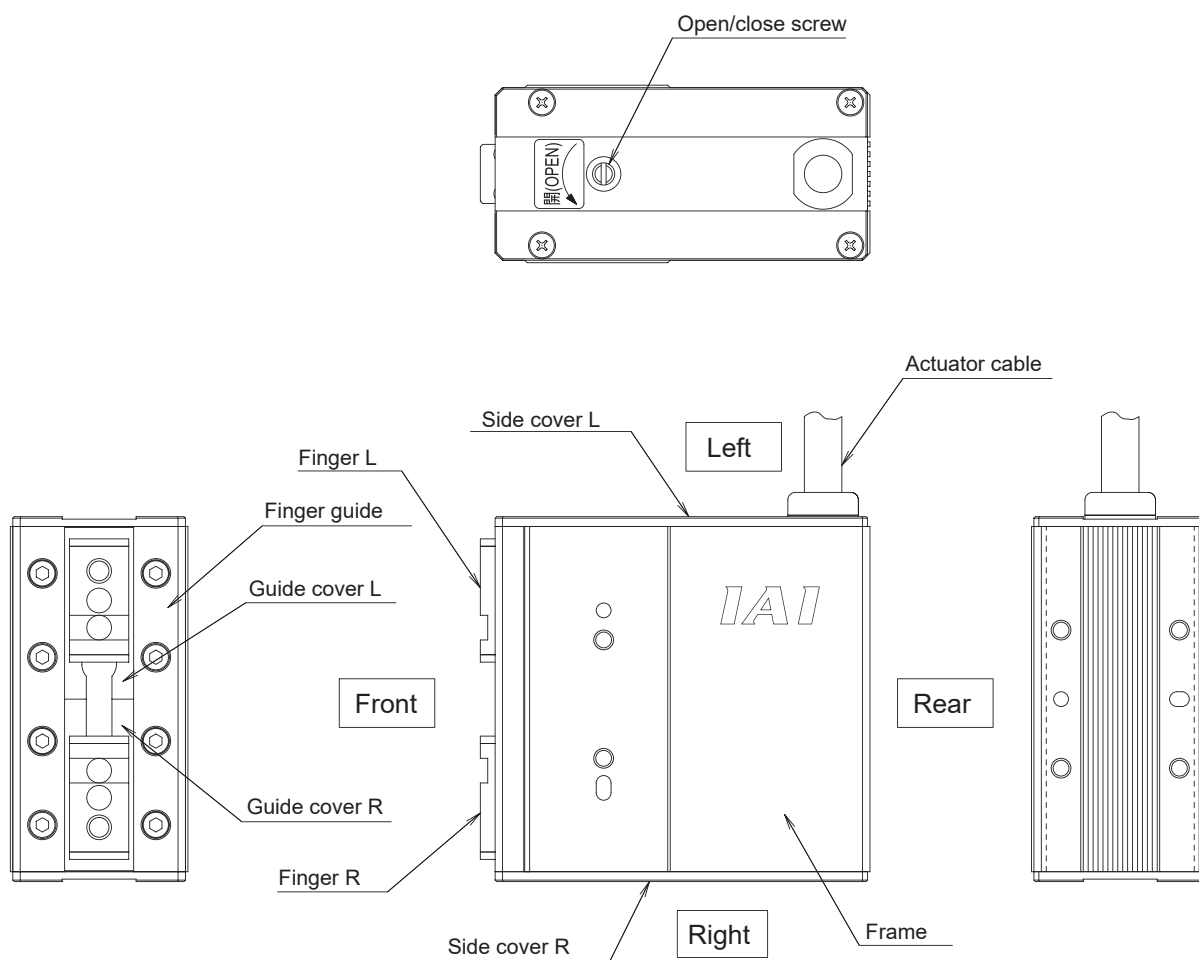
1. Small Slim Two-finger Slide Type: GRSS



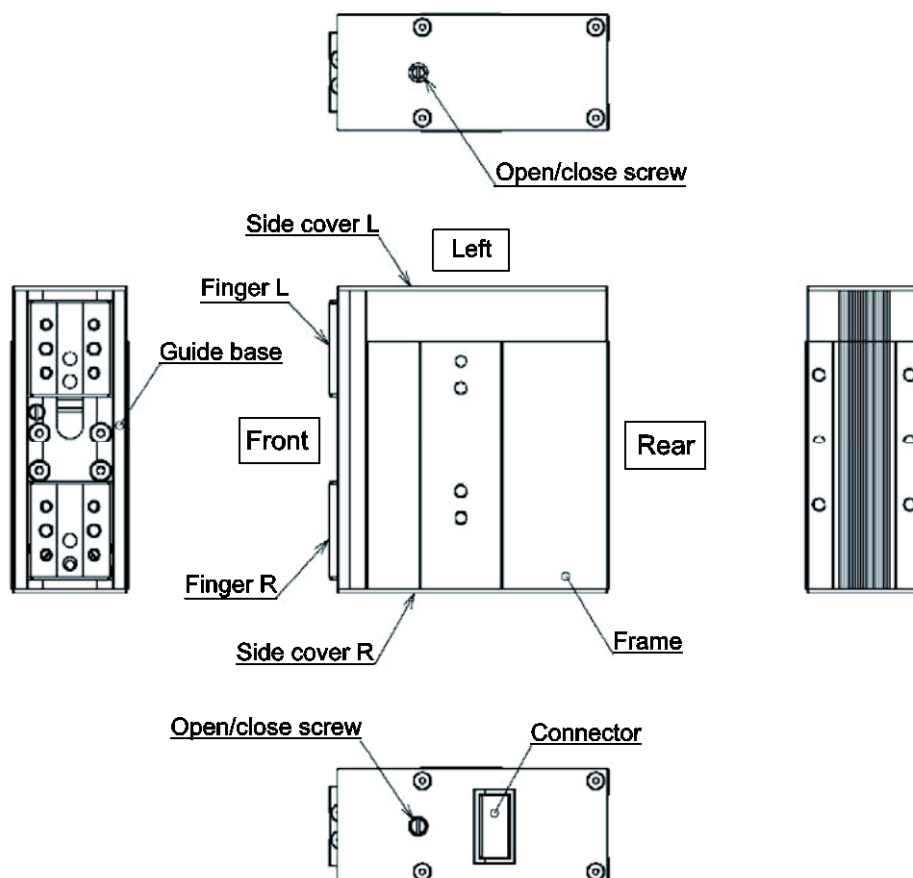
2. Small Slim Two-finger Slide Type: GRLS



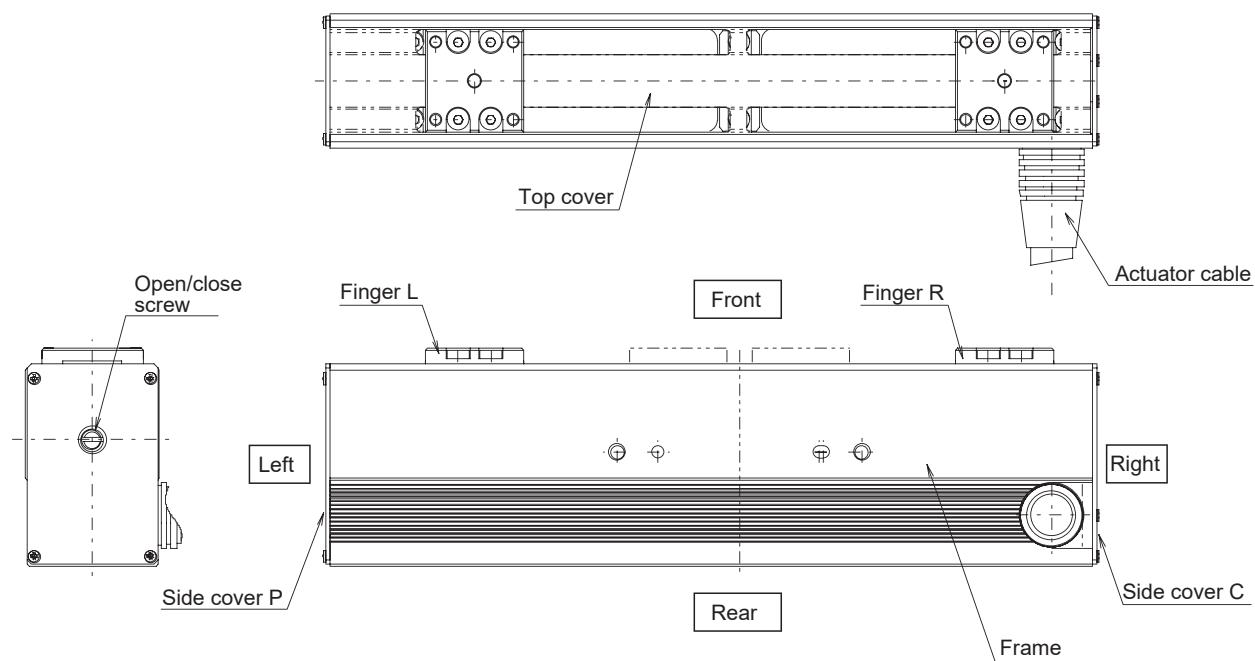
3. Small and Medium Two-finger Type: GRS/GRM



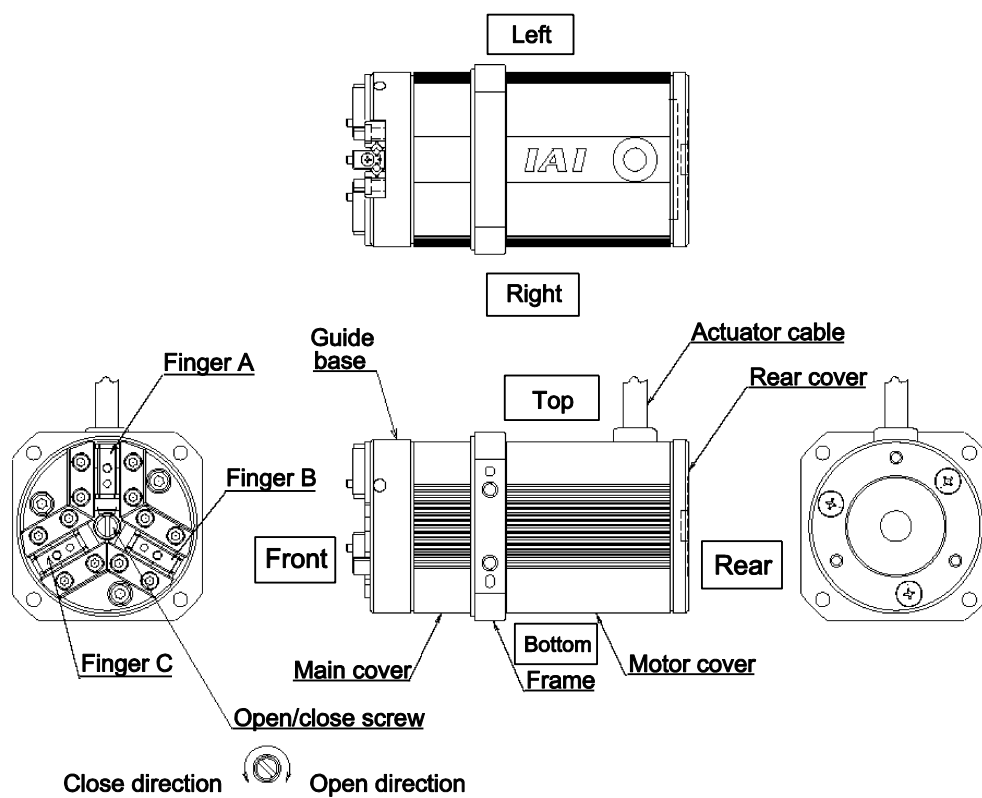
4. Two-finger Type with High Gripping Force: GRHM/GRHB



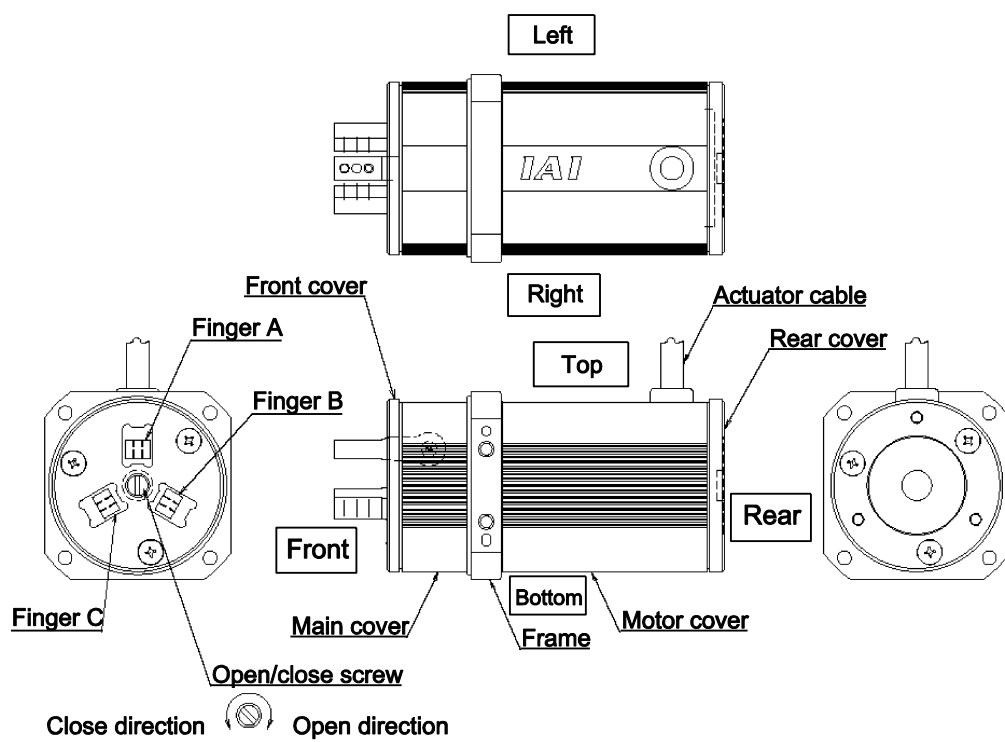
5. Two-finger Long-stroke Type: GRST



6. Three-finger Slide Type: GR3SS/GR3SM



7. Three-finger Lever Type: GR3LS/GR3LM



1. Specifications Check

1.1 Checking the Product

The standard configuration of this product is comprised of the following parts.
See the component list for the details of the enclosed components. If you find any fault or missing parts, contact your local IAI distributor.

1.1.1 Parts

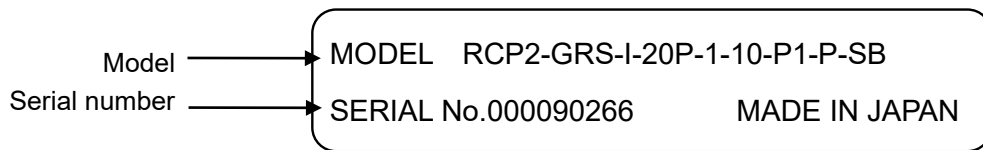
No.	Name	Model number	Quantity	Remarks
1	Actuator	Refer to "How to Read the Model Nameplate" and "How to Read the Model Number."	1	
Accessories				
2	Safety Guide		1	

1.1.2 Instruction Manuals for the Controllers Related to this Product

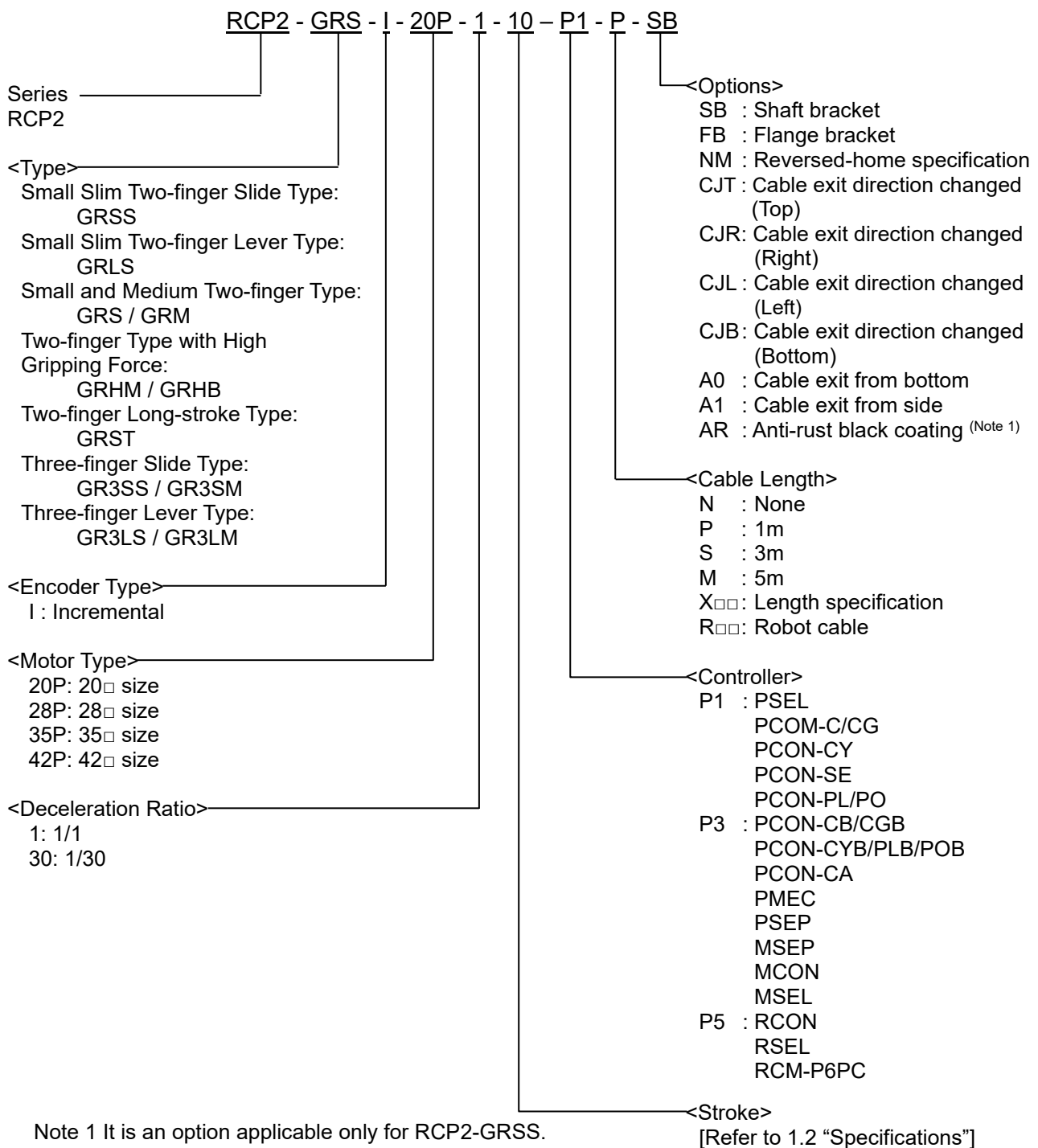
No.	Name	Control No.
1	Instruction Manual for PSEL Controller	ME0172
2	Instruction Manual for MSEL-PC/PG	ME0336
3	Instruction Manual for RSEL System	ME0392
4	Instruction Manual for PCON-CB/CGB Controller	ME0342
5	Instruction Manual for PCON- CYB/PLB/POB Controller	ME0353
6	Instruction Manual for PCON-CA/CFA Controller	ME0289
7	Instruction Manual for PCON-C/CG/CF Controller	ME0170
8	Instruction Manual for PCON-CY Controller	ME0156
9	Instruction Manual for PCON-SE Controller	ME0163
10	Instruction Manual for PCON-PL/PO Controller	ME0164
11	Instruction Manual for MSEP Controller	ME0299
12	Instruction Manual for ASEP/PSEP Controller	ME0216
13	Instruction Manual for MCON-C/CG Controller	ME0341
14	Instruction Manual for RCON System	ME0384
15	Instruction Manual for PC Software IA-101-X-MW/IA-101-TT-USB	ME0154
16	Instruction Manual for PC Software RCM-101MW/RCM-101-USB	ME0155
17	Instruction Manual for Teaching Pendant CON-T/TD/TG	ME0183
18	Instruction Manual for Teaching Pendant CON-T/TD/TGS	ME0178
19	Instruction Manual for Touch Panel Teaching Pendant CON-PTA/PDA/PGA	ME0295
20	Instruction Manual for Touch Panel Teaching Pendant CON-PT/PD/PG	ME0227
21	Instruction Manual for Touch Panel Teaching Pendant SEP-PT	ME0217
22	Instruction Manual for Simple Teaching Pendant RCM-E	ME0174
23	Instruction Manual for Data Setter RCM-P	ME0175
24	Instruction Manual for Touch Panel Display RCM-PM-01	ME0182

No.	Name	Control No.
25	Instruction Manual for Touch Panel Teaching TB-01/01D/01DR Applicable for Program Controller	ME0325
26	Instruction Manual for Touch Panel Teaching TB-01/01D/01DR Applicable for Position Controller	ME0324
27	Instruction Manual for Touch Panel Teaching Pendant TB-02/02D Applicable for Position Controller	ME0355
28	Instruction Manual for Touch Panel Teaching Pendant TB-02/02D Applicable for Program Controller	ME0356
29	Instruction Manual for Touch Panel Teaching Pendant TB-03 Applicable for Position Controller	ME0376
30	Instruction Manual for Touch Panel Teaching Pendant TB-03 Applicable for Program Controller	ME0377

1.1.3 How to Read the Model Nameplate



1.1.4 How to Read the Model Number



1.2 Specifications

1.2.1 Common

	Small Slim Two-finger Type		Small Two-finger Type	Medium Two-finger Type
	Slide type	Lever type	Slide type	
	GRSS	GRLS	GRS	GRM
Open/Close Stroke	8 mm (4 mm per side)	180 deg (90 deg per side)	10 mm (5 mm per side)	14 mm (7 mm per side)
Maximum Gripping Force	14 N	6.4 N	21 N	80 N
Maximum Open/Close Speed	78 mm/sec (Per side)	600 deg/sec (Per side)	33 mm/sec (Per side)	36 mm/sec (Per side)
Read	1.57 mm	12 mm	1 mm	1.1 mm
No. of Encoder Pulses	800	800	800	800
Stopping Repeatability	±0.01 mm	±0.01 deg	±0.01 mm	±0.01 mm
Backlash	0.2 mm max. on each side (Note 1)	1 deg max. on each side (Note 1)	0.15 mm max. on each side (Note 1)	0.15 mm max. on each side (Note 1)
Lost Motion	0.05 mm max. on each side	0.1 deg max. on each side	0.1 mm max. on each side	0.1 mm max. on each side
Allowable Load Moment (Note 2)	Ma: 0.5 N•m Mb: 0.5 N•m Mc: 1.5 N•m		Ma: 6.3 N•m Mb: 6.3 N•m Mc: 7.0 N•m	Ma: 6.3 N•m Mb: 6.3 N•m Mc: 8.3 N•m
Finger Drive Method	Worm gear + Spiral bevel gear + Spiral bevel rack	Worm gear + Spiral bevel gear	Timing belt + Trapezoid screw	
Finger Guide Structure	Linear guide (ball)	---	Cross roller guide	

Note 1 Constantly pushed toward the opening side by a spring.

Note 2 Moments generated in a standstill state

	Two-finger Type with High Gripping Force	
	Slide type	
	GRHM (Gear ratio 1:1)	GRHB (Gear ratio 1:1)
Open/Close Stroke	32 mm (16 mm per finger)	40 mm (20 mm per finger)
Maximum Gripping Force	125 N	200 N
Maximum Open/Close Speed	100 mm/s (on each side)	
Read	2 mm	
No. of Encoder Pulses	800	
Stopping Repeatability	±0.01 mm	
Backlash	0.2 mm	
Lost Motion	0.15 mm max.	
Allowable Load Moment	Ma: 11.7N•m Mb: 16.7N•m Mc: 46.5N•m	Ma: 15.7N•m Mb: 26.4N•m Mc: 59.8N•m
Finger Drive Method	Stepping motor + Timing belt + Trapezoidal lead screw	
Finger Guide Structure	Linear limited-rotation rolling ball bearing	

	Long-stroke Type											
	Slide type											
	GRST High-velocity Type (Gear ratio: 1)						GRST Standard type (Gear ratio: 2)					
Open/Close Stroke	40 mm (20 mm Per finger)	60 mm (30 mm Per finger)	80 mm (40 mm Per finger)	100 mm (50 mm Per finger)	120 mm (60 mm Per finger)	150 mm (75 mm Per finger)	40 mm (20 mm Per finger)	60 mm (30 mm Per finger)	80 mm (40 mm Per finger)	100 mm (50 mm Per finger)	120 mm (60 mm Per finger)	150 mm (75 mm Per finger)
Maximum Gripping Force	20 N						40 N					
Maximum Open/Close Speed	75 mm/s						34 mm/s					
Read	2.27 mm						1.05 mm					
No. of Encoder Pulses	800											
Stopping Repeatability	±0.01 mm											
Backlash	0.2 mm max. on each side											
Lost Motion	Ma: 2.93 N•m Mb: 2.93 N•m Mc: 5.0 N•m											
Allowable Load Moment	Stepping motor + Timing belt + Worm/rack gears											
Finger Drive Method	Linear guide (ball)											

	Three-finger Type			
	Slide type		Lever type	
	GR3SS	GR3SM	GR3LS	GR3LM
Open/Close Stroke	5 mm (per finger)	7 mm (per finger)	19 deg (-14 to +5)	19 deg (-14 to +5)
Maximum Gripping Force	22 N	102 N	18 N	51 N
Maximum Open/Close Speed	400 mm/s (Per side)	50 mm/s (Per side)	200 deg/s (Per side)	200 deg/s (Per side)
Read	2.5 mm	3 mm	12 mm	12 mm
No. of Encoder Pulses	800	800	800	800
Stopping Repeatability	±0.01 mm	±0.01 mm	±0.01 deg	±0.01 deg
Backlash	0.3 mm max. on each side (Note 1)	0.3 mm max. on each side (Note 1)	1.0 deg max. on each side (Note 1)	1.0 deg max. on each side (Note 1)
Lost Motion	0.1 mm max. on each side	0.1 mm max. on each side	0.15 deg max. on each side	0.15 deg max. on each side
Allowable Load Moment (Note 2)	Ma: 3.8 N•m Mb: 3.8 N•m Mc: 3.0 N•m	Ma: 6.3 N•m Mb: 6.3 N•m Mc: 5.7 N•m	---	---
Finger Drive Method	Worm gear + Worm wheel gear			
Finger Guide Structure	Cross roller guide			

Note 1 Constantly pushed toward the opening side by a spring.

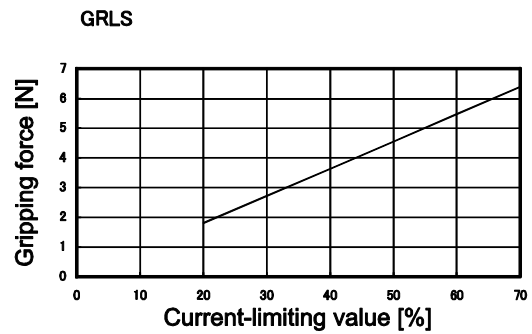
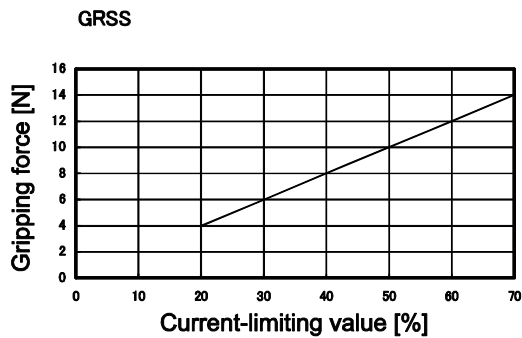
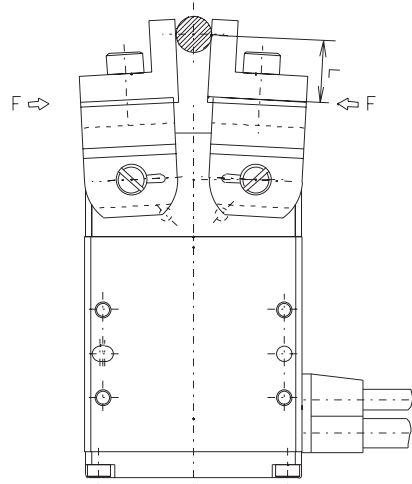
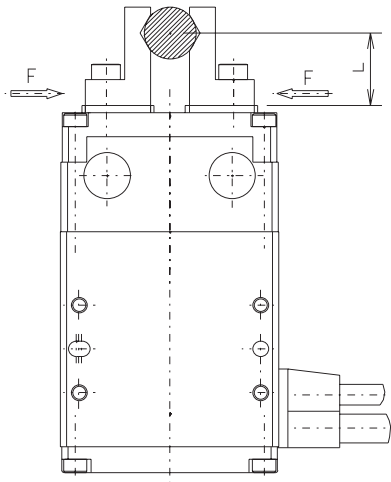
Note 2 Moments generated in a standstill state

1.2.2 Relation between the Current Limit Value and the Grip Force

The gripping force is freely adjustable via push-motion setting within a range of 20 to 70% of the currentlimiting value of the controller.

* The gripping force shown in the graphs below indicates a sum of gripping forces of both fingers.

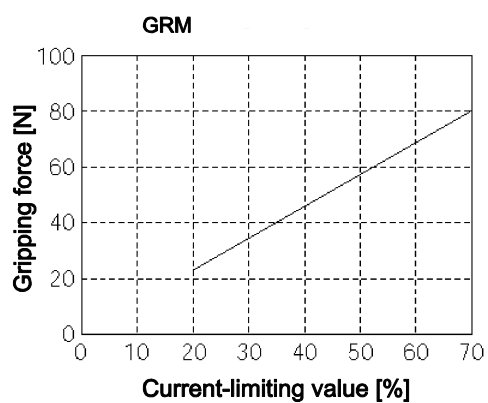
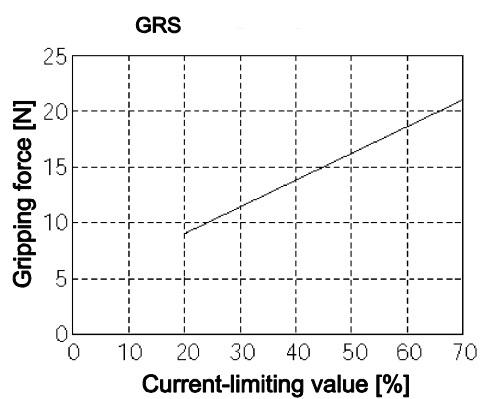
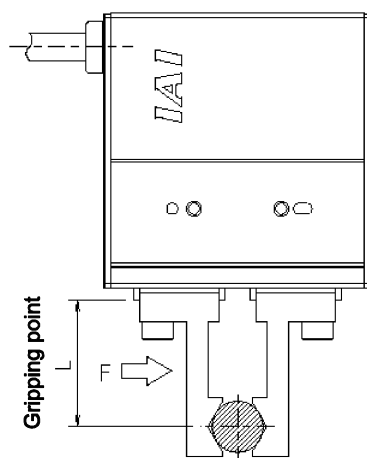
- Small Slim Two-finger Slide Type (GRSS)
- Small Slim Two-finger Lever Type (GRLS)



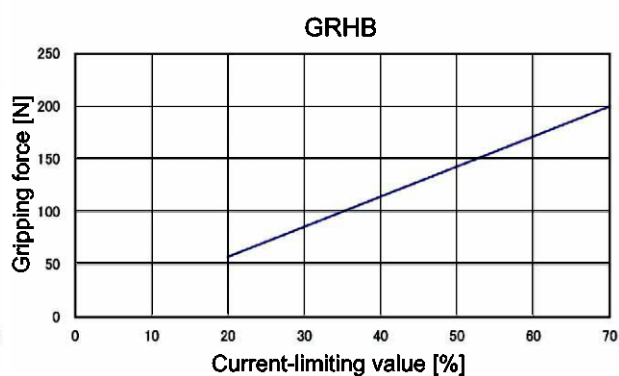
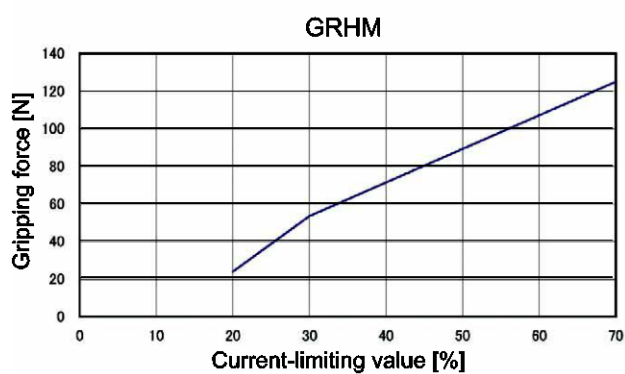
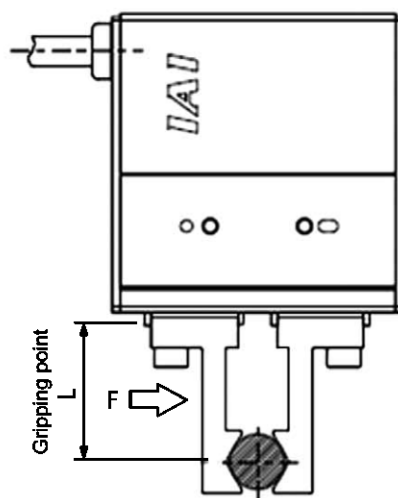
* The gripping force of the GRLS is measured on the top face of the lever. The actual gripping force drops in inverse proportion to the distance from the opening/closing fulcrum. Calculate the effective gripping force using the formula below.

$$\text{Effective gripping force (GRLS)} = F \times 15.5 / (L + 15.5)$$

- Small and Medium Two-finger Type (GRS/GRM)

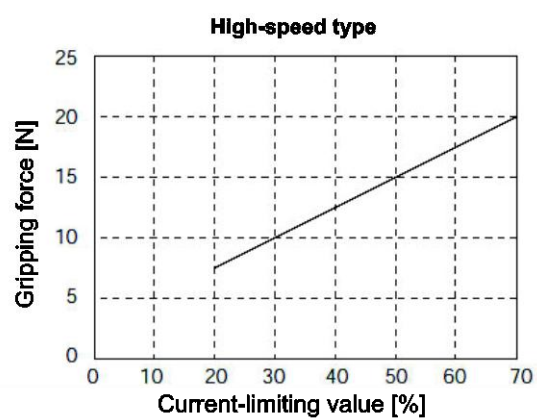
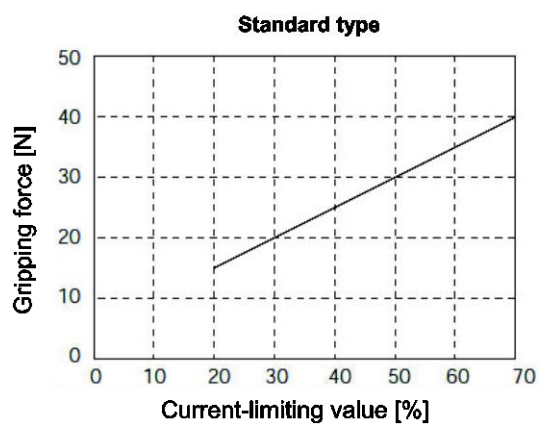
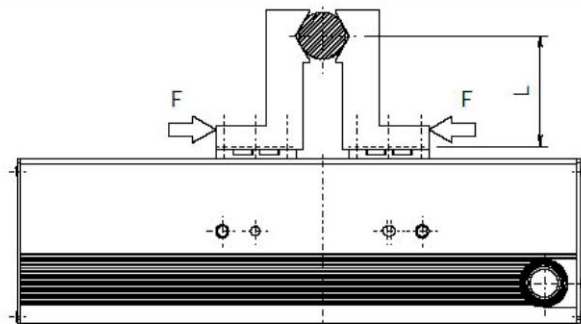


- Two-finger Type with High Gripping Force (GRHM/GRHB)

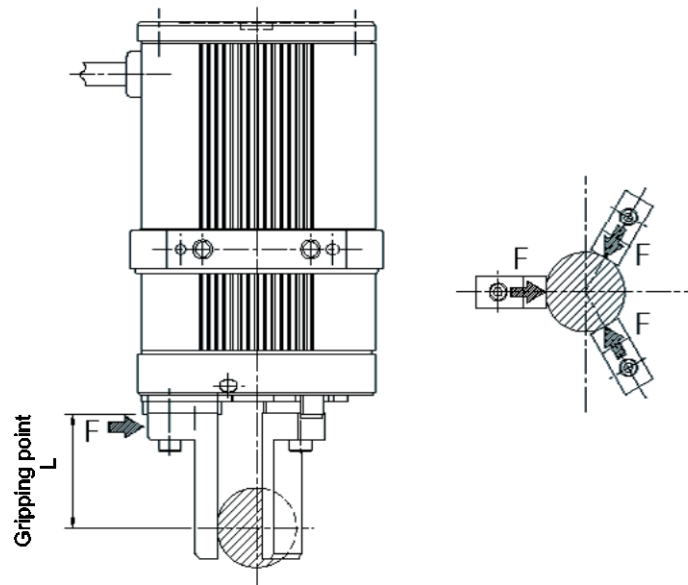


- Two-finger Long-stroke Type (GRST)

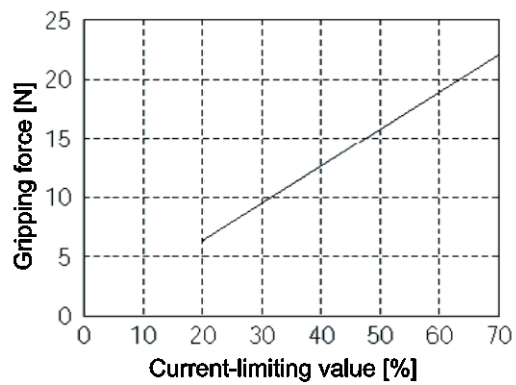
* The gripping force shown in the graphs below indicates a sum of gripping forces of both fingers.



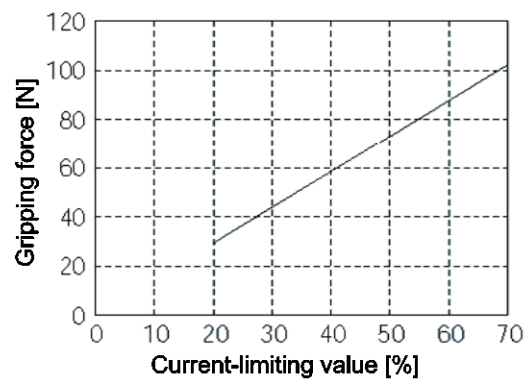
- Three-finger Slide Type (GR3SS/GR3SM)



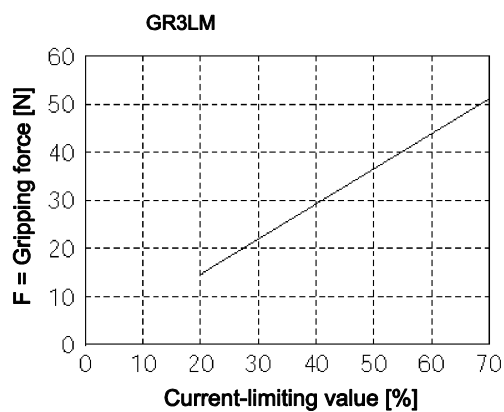
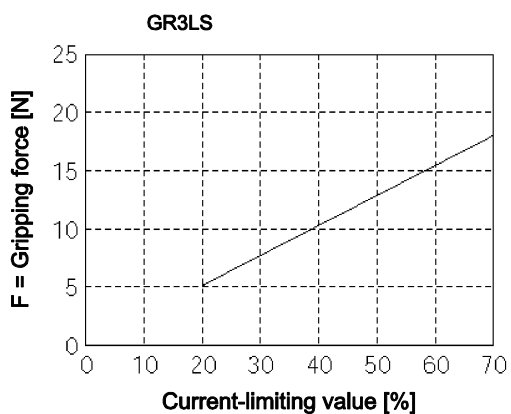
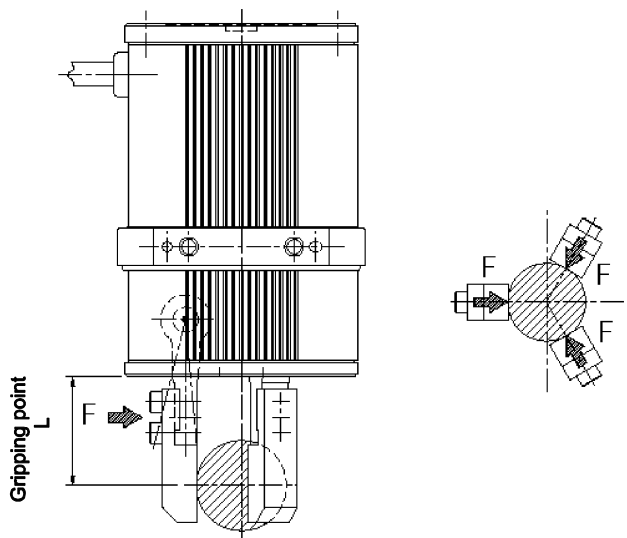
GR3SS



GR3SM



- Three-finger Lever Type (GR3LS/GR3LM)



* The above values are calculated at a gripping point of 10 mm. The actual gripping force decreases in inverse proportion to the distance from the open/close fulcrum. Calculate the actual gripping force using the formula below:

$$\text{Effective gripping force (GR3LS)} = F \times 24 / (L + 14)$$

$$\text{Effective gripping force (GR3LM)} = F \times 28.5 / (L + 18.5)$$

Caution:

(1) It is a reference when pressing performed with speed 5mm/s for Slide Type, and with 20deg/s for Lever Type.

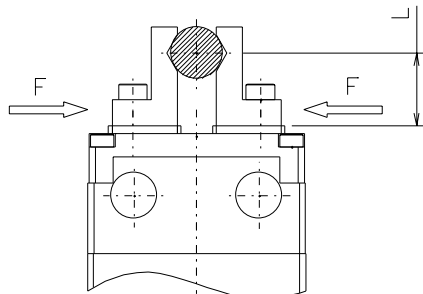
(2) The grip force is the values under the conditions stated below.

• Two-finger Type

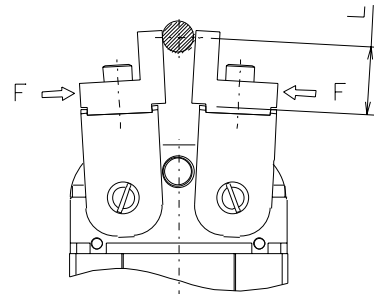
Slide Type: Total value of grip force of both slides at the top surface of the slides (gripping point = 0mm, overhang = 0mm)

Lever Type: Total value of grip force of both slides at the top surface of the Levers (gripping point = 0mm, overhang = 0mm)

The actual grip force drops in inverse proportion to the distance from the fulcrum of open and close.



Slide Type



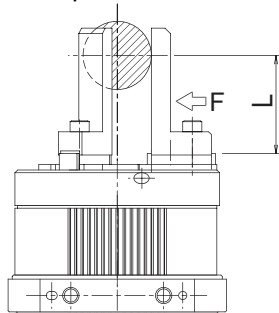
Lever Type

• Three-finger Type

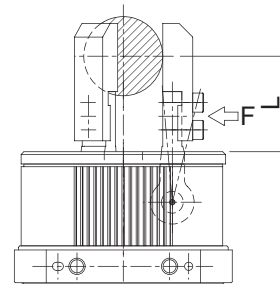
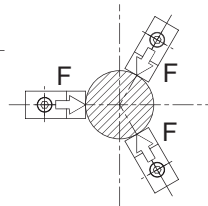
Slide Type: Total value of grip force of all slides at the top surface of the slides (gripping point = 10mm, overhang = 0mm)

Lever Type: Total value of grip force of all slides at the top surface of the Levers (gripping point = 10mm, overhang = 0mm)

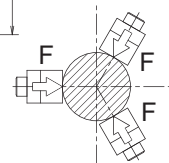
The actual grip force drops in inverse proportion to the distance from the fulcrum of open and close.



Slide Type



Lever Type



(3) There is a little variance in the actual grip force. The variance of the grip force becomes large when the current limit value is low.

(4) Use the product within the range in the graph for the current limit value. Pressing force will not be stable if used below 20%. There is even a case that it would not operate. The product cannot be used above 70%. Doing so may cause degradation in the motor coil insulation by heat radiation, which results in shortening the product life.

(5) For the CON system controllers such as PCON, when the approach speed (setting in the position table) to the pressing start position is 5mm/s or less, pressing is performed at the approach speed. In such a case also the pressing force will be unstable. In such cases, check in advance that the actuator can be used with no problem before omit using.

For the SEL system controllers such as MSEL, pressing operation is performed at the speed set in PAPR Command regardless of the approach speed to the pressing start position.

1.2.3 Duty in Continuous Operation

Continuous operation is available with the duty 100%.

Duty is the rate of operation expressed in % that represents the time of the actuator being operated in 1 cycle of operation.

1.3 Operating Conditions

It is necessary to satisfy the conditions stated below to use the product. Conduct the following calculation to make sure it is satisfied.

1.3.1 Gripping Force

[1] Slide Types

Procedure 1 : Check for the necessary grip force and transportable work piece mass



Procedure 2 : Check for the vertical allowable load of the fingers and allowable moment

Procedure 1 : Check for the necessary grip force and transportable work piece mass

If a work piece is to be gripped on the fingers with the friction force created by the grip force, the formula to calculate the necessary grip force is as follows;

(1) In case of ordinary transportation

F : Grip Force [N].....Sum of pressing force on each finger

μ : Coefficient of static friction between finger attachment and work piece

m : Mass of work piece [kg]

g : Gravitational acceleration [= 9.8m/s²]

The condition to grip the work piece statically and that the work piece would not drop is;

$$F\mu > W$$

$$F > \frac{mg}{\mu}$$

The necessary grip force assuming the safety factor recommended for ordinary transportation is 2 should be;

$$F > \frac{mg}{\mu} \times 2 \text{ (safety factor)}$$

When coefficient of friction is $\mu 0.1$ to 0.2 ;

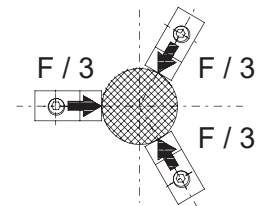
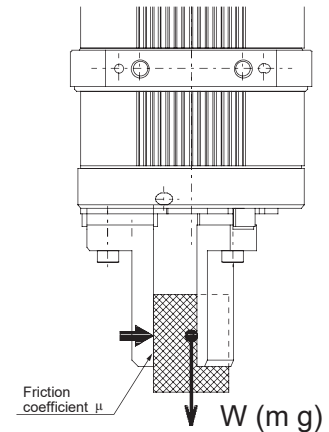
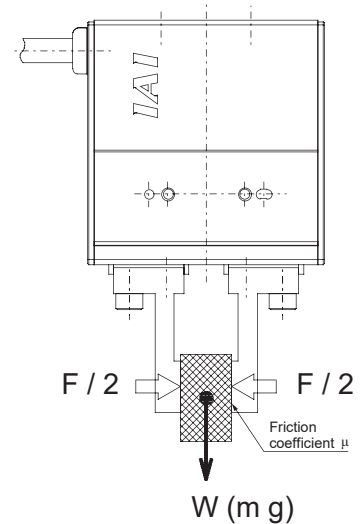
$$F > \frac{mg}{0.1 \text{ to } 0.2} \times 2 = (10 \text{ to } 20) \times mg$$

* The mass of a transportable work piece will get higher as the coefficient of static friction is higher. However it is necessary to that enables it to obtain a grip force of 10 to 20 times or more to ensure the safety.

For ordinary work piece transportation;

Necessary grip force $\Rightarrow$ 10 to 20 times or more of work piece mass

Transportable work piece mass $\Rightarrow$ 1/10 to 1/20 or less of grip force



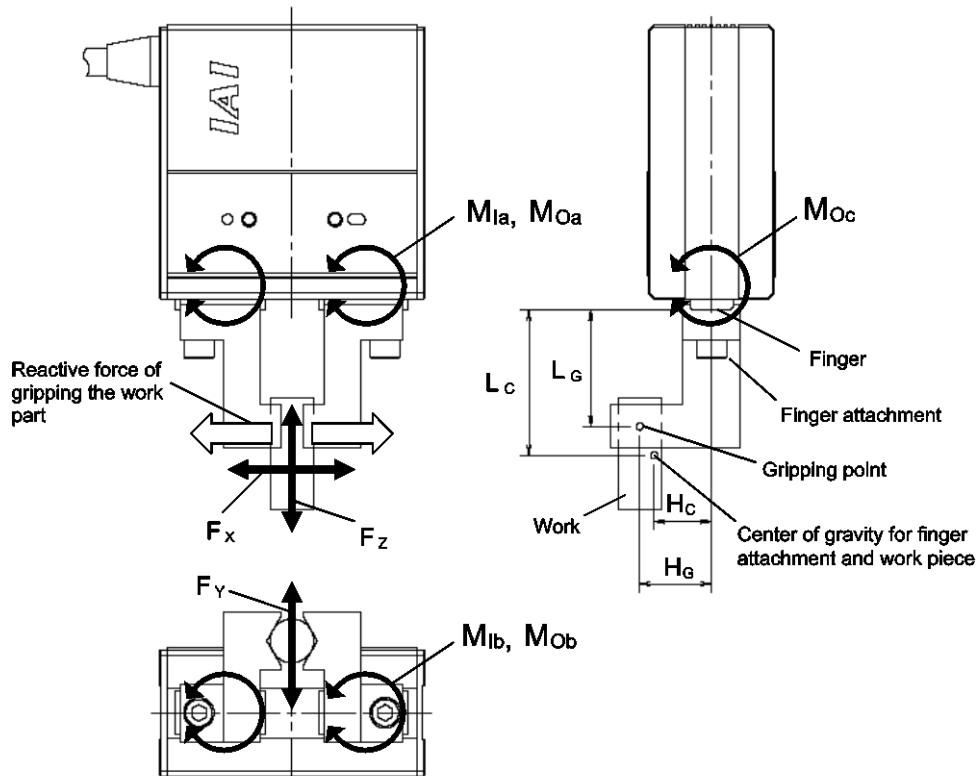
- (2) In case of high acceleration/deceleration speed or a big impact is applied to the work piece during transportation

High inertial force, in addition to the gravity, will be applied to the work piece. In such cases, consider an even higher safety factor if it is necessary.

When high acceleration/deceleration speed or a big impact is applied;
Necessary grip force $\Rightarrow$ 30 to 50 times or more of the work piece mass
Transportable work piece mass $\Rightarrow$ 1/30 to 1/50 or less of the grip force

Procedure 2 : Check for the vertical allowable load of the fingers and allowable moment
Check the vertical load and the moment applicable to the finger. Figure out F_z , M_a , M_b and M_c by referring to (1) to (3) described below, and it is necessary to select a suitable model considering not to exceed the allowable values.

Fig. 1 Load and the moment applicable to the finger



F_x : External force in X direction applied to work piece and finger [N]

F_y : External force in Y direction applied to work piece and finger [N]

F_z : External force in Z direction applied to work piece and finger [N]

L_g : Distance from finger attachment surface to gripping point (Gripping point) [mm] (Note 1)

L_c : Distance from center of fingers to gripping point (Overhang) [mm] (Note 1)

H_c : Distance from finger attachment surface to center of gravity for work piece and finger attachment [mm]

H_g : Distance from center of fingers to center of gravity for work piece and finger attachment [mm]

Note1 For L_g and H_g , have the values next page as the upper limit. Exceeding the allowable range may generate an excessive moment on the finger sliding mechanism, which may be a cause of a bad impact to the product life.

M_{la} : Moment in M_a direction generated on fingers due to grip force [N·m]

M_{lb} : Moment in M_b direction generated on fingers due to grip force [N·m]

M_{oa} : Moment in M_a direction generated on fingers due to external force [N·m]

M_{ob} : Moment in M_b direction generated on fingers due to external force [N·m]

M_{oc} : Moment in M_c direction generated on fingers due to external force [N·m]

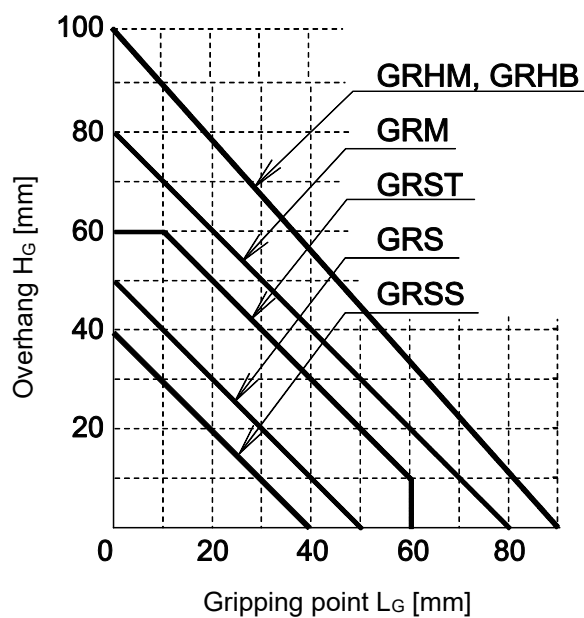
M_a : All moments in M_a direction generated on fingers [N·m]

M_b : All moments in M_b direction generated on fingers [N·m]

M_c : All moments in M_c direction generated on fingers [N·m]

◆ Two-finger Gripper

Fig. 2 Upper Limits of Gripping Point L_G and Overhang H_G of Two-finger Gripper



◆ Three-finger Gripper

Fig. 3 Upper Limit of Gripping Point L_G of Three-finger Gripper

GR3SS $\Rightarrow$ L50 mm or less
GR3SM $\Rightarrow$ L80 mm or less

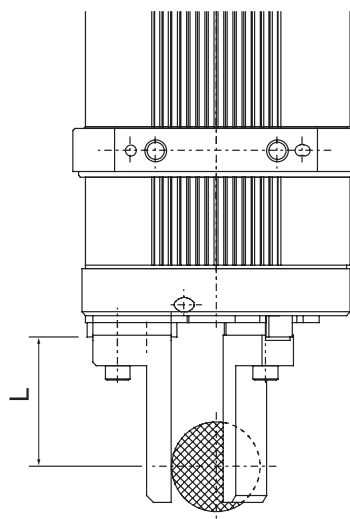


Table 1: Allowable Load and Allowable Moment on the Fingers (Note 1)

Model	Allowable Load in Vertical [N] F_{Zmax}	Max. Allowable Moment [N·m] (Note 2)		
		M_{amax}	M_{bmax}	M_{cmax}
GRSS	60	0.5	0.5	1.5
GRS	253	6.3	6.3	7.0
GRM	253	6.3	6.3	8.3
GRHM	390	11.7	16.7	46.5
GRHB	502	15.7	26.4	59.8
GRST	275	2.93	2.93	5.0
GR3SS	169	3.8	3.8	3.0
GR3SM	253	6.3	6.3	5.7

Note 1 The graphs show the values for allowable load and allowable moment in static on one finger.

Note 2 The values for the allowable moment are those when the load is applied in one direction only.

- The values become one half when the load is applied from in two directions.
- The values become 1/3 when the load is applied from in three directions.

(1) Moment generated on fingers due to gripping force

1) Moment in M_a direction [M_{ia}]

- Two-finger type $M_{ia} = L_G \frac{1.5F_G}{2} \times 10^{-3}$
- Three-finger type $M_{ia} = L_G \frac{1.5F_G}{3} \times 10^{-3}$

F_G : Grip force of gripper [N]

2) Moment in M_b direction [M_{ib}]

- Two-finger type $M_{ib} = H_G \frac{1.5F_G}{2} \times 10^{-3}$
- Three-finger type: Need not be calculated.

F_G : Grip force of gripper [N]

Refer to "1.2.2 Relation between Current Limit Value and Grip Force" for gripping force F_G .

As the gripping force is a reference value, it is multiplied by 1.5 for the safety margin in the moment calculation.

(2) Moment generated on the fingers due to an external force

External force as well as gripping force will be applied to the work piece and the finger attachment in the movements such as moving straight or turning in the condition of the gripper being attached on a Cartesian Robot, Articulated Robot or other actuators.
Have the following calculation.

- ◆ External force applied on the work piece and finger attachment [F_x , F_y , F_z]
Figure out the following types of external forces in three directions, X, Y and Z, applied on the work piece and finger attachment considering the condition of the gripper use, and sum up all the values to determine F_x , F_y and F_z .
 - a) Weight of the work piece and finger attachment
 $F = mg$ m : mass of the work piece and finger attachment [kg],
 g : gravitational acceleration [=9.8m/s²]
 - b) Inertial force in the gripper moving straight
 $F = ma$ a : Acceleration/deceleration during transportation [m/s²]
 - c) Centrifugal force in gripper turning
 $F = mr \omega^2$ r : Radius of turning [m], ω : Angular velocity [deg/s]

Confirm that F_z is below the allowable load vertical direction, F_{zmax} in Table 1.

- ◆ Moment generated on the fingers due to an external force
Figure out the moment in each direction due to external forces F_x , F_y and F_z calculated above.
 - 1) Moment in M_a direction [M_{oa}]
 $M_{oa} = L_c F_x \times 10^{-3}$
 - 2) Moment in M_b direction [M_{ob}]
 $M_{ob} = H_c F_x \times 10^{-3}$
 - 3) Moment in M_c direction [M_{oc}]
 $M_{oc} = L_c F_y \times 10^{-3} + H_c F_z \times 10^{-3}$

(3) All moments in each direction generated to the fingers

- Two-finger type
 $M_a = M_{la} + M_{oa}, \quad M_b = M_{lb} + M_{ob}, \quad M_c = M_{oc}$
- Three-finger type
 $M_a = M_{la} + M_{oa}, \quad M_b = M_{ob}, \quad M_c = M_{oc}$

Confirm that the value figured out in the calculation above is below the allowable moment stated in Table 1.

(Note) Select finger attachments that are as small and light as possible within the allowable ranges. If the fingers are long and large or heavy, moments may generate due to impact upon gripping of the work part and consequently the actuator performance may drop or guide may be negatively affected.

[2] Lever Types

Procedure 1 : Check for the necessary gripping force and transportable work piece mass

Procedure 2 : Check for the moment of inertia on the finger attachment

Procedure 3 : Check for the external force applied on finger

Procedure 1 : Check for the necessary gripping force and the transportable work piece mass
In the same manner as Procedure 1 for Slide types, figure out the necessary grip force and confirm that the requirement is satisfied.
Figure out the effective grip force on the gripping point by referring to "1.2.2 Relation between the Current Limit Value and the Gripping Force".

For ordinary work piece transportation;

Necessary gripping force $\Rightarrow$ 10 to 20 times or more of the work piece mass

Transportable work piece mass $\Rightarrow$ 1/10 to 1/20 or less of the gripping force

When high acceleration/deceleration speed or a big impact is applied;

Necessary gripping force $\Rightarrow$ 30 to 50 times or more of the work piece mass

Transportable work piece mass $\Rightarrow$ 1/30 to 1/50 or less of the gripping

Procedure 2 : Check for the moment of inertia on the finger attachment

Make sure all the moments of inertia for the Z-axis (fulcrum) turning on the finger attachment are within the allowable range. Figure out by dividing to several equations considering the structure and profile of the finger attachment. For reference, shown below is an example how to figure out by dividing to two equations.

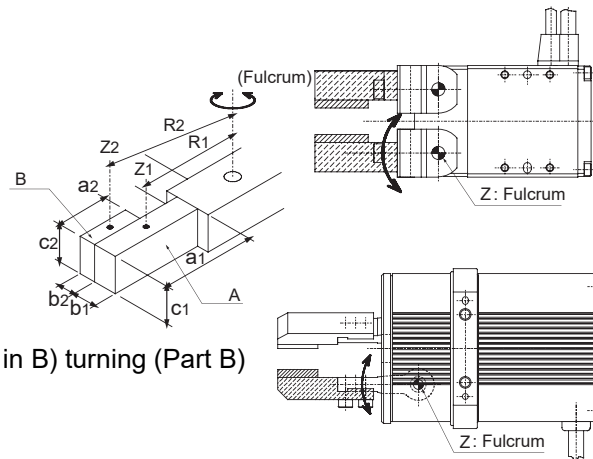
(1) Moment of inertia for Z1-axis (center of gravity in A) turning (Part A)

m_1 : Mass of A [kg]

a, b, c : Dimensions of A [mm]

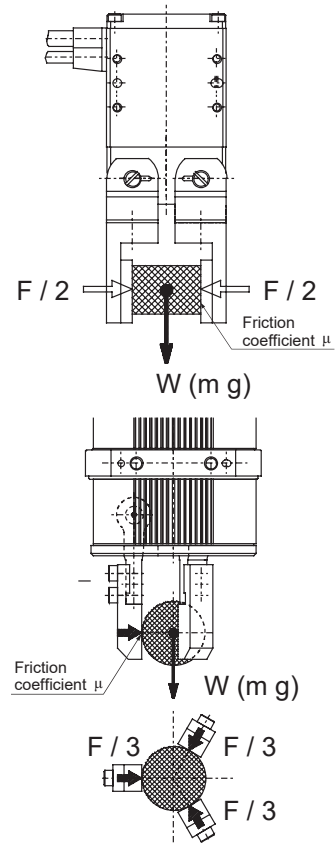
m_1 [kg] = $a_1 \times b_1 \times c_1 \times \text{Specific gravity} \times 10^{-6}$

$$I_{Z1} [\text{kg} \cdot \text{m}^2] = \frac{m_1 (a_1^2 + b_1^2)}{12} \times 10^{-6}$$



(2) Moment of inertia for Z2-axis (center of gravity in B) turning (Part B)

$$I_{Z2} [\text{kg} \cdot \text{m}^2] = \frac{m_2 (a_2^2 + b_2^2)}{12} \times 10^{-6}$$



- (3) All Moments of inertia for Z-axis (fulcrum) Turning
 R_1 : Distance from center of gravity of A to the finger open/close fulcrum [mm]
 R_2 : Distance from center of gravity of B to the finger open/close fulcrum [mm]

$$I [\text{kg}\cdot\text{m}^2] = (I_{z1} + m_1 R_1^2 \times 10^{-6}) + (I_{z2} + m_2 R_2^2 \times 10^{-6})$$

Confirm that the value figured out in the calculation above is below the allowable moment of inertia stated in Table 2.

Table 2: Allowable Moment of Inertia on the Finger (Note 1)

Model	Allowable Moment of Inertia $I_{\text{max}} [\text{kg}\cdot\text{m}^2]$	Mass (Reference) Max [kg]
GRLS	1.5×10^{-4}	0.05
GR3LS	3.0×10^{-4}	0.1
GR3LM	9.0×10^{-4}	0.2

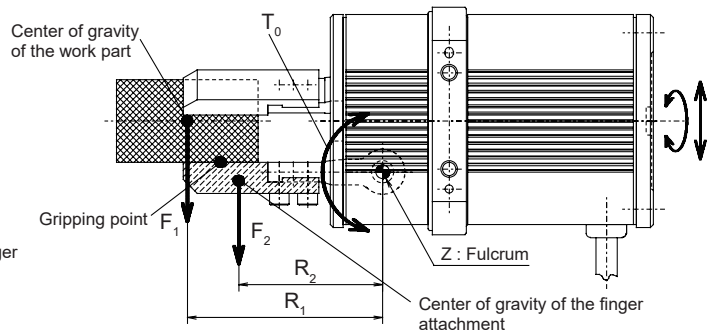
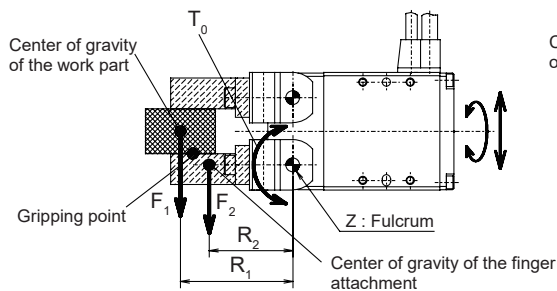
(Note 1) The table shows the values for allowable moment of inertia, allowable load torque and allowable thrust load for the static condition on one finger.

Procedure 3 : Check for the external force applied on the finger

External force as well as grip force will be applied to the work piece and the finger attachment in the movements such as moving straight or turning in the condition of the gripper being attached on a Cartesian Robot, Articulated Robot or other actuators.

(1) Allowable Load Torque

Use the product in a condition that the load torque applied to the fingers is below the maximum allowable load torque.



m_1 : Mass of the work piece [kg]

m_2 : Mass of the finger attachment [kg]

R_1 : Distance from the center of gravity for the work piece to the finger open/close fulcrum [mm]

R_2 : Distance from the center of gravity for the finger attachment to the finger open/close fulcrum [mm]

F_1 : External force applied on the work piece [N]

F_2 : External force applied on the finger attachment [N]

T_0 : Torque generated on the fingers due to an external force [N·m]

◆ External force applied on the work piece and the finger attachment

Figure out the following types of external forces applied on the work piece and finger attachment considering the condition of the gripper use, and sum up all the values.

a) Weight of the work piece and finger attachment

$$F = mg \quad m : \text{mass of the work piece and finger attachment [kg],} \\ g : \text{gravitational acceleration [=9.8m/s}^2]$$

b) Inertial force in gripper moving straight

$$F = ma \quad a : \text{Acceleration/deceleration during transportation [m/s}^2]$$

c) Centrifugal force in gripper turning

$$F = mr \omega^2 \quad r : \text{Radius of turning [m], } \omega : \text{Angular velocity [deg/s]}$$

Total External Force

$$F_1 = m_1 g + m_1 a + m_1 r \omega^2 \quad \dots \text{External force applied on the work piece}$$

$$F_2 = m_2 g + m_2 a + m_2 r \omega^2 \quad \dots \text{External force applied on the finger attachment}$$

- ◆ Torque generated on the fingers due to an external force

$$T_0 = F_1 R_1 \times 10^{-3} + F_2 R_2 \times 10^{-3}$$

Confirm that the value figured out with the formula above is below the maximum allowable load torque stated in Table 3.

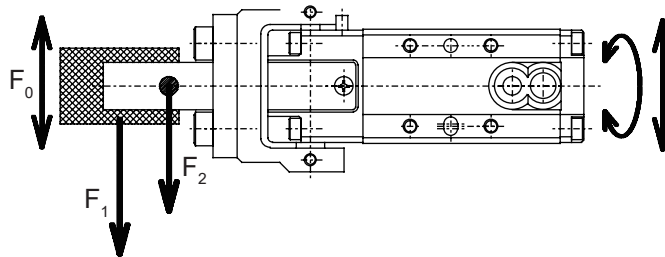
Table 3: Allowable Load Torque on the Finger (Note 1)

Model	Max. Allowable Load Torque T_{max} [N·m]
GRLS	0.05
GR3LS	0.1
GR3LM	0.3

Note 1 The table shows the values for allowable moment of inertia, allowable load torque and allowable thrust load for the static condition on one finger.

(2) Allowable Thrust Load

Use the product in a condition that the load torque applied to the fingers is below the maximum allowable load torque.



- m_1 : Mass of the work piece [kg]
- m_2 : Mass of the finger attachment [kg]
- F_1 : External force applied on the work piece [N]
- F_2 : External force applied on the finger attachment [N]
- F_0 : Load generated on the finger attachment [N]

Table 4: Allowable Thrust Load on Finger (Note 1)

Model	Allowable Thrust Load F_{max} [N]
GRLS	15
GR3LS	-
GR3LM	-

Note 1 The table shows the values for allowable moment of inertia, allowable load torque and allowable thrust load in static on one finger.

- ◆ External force applied on the work piece and the finger attachment
Figure out the following types of external forces applied on the work piece and the finger attachment considering the condition of the gripper use, and sum up all the values.

a) Weight of the work piece and the finger attachment

$$F = mg \quad m : \text{mass of the work piece and the finger attachment [kg]}, \\ g : \text{gravitational acceleration [=9.8m/s}^2]$$

b) Inertial force in the gripper moving straight

$$F = ma \quad a : \text{Acceleration/deceleration during transportation [m/s}^2]$$

c) Centrifugal force in the gripper turning

$$F = mr \omega^2 \quad r : \text{Radius of turning [m]}, \omega : \text{Angular velocity [deg/s]}$$

Total External Force

$$F_1 = m_1 g + m_1 a + m_1 r \omega^2 \quad \dots \text{External force applied on the work piece}$$

$$F_2 = m_2 g + m_2 a + m_2 r \omega^2 \quad \dots \text{External force applied on the finger attachment}$$

- ◆ Load generated on the Finger due to an External Force

$$F_0 = F_1 + F_2$$

Confirm that the value figured out with the formula above is below the allowable thrust load stated in Table 4.

(Note) Attempt to have the finger attachment minimized in size and weight even if it is in the allowable range. If the fingers are long and big in size and heavy in mass, the moment caused by an impact at gripping may cause a performance drop or give a bad impact to the structural area.

1.4 Option

1.4.1 Reversed-home Specification (Model: NM)

In standard, the direction described in “4.1 Operation of Finger Part in 4. Operation” is the home-return direction. It can be on the opposite side in case the home position is set on the other side due to such reasons as layout of equipment.

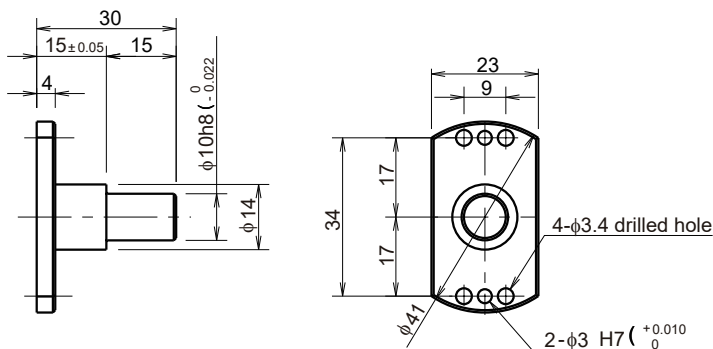
(Note) The home position is adjusted at the factory before shipment. If you wish to change the home after the delivery of your actuator, you must return the actuator to IAI for adjustment.

1.4.2 Shaft Bracket (Model: SB)

It is a fixing bracket to attach the gripper body.

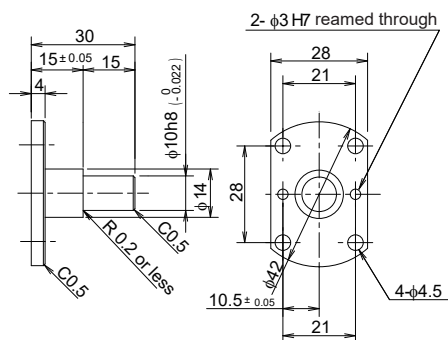
For GRSS/GRLS

Model code of single product : RCP2-SB-GRSS



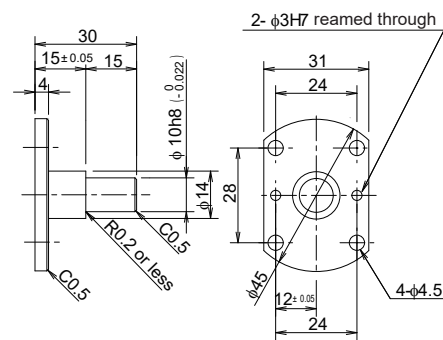
For GRS

Model code of single product : RCP2-SB-GRS



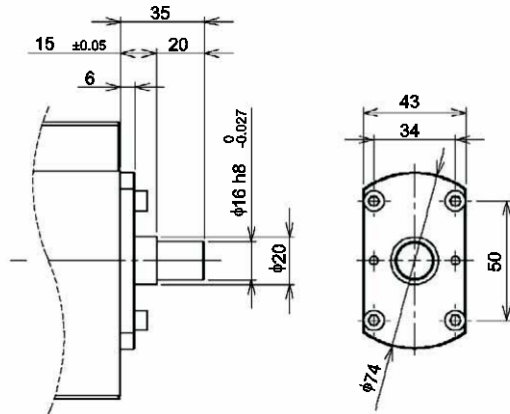
For GRM

Model code of single product : RCP2-SB-GRM



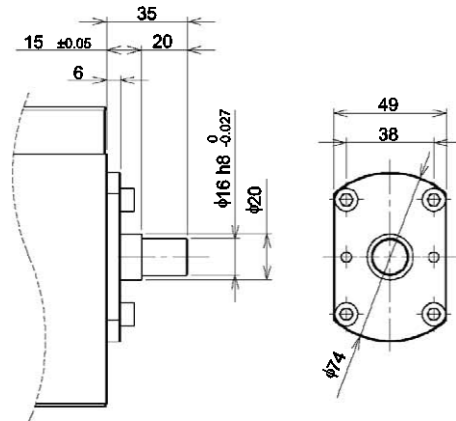
For GRHM

Model code of single product : RCP2-SB-GRHM



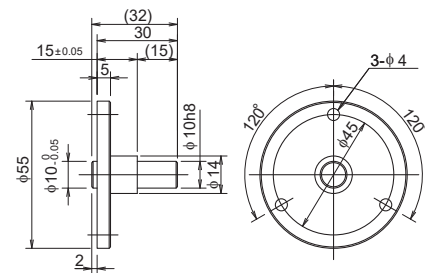
For GRHB

Model code of single product : RCP2-SB-GRHB



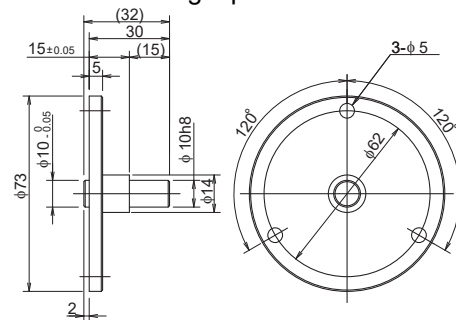
For GR3SS/GR3LS

Model code of single product : RCP2-SB-GR3S



For GR3SM/GR3LM

Model code of single product : RCP2-SB-GR3M

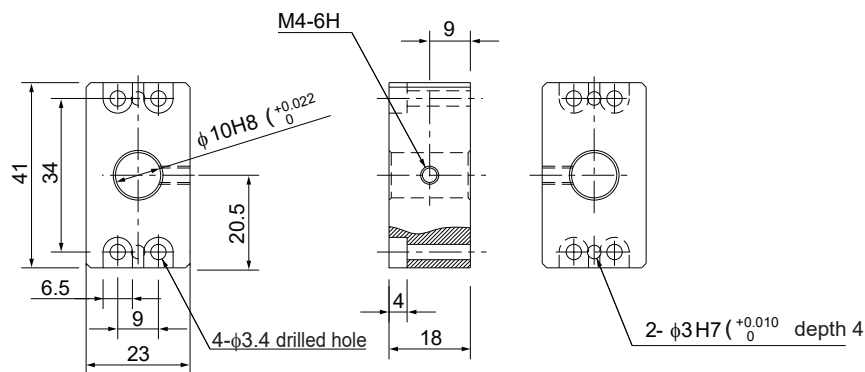


1.4.3 Flange Bracket (Model: FB)

It is a bracket to fix the gripper body.

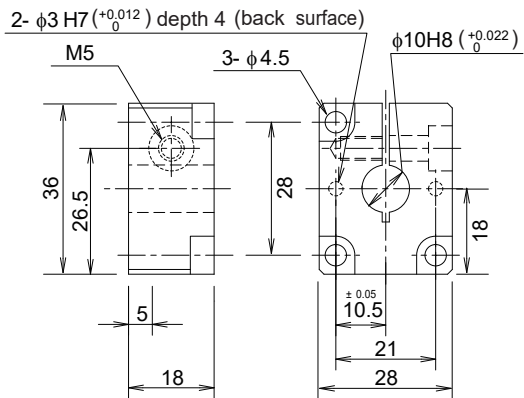
For GRSS/GRLS

Model code of single product : RCP2-FB-GRSS



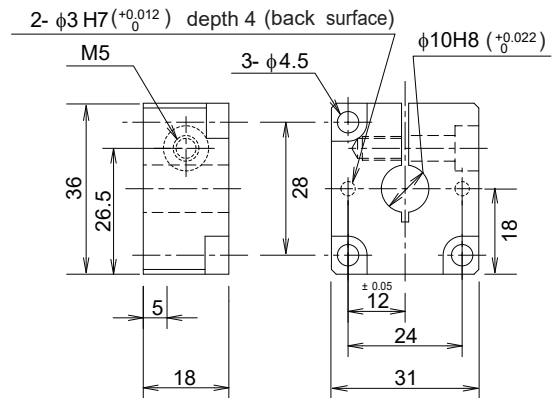
For GRS

Model code of single product : RCP2-FB-GRS



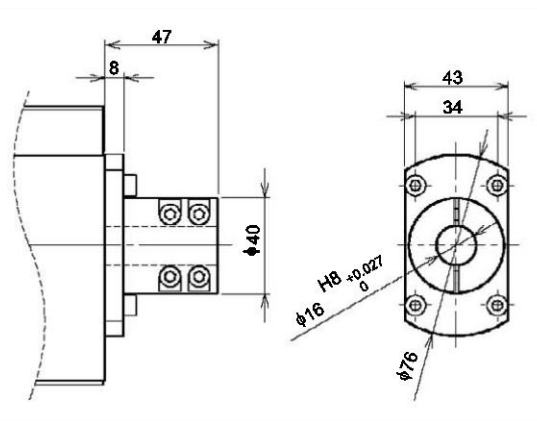
For GRM

Model code of single product : RCP2-FB-GRM



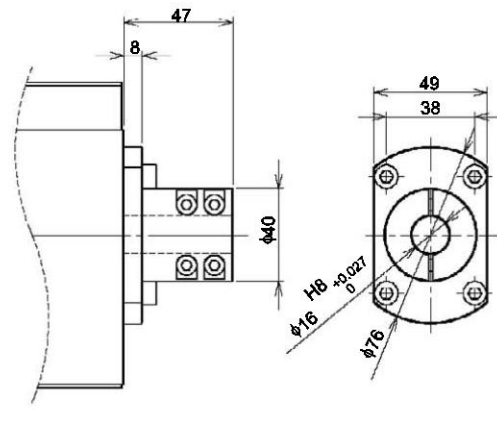
For GRHM

Model code of single product : RCP2-FB-GRHM



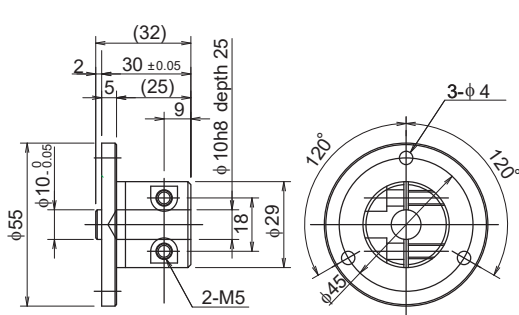
For GRHB

Model code of single product : RCP2-FB-GRHB



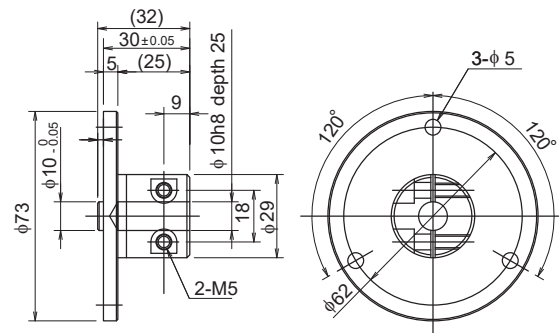
For GR3SS

Model code of single product : RCP2-FB-GRS



For GR3SM

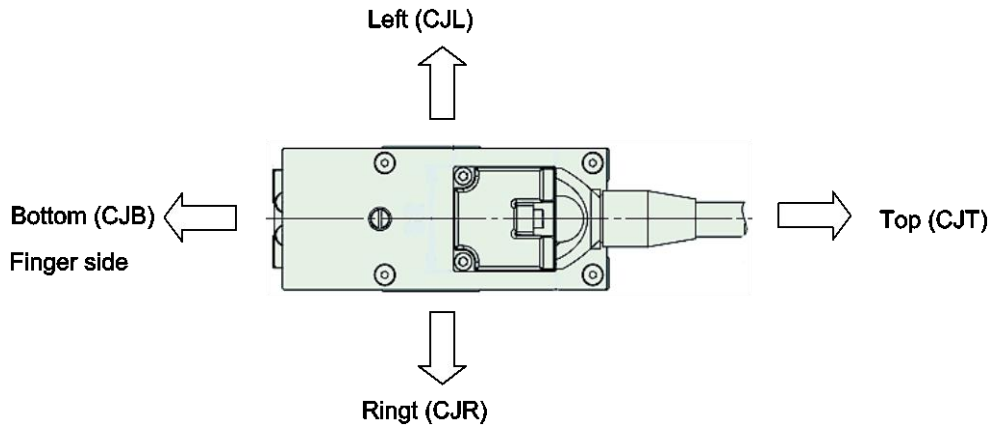
Model code of single product : RCP2-FB-GRM



1.4.4 Cable Eject Direction Changed (Model: CJT, CJR, CJL, CJB)

Application: GRHM/GRHB

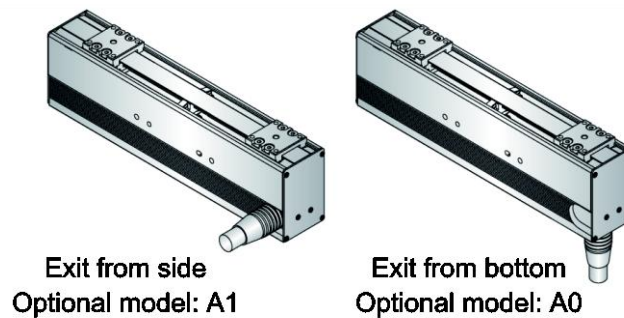
If a change in the cable ejection direction is made, the direction of cable ejection will be changed. There are four types of ejection directions, top (model code: CJT), right (model code: CJR), left (model code: CJL) and bottom (model code: CJB).



1.4.5 Cable Exit from Bottom and Cable Exit from Side (Model: A0, A1)

Application: GRST

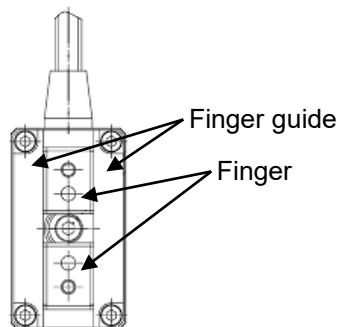
If a change in the cable ejection direction is made, the direction of cable ejection will be changed. There are two types for the direction change, bottom (model: A0) and side (model: A1).



1.4.6 Anti-Rust Black Coating (Model: AR)

Application: GRSS

Anti-rust black coating is applied on the finger guides and fingers. It is to be used in an environment that is easy to rust.



1.5 Motor • Encoder Cables

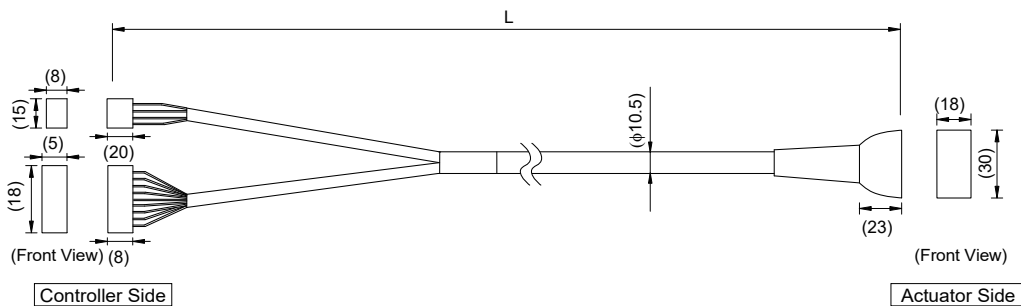
1.5.1 Small Slim Two-finger Slide Type (GRSS), Small Slim Two-finger Lever Type (GRLS), Two-finger Long-stroke Type (GRST), Two-finger Type with High Gripping Force (GRHM/GRHB)

[PSEL and PCON Controller (Except for PCON-CB/CGB/CYB/PLB/POB, PCON-CA)]

1) Motor • Encoder Integrated Cables Robot Type

Model: CB-PCS-MPA□□□

(□□□ indicates the cable length L Example: 020 = 2m), up to 20m



Signal	Pin No.	(Wire Color)	Pin No.	Signal
A	B1	Black	A1	A
VMM	A2	White	B1	VMM
/A	A1	Red	A2	/A
B	B3	Green	B2	B
VMM	B2	Yellow	A3	VMM
/B	A3	Brown	B3	/B
			A4	NC
			B4	NC
BK+	14	Orange	A5	BK+
BK-	13	Gray	B5	BK-
LS+	16	White	A6	LS+
LS-	15	Yellow	B6	LS-
A+	12	Red	A7	A+
A-	11	Green	B7	A-
B+	10	Black	A8	B+
B-	9	Brown	B8	B-
NC	8		A9	NC
VPS	7	Yellow (Identification tape)	B9	VPS
VCC	6	Red (Identification tape)	A10	VCC
GND	5	Green (Identification tape)	B10	GND
NC	4		A11	NC
FG	1	Shielded wire	B11	FG

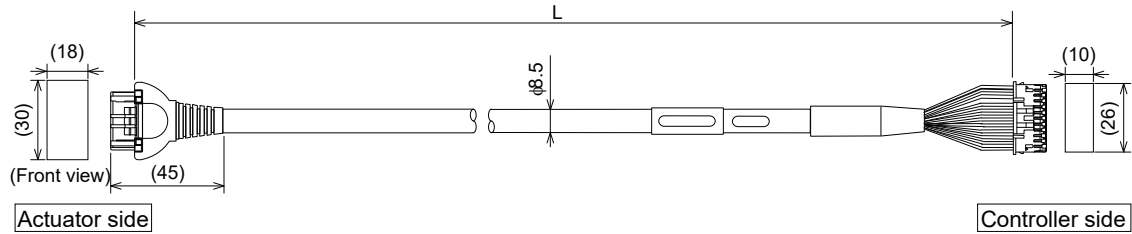
(Note) The cable colors shown are those after cables have changed. The cable colors before changed is different.

[PCON-CB/CGB/CYB/PLB/POB, PCON-CA, PMEC, PSEP, MSEP, MCON and MSEL Controller]

1) Motor • Encoder Integrated Cables Robot Type/Motor • Encoder Integrated Cables

Model: CB-APSEP-MPA□□□ / CB-APSEP-MPA□□□-LC

(□□□ indicates the cable length L Example: 020 = 2m), up to 20m



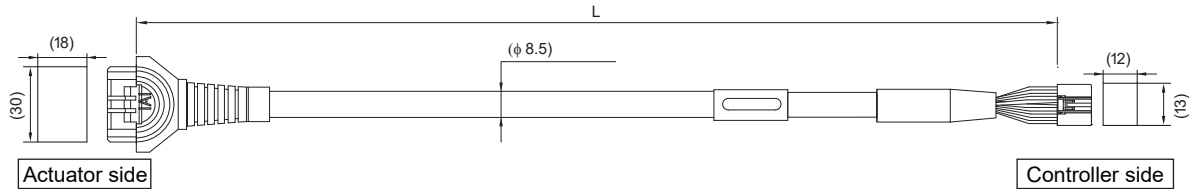
Actuator side Terminal No.				Controller side Terminal No.
A1		Black [φA]		1
B1		White [VMM]		2
A2		Brown [φA]		5
B2		Green [φB]		3
A3		Yellow [VMM]		4
B3		Red [φB]		6
A4		Orange [LS+]		7
B4		Gray [LS-]		8
A6		White [-]		11
B6		Yellow [-]		12
A7		Red [A+]		13
B7		Green [A-]		14
A8		Black [B+]		15
B8		Brown [B-]		16
A5		Black (Identification tape) [BK+]		9
B5		Brown (Identification tape) [BK-]		10
A9		Green (Identification tape) [GNDLS]		20
B9		Red (Identification tape) [VPS]		18
A10		White (Identification tape) [VCC]		17
B10		Yellow (Identification tape) [GND]		19
A11		NC		21
B11		Shielded [FG]		24
		NC		22
		NC		23

[RCON、RSEL]

1) Motor • Encoder Integrated Cables/Motor • Encoder Integrated Cables Robot Type

Model: CB-RCAPC-MPA□□□ / CB-RCAPC-MPA□□□-RB

(□□□ indicates the cable length L Example: 020 = 2m), up to 20m



1-1827863-1(AMP)			DF62DL-24S-2.2C(Hirose)		
Wire Color	Signal Name	Pin No.	Pin No.	Signal Name	Wire Color
Blue (AWG22/19)	PC	A1	3	PC	Blue (AWG22/19)
Orange (AWG22/19)	φA	B1	5	φA	Orange (AWG22/19)
Brown (AWG22/19)	VMM	B2	10	VMM	Brown (AWG22/19)
Gray (AWG22/19)	φB	A3	9	φB	Gray (AWG22/19)
Green (AWG22/19)	VMM	A2	4	VMM	Green (AWG22/19)
Red (AWG22/19)	φ_A	B3	15	φ_A	Red (AWG22/19)
Light blue (AWG26)	φ_B	A6	12	φ_B	Light blue (AWG26)
Orange (AWG26)	SA[mABS]	B6	17	SA[mABS]	Orange (AWG26)
Green (AWG26)	SB[mABS]	A7	1	SB[mABS]	Green (AWG26)
Brown (AWG26)	A+	B7	6	A+	Brown (AWG26)
Gray (AWG26)	A-	A8	11	A-	Gray (AWG26)
Red (AWG26)	B+	B8	16	B+	Red (AWG26)
Black (AWG26)	B-	B9	18	B-	Black (AWG26)
Yellow (AWG26)	VPS	A4	8	VPS	Yellow (AWG26)
Light blue (AWG26)	LS+	A5	20	LS+	Light blue (AWG26)
Orange (AWG26)	BK+	B5	2	BK+	Orange (AWG26)
Gray (AWG26)	BK-	A10	21	BK-	Gray (AWG26)
Red (AWG26)	VCC	B10	7	VCC	Red (AWG26)
Brown (AWG26)	GND	B4	14	GND	Brown (AWG26)
Green (AWG26)	LS-	A9	13	LS-	Green (AWG26)
-	LS_GND	A11	19	LS-GND	-
-	-	-	22	-	-
-	-	-	23	CF_VCC	Gray (AWG26)
-	-	-	24	-	-
Black (AWG26)	FG	B11	24	FG	Black (AWG26)

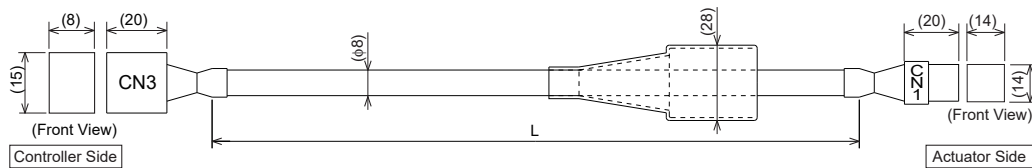
1.5.2 Small and Medium Two-finger Type (GRS/GRM), Three-finger Slide Type (GR3SS/GR3SM), Three-finger Lever Type (GR3LS/GR3LM)

[PSEL, PCON controller (Except for PCON-CA)]

1) Motor Cable

Model: CB-RCP2-MA□□□

(□□□ indicates the cable length L Example: 020 = 2m), up to 20m

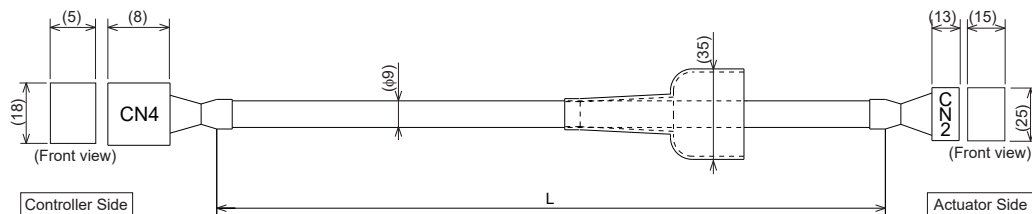


	CN3	M Cable	CN1	
I-1318119- (AMP)	Orange	Ā	A1	1 A Yellow
	Gray	VMM	A2	2 VMM Gray
	White	B	A3	3 Ā Orange
	Yellow	A	B1	4 B Orange(Black1)
	Pink	VMM	B2	5 VMM Pink
	Orange(Black1)	B	B3	6 B̄ White
				SLP-06V (JST)

2) Encoder Cable / Encoder Cable Robot Type

Model: CB-RCP2-PB□□□ / CB-RCP2-PB□□□-RB

(□□ indicates the cable length L Example: 020 = 2m), up to 20m



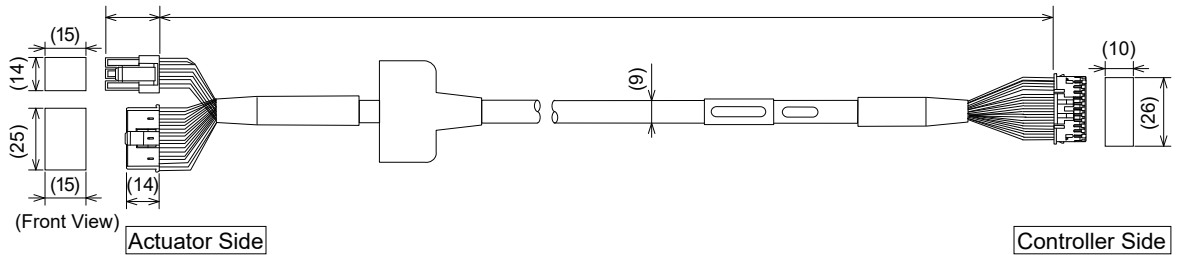
CN4	Cable color		Signal name	Pin No.		Pin No.	Signal name	Cable color		CN2
	Standard cable	Robot cable						Standard cable	Robot cable	
PHDR-16VS (JST)	Blue (Red1)	Orange (Black2)	LS+	16	Shielded wire Ground wire	1	ENA	Brown	Light Gray (Black1)	XMP-18V (JST)
	White	Orange (Red2)	LS-	15		2	ENA	Green	Light Gray (Red1)	
	Red	Orange (Black1)	BK+	14		3	ENB	Purple	White (Black1)	
	Gray	Orange (Red1)	BK-	13		4	ENB	Pink	White (Red1)	
	Brown	Light Gray(Black1)	ENA	12		5	-	-	-	
	Green	Light Gray (Red1)	ENA	11		6	-	-	-	
	Purple	White (Black1)	ENB	10		7	-	-	-	
	Pink	White (Red1)	ENB	9		8	-	-	-	
	-	-	-	8		9	GND	Blue	Pink (Black1)	
	Yellow	Yellow (Black1)	VPS	7		10	VBB	Orange	Pink (Red1)	
	Orange	Pink (Red1)	VBB	6		11	VPS	Yellow	Yellow(Black1)	
	Blue	Pink (Black1)	GND	5		12	-	-	-	
	-	-	(N.C)	4		13	LS+	Blue(Red1)	Orange (Black2)	
	-	-	(N.C)	3		14	LS-	White	Orange (Red2)	
	-	-	(N.C)	2		15	-	-	-	
	Drain	Drain	F.G	1		16	BK+	Red	Orange (Black1)	
						17	BK-	Gray	Orange (Red1)	
						18	F.G	Drain	Drain	

[PCON-CA, PMEC, PSEP and MSEP Controller]

1) Motor • Encoder Integrated Cables

Model: CB-PSEP-MPA□□□

(□□□ indicates the cable length L Example: 020 = 2m), up to 20m



Actuator Side			Controller Side
Terminal No.			Terminal No.
1	Black [φA]		1
2	White [VMM]		2
4	Red [φB]		3
5	Green [VMM]		4
3	Brown [φ/A]		5
6	Yellow [φ/B]		6
16	Orange [BK+]		9
17	Gray [BK-]		10
5	NC		11
6	NC		12
13	Black [LS+]		7
14	Brown [LS-]		8
1	White [A+]		13
2	Yellow [A-]		14
3	Red [B+]		15
4	Green [B-]		16
10	White (Identification tape) [VCC]		17
11	Yellow (Identification tape) [VPS]		18
9	Red (Identification tape) [GND]		19
12	Green (Identification tape) [Spare]		20
15	NC		21
7	NC		22
8	NC		23
18	Shielded wire [FG]		24

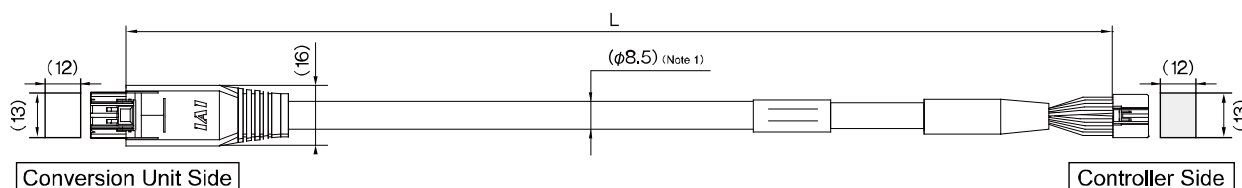
[RCON, RSEL]

Connect the conversion unit RCH-CU-APCS to CB-PSEP-MPA□□□ and join the following cable to it and then connect it to RCON or RSEL.

1) Motor • Encoder Integrated Cables/Motor • Encoder Integrated Cables Robot Type

Model: CB-ADPC-MPA□□□ / CB-RCAPC-MPA□□□-RB

(□□□ indicates the cable length L Example: 020 = 2m), up to 20m



1-1827863-1(AMP)			DF62DL-24S-2.2C(Hirose)		
Wire Color	Signal Name	Pin No.	Pin No.	Signal Name	Wire Color
Blue (AWG22/19)	φA	3	3	φA	Blue (AWG22/19)
Orange (AWG22/19)	VMM	5	5	VMM	Orange (AWG22/19)
Brown (AWG22/19)	φB	10	10	φB	Brown (AWG22/19)
Gray (AWG22/19)	VMM	9	9	VMM	Gray (AWG22/19)
Green (AWG22/19)	φA	4	4	φA	Green (AWG22/19)
Red (AWG22/19)	φB	15	15	φB	Red (AWG22/19)
Light blue (AWG26)	SA[mABS]	12	12	SA[mABS]	Light blue (AWG26)
Orange (AWG26)	SB[mABS]	17	17	SB[mABS]	Orange (AWG26)
Green (AWG26)	A+	1	1	A+	Green (AWG26)
Brown (AWG26)	A-	6	6	A-	Brown (AWG26)
Gray (AWG26)	B+	11	11	B+	Gray (AWG26)
Red (AWG26)	B-	16	16	B-	Red (AWG26)
Black (AWG26)	VPS	18	18	VPS	Black (AWG26)
Yellow (AWG26)	LS+	8	8	LS+	Yellow (AWG26)
Light blue (AWG26)	BK+	20	20	BK+	Light blue (AWG26)
Orange (AWG26)	BK-	2	2	BK-	Orange (AWG26)
Gray (AWG26)	VCC	21	21	VCC	Gray (AWG26)
Red (AWG26)	GND	7	7	GND	Red (AWG26)
Brown (AWG26)	LS-	14	14	LS-	Brown (AWG26)
Green (AWG26)	LS_GND	13	13	LS-GND	Green (AWG26)
-	-	19	19	-	-
Pink (AWG26)	CV_VCC	22	22	CF_VCC	Pink (AWG26)
-	-	23	23	-	-
Black (AWG26)	FG	24	24	FG	Black (AWG26)

Note1 It should be φ9.1 when the cable length exceeds 3m.

2. Installation

2.1 Transportation

[1] Handling of the Actuator

Unless otherwise specified, the actuator is shipped with each axis unit packaged separately.

(1) Handling the Packed Unit

- Do not damage or drop. The package is not applied with any special treatment that enables it to resist an impact caused by a drop or crash.
- Transport a heavy package with at least more than two operators. Consider an appropriate method for transportation.
- Keep the unit in a horizontal orientation when placing it on the ground or transporting. Follow the instruction if there is any for the packaging condition.
- Do not step or sit on the package.
- Do not put any load that may cause a deformation or breakage of the package.

(2) Handling the Actuator After Unpacking

- Do not carry the actuator by its motor unit or its cable or attempt to move it by pulling the cable.
- Hold the frame or motor cover section of the body when transporting the actuator main body.
- Do not hit or drop the actuator during transportation.
- Do not attempt to force any part of the actuator. Do not apply excess force especially on the fingers, finger guide and levers.

[2] Handling in the Assembled Condition

This is the case when the product is delivered from our factory under a condition that it is assembled with other actuators. The combined axes are delivered in a package that the frame is nailed on the lumber base.

(1) How to Handle the Package

- Do not hit or drop the package. No special treatment is conducted on this package to endure a drop or impact on it.
- Do not attempt to carry a heavy package with only one worker. Also, have an appropriate method for transportation.
- When hanging up with ropes, support on the reinforcement frame on the bottom of the lumber base. When bringing up the package with a forklift, also support on the bottom of the lumber base.
- Handle with care when putting the package down to avoid impact or bounce.
- Do not step on the package.
- Do not put anything on the package that could deform or damage it.

(2) How to Handle after Unpackaged

- Fix the finger so they would not accidentally move during transportation.
- If the tip of an actuator is overhanging, have an appropriate way to fix it to avoid shake due to the external vibration. In the transportation without the tip being fixed, do not apply any impact with 0.3G or more.
- When hanging up with ropes, have appropriate cushioning to avoid any deformation of the actuator body. Also keep it in stable horizontal orientation. Make a fixture utilizing the attachment holes and the tapped holes on the actuator body if necessary.
- Do not attempt to apply load on the actuators or the connector box. Also pay attention not to pinch cables and bend or deform them forcefully.

[3] Handling in Condition of being assembled in Machinery Equipment (System)

These are some caution notes for when transporting the actuator being assembled in the machinery equipment (system):

- Fix the finger so it would not move during transportation.
- If the tip of an actuator is overhanging, have an appropriate way to fix it to avoid shake due to the external vibration. In the transportation without the tip being fixed, do not apply any impact with 0.3G or more.
- When hanging up the machinery equipment (system) with ropes, do not attempt to apply load on the actuators or the connector box. Also pay attention not to pinch cables and bend or deform them forcefully.

2.2 Installation and Storage • Preservation Environment

[1] Installation Environment

The actuator should be installed in a location other than those specified below.
Also provide sufficient work space required for maintenance inspection.

- Where the actuator receives radiant heat from strong heat sources such as heat treatment furnaces
- Where the ambient temperature exceeds the range of 0 to 40°C
- Where the temperature changes rapidly and condensation occurs
- Where relative humidity larger than 85%RH
- Where the actuator receives direct sunlight
- Where the actuator is exposed to corrosive or combustible gases
- Where the ambient air contains a large amount of powder dust, salt or iron (at level exceeding what is normally expected in an assembly plant)
- Where the actuator is subject to splashed water, oil (including oil mist or cutting fluid) or chemical solutions
- Where the actuator receives impact or vibration
- Place with an altitude of 2,000m or more

When using the product in any of the locations specified below, provide a sufficient shield.

- Where noise generates due to static electricity, etc.
- Where the actuator is subject to a strong electric or magnetic field
- Where the actuator is subject to ultraviolet ray or radiation

[2] Storage • Preservation Environment

- The storage and preservation environment should comply with the same standards as those for the installation environment. In particular, when the machine is to be stored for a long time, pay close attention to environmental conditions so that no dew condensation forms.
- Unless specially specified, moisture absorbency protection is not included in the package when the machine is delivered. In the case that the machine is to be stored and preserved in an environment where dew condensation is anticipated, take the condensation preventive measures from outside of the entire package, or directly after opening the package.
- For storage and preservation temperature, the machine withstands temperatures up to 60°C for a short time, but in the case of the storage and preservation period of 1 month or more, control the temperature to 50°C or less.
- Storage and preservation should be performed in the horizontal condition. In the case it is stored in the packaged condition, follow the posture instruction if any displayed on the package.

2.3 How to Install

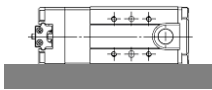
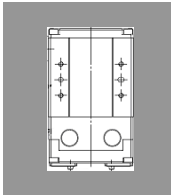
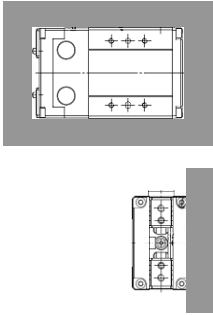
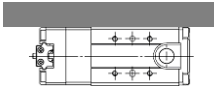
This chapter explains how to install the actuator on your mechanical system.

2.3.1 Installation

○ : Possible × : Not possible

Horizontal installation	Vertical installation	Sideways installation	Ceiling Mount installation
○	○	○	○

Installation Orientation

Horizontal	Vertical	Sideways	Ceiling Mount
			

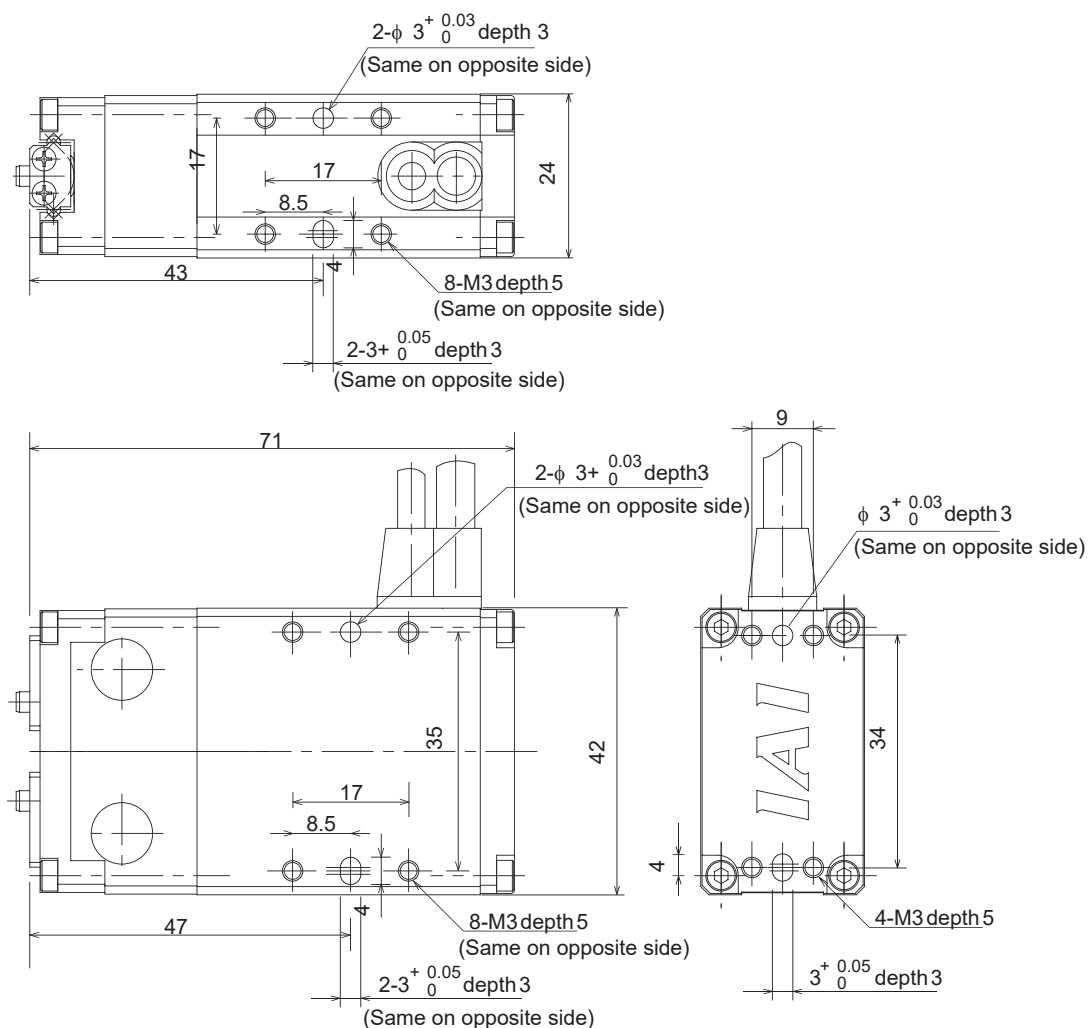
2.3.2 Installation of the Main Unit

The surface on which the gripper is installed must be machined or otherwise have a flat surface of equivalent precision.

- The effective thread depths of holes will vary depending on the gripper model and installation surface. Determine the lengths of screws to be used by referring to the figure below. (Never use long screws exceeding the effective thread depth. They may damage the mechanical or electrical parts inside the gripper.)
- Round and elongated holes are provided in each mounting surface for receiving positioning pins. Use these holes as necessary.

[1] GRSS

The actuator can be mounted and affixed on five surfaces.

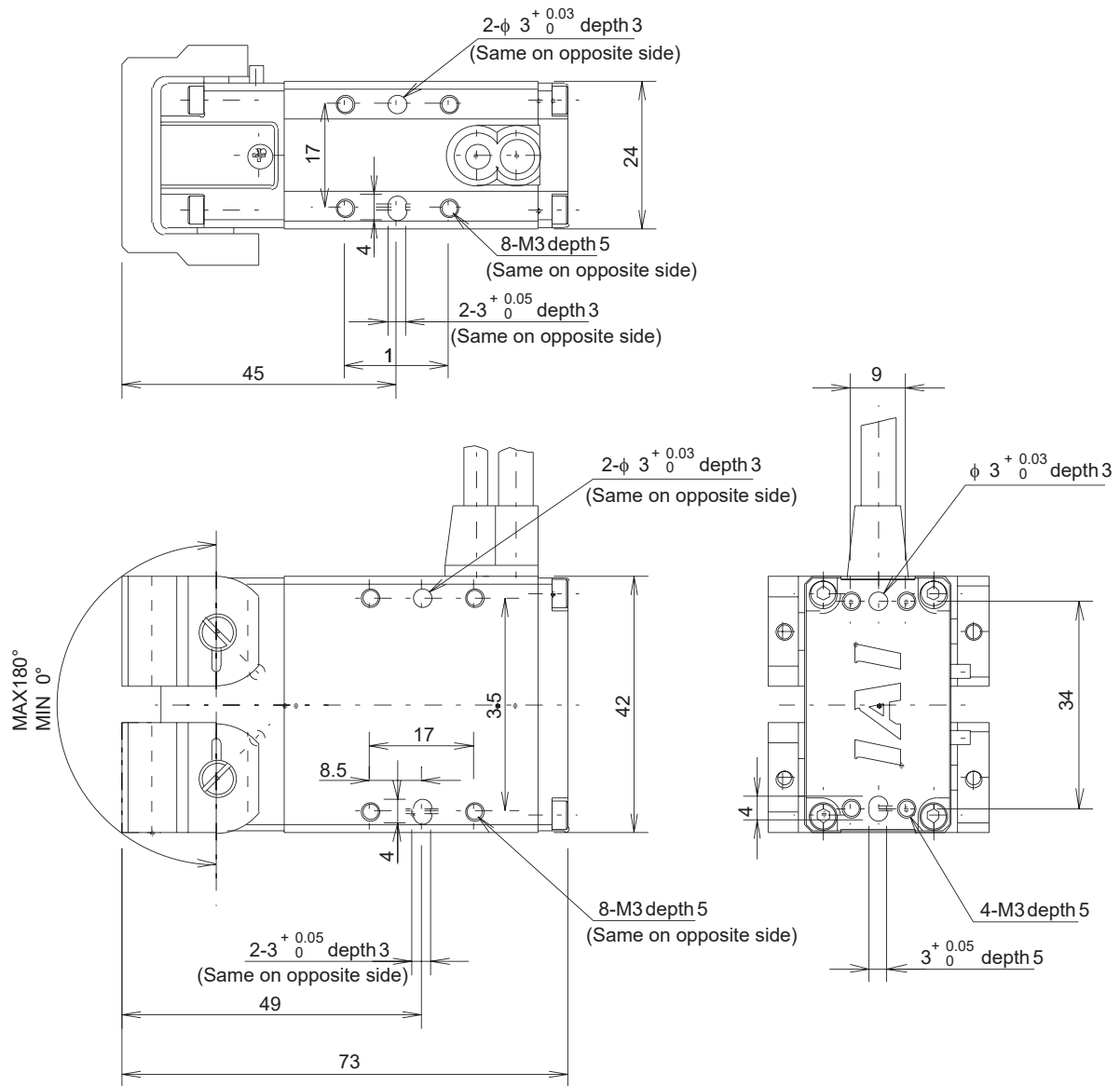


Caution: Some of the tapped holes used for installing the gripper are through holes. Therefore, never use long screws exceeding

[2] GRLS

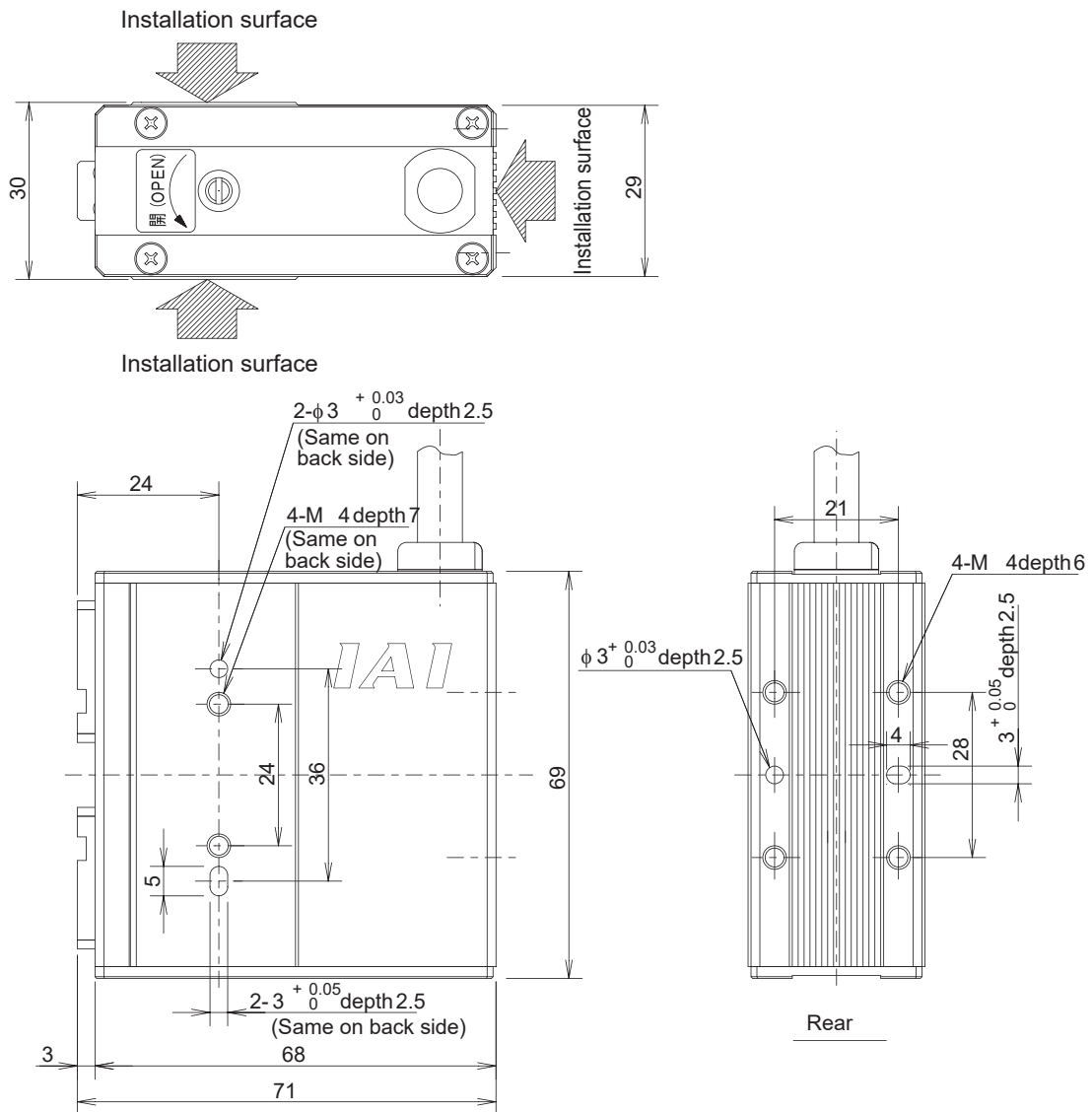
The actuator can be mounted and affixed on five surfaces.

2. Installation



Caution: Some of the tapped holes used for installing the gripper are through holes. Therefore, never use long screws exceeding

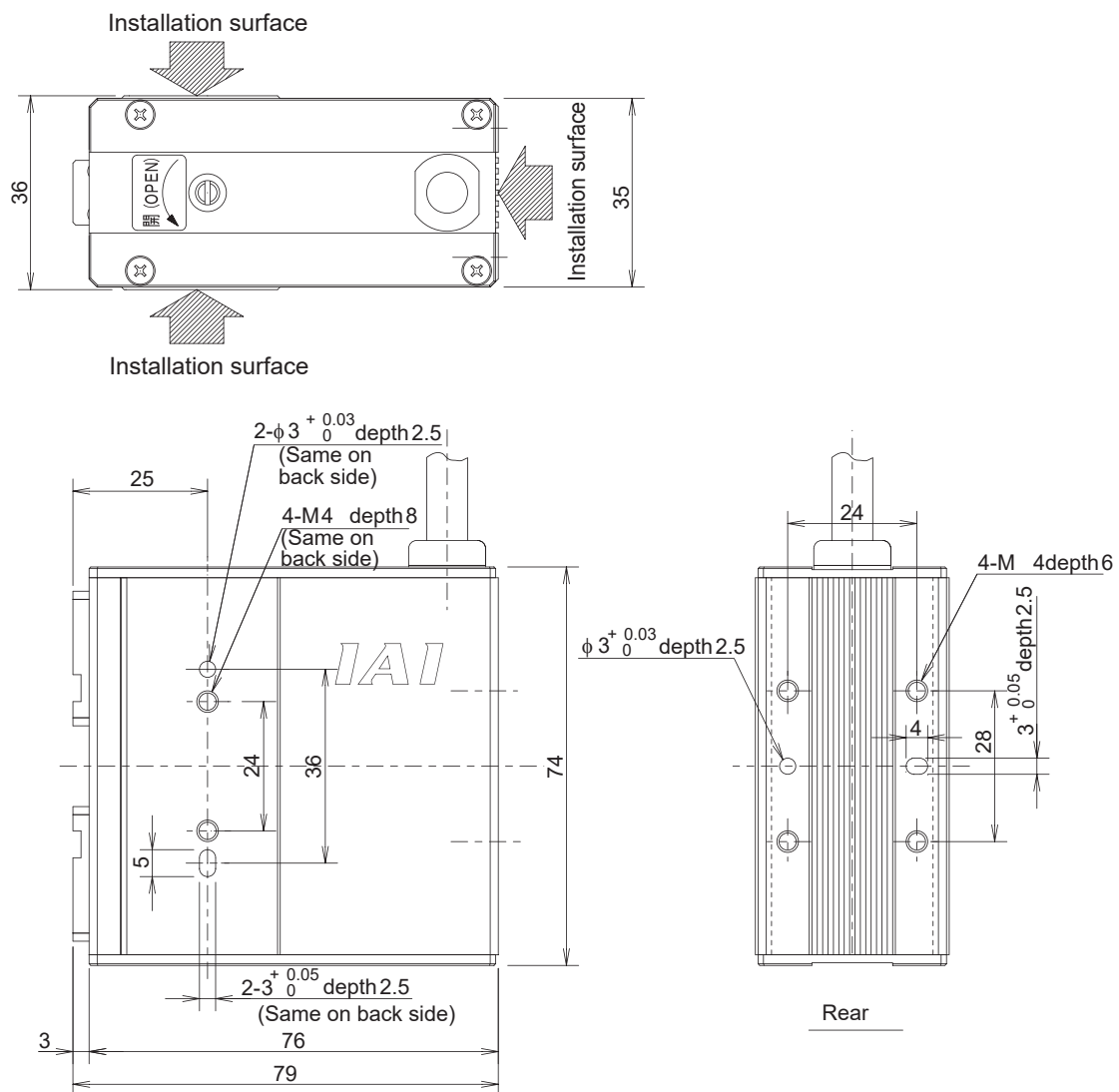
[3] GRS



Caution: Some of the tapped holes used for installing the gripper are through holes. Therefore, never use long screws exceeding

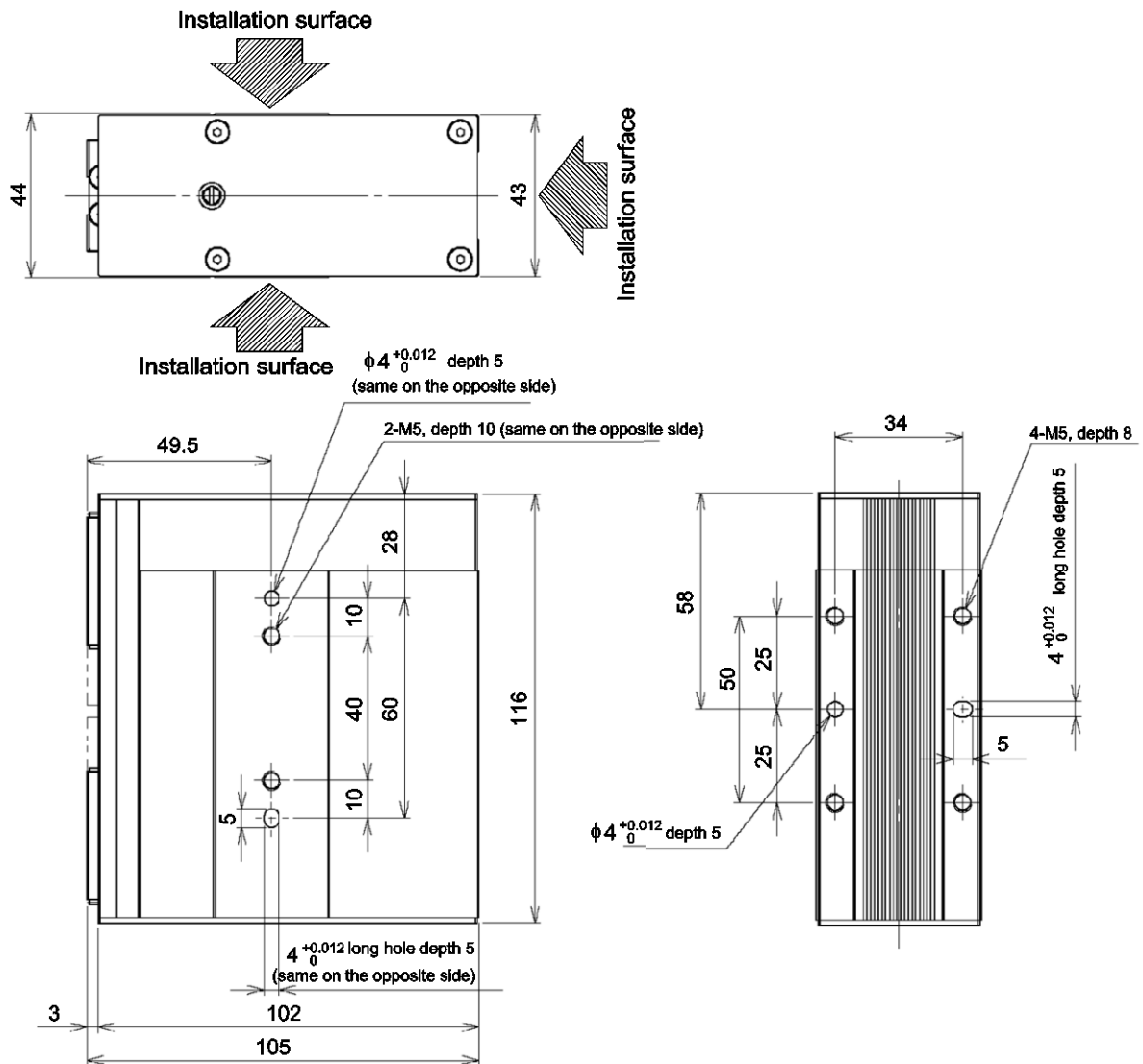
[4] GRM

2. Installation



Caution: Some of the tapped holes used for installing the gripper are through holes. Therefore, never use long screws exceeding

[5] GRHM



Caution: Some of the tapped holes used for installing the gripper are through holes. Therefore, never use long screws exceeding

Technical drawing of a rectangular plate with three views: top, front, and side.

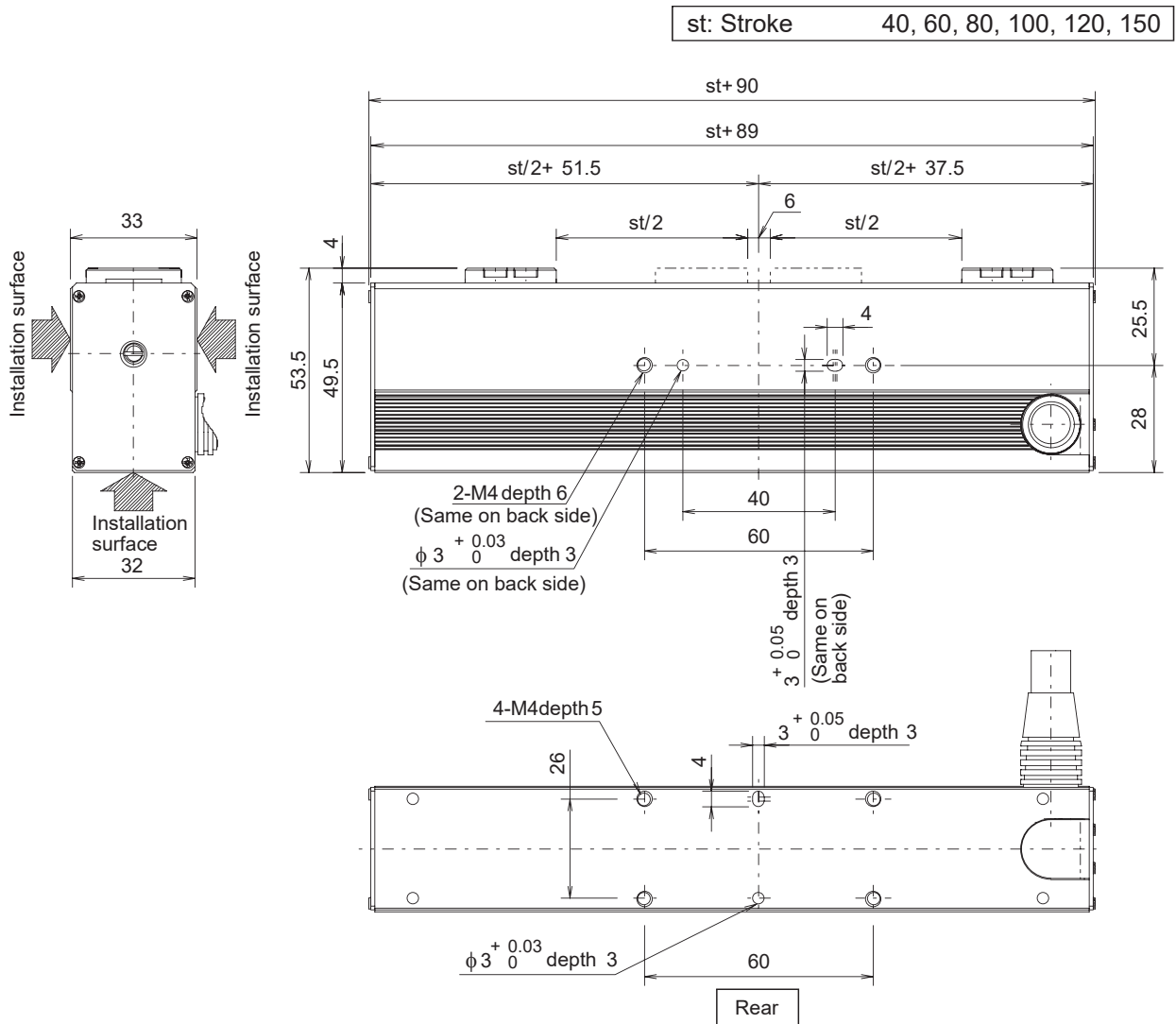
Top View: Dimensions 50 (width) and 49 (height). Features include four holes (2-M6, depth 12) and two smaller holes (phi 5 H7, depth 6). Installation surfaces are indicated by arrows.

Front View: Dimensions 131 (height) and 50 (width). Features include two long holes (5+0.012, depth 6) and two smaller holes (phi 5 H7, depth 6). Installation surfaces are indicated by arrows.

Side View: Dimensions 65.5 (height) and 38 (width). Features include four holes (4-M6, depth 10) and two smaller holes (phi 5 H7, depth 6).

ME3627-11P

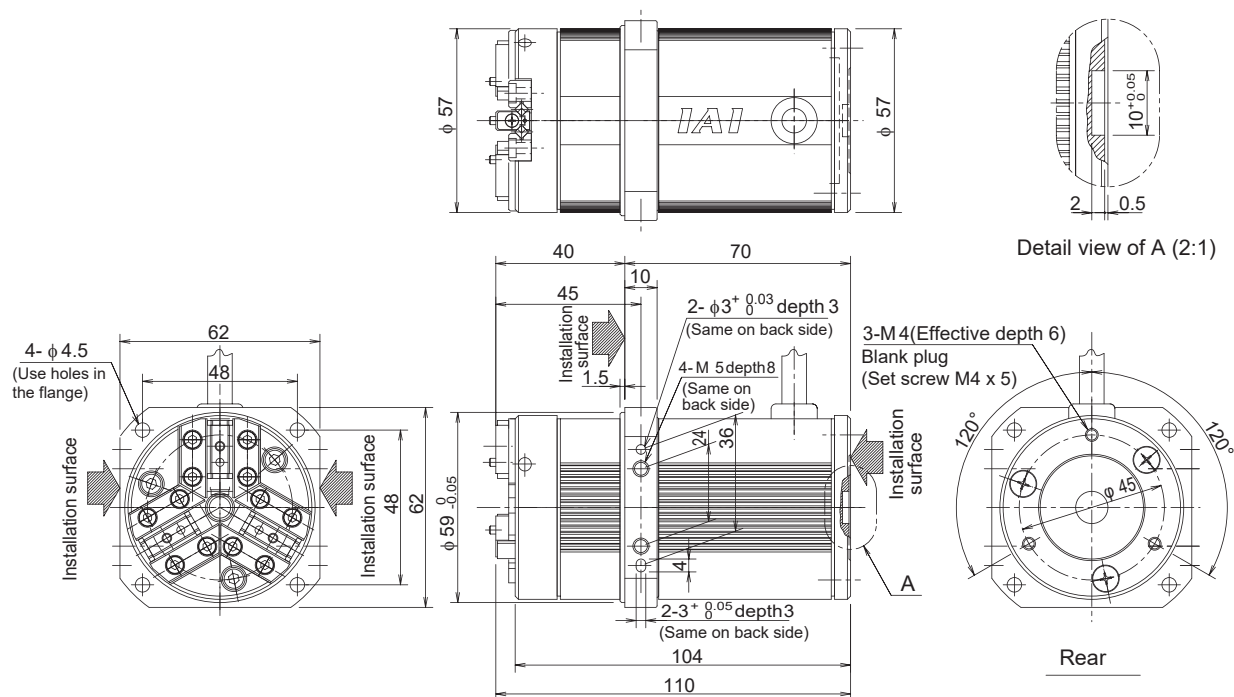
[7] GRST



Caution: Some of the tapped holes used for installing the gripper are through holes. Therefore, never use long screws exceeding

[8] GR3SS

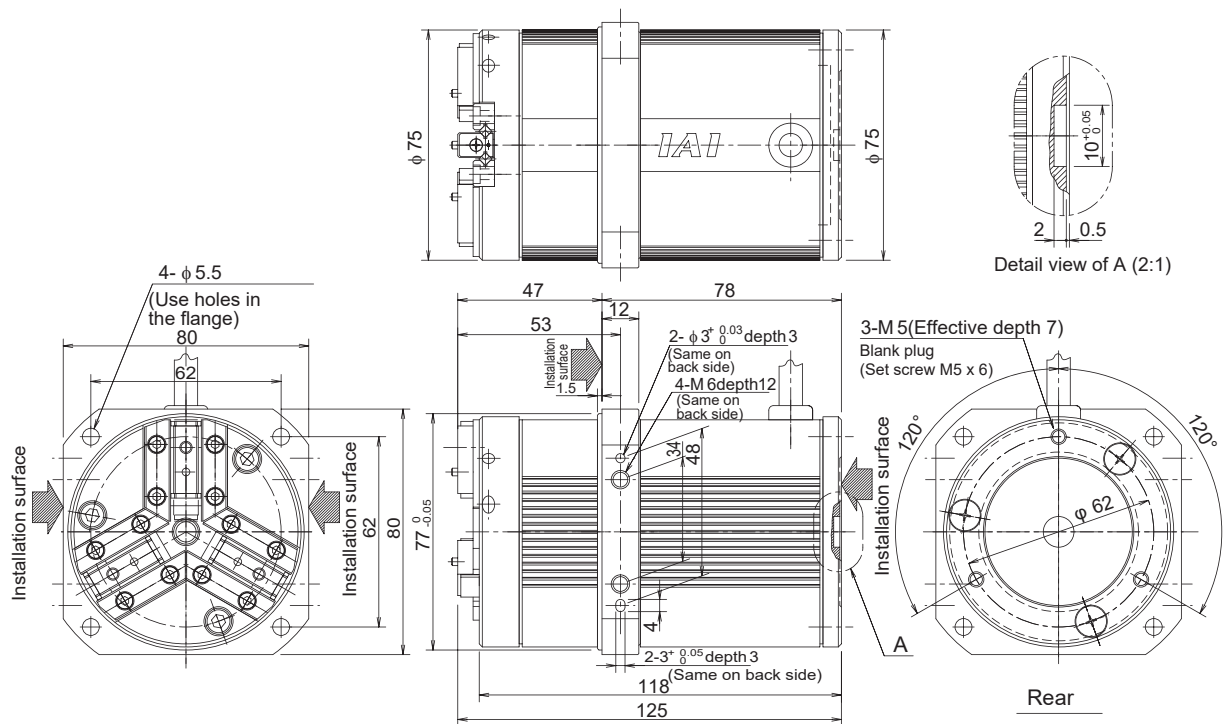
2. Installation



(Note) If the gripper is installed from the rear side, remove the blank plugs from the tapped holes.

Caution: Some of the tapped holes used for installing the gripper are through holes. Therefore, never use long screws exceeding

[9] GR3SM



(Note) If the gripper is installed from the rear side, remove the blank plugs from the tapped holes.

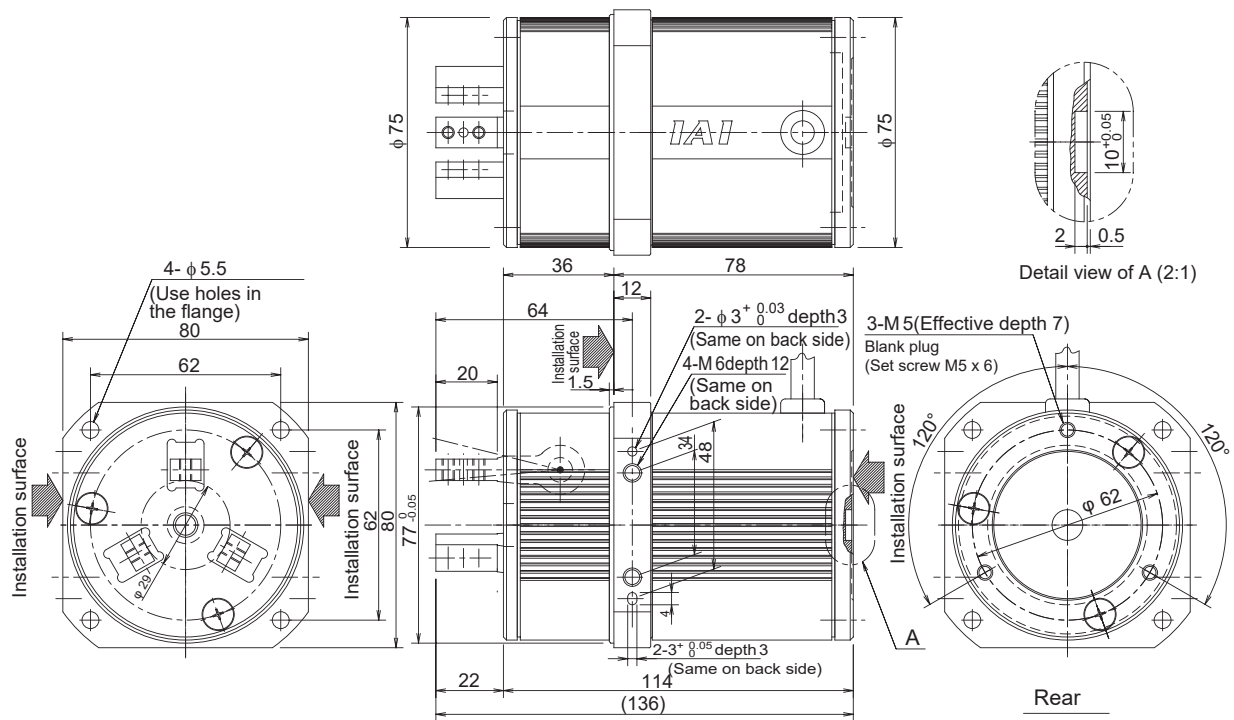
Caution: Some of the tapped holes used for installing the gripper are through holes. Therefore, never use long screws exceeding

[illegible]

(Note) If the gripper is installed from the rear side, remove the blank plugs from the tapped holes.

68

[11] GR3LM



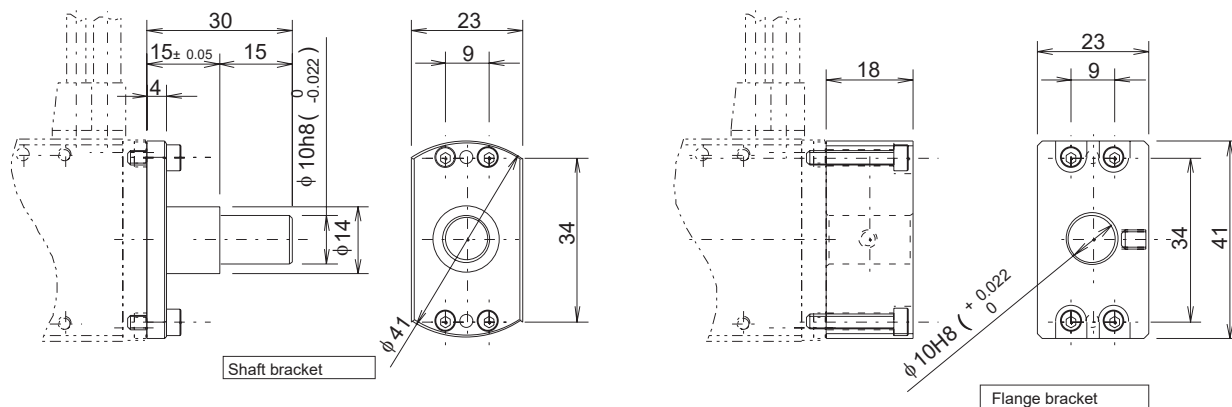
(Note) If the gripper is installed from the rear side, remove the blank plugs from the tapped holes.

Caution: Some of the tapped holes used for installing the gripper are through holes. Therefore, never use long screws exceeding

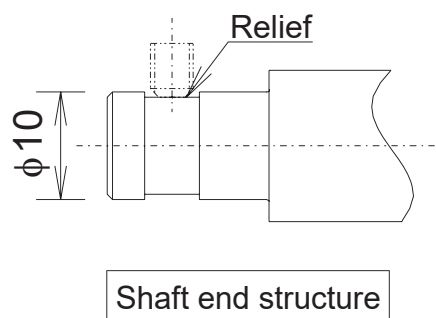
2.3.3 Gripper Brackets (Optional)

Optional brackets that can be installed on the rear face of the gripper are available. The external dimensions of each optional bracket are shown below.

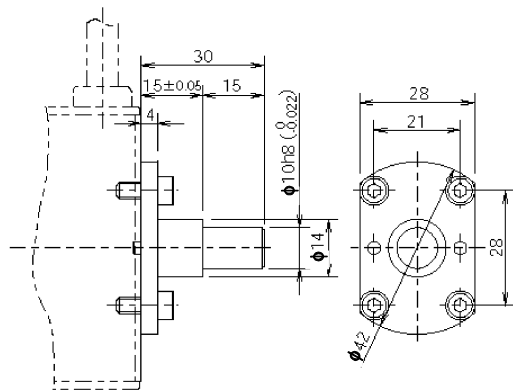
[1] GRSS/GRLS



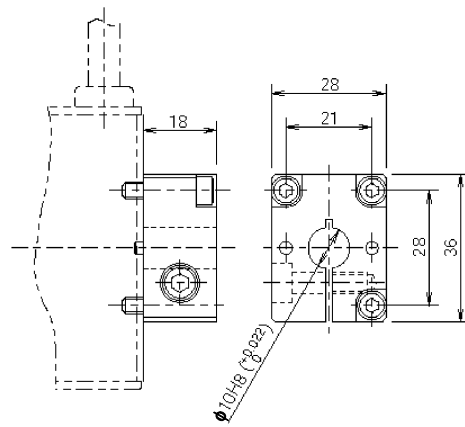
* If a flange bracket is used, it is recommended that a relief space be provided at the shaft end structure of the mating part as shown in the figure on the right.



[2] GRS

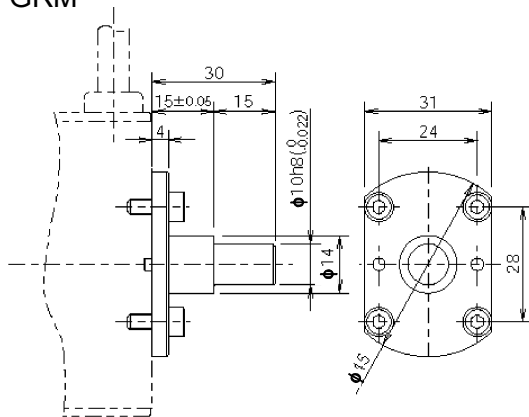


Shaft bracket

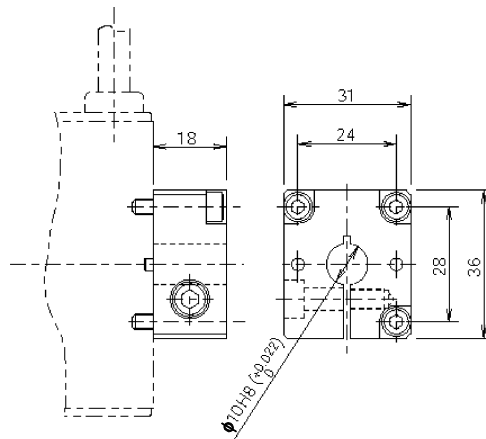


Flange bracket

[3] GRM

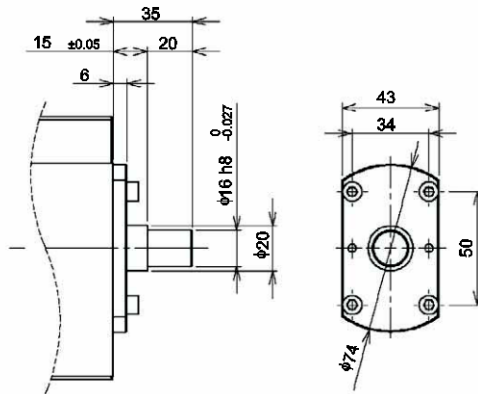


Shaft bracket

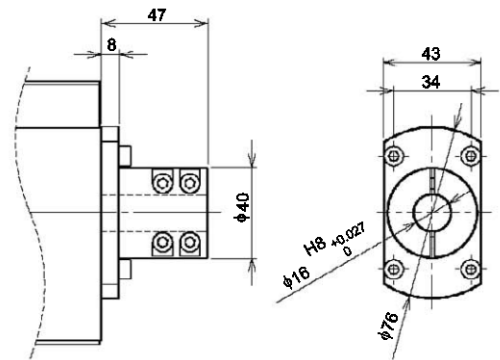


Flange bracket

[4] GRHM

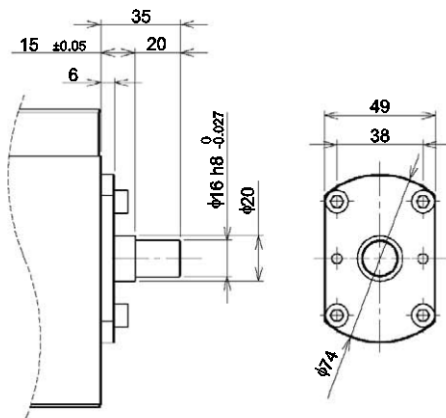


Shaft bracket

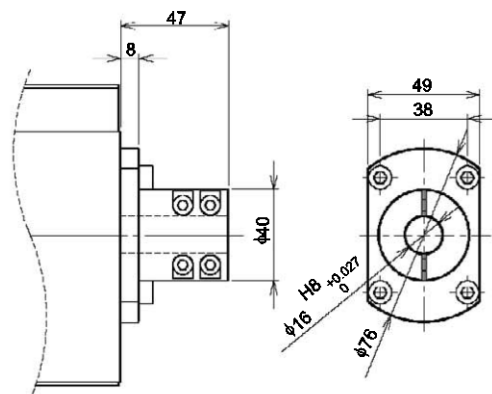


Flange bracket

[5] GRHB

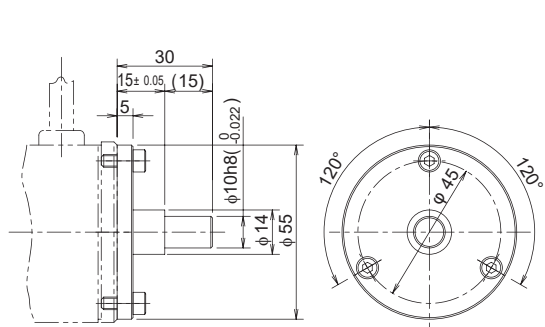


Shaft bracket

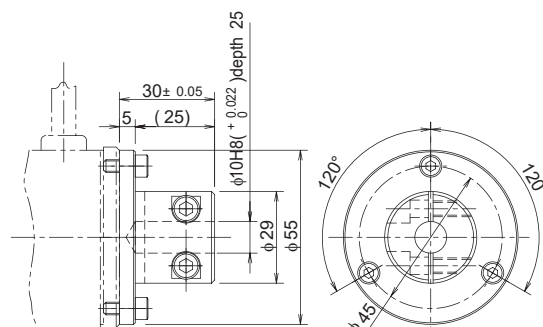


Flange bracket

[6] GR3SS/GR3LS

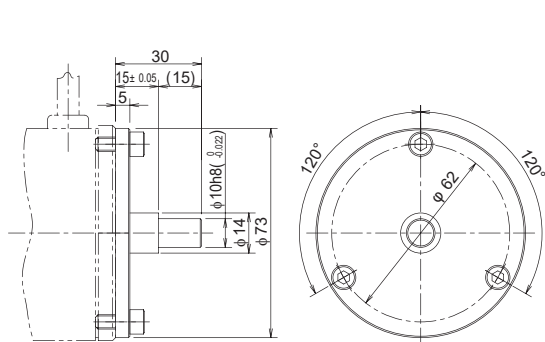


Shaft bracket

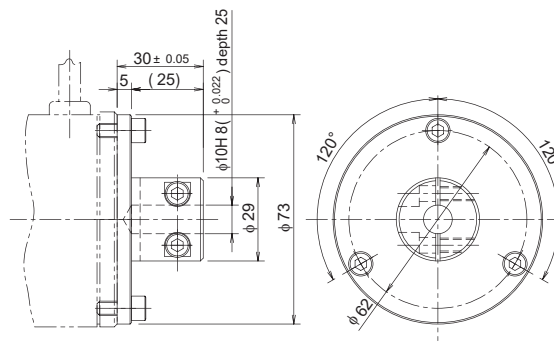


Flange bracket

[7] GR3 GR3LM



Shaft bracket



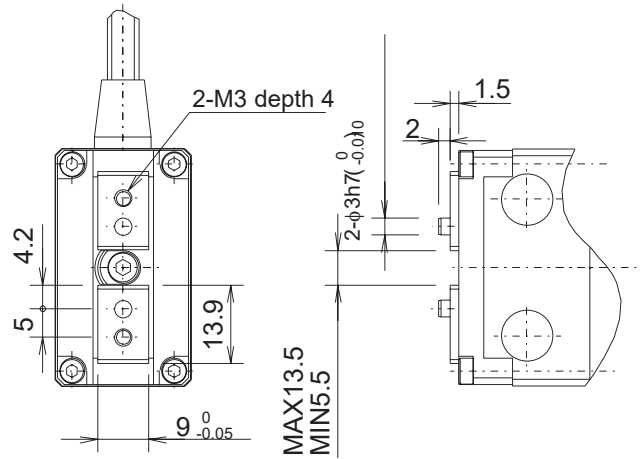
Flange bracket

2.3.4 Installation of Finger Attachments

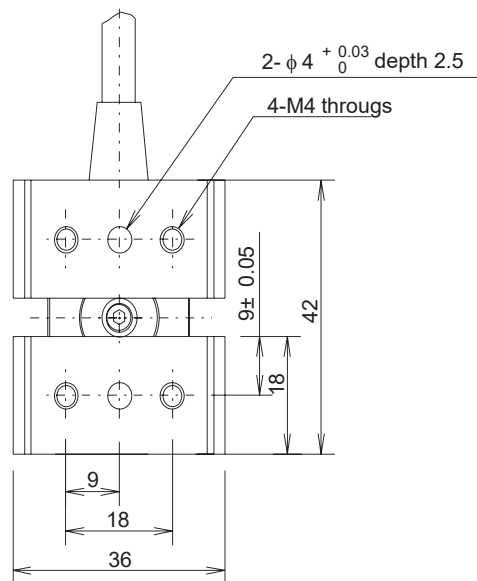
The finger attachments are provided by the customer.

[1] Installation dimensions for finger attachments

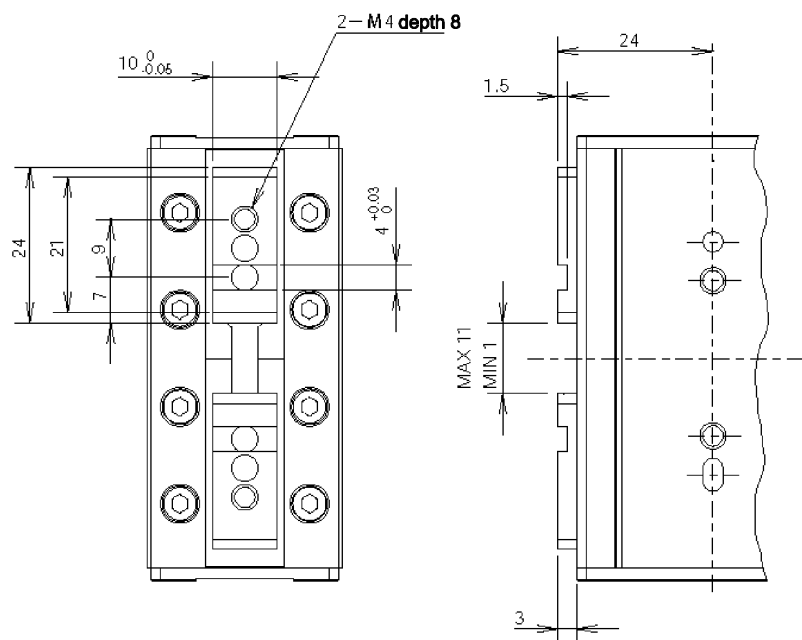
• GRSS



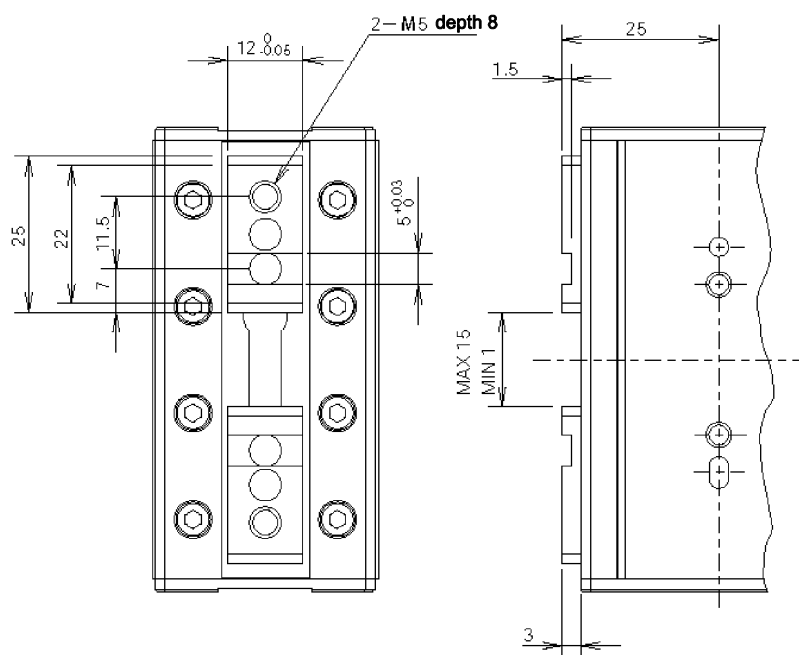
• GRLS



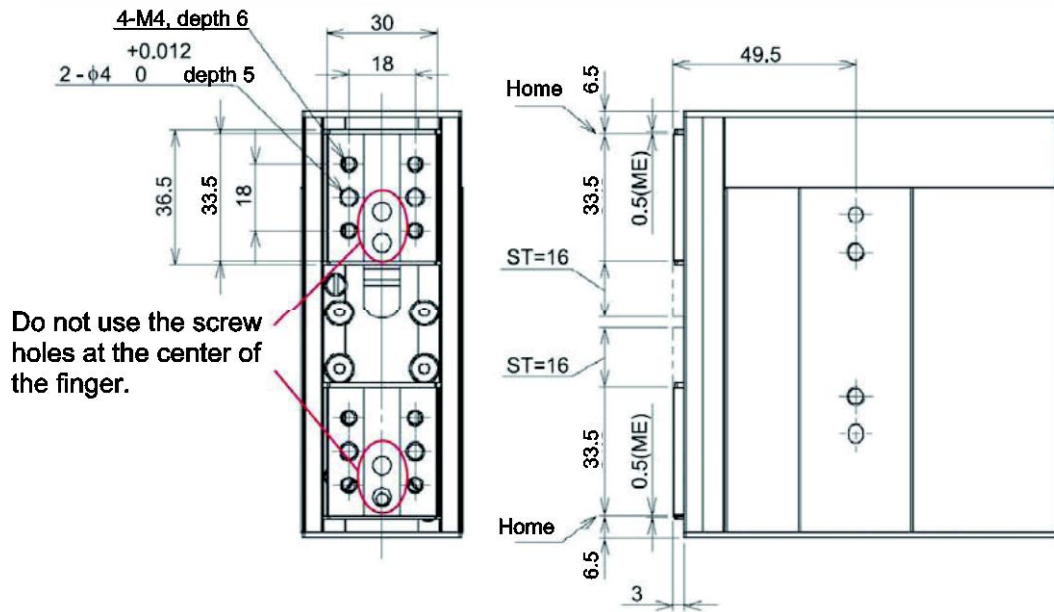
• GRS



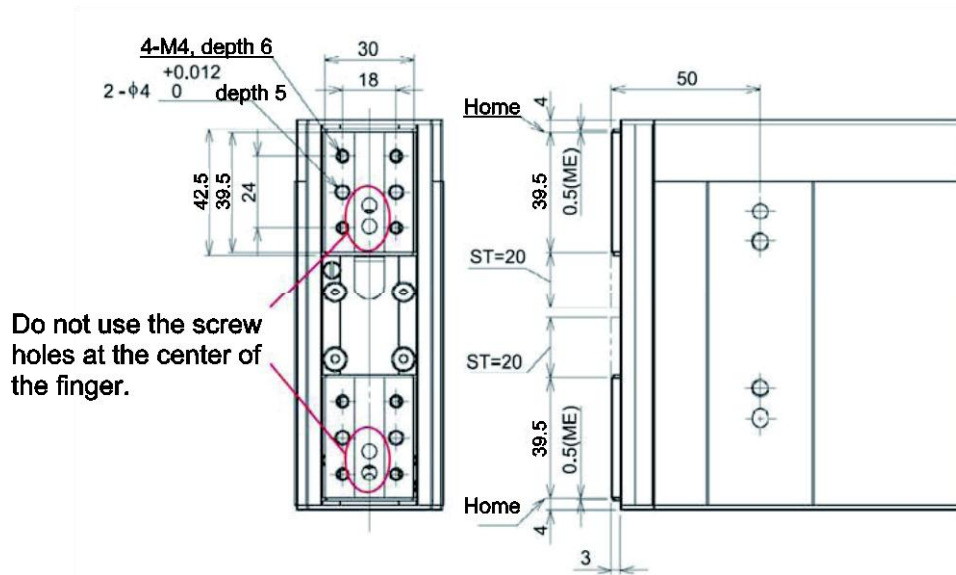
• GRM



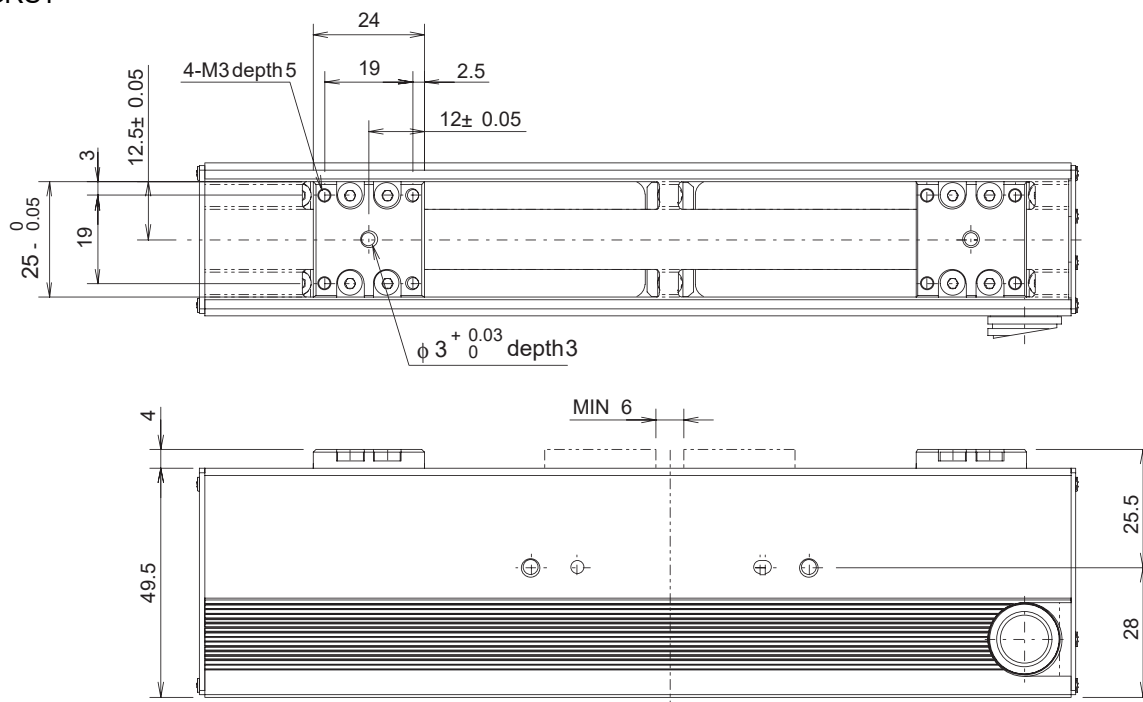
• GRHM



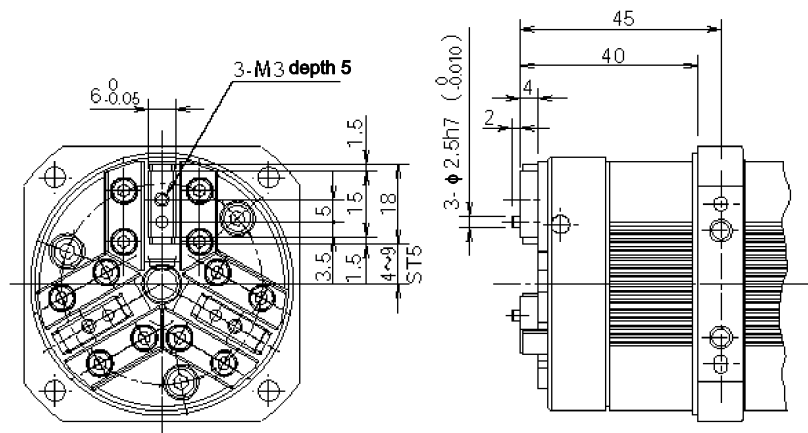
• GRHB



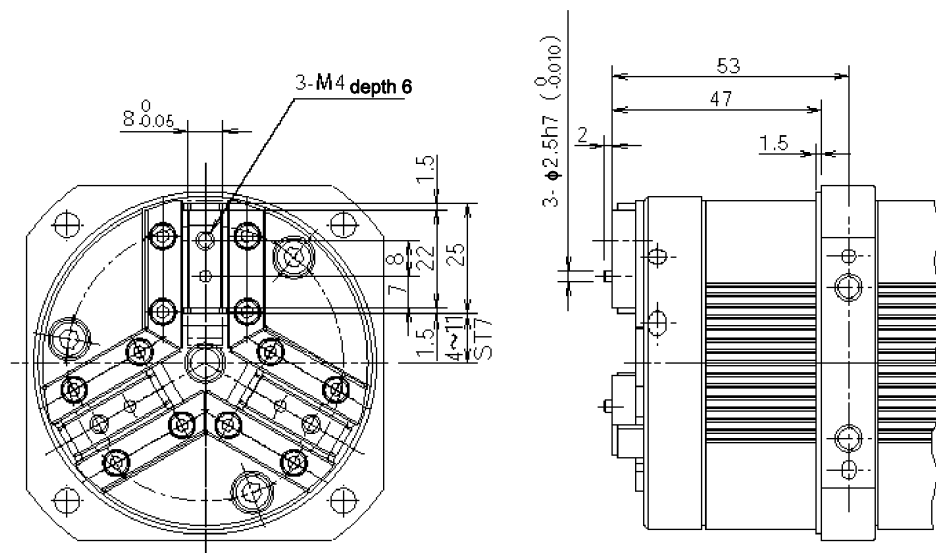
• GRST



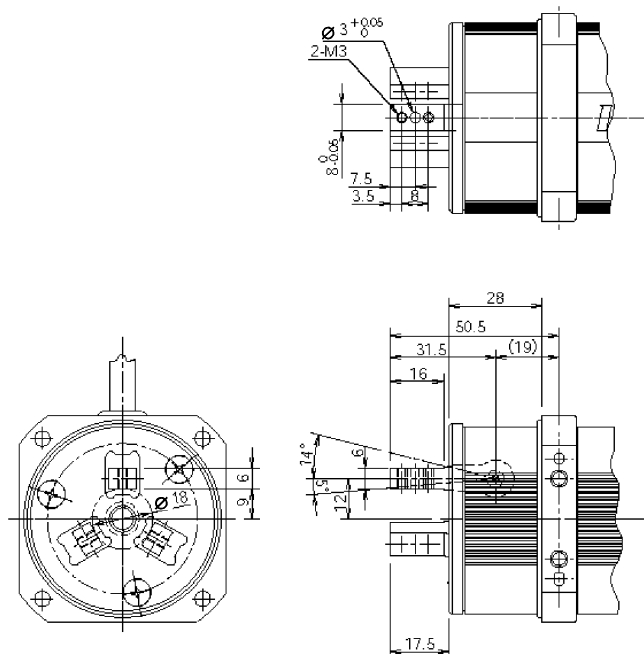
• GR3SS



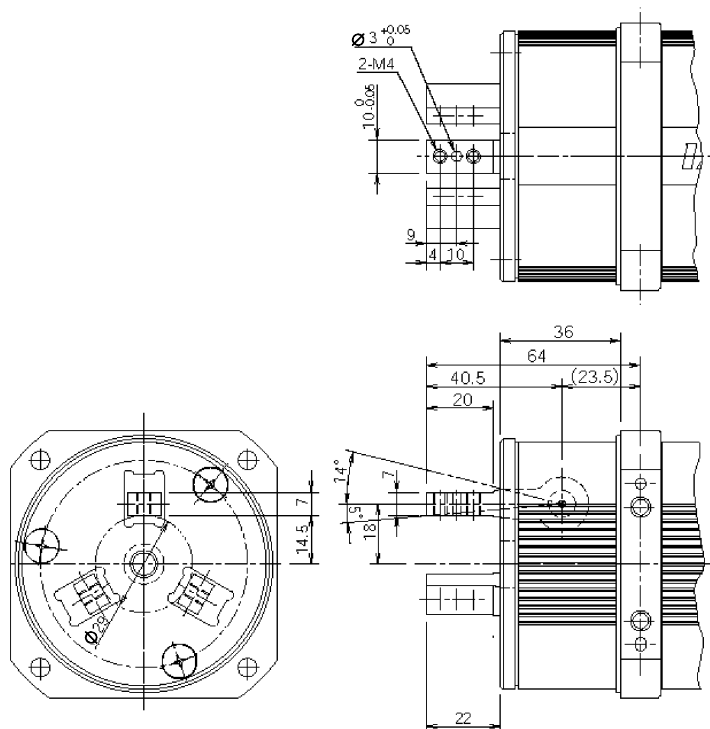
• GR3SM



• GR3LS



• GR3LM

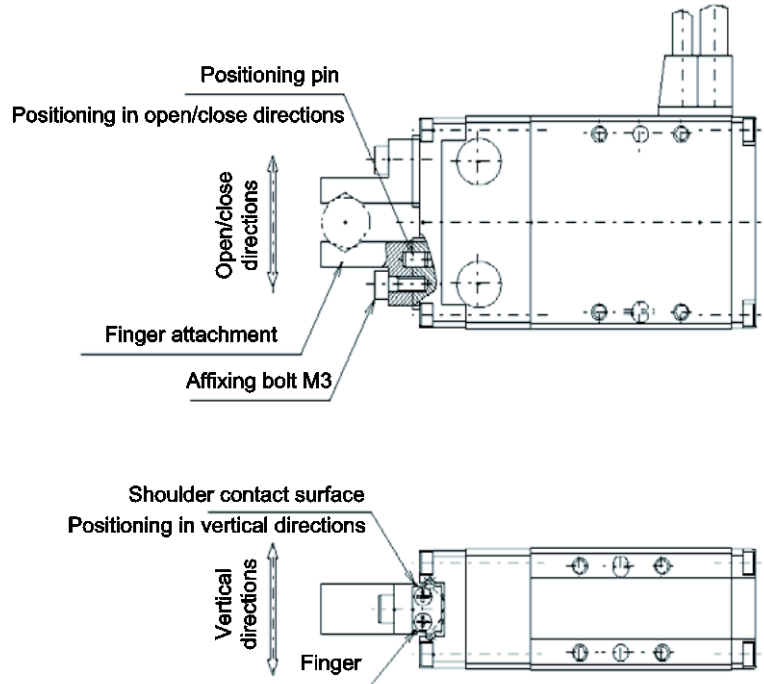


[2] Positioning in open/close and vertical directions

To achieve higher installation precision and repeatability for finger attachments, it is recommended that each finger attachment be positioned by sandwiching the attachment between the positioning pin and the side face of the finger, as illustrated below.

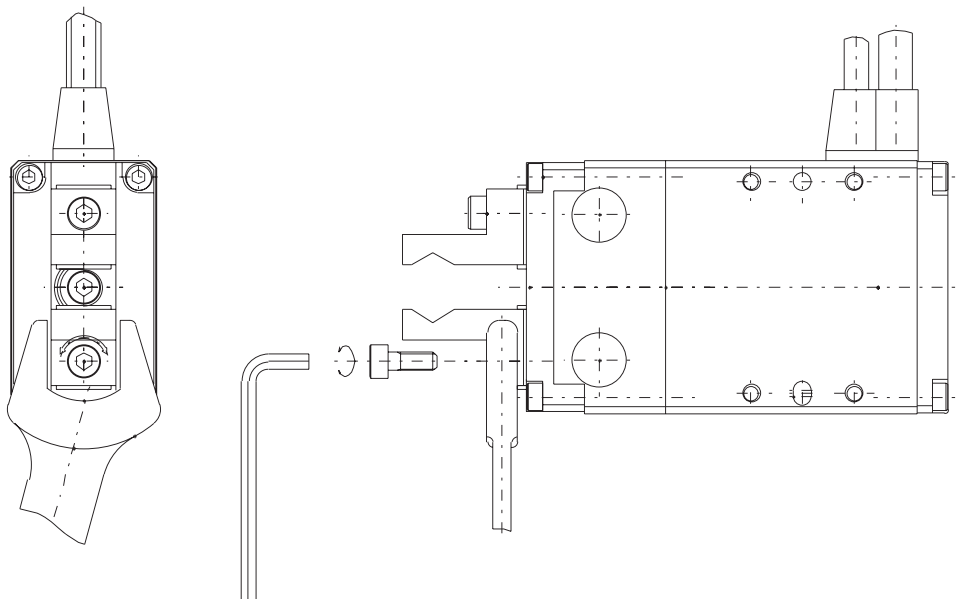
It is also recommended that a clearance of 3 mm or more be provided between the attachments so that the gripped work part can be removed by turning the opening/closing screw in the event of power outage.

• GRSS



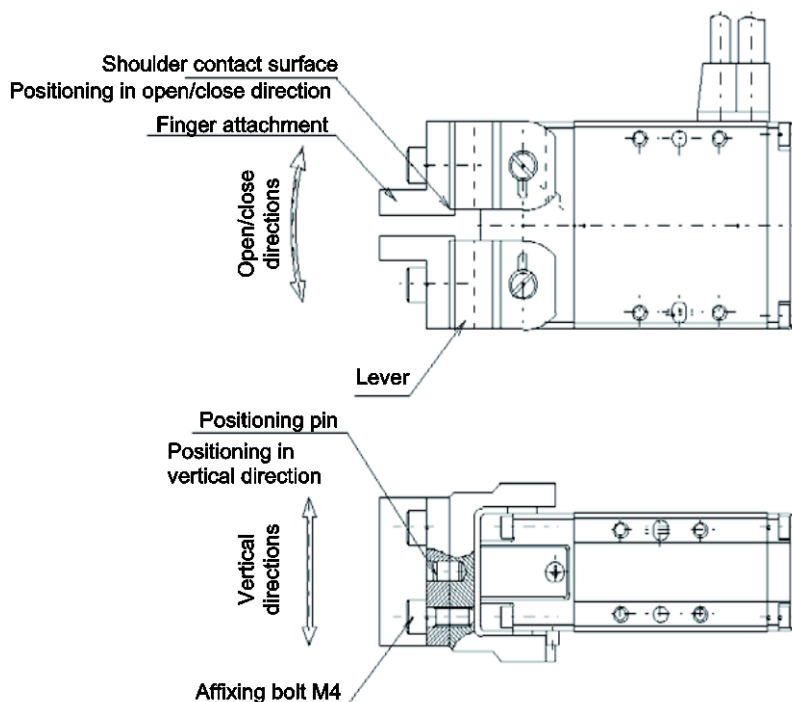
Caution:

- When installing or removing an attachment to/from a finger, tighten the mounting bolts while securely holding the attachment with a spanner wrench, etc., to prevent the guide from receiving any load or impact.
- Some finger attachment profiles may make the grip condition of a workpiece unstable. If a workpiece moves during grip, stress may get applied to the internal structure, which could cause unchucking unavailable (operation not available) or performance drop.



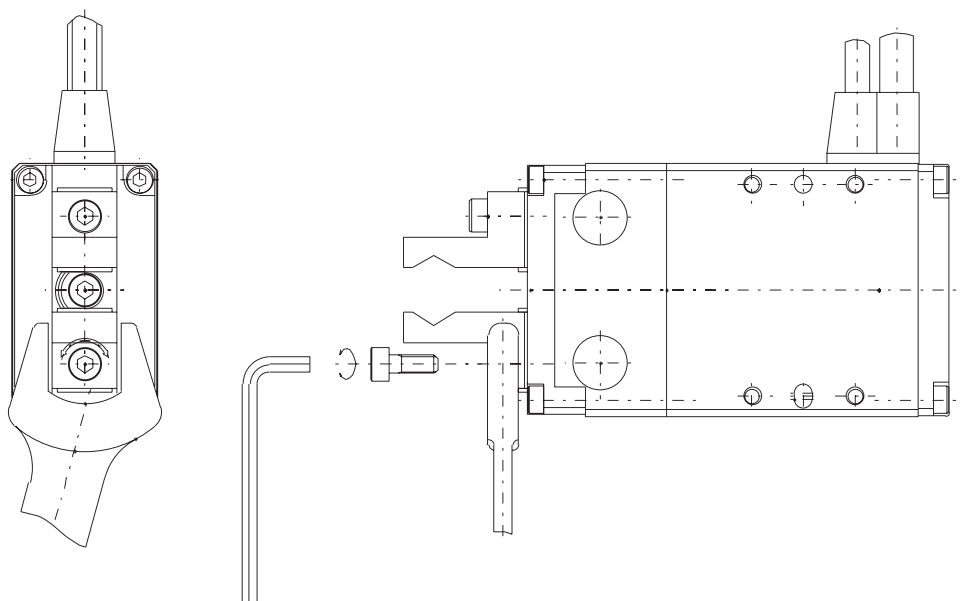
To achieve higher installation precision and repeatability for finger attachments, it is recommended that each finger attachment be positioned by sandwiching the attachment between the positioning pin and the side face of the finger, as illustrated below.

• GRLS



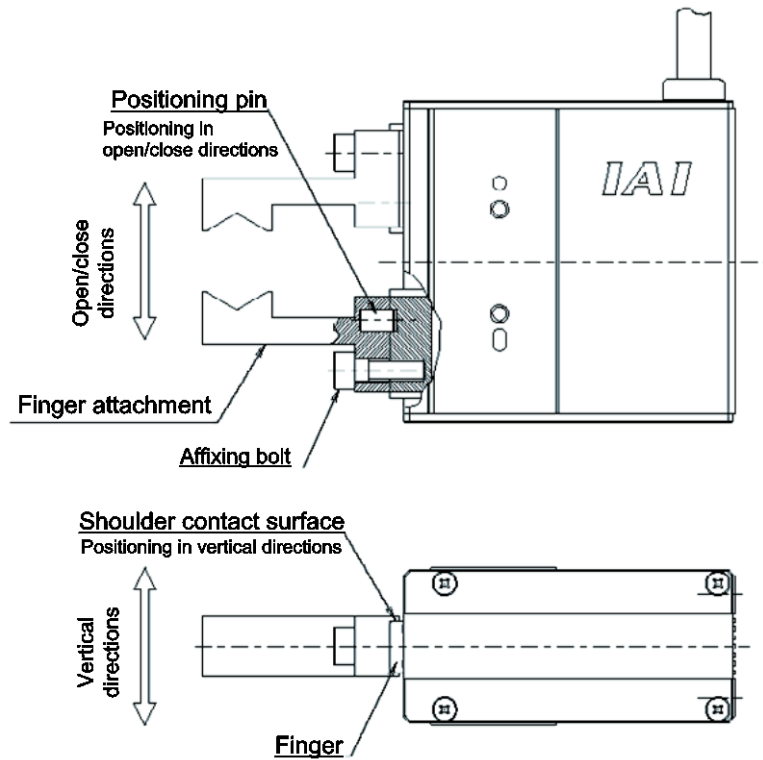
Caution:

- When installing or removing an attachment to/from a finger, tighten the mounting bolts while securely holding the attachment with a spanner wrench, etc., to prevent the guide from receiving any load or impact.
- Some finger attachment profiles may make the grip condition of a workpiece unstable. If a workpiece moves during grip, stress may get applied to the internal structure, which could cause unchucking unavailable (operation not available) or performance drop.



To achieve higher installation precision and repeatability for finger attachments, it is recommended that each finger attachment be positioned by sandwiching the attachment between the positioning pin and the side face of the finger, as illustrated below.

- GRS/GRM

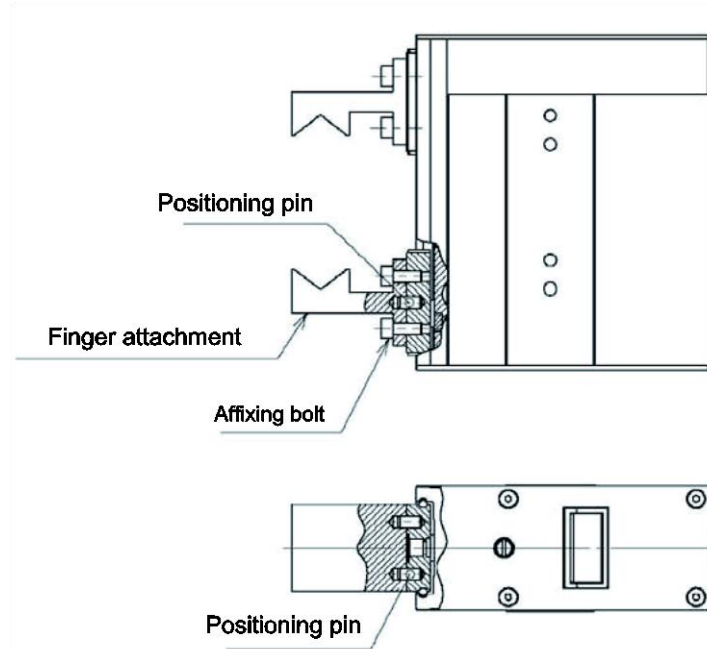


Caution:

- When installing or removing the attachment to/from the finger, tighten the screw while holding the attachment with a spanner wrench, etc., so that the guide will not receive any load or impact.
- The tapping holes are through holes. Never use long screws exceeding the effective thread length. The screws may contact the internal structure, resulting in gripper malfunction or damage to the internal structure.

To achieve higher installation precision and repeatability for finger attachments, it is recommended that each finger attachment be positioned by sandwiching the attachment between the positioning pin and the side face of the finger, as illustrated below.

- GRHM/GRHB

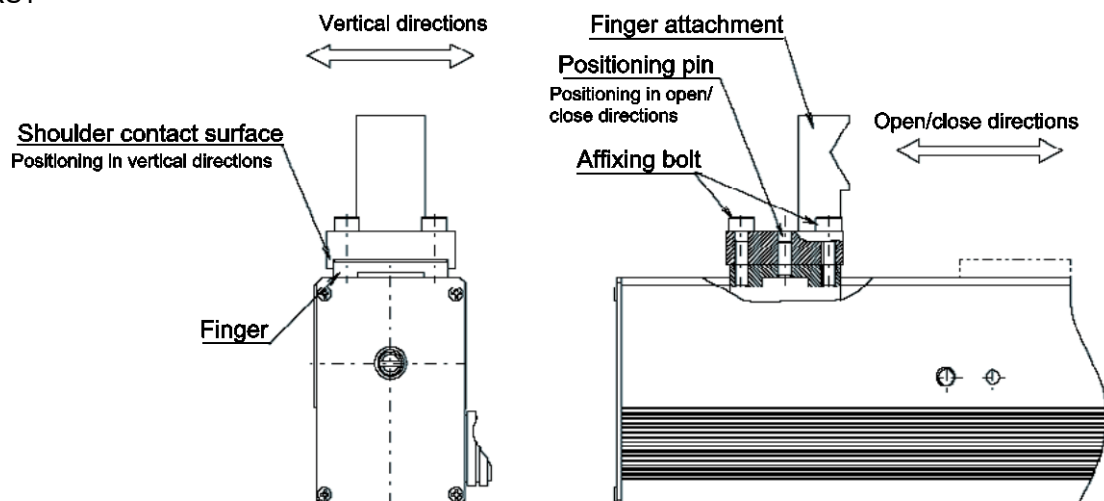


Caution:

- When installing or removing the attachment to/from the finger, tighten the screw while holding the attachment with a spanner wrench, etc., so that the guide will not receive any load or impact.
- The tapping holes are through holes. Never use long screws exceeding the effective thread length. The screws may contact the internal structure, resulting in gripper malfunction or damage to the internal structure.

To achieve higher installation precision and repeatability for finger attachments, it is recommended that each finger attachment be positioned by sandwiching the attachment between the positioning pin and the side face of the finger, as illustrated below.

• GRST

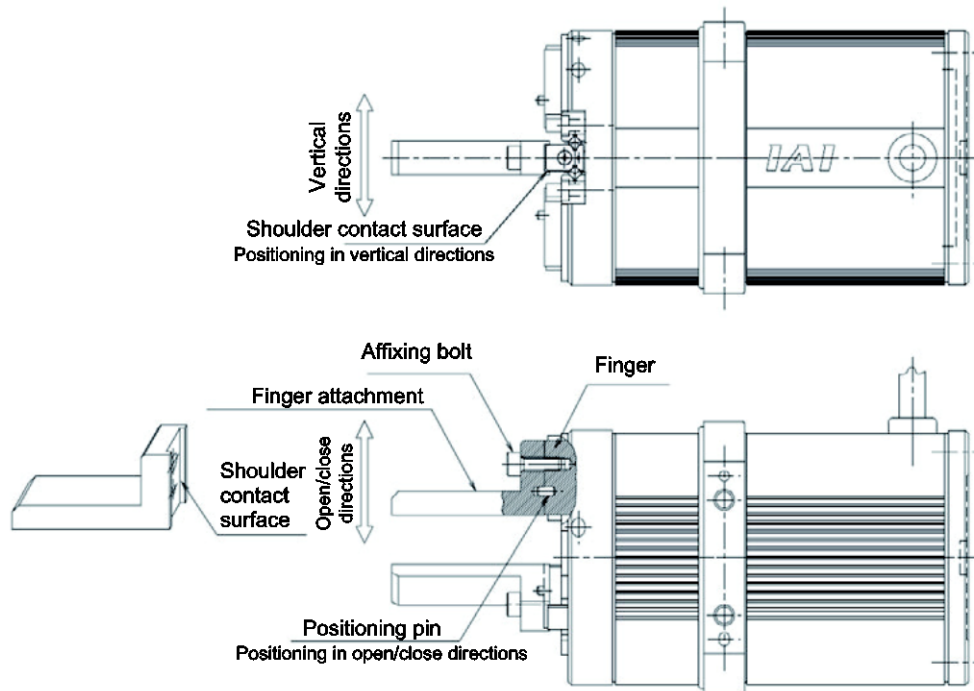


Caution:

- When installing or removing the attachment to/from the finger, tighten the screw while holding the attachment with a spanner wrench, etc., so that the guide will not receive any load or impact.
- The tapping holes are through holes. Never use long screws exceeding the effective thread length. The screws may contact the internal structure, resulting in gripper malfunction or damage to the internal structure.

To achieve higher installation precision and repeatability for finger attachments, it is recommended that each finger attachment be positioned by sandwiching the attachment between the positioning pin and the side face of the finger, as illustrated below.

- GR3SS/GR3SM

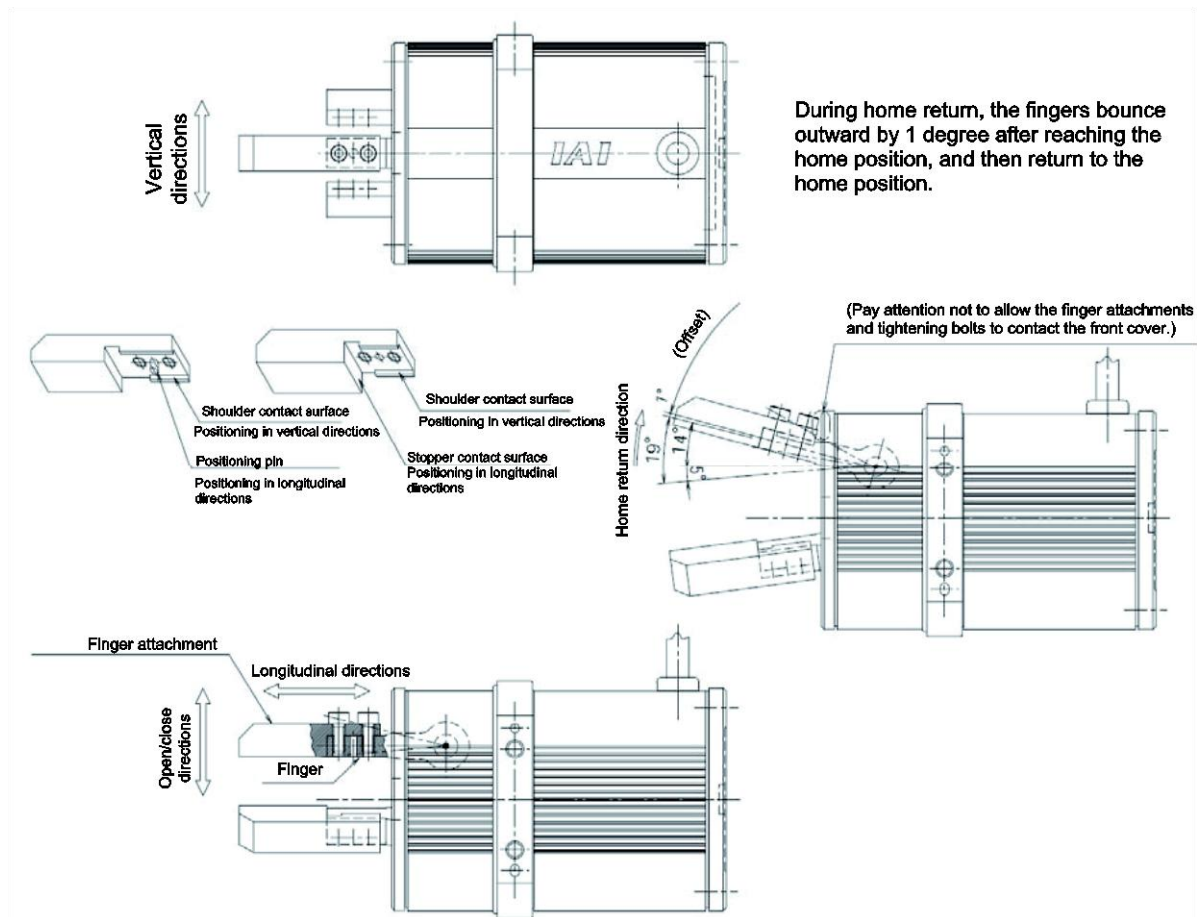


Caution:

- When installing or removing the attachment to/from the finger, tighten the screw while holding the attachment with a spanner wrench, etc., so that the guide will not receive any load or impact.

To achieve higher installation precision and repeatability for finger attachments, it is recommended that each finger attachment be positioned by sandwiching the attachment between the positioning pin and the side face of the finger, as illustrated below.

• GR3LS/GR3LM



Caution:

- When installing or removing the attachment to/from the finger, tighten the screw while holding the attachment with a spanner wrench, etc., so that the guide will not receive any load or impact.

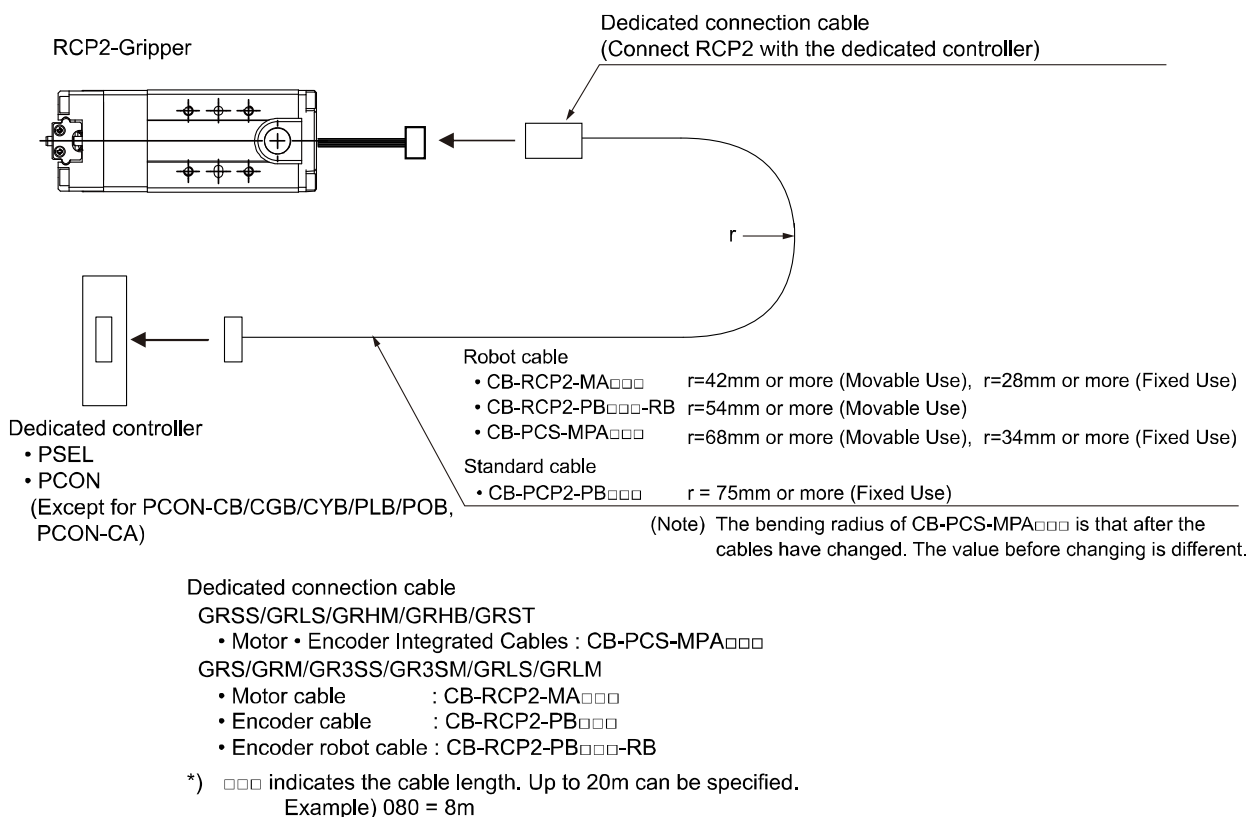
3. Connecting with the Controller

Use the IAI dedicated connection cable for the connection of the actuator to the controller.

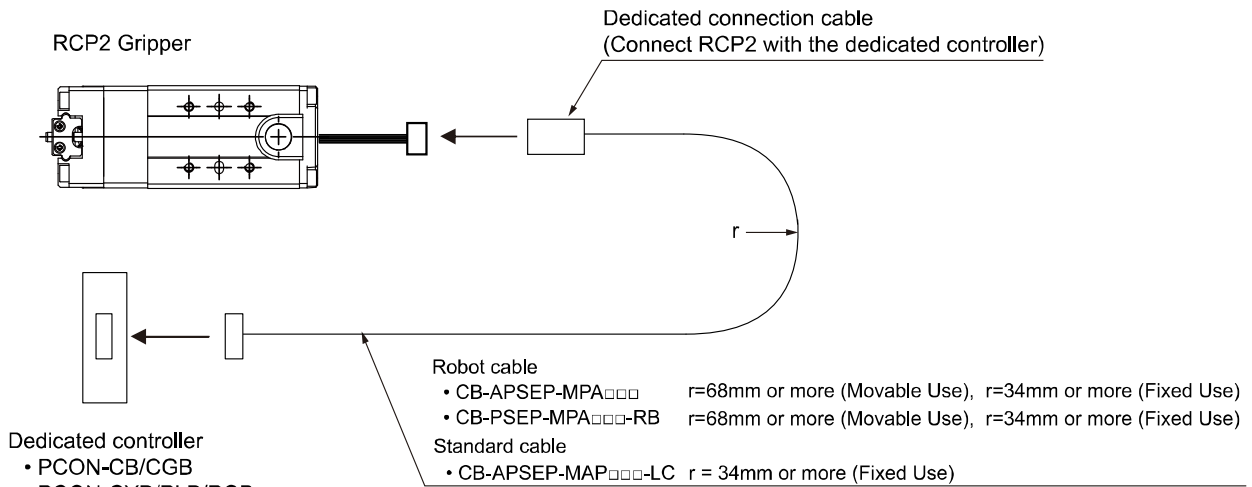
- If the dedicated connection cable cannot be secured, reduce the load on the cable by allowing it to deflect only by the weight of the cable or wire it in a self-standing cable hose, etc., having a large radius.
- Do not cut and reconnect the dedicated connection cable for extension or shorten the cable.
- Do not pull on the dedicated connection cable or bend it forcibly.
- The actuator cable is for fixed use. Fix the cable so it would not be bent repeatedly.

Please consult with IAI if you require a different kind of cable than the one supplied.

(1) For Controllers PSEL and PCON (except for PCON-CB/CGB/CYB/PLB/POB and PCON-CA)



(2) For Controllers PCON-CB/CGB/CYB/PLB/POB, PCON-CA, MSEP, PMEC, PSEP, MCON and MSEL



Dedicated connection cable

RCP2-GRSS/GRLS/GRHM/GRHB/GRST

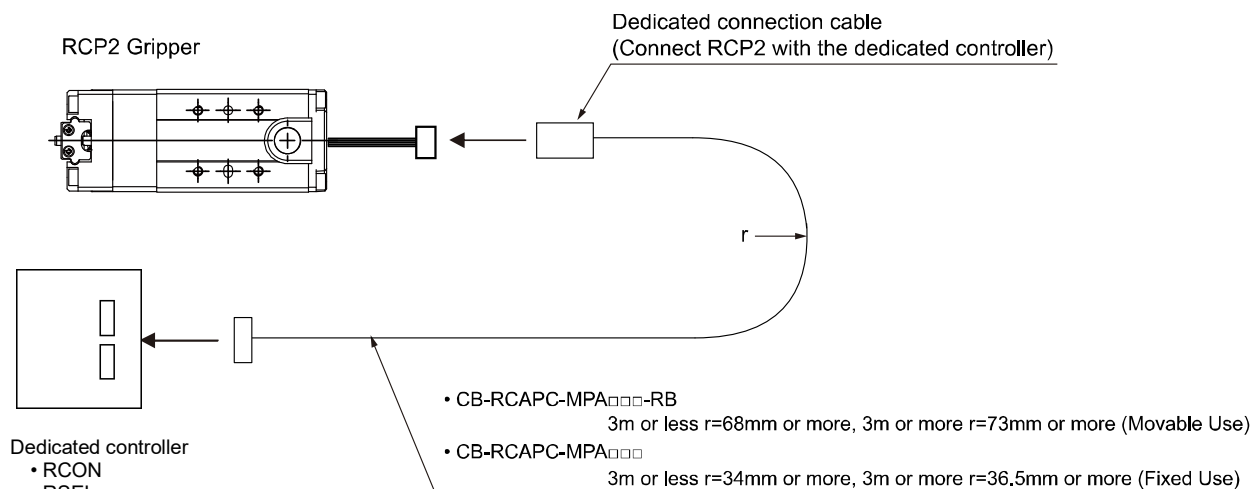
- Motor • Encoder Integrated Robot Cables : CB-APSEP-MPA□□□
- Motor • Encoder Integrated Cables : CB-APSEP-MPA□□□-LC

GRS/GRM/GR3SS/GR3SM/GR3LS/GR3LM

- Motor • Encoder Integrated Robot Cables : CB-PSEP-MPA□□□

*) □□□ indicates the cable length. Up to 20m can be specified.
Example) 080 = 8m

(3) For Controllers RCON, RSEL and RCM-P6PC



Dedicated connection cable

GRSS/GRLS/GRHM/GRHB/GRST

- Motor•Encoder Integrated Cables : CB-RCAPC-MPA□□□
- Motor•Encoder Integrated Robot Cables : CB-RCAPC-MPA□□□-RB

GRS/GRM/GR3SS/GR3SM/GR3LS/GR3LM

Connect the conversion unit RCM-CV-APCS to CB-PSEP-MPA□□□ and Join the following cable to it and then connect it to RCON or RSEL.

- Motor•Encoder Integrated Cables : CB-ADPC-MPA□□□
- Motor•Encoder Integrated Robot Cables : CB-ADPC-MPA□□□-RB
- Motor•Encoder Integrated Cables 4-way connector type : CB-ADPC2-MPA□□□
- Motor•Encoder Integrated Robot Cables 4-way connector type : CB-ADPC2-MPA□□□-RB

*) □□□ indicates the cable length. Up to 20m can be specified.

Example) 080=8m

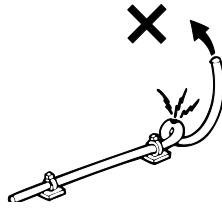
[illegible]

(Note) The figure shows an example shown with CB-RCAPC-MPA□□□.

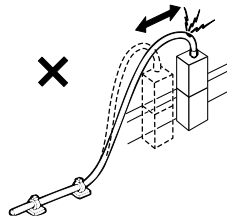
- Have a sufficient radius for bending, and avoid a bend concentrating on one point.



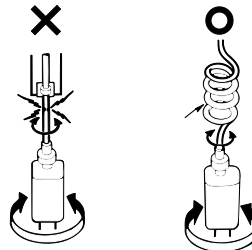
- Do not let the cable bend, kink or twist.



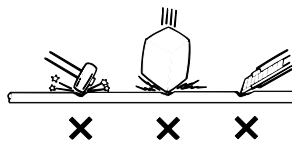
- Do not pull the cable with a strong force.



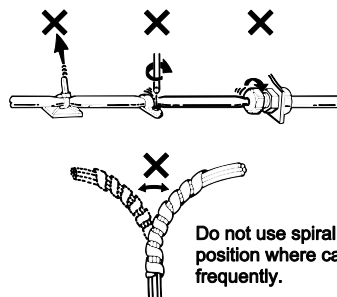
- Pay attention not to concentrate the twisting force to one point on a cable.



- Do not pinch, drop a heavy object onto or cut the cable.

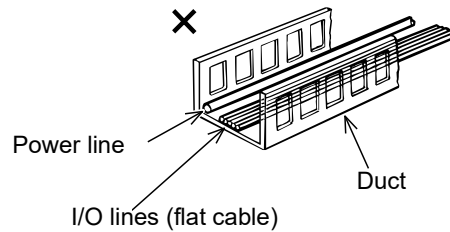


- When a cable is fastened to affix, make sure to have an appropriate force and do not tighten too much.



Do not use spiral tube in any position where cables are bent frequently.

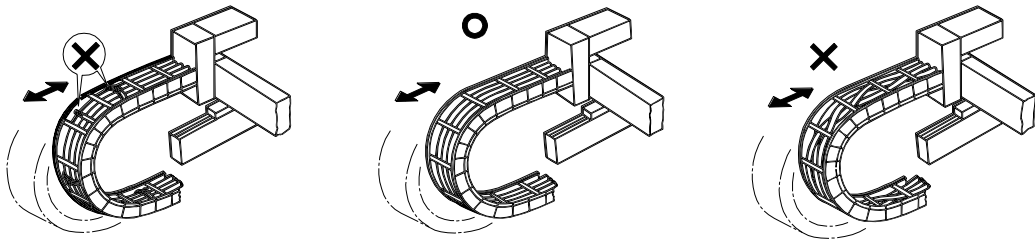
- PIO line, communication line, power and driving lines are to be put separately from each other and do not tie them together. Arrange so that such lines are independently routed in the duct.



Follow the instructions below when using a cable carriers.

- If there is an indication to the cable for the space factor in a cable carriers, refer to the wiring instruction given by the supplier when storing the cable in the cable carriers.
- Avoid the cables to get twined or twisted in the cable carriers, and also to have the cables move freely and do not tie them up. (Avoid tension being applied when the cables are bent.)

Do not pile up cables. It may cause faster abrasion of the sheaths or cable breakage.



4. Operation

4.1 Operation of the Fingers

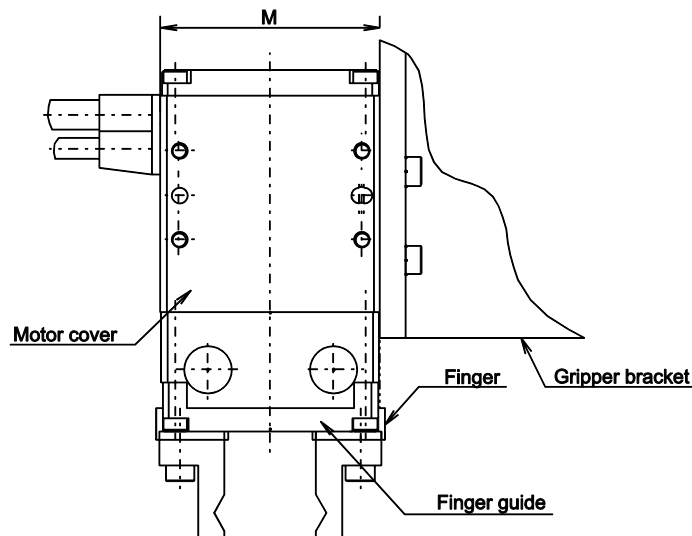
[1] Movement Stroke

The design stroke of the two-finger type is a sum of travel distances of both fingers. The travel distance of one finger is one-half the design stroke.

[2] Home Return Direction

The open side moving end of the finger is the home position. The home position is on the closing end for the home reversed type (NM).

Caution: Finger of GRSS becomes wider than the motor cover width (M) upon home return, so watch out for interference with gripper bracket, etc.



[3] Position Indication

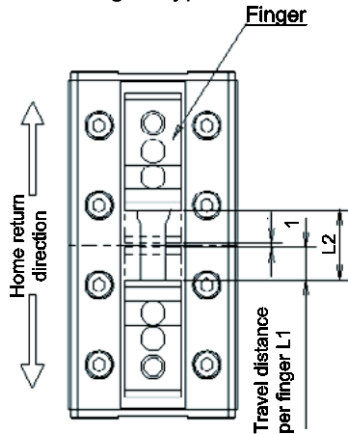
The movement distance from the home position of one finger to the closing side is the position value.

(In the case of Two-finger Type : indication of max. position value = 1/2 of stroke)

[4] Indication of Speed and Acceleration

Speed/acceleration commands are specified based on a value per finger. The relative speed/acceleration of the two-finger type is twice the command value.

• Two-finger Type

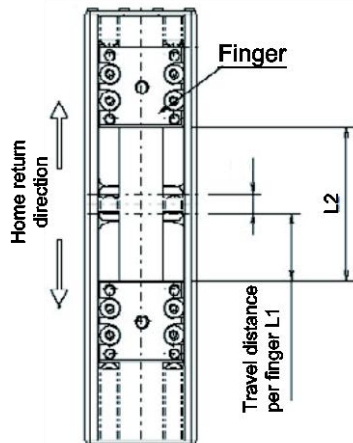


	GRSS	GRLS
Stroke	8 mm	180°
Travel distance per side L1/Angle	4 mm	90°
Distance between fingers L2/Angle	Max. 13.5 mm/ Min. 5.5 mm	Max. 180°/ Min. 0°

	GRM	GRS
Stroke	14 mm	10 mm
Travel distance per side L1	7 mm	5 mm
Distance between fingers L2	Max. 15 mm/ Min. 1 mm	Max. 10 mm/ Min. 1 mm

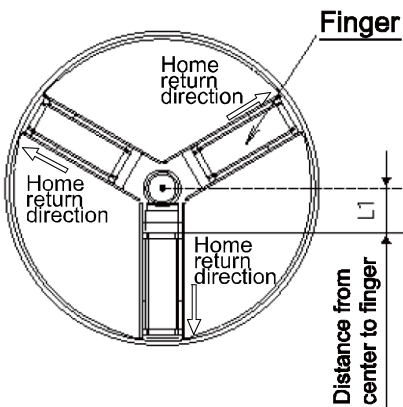
	GRHM	GRHB
Stroke	32 mm	40 mm
Travel distance per side L1	16 mm	20 mm
Distance between fingers L2	Max. 33 mm/ Min. 1 mm	Max. 41 mm/ Min. 1 mm

• Two-finger Long-stroke Type



	GRST
Stroke	40, 60, 80, 100, 120, 150
Travel distance per side L1	20, 30, 40, 50, 60, 75
Distance between fingers L2	Max. 156/ Min. 6 (Stroke 150)

• Three-finger Type



	GR3SM	GR3SS
Stroke	7 mm	5 mm
Distance between fingers	4 mm to 11 mm	4 mm to 9 mm

* Lever types GR3LS and GR3LM of the three-finger type perform the home-return operation to the open directions by 14deg.

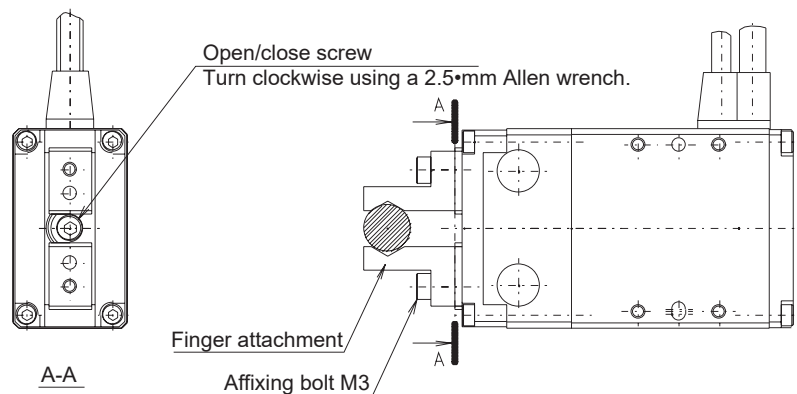
4.2 Removal of Gripped Work Part

This gripper is structured in such a way that the work part-gripping force will be maintained by means of self-lock even after the controller power is cut off.

If the gripped work part must be removed while the controller power is cut off, turn the opening/closing screw or remove the finger attachment on one side to release the work part.

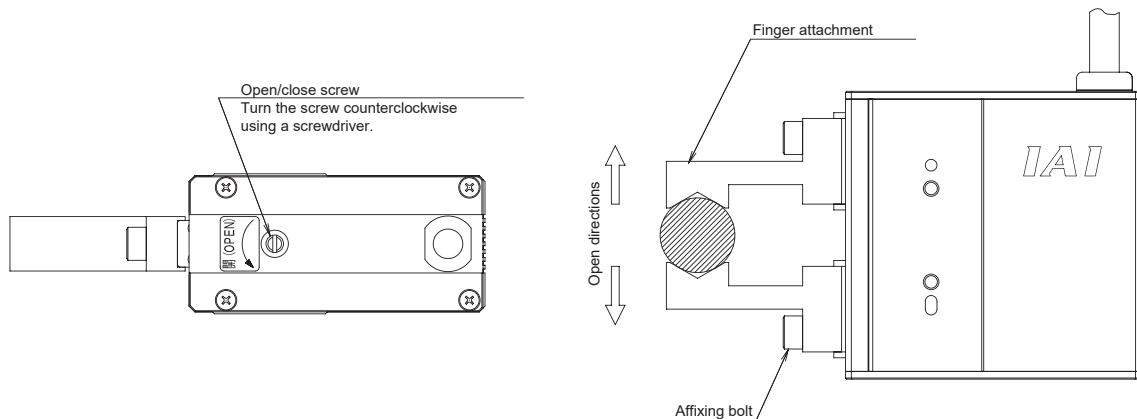
- Small Slim Two-finger Slide Type (GRSS)
- Small Slim Two-finger Lever Type (GRLS)

Turn the opening/closing screw clockwise or remove the finger attachment on one side.



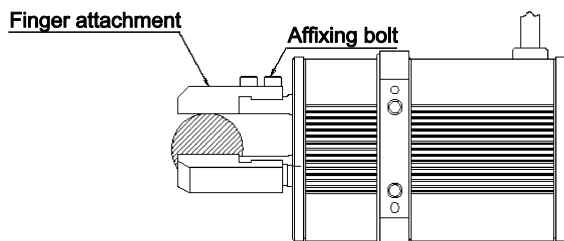
- Small and Medium Two-finger Type (GRS/GRM)
- Two-finger Type with High Gripping Force (GRHM/GRHB)

Turn the opening/closing screw or remove the finger attachment on one side.

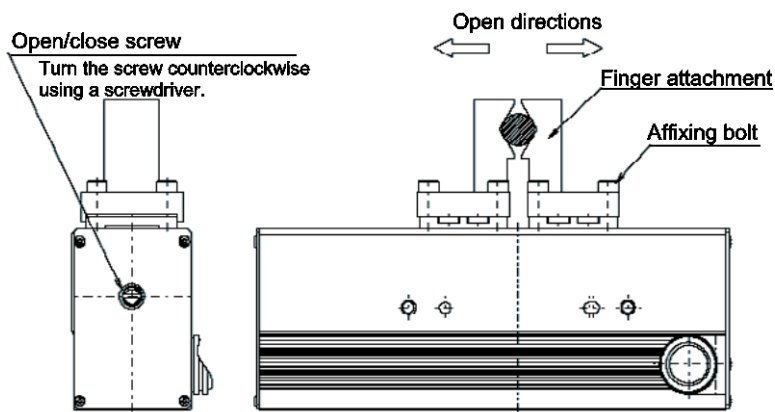


- Three-finger Type (GR3SS/GR3SM, GR3LS/GR3LM)

Remove one finger attachment.



- Two-finger Long-stroke Type (GRST)



Caution:

- If the gripped work part must be removed while the controller power is cut off, turn the opening/closing screw or remove the finger attachment on one side to release the work part. Forcibly pulling the work part out of the fingers may damage the machine.
- Remove the gripped work part if the machine will not be operated for a prolonged period. If the gripper remains stationary for a prolonged period with a work part gripped, the gripper performance may drop or its guide function may be negatively affected.

5. Maintenance and Inspection

5.1 Inspection Items and Schedule

Perform maintenance and inspection at the intervals specified below.

This schedule assumes that the actuator is operated eight hours a day.

If the actuator is operated at a higher utilization, such as when the machine is used continuously day and night, reduce the inspection intervals accordingly.

	Visual inspection of exterior	Greasing
Start-up inspection	○	
After 1 month of operation	○	
After 6 months of operation	○	○
After 1 year of operation	○	
Every 6 months thereafter	○	○
Every 1 year	○	

* Any adjustments requiring the following operations must be carried out at our factory. Do not disassemble the gripper or cut any of its cables in the location where the gripper is installed.

- Disassemble the motor
- Disassembly of guide
- Disassembly of finger feed mechanism
- Disassemble the bearing
- Cut a cable

If the user has disassembled any of the above components or cut any of the gripper's cables, IAI will not be responsible for any malfunction or problem that may occur thereafter.

Caution:

- Performing inspection or maintenance work part without a thorough understanding of the specific tasks involved may result in a serious accident.
- If inspection is not carried out regularly, the drive part may reach its life prematurely.

5.2 Visually Inspecting the Exterior

Visually check the exterior of the following items.

Actuator	Loosening of actuator mounting screws
Cables	Scratches, connector engagement
Overall	Noise, vibration

5.3 Exterior Cleaning

- Clean the exterior surface as necessary.
- Wipe dirty areas using a soft cloth, etc.
- Do not blow highly compressed air onto the actuator, as it may cause dust to enter the actuator through gaps between parts.
- Do not use petroleum-based solvent as it damages resin and coated surfaces.
- To remove stubborn stains, take neutral detergent or alcohol into a soft cloth, etc., and wipe the area gently.

5.4 Grease Supply for Two-Fingered Small Slim Type, Small Type and Medium Type

5.4.1 Guide, Finger and Finger Guide

Applicable models for grease supply on fingers and finger guides : GRSS, GRS, GRM

[1] Applicable Greases

IAI uses the following grease in our plant.

Idemitsu Kosan	Daphne Grease MP No. 2
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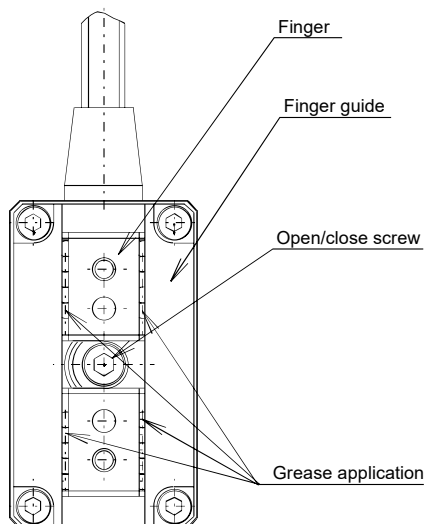
Other companies also sell similar types of grease. For details, give the above grease name to the manufacturer you want to purchase from and ask what corresponding product they have available.

Use lithium spray grease during maintenance. Take note that grease should not be sprayed for more than 1 second.

WAKO CHEMICAL, LTD.	Spray Grease No. A161 or equivalent
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[2] How to Apply Grease

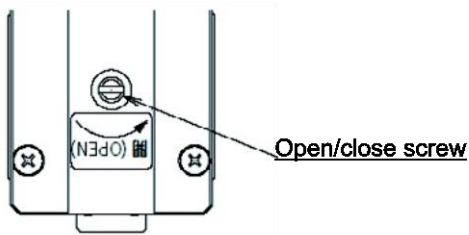
- Small Slim Two-finger Slide Type (GRSS)
- Small Slim Two-finger Lever Type (GRLS)



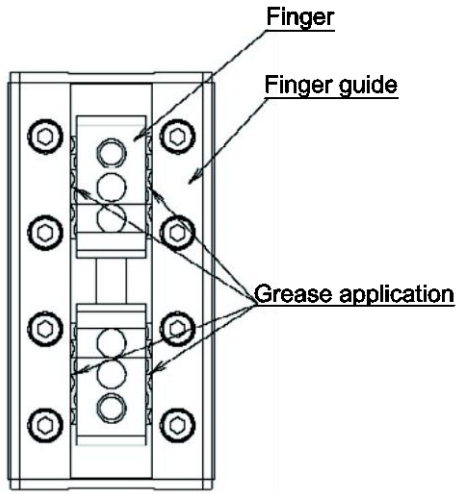
- 1) Using a 2.5-mm Allen wrench, turn the opening/closing screw at the center of the fingers to move the fingers toward the stroke center.
- 2) Using a grease spray gun, apply grease (on the steel balls) between the fingers and finger guides. (Spray grease in four locations for less than 1 second each.) After spraying, turn the opening/closing screw to move the fingers back and forth several times to spread the grease evenly. Remove excess grease or grease spatters in surrounding areas.
- 3) Spread out the grease evenly on the fingers and finger guides with hand for GRSS (for rust prevention treatment)

Caution: In case the grease got into your eye, immediately go to see the doctor to get an appropriate care. After finishing the grease supply work, wash your hands carefully with water and soap to rinse the grease off.

• Small and Medium Two-finger Type (GRS/GRM)



- 1) Use a flathead screwdriver to turn the opening/closing screw on side cover L to move the fingers toward the stroke center.



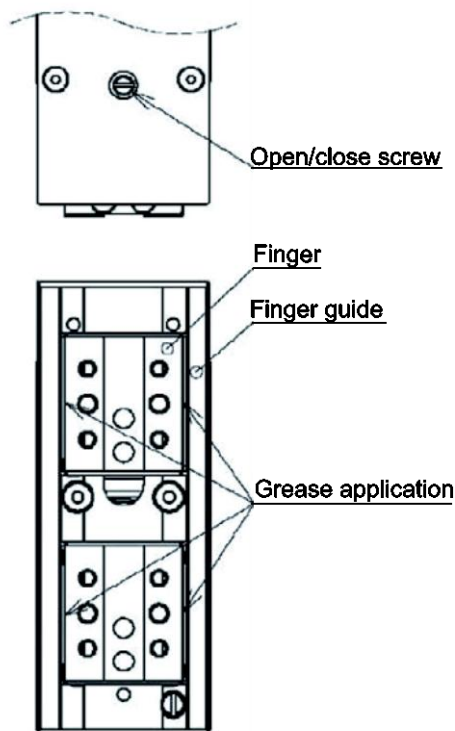
- 2) Spray grease in the gap (on the steel balls) between the finger and finger guide (4 locations; keep the spray time to a maximum of 1 second at each location). After spraying, turn the opening/closing screw to move the fingers back and forth several times to spread the grease evenly. Remove excess grease or grease spatters in surrounding areas.

- 3) Spread out the grease evenly on the fingers and finger guides with hand (for rust prevention treatment)

Caution:

- Never use fluorine grease. If fluorine grease is mixed with lithium grease, the lubricating function of grease will drop and the machine may suffer damage due to increased friction.
- Do not use spray oil. Be sure to use spray grease. Keep the spray time to a maximum of 1 second, and never spray more than once. If too much grease is applied, excess grease may flow into the electronic components and cause malfunction.
- In case the grease got into your eye, immediately go to see the doctor to get an appropriate care. After finishing the grease supply work, wash your hands carefully with water and soap to rinse the grease off.

• Two-finger Type with High Gripping Force (GRHM/GRHB)



1) Use a flathead screwdriver to turn the opening/closing screw on side cover to move the fingers toward the stroke center.

2) Spray grease in the gap (on the steel balls) between the finger and finger guide (4 locations; keep the spray time to a maximum of 1 second at each location). After spraying, turn the opening/closing screw to move the fingers back and forth several times to spread the grease evenly. Remove excess grease or grease spatters in surrounding areas.

Caution:

- Never use fluorine grease. If fluorine grease is mixed with lithium grease, the lubricating function of grease will drop and the machine may suffer damage due to increased friction.
- Do not use spray oil. Be sure to use spray grease. Keep the spray time to a maximum of 1 second, and never spray more than once. If too much grease is applied, excess grease may flow into the electronic components and cause malfunction.
- In case the grease got into your eye, immediately go to see the doctor to get an appropriate care. After finishing the grease supply work, wash your hands carefully with water and soap to rinse the grease off.

5.5 Feed Screw Small and Medium Two-finger Type (GRS/GRM)

[1] Applicable Greases

IAI uses the following grease in our plant.

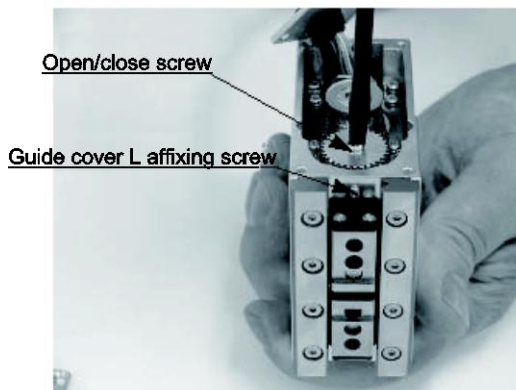
Idemitsu Kosan	Daphne Grease MP No. 2
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Use lithium spray grease during maintenance. Take note that grease should not be sprayed for more than 1 second.

WAKO CHEMICAL, LTD.	Spray Grease No. A161 or equivalent
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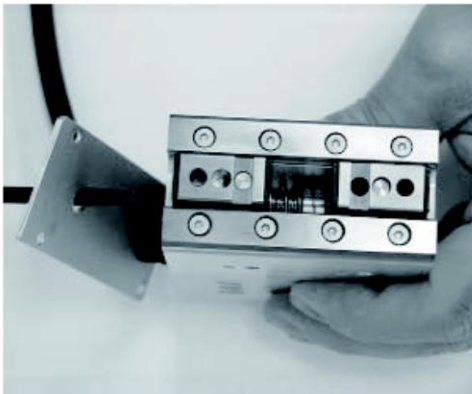
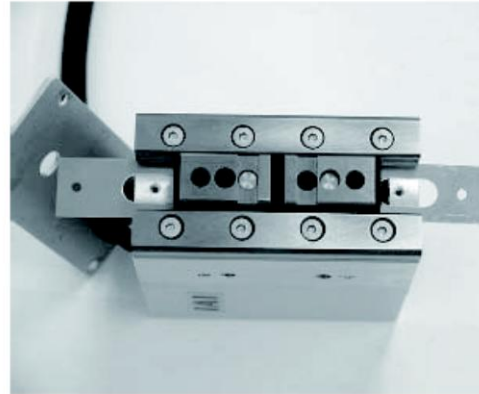
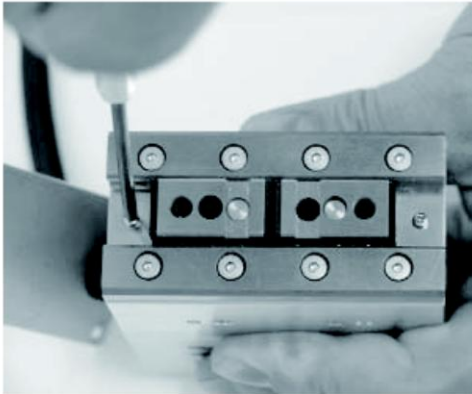
[2] How to Apply Grease

- 1) Remove the screws affixing side cover R and side cover L (countersunk head screw M2.6 × 6).
Remove side cover R.
Separate side cover L from the gripper frame. (The cover is still connected via internal cables. Do not pull the internal cables.)



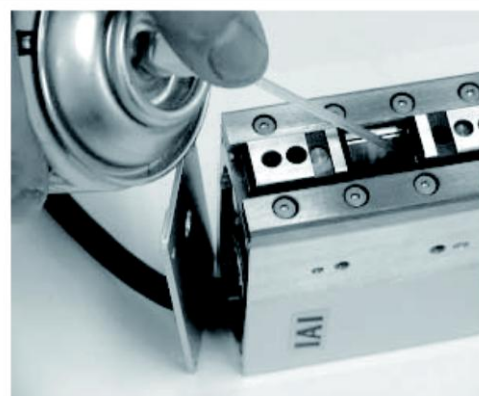
- 2) Turn the opening/closing screw on side cover L to move the fingers toward the closing side until the guide cover R/L affixing screws are visible.

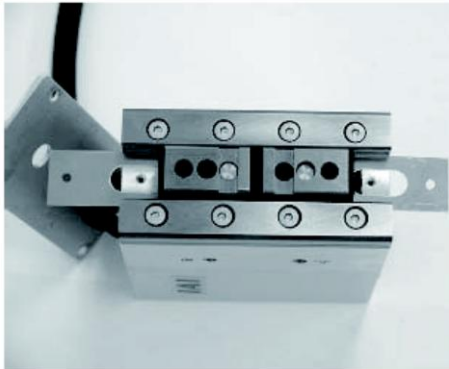
- 3) Remove screws affixing guide covers R and L (2 pieces on each side). Slide the guide covers horizontally to the opening side and remove. (Countersunk head screw M2 × 3)
 Note: The cutout dimensions are different between guide covers R and L. Keep the removed guide covers properly so that they will not be mixed up when installed.



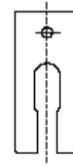
- 4) Use a flathead screwdriver to turn the opening/closing screw on side cover L to move the fingers toward the opening side.

- 5) From the opening, spray grease over the feed screw at 2 locations through the springs (keep the spray time to a maximum of 1 second). After spraying, turn the opening/closing screw to move the fingers back and forth several times to spread the grease evenly.

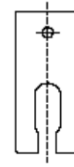




- 6) Move the fingers to the closing side. Insert the guide covers from sides and affix with screws. Insert guide covers R and L on the correct sides.



Guide cover R



Guide cover L



- 7) Install and securely affix side covers R and L. When affixing side cover L, be careful not to pinch the cables.

Caution:

- Never use fluorine grease. If fluorine grease is mixed with lithium grease, the lubricating function of grease will drop and the machine may suffer damage due to increased friction.
- Do not use spray oil. Be sure to use spray grease. Keep the spray time to a maximum of 1 second, and never spray more than once. If too much grease is applied, excess grease may flow into the electronic components and cause malfunction.
- In case the grease got into your eye, immediately go to see the doctor to get an appropriate care. After finishing the grease supply work, wash your hands carefully with water and soap to rinse the grease off.

5.6 Two-finger Type with High Gripping Force (GRHM/GRHB)

[1] Applicable Greases

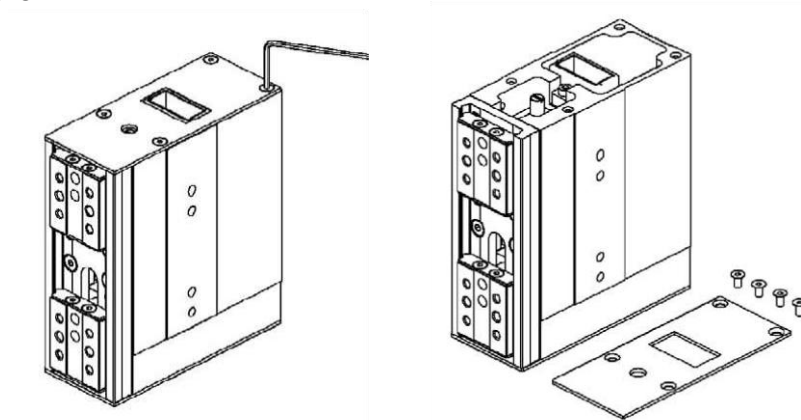
Synthetic poly- α olefin grease has been charged to the feed screw prior to shipment.

The following grease is applied to the feed screw before the gripper is shipped from the factory.

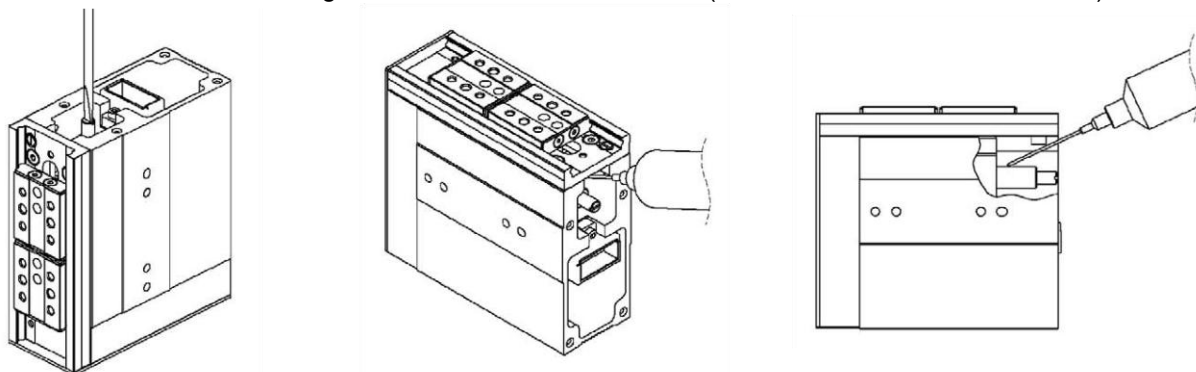
Lubricant by Sumitomo Metal Mining	Sumitec 308
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Other manufacturers also offer equivalent products, but exercise caution when using a different product because the life of the actuator may be affected depending on the selected grease.

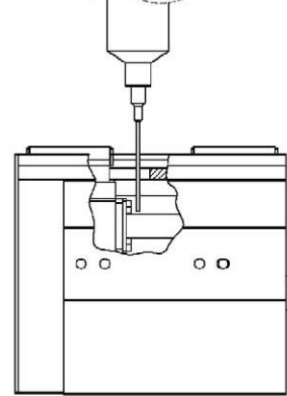
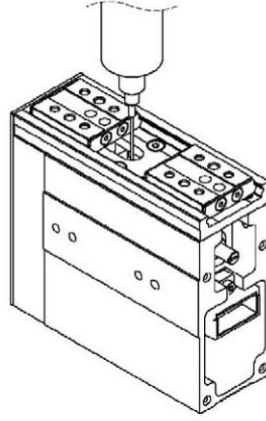
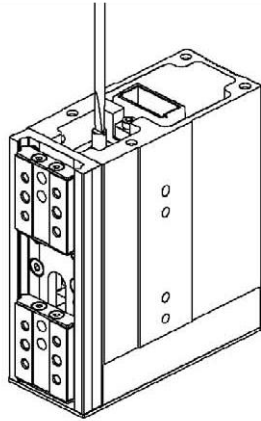
[2] How to apply grease



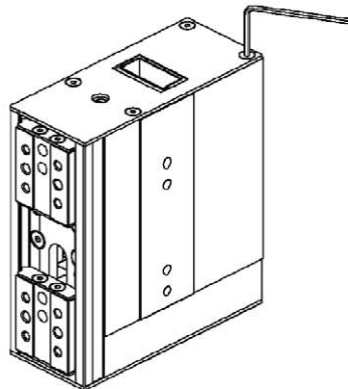
- 1) Remove the screws affixing side cover R and side cover R (countersunk head screw M3 × 6).



- 2) Turn the opening/closing screw to move the fingers to their stroke ends on the closed side.
- 3) Use a grease syringe to charge grease from the opening on the right side so as to coat the feed screw with grease. After the feed screw has been coated with grease roughly, turn the opening/closing screw to move the fingers back and forth several times to spread grease evenly.



- 4) Turn the opening/closing screw to move the fingers to their stroke ends on the open side.
- 5) Use a grease syringe to charge grease from the opening on the bottom face of the guide base so as to coat the feed screw with grease. After the feed screw has been coated with grease roughly, turn the opening/closing screw to move the fingers back and forth several times to spread grease evenly.



- 6) Install and securely affix side cover R.

Caution:

- Never use grease other than synthetic poly- α olefin grease. If synthetic poly- α olefin grease is mixed with other type of grease, not only the mixed grease will lose its intended function, but the actuator may also suffer damage depending on the situation.
- In case the grease got into your eye, immediately go to see the doctor to get an appropriate care. After finishing the grease supply work, wash your hands carefully with water and soap to rinse the grease off.

5.7 Greasing the Two-finger Long-stroke Type (GRST)

5.7.1 Greasing to the Feed Screw (Worm/Rack Gears)

[1] Applicable Greases

The following grease is applied to the guide before the gripper is shipped from the factory.

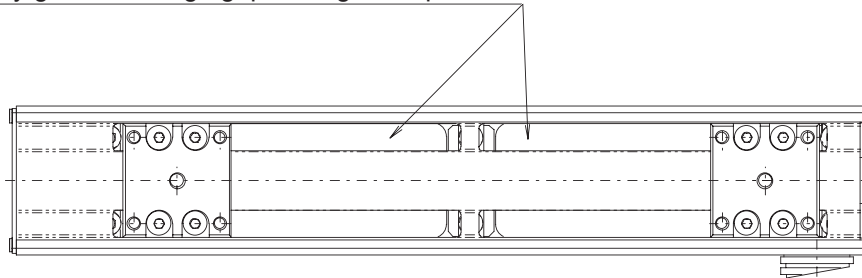
Idemitsu Kosan	Daphne Grease MP No. 2
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During maintenance, use spray-type lithium grease. Do not spray grease for more than 1 second.

WAKO CHEMICAL, LTD.	Spray Grease No. A161 or equivalent
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[2] How to Apply Grease

Apply grease through gaps along the top cover.



- 1) Turn the opening/closing screw with a screwdriver to move the fingers toward their homes.
- 2) Spray grease toward the worm gears through gaps along the top cover. (Do not spray more than 1 second on the left and right.)
- 3) Turn the opening/closing screw using a screwdriver to move the fingers in the directions opposite their homes (toward the stroke center).
- 4) Spray grease in the same manner as in 2).
- 5) After grease has been applied, turn the opening/closing screw to move the fingers back and forth several times to spread the grease evenly

Caution:

- Never use fluorine grease. If fluorine grease is mixed with lithium grease, the lubricating function of grease will drop and the machine may suffer damage due to increased friction.
- Do not use spray oil. Be sure to use spray grease. Keep the spray time to a maximum of 1 second, and never spray more than once. If too much grease is applied, excess grease may flow into the electronic components and cause malfunction.
- In case the grease got into your eye, immediately go to see the doctor to get an appropriate care. After finishing the grease supply work, wash your hands carefully with water and soap to rinse the grease off.

5.7.2 Greasing to the Guide

[1] Applicable Greases

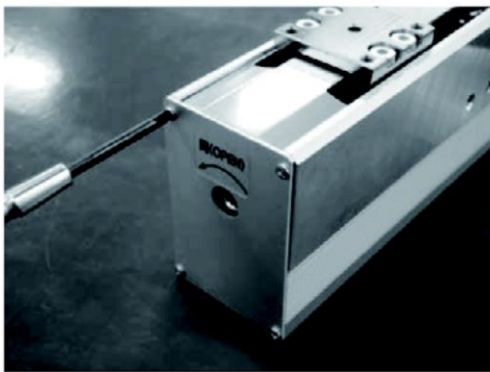
The following grease is applied to the guide before the gripper is shipped from the factory.

Idemitsu Kosan	Daphne Grease MP No. 2
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During maintenance, use spray-type lithium grease. Do not spray grease for more than 1 second.

WAKO CHEMICAL, LTD.	Spray Grease No. A161 or equivalent
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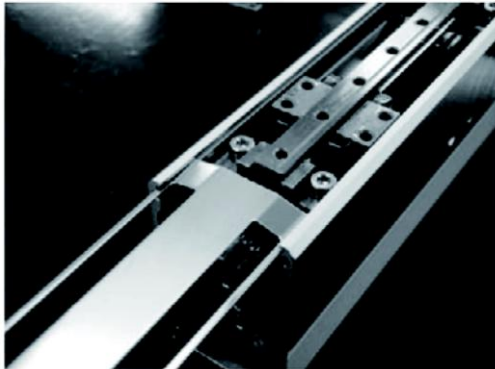
[2] How to Apply Grease



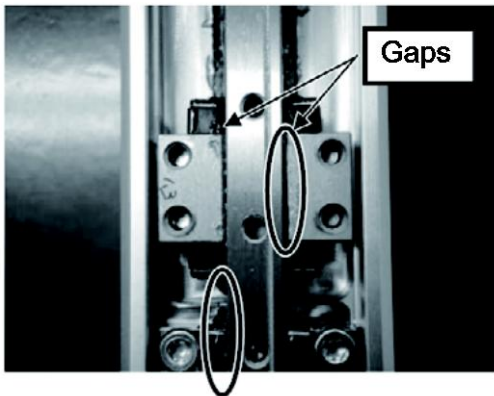
- 1) Remove the affixing screws from the side cover P.
(Cross-recessed head machine screw for precision equipment M2 × 4)



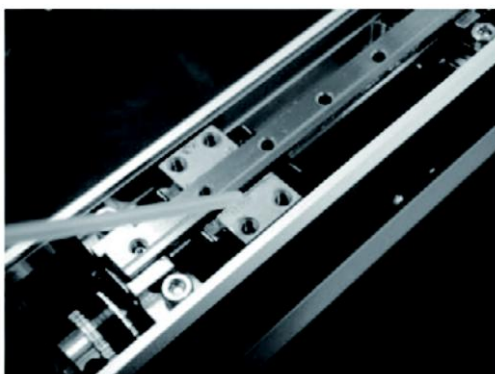
- 2) Remove the affixing screws from the fingers L/R.
(Low hexagonal head socket bolts M3 × 6)



- 3) Slide the top cover and pull it out.



- 4) Spray grease into the gaps along the LM guide. Apply grease at a total of four locations on the left and right guide blocks. Do not spray grease for more than 1 second in each location.



- 5) After grease has been applied, turn the opening/closing screw to move the fingers back and forth several times to spread the grease evenly. Wipe off excess grease or grease that has scattered.
- 6) Install the top cover, fingers L/R and side cover P you have removed earlier.

Caution:

- Never use fluorine grease. If fluorine grease is mixed with lithium grease, the lubricating function of grease will drop and the machine may suffer damage due to increased friction.
- Do not use spray oil. Be sure to use spray grease. Keep the spray time to a maximum of 1 second, and never spray more than once. If too much grease is applied, excess grease may flow into the electronic components and cause malfunction.
- In case the grease got into your eye, immediately go to see the doctor to get an appropriate care. After finishing the grease supply work, wash your hands carefully with water and soap to rinse the grease off.

5.8 Grease Supply for Three-Fingered Slide Type (GR3SS/GR3SM)

5.8.1 Greasing the Guide, Finger and Finger Guide

[1] Applicable Greases

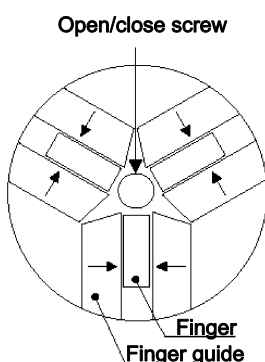
IAI uses the following grease in our plant.

Idemitsu Kosan	Daphne Grease MP No. 2
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Use lithium spray grease. Take note that grease should not be sprayed for more than 1 second.

WAKO CHEMICAL, LTD.	Spray Grease No. A161 or equivalent
---------------------	-------------------------------------

[2] How to apply grease



- 1) Use a flathead screwdriver to turn the opening/closing screw located deep at the center clockwise to move the levers toward the ends of their respective strokes.
- 2) Spray grease in the gap (on the steel balls) between the finger and finger guide (6 locations; keep the spray time to a maximum of 1 second at each location). After spraying, turn the opening/closing screw to move the fingers back and forth several times to spread the grease evenly.
Remove excess grease or grease spatters in surrounding areas.
- 3) Spread out the grease evenly on the fingers and finger guides with hand (for rust prevention treatment)

5.8.2 Greasing the Gears

[1] Applicable Greases

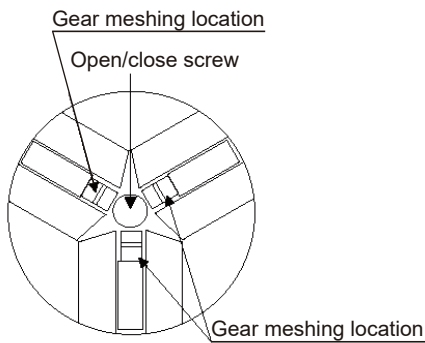
IAI uses the following grease in our plant.

Idemitsu Kosan	Daphne Grease MP No. 2
----------------	------------------------

Use lithium spray grease. Take note that grease should not be sprayed for more than 1 second.

WAKO CHEMICAL, LTD.	Spray Grease No. A161 or equivalent
---------------------	-------------------------------------

[2] How to apply grease



- 1) Use a flathead screwdriver to turn the opening/closing screw located deep at the center clockwise to move the fingers toward the ends of their respective strokes.
- 2) Spray grease at the gear meshing locations (3 locations; keep the spray time to a maximum of 1 second at each location).
After spraying, turn the opening/closing screw to move the fingers back and forth several times to spread the grease evenly. Remove excess grease or grease spatters in surrounding areas.

Caution:

- Never use fluorine grease. If fluorine grease is mixed with lithium grease, the lubricating function of grease will drop and the machine may suffer damage due to increased friction.
- Do not use spray oil. Be sure to use spray grease. Keep the spray time to a maximum of 1 second, and never spray more than once. If too much grease is applied, excess grease may flow into the electronic components and cause malfunction.
- In case the grease got into your eye, immediately go to see the doctor to get an appropriate care. After finishing the grease supply work, wash your hands carefully with water and soap to rinse the grease off.

5.9 Grease Supply for Three-Fingered Lever Type (GR3LS/GR3LM)

5.9.1 Greasing the Gears

[1] Applicable Greases

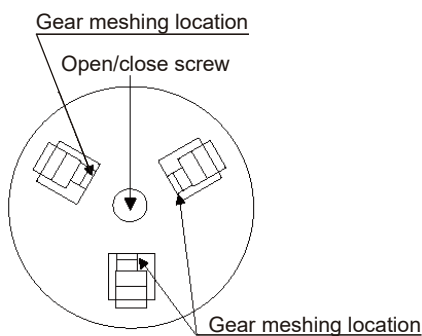
IAI uses the following grease in our plant.

GearsKyodo Yushi	Multemp AC-D
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Use lithium spray grease. Take note that grease should not be sprayed for more than 1 second.

WAKO CHEMICAL, LTD.	Spray Grease No. A161 or equivalent
---------------------	-------------------------------------

[2] How to apply grease



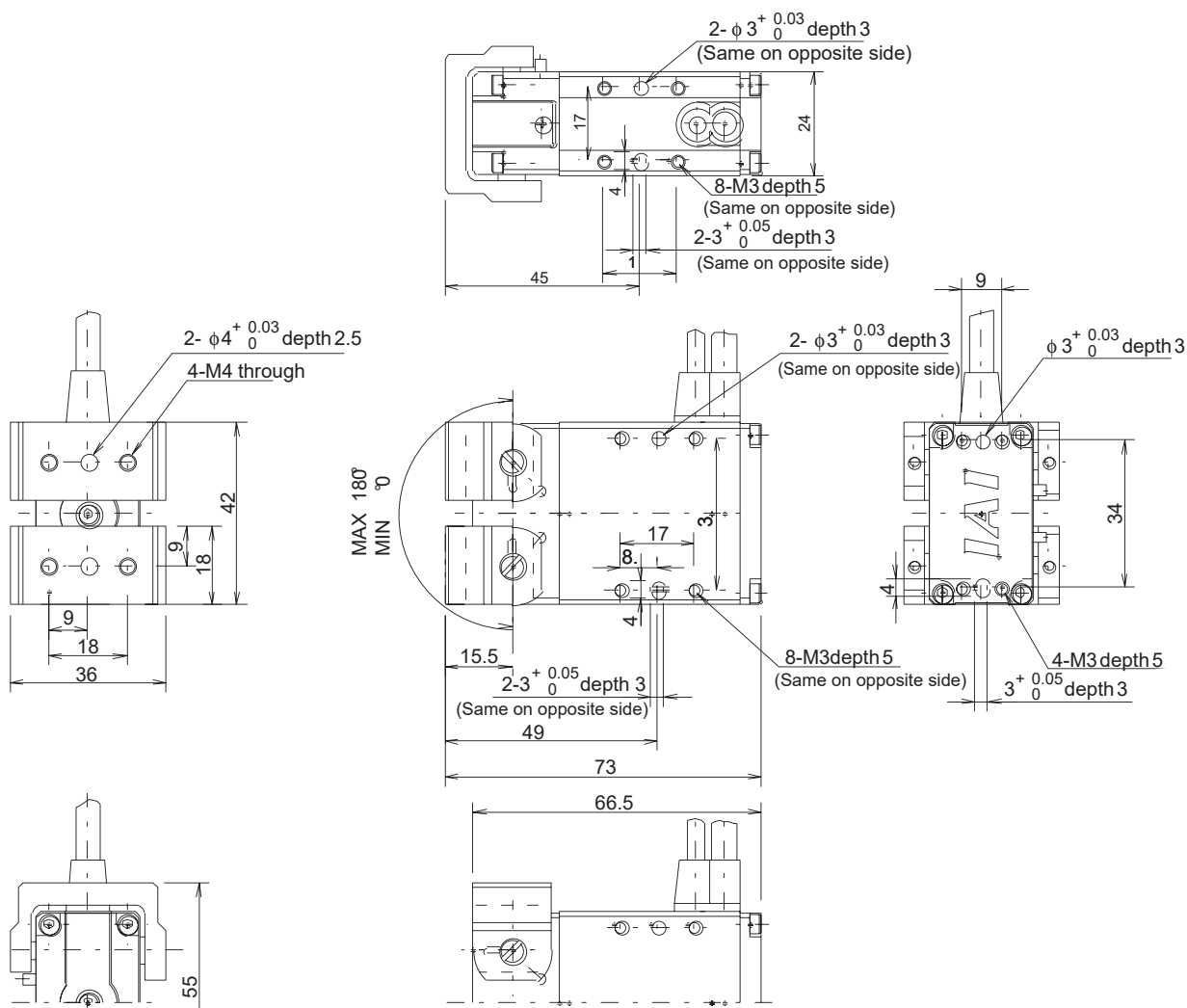
- 1) Use a flathead screwdriver to turn the opening/closing screw located deep at the center clockwise to move the levers toward the ends of their respective strokes.
- 2) Spray grease at the gear meshing locations (3 locations; keep the spray time to a maximum of 1 second at each location).
After spraying, turn the opening/closing screw to move the levers back and forth several times to spread the grease evenly. Remove excess grease or grease spatters in surrounding areas.

Caution:

- Never use fluorine grease. If fluorine grease is mixed with lithium grease, the lubricating function of grease will drop and the machine may suffer damage due to increased friction.
- Do not use spray oil. Be sure to use spray grease. Keep the spray time to a maximum of 1 second, and never spray more than once. If too much grease is applied, excess grease may flow into the electronic components and cause malfunction.
- In case the grease got into your eye, immediately go to see the doctor to get an appropriate care. After finishing the grease supply work, wash your hands carefully with water and soap to rinse the grease off.

6.2 GRLS

6. External Dimensions

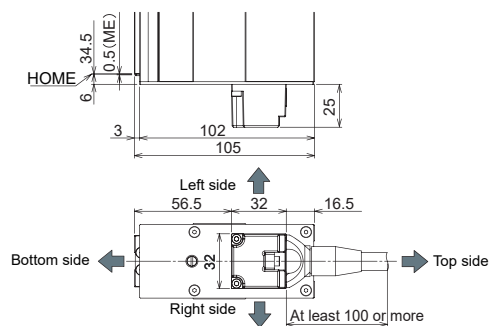


Mass [kg]	0.2
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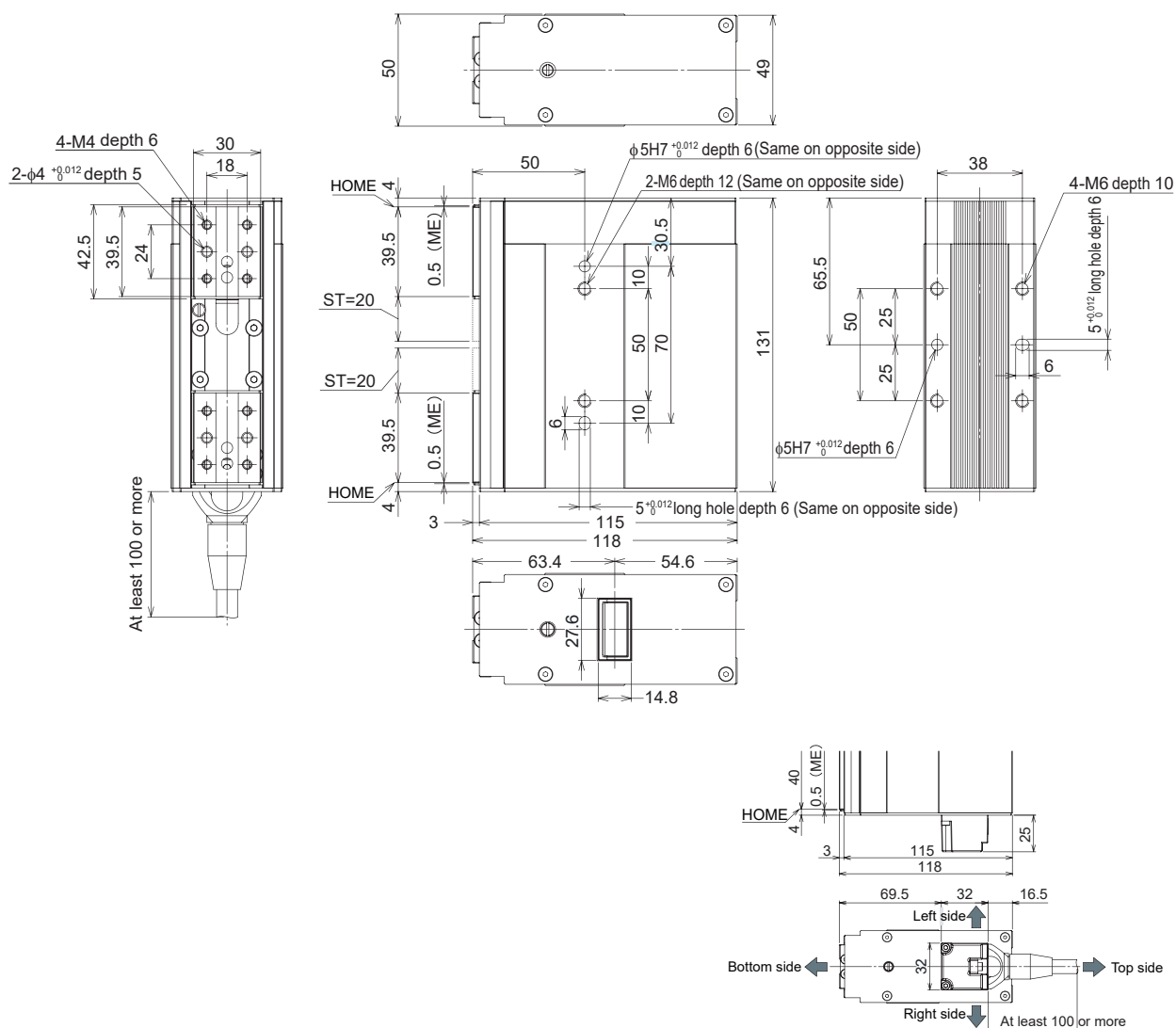
6. External Dimensions

Mass [kg]

6. External Dimensions

119

6.6 GRHB



6.7 GRST

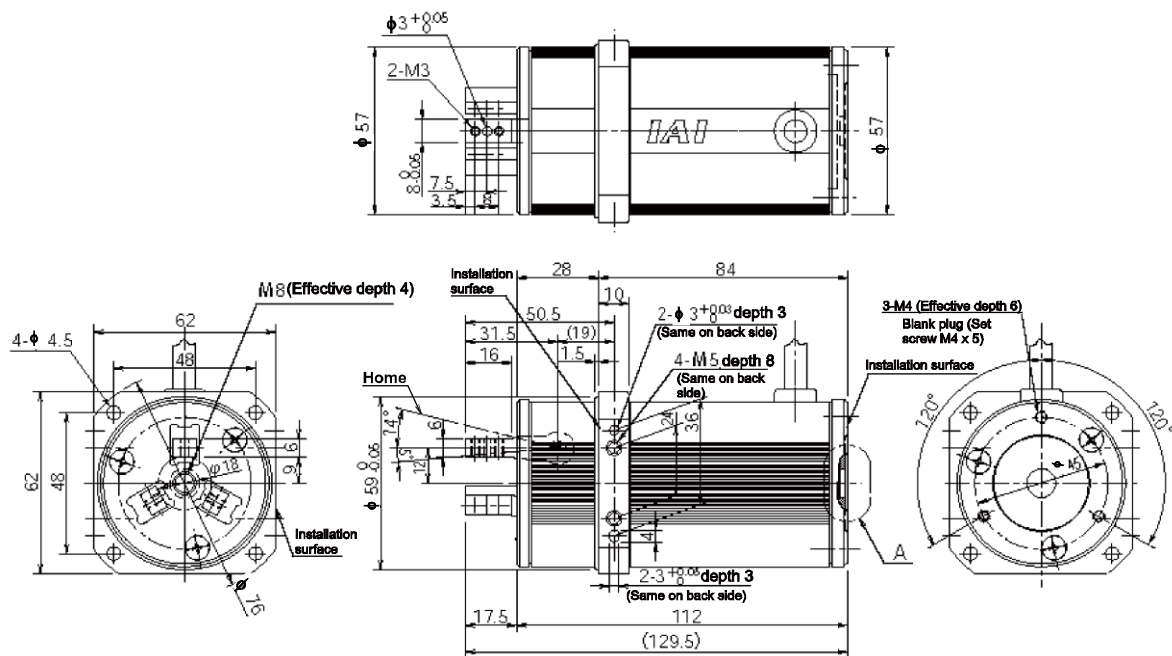
6. External Dimensions

Stroke	40	60	80	100	120	150
L	130	150	170	190	210	240
M	71.5	81.5	91.5	101.5	111.5	126.5
N	57.5	67.5	77.5	87.5	97.5	112.5
Mass [kg]	0.51	0.56	0.61	0.66	0.71	0.78

[illegible]

Mass [kg]	0.6
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6.10 GR3LS



Mass [kg]	0.6
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7. Warranty

7.1 Warranty Period

One of the following periods, whichever is shorter:

- 18 months after shipment from our company
- 12 months after delivery to the specified location
- 2,500 operational hours

7.2 Scope of Warranty

Our products are covered by warranty when all of the following conditions are met. Faulty products covered by warranty will be replaced or repaired free of charge:

- (1) The breakdown or problem in question pertains to our product as delivered by us or our authorized dealer.
- (2) The breakdown or problem in question occurred during the warranty period.
- (3) The breakdown or problem in question occurred while the product was in use for an appropriate purpose under the conditions and environment of use specified in the Instruction Manual and catalog.
- (4) The breakdown or problem in question was caused by a specification defect or problem, or by a quality issue with our product.

Note that breakdowns due to any of the following reasons are excluded from the scope of warranty:

- Anything other than our product
- Modification or repair performed by a party other than us (unless we have approved such modification or repair)
- Anything that could not be easily predicted with the level of science and technology available at the time of shipment from our company
- A natural disaster, man-made disaster, incident or accident for which we are not liable
- Natural fading of paint or other symptoms of aging
- Wear, depletion or other expected result of use
- Operation noise, vibration or other subjective sensation not affecting function or maintenance

Note that the warranty only covers our product as delivered and that any secondary loss arising from a breakdown of our product is excluded from the scope of warranty.

7.3 Honoring the Warranty

As a rule, the product must be brought to us for repair under warranty.

7.4 Limited Liability

- (1) We shall assume no liability for any special damage, consequential loss or passive loss such as a loss of expected profit arising from or in connection with our product.
- (2) We shall not be liable for any program or control method created by the customer to operate our product or for the result of such program or control method.

7.5 Conditions of Conformance with Applicable Standards/Regulations, Etc., and Applications

- (1) If our product is combined with another product or any system, device, etc., used by the customer, the customer must first check the applicable standards, regulations and/or rules. The customer is also responsible for confirming that such combination with our product conforms to the applicable standards, etc. In such a case we will not be liable for the conformance of our product with the applicable standards, etc.
- (2) Our product is for general industrial use. It is not intended or designed for the applications specified below, which require a high level of safety. Accordingly, as a rule our product cannot be used in these applications. Contact us if you must use our product for any of these applications:
 - Medical equipment pertaining to maintenance or management of human life or health
 - A mechanism or mechanical equipment intended to move or transport people (such as a vehicle, railway facility or aviation facility)
 - Important safety parts of mechanical equipment (such as safety devices)
 - Equipment used to handle cultural assets, art or other irreplaceable items
- (3) Contact us at the earliest opportunity if our product is to be used in any condition or environment that differs from what is specified in the catalog or Instruction Manual.

7.6 Other Items Excluded from Warranty

The price of the product delivered to you does not include expenses associated with programming, the dispatch of engineers, etc. Accordingly, a separate fee will be charged in the following cases even during the warranty period:

- Guidance for installation/adjustment and witnessing of test operation
- Maintenance and inspection
- Technical guidance and education on operating/wiring methods, etc.
- Technical guidance and education on programming and other items related to programs

Change History

Revision Date	Description of Revision
November 2008	Fifth edition Descriptions for the following grippers have been added. • Cleanroom specification • Small two-finger slide type RCP2CR-GRSS • Small two-finger lever type RCP2CR-GRLS • Dust-proof specification • Small two-finger slide type RCP2W-GRSS • Small two-finger lever type RCP2W-GRLS
December 2008	Sixth edition Descriptions for the following grippers have been added. • Two-finger long-stroke type RCP2-GRST
April 2010	Seventh edition Added information regarding the following grippers: • Two-finger type with high gripping force: RCP2-GRHM, GRHB
October 2010	Eighth edition Page 45 Change in dimensions on finger area for RCP2-GRHM and GRHB Page 90 and 110 Change in allowable load moment for GRHM and GRHB • GRHM Ma : 15.2 N•m → 11.7 N•m Mb : 21.7 N•m → 16.7 N•m Mc : 60.5 N•m → 46.5 N•m • GRHB Ma : 20.4 N•m → 15.7 N•m Mb : 34.3 N•m → 26.4 N•m Mc : 77.8 N•m → 59.8 N•m
April 2011	Ninth edition A page for CE Marking added
March 2012	Tenth edition Page 1 to 7 Contents added and changed in Safety Guide Page 8 Note “Make sure to attach the actuator properly by following this instruction manual.” added in Caution in Handling Page 72 to 74, 76, 79, 81, 82, 85 to 87 Warning notes added such as in case the grease got into your eye, immediately go to see the doctor for an appropriate care. Page 92 to 106 Mass added to appearance drawing Page 116 to 117 Contents changed in 12. Warranty
May 2014	Eleventh edition Revised overall Cleanroom Specification and Dust-proof Specification deleted
June 2015	Edition 11C Change made to GRS, GRM max. open/close velocity GRS 33.3mm/s → 33mm/s GRM 36.7mm/s → 36mm/s

Revision Date	Description of Revision
August 2015	Edition 11D • Page 22 Change made to GR3SM max. open/close velocity 40mm/s → 50mm/s • Page 44 Change made to wire color • Page 80 Change made to bending radius
August 2015	Edition 11E • Page 8 Note added to notify rust prevention treatment should be implemented in case of removing grease on fingers and finger guides after delivery • Page 91, 92, 103 Grease supply added for fingers and finger guides
December 2015	Edition 11G • Page 29 Contents of SEL system controllers added in caution
February 2016	Edition 11H • Page 39 Correction made Calculation formula of the “Torque generated to the finger by an external force.” $10^{-6} \rightarrow 10^{-3}$
February 2017	Edition 11I • Page 114, 116 Correction made $77 \begin{smallmatrix} 0 \\ -0.05 \end{smallmatrix} \rightarrow \phi 77 \begin{smallmatrix} 0 \\ -0.05 \end{smallmatrix}$
May 2018	Edition 11J • Page 22 High-velocity Type and Standard Type added in model codes for Long-stroke Type
May 2019	Edition 11K • Page 29 Pressing velocity of lever type changed from 5deg/s to 20deg/s
January 2020	Edition 11L • Page 92, 96, 101, 102, 105, 106 Grease changed from Daphne Eponex Grease No. 2 to Daphne Grease MP No. 2 • Stroke 100mm and 150mm in GRST added • PCON-CB/CGB/CYB/PLB/POB, MCON, MSEL and RCON added
January 2021	Edition 11M • Page 20, 43 Anti-rust black coating option added
March 2021	Edition 11N • Page 86 Note added stating not to bend cable in range of 150mm or less from connector tip • Page 90 Description added stating home-return operations for three-finger type • Page 117 to 120 Home position described • RCON added

Revision Date	Description of Revision
September 2024	Edition 11O • Page 11 Complied with RoHS3 Directive • Page 19 Enclosed DVD abolished • Page 76, 77 2.3.4 Caution note added regarding finger attachment • Page 109 Correction made to grease name • Minor corrections made, terms integrated
March 2026	Edition 11P • Changes due to discontinuation of including the First Step Guide





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