





# Revolutionary Technology

The Soft Robotics *mGrip* modular gripping system is a suite of configurable gripper and controller products that enables reliable, high-speed picking of traditionally hard to grasp items in the food and beverage processing and consumer packaged goods industries.

For more information, visit:  
**[softroboticsinc.com/mgrip](https://softroboticsinc.com/mgrip)**



*For 3 Finger Configuration, Skip to Step 4.*

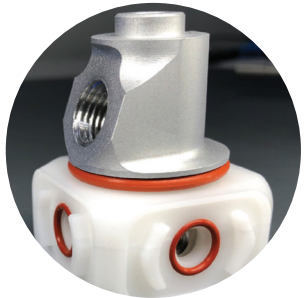
1

**Install** the Lower Hub Mount into Circular Hub if not already installed.

2

**Install** the Upper Hub Mount into the Circular Hub.

Ensure the mating surfaces are clean and dry.

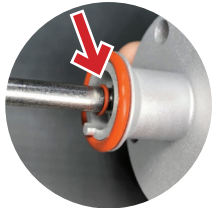


3

**Install** the Circular Hub Screw into Robot Adapter.



**Ensure** the small O-Ring is installed properly on the Hub Screw after the screw is installed into the robot adapter.



***Note:** We recommend grease for the O-Ring and Anti-Seize gel for the screw.*

4

**Install** the Robot Adapter onto the Upper Hub Mount. **Torque** the Circular Hub Screw to **7.4Nm**.

Ensure the mating surfaces are clean and dry.





5

**Install** the Air Fitting into the Upper Hub Mount and **Torque** to **6Nm**.

*Note: This does not apply to 3-finger configuration.*

6

**Install** the desired Spacer onto the Circular Hub (if required) by aligning the features and pressing firmly.



7

**Install** the Finger Module onto the Spacer.

*Note: Fingers can be mounted directly to the hub if spacers are not being used.*

8

**Tighten** the Hex Nut onto the tie rod (after anti-seize is applied) and then place through the installed finger module and spacer (if present) to attach to the hub.



*Note: Use the Tie Rod and spacer chart (located on the right panel of this guide) to identify which tie rod is best for your gripper. We recommend Anti-Seize gel onto the Tie Rod before M4 Hex Nut is installed.*



9

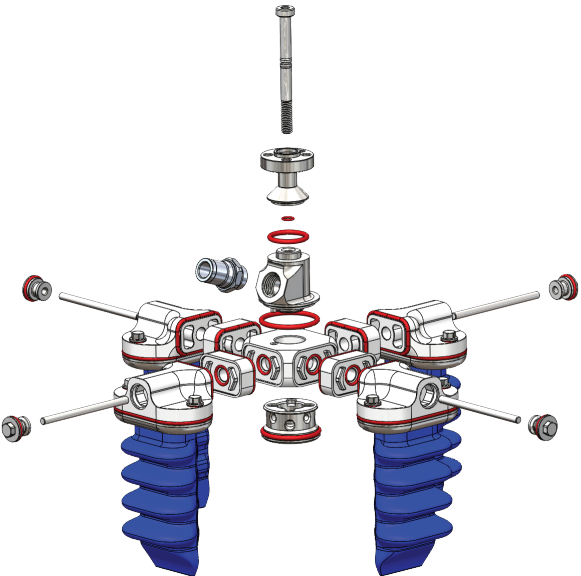
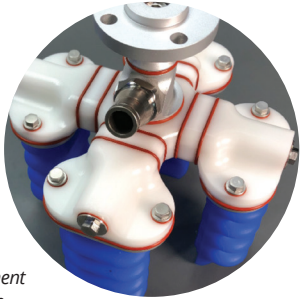
**Torque** the hex nut on the Tie Rod to **2.2Nm**.

*If blanking plates are utilized, follow steps 6, 8, and 9.*

10

**Repeat** steps 7 through 9 to secure other Finger Modules to the Circular Hub.

***Note:** After the EOAT has been present in its operating environment for at least 8 hours, **Torque** the center hub bolt to **7.4Nm** for optimal operation.*



Circular 3 Finger EOAT

	Traditional Finger Modules		Compact Finger Modules	
Grip Spacing	Spacer Size	Tie Rod Size	Spacer Size	Tie Rod Size
30	-	-	None	40
40	-	-	5	45
50	None	45	10	50
60	5	50	15	55
70	10	55	20	60
80	15	60	25	65
90	20	65	30	70
100	25	70	35	75
110	30	75	40	80
120	35	80	-	-
130	40	85	-	-

Circular 4 Finger EOAT

	Traditional Finger Modules		Compact Finger Modules	
Grip Spacing	Spacer Size	Tie Rod Size	Spacer Size	Tie Rod Size
N/A	Blanking Plate	25	Blanking Plate	25
45	-	-	None	45
55	-	-	5	50
65	None	50	10	55
75	5	55	15	60
85	10	60	20	65
95	15	65	25	70
105	20	70	30	75
115	25	75	35	80
125	30	80	40	85
135	35	85	-	-
145	40	90	-	-

Circular 5 Finger EOAT

	Traditional Finger Modules		Compact Finger Modules	
Grip Spacing	Spacer Size	Tie Rod Size	Spacer Size	Tie Rod Size
N/A	Blanking Plate	30	Blanking Plate	30
55	-	-	None	50
65	-	-	5	55
75	None*	55	10	60
85	5	60	15	65
95	10	65	20	70
105	15	70	25	75
115	20	75	30	80
125	25	80	35	85
135	30	85	40	90
145	35	90	-	-
155	40	95	-	-

\* Only compatible with Traditional Mini Finger Module

Circular 6 Finger EOAT

	Traditional Finger Modules		Compact Finger Modules	
Grip Spacing	Spacer Size	Tie Rod Size	Spacer Size	Tie Rod Size
N/A	Blanking Plate	35	Blanking Plate	35
65	-	-	None**	-
75	-	-	5	60
85	None*	60	10	65
95	5*	65	15	70
105	10	70	20	75
115	15	75	25	80
125	20	80	30	85
135	25	85	35	90
145	30	90	40	95
155	35	95	-	-
165	40	100	-	-

\* Only compatible with Traditional Mini Finger Module      \*\* Not feasible