GET TO KNOW THE TECHNOLOGY

*m*Grip is an on-demand, modular gripping system from Soft Robotics. Developed with our award winning technology, *m*Grip brings infinite robotic grasping solutions to picking challenges that couldn't previously be automated. *m*Grip allows quick tool builds with limitless configurations and spacing options getting users operational quickly.

Each *m*Grip kit comes equipped with the components you need to build, validate and install production-ready systems in minutes. When paired with the Soft Robotics Control Unit, the *m*Grip gripper can cycle 3-4 times per second, keeping up with even the most demanding applications.

Reference list of parts: **see back**

IN YOUR KIT

All the components needed to build a parallel tool with either 2, 4, or 6 fingers

The ability to handle a wide set of geometries with a gripper spacing range of 40mm to 120mm

+

Parallel 2, 4, and 6 hubs

(6) 5mm-40mm spacers, in 5mm increments

(6) 4 accordion Soft Robotics finger modules

10mm Air Fitting

(4) Pneumatic Blanking Plates

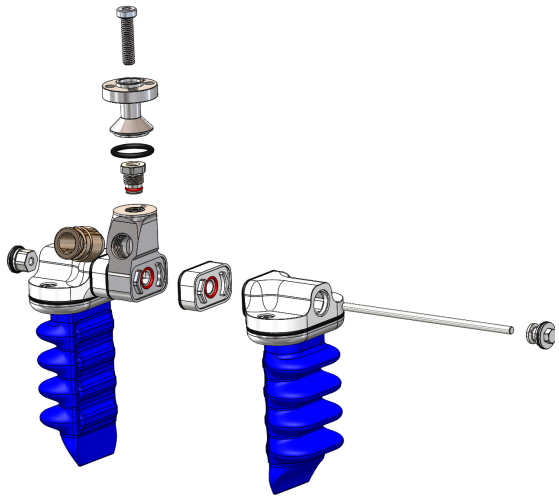
All other relevant hardware

For more information, visit:
softroboticsinc.com/mgrip

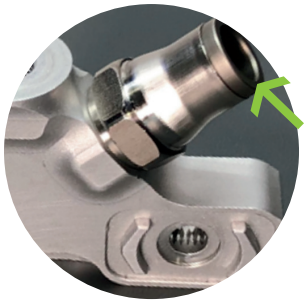
P/N 800130 Rev A

SOFT ROBOTICS

*m*Grip Parallel Kit
QUICK START GUIDE



www.SoftRoboticsInc.com



1

Install the Air Fitting onto the desired Parallel Hub. Torque to 6Nm.

5

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

9

Install the second Finger Module onto Spacer and through the tie rod.

2

Install the Robot Adapter onto the Parallel Hub.

6

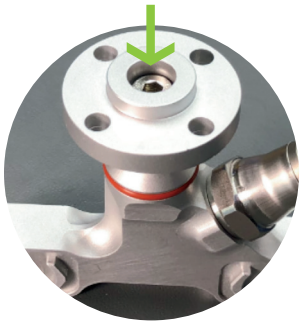
Install Finger Module onto the Spacer by aligning features and pressing firmly.

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

10

Install an M4 Sealing Cap Nut onto the end of the tie rod to secure the Spacers and Finger Modules in place. Torque Hex Nut to 2.2Nm.

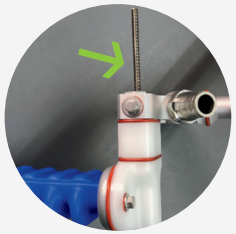
Note: *We recommend Anti-Seize gel onto Tie Rod before M4 Cap Nut installation.*



3

Insert the M6 Screw to attach Robot Adapter through Parallel Hub. Torque this screw to 5Nm.

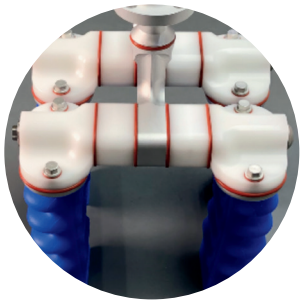
Note: *We recommend Anti-Seize gel onto M6 screw before installation.*



7

Use the M4 Hex Nut to be tightened onto Tie Rod (after Anti-Seize applied) and then used to attached Finger Module and Spacer (if required) to 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 Tie Rod before M4 Hex Nut is installed.*



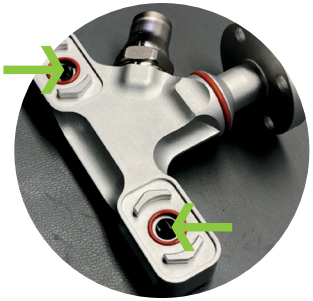
11

Repeat steps 5 through 10 to secure other Spacers and Finger Modules to the Parallel Hub

(for Parallel 4 and Parallel 6 EOATs)

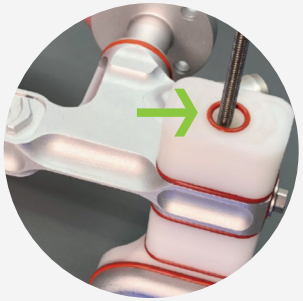
4

Ensure O-Rings are installed on the Parallel Hub and did not come loose during shipping.



8

Install the second Spacer, if required, onto the opposite side of the Parallel Hub by passing the tie rod through the center of the spacer and pressing firmly against the Parallel Hub.



PARALLEL KIT SPACER AND TIE ROD CHART

Grip Spacing (mm)	Spacer (mm)	Tie Rod (mm)
40	0	85
50	5	95
60	10	105
70	15	115
80	20	125
90	25	135
100	30	145
110	35	155
120	40	165
Blanking Plate	-	35