

# THANK YOU FOR CHOOSING ROBOTIQ

This step-by-step guide will allow you to **install** and **use your Hand-E** on TM Series robots.



## 1. WHAT IS SUPPLIED?

Standard upon delivery of a TM Series kit:

- Hand-E Adaptive Gripper..... (HND-GRP)
- Gripper Coupling .....(GRP-CPL-062)
- Fingertip Starting Kit .....(AGC-TIP-204-002)
- High-Flex Device Cable .....(CBL-COM-2065-10-HF)
- RS232 to RS485 Adapter.....(ACC-ADT-RS232-RS485)
- USB to RS485 Adapter.....(ACC-ADT-USB-RS485)
- Necessary Hardware



## 2. TOOLS YOU NEED



2 mm Slotted Screwdriver (not included)



4 mm Hex Key



## 3. GET THE LATEST

- Go to [support.robotiq.com](http://support.robotiq.com).
- Select Techman Robot, Hand-E Adaptive Gripper, Software, Gripper Software.
- Download the TM Plug & Play Software Package.
- Decompress the package at the root of a USB storage device and rename the USB device "TMROBOT".

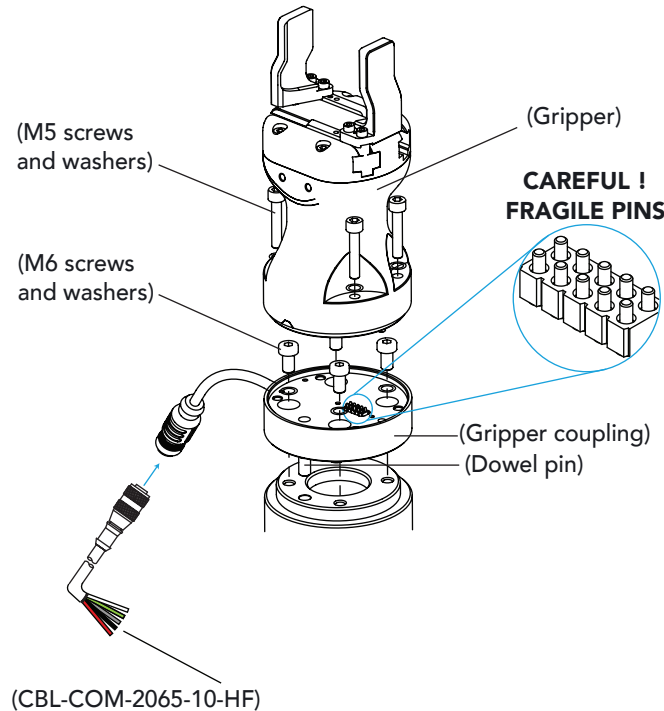


**BEFORE OPERATING THE GRIPPER, PLEASE READ THE INSTRUCTION MANUAL.**



## 4. MOUNTING

- Mount the coupling on your robot arm. Align with the provided dowel pin.
- Secure using the provided M6 screws and tooth lock washers.
- Mount the Gripper on the coupling. Align with the dowel pin.
- Secure using the provided M5 screws and tooth lock washers.
- Plug the device cable into the Gripper's pigtail and attach the cable along the robot arm using a cable routing system.



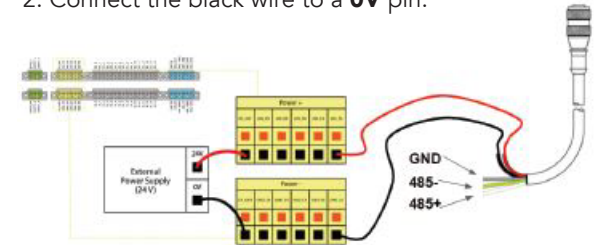
**LEAVE ENOUGH EXCESS CABLE TO ALLOW FULL ROBOT MOVEMENT.**



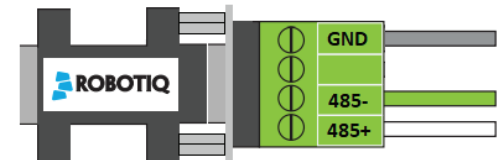
## 5. WIRING

**i** The red (24V) and black (0V) wires of the device cable provide power to the gripper.

1. Connect the red wire to a **24V** pin.
2. Connect the black wire to a **0V** pin.

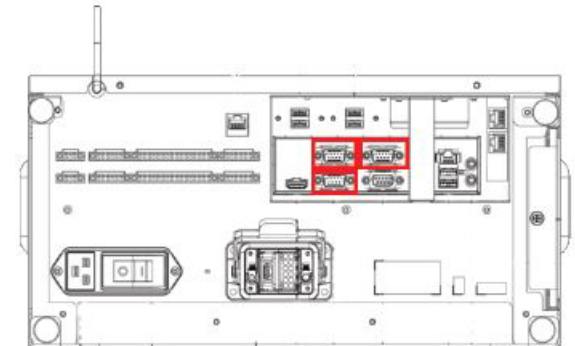


3. Connect the communication wires in the RS232 signal converter (ACC-ADT-RS232-RS485) as shown below.



Pin	Signal Name	CBL-COM-2065-10-HF High-Flex Device Cable
1	<b>485 + (A)</b>	<b>WHITE</b>
2	<b>485 - (B)</b>	<b>GREEN</b>
3	<b>485 GND</b>	<b>SHIELD</b>

4. Connect the RS232 end of the signal converter to a COM port of the robot controller.





## 6. SOFTWARE INSTALLATION

- Turn on the robot and log in to TM Flow.
  - Connect the USB device that contains the **Components** in the robot controller.
  - Take control of the robot, tap the **triple bar icon** and select **System Settings**.
  - Click on **Import/Export**.
  - Click on the **Import** button, select **TMComponent** in the **Robot List** menu and click **OK**.
  - Select the files to import in the list on the left and click on the **Send** button.
- 
- Tap the **triple bar icon** and select **Robot Setting**.
  - Enable the appropriate Components by clicking on the **radio buttons** and click on the **Save** button.



## 7. GRIPPER BUTTON CONFIGURATION

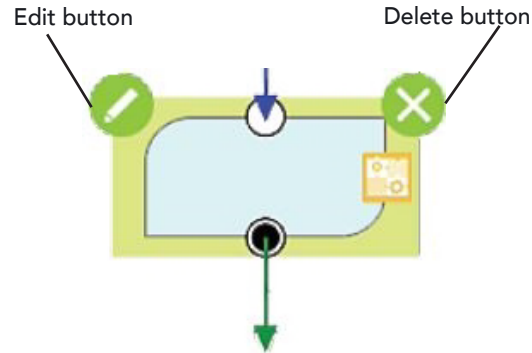
Follow the indications below to assign Gripper commands to the Gripper button found on the robot camera mounted on the robot wrist.

- In the TM Flow robot software, tap the **triple bar icon** and select the **Setting** icon.
- Click on **Gripper Button**.
- In the **Gripper Button** window, tick the **Using Customized Component** radio button.
- Select the Component you want to assign to either one of the Gripper actions.
- In the popup window, select or change the Component your wish to assign to the Gripper action/button.
- Click **OK**.

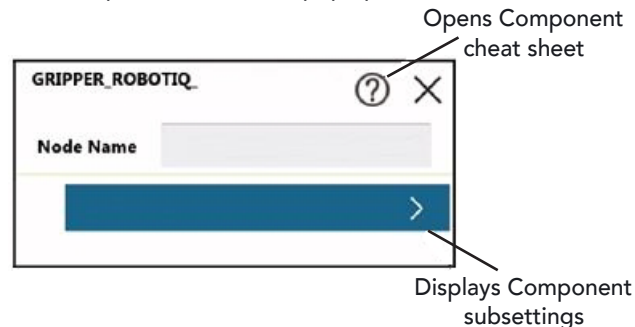


## 8. USE COMPONENTS TO PROGRAM WITH THE GRIPPER

- From the TM Flow homepage, tap the **triple bar icon** and select the **Project** icon.
- Locate the Gripper Components in the navigation pane on the left side of the screen.
- Click on the program Component after which you wish to insert a Gripper Component.
- Drag and drop the desired Gripper Component under the highlighted Component.



- For advanced parameters, click on the Edit button (pencil icon) in the upper left corner of the Component; the Components menu will pop up.



[support.robotiq.com](https://support.robotiq.com)

support@robotiq.com  
T: 1.418.380.2788 option 3

November 2021  
X-990059-C



## HAND-E ADAPTIVE GRIPPERS

### QUICK START GUIDE

For installation on  
TM Series  
collaborative robots

