

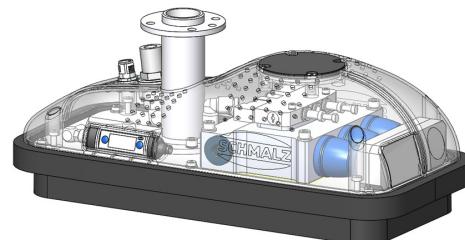
# Robot-Set FXCB

Components, assembly and installation of the set



## Components of the set

- Pneumatic Area Gripper FXCB  
(Part no. 10.01.43.00016)
- Connection cable ASK (Part no. 21.04.05.00350)
- USB-key with URCap software



## Assembly of the set

1. Mount the Area Gripper (1) with the help of the included screws onto the robot arm.
2. Connect the FXCB (2) with the help of the connection cable to the robot. Therefore use the connection cable and put it in the electric port of the FXCB. Then connect the cable and the first joint of the robot.
3. Use a suitable vacuum hose, connect it with the hose connection and use an included hose clamp to secure it. Now you can connect the gripper with the compressed air supply.

## Installation of the set

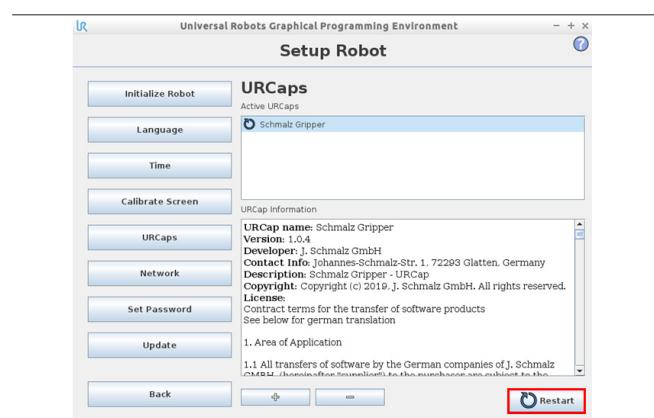
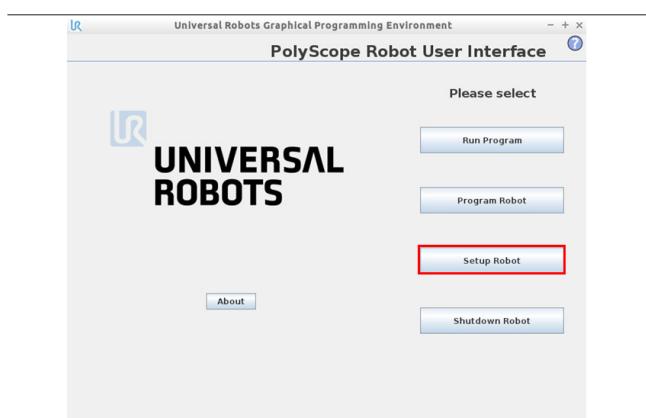
Plug the USB-key with the URCap of Schmalz into the robot port.

Navigate via "Setup Robot" to "URCaps" and choose it by clicking on it.

Press the "+"-button.

Then open the folder of the USB-key and select the URCap file of Schmalz.

To activate the software simply click "Restart".

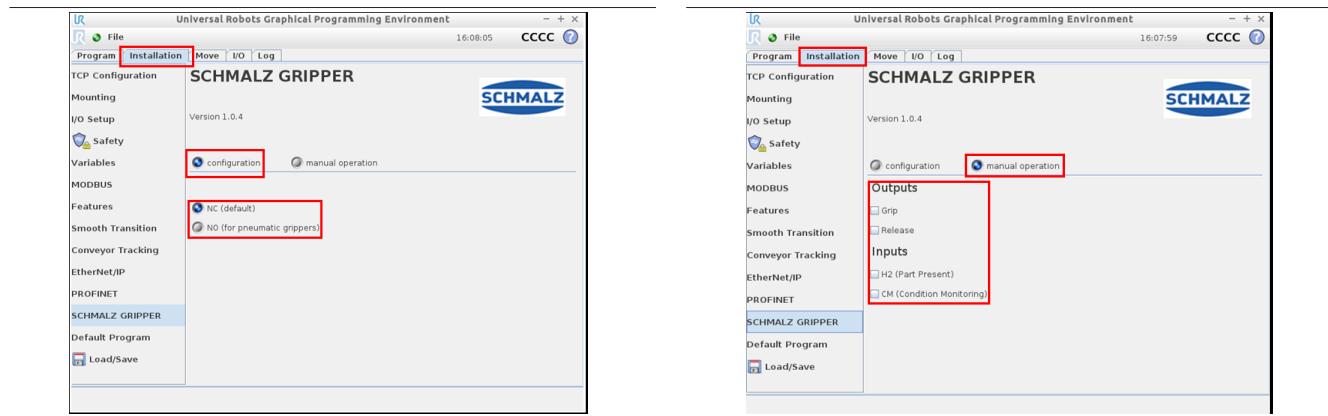


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In the tab "Installation" then "configuration" you can either choose NC (electrical driven grippers e.g. ECBPi) or NO (pneumatic grippers e.g. FXCB).

In the same tab but in "manual operation" you can set the output or check the input.



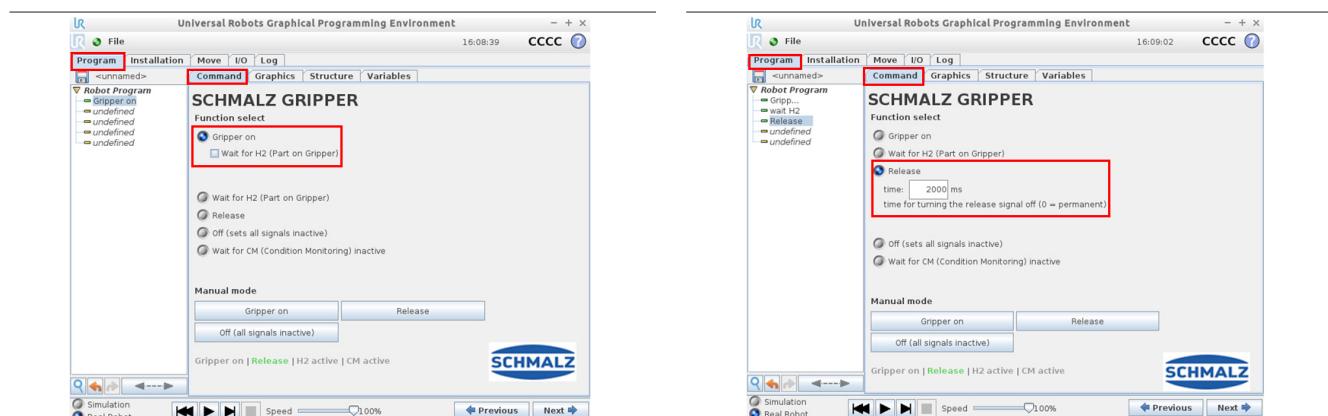
In the tab "Program" you can add a program for your gripper.

Here you can alternate and see all of the features of the gripper.

If the checkbox "Wait for H2" is being activated during the activation ("Gripper on" is activated) the gripper will wait for the part.

In the input field "Release" the desired release time can be configured.

You can see the currently activated status below, highlighted in green.



The gripper can be controlled manually via these buttons.



URCap compatible with:

CB-Series 3.9.0 and e-Series 5.3.02

State: 05/2019