

LGR Gripper



Manufacturer: Lets Go Robotics, Incorporated
 Model Number: LGR-Gripster
 Web Address: www.letsgorobotics.net

The LGR Gripster features a worm gear drive design to move gripper fingers open and closed while eliminating backlash. It is designed to handle a wide range of gripping applications, including portrait and landscape gripping capabilities. Various plate type settings are easily uploaded into the Gripster by using simple, custom software. The Gripster utilizes computer algorithms to detect whether a plate has been gripped, minimizing unnecessary wires and expensive sensors.

LGR Gripper: Commands

- **Home()** - Homes the gripper to be ready for operations.
- **Move(position)** - Moves the gripper to the target position.

position	Integer	Specified target position.
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- **Grip()** - Grips an object.
- **Ungrip()** - Releases the object that was gripped.
- **GetGripPos()** - Retrieves the current grip position setting.
- **SetGripPos(position)** - Sets the grip position setting.

position	Integer	Grip position setting.
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- **GetUngripPos()** - Retrieves the current ungrasp position setting.
- **SetUngripPos(position)** - Sets the ungrasp position setting.

position	Integer	Ungrip position setting.
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- **GetGripThreshold()** - Retrieves the current grip threshold setting.
- **SetGripThreshold(threshold)** - Sets the grip threshold setting.

threshold	Integer	Grip threshold setting.
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- **GetGripForce()** - Retrieves the current grip force.
- **SetGripForce(force)** - Sets the grip force.

force	Integer	Grip force level.
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- **GetGripVelocity()** - Retrieves the current grip velocity level.
- **SetGripVelocity(velocity)** - Sets the grip velocity.

velocity	Integer	Grip velocity level.
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Gripper Error

- **ErrorCode(errorCode, description)** - Error occurred during

command execution.

errorCode	Integer	Error status for the reader.
description	String	Error description.

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