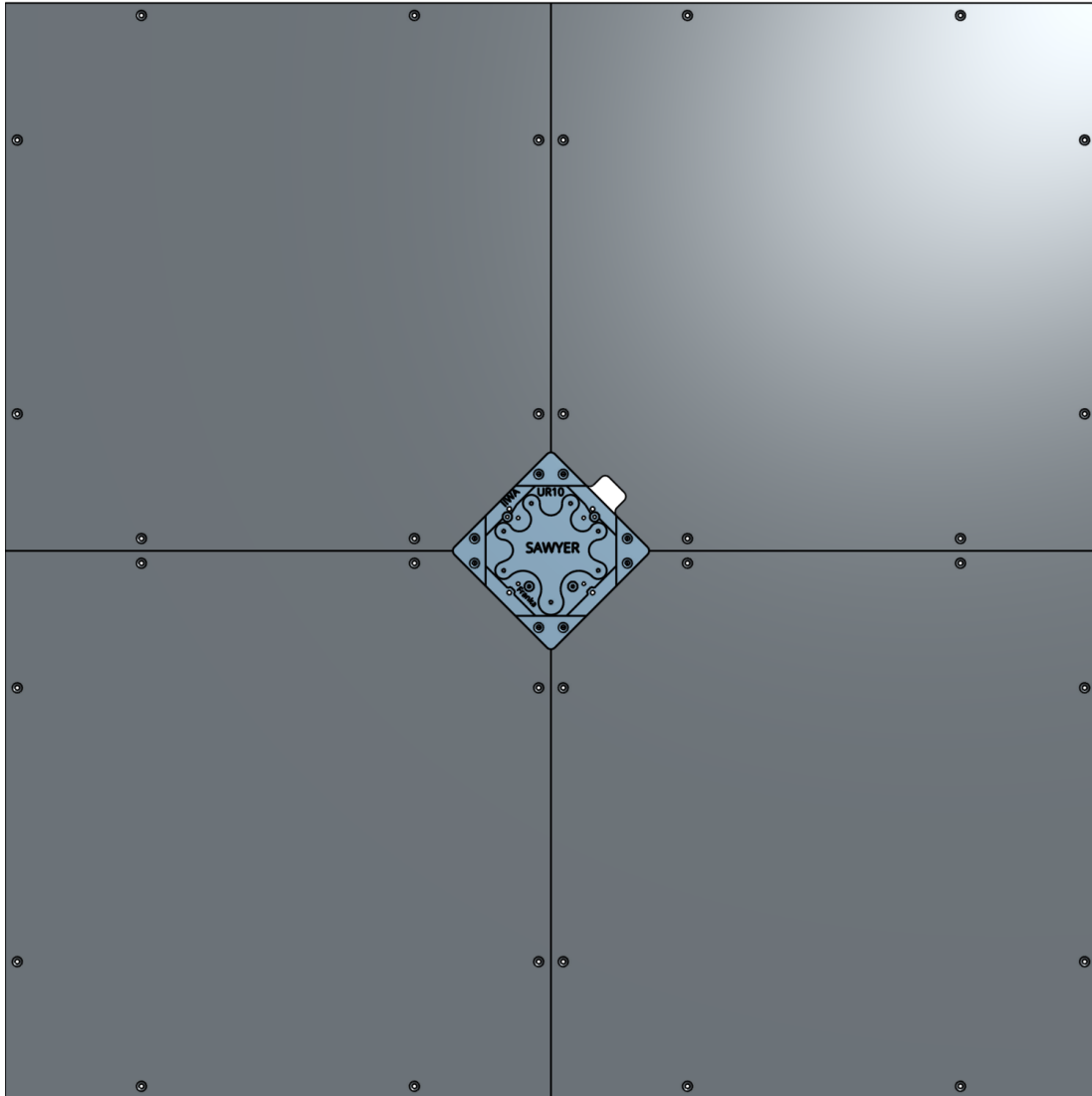
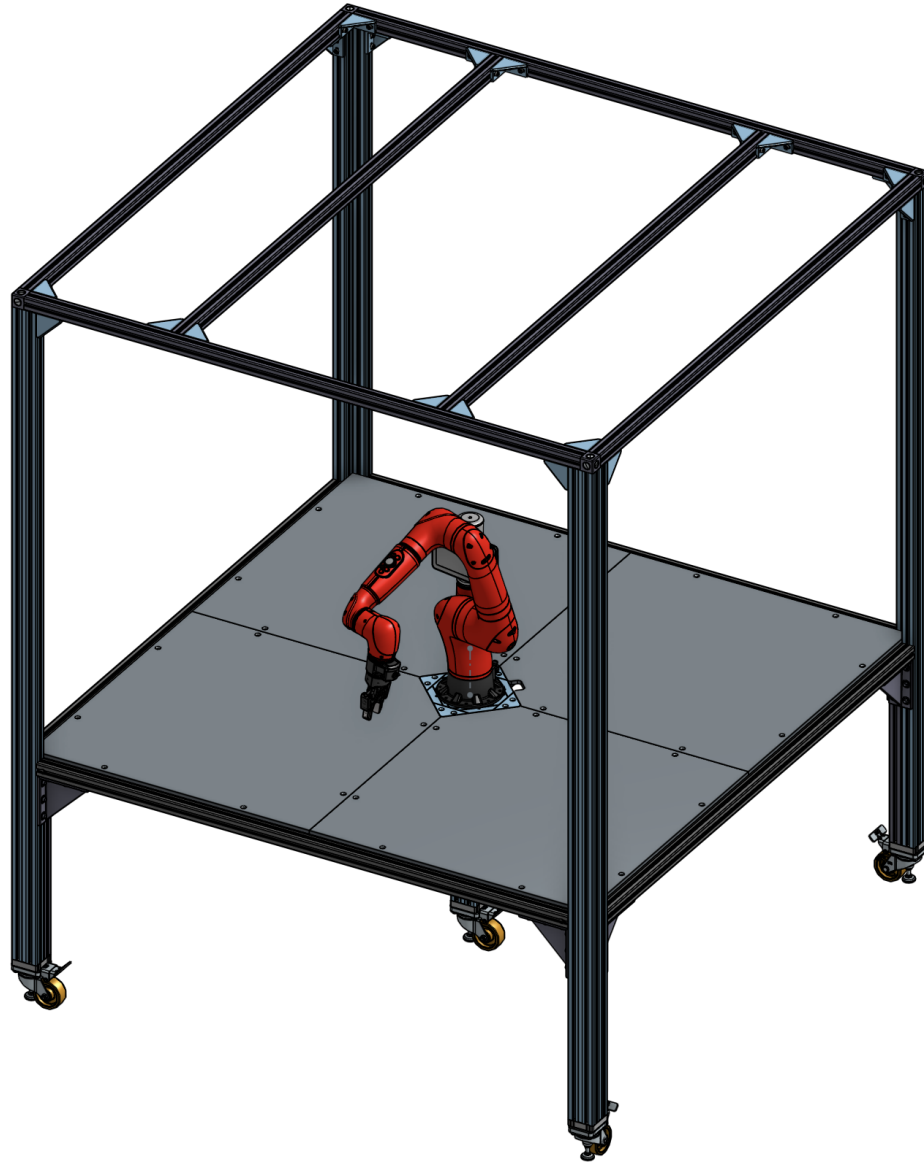


Assembly Robot Instruction

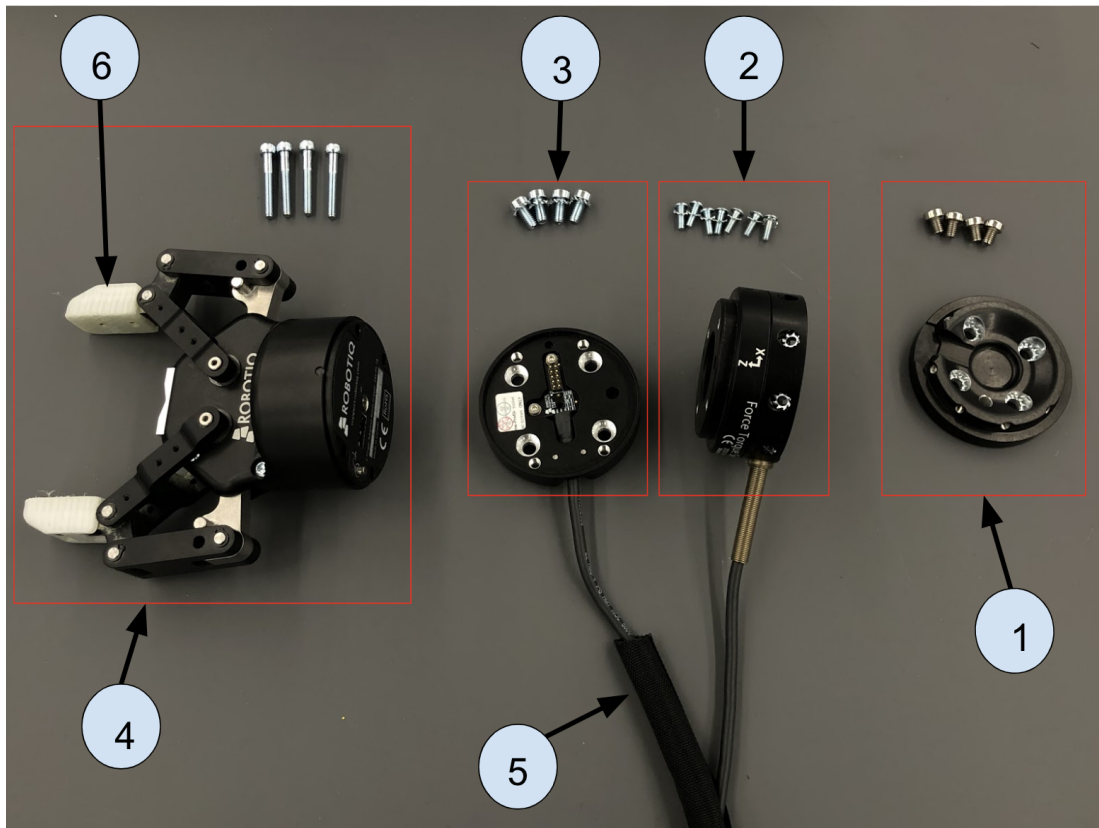
1. Attach Sawyer base plate to cell with [8 M8x25 countersunk screws](#).



2. Mount sawyer arm to the base Plate, make sure the robot is positioned in the correct orientation on the base plate. Sawyer arm is screwed into the base plate with [8 M8x20 screws](#)



Gripper Instructions



1. Screw force torque adapter plate to sawyer arm with 4 M5x10 screws*.
2. Attach Force Torque sensor to adapter plate with 7 M2x12 screws*.
3. Attach gripper coupling plate to FT sensor with 4 m5x10 screws*.
4. Mount gripper to force torque sensor with 4 M4x25 gripper screws*.
5. Tidy up Force Torque sensor and gripper cabling. Add [cable sheathing](#) to cabling for added protection and then cable tie to sawyer arm.
6. Add fingertips to the gripper. Each finger tip has two dowel pins M2x12mm which insert inside the finger tip. Fingertips are screwed into the gripper with M5x30 screws.
7. Plug Power and Ethernet cable into the sawyer arm from the motor control box.

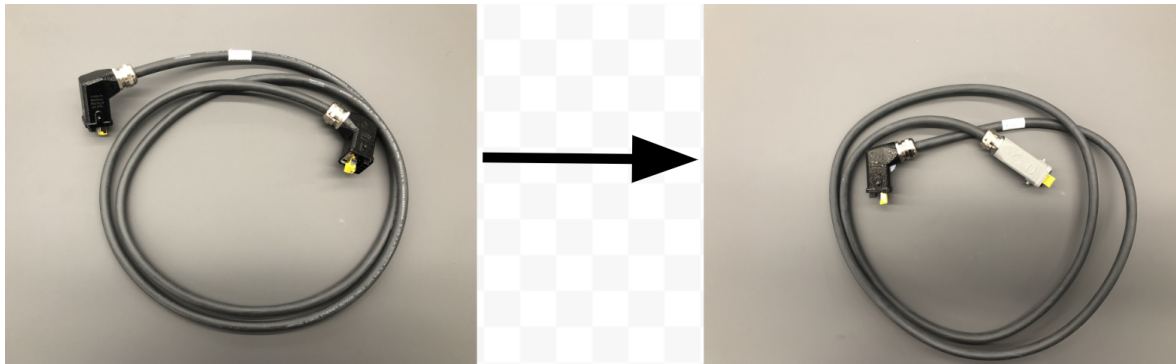
*Screws provided with Gripper kit

How to make a straight Harting Cable

The standard size Harting cable that is provided with a sawyer arm comes with one end that has a 90 degree connector, unfortunately this does not fit due to clashing with the cable notch tile.



We usually order a straight cable from active8 or modify the cable provided with the sawyer arm (90 degree connector end) to a straight connector using these [instructions](#).



This allows us to connect the sawyer power cable, without having to rotate the sawyer arm base 20 degrees to fit the 90 degree power connector.

