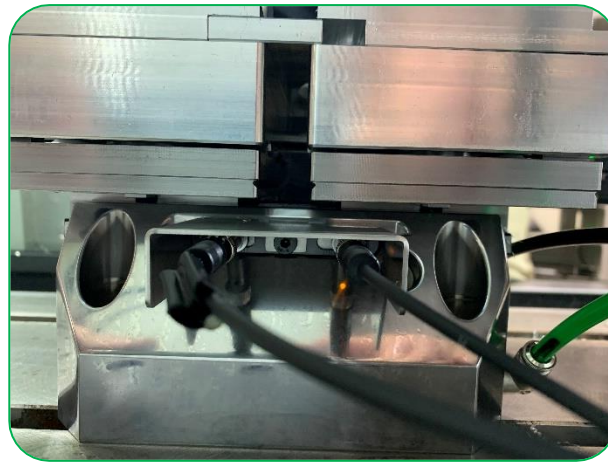![AWR - Automation Within Reach logo]

VBX Series Load & Go
Sensor adjustments, vise & robot gripper

Vise sensors

- The purpose of the vise sensors are to confirm that the MultiGrip workholding is seated properly on the vise. It does not detect whether the part is present.
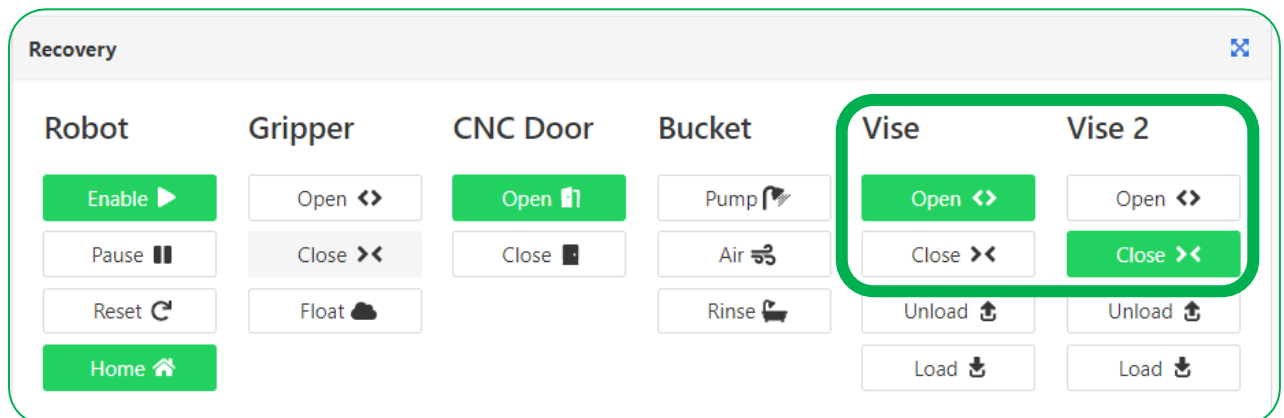
Vise sensor (open)

Left sensor= CLOSE | Right sensor= OPEN

- From the VBX user interface, an active sensor is shown in green.

VBX user interface

| Vise closed, empty	Vise closed with MultiGrip jaws	Vise open
Close sensor: ON	Close sensor: -	Close sensor: -
Open sensor: -	Open sensor: -	Open sensor: ON

- If needed, adjust the vise sensors using a 7mm combination "box" wrench to loosen the sensor nut.

1) Turn the sensor slowly until it hits the vise.
2) Back out 1.25 turn.
3) Plug in the sensor cable and adjust laterally for the desired results.
4) Tighten the nut carefully.
5) Verify all three conditions: vise empty, vise with MultiGrip jaws, vise open.

AUTOMATION WITHIN REACH

Robot gripper sensors

- Open the robot gripper. Put on the MultiGrip jaws by hand. Select Float to allow the robot grippers to move freely.

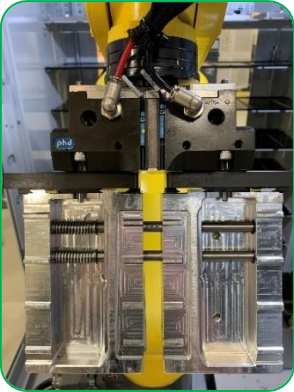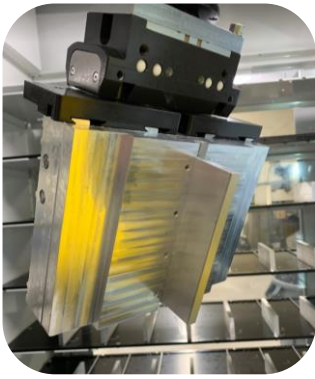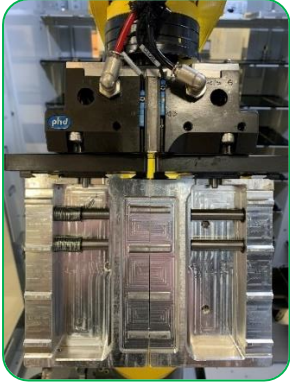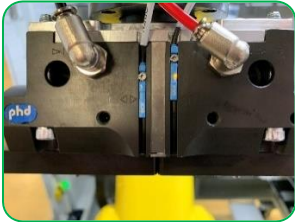- Verify the robot gripper sensors are in these positions.

Gripper
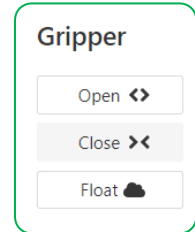
Open <>
Close ><
Float ☁

| *Fully open*	*Closed gripper with a part (or 1/8" spacer)*	*Closed gripper with MultiGrip jaws*	*Closed gripper, empty*
Close sensor: OFF	Close sensor: OFF	**Close sensor: ON**	**Close sensor: ON**
Open sensor: ON	Open sensor: OFF	Open sensor: OFF	Open sensor: OFF

Robot gripper adjustment, if needed:

- From the VBX screen, OPEN the robot gripper, then FLOAT.
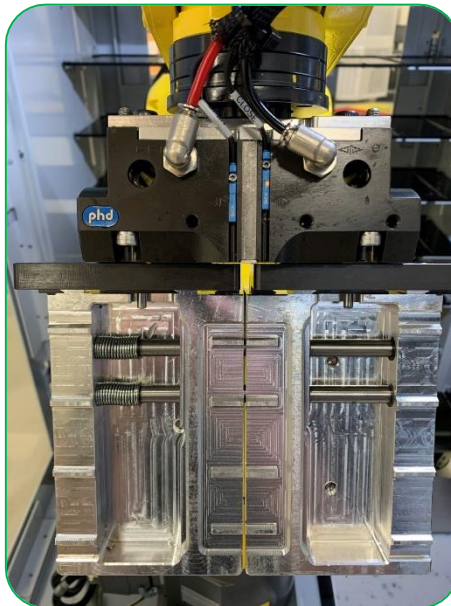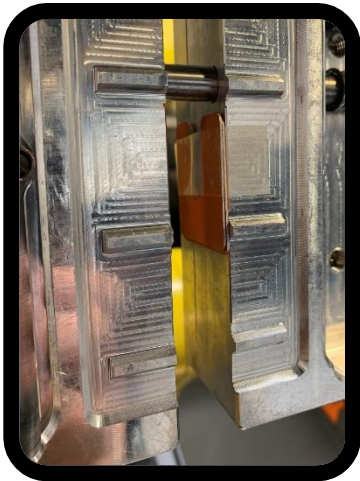- Place MultiGrip jaws on the robot gripper.
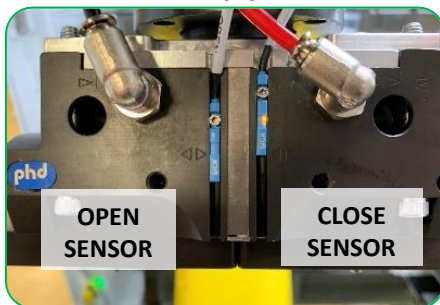
1) Adjust the robot gripper sensors using an M1.5 Allen wrench.

2) Slide the open sensor until it aligns with this picture. The arrows should line up with the indentation line below the light.
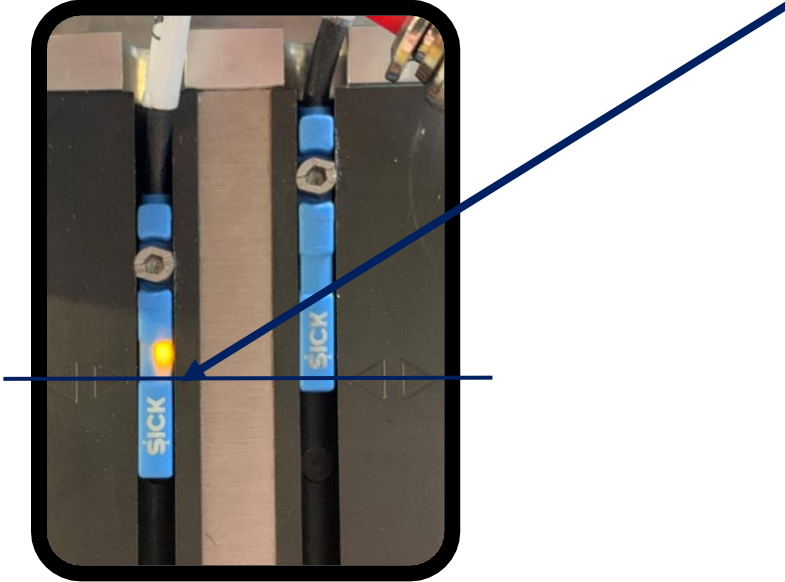
3) Tape a 0.030" shim between the MultiGrip jaws.

4) Close the robot gripper.
5) Slide the close sensor down (starting from the top). STOP as soon as the sensor light turns on.

6) Tighten. Be careful not to slide the sensor further down.