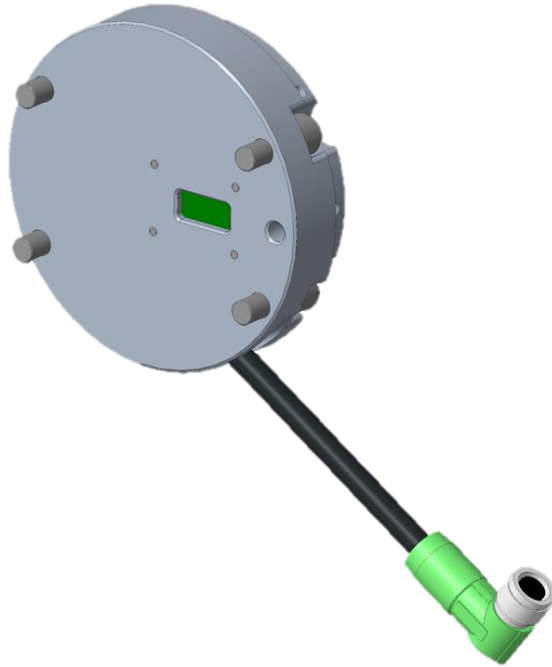


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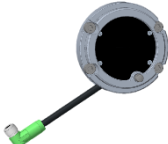


qb SoftHand
RESEARCH

ADAPTER FLANGE TO KINOVA *Gen3* WRIST
INTERFACE

Bill of materials

1 x



LA_WR_RES_KNV_G3_R_100

4 x



EN ISO 4762 M5x14

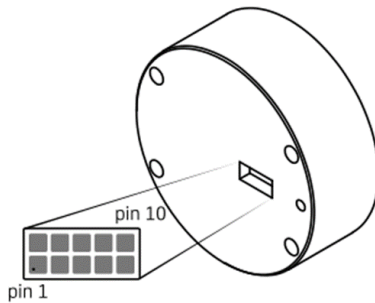
1 x



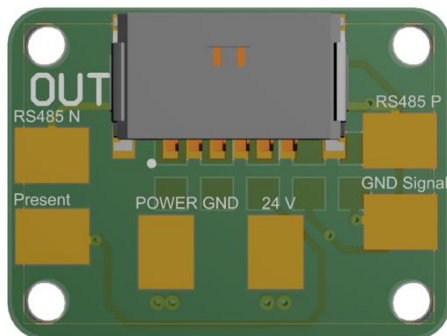
MC_TOOL_ALLENKEY_M_4

Junction board pinout details

| Pin | Name |
|-----|---------|
| 1 | GND |
| 2 | GND |
| 3 | +24V |
| 4 | +24V |
| 5 | N/C |
| 6 | PRESENT |
| 7 | RS485_P |
| 8 | RS485_N |
| 9 | N/C |
| 10 | SGN_GND |

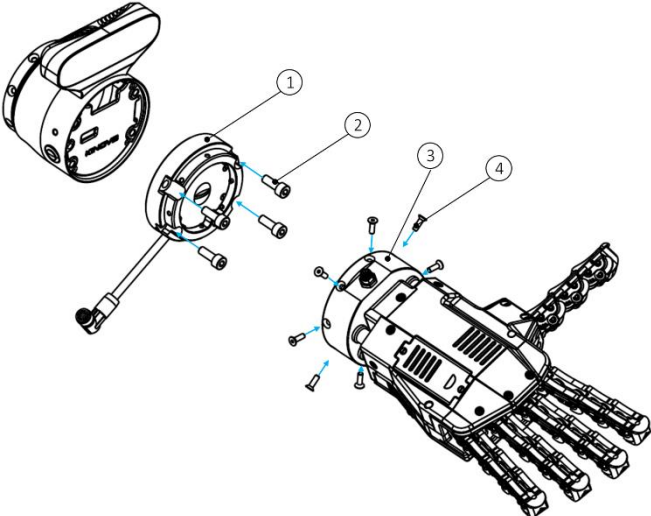
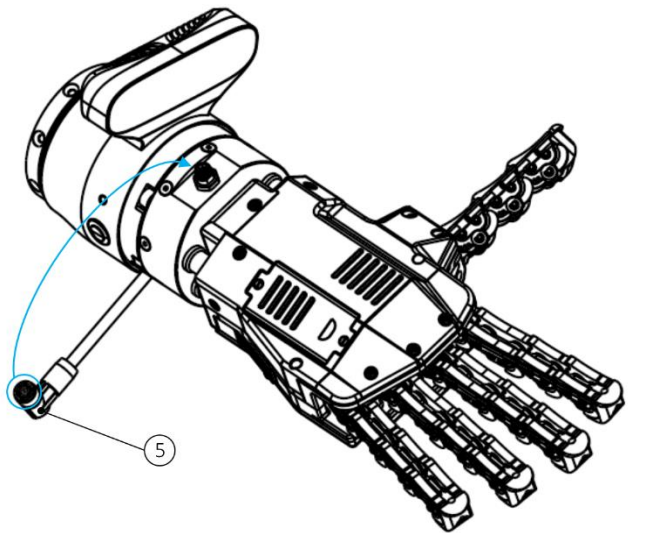



pin 6 and pin 10 are not connected to the qb SoftHand Research
(the M8 connector pinout can be found in the user manual)



Internal view of the junction board

Assembly instructions

| # | instructions | |
|---|--|---|
| A |  | <p>Center (1) on the KINOVA Gen3 robot wrist. Fasten (1) to the robot wrist by tightening the four screws (2). Center (3) on (2). Fasten (3) to (1) by tightening the eight screws (4).</p> |
| B |  | <p>Connect (5) to the M8 8pin male connector on the flange of the hand.</p> <p>WARNING:  Be careful to insert the connector in the right direction; Do not rotate the M8 connector when inserted into the receptacle; Minimum curve radius of the cable (4) = 51mm.</p> |