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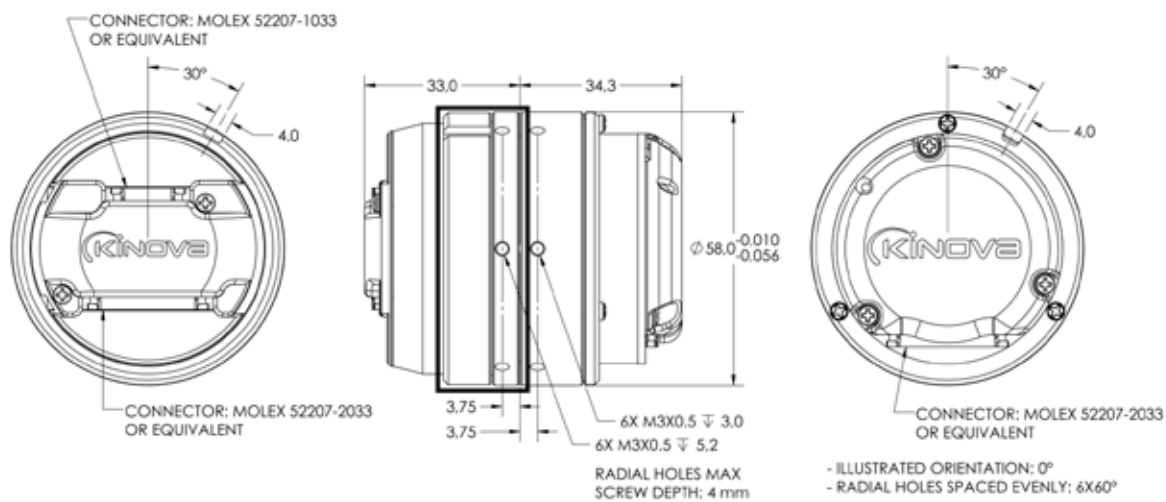
KINOVA™ End effector mounting

# Specifications



The KINOVA™ Ultra lightweight robotic arm and KINOVA™ MICO robotic arm are designed to integrate particularly well with KINOVA™ KG-Series Grippers. However, they can also be integrated with other end effectors. This document gives specifications for the mechanical mounting of the end effector. For more details on how to integrate an end effector for power and controls with a Kinova robotic arm, consult the particular robotic arm user guide.

The procedure to mount an end effector to a KINOVA™ MICO robotic arm (4/6 DOF) or a KINOVA™ Ultra lightweight robotic arm (JACO<sup>2</sup>) (4/6/7 DOF) is the same. In all cases, the end effector is attached to a KA-58 actuator at the final joint on the arm. The mounting location (highlighted in black) and dimensions (mm) are provided in the following drawing.



The attachment of your end effector should be a circular part with six M3 screw holes. To facilitate the design of the end effector mounting part, download the CAD of the KA-58 actuator on the Kinova website product page.

**⚠ Note that there is a 4.0 mm groove on the actuator to correctly align the gripper and have a reference alignment for the robot's inverse kinematics.**