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## Reaching ultimate flexibility for robot grippers

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Since the beginning of robotics until today most robots in assembly and handling automation are equipped with part-specific grippers. Typically, these grippers are mechanical or vacuum in form factor. This approach does not work with high mix applications. One example of a high mix application is in the order fulfillment market for E-commerce order fulfillment. This talk will address the challenge in more detail, technology limitations in meeting the challenge, and new developments that hold promise to truly build a flexible robot gripper for very broad ranges of products.

### Biography

Charlie Duncheon is the Co-founder and Advisor of Grabit, Inc. He has more than 25 years of senior management experience in leading the growth of start-ups to successful companies. Duncheon has served on several Board of Directors including the Robotics Industries Association and Automation Technology Council. In 2000, he received the Robotic Industries Association Joseph Engleberger Leadership Award. Previously, he was elected president of the Robotics Industries Association, and served as the U.S. National Chairman for the United Nations International Federation of Robotics. Duncheon received his MBA from Southern Illinois University and his B.S. in industrial engineering from Purdue University.

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