



INSTALLATION AND OPERATING INSTRUCTIONS

Robot-specific SCM

for Denso robots

DDOC01259

THE KNOW-HOW FACTORY



Parameter explanation (glossary)

Parameter	Explanation
Cmd_Grip	Motion command for gripping the workpiece
Cmd_Release	Motion command for releasing the workpiece
IsReleased	The gripper signals that it is open.
IsGrasped	The gripper has gripped the workpiece and the position is within the taught-in workpiece window.
IsClosed	The gripper has gripped but there is no workpiece, so it is in the maximum position.

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1 Supporting documents

NOTICE



Read through the installation and operating instructions before installing or working with the product.

The installation and operating instructions contain important notes for your personal safety. They must be read and understood by all persons who work with or handle the product during any phase of the product lifetime.



The documents listed below are available for download on our website www.zimmer-group.com.

- Installation and operating instructions
 - Catalogs, drawings, CAD data, performance data
 - Information on accessories
 - Technical data sheets
 - General Terms and Conditions, including warranty information.
- ⇒ Only those documents currently available on the website are valid.

In these installation and operating instructions, "product" refers to the product designation on the title page!

1.1 Notices and graphics in the installation and operating instructions

DANGER



This notice warns of an imminent danger to the life and health of people. Ignoring these notices can lead to serious injury or even death.

► You absolutely must comply with the described measures for avoiding these dangers!

⇒ The warning symbols are assigned according to the type of danger.

WARNING



This notice warns of a situation that is potentially hazardous to personal health. Ignoring these notices can cause serious injury or damage to health.

► You absolutely must comply with the described measures for avoiding these dangers!

⇒ The warning symbols are assigned according to the type of danger.

CAUTION



This notice warns of a situation that is potentially hazardous for people or that may result in material or environmental damage. Ignoring these notices may result in slight, temporary injuries or damage to the product or to the environment.

► You absolutely must comply with the described measures for avoiding these dangers!

⇒ The warning symbols are assigned according to the type of danger.

NOTICE



General notices contain usage tips and valuable information, but no warnings of dangers to health.

INFORMATION



This category contains useful tips for handling the product efficiently. Failure to observe these tips will not result in damage to the product. This information does not include any information relevant to health or workplace safety.

2 Safety notices

CAUTION



Risk of injury and material damage in case of non-compliance

Installation, commissioning, maintenance and repairs may only be performed by qualified specialists in accordance with these installation and operating instructions.

The product is state-of-the-art.

It is fitted to industrial machines and is used to hold, transport and store workpieces.

The following are examples of situations in which the product may cause a hazard:

- The product is not properly installed, used or maintained.
- The product is not used for its designated purpose.
- The locally applicable regulations, laws, directives or guidelines are not observed.
- The product may only be used in accordance with these installation and operating instructions and the product's technical data.
- ⇒ Zimmer GmbH shall accept no liability for any damage caused by improper use. The operator bears sole responsibility.

3 Proper use

NOTICE



The product is only to be used in its original state with its original accessories, with no unauthorized changes and within the stipulated parameter limits and operating conditions.

Any other or secondary use is deemed improper.

- Operate the product only in compliance with the associated installation and operating instructions.
- Operate the product only when it is in a technical condition that corresponds to the guaranteed parameters and operating conditions.
- ⇒ Zimmer GmbH shall accept no liability for any damage caused by improper use. The operator bears sole responsibility.

The product is designed exclusively for electric operation using a 24 V DC power supply.

Direct contact with perishable goods/food is not permitted.

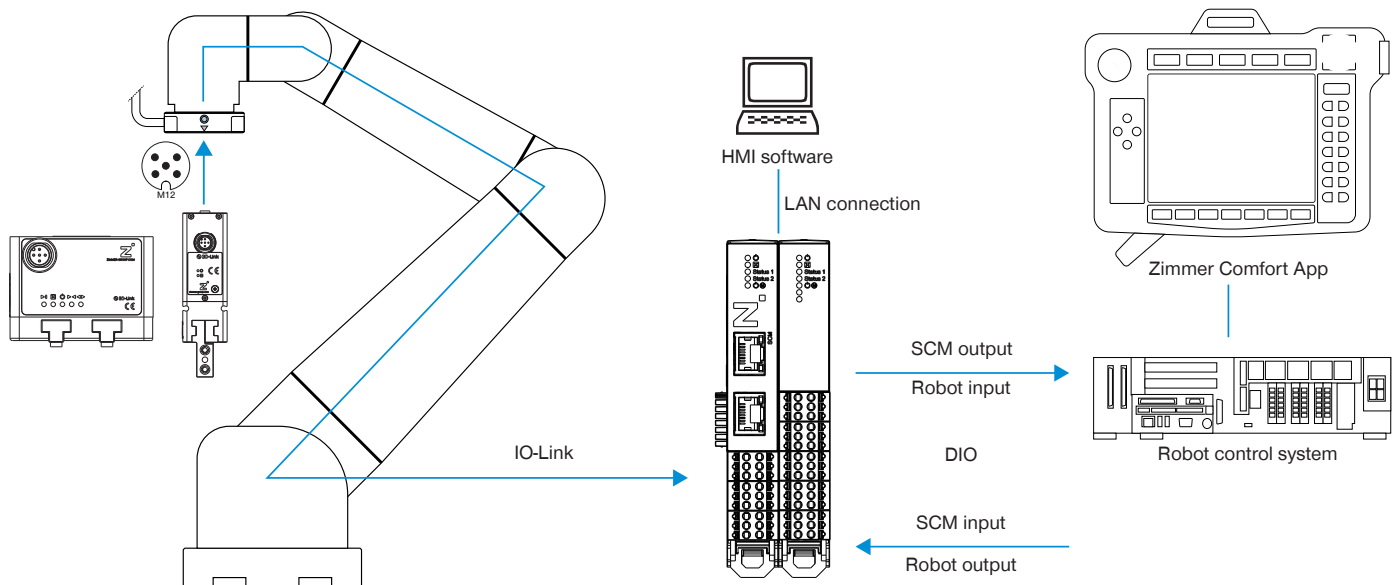
4 Personnel qualification

Installation, commissioning and maintenance may only be performed by trained specialists. These persons must have read and understood the installation and operating instructions in full.

5 Product description

The Smart Communication Module (SCM) is a gateway between the grippers and the robot control system. The SCM can be configured via the HMI software or Zimmer Comfort app. The grippers can be controlled using the Zimmer Comfort app on the robot control panel.

The image shows a simplified view of the structure of the overall system. All parts for the electrical connection of a gripper with the robot are included or are available from Zimmer GmbH as optional accessories.



Installation steps:

- ▶ Install the hardware.
- ▶ Establish the electrical connections at the robot control system.
- ▶ Establish a 24 V power supply.
- ▶ Install the HMI software and teach in the workpieces.
- ▶ Install the Zimmer Comfort app, see the operating instructions for the robot-specific Zimmer Comfort app.

6 Technical data

INFORMATION



- ▶ You can find the information in the technical data sheet on our website.
- This data varies within the series, depending on the specific design.
- ▶ Please contact Zimmer Customer Service if you have any questions.

7 Accessories/scope of delivery

INFORMATION



- If any accessories not sold or authorized by Zimmer GmbH are used, the function of the product cannot be guaranteed. Zimmer GmbH accessories are specifically tailored to the individual products.
- ▶ For optional accessories and those included in the scope of delivery, refer to our website.

8 Transportation/storage/preservation

- ▶ Transport and storage of the product must be done only with the original packaging.
- ▶ If the product has already been installed on the superordinate machine unit, care must be taken during transport to ensure that no unexpected movements can occur.
 - ▶ Before commissioning the product and after transport, check all power and communication connections as well as all mechanical connections.
- ▶ Visually inspect all components.

9 Installation

WARNING



Risk of injury due to uncontrolled movements

Risk of injury in case of unexpected movement of the machine or system into which the product is to be installed.

- ▶ Switch off the energy supply of the machine before any work.
- ▶ Secure the power supply against being switched on unintentionally.
- ▶ Check the machine for any residual energy that may be present.

CAUTION



Risk of injury due to electrical voltage

Risk of injury in the event of uncontrolled movement of the product when the power supply is connected.

- ▶ Switch off the power supply to the machine before carrying out any work.
- ▶ Secure the power supply against being switched on unintentionally.

NOTICE



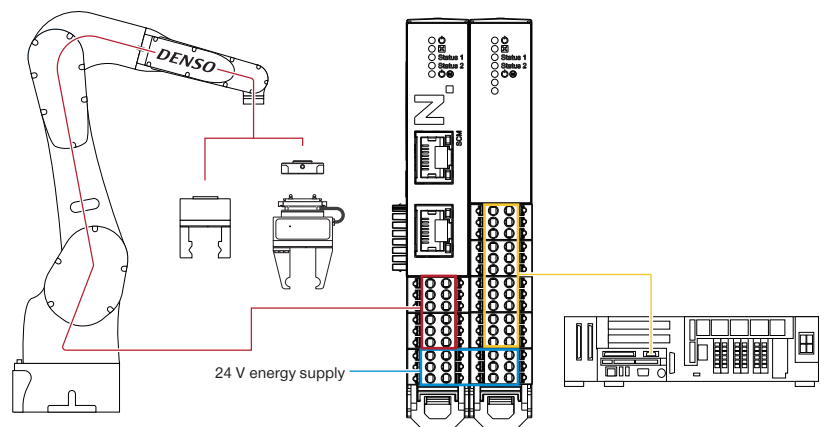
- ▶ Installation may only be carried out by qualified personnel in accordance with these installation and operating instructions.
- ▶ Switch off the power supply before any assembly, installation or maintenance work.

9.1 Installing hardware

The product is designed for installation on a standard 35 mm-wide profile rail.

The mounting position can be upright on the profile rail or suspended (profile rail mounted in the control cabinet).

- ▶ Keep a clearance of 5 cm each on the side of the ventilation slots of the product for air circulation.



9.1.1 Standard wiring

NOTICE



The gripper wiring must match the gripper configuration done in the Zimmer Comfort app.

NOTICE

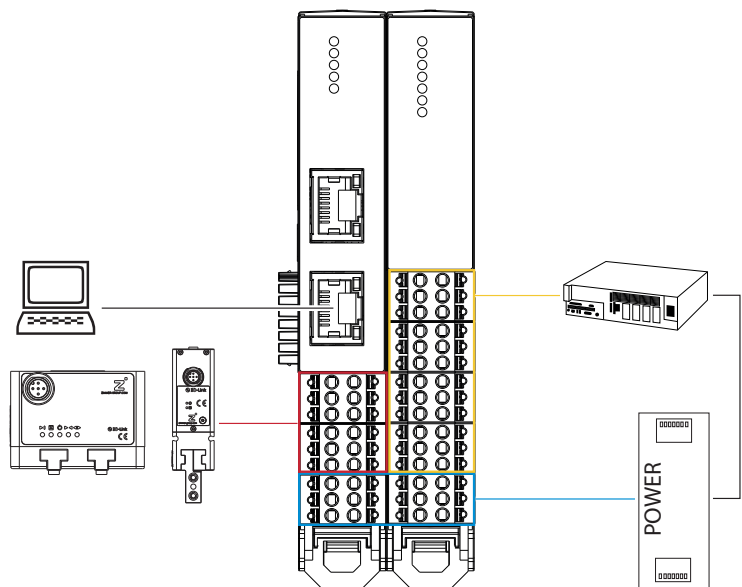


Because the robot control system does not provide sufficient power, an external power supply unit is necessary for the 24 V power supply.

For the connection assignment of the robot inputs and robot outputs, refer to the manufacturer documentation.

For the connection assignment of the SCM inputs and SCM outputs, refer to the installation and operating instructions of the SCM. The installation and operating instructions of the SCM are downloaded along with the Zimmer HMI.

► Note the potential equalization by connecting the GND/0V potentials of the SCM and robot control system.



The standard wiring corresponds to the standard configuration in the Zimmer Comfort app. If you do the standard wiring and keep the standard configuration in the Zimmer Comfort app, your grippers will function with the robot.

You have the option to change the standard wiring.

One reason for changing the standard wiring is when the robot input and output numbers are already used for a different external application and thus you cannot assign these to the gripper functions.

Another reason is if, on your robot, you can assign more than eight robot inputs and eight robot outputs to the gripper functions. In this case, you can use the full functionality of the SCM by assigning all SCM inputs and SCM outputs to the robot inputs and robot outputs.

9.1.2 Wiring of the robot IO card

Mini IO or Hand IO can be used on the Denso robot control system.

The default setting for the Zimmer Comfort app is Hand IO input Hin1 to 8 and Hand IO output Hout1 to 8.

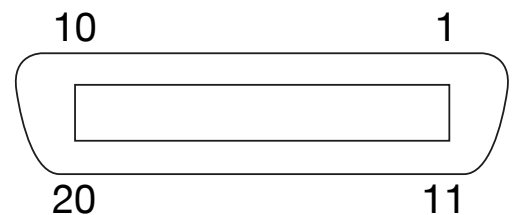
INFORMATION



► For more information on the robot control system, refer to the manufacturer documentation.

9.1.2.1 Connection assignment Hand IO input and Hand IO output [PNP type]

View of cable side

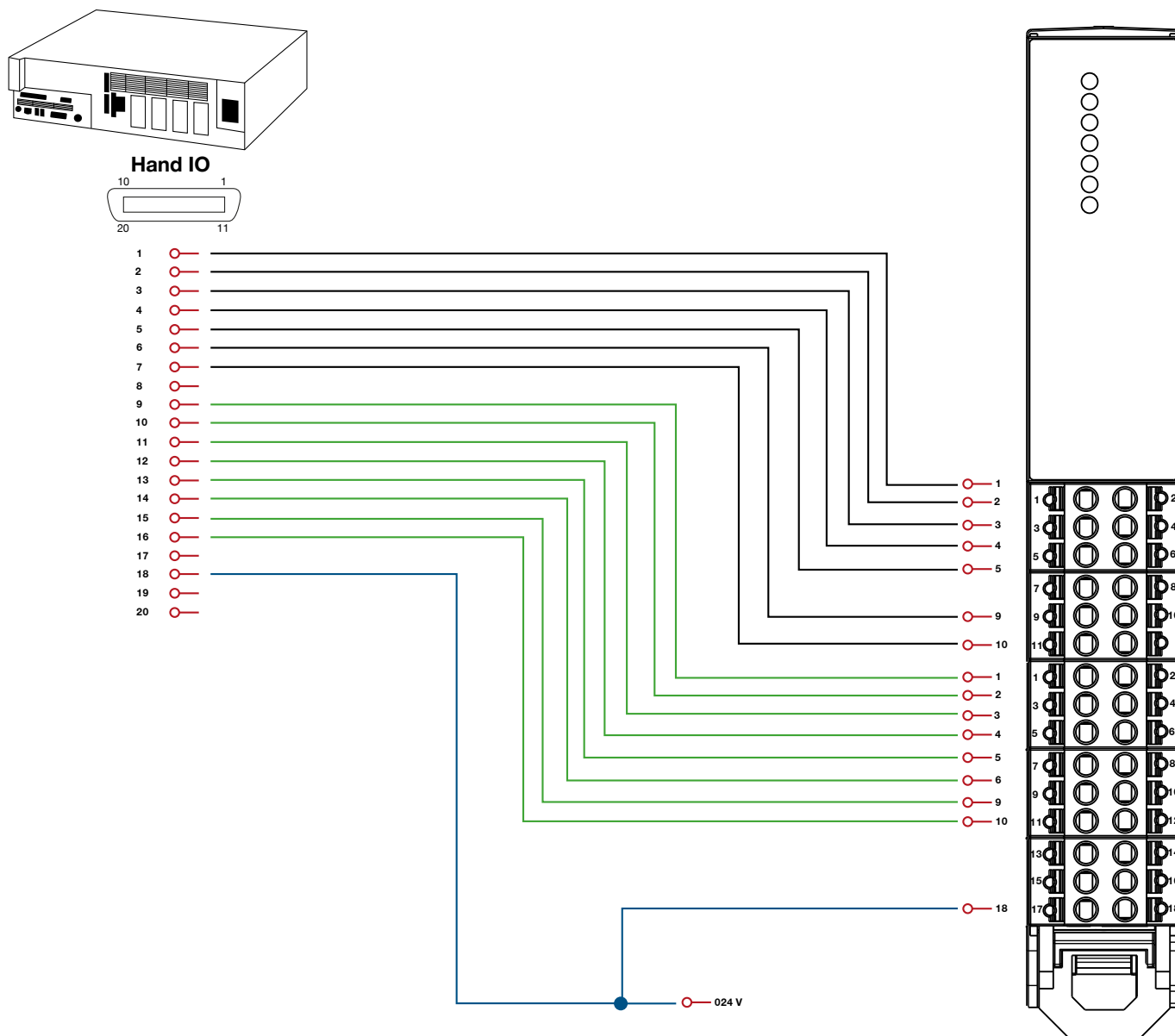


Terminal no.	Name	Connection no.	Wire color	
			Standard	Reinforced
1	Hand IO output	64	Black	Blue
2	Hand IO output	65	Brown	Yellow
3	Hand IO output	66	Black	Green
4	Hand IO output	67	Brown	Red
5	Hand IO output	68	Red	Violet
6	Hand IO output	69	Orange	Blue
7	Hand IO output	70	Yellow	Yellow
8	Hand IO output	71	Green	Green
9	Hand IO input	48	Blue	Red
10	Hand IO input	49	Violet	Violet
11	Hand IO input	50	Pink	White
12	Hand IO input	51	Pink	White
13	Hand IO input	52	White	White
14	Hand IO input	53	White	White
15	Hand IO input	54	White	White
16	Hand IO input	55	White	Brown
17	Current output (+0 VDC) (external/internal source)	-	White	Brown
18	Current output (+24 VDC) (external/internal source)	-	White	Brown
19	-	-	White	Brown
20	-	-	White	Brown

9.1.3 Standard wiring for individual grippers

SCM input and SCM output		
	Basic gripper	Advanced gripper
Cmd_Release	Out1	Out1
Cmd_Grip	Out2	Out2
Cmd_Reset	Out3	Out3
Cmd_MotorOn	-	Out4
Cmd_Homing	-	Out5
Cmd_WP_Bit0	Out6	Out6
Cmd_WP_Bit1	Out7	Out7
Cmd_WP_Bit2	-	-
Cmd_WP_Bit3	-	-
IsReleased	In1	In1
IsGripped	In2	In2
IsClosed	In3	In3
OnUndefinedPos	In4	In4
Error	In5	In5
MotorOn	-	In6
HomingOk	-	-
Act_WP_Bit0	In7	In7
Act_WP_Bit1	In8	In8
Act_WP_Bit2	-	-
Act_WP_Bit3	-	-

The following image shows the standard wiring for the Advanced gripper:



9.1.3.1 Basic gripper

If you keep the standard wiring, you can address workpiece numbers 1 to 7 because the SCM input Cmd_WP_Bit3 and the SCM output Act_WP_Bit3 are not connected.

Deviate from the standard wiring and add the necessary signals in the wiring to address all workpiece numbers from 1 to 15. A corresponding assignment of the SCM inputs and SCM outputs in the Zimmer Comfort app is required.

SCM connection	Command	Color	Robot output
1	Cmd_Release	White	Hout1
2	Cmd_Grip	Brown	Hout2
3	Cmd_Reset	Green	Hout3
4	-	-	-
5	-	-	-
6	-	-	-
7	-	-	-
8	-	-	-
9	Cmd_WP_Bit0	Black	Hout6
10	Cmd_WP_Bit1	Violet	Hout7
11	Cmd_WP_Bit2	Gray/pink	(Hout8)
12	Cmd_WP_Bit3	Rot/Blau	-
SCM connection	Command	Color	Robot input
1	IsReleased	White	Hin1
2	IsGripped	Brown	Hin2
3	IsClosed	Green	Hin3
4	OnUndefinedPos	Yellow	Hin4
5	Error	Gray	Hin5
6	-	-	-
7	-	-	-
8	-	-	-
9	Act_WP_Bit0	Black	Hin6
10	Act_WP_Bit1	Violet	Hin7
11	Act_WP_Bit2	Gray/pink	-
12	Act_WP_Bit3	Rot/Blau	-

9.1.3.2 Advanced gripper

If you keep the standard wiring, you can address workpiece numbers 1 to 3, because the SCM inputs (Cmd_WP_Bit2 and Cmd_WP_Bit3) and SCM outputs (Act_WP_Bit2 and Act_WP_Bit3) are not connected.

Deviate from the standard wiring and add the necessary signals in the wiring to address all workpiece numbers from 1 to 15. A corresponding assignment of the SCM inputs and SCM outputs in the Zimmer Comfort app is required.

SCM connection	Command	Color	Robot output
1	Cmd_Release	White	Hout1
2	Cmd_Grip	Brown	Hout2
3	Cmd_Reset	Green	Hout3
4	Cmd_Homing	Yellow	Hout4
5	Cmd_Homing	Gray	Hout5
6	-	-	-
7	-	-	-
8	-	-	-
9	Cmd_WP_Bit0	Black	Hout6
10	Cmd_WP_Bit1	Violet	Hout7
11	Cmd_WP_Bit2	Gray/pink	(Hout8)
12	Cmd_WP_Bit3	Rot/Blau	-
SCM connection	Command	Color	Robot input
1	IsReleased	White	Hin1
2	IsGripped	Brown	Hin2
3	IsClosed	Green	Hin3
4	OnUndefined	Yellow	Hin4
5	Error	Gray	Hin5
6	MotorOn	Pink	Hin6
7	HomingOk	Blue	-
8	-	-	-
9	Act_WP_Bit0	Black	Hin7
10	Act_WP_Bit1	Violet	Hin8
11	Act_WP_Bit2	Gray/pink	-
12	Act_WP_Bit3	Rot/Blau	-

9.1.4 Standard wiring for two grippers

In the scenario with two grippers, the SCM does not add the SCM inputs and SCM outputs provided for the workpiece numbers. Even if your robot has additional robot input and robot output lines available, only one workpiece per gripper is addressed. Some of the status lines, such as *isUndefinedPosition*, *isHomingOK*, *isMotorOn* are not used in some of the standard configurations.

SCM input and SCM output				
	Basic Greifer an Anschluss 1	Advanced gripper at port 1	Basic gripper at port 2	Advanced gripper at port 2
Cmd_Release	Out1	Out1	Out5	Out5
Cmd_Grip	Out2	Out2	Out6	Out6
Cmd_Reset	Out3	-	Out7	-
Cmd_MotorOn	-	Out3	-	Out3 or Out7
Cmd_Homing	-	Out4	-	Out8
Cmd_WP_Bit0	-	-	-	-
Cmd_WP_Bit1	-	-	-	-
Cmd_WP_Bit2	-	-	-	-
Cmd_WP_Bit3	-	-	-	-
IsReleased	In1	In1	In5	In5
IsGripped	In2	In2	In6	In6
IsClosed	In3	In3	In7	In7
OnUndefinedPos	-	-	-	-
Error	In4	In4	In8	In8
MotorOn	-	-	-	-
HomingOk	-	-	-	-
Act_WP_Bit0	-	-	-	-
Act_WP_Bit1	-	-	-	-
Act_WP_Bit2	-	-	-	-
Act_WP_Bit3	-	-	-	-

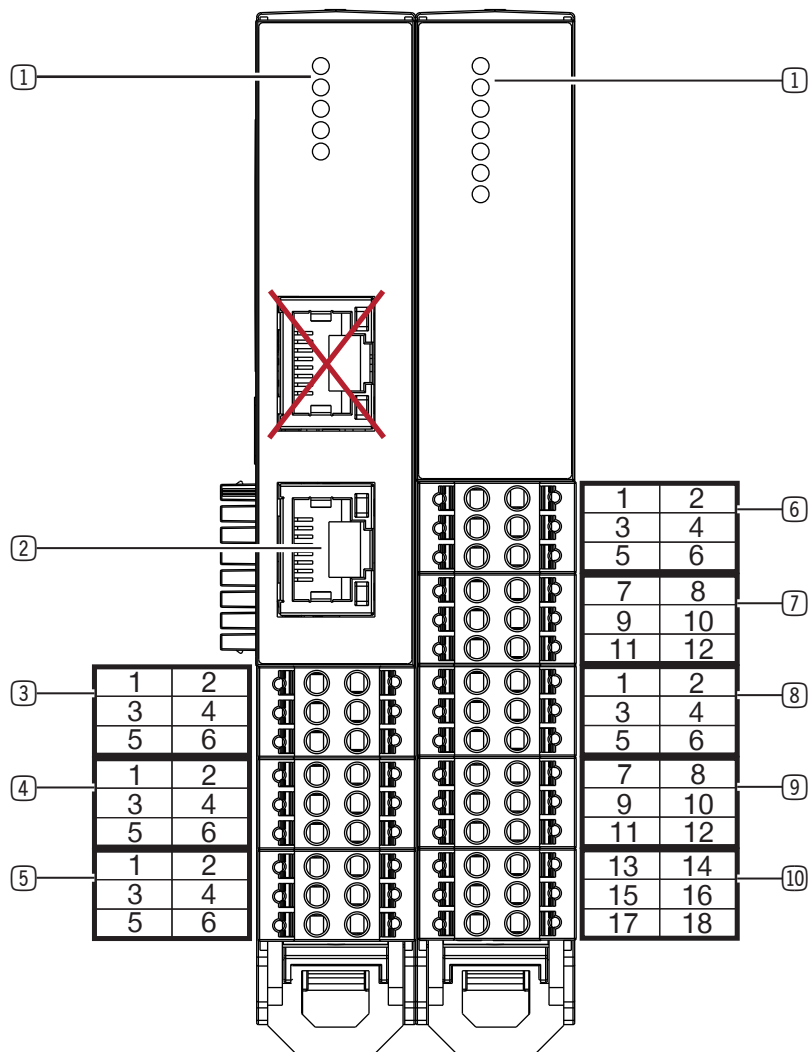
9.1.5 Advanced configuration

You can use the full functionality of the SCM by using more robot inputs and robot outputs. The functional assignment of the robot input and robot output numbers can be modified. A corresponding configuration of the extended wiring in the Zimmer Comfort app is required.

9.2 Installing the energy supply

9.2.1 Mounting the pin assignment

- ① Status
- ② Ethernet port
- ③ IO-Link X1
- ④ IO-Link X2
- ⑤ Power supply of basic module X3
- ⑥ Digital input X4
- ⑦ Digital input X5
- ⑧ Digital output X6
- ⑨ Digital output X7
- ⑩ Power supply of IO module X8



9.2.2 Installing the power supply for the basic module

- Fuse the product using a suitable circuit breaker in accordance with the expected current draw and the cable cross-sections used.

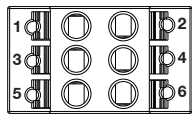
INFORMATION



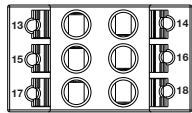
The signal and actuator voltage is electrically isolated in the product.

- Connect a maximum load of 10 A to pin 1 and pin 2.
- Connect a maximum load of 500 mA to pin 3 and pin 4.

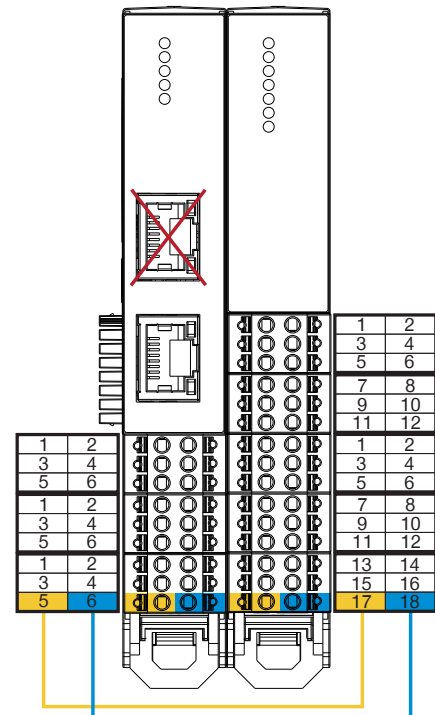
The maximum permitted current draw allows you to operate all grippers directly on the product. No Y-cable for a special power supply is required.

pin	Function	Explanation	 <p>Power supply of basic module X3</p>
1	+ 24 V DC actuator	Actuator supply voltage	
2	GND actuator	0 V DC actuator supply voltage	
3	+24 V DC input signal	SCM supply voltage and signal voltage for the grippers	
4	GND input signal	SCM ground and signal voltage for the grippers	
5	+24 V DC output signal	Signal voltage output for supplying power to the I/O module (connect to pin 17)	
6	GND output signal	GND output for supplying power to the I/O module (connect to pin 18)	

9.2.3 Installing the power supply for the IO module

pin	Function	Explanation	 <p>Power supply of IO module X8</p>
13	-	-	
14	-	-	
15	-	-	
16	-	-	
17	+ 24 V DC	+ 24 V DC supply voltage	
18	GND	0 V DC supply voltage	

- Connect pin 5 of the basic module to pin 17 of the IO module.
- Connect pin 6 of the basic module to pin 18 of the IO module.



9.2.4 Installing IO-Link

NOTICE



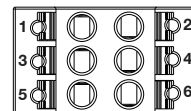
Non-compliance may result in material damage.

If the wiring is done differently, the gripper will be damaged.

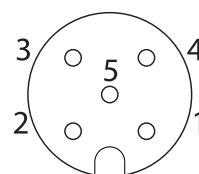
If the gripper has an additional STO cable (Safe-Torque-OFF), this is wired with the external safety circuit independently of the SCM.

The pin assignments listed in the table are for both IO-Link channels.

IO-Link X1/IO-Link X2				M12 5-pin socket	
pin	Color	Function	Explanation	pin	Color
1	Black	C/Q	IO-Link communication	4	Black
2	-	-	-	6	-
3	White	+ 24 V DC actuator	Actuator supply voltage	2	White
4	Gray	GND actuator	0 V DC actuator supply voltage	5	Gray
5	Brown	+ 24 V DC sensor	Supply voltage of sensor	1	Brown
6	Blue	GND sensor	0 V DC sensor supply voltage	3	Blue



IO-Link X1/IO-Link X2



M12 5-pin socket

10 Installation

10.1 Setting up the Ethernet connection

Only the lower Ethernet port is active and is connected to a Windows PC to configure the product.

INFORMATION



Factory setting:

- IP: 10.0.0.5
- Network mask: 255.0.0.0

- ▶ Adapt your network card.
- ▶ Check whether your firewall supports communication with the product.

INFORMATION



The communication protocol used is UDP. Therefore, integration into a network is possible only with limitations.

- ▶ For more information on changing the IP address, refer to the section "SCM network settings".
- ▶ Please contact Zimmer Customer Service if you have any questions.

10.2 Downloading software

Every SCM device is delivered with a digitalZ document including a download code.

- ▶ Download the HMI software *ZG_IO_LINK_HMI* using the reference link specified in the digitalZ document or the QR code.
- ▶ Install the HMI software *ZG_IO_LINK_HMI* on a Windows PC.

11 Commissioning

This section describes how to configure the gripper using the product.

NOTICE



- ▶ All workpiece recipes must be taught in in the *guideZ* control level.
- ▶ At least the first workpiece recipe must be assigned with a taught-in workpiece in the product.

The product boots if it is wired correctly, the desired grippers are connected and the power supply is switched on.

Depending on the most recently stored configuration on the product, the power LEDs light up in green. Then Status 1 and Status 2 flash on the basic module as long as the grippers are being searched for.

NOTICE



- ▶ When cold booting the SCM, ensure that all digital SCM inputs are not connected so that the initialization sequence can finish successfully.
- ▶ Disconnect the SCM from the power supply only if both grippers are no longer moving.

11.1 Establishing the connection

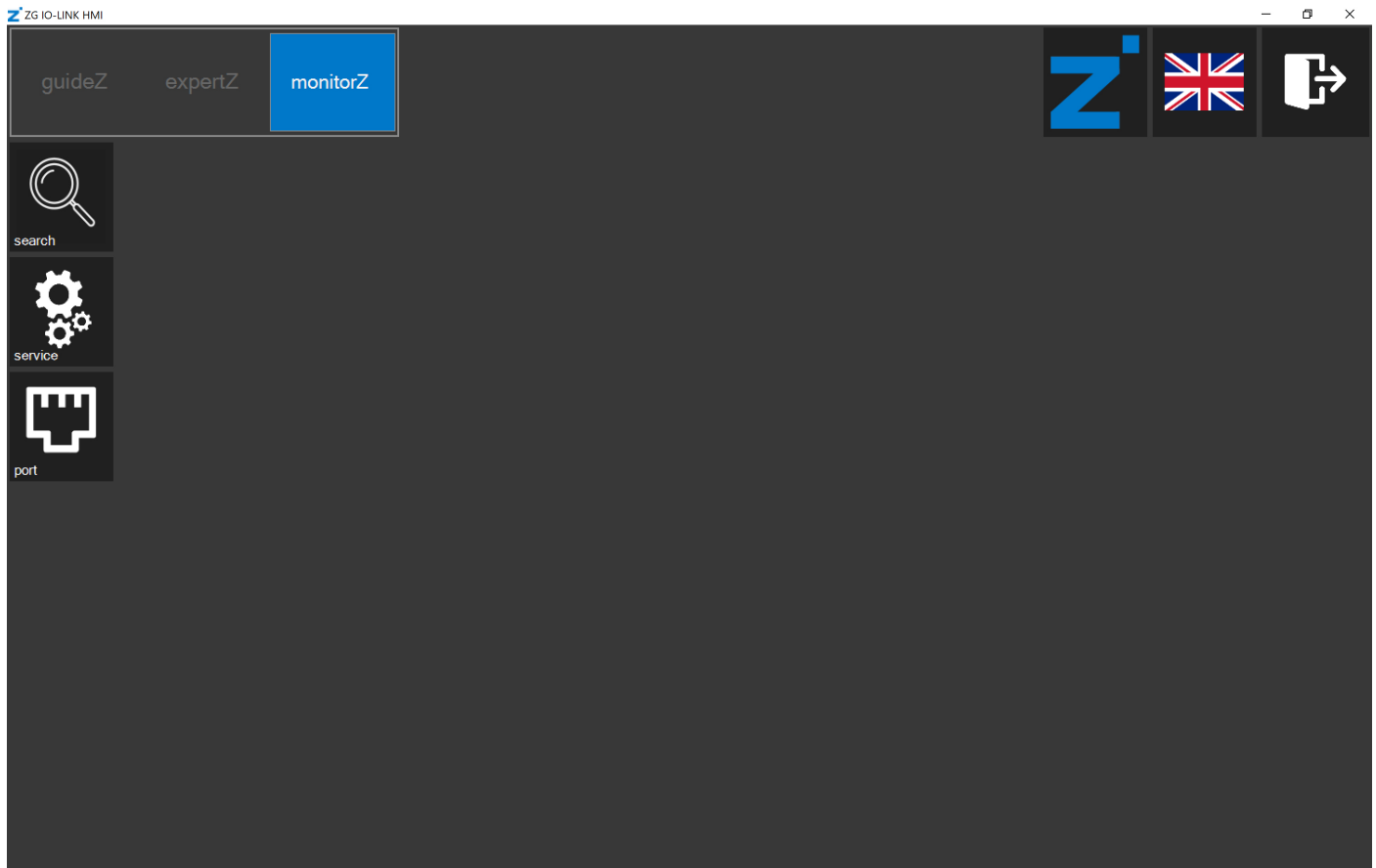
INFORMATION



You need the HMI software *ZG_IO_Link_HMI* from Zimmer GmbH in Version 2.0.1.22 or higher.

The three control levels are located in the top menu bar:

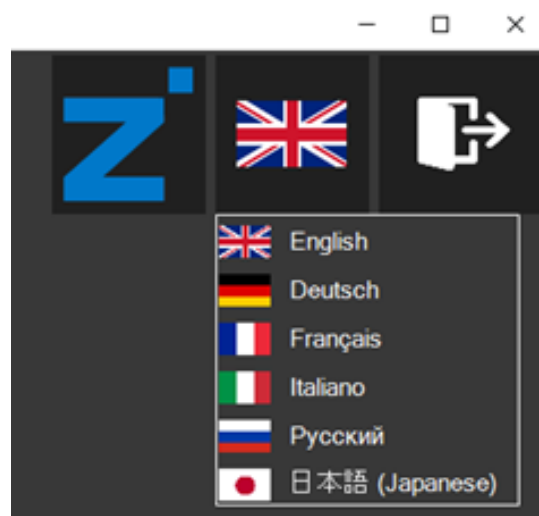
- *expertZ*: expert level where all gripper data can be accessed.
- *guideZ*: configuration level where the gripper can be taught in to the desired workpiece.
- *monitorZ*: diagnostic and observation level for monitoring the gripper during operation.



- Connect the Windows PC with the installed HMI software *ZG_IO_Link_HMI*.

11.2 Selecting the language

- Click the flag to change the language of the HMI software.



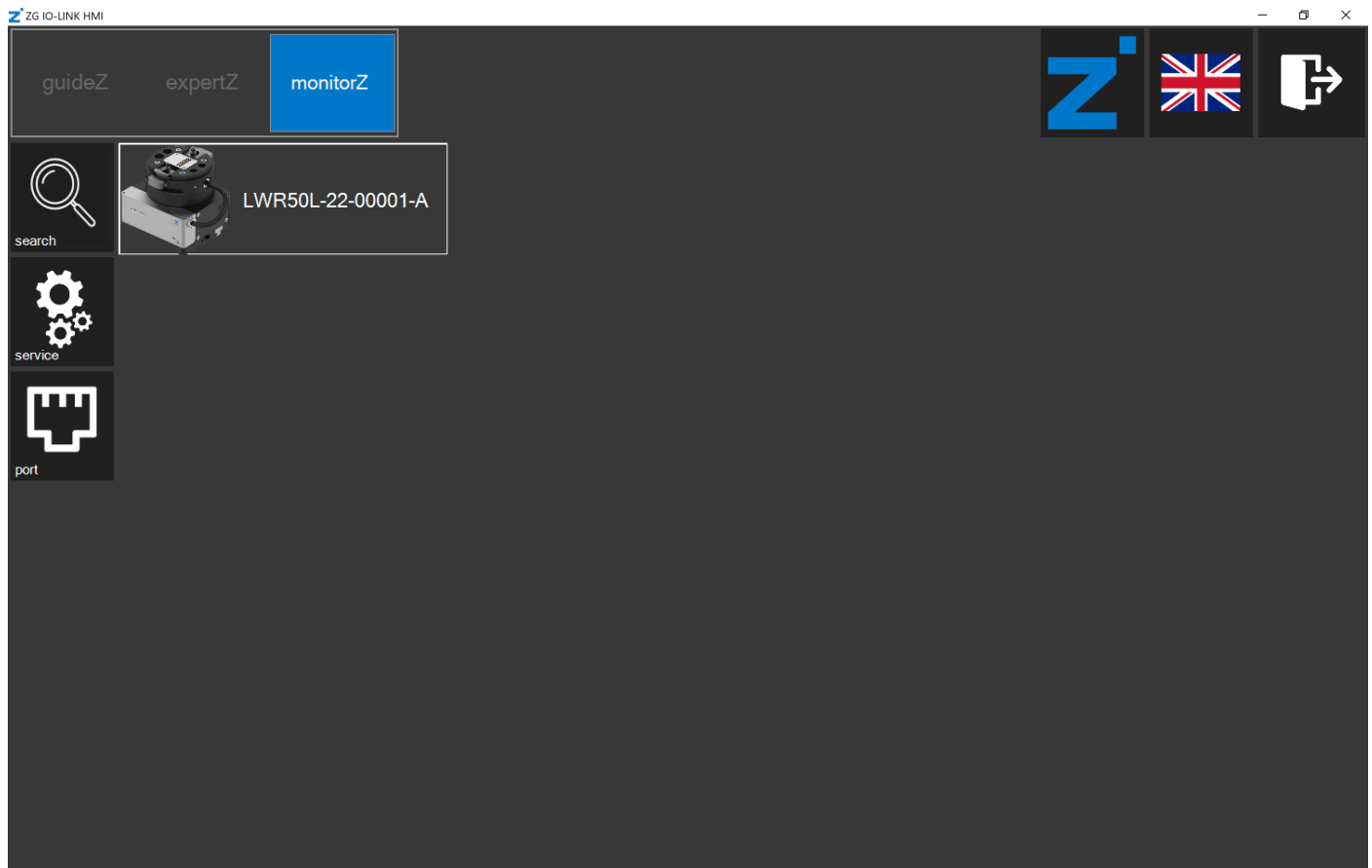
11.3 Checking the version

- Click the Zimmer logo to view information about the HMI software.



11.4 Selecting the gripper

- Click the *search* button.
- ⇒ The connected grippers are listed.



- Click the desired gripper to teach this in to the workpiece.
- ⇒ The *guideZ* control level opens.

11.5 Switching on and referencing the motor

NOTICE



- Switch on the motor in the robot control panel also.

- Connect the actuator voltage.
- ⇒ The *power supply* LED lights up green if the actuator voltage is connected.
- Click the *on* button to switch on the motor.
- Click and hold the > < button for referencing the gripper.
- ⇒ This also references the gripper towards the outside or inside.

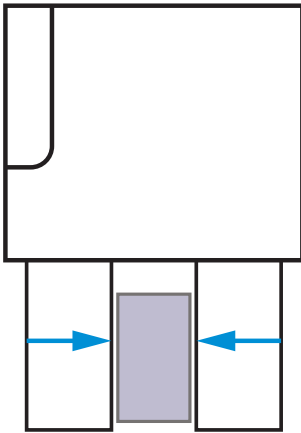


- Click the > button.

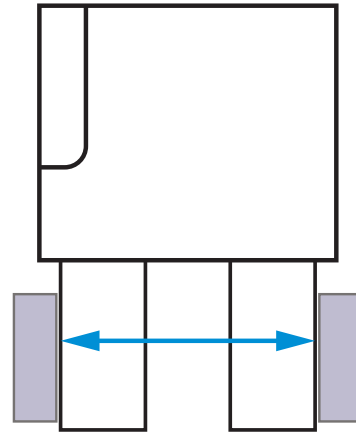
11.6 Selecting the gripping direction

- Select the gripping direction.

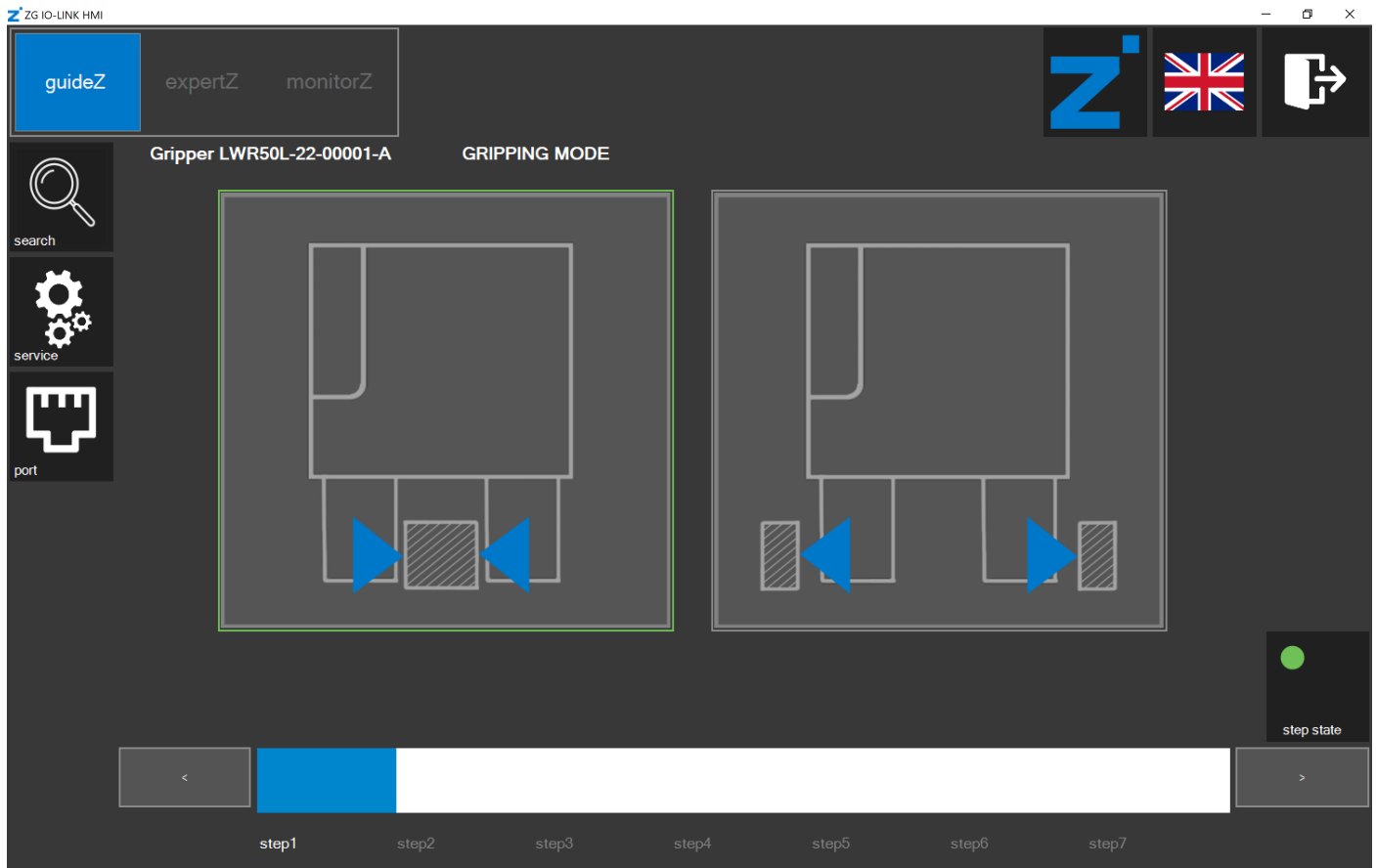
Outside gripping



Inside gripping



⇒ The parameters are set for the gripper automatically.



⇒ The *step state* LED lights up green.

- Click the > button.

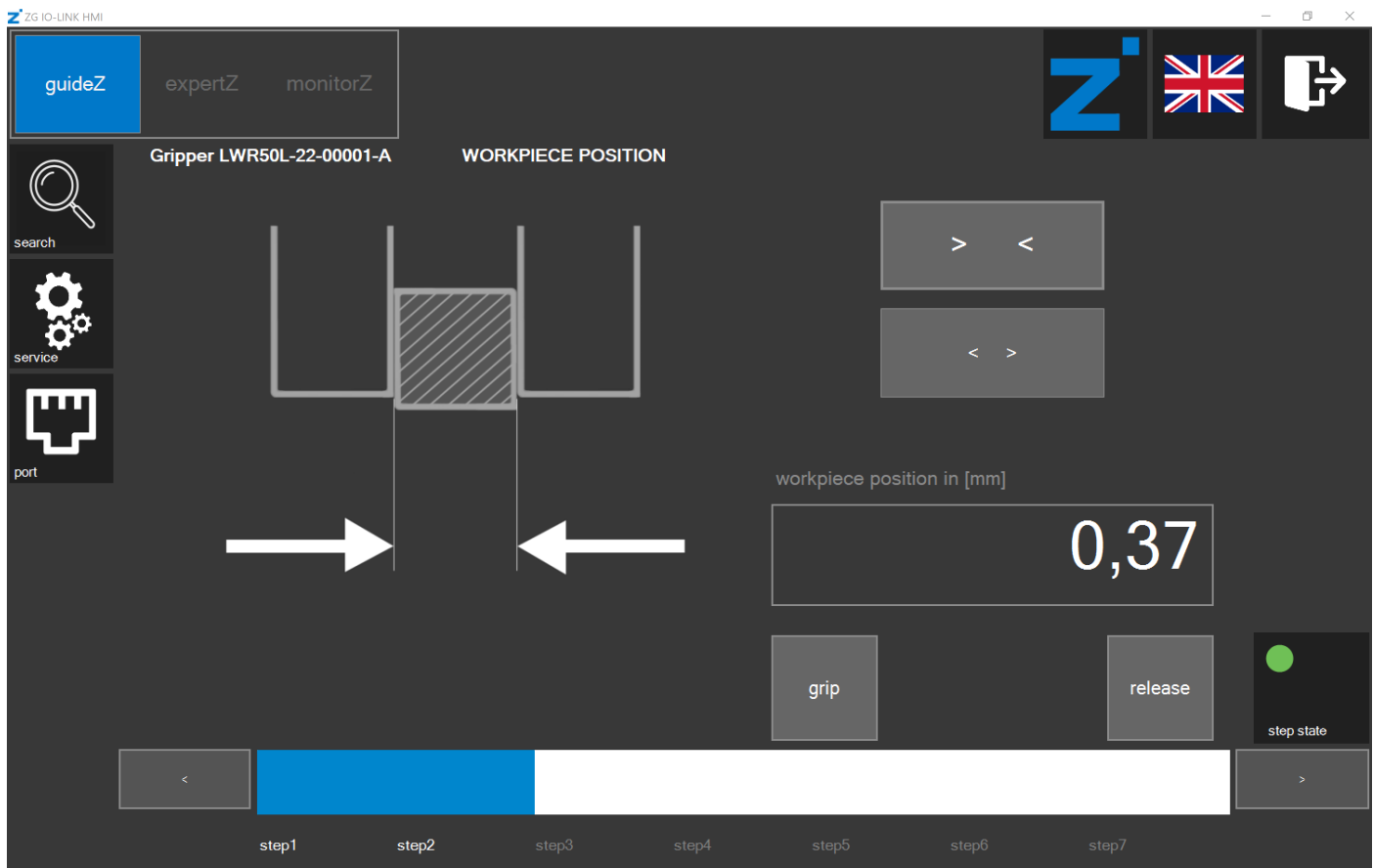
11.7 Teaching in the workpiece

INFORMATION



The buttons for the preferred setting are highlighted visually.

- Click and hold the > < and < > buttons to teach in the workpiece parameters for the gripper.
- ⇒ The gripper detects the standstill and remembers the workpiece position.



INFORMATION



You can use the *grip* button and the *release* button to test the settings.

- Click the > button.

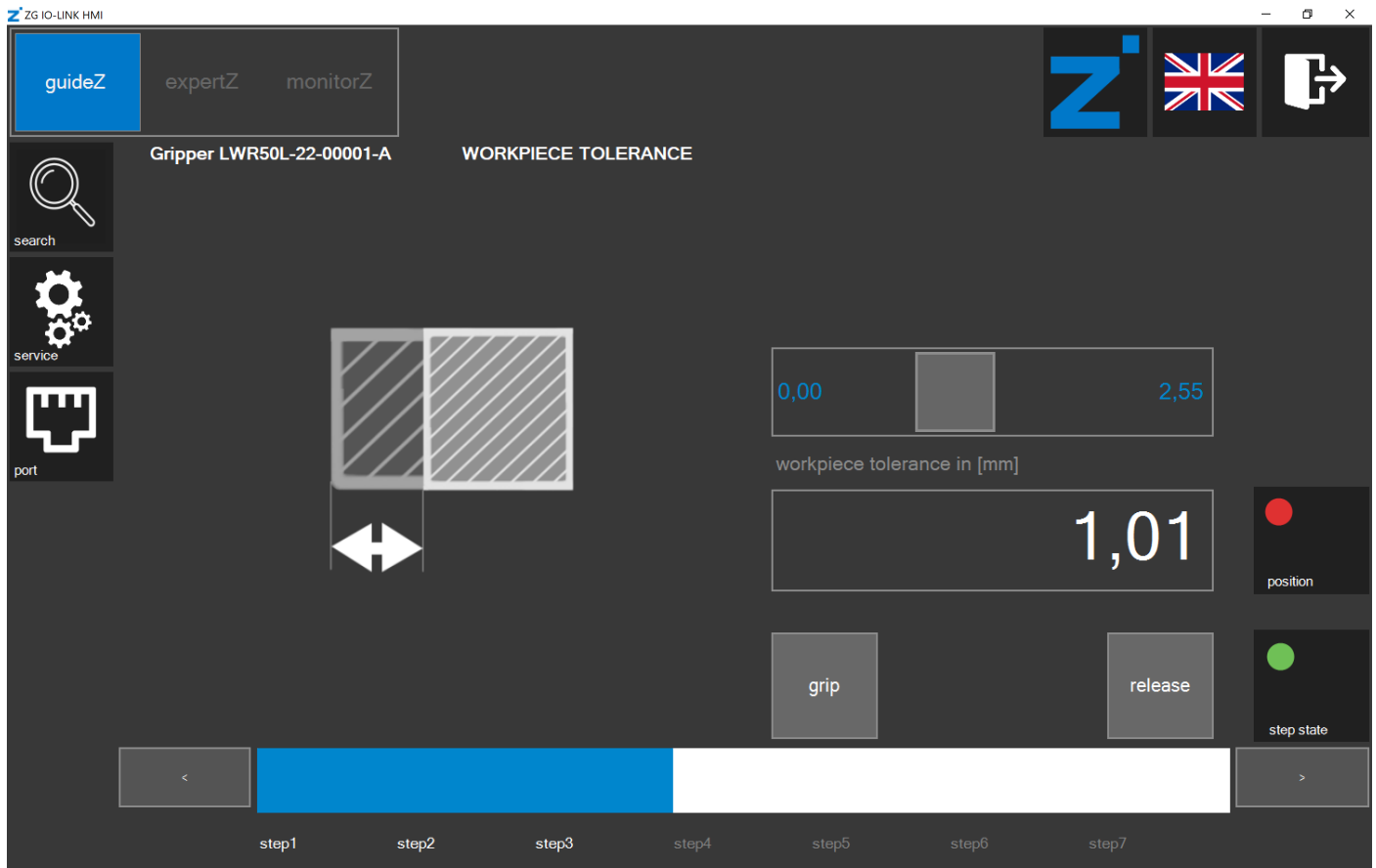
11.8 Setting the workpiece tolerance

- Slide the bar to a tolerance of 0.00 mm to 2.55 mm.

INFORMATION



A gripper with servo function automatically sets its closed position just after the workpiece tolerance.



- Click the > button.

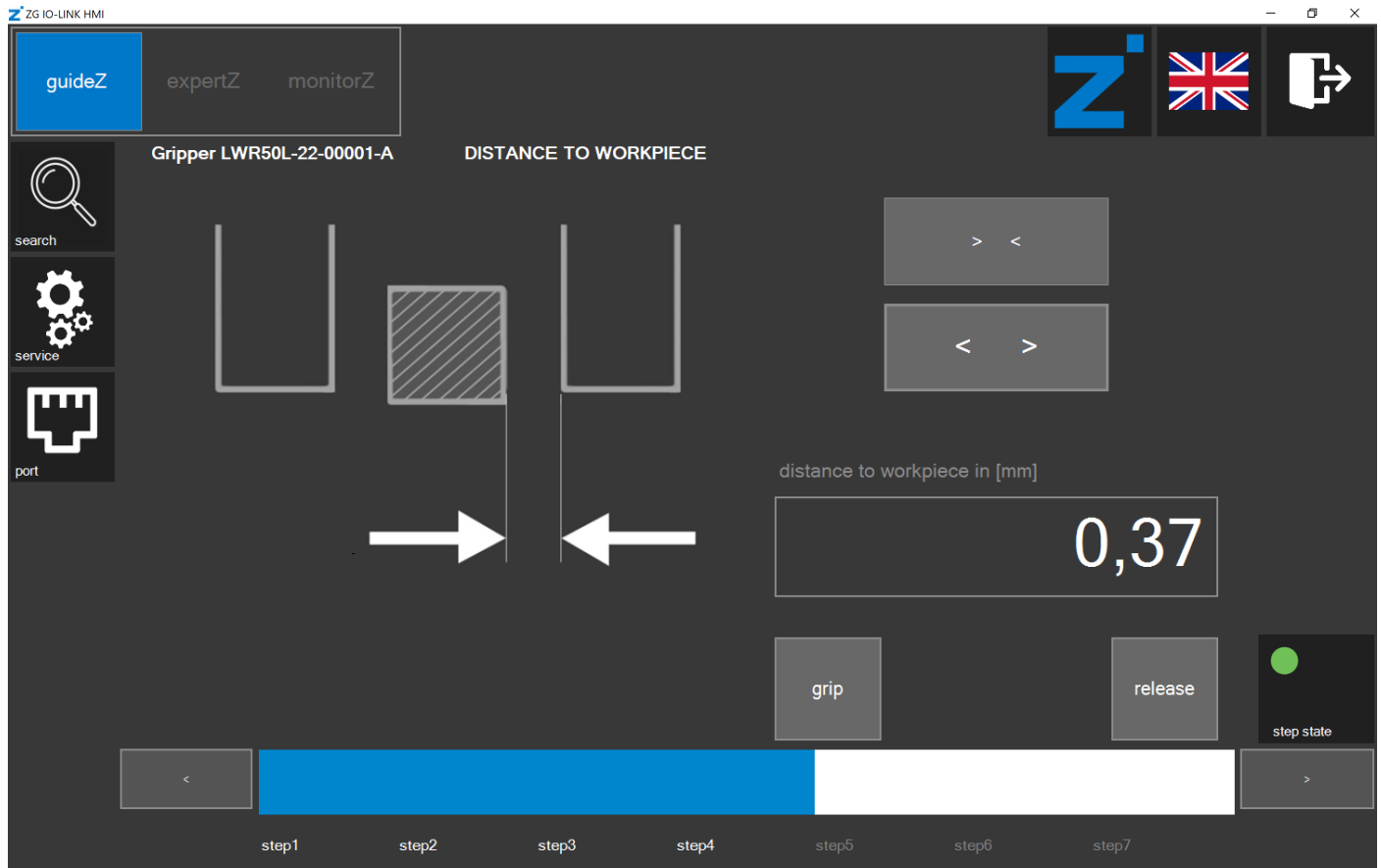
11.9 Setting the open position

INFORMATION



The open position can only be set for grippers with a servo function.

- Click and hold the > < and < > buttons to set the position at which the gripper is to be open.

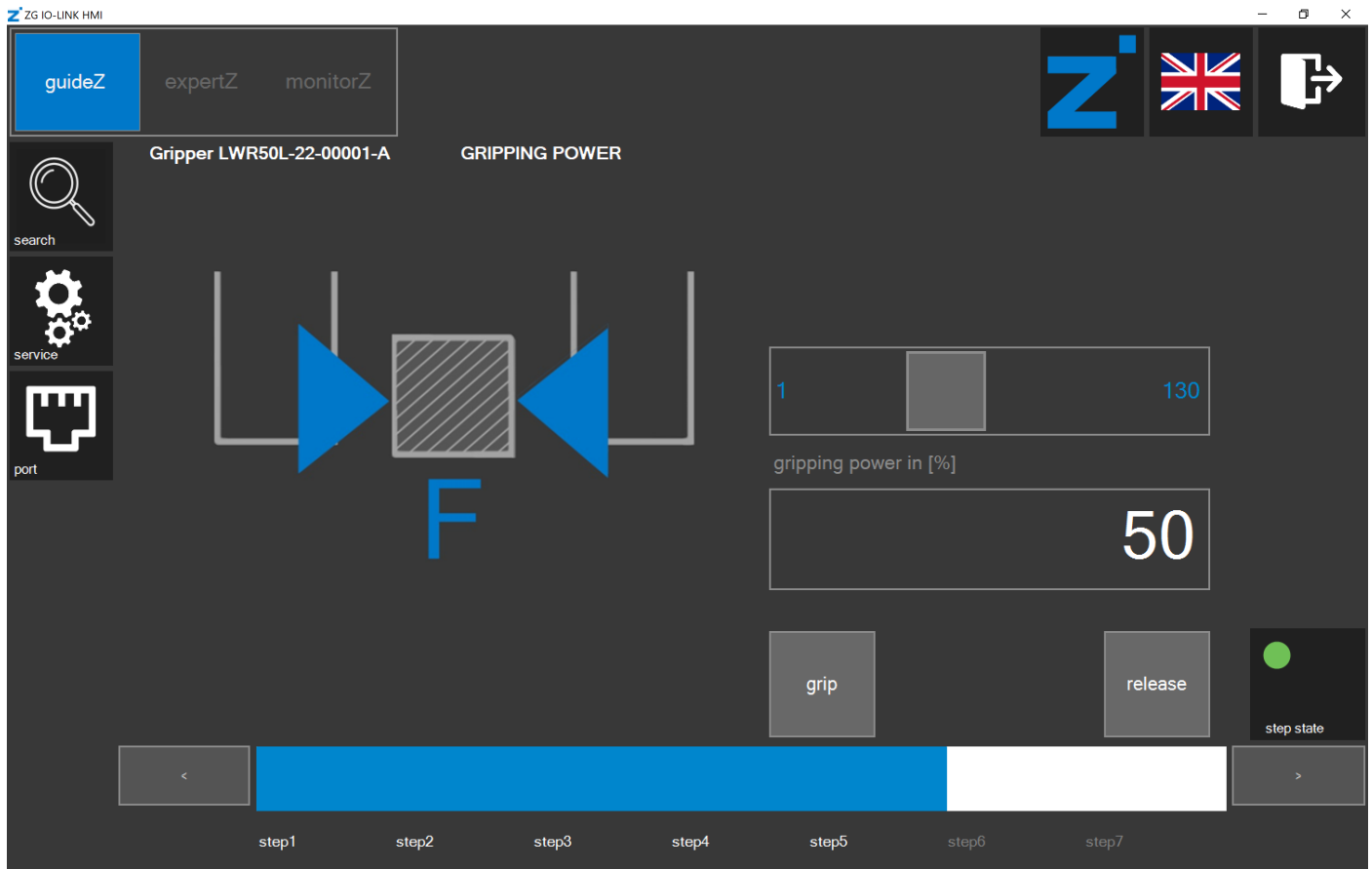


- Click the > button.

11.10 Setting the gripping force

Depending on the gripper, the gripping force can be configured and in addition, the speed for closing can be configured.

- Slide the bar to the desired gripping force.



- Click the > button.

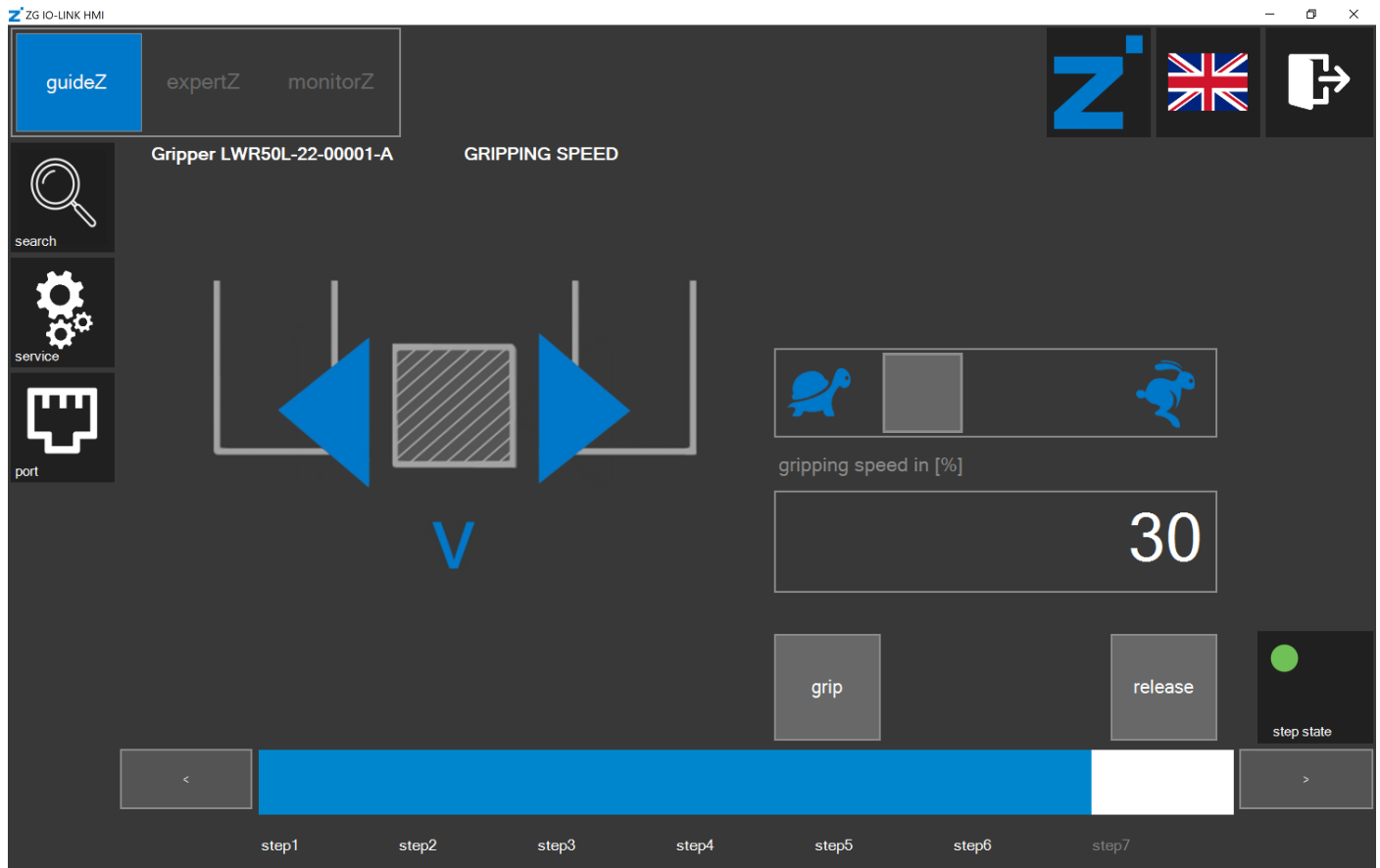
11.11 Setting the speed for opening the gripper

INFORMATION



Setting the speed for opening the gripper is only possible for grippers with a servo function.

► Slide the bar to the desired speed.



► Click the > button.

11.12 Checking the settings

Workpiece training for the gripper is ended when the data is saved in the corresponding workpiece recipe.

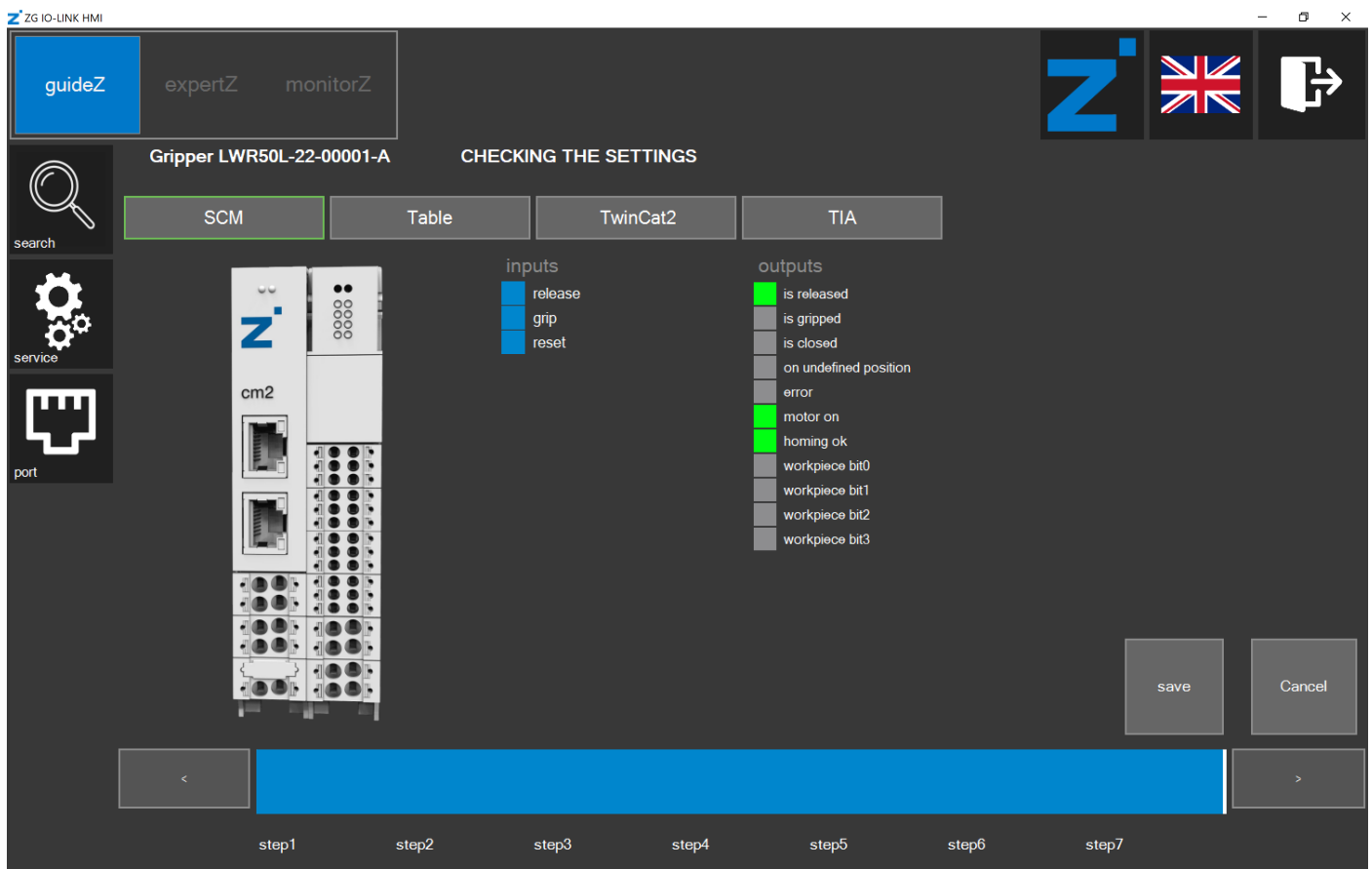
INFORMATION



At this point, the set parameters are not yet saved in the corresponding workpiece recipe.

The settings can also be checked without the robot inputs and robot outputs of the robot control system.

- *inputs:*
 - ▶ Click the fields to set a command.
 - ⇒ The yellow commands are set.
- *outputs:*
 - ▶ The fields indicate the status of the gripper.
 - ⇒ The green statuses are active.



INFORMATION



The *Table* view shows the parameters of the corresponding gripper generated in the background.

The *TwinCat2* and *TIA* views show the wiring of the PLC function blocks to fit the parameters of the gripper.

- ▶ Click the *Save* button.
- ⇒ The window for saving the workpiece recipe opens.

11.13 Saving the workpiece recipe

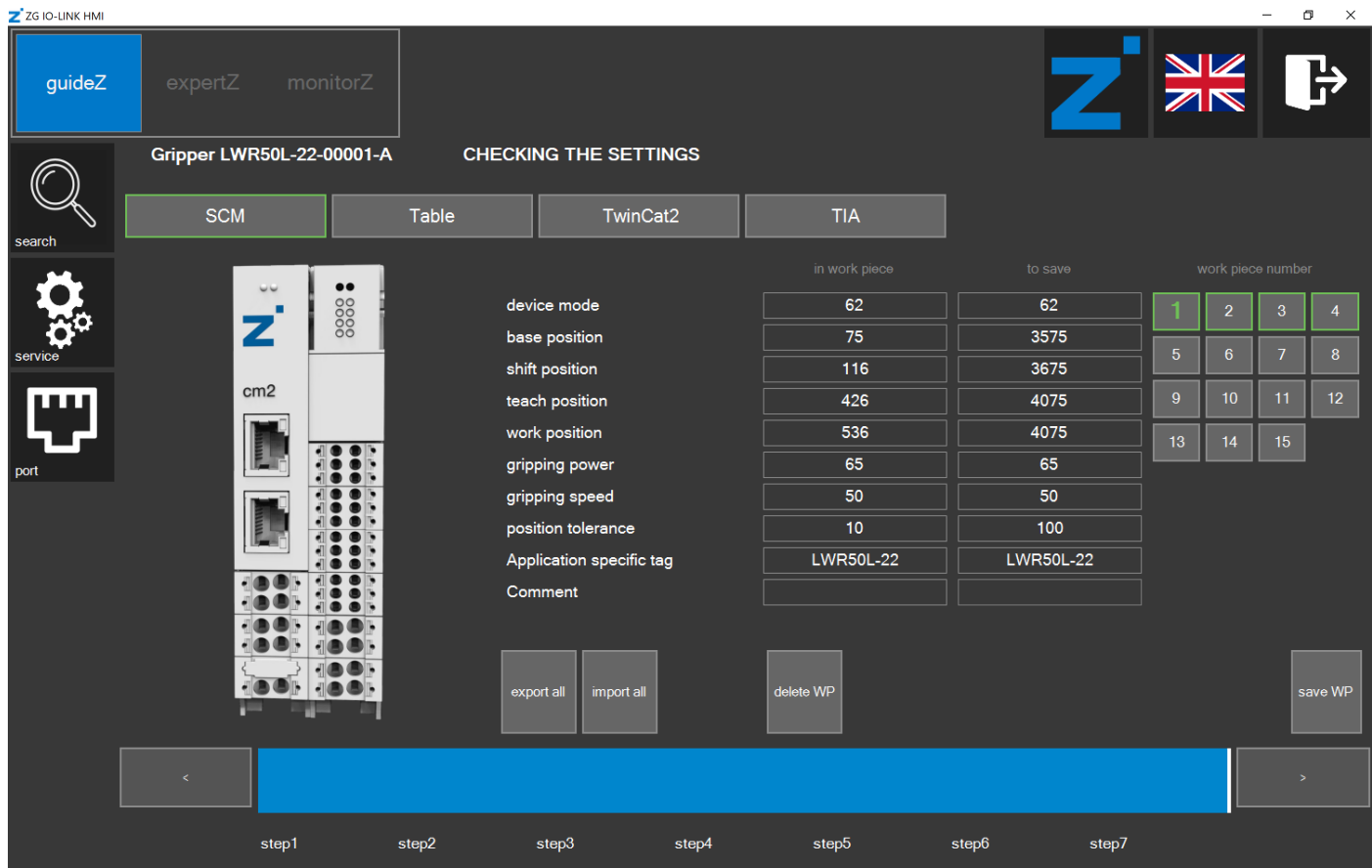
INFORMATION



The highlighted digit in the workpiece number shows the respective selected workpiece recipe number.

The workpiece recipe numbers in a green frame show stored recipes of the current gripper.

The workpiece recipe numbers in an orange frame show stored recipes of another gripper.



- Click the desired workpiece recipe number.
- Click the save *WP* button.

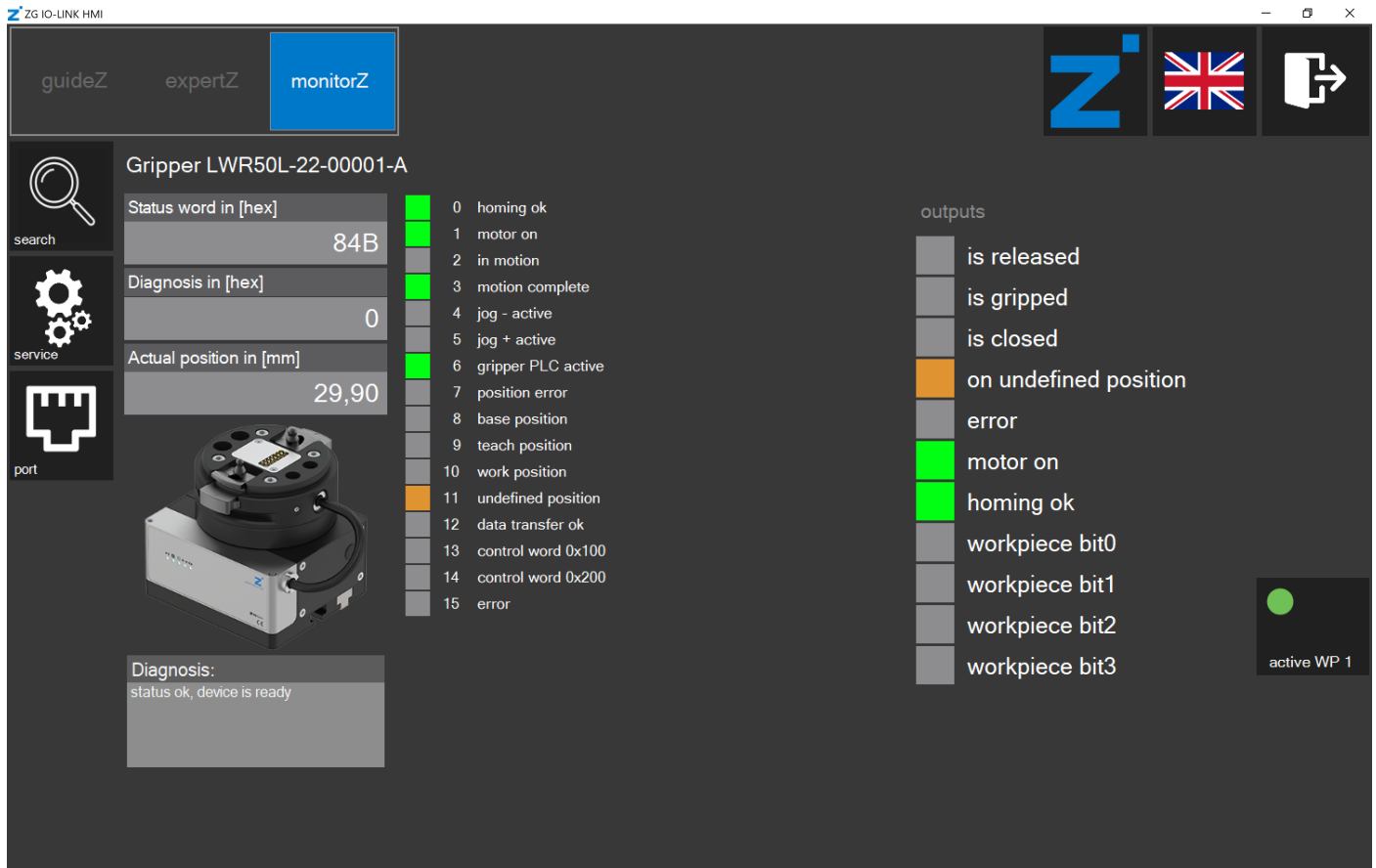
11.14 Data storage ended

- After successful data storage, the window for teaching in a new workpiece is displayed, see the section "Teaching in the workpiece".
- Click the *monitorZ* button if you want to switch to the *monitorZ* control level instead.



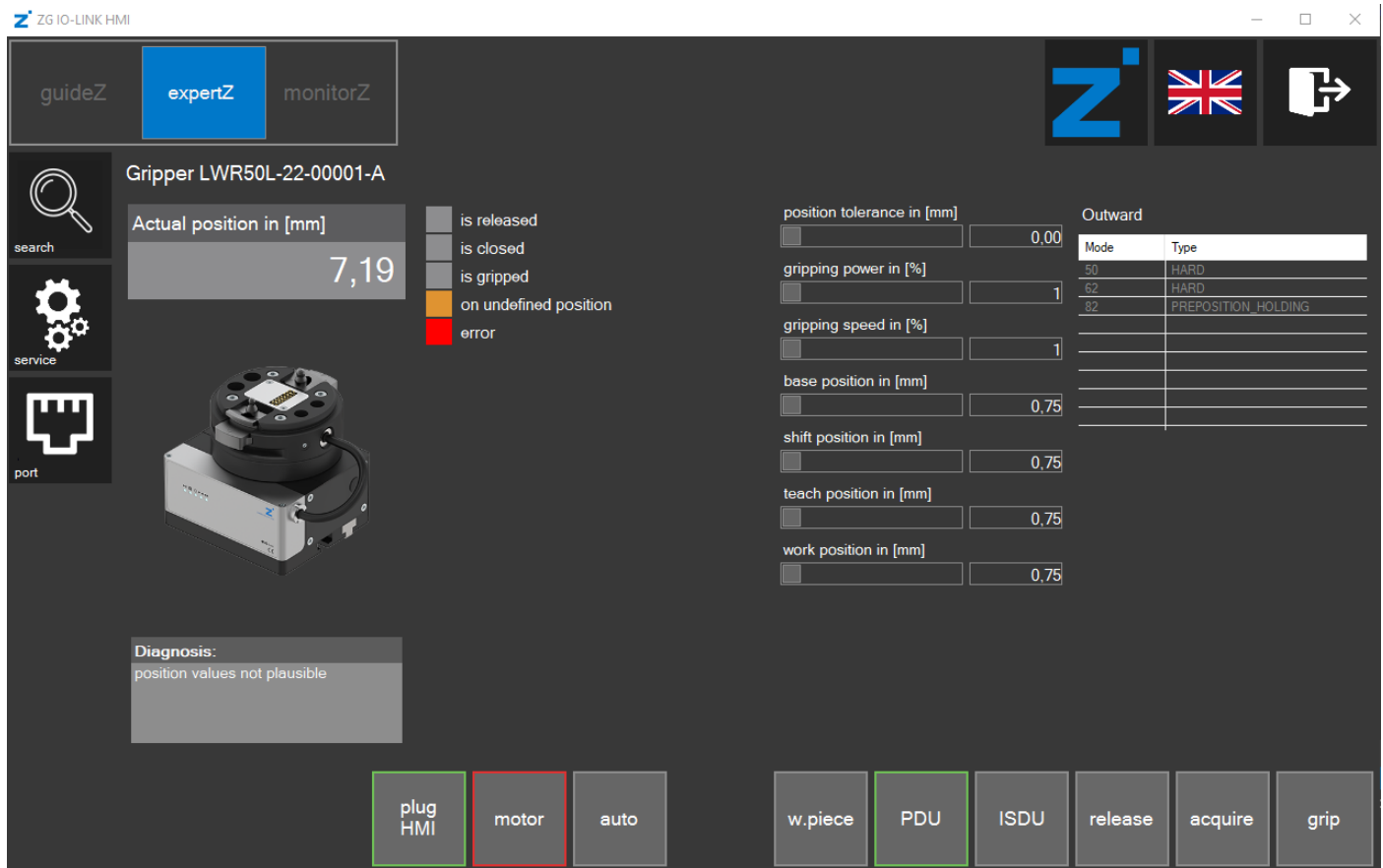
11.15 monitorZ control level

- Click the *plug HMI* button to transfer the control ability to the digital robot inputs and robot outputs.
- ⇒ The LED lights up red.
- ⇒ The control system of the gripper with the HMI software *ZG_IO_LINK_HMI* is no longer possible because the input and output signals now have control.
- ⇒ You can move the gripper with the external control system and the saved settings.



11.16 expertZ control level

In the *expertZ* control level, fine tuning of the gripping parameters as well as access to all process data (PDU), service data (ISDU) and workpieces is possible.



By default, the *fine tuning* setting is active. This is a view based on the parameters configured in the *guideZ* control level. You can optimize these parameters in this view.

- Slide the bar to the desired value to change it.
 - In the *Outward* area, click the desired *mode* to change it.
 - Click the *release* button or the *grip* button to apply the changes and run the motion task.
- ⇒ The HMI software checks whether the value can be processed by the gripper and, if necessary, adapts these to its limit values.

11.16.1 Service

- Click the *service* button.
- ⇒ A login window opens.
- Enter the password: *Service*

- ⇒ The *Service* window opens.

11.16.1.1 Service report

- In the *service report* area, click the create button to create a service report.

11.16.1.2 Data transfer time

The *Data transfer time* is the time needed for data transmission to the gripper.

11.16.1.3 Automatic time

The *Automatic time* is the pause time of the automatic sequence.

- Slide the bar to the desired time.

11.16.1.4 Application settings

- Enable the option *expertZ as start* if *expertZ* is to be displayed as the new start view.
- To get full access to all the parameters, *expertZ fine tuning* mode must be switched off.
- Disable the option *expertZ fine tuning*.

Gripper LWR50L-22-00001-A

Status word in [hex]: 84B

Diagnosis in [hex]: 0

Actual position in [mm]: 29,92

Diagnosis: status ok, device is ready

0	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15
homing ok	motor on	in motion	motion complete	jog - active	jog + active	gripper PLC active	position error	base position	teach position	work position	undefined position	data transfer ok	control word 0x100	control word 0x200	error

0	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15
acquire	store wp	reset flag	teach	to base	to work	jog plus	jog minus	reset error							

device mode: 62

workpiece no: 0

position tolerance in [mm]: 0,10

gripping power in [%]: 65

gripping speed in [%]: 50

base position in [mm]: 30,06

shift position in [mm]: 30,07

teach position in [mm]: 30,06

work position in [mm]: 31,16

Outward		Inward	
Mode	Type	Mode	Type
50	POSITION	72	HARD
62	HARD	92	PREPOSITION
82	PREPOSITION		

grip force graph: [Graph showing grip force over time]

Buttons: plug HMI, motor, auto, w.piece, PDU, ISDU, to base, acquire, to work

- In the *Application settings* area, enable the *USB master only* option if network communication is to be switched off.
 - Enable the option only if you have a Zimmer PrepBox with a USB cable.
- ⇒ The HMI software searches for USB nodes only.

11.16.1.5 SCM network settings

- In the *IP address* area, click the field to change the IP address of the SCM.
- Close the *Service* window.
- Run out a cold boot.

11.16.2 Starting the automatic sequence

In the automatic sequence, the gripper makes cyclical opening and closing movements.

► Click the *autobutton*.

11.16.3 Workpiece recipe management

In workpiece recipe management, the previously adapted parameters can be stored to the workpiece database again. In the *in work piece* area, the data with workpiece recipe numbers that are currently selected in the *work piece number* is displayed. In the *to save* area, the data that can be stored to the selected workpiece recipe number with the save *WP* button is displayed.

► Click the *w.piece* button to open workpiece recipe management.

ZG IO-LINK HMI

guideZ
expertZ
monitorZ

search

service

port

Gripper LWR50L-22-00001-A

	in work piece	to save
device mode	62	82
base position	317	692
shift position	961	1525
teach position	1256	1874
work position	1927	2625
gripping power	13	47
gripping speed	47	67
position tolerance	31	65
Application specific tag	LWR50L-22	LWR50L-22
Comment	LWR	

export allimport all

delete WP

load from WP

save WP

1234

5678

9101112

131415

plug HMI

motor

auto

w.piece

PDU

ISDU

to base

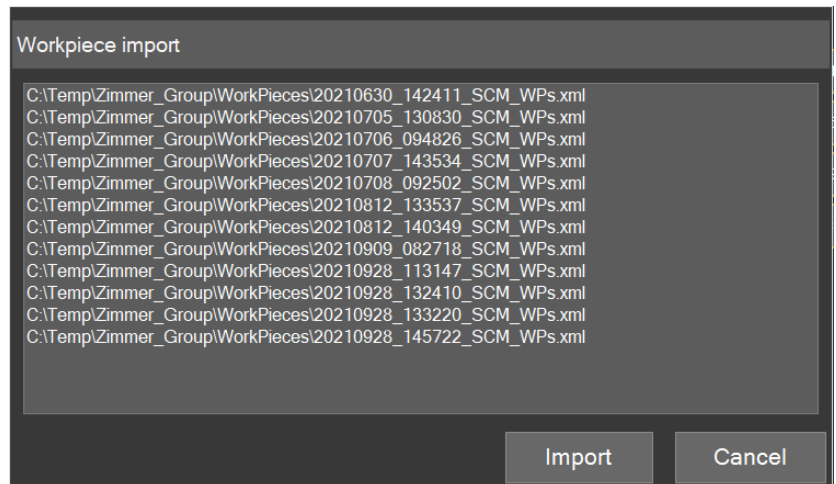
acquire

to work

11.16.3.1 Importing workpiece recipes

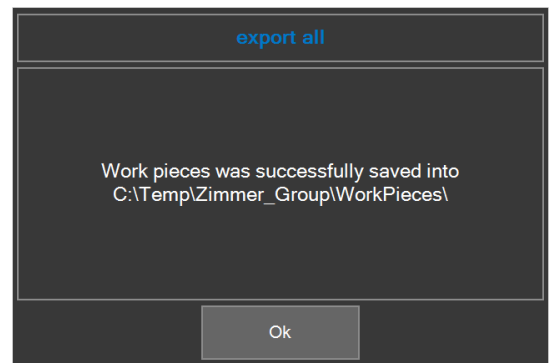
Only the entire data set can be loaded. All 15 workpiece recipes are overwritten during import.

- ▶ Click the *import all* button.
- ⇒ The *Workpiece import* window with the previously stored data sets is displayed.
- ▶ Click the desired data set.
- ▶ Click the *Import* button.



11.16.3.2 Exporting workpiece recipes

- ▶ Click the *export all* button.
- ⇒ All workpiece recipes are stored on the hard drive: *C:\Temp\Zimmer_Group\WorkPieces*



11.16.4 ISDU

The ISDU is acyclic service data that is written directly to the memory of the gripper. This data is thus not stored in the SCM. Acyclic service data that is writable can be adapted here.

► Click the ISDU button to view the acyclic service data.

ZG IO-LINK HMI

guideZ **expertZ** monitorZ

search

service

port

Gripper LWR50L-22-00001-A

Status word in [hex]
884B

Diagnosis in [hex]
301

Actual position in [mm]
7,69

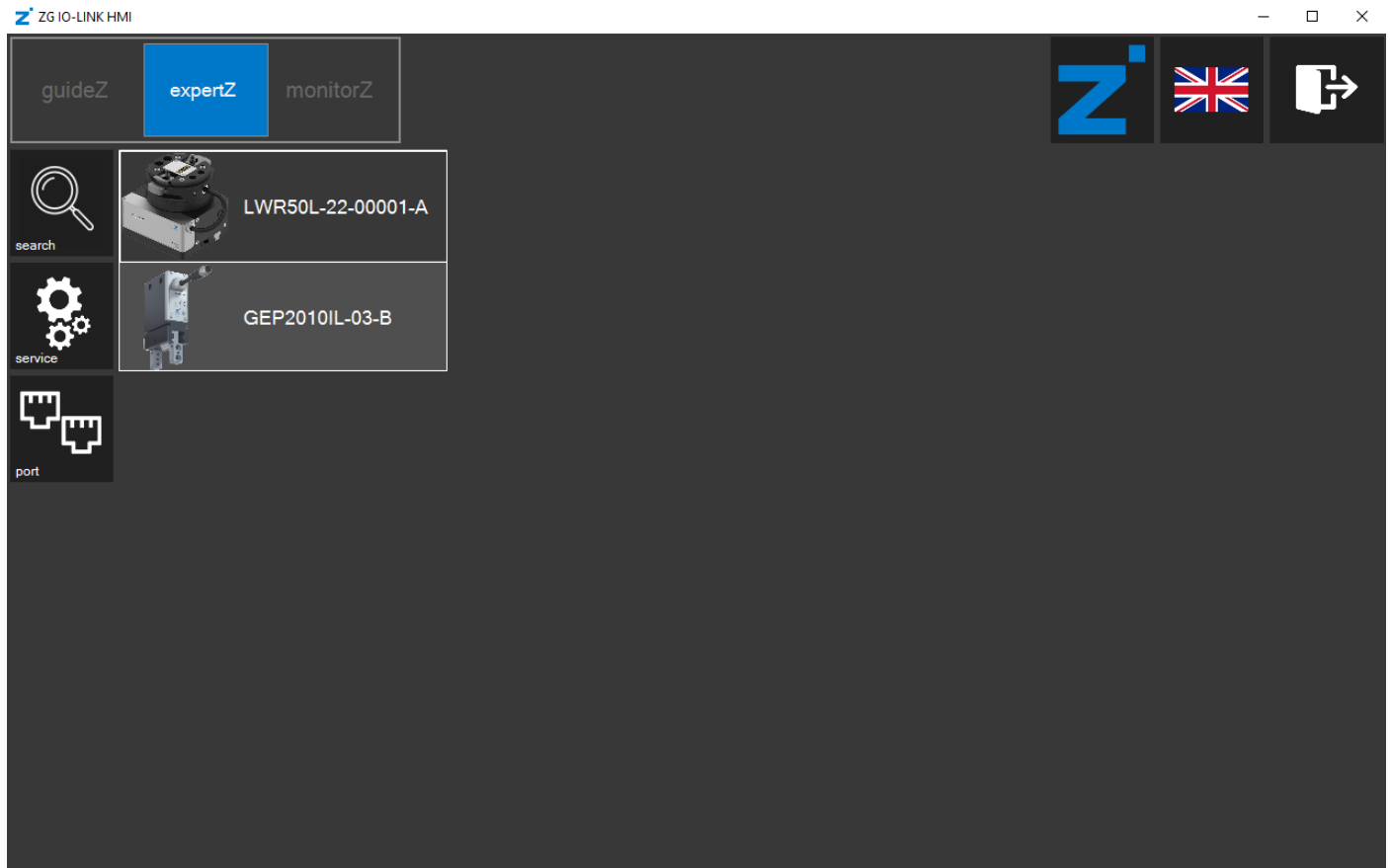
Diagnosis:
position values not plausible

idx	sdx	name	value	rights	type	iol_type
+	0	Direct Parameters - Page 1		rw	0	recordt
+	1	Direct Parameters - Page 2		rw	0	recordt
	2	System Command		wo	uint8	std_d_system
+	12	Device Access Locks		rw	0	recordt
	16	Vendor Name	Zimmer GmbH	ro	string	stringt
	17	Vendor Text	www.zimmer-group.c	ro	string	stringt
	18	Product Name	LWR50L	ro	string	stringt
	19	Product ID	LWR50L-22-00001-	ro	string	stringt
	20	Product Text	gripper electric: 2-jar	ro	string	stringt
	21	Serial Number	01-00025505	ro	string	stringt
	22	Hardware Revision	BG00104 F00	ro	string	stringt
	23	Firmware Revision	SWA000058 Q00+5	ro	string	stringt

plug HMI motor auto w.piece PDU **ISDU** to base acquire to work

11.17 Selecting the active gripper(s)

If two grippers are connected, you can select whether both are to be active or only one of the two.

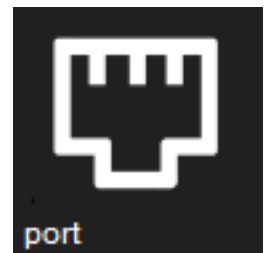


Both connected grippers are active.



Only one of the two connected grippers is active.

- Click the corresponding gripper to select it.



12 Error diagnosis

INFORMATION



- For further information on troubleshooting for grippers, refer to the current installation and operating instructions of the gripper on our website.
- For further information on troubleshooting for the SCM, refer to the current installation and operating instructions on our website.
- Please contact Zimmer Customer Service if you have any questions.

13 RoHS declaration

in terms of the EU Regulation 2011/65/EU

Name and address of the manufacturer:

Zimmer GmbH

📍 Im Salmenkopf

77866 Rheinau, Germany

☎ +49 7844 9138 0

✉ info@zimmer-group.com

💻 www.zimmer-group.com

We hereby declare that the incomplete machine described below

Product designation: Smart Communication Module

Type designation: SCM

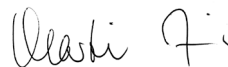
conforms to the requirements of the directive in its design and the version we put on the market.

Michael Hoch

Authorized representative for the
compilation of relevant technical
documents

Rheinau, Germany, 2020-02-28

(Place and date of issuance)



Martin Zimmer
(Legally binding signature)
Managing Partner

14 Declaration of Conformity

As defined by the EC Directive 2014/30/EU on electromagnetic compatibility

Name and address of the manufacturer:

Zimmer GmbH

Im Salmenkopf
77866 Rheinau, Germany
+49 7844 9138 0
info@zimmer-group.com
www.zimmer-group.com

We hereby declare that the products described below

Product designation: Smart Communication Module

Type designation: SCM

conform to the requirements of the Electromagnetic Compatibility Directive 2014/30/EU in its design and the version we put on the market.

The following harmonized standards have been used:

DIN EN ISO 12100	Safety of machinery - General principles for design - Risk assessment and risk reduction
DIN EN 61000-6-3	EMC Generic standard, Emission standard for residential, commercial and light-industrial
DIN EN 61000-6-2	EMC Generic standard, Emission standard for industrial environments
DIN EN 61000-6-4	EMC Generic standard, Immunity for industrial environments

A full list of applied standards can be obtained from the manufacturer.

Kurt Ross

Authorized representative for the compilation of relevant technical documents

Rheinau, Germany, 2020-02-28

(Place and date of issuance)



Martin Zimmer
(Legally binding signature)
Managing Partner

15 Declaration of Conformity

In terms of the EU Directive 2014/35/EU (Low voltage directive)

Name and address of the manufacturer:

Zimmer GmbH

📍 Im Salmenkopf
77866 Rheinau, Germany
☎ +49 7844 9138 0
✉ info@zimmer-group.com
💻 www.zimmer-group.com

We hereby declare that the products described below

Product designation: Smart Communication Module

Type designation: SCM

conforms to the requirements of the 2014/35/EC directive in its design and the version we put on the market.

The following harmonized standards have been used:

DIN EN ISO 12100	Safety of machinery - General principles for design - Risk assessment and risk reduction
DIN EN 60204-1	Safety of machinery – Electrical equipment of machines - Part 1: General requirements

A full list of applied standards can be obtained from the manufacturer.

Kurt Ross

Authorized representative for the
compilation of relevant technical
documents

Rheinau, Germany, 2020-02-28

(Place and date of issuance)



Martin Zimmer
(Legally binding signature)
Managing Partner