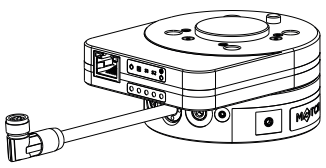
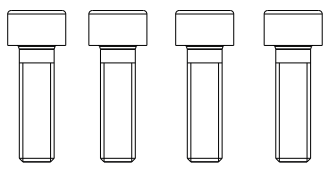
1 Required components

1.1 Scope of delivery

MATCH robot module with integrated SCM with RS485 interface



4 M6 mounting screws
Strength class 8.8
DIN EN ISO 4762



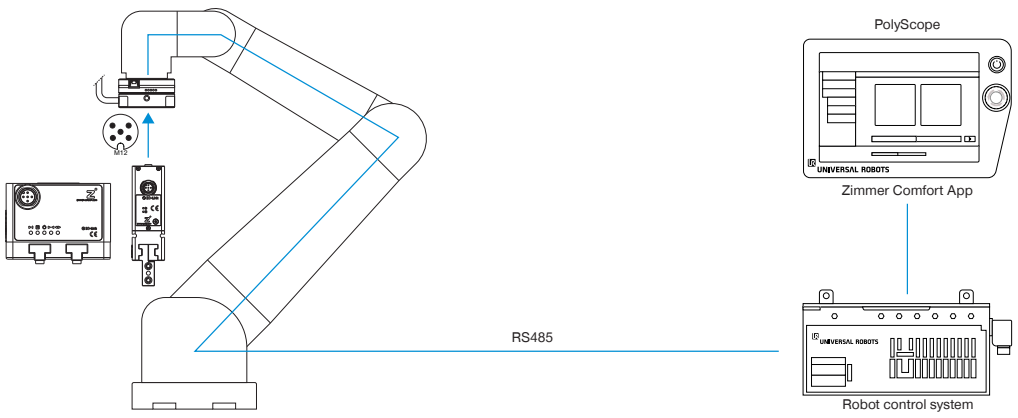
Download information from the Zimmer Comfort app and associated instructions

1.2 Required tools

Allen key 5 mm

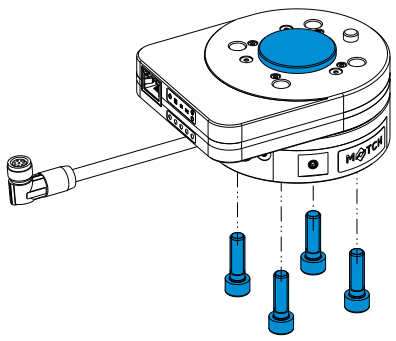
USB memory stick FAT32
> 1 GB

2 Design



3 Installing the MATCH robot module

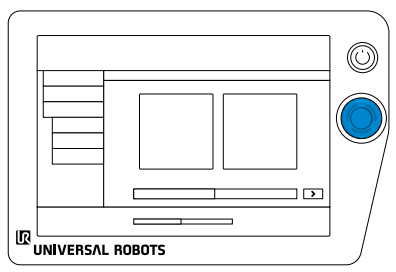
- ► Insert the product into the robot arm via the connection.
- ► Loosely attach the mounting screws.
- ► Tighten the mounting screws crosswise to 10 Nm.

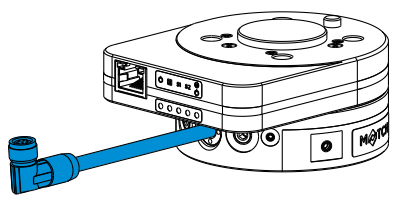


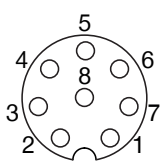
3.1 Installing the power supply

- ► Switch off the voltage supply on the robot tool I/O via the emergency stop button.

- ► Connect the product to the robot or route the connecting cable along the robot to the IO-Link master.





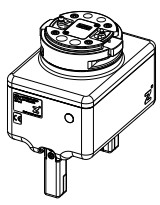


M8 8-pin socket

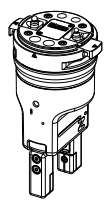
3.2 Installing the MATCH gripper

- ► Use an IO-Link-capable MATCH gripper with the MATCH robot module.

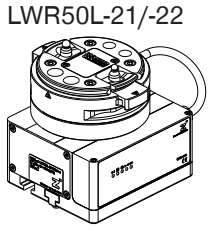
LWR50L-02



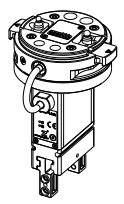
LWR50L-03

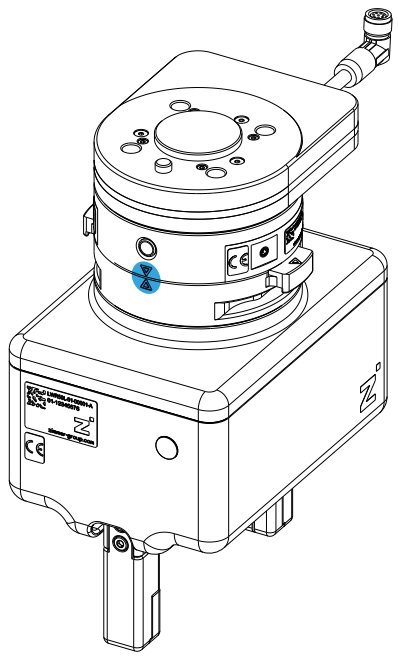


LWR50L-21/-22



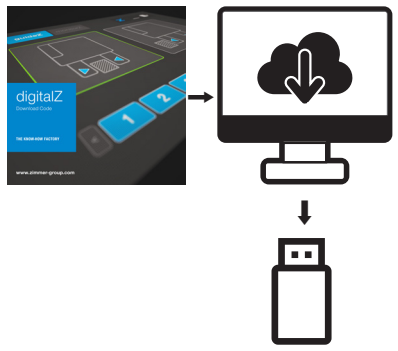
LWR50L-23





4 Preparing the data carrier

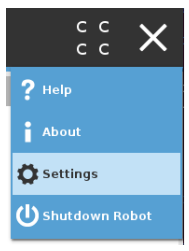
- ► Download the files via the QR code or via the reference link provided in the download information.



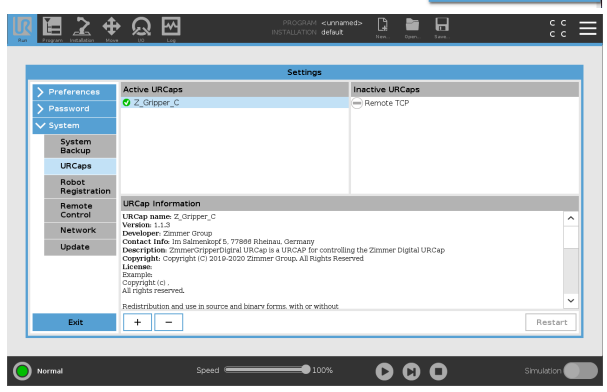
- ► Copy the *zimmerDigital-urcap* file to a USB memory stick.

5 Installing the Comfort app

- ► Press the ☰ button in the header.
- ► Press Settings.

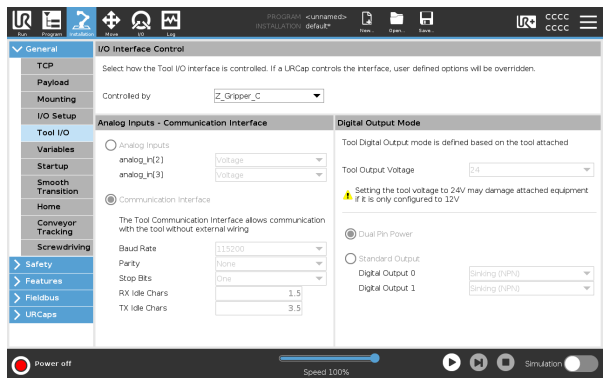


- ► In the *System* menu item, press *URCaps*.
- ► Add the *zimmerDigital-urcap* file from the USB memory stick as *Active URCaps*.
- ► Press the *Restart* button to activate the firmware.



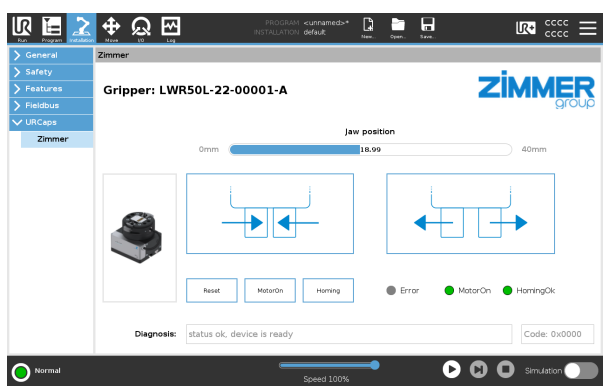
6 Setting the tool I/O

- ► In the *General* menu, press *Tool I/O*.
- ► In the *Controlled by* drop-down menu, select the *Z_Gripper_C* control level.
- ⇨ Settings can only be made via the Zimmer Comfort app.

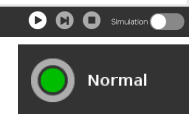


7 Manual operation

- ► In the *URCaps* menu, press *Zimmer*.
- ⇨ The Zimmer Comfort app opens for manual operation.



- ► Initialize the robot.



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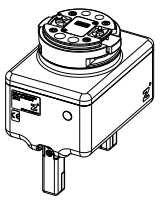
7.1 Reference run for long stroke gripper with > 20 mm jaw stroke

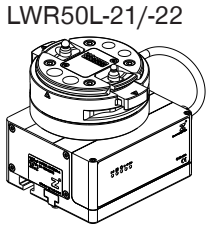
► Press the *Homing* button.

⇨ The correct positioning is performed after the cold start.

LWR50L-02



LWR50L-21/-22



7.2 Function test

► Press the buttons to test the *Grip* and *Release* commands.

⇨ The MATCH gripper and the motor voltage are initialized automatically.

7.3 Parameters

Default settings are used for the initial commissioning of the MATCH gripper. Then the parameters last used in the program sequence are applied.

8 Programming URCaps

The two commands *Z_Grip* and *Z_Release* are available as URCaps program nodes.

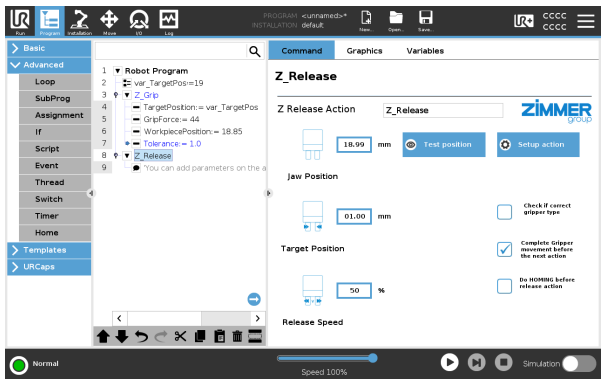
► In the *URCaps* menu, press *Z_Grip* or *Z_Release*.

8.1 Z_Grip

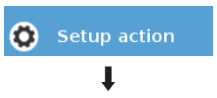
Functions for closing the MATCH gripper.

Level 1 provides an overview of the settings as well as access to interactive functions.

► Press the *Test position* button to test the settings.



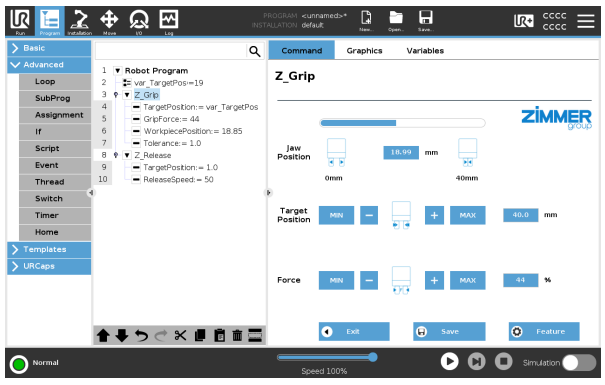
► Press the *Setup action* button to make settings.



In **level 2**, basic settings can be made:

- Move gripper in jog mode or to the end positions via buttons.
- Move to the gripping position.
- Set the gripping force.

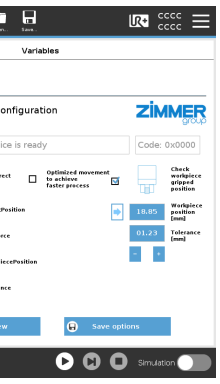
► Press the *Save* button to save the settings.



► Press the *Feature* button to define position sensing and variables.

Level 3 enables you to define position sensing and variables.

► Press the *Save* button to save the settings.

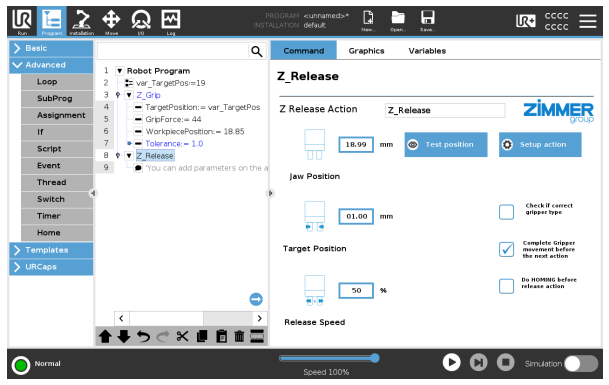


8.2 Z_Release

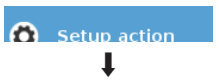
Functions for opening the MATCH gripper.

Level 1 provides an overview of the settings as well as access to interactive functions.

► Press the *Test position* button to test the settings.



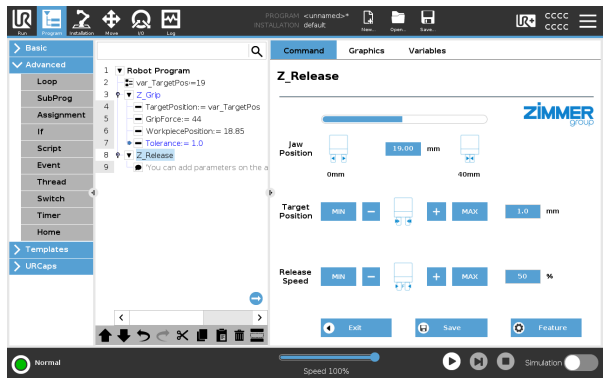
► Press the *Setup action* button to make settings.



In **level 2**, basic settings can be made:

- Move gripper in jog mode or to the end positions via buttons.
- Move to the gripping position.
- Setting the speed.

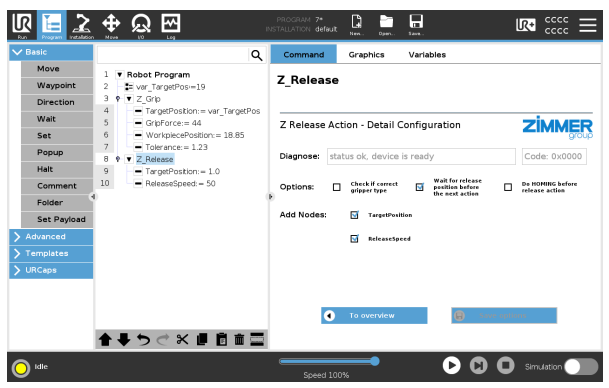
► Press the *Save* button to save the settings.



► Press the *Feature* button to define position sensing and variables.

Level 3 enables you to define position sensing and variables.

► Press the *Save* button to save the settings.



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