

INSTALLATION AND OPERATING INSTRUCTIONS

Robot-specific SCM and Comfort App for universal robots

DDOC01258

THE KNOW-HOW FACTORY

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 to persons. Ignoring these notices can cause minor, reversible injuries.

- ▶ You absolutely must comply with the described measures for avoiding these dangers!
- ⇒ The warning symbols are assigned according to the type of danger.

NOTICE



This notice warns of possible material and environmental damage. Ignoring these notices can result in damage to the product or 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.

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.

Grippers with a control system are used on industrial machines for IO-Link communication.

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



Material damage and malfunction in case of non-compliance

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

WARNING



Inadequate qualification can cause injury and material damage

If inadequately qualified personnel perform work on the product, this can cause serious injuries and significant material damage.

- ▶ All work on the product must be performed by qualified personnel.
- ▶ Before working with the product, read the document in its entirety and make sure that you have understood everything.
- ▶ Observe country-specific accident prevention regulations and the general safety notices.

The following qualifications are a prerequisite for performing various work on the product.

4.1 Electricians

Electricians are able to perform work on electrical systems, can recognize and avoid possible dangers and know the relevant standards and provisions due to their technical training, knowledge and experience.

4.2 Specialists

Specialists are able to perform the assigned work, can recognize and avoid possible dangers and know the relevant standards and provisions due to their technical training, knowledge and experience.

4.3 Instructed personnel

Instructed personnel have been trained by the operating company on the tasks and possible dangers of improper behavior.

4.4 Service personnel

Service personnel are able to perform the assigned work and can recognize and avoid possible dangers due to their technical training, knowledge and experience.

4.5 Additional qualifications

Persons who work with the product must be familiar with the valid safety regulations and laws as well as the standards, guidelines and laws listed in this document.

Personnel who work with the product must have facility-issued authorization to commission, program, configure, operate, maintain and also decommission this product.

5 Product description

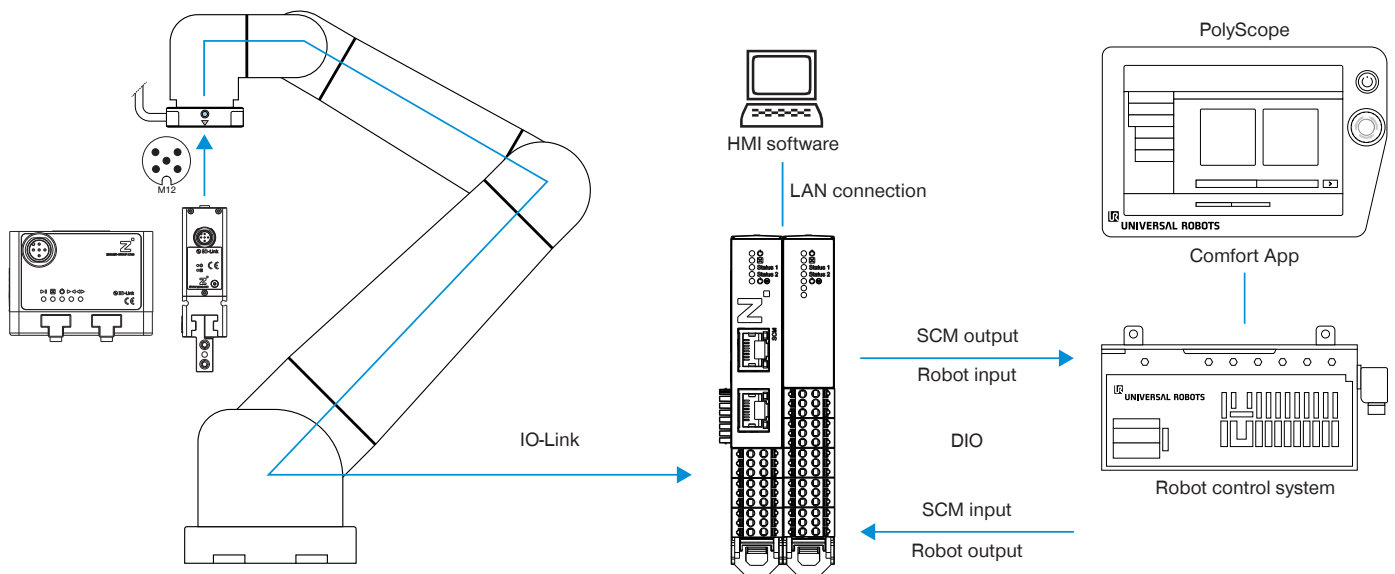
The Smart Communication Module (SCM) is a gateway between the grippers and the robot control system. The SCM can be configured via the HMI software or Comfort App. The grippers can be controlled using the Comfort App on the robot control panel.

Using the Comfort App, Zimmer GmbH grippers can be controlled directly from the robot control panel and generated robot jobs can be configured.

The generated robot tasks simplify the use of Zimmer GmbH grippers in the customer program and reduce the development time.

The names of the newly configured robot jobs remain unchanged. This means that the basic program does not have to be modified for configuration changes.

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.
- ▶ Install the HMI software and teach in the workpieces.
- ▶ Install the Comfort App, see the operating instructions for the robot-specific 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.

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 uncontrolled movements

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.
- ▶ Check the machine for any residual energy that may be present.

9.1 Installing hardware

INFORMATION

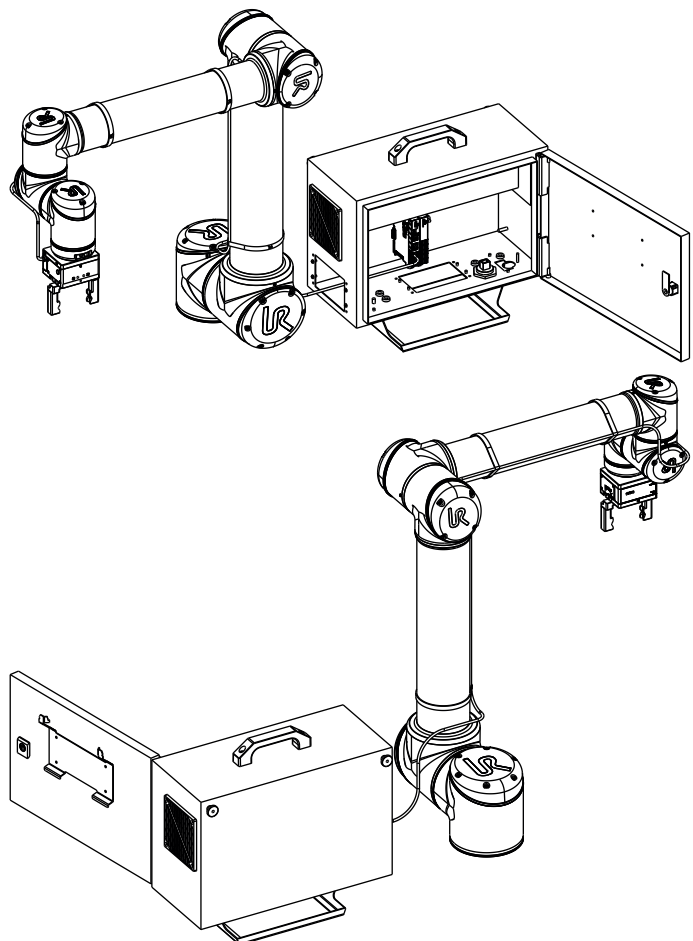


- ▶ For more information, refer to the circuit diagram on our website.

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.

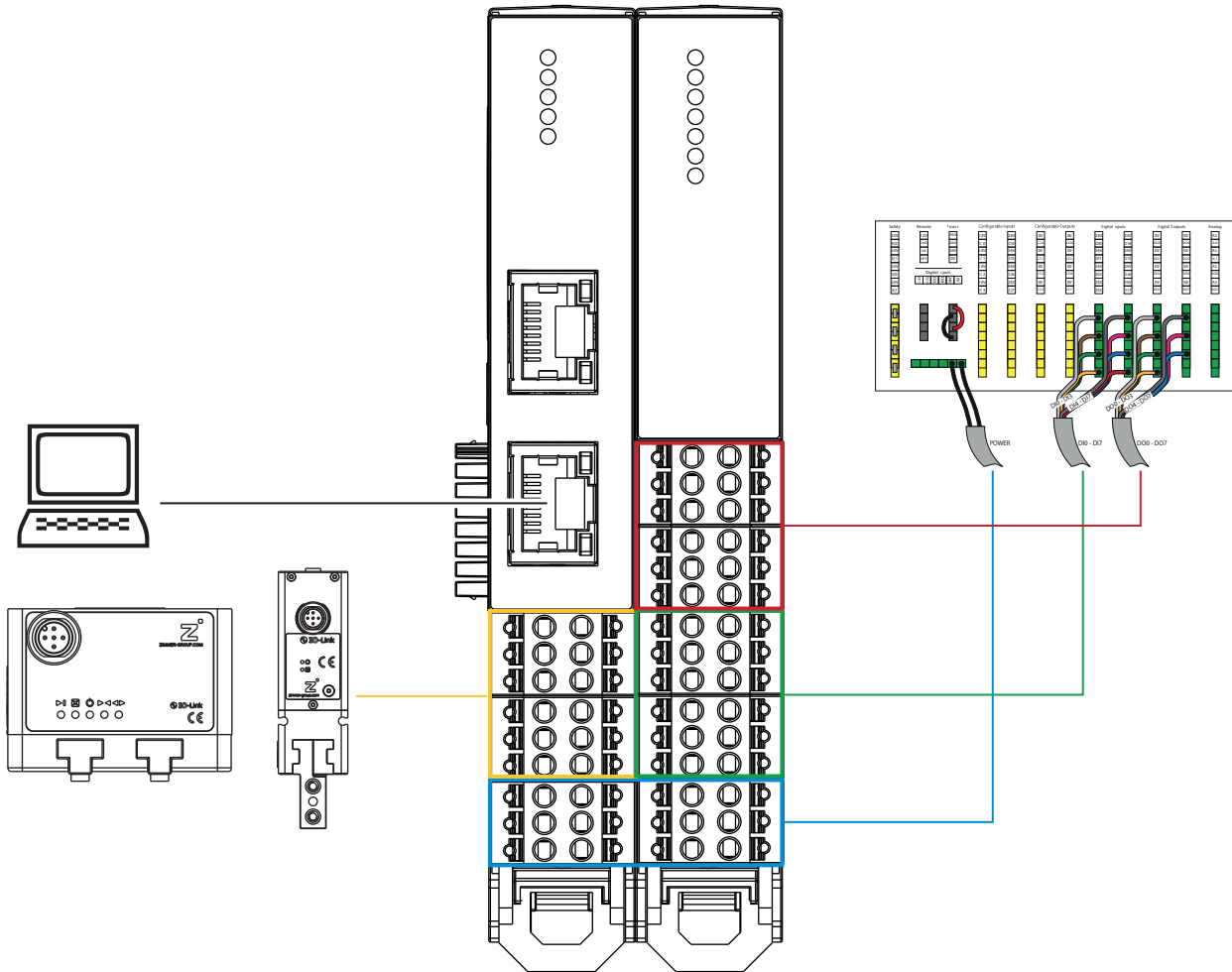


9.1.1 Installing standard wiring

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 Comfort App. If you do the standard wiring and keep the standard configuration in the Comfort App, your grippers will function with the robot.

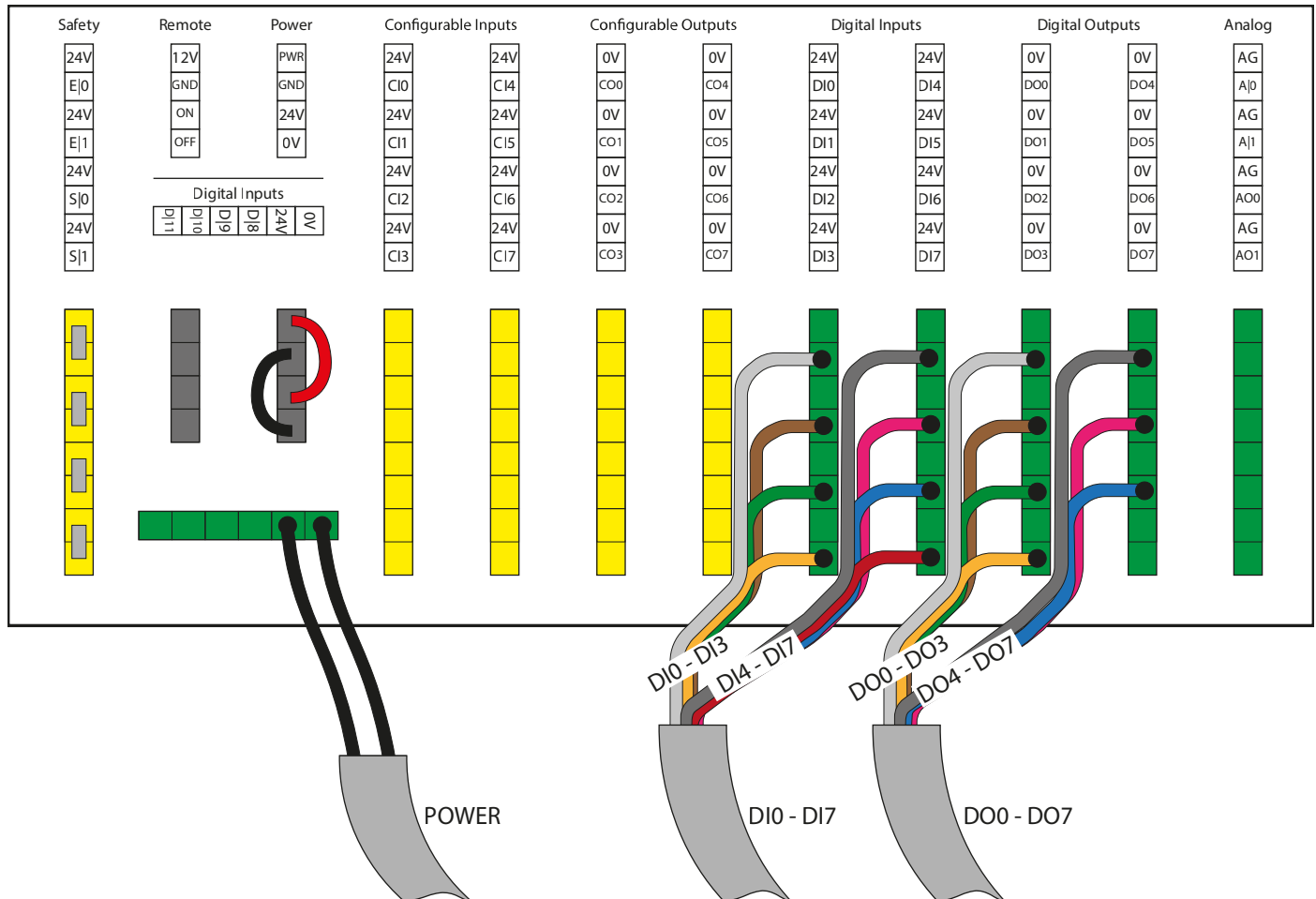
You have the option to change the standard wiring.

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 control system

- ▶ De-energize the robot.
 - ▶ Remove the original connectors of the robot.
 - ▶ Connect the product to the robot control system with the five connectors.
 - ▶ Mount the product in the robot cabinet with the adhesive strip.
- ⇒ The respective gripper can now be connected to the product using the included cable.
- ▶ Switch on the robot to supply the product with power.



9.1.2.1 Customer-specific wiring

Customer-specific wiring with full functionality of the product is possible by using other robot inputs and robot outputs at the robot control system and attaching them to the free pins of the product.

- ⇒ Expands the number of workpiece recipes to up to 15 pieces.

9.1.2.2 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 Comfort App is required.

SCM connection	Command	Color	Robot output	CN307	
1	Cmd_Release	White	Out17	B8	A8
2	Cmd_Grip	Brown	Out18	B9	A9
3	Cmd_Reset	Green	Out19	B10	A10
4	-	-	-	-	-
5	-	-	-	-	-
6	-	-	-	-	-
7	-	-	-	-	-
8	-	-	-	-	-
9	Cmd_WP_Bit0	Black	Out22	B13	A13
10	Cmd_WP_Bit1	Violet	Out23	B14	A14
11	Cmd_WP_Bit2	Gray/pink	(Out24)	(B15)	(A15)
12	Cmd_WP_Bit3	Red/blue	-	-	-
SCM connection	Robot input	Color	Robot input	CN307	
1	IsReleased	White	In17	B1	-
2	IsGripped	Brown	In18	A1	-
3	IsClosed	Green	In19	B2	-
4	OnUndefinedPos	Yellow	In20	A2	-
5	Error	Gray	In21	B3	-
6	-	-	-	-	-
7	-	-	-	-	-
8	-	-	-	-	-
9	Act_WP_Bit0	Black	In23	B4	-
10	Act_WP_Bit1	Violet	In24	A4	-
11	Act_WP_Bit2	Gray/pink	-	-	-
12	Act_WP_Bit3	Red/blue	-	-	-

9.1.2.3 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 Comfort App is required.

SCM connection	Command	Color	Robot output	CN307	
1	Cmd_Release	White	Out17	B8	A8
2	Cmd_Grip	Brown	Out18	B9	A9
3	Cmd_Reset	Green	Out19	B10	A10
4	Cmd_MotorOn/ Cmd_MotorOff	Yellow	Out20	B11	A11
5	Cmd_Homing	Gray	Out21	B12	A12
6	-	-	-	-	-
7	-	-	-	-	-
8	-	-	-	-	-
9	Cmd_Release	Cmd_WP_Bit0	Out22	B13	A13
10	Cmd_WP_Bit1	Violet	Out23	B14	A14
11	Cmd_WP_Bit2	Gray/pink	(Out24)	(B15)	(A15)
12	Cmd_WP_Bit3	Red/blue	-	-	-
SCM connection	Confirmation	Color	Robot input	CN307	
1	IsReleased	White	In17	B1	-
2	IsGripped	Brown	In18	A1	-
3	IsClosed	Green	In19	B2	-
4	OnUndefinedPos	Yellow	In20	A2	-
5	Error	Gray	In21	B3	-
6	MotorOn	Pink	In22	A3	-
7	HomingOk	Blue	-	-	-
8	-	-	-	-	-
9	Act_WP_Bit0	Cmd_WP_Bit0	In23	B4	-
10	Act_WP_Bit1	Violet	In24	A4	-
11	Act_WP_Bit2	Gray/pink	-	-	-
12	Act_WP_Bit3	Red/blue	-	-	-

9.1.3 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.

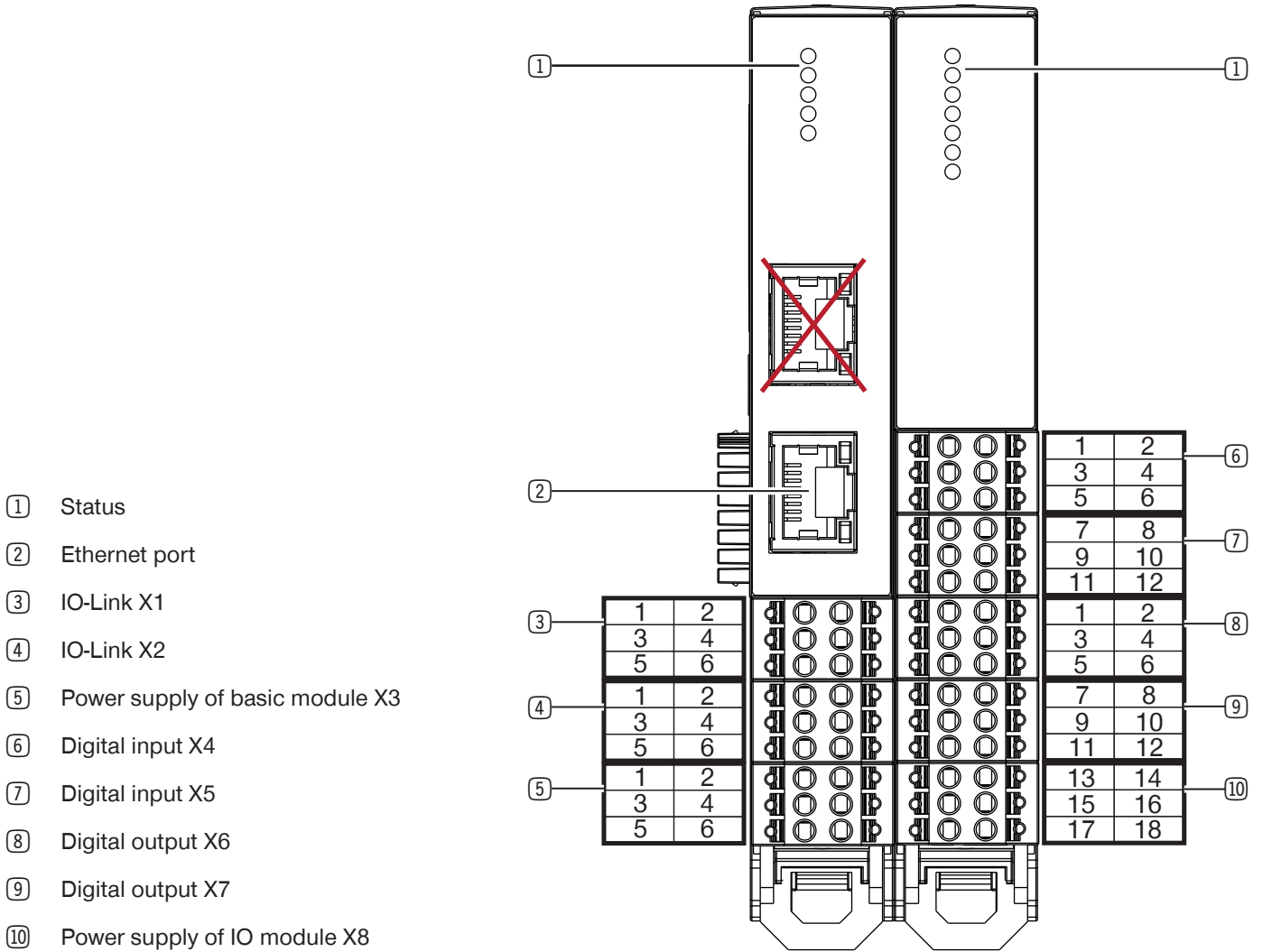
SCM input and SCM output				
	Basic gripper at port 1	Advanced gripper at port 1	Basic gripper at port 2	Advanced gripper at port 2
Cmd_Release	Out1	Out1	Out5	Out5
Cmd_Grip	Out2	Out2	Out6	Out6
Cmd_Reset	Out3	-	Out7	-
Cmd_MotorOn	-	Out3	-	Out3 or Out7
Cmd_Homing	-	Out4	-	Out8
Cmd_WP_Bit0	-	-	-	-
Cmd_WP_Bit1	-	-	-	-
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	-	-	-	-

9.1.4 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 Comfort App is required.

9.2 Installing the energy supply

9.2.1 Mounting the pin assignment



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.

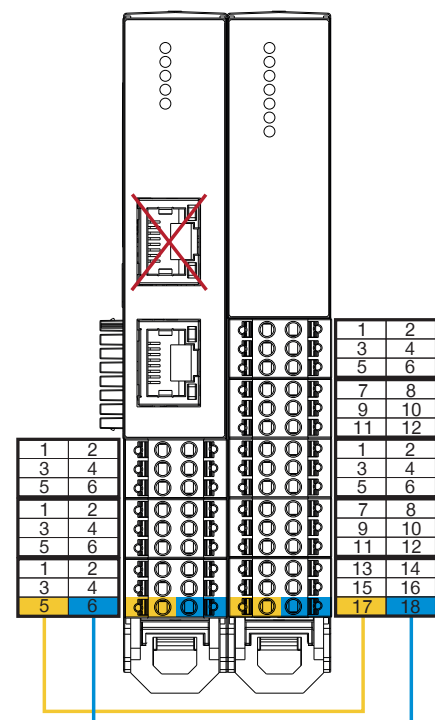
The maximum permitted current draw allows you to operate all grippers directly on the product. No Y-cable for a special power supply is required.

Pin	Function	Explanation	Power supply of basic module X3
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	Power supply of IO module X8
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

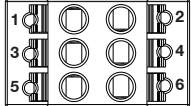
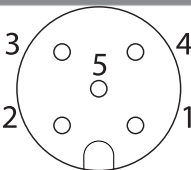


Non-compliance may result in material damage.

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				IO-Link X1/IO-Link X2	M12 5-pin socket	
Pin	Color	Function	Explanation		Pin	Color
1	Black	C/Q	IO-Link communication	M12 5-pin socket 	4	Black
2	-	-	-		6	-
3	White	PWR 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

10 Installation HMI

INFORMATION



► For information, refer to the commissioning instructions for the HMI.

11 Commissioning HMI

INFORMATION

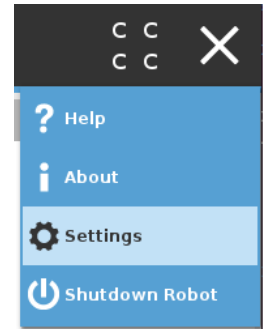


► For information, refer to the commissioning instructions for the HMI.

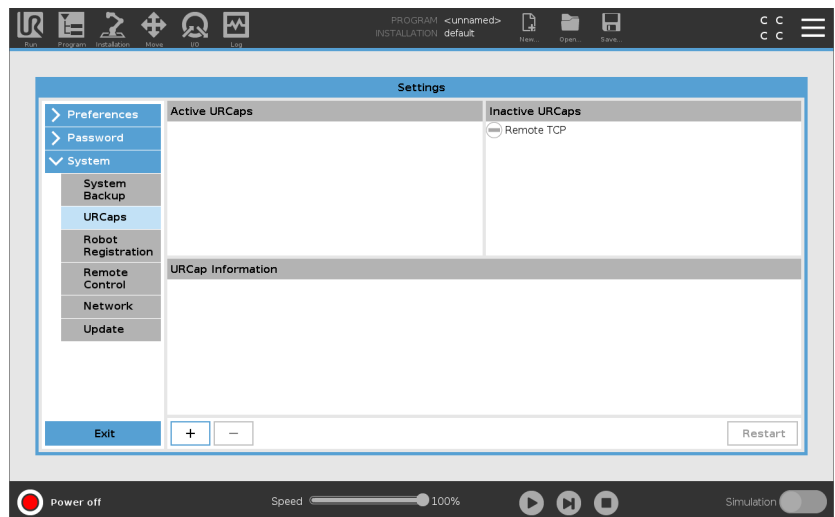
12 Installation Comfort App

The Comfort App is installed to the robot control panel to enable direct control of the grippers.

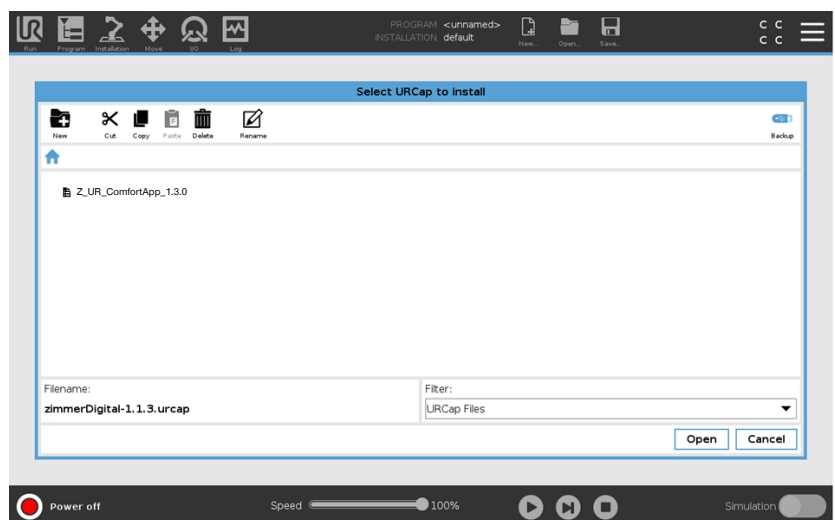
- ▶ Download the robot app from our website.
- ▶ Copy the installation file to a USB memory device.
- ▶ Make sure that the robot control panel is already connected to the robot control system.
- ▶ Switch off the voltage supply on the robot tool I/O via the emergency stop button.
- ▶ Plug the USB memory stick with the installation files for the Comfort App into the robot control panel.
- ▶ Press the button in the header.
- ▶ Press *Settings*.



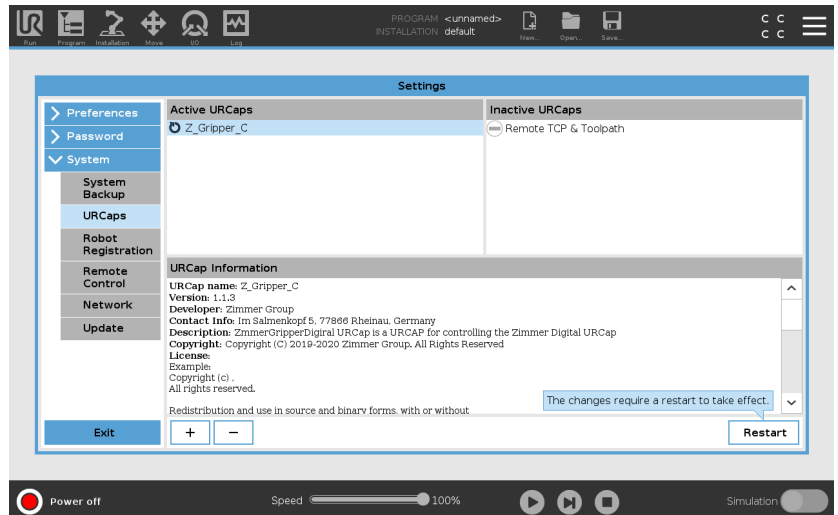
- ▶ In the menu, press *System*.
- ▶ In the *System* menu item, press *URCaps*.
- ▶ Press the + Button.



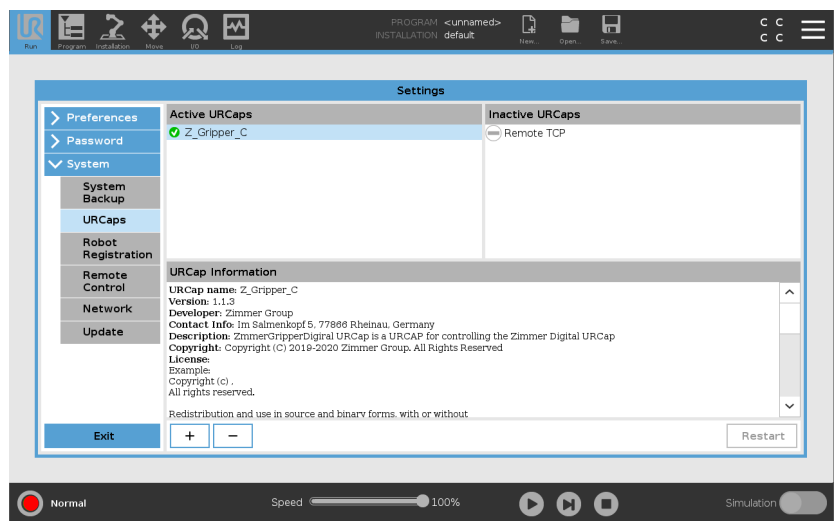
- ▶ Navigate to the file *zimmerDigital-urcap*.
- ▶ Select the file *Z_UR_ComfortApp_X.X.X*.
- ▶ Press the *Open* button.



- ▶ Press the *Restart* button to activate the firmware.
- ⇒ The robot control panel performs a restart.



- ▶ After the restart, check whether the Comfort App has been installed correctly.
- ⇒ The Comfort App has been installed correctly if the green checkmark is displayed in the *Active URCaps* area.



13 Commissioning Comfort App

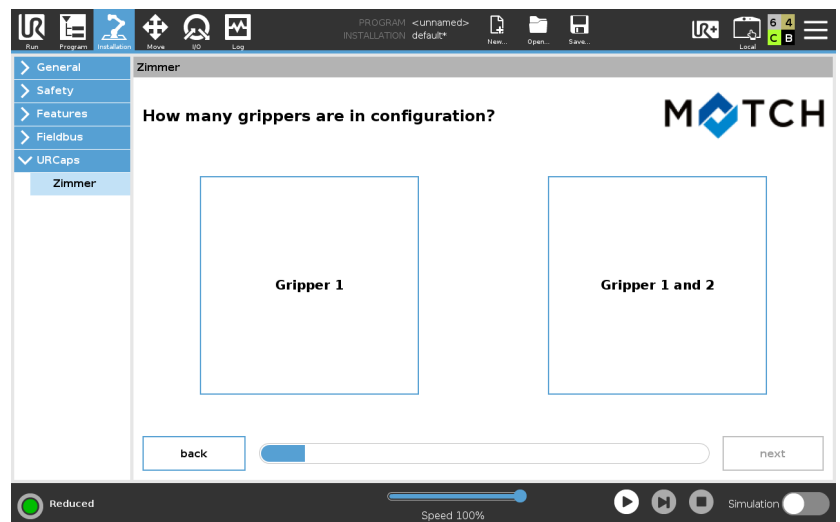
- ▶ Install the gripper to the robot.
- ▶ Switch the robot on.
- ▶ Press *Installation* in the menu bar.
- ▶ In the *URCaps* menu, press *Zimmer*.

13.1 Deleting existing setups

The following screen is displayed only if an existing setup is found for two grippers.

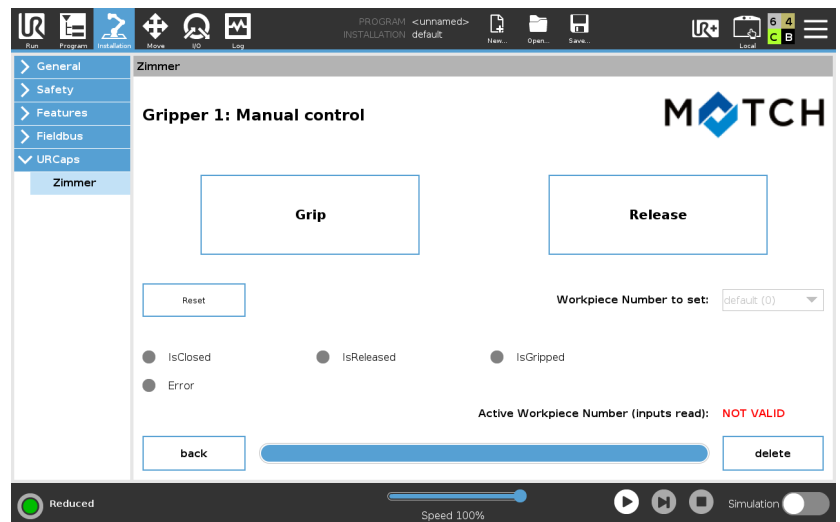
This screen does not appear if the available setup is only found for one gripper. In this case, the next screen is shown right away.

- ▶ Click the button of the desired gripper.
- ⇒ The *Manual control* screen for the manual control is displayed.

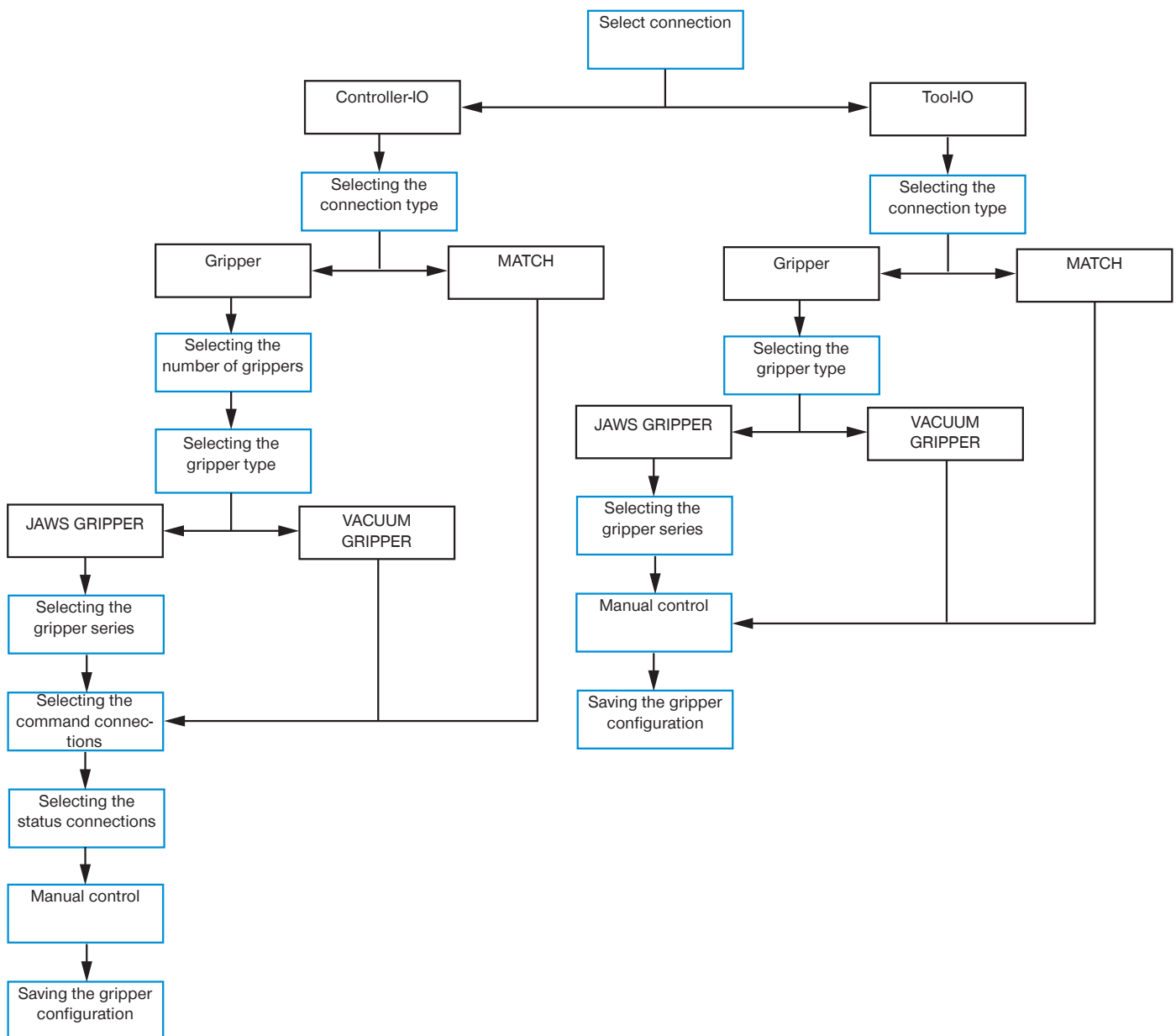


In the *Manual control* screen, you can operate the gripper manually and display the status.

- ▶ Click the *delete* button.

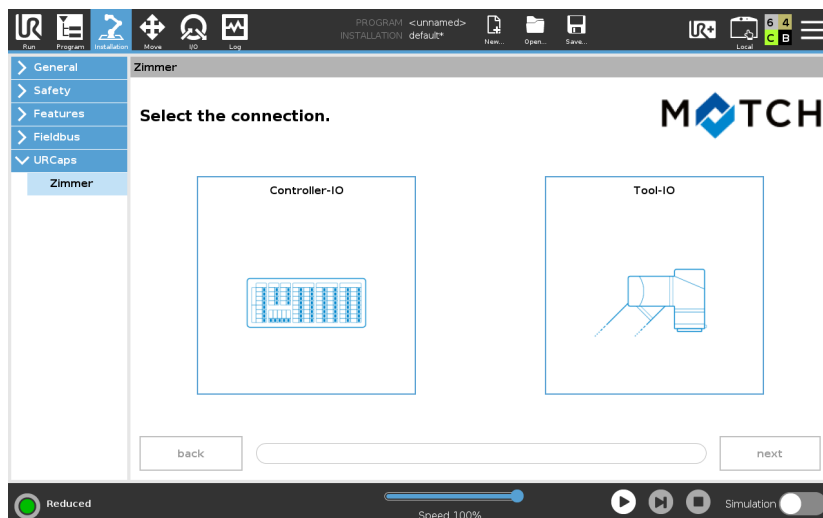


13.2 Creating a gripper configuration



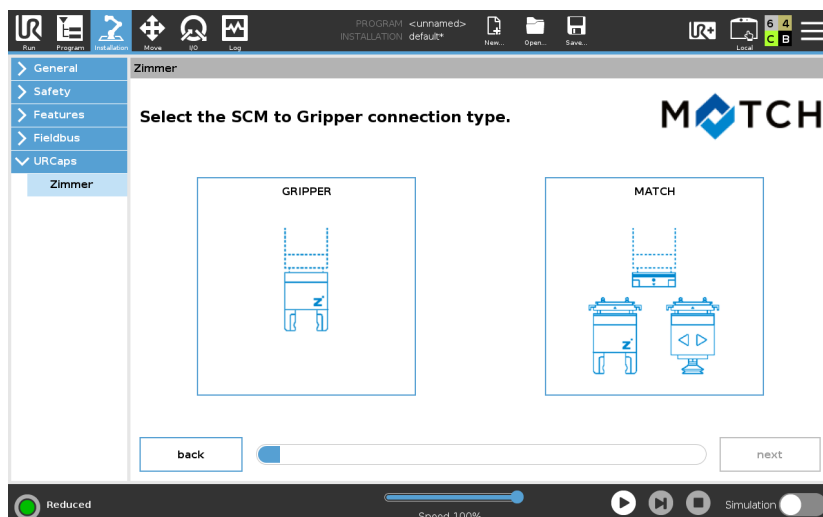
13.2.1 Selecting the connection

- ▶ Press the *Controller IO* button if you want to use a MATCH gripper without an integrated SCM on the MATCH robot module.
- ▶ Press the *Tool-IO* button if you want to use a gripper with an integrated SCM on the MATCH robot module.
- ▶ Click the *next* button.



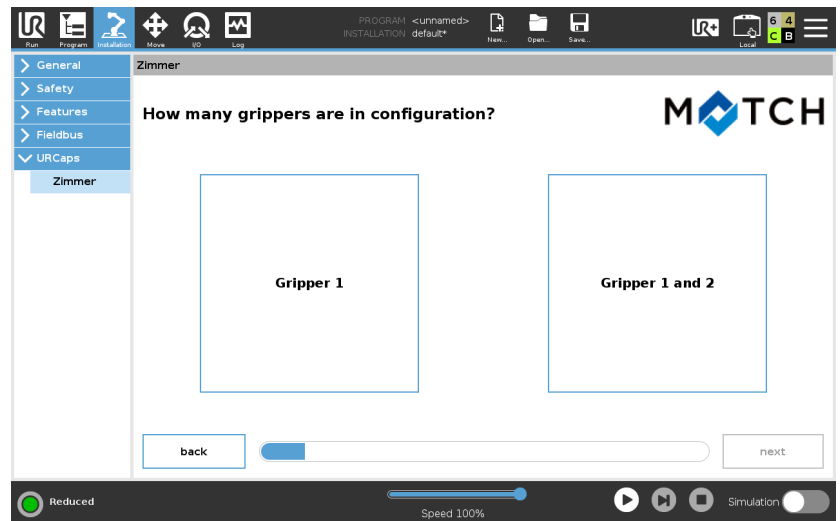
13.2.2 Selecting the connection type

- ▶ Click *Gripper* if you have connected a gripper.
- ▶ Click *MATCH* if you have connected a MATCH gripper.
- ▶ Click the *next* button.



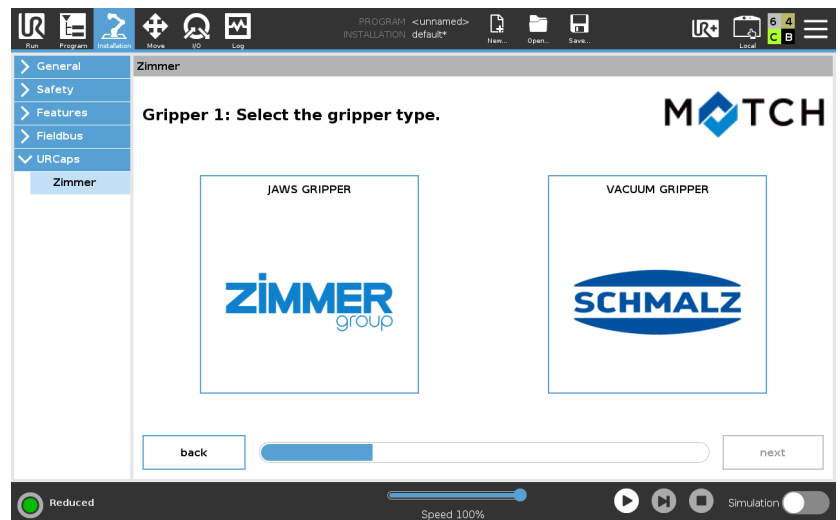
13.2.3 Selecting the number of grippers

- ▶ Click the desired number of grippers you want to have in your robot application.
- ▶ Click the *next* button.



13.2.4 Selecting the gripper type

- ▶ Click the desired gripper type.
- ▶ Click the *next* button.



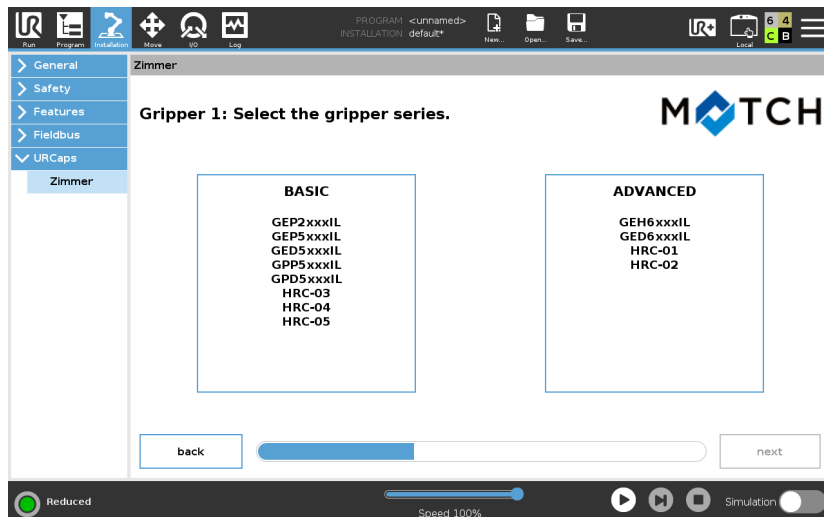
13.2.5 Selecting the gripper series

INFORMATION



Basic and *Advanced* designate different classes of grippers from Zimmer GmbH.

- ▶ Click the class of your gripper.
- ▶ Click the *next* button.



13.2.6 Selecting the command connections

NOTICE



The gripper wiring must match the gripper configuration done in the Comfort App.

NOTICE



If this screen is displayed for the first time, a standard assignment is displayed.

► Complete the wiring precisely as shown on this screen.

To reset the values to the defaults, edit the values or return to the selection of the number of grippers (see the section "Selecting the number of grippers").

► Establish the correspondence of the robot output number with the digital input function of the SCM.

You can accept the default assignment or change it.

► Click the *next* button if you want to keep the default assignment.

Editing the command connection

► Click the button of the desired signal.

- e.g. Release

► Click the desired output.

- e.g. DO7

⇒ The output has been assigned to the signal.

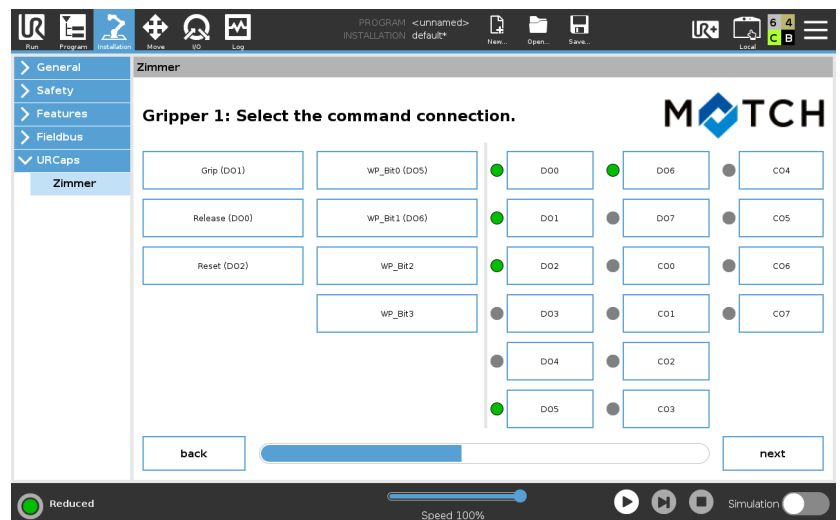
⇒ The button of the signal is expanded by adding the output.

- e.g. Release (DO7)

► Press the *Next* button.

► In the prompt, click the *YES* button.

⇒ The *Select status connections* screen for status connections is displayed.



Default assignment



Do you accept the default assignment?

Yes

No

13.2.7 Selecting the status connections

- ▶ Establish the correspondence of the robot input number with the digital input function of the SCM.

NOTICE



If this screen is displayed for the first time, a standard assignment is displayed.

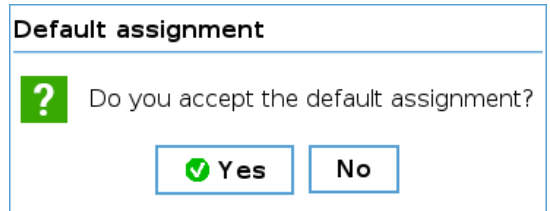
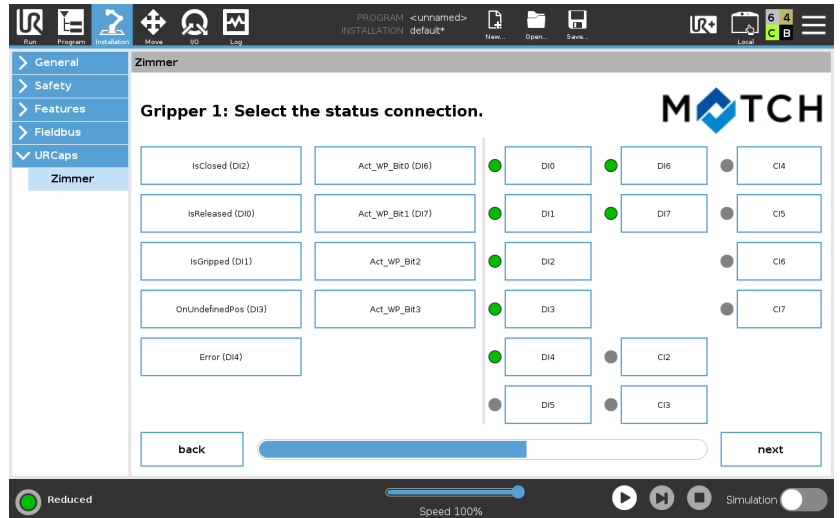
- ▶ Complete the wiring precisely as shown on this screen.

You can accept the default assignment or change it.

- ▶ Click the *next* button if you want to keep the default assignment.

Editing the status connections

- ▶ Click the button of the desired signal.
 - e.g. IsClosed
- ▶ Click the desired input.
 - e.g. DI7
- ⇒ The input has been assigned to the signal.
- ⇒ The button of the signal is expanded by adding the input.
 - e.g. IsClosed (DI7)
- ▶ Press the *Next* button.
- ▶ In the prompt, click the *YES* button.



13.2.8 Manual control

NOTICE

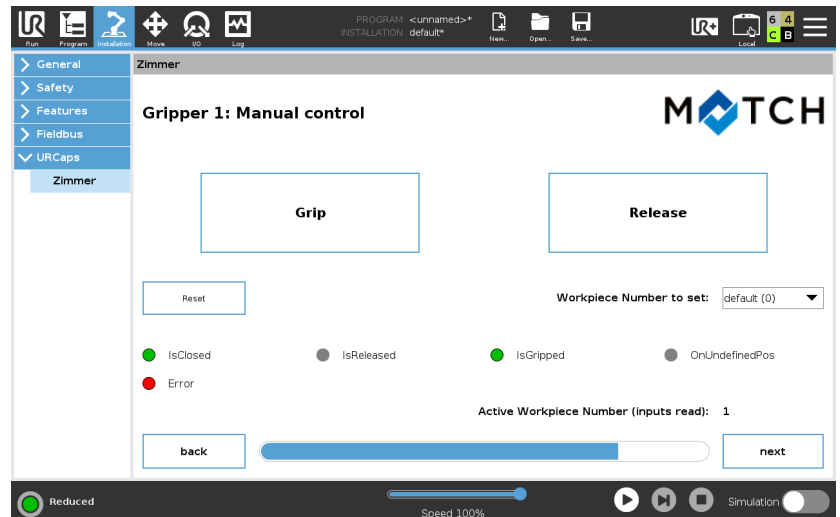


The prerequisite for the function test is that the wiring between the robot and SCM is present and that the robot, SCM and gripper are switched on.

You can test and operate the function of the gripper and view its status in the lower area of the screen.

Connection type: Gripper

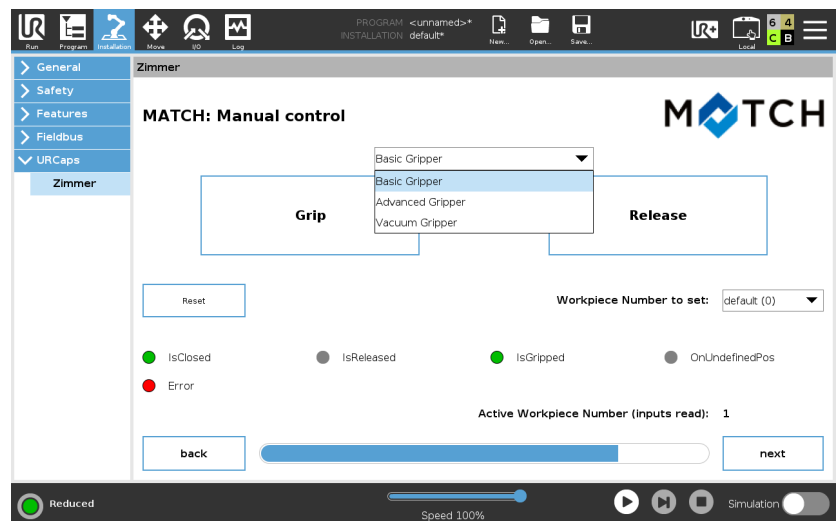
You can test and operate the function of the gripper and view its status in the lower area of the screen.



Connection type: MATCH

You can test and operate the function of the gripper and view its status in the lower area of the screen.

You can choose between the grippers in the drop-down menu.



► Click the *next* button.

13.2.9 Saving the gripper configuration

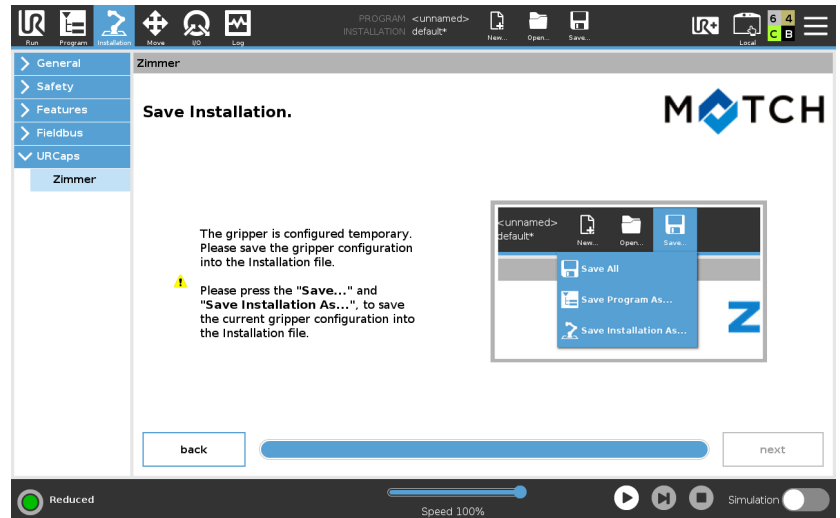
NOTICE



The settings are temporary.

- ▶ Save the settings to the installation file.

- ▶ In the prompt, press the *Save All* or *Save Installation As* button.
- ⇒ The gripper configuration has been stored.
- ▶ In the prompt, click the *Ok* button.
- ⇒ The gripper configuration is complete.
- ⇒ The function blocks/subprograms have been created and are available for programming.



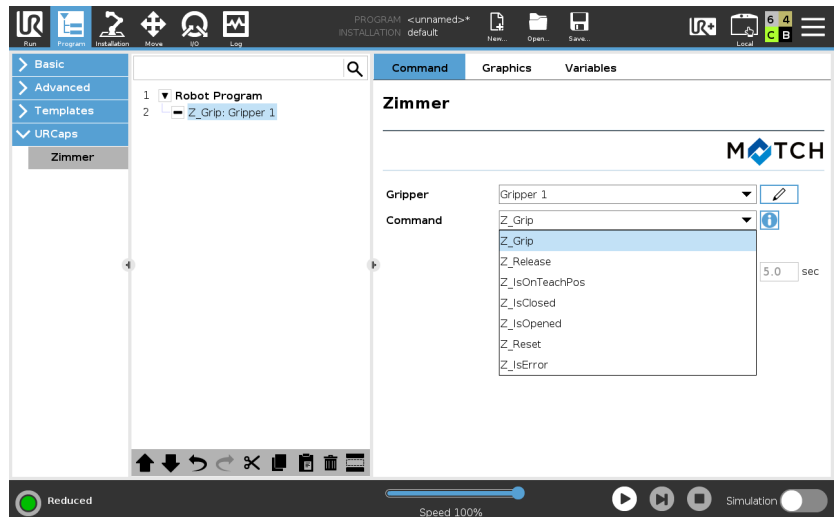
13.3 URCaps

Program nodes can be set in the *URCaps* menu item.

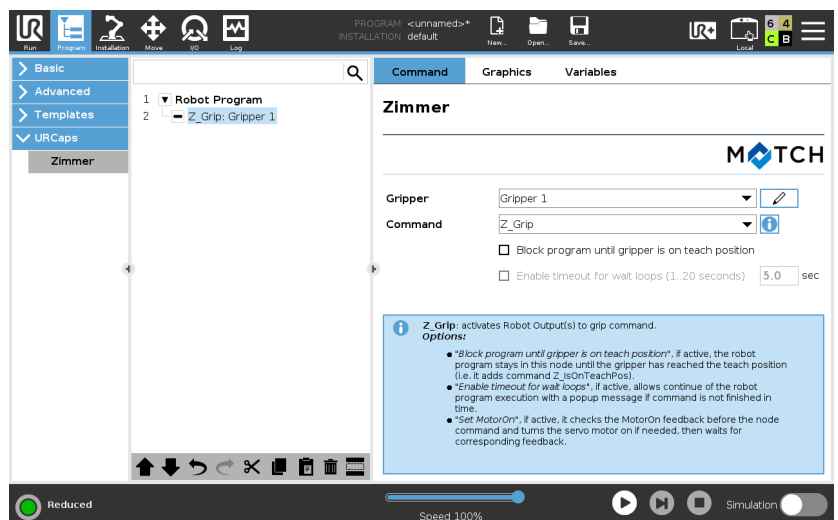
- ▶ Press *Program* in the menu bar.
- ▶ In the *URCaps* menu, press *Zimmer*.

13.3.1 URCaps Zimmer

- ▶ In the *Command* drop-down menu, select the robot job that you want to define for the gripper.



- ▶ Activate the desired checkboxes.



14 Operation

14.1 Control principle of the gripper

- ▶ Prepare the *Advanced* gripper for the control system:
 - ▶ If necessary, do a reference run (Z_Homing).
 - ▶ Switch on the motor (Z_MotorOn).
 - ▶ Check whether the motor is switched on (Z_IsMotorOn).
 - ⇒ The gripper is prepared for the control system if no error is present (Z_IsError).
- ▶ If more than one workpiece is being used, adjust the workpiece (Z_ChangeWP(number)) configured using the HMI software.
- ▶ Check whether a workpiece has changed (Z_IsWpChanged(number)).
- ▶ Grip (Z_Grip) or release (Z_Release) the workpiece.
- ▶ Check the position of the gripper jaw (Z_IsOnTeachPos, Z_IsOpened, Z_IsClosed or Z_IsOnUndefPos).

14.2 Overview of generated robot jobs

After successful configuration of the grippers using the HMI software, robot jobs for various functions are generated in the robot control panel. The robot jobs can be called up from user jobs. The following robot jobs can be created using the Comfort App.

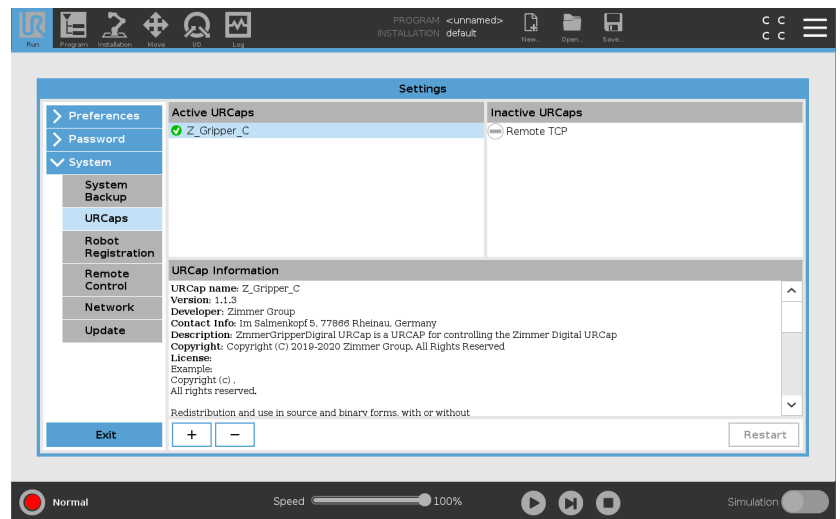
Not all robot jobs are generated after successful configuration of the grippers. The job is created only if the corresponding command or status is wired and used by the equipped gripper(s).

Generated robot job name	Parameter In	Parameter Out	Function
Z_Grip1 Z_Grip2	1: Address gripper 1 2: Address gripper 2	<i>bCmdFail</i> = <i>TRUE</i> , if command fails = <i>FALSE</i> , if command was successful	Gripping
Z_Release1 Z_Release2	1: Address gripper 1 2: Address gripper 2	<i>bCmdFail</i> = <i>TRUE</i> , if command fails = <i>FALSE</i> , if command was successful	Release
Z_MotorOn1 Z_MotorOn2	1: Address gripper 1 2: Address gripper 2	<i>bCmdFail</i> = <i>TRUE</i> , if command fails = <i>FALSE</i> , if command was successful	Switch on motor for <i>Advanced</i> grippers.
Z_MotorOff1 Z_MotorOff2	1: Address gripper 1 2: Address gripper 2	<i>bCmdFail</i> = <i>TRUE</i> , if command fails = <i>FALSE</i> , if command was successful	Switch off motor if gripper is present.
Z_Homing1 Z_Homing2	1: Address gripper 1 2: Address gripper 2	<i>bCmdFail</i> = <i>TRUE</i> , if command fails = <i>FALSE</i> , if command was successful	Perform reference run for <i>Advanced</i> grippers.
Z_Reset1 Z_Reset2	1: Address gripper 1 2: Address gripper 2	<i>bCmdFail</i> = <i>TRUE</i> , if command fails = <i>FALSE</i> , if command was successful	Reset if gripper is present.
Z_ChangeWP1 Z_ChangeWP2	<i>WpNumber</i> = workpiece number (1 to 15)	<i>bCmdFail</i> = <i>TRUE</i> , if command fails = <i>FALSE</i> , if command was successful	Set workpiece number (n) for use with SCM.
Z_IsWpChanged1 Z_IsWpChanged2	<i>WpNumber</i> = workpiece number (1 to 15)	<i>bWPchanged</i> = <i>TRUE</i> , if workpiece is active = <i>FALSE</i> , if workpiece is not active <i>bCmdFail</i> = <i>TRUE</i> , if command fails = <i>FALSE</i> , if command was successful	Disables Error/Warning for robot if gripper present.

Generated robot job name	Parameter In	Parameter Out	Function
Z_IsOpened1 Z_IsOpened2	1: Address gripper 1 2: Address gripper 2	<p><i>bOpened</i> = <i>TRUE</i>, if gripper is open = <i>FALSE</i>, if gripper is closed</p> <p><i>bCmdFail</i> = <i>TRUE</i>, if command fails = <i>FALSE</i>, if command was successful</p>	Outputs <i>TRUE</i> if the gripper is open.
Z_IsClosed1 Z_IsClosed2	1: Address gripper 1 2: Address gripper 2	<p><i>bClosed</i> = <i>TRUE</i>, if gripper is open = <i>FALSE</i>, if gripper is closed</p> <p><i>bCmdFail</i> = <i>TRUE</i>, if command fails = <i>FALSE</i>, if command was successful</p>	Outputs <i>TRUE</i> if the gripper is closed.
Z_IsOnTeachPos1 Z_IsOnTeachPos2	1: Address gripper 1 2: Address gripper 2	<p><i>bIsOnTeachPos</i> = <i>TRUE</i>, if gripper is set to TeachPosition = <i>FALSE</i>, if gripper is not set to TeachPosition</p> <p><i>bCmdFail</i> = <i>TRUE</i>, if command fails = <i>FALSE</i>, if command was successful</p>	Outputs <i>TRUE</i> if the gripper is set to <i>TeachPosition</i> .
Z_IsOnUndefPos1 Z_IsOnUndefPos2	1: Address gripper 1 2: Address gripper 2	<p><i>bUndefPos</i> = <i>TRUE</i>, if gripper is set to UndefinedPosition = <i>FALSE</i>, if gripper is not set to UndefinedPosition</p> <p><i>bCmdFail</i> = <i>TRUE</i>, if command fails = <i>FALSE</i>, if command was successful</p>	Outputs <i>TRUE</i> if the gripper is set to <i>OnUndefinedPos</i> .
Z_IsError1 Z_IsError2	1: Address gripper 1 2: Address gripper 2	<p><i>bError</i> = <i>TRUE</i>, if gripper is in error state = <i>FALSE</i>, if gripper is not in error state</p> <p><i>bCmdFail</i> = <i>TRUE</i>, if command fails = <i>FALSE</i>, if command was successful</p>	Outputs <i>TRUE</i> if the gripper is in an error state.
Z_IsMotorOn1 Z_IsMotorOn2	1: Address gripper 1 2: Address gripper 2	<p><i>bMotorOn</i> = <i>TRUE</i>, if motor is on = <i>FALSE</i>, if motor is off</p> <p><i>bCmdFail</i> = <i>TRUE</i>, if command fails = <i>FALSE</i>, if command was successful</p>	Outputs <i>TRUE</i> if the motor of the gripper is switched on.

15 Uninstalling the Comfort App

- ▶ Press the button in the header.
- ▶ Press *Settings*.
- ▶ In the menu, press *System*.
- ▶ In the *System* menu item, press *URCaps*.
- ▶ In the *Active URCaps* area, press *Z_Gripper_C*.
- ▶ Press the - Button.
- ⇒ Uninstallation is complete.
- ▶ Press the *Restart* button to activate the firmware.
- ⇒ The robot control panel performs a restart.



16 Error diagnosis

INFORMATION



- ▶ More information can be found in the installation and operating instructions of the gripper.
- ▶ Please contact Customer Service if you have any questions.

17 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

18 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 product described below

Product designation: Smart Communication Module
Type designation: SCM

conforms 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

19 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 product 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