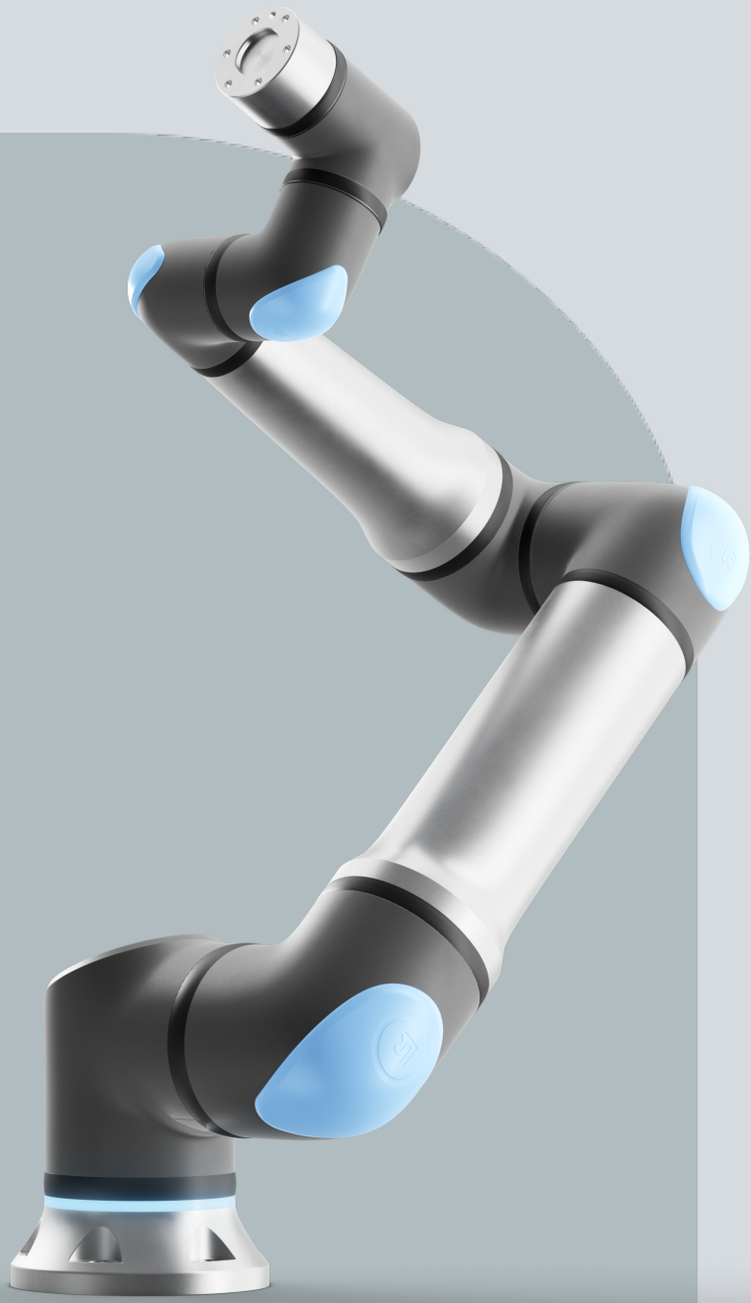
UNIVERSAL ROBOTS

User Manual

UR30 PolyScope X



Original instructions (en)

PolyScope X

Contents

1. Liability and Intended Use

1.1. Limitation of Liability

Description

Any information provided in this manual must not be construed as a warranty, by UR, that the industrial robot will not cause injury or damage, even if the industrial robot complies with all safety instructions and information for use.

1.2. Intended Use

Description

READ MANUAL

Failure to use the robot in accordance with the intended use can result in hazardous situations.

- Read and follow the recommendations for intended use and the specifications provided in the User Manual.

Universal Robots robots are intended for industrial use, to handle tools/end effectors and fixtures, or to process or transfer components or products. For details about the conditions under which the robot should operate.

All UR robots are equipped with safety functions, which are purposely designed to enable collaborative applications, where the robot application operates together with a human. The safety function settings must be set to the appropriate values as determined by the robot application risk assessment.

Collaborative applications are only intended for non-hazardous applications, where the complete application, including tool/end effector, work piece, obstacles and other machines, is low risk according to the risk assessment of the specific application.

WARNING

Using UR robots or UR products outside of the intended uses can result in injuries, death and/or property damage. Do not use the UR robot or products for any of the below unintended uses and applications:

- Medical use, i.e. uses relating to disease, injury or disability in humans including the following purposes:
  - Rehabilitation
  - Assessment
  - Compensation or alleviation
  - Diagnostic
  - Treatment
  - Surgical
  - Healthcare
  - Prosthetics and other aids for the physically impaired
  - Any use in proximity to patient/s
- Handling, lifting, or transporting people
- Any application requiring compliance with specific hygienic and/or sanitation standards, such as proximity or direct contact with food, beverage, pharmaceutical, and /or cosmetic products.
  - UR joint grease can be released into the air (vapor), or drip.
- Any use, or any application, deviating from the intended use, specifications, and certifications of UR robots or UR products.
- Misuse is prohibited as the result could be death, personal injury, and /or property damage

UNIVERSAL ROBOTS EXPRESSLY DISCLAIMS ANY EXPRESS OR IMPLIED WARRANTY OF FITNESS FOR ANY PARTICULAR USE.

WARNING

Do not modify the robot. Do not modify or alter e-Series end caps. A modification can create unforeseen hazards. All authorized disassembling and reassembling shall be done at a UR service center, or can be done according to the newest version of all relevant service manuals by skilled persons.

WARNING

Failure to consider the added risks due to the reach, payloads, operating torques and speeds associated with robot application, can result in injury or death.

- Your application risk assessment shall include the risks associated with the application's reach, motion, payload and speed of the robot, end effector and workpiece.

2. Your Robot

Introduction

Congratulations on the purchase of your new Universal Robots robot, which consists of the robot arm (manipulator), Control Box and the Teach Pendant.

Originally designed to mimic the range of motion of a human arm, the robot arm is composed of aluminium tubes, articulated by six joints, allowing for a high range of flexibility in your automation installation.
The Universal Robots patented programming interface, PolyScope, allows you to create, load and run your automation applications.

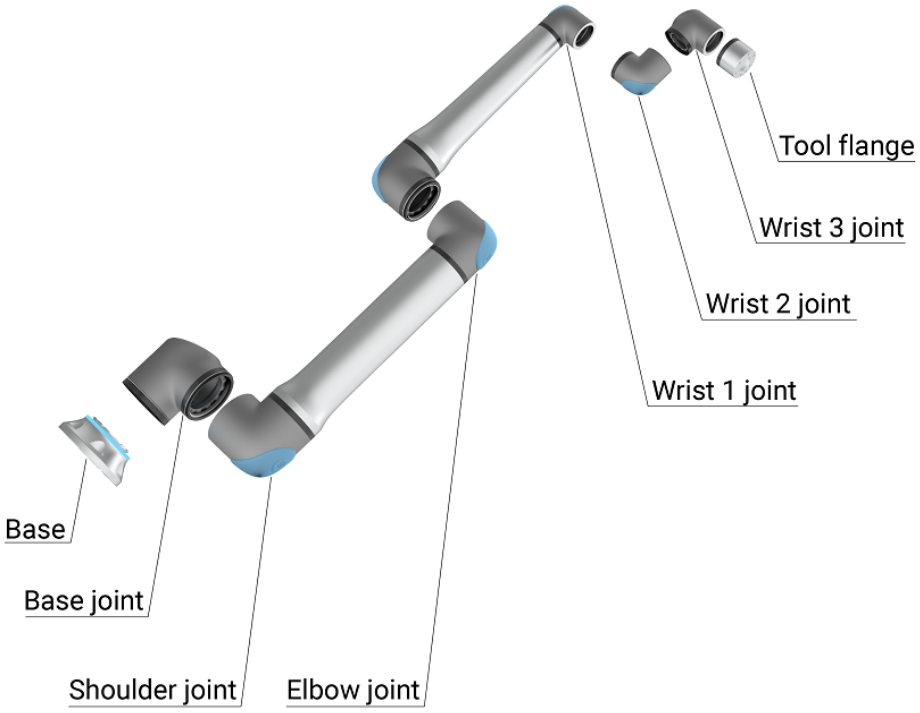
In the boxes

- Robot arm
- Control Box
- Teach Pendant or a 3PE Teach Pendant
- Mounting bracket for the Control Box
- Mounting bracket for the 3PE Teach Pendant
- Key for opening the Control Box
- Cable for connecting the robot arm and the Control Box (multiple options available depending on robot size)
- Mains cable or power cable compatible with your region
- Round sling or lifting sling (depending on robot size)
- Tool cable adapter (depending on robot version)
- This manual

About the robot arm

The Joints, Base and Tool Flange are the main components of the robot arm. The controller coordinates joint motion to move the robot arm.

Attaching an end effector (tool) to the Tool Flange at the end of the robot arm, allows the robot to manipulate a workpiece. Some tools have a specific purpose beyond manipulating a part, for example, QC inspection, applying adhesives and welding.



1.1: *The main components of the robot arm.*

- **Base**: where the robot arm is mounted.
- **Shoulder** and **Elbow**: make larger movements.
- **Wrist 1** and **Wrist 2**: make finer movements.
- **Wrist 3**: where the tool is attached to the Tool Flange.

The robot is partly completed machinery, as such a Declaration of Incorporation is provided. A risk assessment is required for each robot application.

About the manual

This manual contains safety information, guidelines for safe use, and instructions to mount the robot arm, Control Box and Teach Pendant. You can also find instructions for how to begin to install and how to start programming the robot.

Read and adhere to the intended uses. Perform a risk assessment. Install and use in accordance with the electrical and mechanical specifications provided in this user manual.

Risk assessment requires an understanding of the hazards, risks and risk reduction measures for the robot application. Robot integration can require a basic level of mechanical and electrical training.

Content disclaimer

Universal Robots A/S continues to improve the reliability and performance of its products, and as such reserves the right to upgrade products, and product documentation, without prior warning. Universal Robots A/S takes every care to ensure the content of the User Manual/s is precise and correct, but takes no responsibility for any errors or missing information.

This manual does not contain warranty information.

myUR

The myUR portal allows you to register all your robots, keep track of service cases and answer general support questions.

Sign into myur.universal-robots.com to access the portal.

In the myUR portal, your cases are handled either by your preferred distributor, or escalated to Universal Robots Customer Service teams.
You can also subscribe to robot monitoring and manage additional user accounts in your company.

Support

The support site www.universal-robots.com/support contains other language versions of this manual

UR+

The online showroom UR+www.universal-robots.com/plus provides cutting-edge products to customize your UR robot application. You can find everything you need in one place – from tools and accessories to software.

UR+ products connect to and work with UR robots to ensure simple set-up and an overall smooth user experience. All UR+ products are tested by UR.

You can also access the UR+ Partner Program via our software platform plus.universal-robots.com to design more user-friendly products for UR robots.

UR forums

The UR Forum forum.universal-robots.com allows robot enthusiasts of all skill levels to connect to UR and each other, to ask questions and to exchange information. While the UR Forum was created by UR+ and our admins are UR employees, the majority of the content is created by you, the UR Forum user.

Academy

The UR Academy site academy.universal-robots.com offers a variety of training opportunities.

Developer suite

The UR Developer Suite universal-robots.com/products/ur-developer-suite is a collection of all the tools needed to build an entire solution, including developing URCaps, adapting end-effectors, and integrating hardware.

Online manuals

Manuals, guides and handbooks can be read online. We have gathered a large number of documents at https://www.universal-robots.com/manuals

- PolyScope Software Handbook with descriptions and instructions for the software
- The Service Handbook with instructions for troubleshooting, maintenance and repair
- The Script Directory with scripting for in depth programming

2.1. Technical Specifications UR30

Robot type	UR30
Maximum payload	30 kg (66.1 lb) 35 kg (77.1 lb) with boundary conditions according to the manual
Reach	1300 mm / 51.18 in
Degrees of freedom	6 rotating joints
Programming	PolyScope GUI on 12 in touchscreen
Power consumption (average)	750 W (max.) Approx. 300 W using a typical program
Ambient temperature range	0-50 °C. At ambient temperatures above 35°C, the robot may operate at reduced speed and performance.
Safety functions	17 sophisticated safety functions. PLd Category 3 in accordance with: EN ISO 13849-1.
IP classification	Robot Arm: IP65, Control Box: IP44, Teach Pendant: IP54
Cleanroom classification	Robot Arm: ISO Class 4, Control Box: ISO Class 4, Teach Pendant: ISO Class 1
Noise	Robot Arm: less than 65 dB(A), Control Box: less than 50 dB (A)
Tool I/O ports	2 digital in, 2 digital out, 2 analog in
Tool I/O power supply & voltage	2 A (Dual pin) 1 A (Single pin) & 12 V/24 V
Force Torque sensor accuracy	10 N
Speed	All wrist joints: Max 210 °/s Elbow joint: Max 150 °/s Base and Shoulder joints: Max 120 °/s Tool: Approx. 2 m/s / Approx. 78.7 in/s
Pose repeatability	± 0.1 mm / ± 0.0039 in (3.9 mils) per ISO 9283
Joint ranges	± 360 ° for all joints
Footprint	Ø245 mm / 9.65 in
Materials	Aluminium, PC/ASA plastic, steel
Robot weight	63.5 kg / 140 lb
System update frequency	500 Hz
Control Box size (W × H × D)	460 mm x 449 mm x 254mm / 18.2 in x 17.6 in x 10 in
Control Box weight	12 kg / 26.5 lb
Control Box I/O ports	16 digital in, 16 digital out, 2 analog in, 2 analog out
Control Box I/O power supply	24 V/2 A
Communication	MODBUS TCP & EthernetNet/IP adapter, PROFINET, USB 2.0, USB 3.0
Control Box power source	100-240 VAC, 47-440 Hz
Short-Circuit Current Rating (SCCR)	200A
TP size (W × H × D)	300 mm x 231 mm x 50 mm
TP weight	1.8 kg / 3.961 lb
TP cable: Teach Pendant to Control Box	4.5 m / 177 in
Robot Cable: robot arm to Control Box	Hiflex (PUR) 6 m / 236 in x 12.1 mm

2.2. Teach Pendant with 3-Position Enabling Device

Description

Depending on the robot generation, your Teach Pendant can include a built-in 3PE device. This is called a 3-Position Enabling Teach Pendant (3PE TP).
Higher payload robots can only use the 3PE TP.

If you are using a 3PE TP, the buttons are located on the underside of the Teach Pendant, as illustrated below. You can use either button, according to your preference.

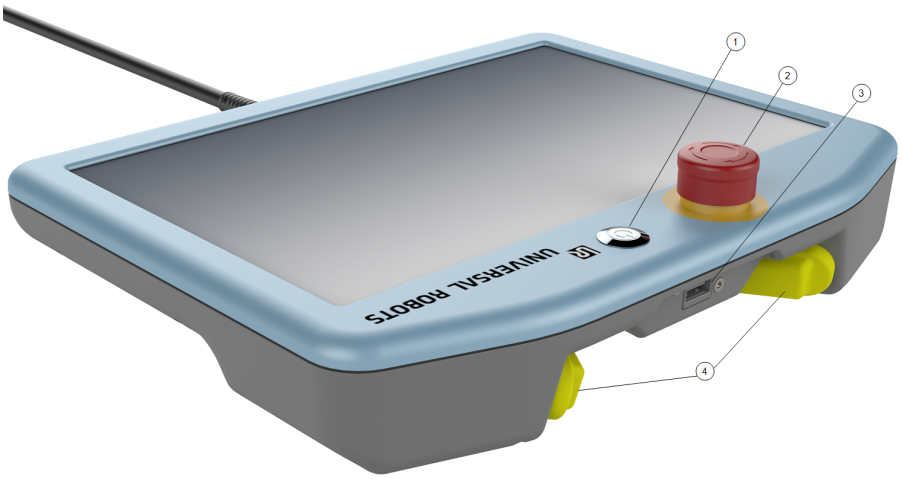
If the Teach Pendant is disconnected, you are required to connect and configure an external 3PE device. The 3PE TP functionality extends to the PolyScope interface, where there are additional functions in the Header.

NOTICE

- If you have bought a UR20 or a UR30 robot, a Teach Pendant without the 3PE device will not work.
- Using a UR20, or a UR30, requires an external enabling device or a 3PE Teach Pendant when programming, or teaching, within the reach of the robot application. See ISO 10218-2.
- The 3PE Teach Pendant is not included with the purchase of the OEM Control Box, so enabling device functionality is not provided.

Overview of TP

1. Power button
2. Emergency Stop button
3. USB port (comes with a dust cover)
4. 3PE buttons



Freedrive A Freedrive robot symbol is located under each 3PE button, as illustrated below.

2.2.1. 3PE Teach Pendant Button Functions

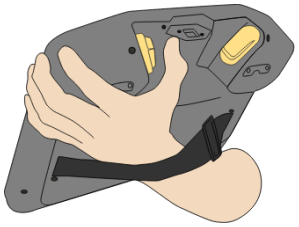
Description

NOTICE

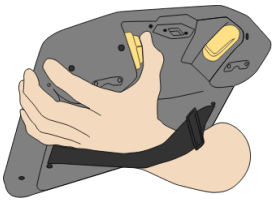
The 3PE buttons are only active in Manual mode. In Automatic mode, robot movement does not require 3PE button action.

The table below describes the functions of the 3PE buttons.

Position		Description	Action
1	Release	There is no pressure on the 3PE button. It is not pressed.	Robot movement is stopped in Manual mode. Power is not removed from the robot arm and the brakes remain released.
2	Light-press (Grip lightly)	There is some pressure on the 3PE button. It is pressed to a middle point.	Allows your program to play when the robot is in Manual mode.
3	Tight-press (Grip tightly)	There is full pressure on the 3PE button. It is pressed all the way down.	Robot movement is stopped in Manual mode. Robot is in 3PE Stop.



1 Button release



2 Button press

2.3. PolyScope X Overview

PolyScope X is the Graphical User Interface (GUI) installed on the Teach Pendant that operates the robot arm via a touch screen. The PolyScope X interface allows you to create, load and execute programs.

Screen Layout

The interface is divided as shown in the following illustration:

- **Header** - with button to load or create programs and access program modules.
- **Left Header** - with icons/tabs to select a main screen.
- **Right Header** - with icons/tabs to select a multitask screen.
- **Footer** - with buttons to control robot power and your loaded program.

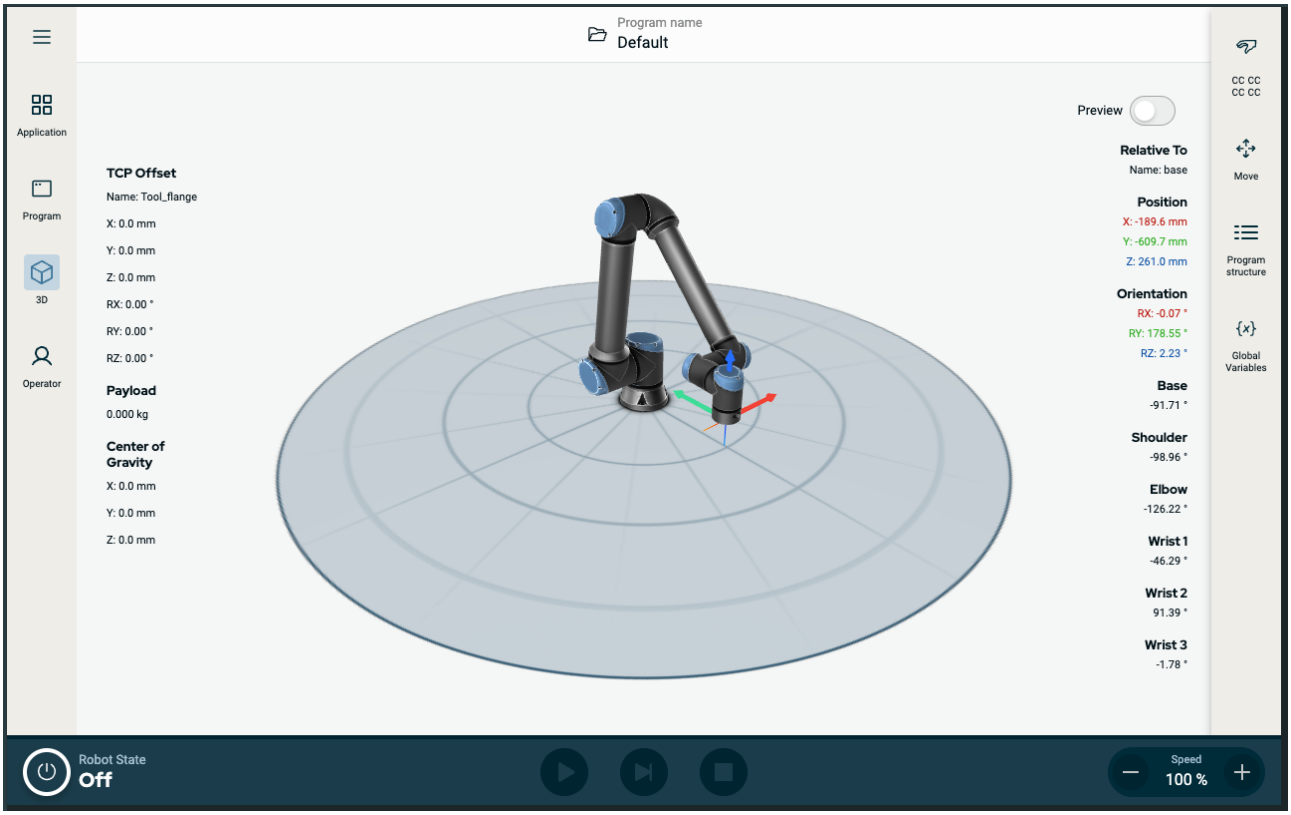


Figure 1.2: *Main screen*

Screen Combinations

The main screen and the multitask screen make up the operating screen combination for the robot.

The multitask screen is independent of the main screen, so you can do separate tasks. For example, you can configure a program in the main screen, while moving the robot arm in the multitask screen. You also can hide the multitask screen if it is not needed.

- **Main screen** - with fields and options to manage and monitor robot actions.
- **Multitask screen** - with fields and options often relating to the main screen.

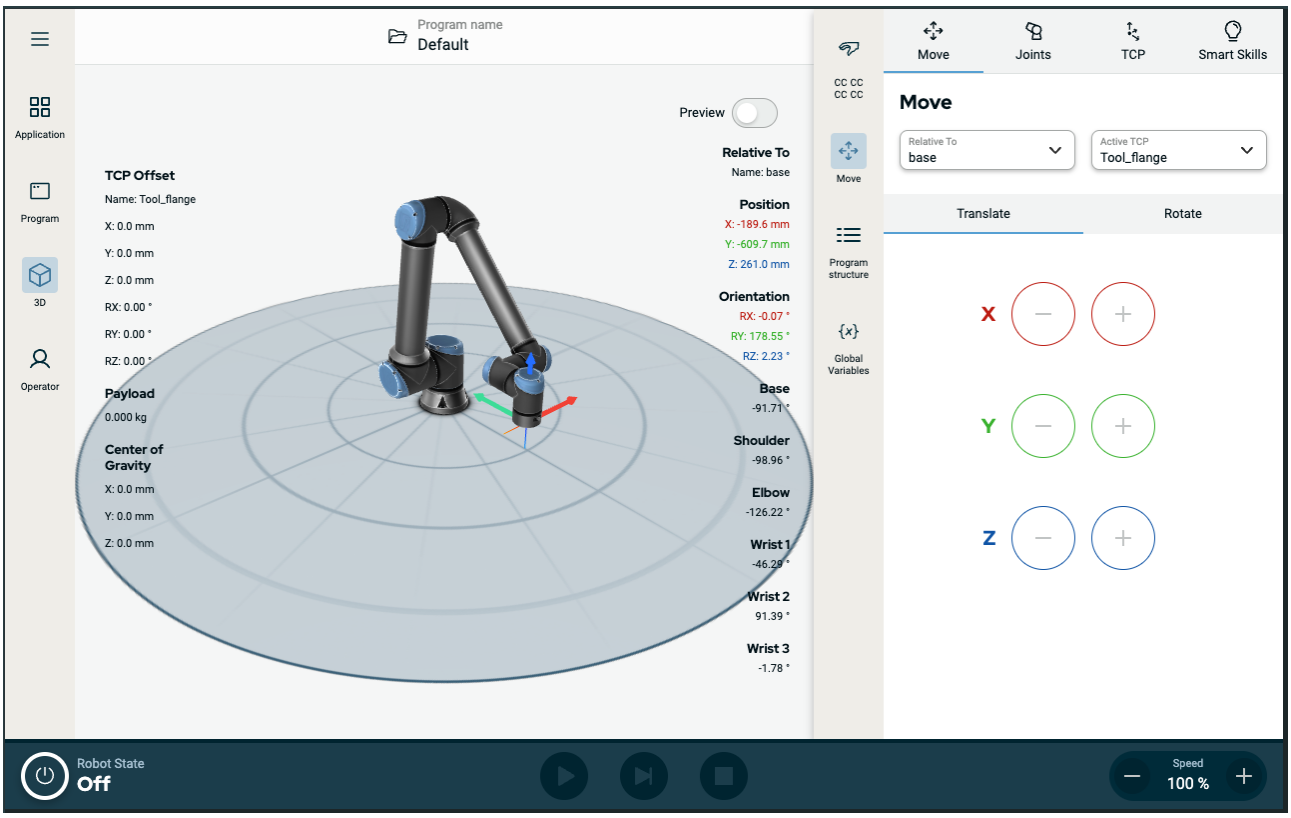


Figure 1.3: *Main screen and multitask screen*

To show/hide the multitask screen

1. In the right header, tap any icon to show the multitask screen.
   The right header expands to the middle of the screen to accommodate the multitask screen.
2. Tap the currently selected icon in the right header to hide the multitask screen.

2.3.1. Touch Screen

The Teach Pendant touch screen is optimised for use in industrial environments. Unlike consumer electronics, Teach Pendant touch screen sensitivity is, by design, more resistant to environmental factors such as:

- Water droplets and/or machine coolant droplets
- Radio wave emissions
- Other conducted noise from the operating environment

The touch sensitivity is designed to avoid false selections on Polyscope X, and to prevent unexpected motion of the robot.

Using the Touch Screen

For best results, use the tip of your finger to make a selection on the screen. In this manual, this is referred to as a "tap". A commercially available stylus may be used to make selections on the screen if desired. The following section lists and defines the icons/tabs and buttons in the Polyscope X interface.

The following section lists and defines the icons/tabs and buttons in the Polyscope X interface.

2.3.2. Icons

Left Header Icons

Icon	Title	Description
	Operator	A simple means of operating the robot using pre-written programs.
	Application	To configure the robot arm settings and external equipment, eg mounting and TCPs.
	Program	Modifies the current robot program.
	3D	Controls and/or regulates robot movement.
	More	Access to About information and Settings.
	About	Displays information about the robot.
	Settings	To configure settings about the software, eg language and units.
	Power	To power on or off the robot.
	Safety Checksum	Displays the active safety checksum and detailed parameters, and change the operation mode.

Footer Buttons

Icon	Title	Description
		
	Initialize	Manages the robot state. When RED, press it to make the robot operational. • Black, Power off. The robot arm is in a stopped state. • Orange, Idle. The robot arm is on, but not ready for normal operation. • Orange, Locked. The robot arm is locked. • Green, Normal. The robot arm is on and ready for normal operation. • Red, Error. The robot is in a fault state, such as e-stop. • Blue, Transition. The robot is changing state, such as brake releasing.
		
	Play	Starts the current loaded program.
	Step	Allows a program to be run single-stepped.
	Stop	Halts the current loaded program.
	Speed slider	Manages the robot state. When RED, press it to make the robot operational.

3. Light Ring

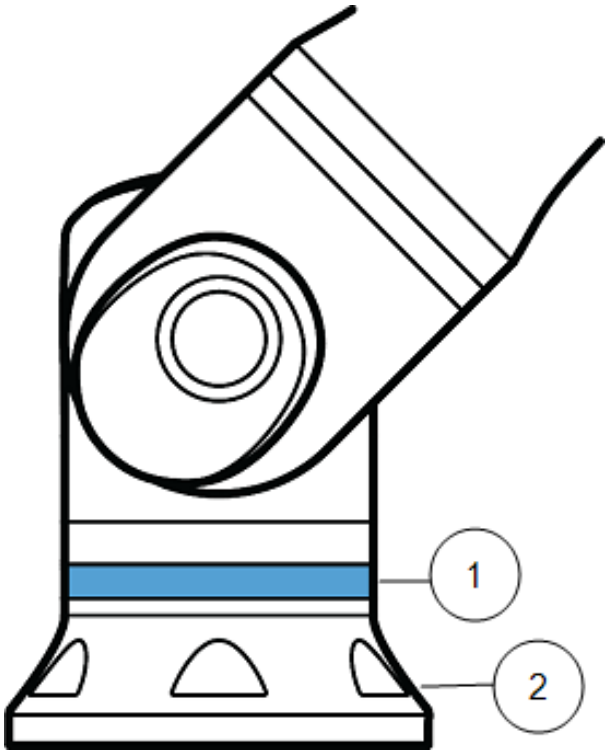
Description

The light ring at the base of the robot arm provides status indication as described in the table below.

NOTICE

The light ring configuration can be modified and/or disabled by the user.

Robot base



1. Light ring
2. Base

Color codes

Color	Mode	
	Steady	Flashing slow 0.5Hz
Red	Robot not moving or in the process of stopping. 1. Emergency stop	
Yellow	Robot not moving or in the process of stopping. 1. Robot stop (previously known as Protective stop) 2. Recovery 3. Safeguard stop (all types)	
Green	Automatic mode 1. Running	Automatic mode 1. Running at reduced parameters
Blue	Manual mode Not Automatic, Not being moved 1. Booting process	Robot can be moved by hand 1. Backdrive 2. Freedrive
OFF	No power available to the robot arm 1. Fault 2. Violation 3. Loading Screen 4. System power OFF	

4. Safety

4.1. General

Description

Read the general safety information and the instructions and guidance pertaining to risk assessment and the intended use. Subsequent sections describe and define safety-related functions particularly relevant for collaborative applications.

WARNING

An application risk assessment must be performed for the safety of personnel and equipment.

Read and understand the specific engineering data relevant to mounting and installation, in order to understand the integration of UR robots before the robot is powered on for the first time.

It is essential to observe and follow all assembly instructions in the following sections of this manual.

NOTICE

Universal Robots disclaims any and all liability if the robot (arm Control Box with or without Teach Pendant) is damaged, changed or modified in any way. Universal Robots cannot be held responsible for any damages caused to the robot or any other equipment due to programming errors, unauthorized access to the UR robot and its contents, or malfunctioning of the robot.

4.2. Safety Message Types

Description

Safety messages are used to emphasize important information. Read all the messages to help ensure safety and to prevent injury to personnel and product damage. The safety message types are defined below.

WARNING

Indicates a hazardous situation that, if not avoided, can result in death or serious injury.

WARNING: ELECTRICITY

Indicates a hazardous electrical situation that, if not avoided, can result in death or serious injury.

WARNING: HOT SURFACE

Indicates a hazardous hot surface where injury can result from contact and non-contact proximity.

CAUTION

Indicates a hazardous situation that, if not avoided, can result in injury.

GROUND

Indicates grounding.

PROTECTIVE GROUND

Indicates protective grounding.

NOTICE

Indicates the risk of damage to equipment and/or information to be noted.

READ MANUAL

Indicates more detailed information that should be consulted in the manual.

4.3. General Warnings and Cautions

Description The following warnings messages can be repeated, explained or detailed in subsequent sections.

WARNING

Failure to adhere to the general safety practices, listed below, can result in injury or death.

- Verify the robot arm and tool/end effector are properly and securely bolted in place.
- Verify the robot application has ample space to operate freely.
- Verify the personnel are protected during the lifetime of the robot application including transport, installation, commissioning, programming/ teaching, operation and use, dismantling and disposing.
- Verify robot safety configuration parameters are set to protect personnel, including those who can be within reach of the robot application.
- Avoid using the robot if it is damaged.
- Avoid wearing loose clothing or jewelry when working with the robot. Tie back long hair.
- Avoid placing any fingers behind the internal cover of the Control Box.
- Inform users of any hazardous situations and the protection that is provided, explain any limitations of the protection and the residual risks.
- Inform users of the location of the emergency stop button(s) and how to activate the emergency stop in case of an emergency or an abnormal situation.
- Warn people to keep outside the reach of the robot, including when the robot application is about to start-up.
- Be aware of robot orientation to understand the direction of movement when using the Teach Pendant.
- Adhere to the requirements and guidance in ISO 10218-2.

WARNING

Handling tools/end effectors with sharp edges and/or pinch points can result in injury.

- Make sure tools/end effectors have no sharp edges or pinch points.
- Protective gloves and/or protective eyeglasses could be required.

WARNING: HOT SURFACE

Prolonged contact with the heat generated by the robot arm and the Control Box, during operation, can lead to discomfort resulting in injury.

- Do not handle or touch the robot while in operation or immediately after operation.
- Check the temperature on the log screen before handling or touching the robot.
- Allow the robot to cool down by powering it off and waiting one hour.

CAUTION

Failure to perform a risk assessment prior to integration and operation can increase risk of injury.

- Perform a risk assessment and reduce risks prior to operation.
- If determined by the risk assessment, do not enter the range of the robot movement or touch the robot application during operation. Install safeguarding.
- Read the risk assessment information.

CAUTION

Using the robot with untested external machinery, or in an untested application, can increase the risk of injury to personnel.

- Test all functions and the robot program separately.
- Read the commissioning information.

NOTICE

Very strong magnetic fields can damage the robot.

- Do not expose the robot to permanent magnetic fields.

READ MANUAL

Verify all mechanical and electrical equipment is installed according to relevant specifications and warnings.

4.4. Integration and Responsibility

Description

The information in this manual does not cover designing, installing, integrating and operating a robot application, nor does it cover all peripheral equipment that can influence the safety of the robot application. The robot application must be designed and installed in accordance with the safety requirements set forth in the relevant standards and regulations of the country where the robot is installed.

The person/s integrating the UR robot are responsible for ensuring that the applicable regulations in the country concerned are observed and that any risks in the robot application are adequately reduced. This includes, but is not limited to:

- Performing a risk assessment for the complete robot system
- Interfacing other machines and additional safeguarding if required by the risk assessment
- Setting the correct safety settings in the software
- Ensuring safety measures are not modified
- Validating the robot application is designed, and installed and integrated
- Specifying instructions for use
- Marking the robot installation with relevant signs and contact information of the integrator
- Retaining all documentation; including the application risk assessment, this manual and additional relevant documentation.

4.5. Stop Categories

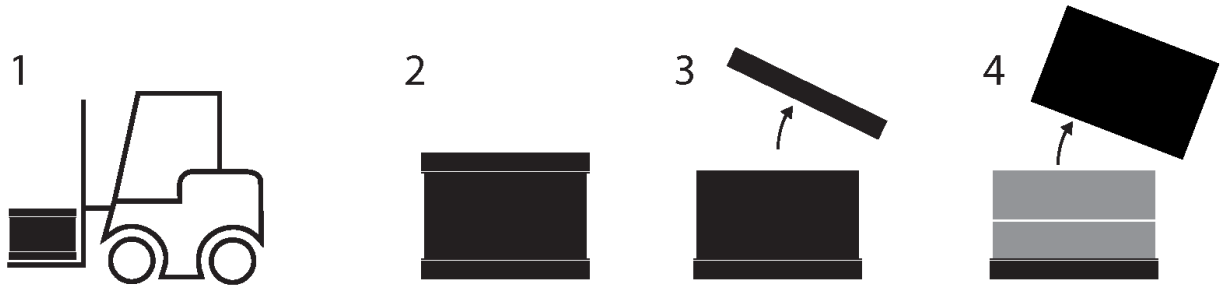
Description

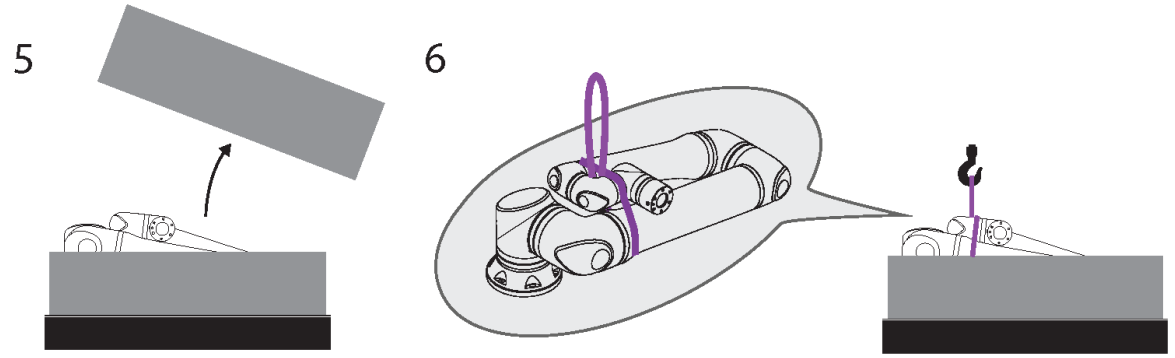
Depending on the circumstances, the robot can initiate three types of stop categories defined according to IEC 60204-1. These categories are defined in the following table.

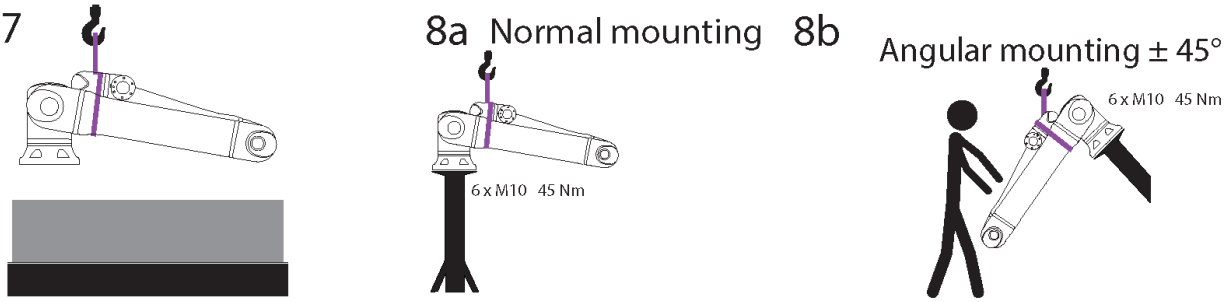
Stop Category	Description
0	Stop the robot by immediate removal of power.
1	Stop the robot in an orderly, controlled manner. Power is removed once the robot is stopped.
2	*Stop the robot with power available to the drives, while maintaining the trajectory. Drive power is maintained after the robot is stopped.

*Universal Robots robots' Category 2 stops are further described as SS1 or as SS2 type stops according to IEC 61800-5-2.

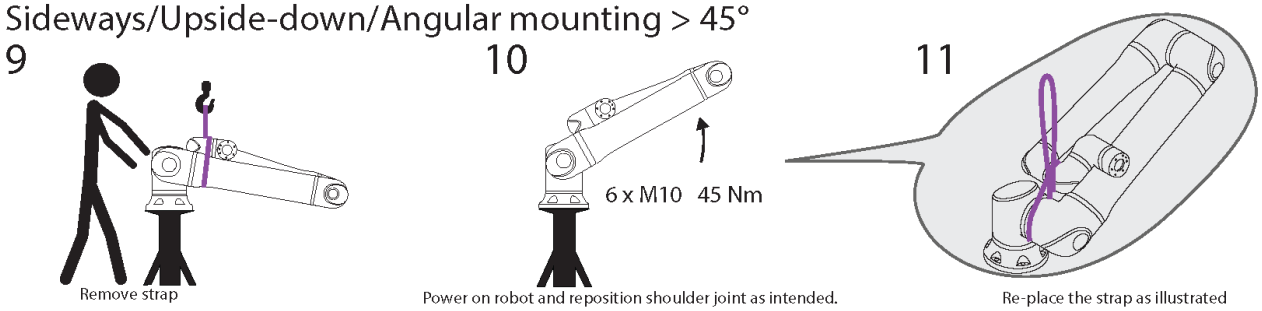
5. Lifting and Handling





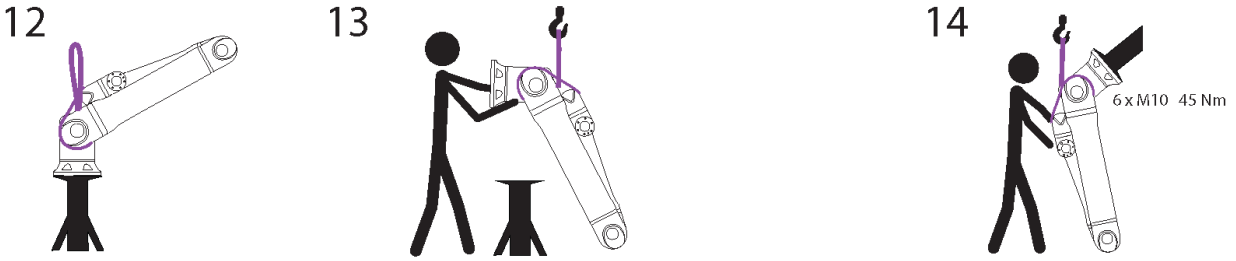


Sideways/Upside-down/Angular mounting > 45°



Power on robot and reposition shoulder joint as intended.
Skip step 10 for sideways mounting.

Re-place the strap as illustrated



When releasing and lifting the robot, support it to rotate and hang as illustrated

Table

	Description	Action	Detail
1	Transport		
2	Opening the box		
3			
4			
5	Removing robot arm from box using strap		
6			
7	Lifting robot arm using strap and hook		When releasing and lifting the robot, support it to rotate and hang as illustrated.
8a	Mounting	a. Normal mounting	• Fasten strap securely when using. • Remove and store strap when not using.
8b		b. Angular mounting +/-45 degrees	
9	Mounting preparation	Sideways/Upsidedown/Angular mounting >45 degrees	1. Remove strap 2. Power on robot and reposition shoulder joint as intended. 3. Skip step 10 for sideways mounting. 4. Replace the strap as illustrated. 5. Move to mounting position. 6. Fasten securely. 7. Remove and store strap.
10			
11			
12	Mounting execution	Sideways/Upsidedown/Angular mounting >45 degrees	When releasing and lifting the robot, support it to rotate and hang as illustrated.
13			
14			

WARNING

Lifting or movement of heavy parts can cause injury.

- Lifting apparatus/aid to lift can be required.

WARNING

Incorrect assembly of components and/or wiring can lead to injury.

- Personal protective gear (footwear, eyewear, gloves) can be required.

CAUTION

Failure to use an appropriate lifting device for the weight of the robot can lead to injury and property damage.

- The lifting device shall be capable of lifting 64kg - robot only.
- The lifting device shall be capable of lifting 84kg - robot with payload.

NOTICE

There may be specific regulations for assembly lifting in your region.

- Follow the local regulations and guidelines for lifting.

For detailed mounting descriptions, see Assembly in the user manual.

5.1. Control Box and Teach Pendant

Description	The Control Box and the Teach Pendant can each be carried by one person. While in use, all cables are to be coiled and held to prevent tripping hazards.

5.2. Robot Arm

Description	The robot arm, depending upon weight, can be carried by one or two people unless the sling is provided. If the sling is provided, equipment for lifting and transport is required.

5.2.1. Round Sling Use

Description	The round sling is provided by UR with UR20 and UR30 robots. According to the manufacturer, the round sling conforms to the following standards: • EN 1492-1 :2000+A1 :2008 Textile slings - Safety - Flat woven webbing slings, made of man-made fibers, for general purpose use. • EN 1492-2 :2000+A1 :2008 Textile slings - Safety - Round slings, made of man-made fibers, for general purpose use.

WARNING

Using the round sling without an inspection can lead to injury.

- Inspect the sling before and after each use.
- Inspect the sling during use if possible.

WARNING

Using a damaged round sling can result in injury.

- Carefully examine the sling visually before each use.
- Do not use the sling if it is cracked, ripped, or the stitching is loose.
- Do not use the sling if there are signs of heat damage.

CAUTION

Incorrect storage and/or handling can cause damage to the round sling.

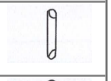
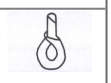
- Keep the sling away from acids and bases.
- Protect the sling against sharp edges and friction.
- Do not tie a knot in the sling.

NOTICE

There may be specific regulations for inspecting lifting equipment in your region.

- Observe local regulations regarding inspection of lifting equipment.
- Observe local regulations regarding inspection frequency of lifting equipment.

Table

Round Sling Description			
Item	Round sling 1T x 1M/2M		
Color	Violet (according to EN 1492-2)		
Material	Polyester		
WLL Factor	1.0 (1000 KG)	Straight Lift	
	0.8 (800 KG)	Choke Hitch	

6. Assembly and Mounting

Description Install and power on the robot arm and Control Box to start using PolyScope.

Assemble the robot You have to assemble the robot arm, Control Box and Teach Pendant to be able to continue.

1. Unpack the robot arm and the Control Box.
2. Mount the robot arm on a sturdy, vibration-free surface.

   Verify the surface can withstand at least 10 times the full torque of the base joint and at least 5 times the weight of the robot arm.
3. Place the Control Box on its Foot.
4. Connect the robot cable to the robot arm and the Control Box.
5. Plug in the mains, or main power cable, of the Control Box.

WARNING

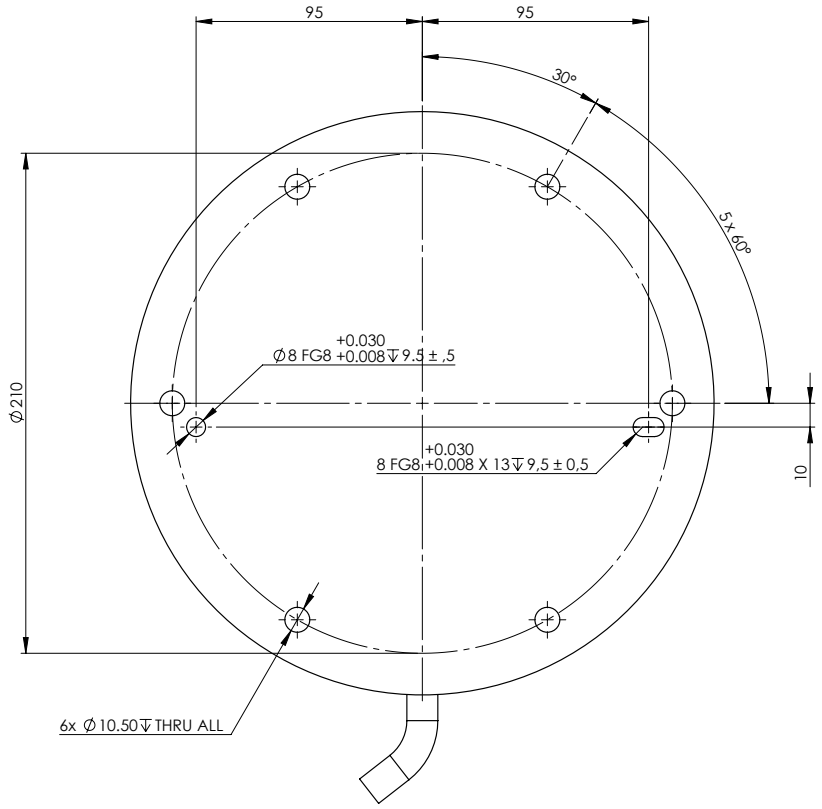
Failure to secure the robot arm to a sturdy surface can lead to injury caused by the robot falling.

- Ensure the robot arm is secured to a sturdy surface

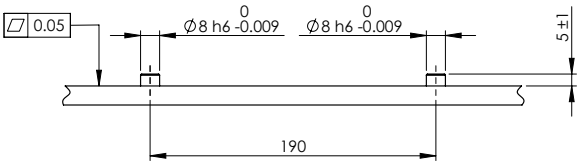
6.1. Securing the Robot Arm

Description

Bottom View of Robot Base



Mounting Plate with Pins for Robot Base



Dimensions and hole pattern for mounting the robot.

To power down the robot arm

WARNING

Unexpected start-up and/or movement can lead to injury

- Power down the robot arm to prevent unexpected start-up during mounting and dismounting.

1. Press the power button on the Teach Pendant to turn off the robot.
2. Unplug the mains cable / power cord from the wall socket.
3. Allow 30 seconds for the robot to discharge any stored energy.

To secure the robot arm

1. Place the robot arm on the surface on which it is to be mounted. The surface must be even and clean.
2. Tighten the six 8.8 strength, M10 bolts to a torque of 45 Nm.
   (Torque values have been updated SW 5.18. Earlier printed version will show different values)
3. If accurate re-mounting of the robot is required, use the Ø8 mm. hole and Ø8x13 mm. slot with corresponding ISO 2338 Ø8 h6 positioning pins in the mounting plate.

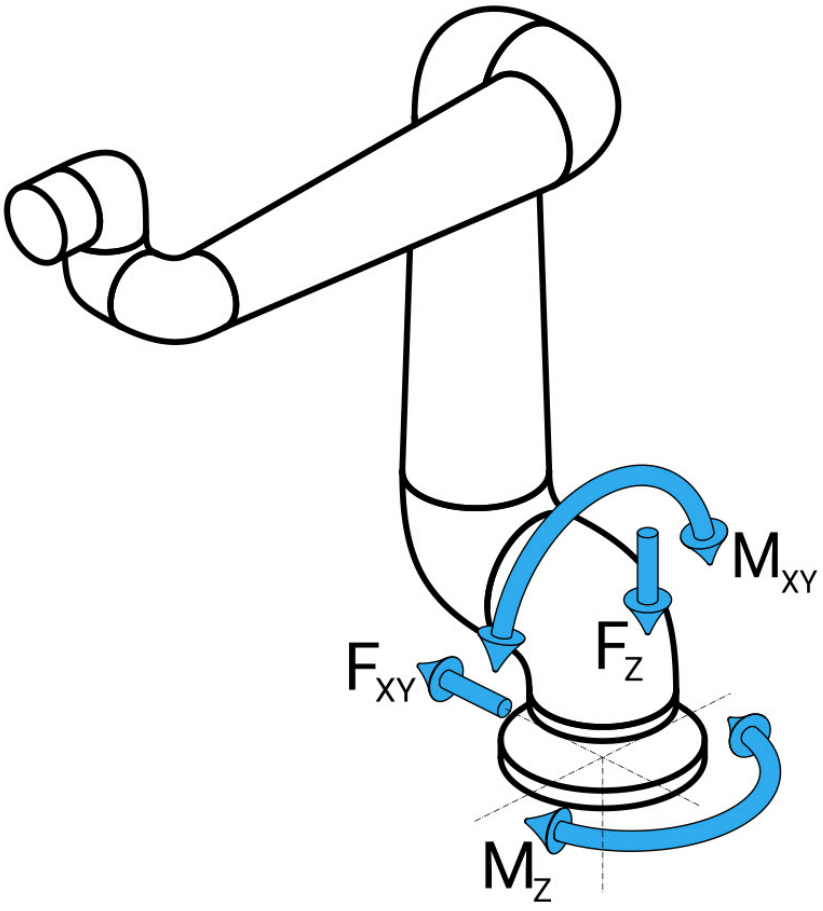
6.2. Dimensioning the Stand

Description

The structure (stand) on which the robot arm is mounted is a crucial part of the robot installation. The stand must be sturdy and free of any vibrations from external sources.

Each robot joint produces a torque that moves and stops the robot arm. During normal uninterrupted operation and during stopping motion, the joint torques are transferred to the robot stand as:

- Mz: Torque around the base z axis.
- Fz: Forces along base z axis.
- Mxy: Tilting torque in any direction of the base xy plane.
- Fxy: Force in any direction in the base xy plane.



Force and moment at base flange definition.

Dimensioning the Stand

The magnitude of the loads depends on robot model, program and multiple other factors. Dimensioning of the stand shall account for the loads that the robot arm generates during normal uninterrupted operation and during category 0, 1 and 2 stopping motion.

During stopping motion, the joints are allowed to exceed the maximum nominal operating torque. The load during stopping motion is independent of the stop category type.
The values stated in the following tables are maximum nominal loads in worst-case movements multiplied with a safety factor of 2.5. The actual loads will not exceed these values.

Robot Model	Mz [Nm]	Fz[N]	M_{xy}[Nm]	F_{xy} [N]
UR30	2220	3520	2700	2370

Maximum joint torques during category 0, 1 and 2 stops.

Robot Model	Mz [Nm]	Fz[N]	M_{xy}[Nm]	F_{xy} [N]
UR30	1850	2690	1890	2080

Maximum joint torques during normal operation.

The normal operating loads can generally be reduced by lowering the acceleration limits of the joints. Actual operating loads are dependent on the application and robot program. You can use URSim to evaluate the expected loads in your specific application.

Safety margins

You can incorporate added safety margins, factoring in the following design considerations:

- **Static stiffness**: A stand that is not sufficiently stiff will deflect during robot motion, resulting in the robot arm not hitting the intended waypoint or path. Lack of static stiffness can also result in a poor freedrive teaching experience or protective stops.
- **Dynamic stiffness**: If the eigenfrequency of the stand matches the movement frequency of the robot arm, the entire system can resonate, creating the impression that the robot arm is vibrating. Lack of dynamic stiffness can also result in protective stops. The stand should have a minimum resonance frequency of 45 Hz.
- **Fatigue**: The stand shall be dimensioned to match the expected operating lifetime and load cycles of the complete system.

CAUTION

- If the robot is mounted on an external axis, the accelerations of this axis must not be too high. You can let the robot software compensate for the acceleration of external axes by using the script command set_base_acceleration()
- High accelerations can cause the robot to make safety stops.

WARNING

- Potential for tip-over Hazards.
- The robot arm's operational loads can cause movable platforms, such as tables or mobile robots, to tip over, resulting in possible accidents.
- Prioritize safety by implementing adequate measures to prevent the tipping of movable platforms at all times.

6.3. Mounting Description

Description

Robot arm (Base)	Mounted with four strength class 8.8, 8.5 mm bolts and four M8 mounting holes at the base.
Tool Flange	Uses four M6 thread holes for attaching a tool to the tool flange. The M6 strength class 8.8 bolts shall be tightened with 8 Nm. For accurate tool repositioning, use a pin in the Ø6 hole provided.
Control Box	The Control Box can be hung on a wall or placed on the ground.
Teach Pendant	The Teach Pendant is wall mounted or placed onto the Control Box. Verify the cable does not cause tripping hazard. You can buy extra brackets for mounting the Control Box and Teach Pendant.

WARNING

Mounting and operating the robot in environments exceeding the recommended IP rating can result in injury.

- Mount the robot in an environment suited to the IP rating. The robot must not be operated in environments that exceed those corresponding to the IP ratings of the robot (IP54), Teach Pendant (IP54) and Control Box (IP44)

WARNING

Unstable mounting can result in injury.

- Always make sure the robot parts are properly and securely mounted and bolted in place.

6.4. Workspace and Operating Space

Description

The workspace is the range of the fully extended robot arm, horizontally and vertically. The operating space is the location where the robot is expected to function.

NOTICE

Disregard for the robot workspace and operating space can result in the damage to property.

It is important to consider the cylindrical volume directly above and directly below the robot base when choosing location to mount the robot. Moving the tool close to the cylindrical volume should be avoided because it causes the joints to move fast even when the tool is moving slowly. This can cause the robot to work inefficiently and can make it difficult to conduct a risk assessment.

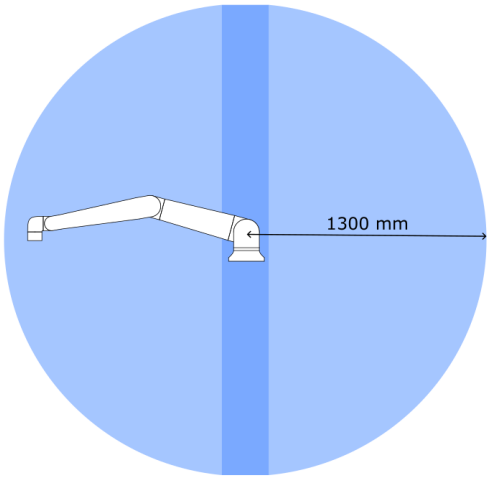
NOTICE

Moving the tool close to the cylindrical volume can cause the joints to move too fast, leading to loss of functionality and damage to property.

- Do not move the tool close to the cylindrical volume, even when the tool is moving slowly.

Workspace

- The robot extends 1300 mm from the base joint.
- The cylindrical volume is both directly above and directly below the robot base.
- The tool should not be moved close to the cylindrical volume, as it causes the joints to move too fast even when the tool is moving slowly. This can present a risk to property and functionality.



Front | Tilted

6.4.1. Singularity

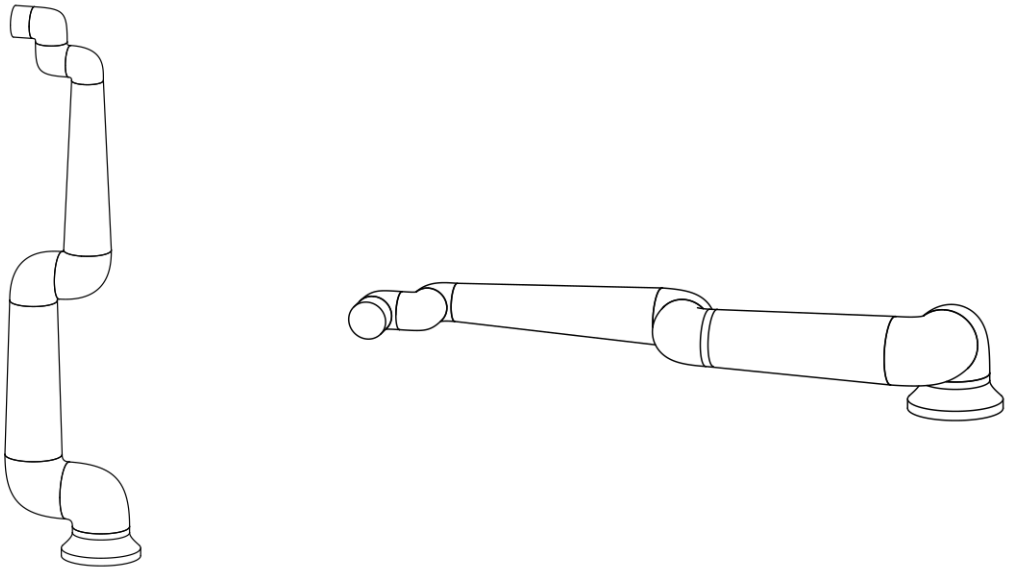
Description

A singularity is a pose that restricts the motion and the ability to position the robot. The robot arm can stop moving or have very sudden and fast movements when approaching and leaving singularity.

WARNING

Make sure that robot motion near a singularity does not create hazards to anyone within the range of the robot arm, end effector, and workpiece.

- Set safety limits for the speed and acceleration of the elbow joint.



The following causes singularity in the robot arm:

- Outer workspace limit
- Inner workspace limit
- Wrist alignment

Outer workspace limit

The singularity occurs because the robot cannot reach far enough or it reaches outside of the maximum working area.

To avoid: Arrange the equipment around the robot to avoid it reaching outside of the recommended workspace.

Inner workspace limit

The singularity occurs because the movements are directly above or directly below the robot base. This causes many positions/orientations to be unreachable.

To avoid: Program the robot task in such a way that it is not necessary to work in or close to the central cylinder. You can also consider mounting the robot base on a horizontal surface to rotate the central cylinder from a vertical to horizontal orientation, potentially moving it away from the critical areas of the task.

Wrist alignment

This singularity occurs because wrist joint 2 rotates on the same plane as the shoulder, elbow and wrist joint 1. This limits the range of movement of the robot arm, regardless of workspace.

To avoid:Layout the robot task in such a way that it is not necessary to align the robot wrist joints in this manner. You can also offset the direction of the tool, so that the tool can point horizontally without the problematic wrist alignment.

6.4.2. Fixed and Movable Installation

Description

Whether the robot arm is fixed (mounted to a stand, wall or floor) or in a movable installation (linear axis, push cart, or mobile robot base), it must be installed securely to ensure stability through all motions.

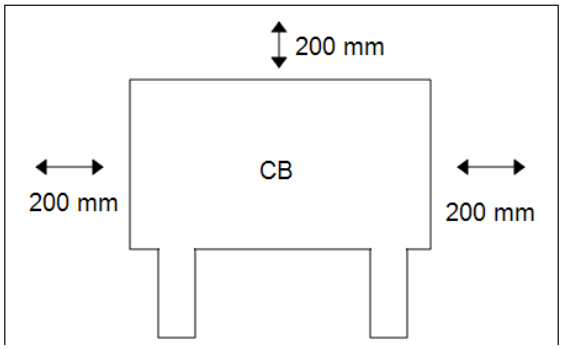
The design of the mounting must ensure stability when there are movements of:

- the robot arm
- the robot base
- both robot arm and robot base

6.5. Control Box Clearance

Description

The flow of hot air in the Control Box can result in equipment malfunction. The recommended Control Box clearance is 200 mm on each side for sufficient cool airflow.



WARNING

A wet Control Box can cause fatal injury.

- Make sure the Control Box and cables do not come into contact with liquids.
- Place the Control Box (IP44) in an environment suited for the IP rating.

6.6. Robot Connections: Base Flange Cable

Description

This subsection describes the connection for a robot arm configured with a Base Flange Cable connector.

Base Flange Cable connector

The Base Flange Cable establishes the robot connection to robot arm to the Control Box. The Robot Cable connects to the Base Flange Cable connector on one end, and to the Control Box connector on the other end.
You can lock each connector when robot connection is established.

CAUTION

Improper robot connection can result in loss of power to the robot arm.

- Do not extend a 12 m Robot Cable.

NOTICE

Connecting the Base Flange Cable directly to any Control Box can result in equipment or property damage.

- Do not connect the Base Flange Cable directly to the Control Box.

6.7. Robot Connections: Robot Cable

Description

This subsection describes the connection for a robot arm configured with a fixed 12 meter Robot Cable.

Connect arm and Control box

Establish the robot connection by connecting the robot arm to the Control Box with the Robot Cable.
Plug and lock the cable from the robot into the connector at the bottom of the Control Box (see illustration below). Twist the connector twice to ensure it is properly locked before turning on the robot arm.
You can turn the connector to the right to make it easier to lock after the cable is plugged in.

CAUTION

Improper robot connection can result in loss of power to the robot arm.

- Do not disconnect the Robot Cable when the robot arm is turned on.
- Do not extend or modify the original Robot Cable.

6.8. Mains Connections

Description

The mains cable from the Control Box has a standard IEC plug at the end. Connect a country specific mains plug, or cable, to the IEC plug.

NOTICE

- IEC 61000-6-4:Chapter 1 scope: “This part of IEC 61000 for emission requirement applies to electrical and electronic equipment intended for use within the environment of existing at industrial (see 3.1.12) locations.”
- IEC 61000-6-4:Chapter 3.1.12 industrial location: “Locations characterized by a separate power network, supplied from a high- or medium-voltage transformer, dedicated for the supply of the installation”

Mains connections

To power the robot, the Control Box shall be connected to the mains via the supplied power cord. The IEC C13 connecter on the power cord connects to the IEC C14 appliance inlet at the bottom of the Control Box.

NOTICE

Always use a power cord with a country specific wall plug when connecting to the Control Box. Do not use an adapter.

As a part of the electrical installation, provide the following:

- Connection to ground
- Main fuse
- Residual current device
- A lockable (in the OFF position) switch

A main switch shall be installed to power off all equipment in the robot application as an easy means for lockout. The electrical specifications are shown in the table below.

Parameter	Min	Typ	Max	Unit
Input voltage	90	-	264	VAC
External mains fuse (90-200V)	15	-	16	A
External mains fuse (200-264V)	8	-	16	A
Input frequency	47	-	440	Hz
Stand-by power	-	-	<1.5	W
Nominal operating power	90	300	750	W

WARNING: ELECTRICITY

Failure to follow any of the below can result in serious injury or death due to electrical hazards.

- Ensure the robot is grounded correctly (electrical connection to ground). Use the unused bolts associated with grounding symbols inside the Control Box to create common grounding of all equipment in the system. The grounding conductor shall have at least the current rating of the highest current in the system.
- Ensure the input power to the Control Box is protected with a Residual Current Device (RCD) and a correct fuse.
- Lockout all power for the complete robot installation during service.
- Ensure other equipment shall not supply power to the robot I/O when the robot is locked out.
- Ensure all cables are connected correctly before the Control Box is powered. Always use the original power cord.

7. Application Tab

The Application tab allows you to configure the settings which affect the overall performance of the robot and PolyScope X.

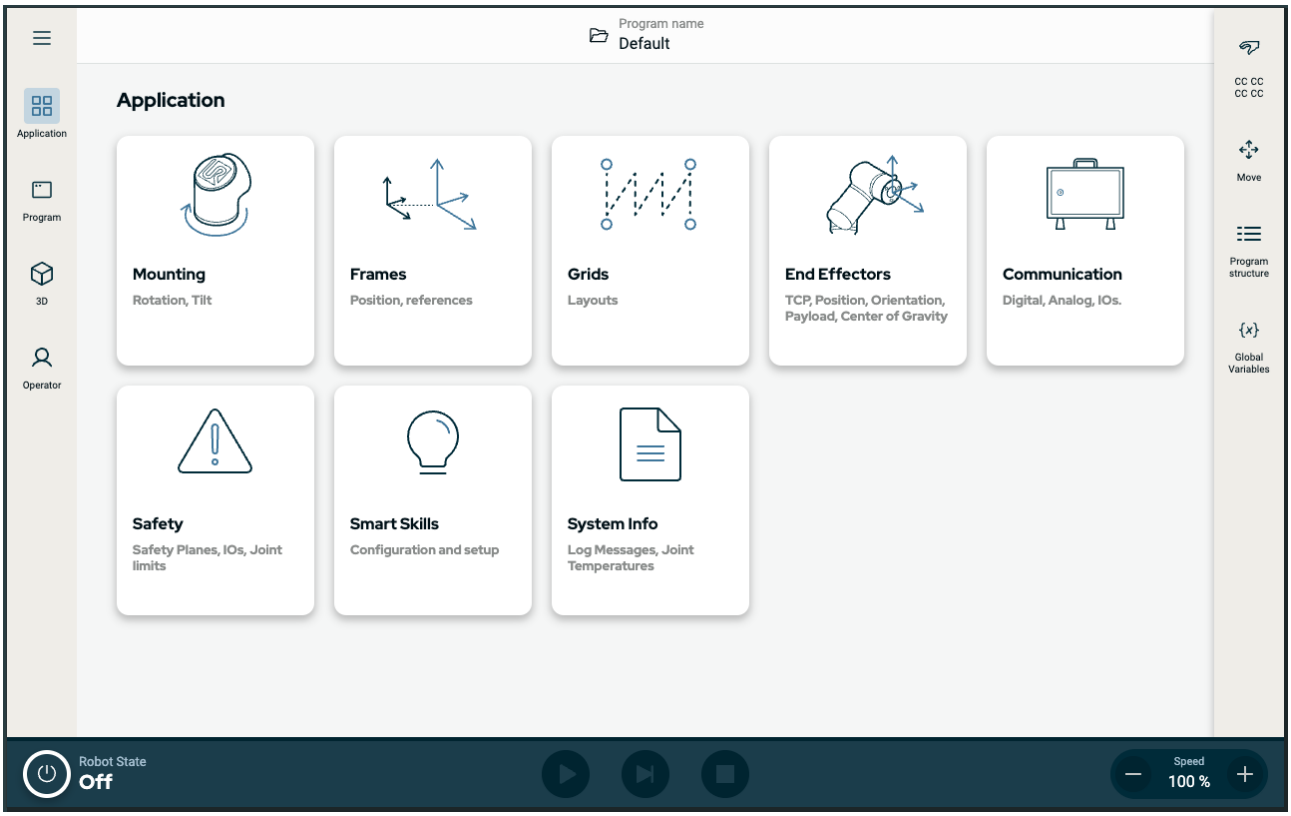


Figure 1.1: *Application screen displaying application buttons.*

Use the Application tab to access to the following configuration screens:

- Mounting
- Frames
- Grids
- End Effectors
- Communication
- Safety
- Smart Skills
- System Info

7.1. Communication

The Communication screen allows you to monitor and set the live I/O signals from/to the robot control box. The screen displays the current state of the I/O, including during program execution. If anything is changed during program execution, the program stops. At program stop, all output signals retain their states.

The Communication screen updates at 10Hz, so very fast signals may not display properly. You can reserve configurable I/Os for special safety settings defined in 8.6.1 Safety I/O Signals on page 63. Those which are reserved will have the name of the safety function in place of the default or user defined name. Configurable outputs reserved for safety settings cannot be selected, they are displayed as LEDs only.

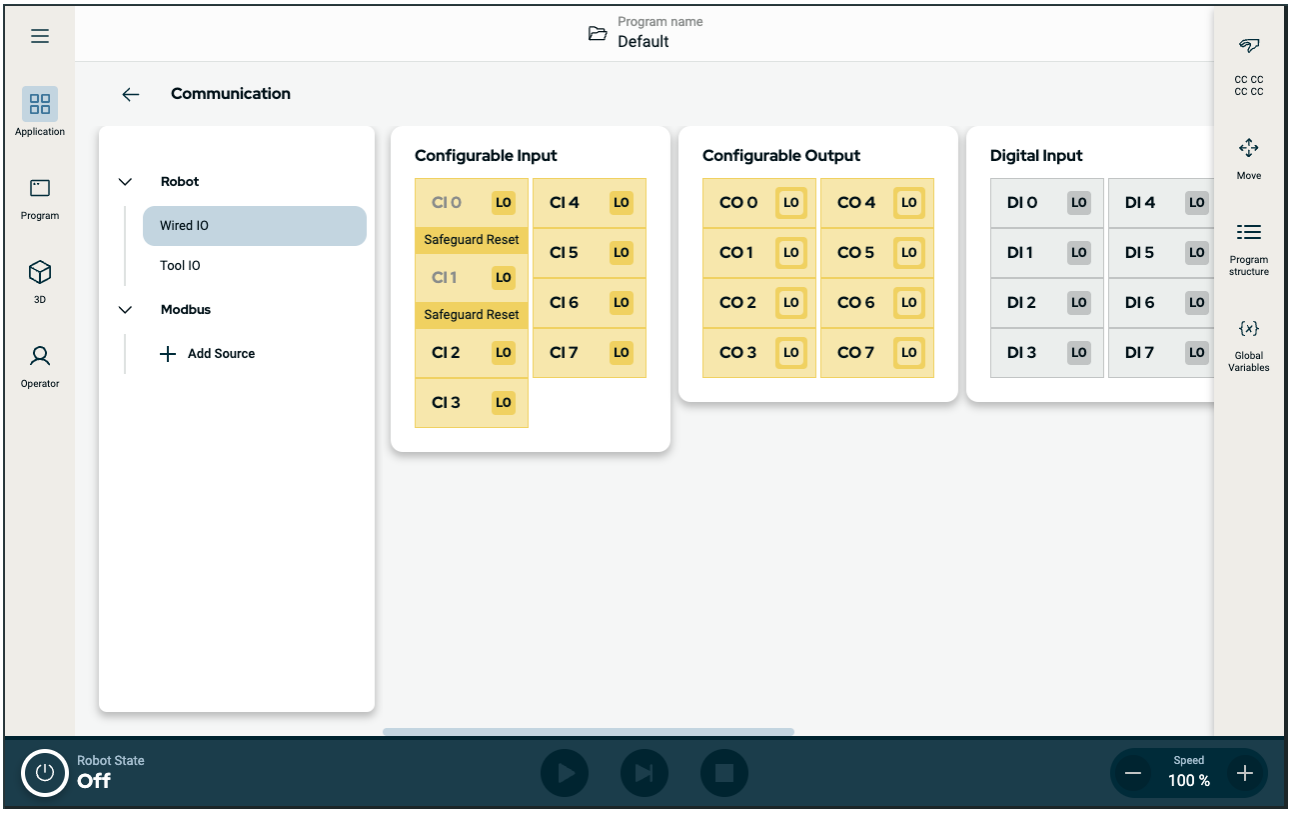


Figure 1.2: *Communication screen displaying I/Os.*

8. Installation

Description

Installing the robot can require the configuration and use of input and output signals (I/Os). These different types of I/Os and their uses are described in the following sections.

8.1. Electrical Warnings and Cautions

Warnings

Observe the following warnings for all the interface groups, including when you design and install an application.

WARNING

Failure to follow any of the below can result in serious injury or death, as the safety functions could be overridden.

- Never connect safety signals to a PLC that is not a safety PLC with the correct safety level. It is important to keep safety interface signals separated from the normal I/O interface signals.
- All safety-related signals shall be constructed redundantly (two independent channels).
- Keep the two independent channels separate so a single fault cannot lead to loss of the safety function.

WARNING: ELECTRICITY

Failure to follow any of the below can result in serious injury or death due to electrical hazards.

- Make sure all equipment not rated for water exposure remain dry. If water is allowed to enter the product, lockout-tagout all power and then contact your local Universal Robots service provider for assistance.
- Only use the original cables supplied with the robot only. Do not use the robot for applications where the cables are subject to flexing.
- Use caution when installing interface cables to the robot I/O. The metal plate in the bottom is intended for interface cables and connectors. Remove the plate before drilling holes. Make sure that all shavings are removed before reinstalling the plate. Remember to use correct gland sizes.

CAUTION

Disturbing signals with levels higher than those defined in the specific IEC standards can cause unexpected behaviors from the robot. Be aware of the following:

- The robot has been tested according to international IEC standards for **ElectroMagnetic Compatibility (EMC)**. Very high signal levels or excessive exposure can damage the robot permanently. EMC problems are found to happen usually in welding processes and are normally prompted by error messages in the log. Universal Robots cannot be held responsible for any damages caused by EMC problems.
- I/O cables going from the Control Box to other machinery and factory equipment may not be longer than 30m, unless additional tests are performed.

GROUND

Negative connections are referred to as Ground (GND) and are connected to the casing of the robot and the Control Box. All mentioned GND connections are only for powering and signalling. For PE (Protective Earth) use the M6-size screw connections marked with earth symbols inside the Control Box. The grounding conductor shall have at least the current rating of the highest current in the system.

READ MANUAL

Some I/Os inside the Control Box can be configured for either normal or safety-related I/O. Read and understand the complete Electrical Interface chapter.

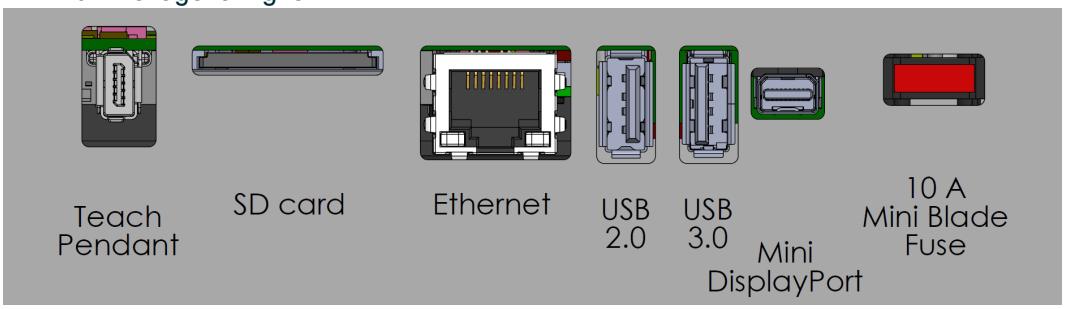
8.2. Control Box Connection Ports

Description

The underside of the I/O interface groups is equipped with external connection ports, as illustrated below. There are capped openings at the base of the Control Box cabinet to run external connector cables to access the ports.

External connection ports

The Mini Displayport supports monitors using Displayport. This requires an active Mini Display to DVI or HDMI converter. Passive converters do not work with DVI/HDMI ports. The Fuse must be a UL marked, Mini Blade type with maximum current rating: 10A and minimum voltage rating: 32V



NOTICE

Connecting or disconnecting a Teach Pendant while the Control Box is powered on can cause damage.

- Do not connect a Teach Pendant while the Control Box is on.
- Power off the Control Box before you connect a Teach Pendant.

Do not connect or disconnect the Teach Pendant while Control Box is powered on. This can cause damage to Control Box.

NOTICE

Failure to plug in the active adapter before powering on the Control Box can hinder the display output.

- Plug in the active adapter before powering on the Control Box.
- In some cases the external monitor must be powered on before the Control Box.
- Use an active adapter that supports revision 1.2 as not all adapters function out-of-the-box.

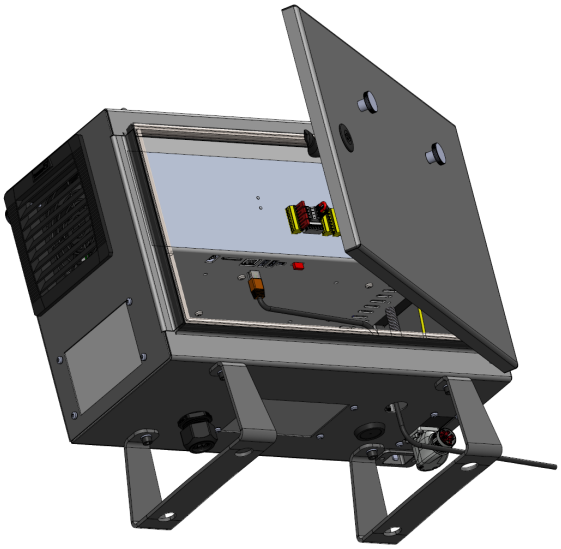
8.3. Ethernet

Description

The Ethernet interface can be used for:

- MODBUS, EtherNet/IP and PROFINET.
- Remote access and control.

To connect the Ethernet cable by passing it through the hole at the base of the Control Box, and plugging it into the Ethernet port on the underside of the bracket.
Replace the cap at the base of the Control Box with an appropriate cable gland to connect the cable to the Ethernet port.



The electrical specifications are shown in the table below.

Parameter	Min	Typ	Max	Unit
Communication speed	10	-	1000	Mb/s

8.4. 3PE Teach Pendant Installation

8.4.1. Hardware Installation

To remove a Teach Pendant

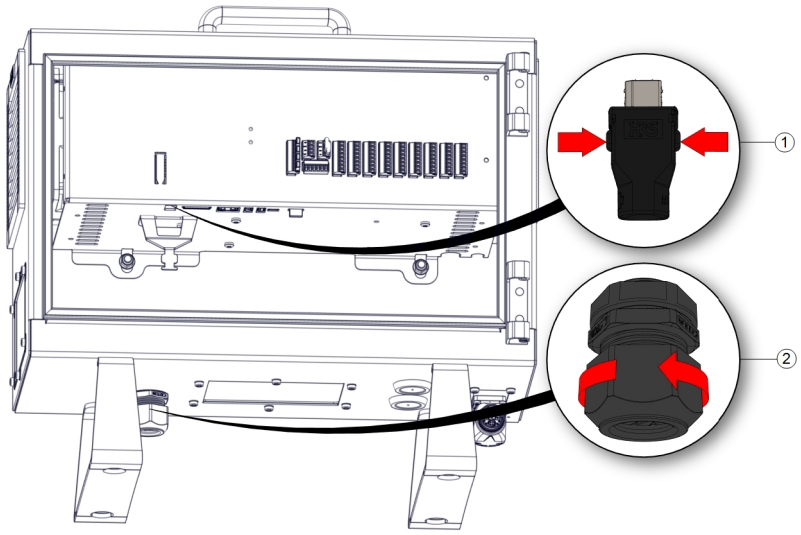
NOTICE

Replacing the Teach Pendant can result in the system reporting a fault on start-up.

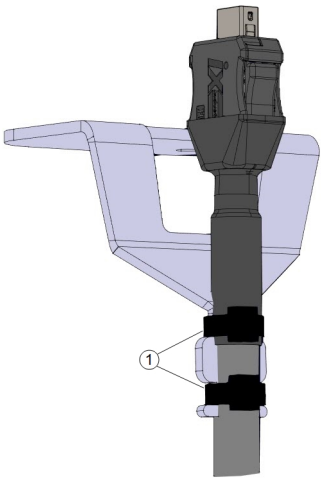
- Always select the correct configuration for the type of Teach Pendant.

To remove the standard Teach Pendant:

1. Power down the control box and disconnect the main power cable from the power source.
2. Remove and discard the two cable ties used for mounting the Teach Pendant cables.
3. Press in the clips on both sides of the Teach Pendant plug as illustrated, and pull down to disconnect from the Teach Pendant port.
4. Fully open/loosen the plastic grommet at the bottom of the control box and remove the Teach Pendant plug and cable.
5. Gently remove the Teach Pendant cable and Teach Pendant.



1	Clips	2	Plastic grommet



1	Cable ties

To install a 3PE Teach Pendant

1. Place the Teach Pendant plug and cable in through the bottom of the control box and fully close/tighten the plastic grommet.
2. Push the Teach Pendant plug into the Teach Pendant port to connect.
3. Use two new cable ties to mount the Teach Pendant cables.
4. Connect the main power cable to the power source and power on the control box.

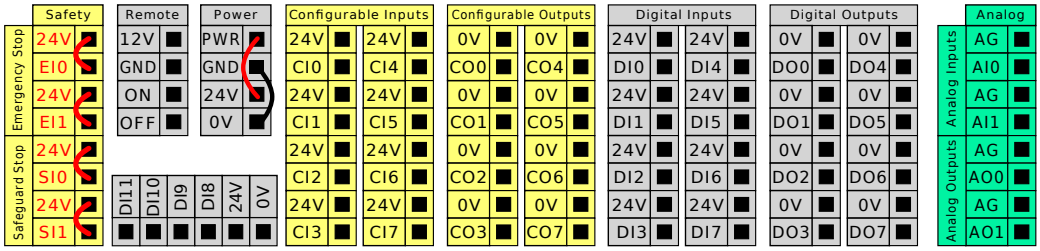
There is always a length of cable with the Teach Pendant that can present a tripping hazard if it is not stored properly.

- Always store the Teach Pendant and the cable properly to avoid tripping hazards.

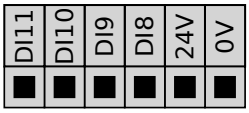
8.5. Controller I/O

Description

You can use the **I/O** inside the Control Box for a wide range of equipment including pneumatic relays, PLCs and emergency stop buttons.
The illustration below shows the layout of electrical interface groups inside the Control Box.



You can use the horizontal Digital Inputs block (DI8-DI11), illustrated below, for quadrature encoding Conveyor Tracking.



The meaning of the color schemes listed below must be observed and maintained.

Yellow with red text	Dedicated safety signals
Yellow with black text	Configurable for safety
Gray with black text	General purpose digital I/O
Green with black text	General purpose analog I/O

In the GUI, you can set up **configurable I/O** as either **safety-related I/O** or **general purpose I/O**.

Common specifications for all digital I/O

This section defines electrical specifications for the following 24V digital I/O of the Control Box.

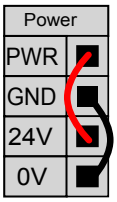
- Safety I/O.
- Configurable I/O.
- General purpose I/O.

> **NOTICE**
> The word **configurable** is used for I/O configured as either safety-related I/O or normal I/O. These are the yellow terminals with black text.

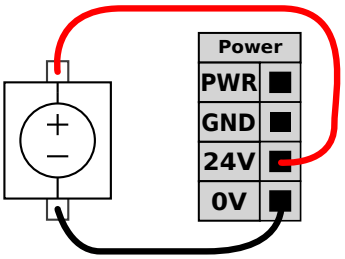
Install the robot according to the electrical specifications which are the same for all three inputs.
It is possible to power the digital I/O from an internal 24V power supply or from an external power source by configuring the terminal block called **Power**. This block consists of four terminals. The upper two (PWR and GND) are 24V and ground from the internal 24V supply. The lower two terminals (24V and 0V) in the block are the 24V input to supply the I/O. The default configuration uses the internal power supply.

Power supply

If more current is needed, connect an external power supply as shown below.



In this example the default configuration using the internal power supply



In this example the default configuration with an external power supply for more current.

The electrical specifications for both the internal and external power supply are shown below.

Terminals	Parameter	Min	Typ	Max	Unit
Internal 24V power supply					
[PWR - GND]	Voltage	23	24	25	V
[PWR - GND]	Current	0	-	2*	A
External 24V input requirements					
[24V - 0V]	Voltage	20	24	29	V
[24V - 0V]	Current	0	-	6	A

*3.5A for 500ms or 33% duty cycle.

Digital I/Os

The digital I/O are constructed in compliance with IEC 61131-2. The electrical specifications are shown below.

Terminals	Parameter	Min	Typ	Max	Unit
Digital Outputs					
[COx / DOx]	Current*	0	-	1	A
[COx / DOx]	Voltage drop	0	-	0.5	V
[COx / DOx]	Leakage current	0	-	0.1	mA
[COx / DOx]	Function	-	PNP	-	Type
[COx / DOx]	IEC 61131-2	-	1A	-	Type
Digital Inputs					
[EIx/SIx/CIx/DIx]	Voltage	-3	-	30	V
[EIx/SIx/CIx/DIx]	OFF region	-3	-	5	V
[EIx/SIx/CIx/DIx]	ON region	11	-	30	V
[EIx/SIx/CIx/DIx]	Current (11-30V)	2	-	15	mA
[EIx/SIx/CIx/DIx]	Function	-	PNP +	-	Type
[EIx/SIx/CIx/DIx]	IEC 61131-2	-	3	-	Type

*For resistive loads or inductive loads of maximum 1H.

8.6. Safety I/O

Safety I/O

This section describes dedicated safety input (Yellow terminal with red text) and configurable I/O (Yellow terminals with black text) when configured as safety I/O.
Safety devices and equipment must be installed according to the safety instructions and the risk assessment in chapter Safety.
All safety I/O are paired (redundant), so a single fault does not cause loss of the safety function. However, the safety I/O must be kept as two separate branches.

The permanent safety input types are:

- **Robot Emergency Stop** for emergency stop equipment only
- **Safeguard Stop** for protective devices
- **3PE Stop** for protective devices

Table

The functional difference is shown below.

	Emergency Stop	Safeguard Stop	3PE Stop
Robot stops moving	Yes	Yes	Yes
Program execution	Pauses	Pauses	Pauses
Drive power	Off	On	On
Reset	Manual	Automatic or manual	Automatic or manual
Frequency of use	Infrequent	Every cycle to infrequent	Every cycle to infrequent
Requires re-initialization	Brake release only	No	No
Stop Category (IEC 60204-1)	1	2	2
Performance level of monitoring function (ISO 13849-1)	PLd	PLd	PLd

Safety caution

Use the configurable I/O to set up additional safety I/O functionality, e.g. Emergency Stop Output. Use the PolyScope interface to define a set of configurable I/O for safety functions.

CAUTION

Failure to verify and test the safety functions regularly can lead to hazardous situations.

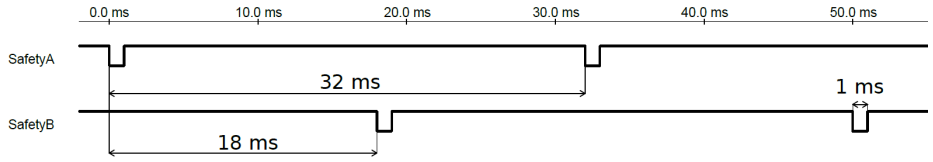
- Safety functions shall be verified before putting the robot into operation.
- Safety functions shall be tested regularly.

OSSD signals

All configured and permanent safety inputs are filtered to allow the use of OSSD safety equipment with pulse lengths under 3ms. The safety input is sampled every millisecond and the state of the input is determined by the most frequently seen input signal over the last 7 milliseconds.

OSSD Safety Signals

You can configure the Control Box to output OSSD pulses when a safety output is inactive/high. OSSD pulses detect the ability of the Control Box to make safety outputs active/low. When OSSD pulses are enabled for an output, a 1ms low pulse is generated on the safety output once every 32ms. The safety system detects when an output is connected to a supply and shuts down the robot.
The illustration below shows: the time between pulses on a channel (32ms), the pulse length (1ms) and the time from a pulse on one channel to a pulse on the other channel (18ms)

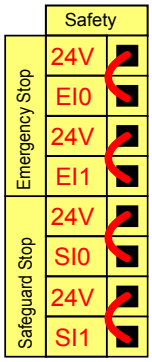


To enable OSSD for Safety Output

1. In the Header, tap **Installation** and select **Safety**.
2. Under **Safety**, select **I/O**.
3. On the I/O screen, under Output Signal, select the desired OSSD checkbox. You must assign the output signal to enable the OSSD checkboxes.

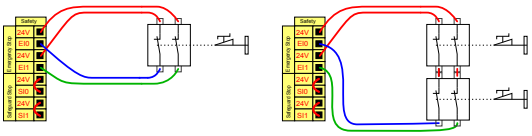
Default safety configuration

The robot is delivered with a default configuration, which enables operation without any additional safety equipment.



Connecting emergency stop buttons

Most applications require one or more extra emergency stop buttons. The illustration below shows how one or more emergency stop buttons can be connected.

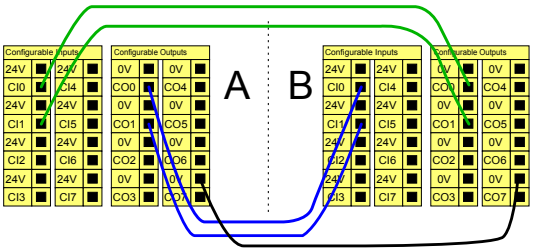


Sharing the Emergency Stop with other machines

You can set up a shared emergency stop function between the robot and other machines by configuring the following I/O functions via the GUI. The Robot Emergency Stop Input cannot be used for sharing purposes. If more than two UR robots or other machines need to be connected, a safety PLC must be used to control the emergency stop signals.

- Configurable input pair: External Emergency Stop.
- Configurable output pair: System Stop.

The illustration below shows how two UR robots share their emergency stop functions. In this example the configured I/Os used are CI0-CI1 and CO0-CO1.

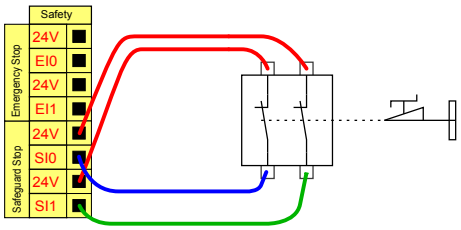


Safeguard stop with automatic resume

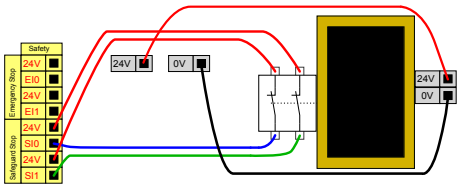
This configuration is only intended for applications where the operator cannot go through the door and close it behind him. The configurable I/O is used to setup a reset button outside the door to reactivate robot motion. The robot resumes movement automatically when the signal is re-established.

WARNING

Do not use this configuration if signal can be re-established from the inside of the safety perimeter.



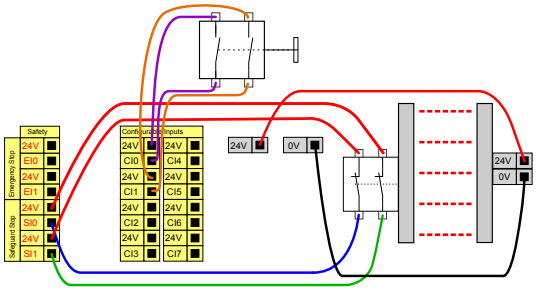
In this example a door switch is a basic safeguard device where the robot is stopped when the door is opened.



In this example a safety mat is a safety device where automatic resume is appropriate. This example is also valid for a safety laser scanner.

Safeguard Stop with reset button

If the safeguard interface is used to interact with a light curtain, a reset outside the safety perimeter is required. The reset button must be a two channel type. In this example the I/O configured for reset is CI0-CI1.



8.6.1. Safety I/O Signals

Description

The I/O are divided between inputs and outputs and are paired up so that each function provides a Category 3 PLd capability.

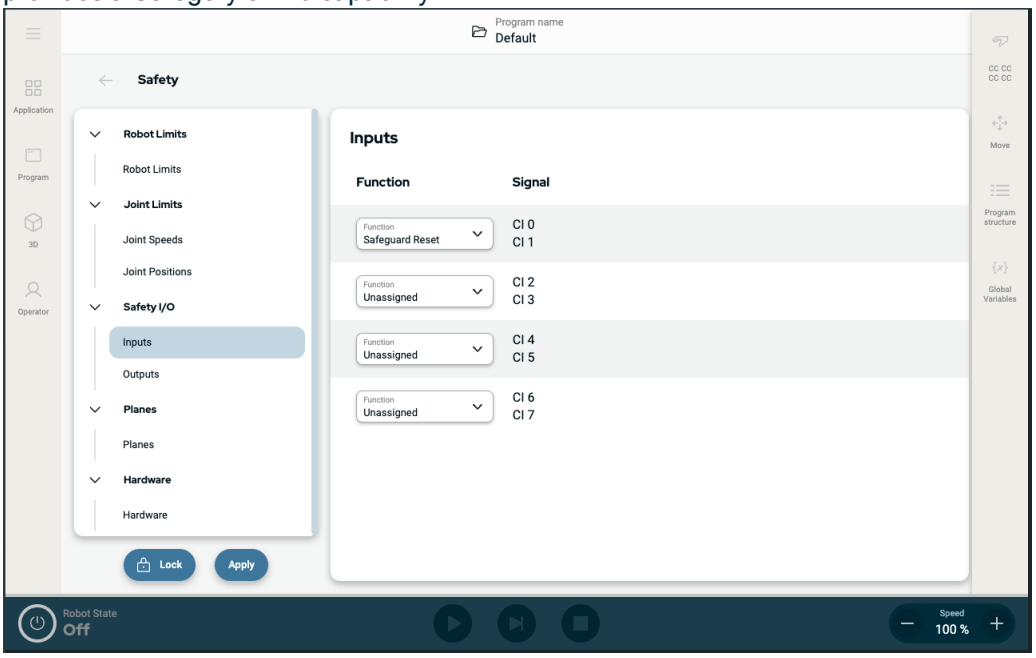
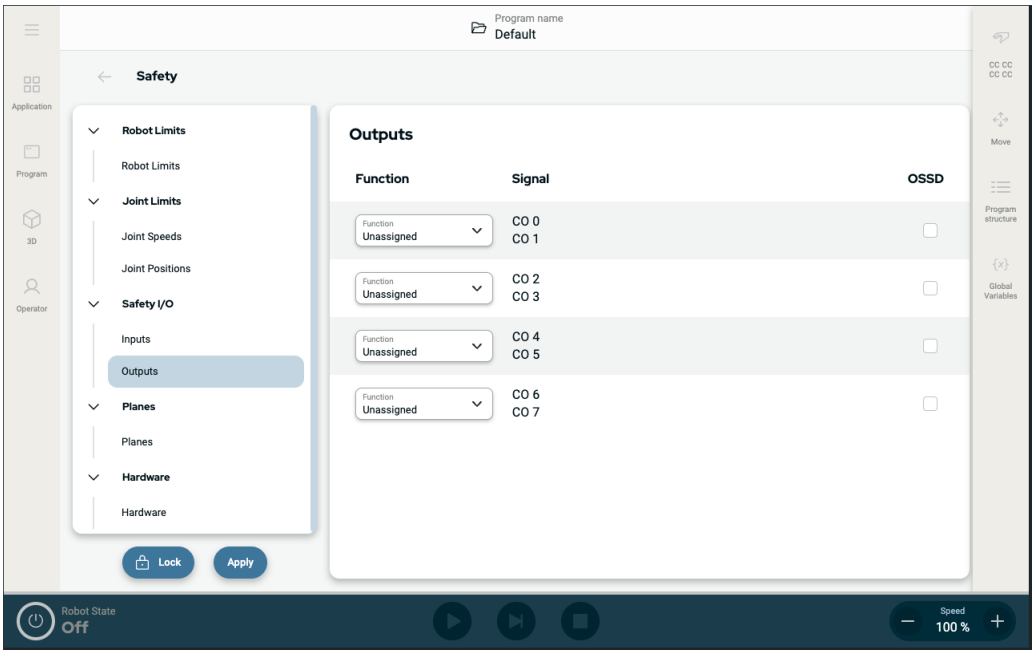


Figure 1.3: *PolyScope X screen displaying the Input signals.*



Input Signals

The inputs are described in the tables below:

Emergency Stop Button	Performs a Stop Category 1 (IEC 60204-1) informing other machines using the System Stop output if that output is defined. A stop is initiated in anything connected to the output.
Robot Emergency Stop	Performs a Stop Category 1 (IEC 60204-1) via Control Box input, informing other machines using the System Emergency Stop Output if that output is defined.
External Emergency Stop	Performs a Stop Category 1 (IEC 60204-1) on robot only.
Reduced	All safety limits can be applied while the robot is using a **Normal** configuration, or a **Reduced** configuration. When configured, a low signal sent to the inputs causes the safety system to transition to the reduced configuration. The robot arm decelerates to satisfy the reduced parameters. The safety system guarantees the robot is within reduced limits less than 0.5s after the input is triggered. If the robot arm continues to violate any of the reduced limits, a Stop Category 0 is triggered. Trigger planes can also cause a transition to the reduced configuration. The safety system transitions to the normal configuration in the same way.

Input Signals

The inputs are described in the table below

Operational Mode	When an external mode selection is used it switches between **Automatic Mode** and **Manual Mode**. The robot is in Automatic mode when input is *low* and Manual mode when the input is *high*.
Safeguard Reset	Returns from the Safeguard Stop state, when a rising edge on the Safeguard Reset input occurs. When a Safeguard Stop occurs, this input ensures that the Safeguard Stop state continues until a reset is triggered.
Safeguard	A stop triggered by a safeguard input. Performs a Stop Category 2 (IEC 60204-1) in all modes, when triggered by a Safeguard.
Automatic Mode Safeguard Stop	Performs a Stop Category 2 (IEC 60204-1) in Automatic mode ONLY. Automatic Mode Safeguard Stop can only be selected when a Three-Position Enabling Device is configured and installed.
Automatic Mode Safeguard Reset	Returns from the Automatic Mode Safeguard Stop state when a rising edge on the Automatic Mode Safeguard Reset input occurs.
Freedrive on robot	You can configure the Freedrive input to enable and use Freedrive without pressing the Freedrive button on a standard TP, or without having to press-and-hold any of the buttons on the 3PE TP in the light-press position.

WARNING

When the default Safeguard Reset is disabled, an automatic reset happens when the safeguard no longer triggers a stop.
This can happen if a person passes though the field of the safeguard.
If a person is not detected by the safeguard and the person is exposed to hazards, automatic reset is forbidden by standards.

- Use the external reset to ensure resetting only when a person is not exposed to hazards.

WARNING

When Automatic Mode Safeguard stop is enabled, a safeguard Stop is not triggered in Manual Mode.

Output Signals

All safety outputs go low in the event of a safety system violation or fault. This means the System Stop output initiates a stop even when an E-stop is not triggered.
You can use the following Safety functions output signals. All signals return to low when the state which triggered the high signal has ended:

[1]System Stop	Signal is *Low* when the safety system has been triggered into a stopped state including by the Robot Emergency Stop input or the Emergency Stop Button. To avoid deadlocks, if the Emergency Stopped state is triggered by the System Stop input, low signal will not be given.
Robot Moving	Signal is *Low* if the robot is moving, otherwise high.
Robot Not Stopping	Signal is *High* when the robot is stopped or in the process of stopping due to an emergency stop or safeguard stop. Otherwise it will be logic low.
Reduced	Signal is *Low* when reduced parameters are active or if the safety input is configured with a reduced input and the signal is currently low. Otherwise the signal is high.
Not Reduced	This is the inverse of Reduced, defined above.
3-Position Enabling Device	In Manual Mode, an external 3-Position Enabling Device must be pressed and held in the center-on position to move the robot. If you are using a built-in 3-Position Enabling Device, the button must be pressed and held in the mid position to move the robot.
Safe Home	Signal is *High* if the robot arm is stopped and is located in the configured Safe Home Position. Otherwise, the signal is *Low*. This is often used when UR robots are integrated with mobile robots.

NOTICE

Any external machinery receiving its Emergency Stop state from the robot through the System Stop output must comply with ISO 13850. This is particularly necessary in setups where the Robot Emergency Stop input is connected to an external Emergency Stop device. In such cases, the System Stop output becomes high when the external Emergency Stop device is released. This implies that the emergency stop state at the external machinery will be reset with no manual action needed from the robot's operator. Hence, to comply with safety standards, the external machinery must require manual action in order to resume.

[1]System Stop was previously known as "System Emergency Stop" for Universal Robots robots. PolyScope can display "System Emergency Stop".

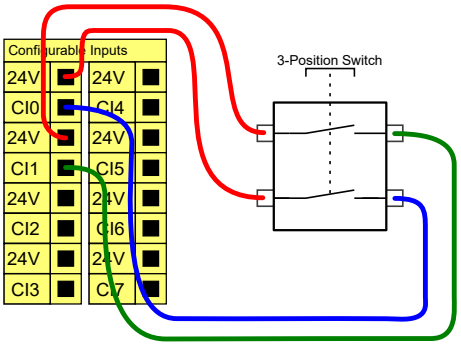
8.7. Three Position Enabling Device

Description

The robot arm is equipped with an enabling device in the form of the 3PE Teach Pendant.
The Control Box supports the following enabling device configurations:

- 3PE Teach Pendant
- External Three-Position Enabling device
- External Three-Position device and 3PE Teach Pendant

The illustration below shows how to connect a Three-Position Enabling device.



Note: The two input channels for the Three-Position Enabling Device input have a disagreement tolerance of 1 second.

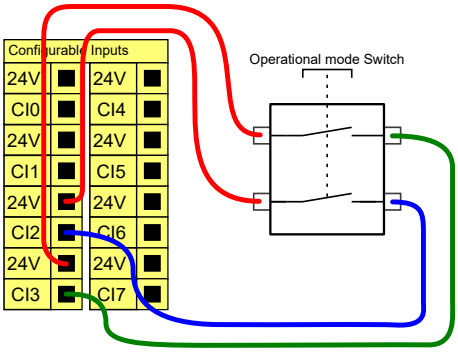
NOTICE

The UR robot safety system does not support multiple external Three-Position Enabling Devices.

Operational Mode Switch

Using a Three-Position Enabling device requires the use of an Operational Mode switch.

The illustration below shows an Operational Mode switch.



8.8. General Purpose Analog I/O

Description

The analog I/O interface is the green terminal. It is used to set or measure voltage (0-10V) or current (4-20mA) to and from other equipment.
The following directions is recommended to achieve the highest accuracy.

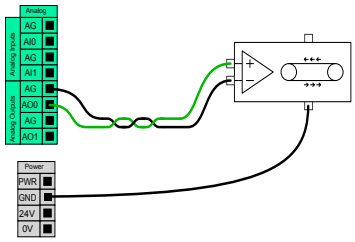
- Use the AG terminal closest to the I/O. The pair share a common mode filter.
- Use the same GND (0V) for equipment and Control Box. The analog I/O is not galvanically isolated from the Control Box.
- Use a shielded cable or twisted pairs. Connect the shield to the GND terminal at the terminal called **Power**.
- Use equipment that works in current mode. Current signals are less sensitive to interferences.

Electrical Specifications

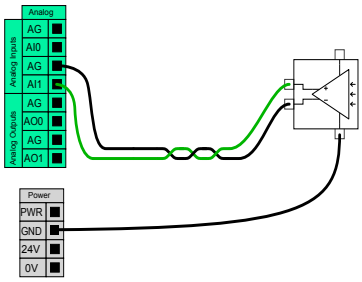
In the GUI you can select input modes. The electrical specifications are shown below.

Terminals	Parameter	Min	Typ	Max	Unit
Analog Input in current mode					
[AIx - AG]	Current	4	-	20	mA
[AIx - AG]	Resistance	-	20	-	ohm
[AIx - AG]	Resolution	-	12	-	bit
Analog Input in voltage mode					
[AIx - AG]	Voltage	0	-	10	V
[AIx - AG]	Resistance	-	10	-	Kohm
[AIx - AG]	Resolution	-	12	-	bit
Analog Output in current mode					
[AOx - AG]	Current	4	-	20	mA
[AOx - AG]	Voltage	0	-	24	V
[AOx - AG]	Resolution	-	12	-	bit
Analog Output in voltage mode					
[AOx - AG]	Voltage	0	-	10	V
[AOx - AG]	Current	-20	-	20	mA
[AOx - AG]	Resistance	-	1	-	ohm
[AOx - AG]	Resolution	-	12	-	bit

Analog Output and Analog Input



This example illustrates controlling a conveyor belt with an analog speed control input.



This example illustrates connecting an analog sensor.

8.8.1. Analog Input: Communication Interface

Description

The Tool Communication Interface (TCI) enables the robot to communicate with an attached tool via the robot tool analog input. This removes the need for external cabling. Once the Tool Communication Interface is enabled, all tool analog inputs are unavailable

Tool Communication Interface

1. Tap the Installation tab and under General tap Tool I/O.
2. Select Communication Interface to edit TCI settings.
   Once the TCI is enabled, the tool analog input is unavailable for the I/O Setup of the Installation and does not appear in the input list. Tool analog input is also unavailable for programs as Wait For options and expressions.
3. In the drop-down menus under Communication Interface, select required values. Any changes in values are immediately sent to the tool. If any installation values differ from what the tool is using, a warning appears.

8.9. General Purpose Digital I/O

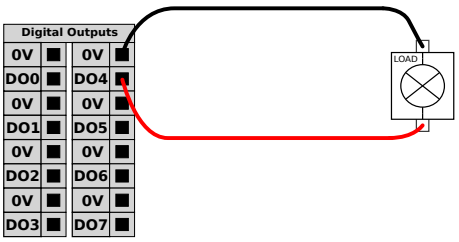
Description

The Startup screen contains settings for automatically loading and starting a default program, and for auto-initializing the Robot arm during power up.

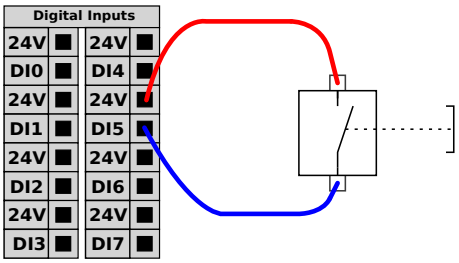
General purpose digital I/O

This section describes the general purpose 24V I/O (Gray terminals) and the configurable I/O (Yellow terminals with black text) when not configured as safety I/O.

The general purpose I/O can be used to drive equipment like pneumatic relays directly or for communication with other PLC systems. All Digital Outputs can be disabled automatically when program execution is stopped.
In this mode, the output is always low when a program is not running. Examples are shown in the following subsections.
These examples use regular Digital Outputs but any configurable outputs could also have be used if they are not configured to perform a safety function.



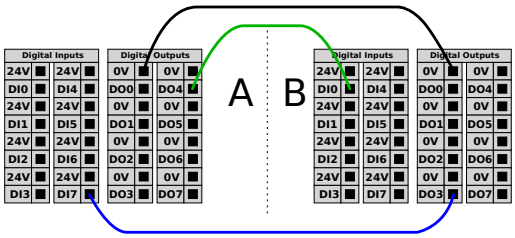
In this example a load is controlled from a Digital Outputs when connected.



In this example a simple button is connected to a Digital Input.

Communication with other machines or PLCs

You can use the digital I/O to communicate with other equipment if a common GND (0V) is established and if the machine uses PNP technology, see below.



8.9.1. Digital Output

Description

The tool communication interface allows two digital outputs to be independently configured. In PolyScope, each pin has a drop-down menu that allows the output mode to be set. The following options are available:

- Sinking: This allows the pin to be configured in an NPN or Sinking configuration. When the output is off, the pin allows a current to flow to the ground. This can be used in conjunction with the PWR pin to create a full circuit.
- Sourcing: This allows the pin to be configured in a PNP or Sourcing configuration. When the output is on, the pin provides a positive voltage source (configurable in the IO Tab). This can be used in conjunction with the GND pin to create a full circuit.
- Push / Pull: This allows the pin to be configured in a Push / Pull configuration. When the output is on, the pin provides a positive voltage source (configurable in IO Tab). This can be used in conjunction with the GND pin to create a full circuit When the output is off, the pin allows a current to flow to the ground.

After selecting a new output configuration, the changes take effect. The currently loaded installation is modified to reflect the new configuration. After verifying the tool outputs are working as intended, make sure to save the installation to prevent losing changes.

Dual Pin Power

Dual Pin Power is used as a source of power for the tool. Enabling Dual Pin Power disables default tool digital outputs.

8.10. End Effector Integration

Description

The end effector can also be referred to as the tool and the workpiece in this manual.

NOTICE

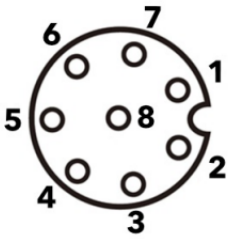
UR provides documentation for the end effector to be integrated with the robot arm.

- Refer to the documentation specific to the end effector/tool/workpiece for mounting and connection.

8.10.1. Tool I/O

Tool Connector

The tool connector illustrated below provides power and control signals for the grippers and sensors used on a specific robot tool. The tool connector has eight holes and is located next to the tool flange on Wrist 3.
The eight wires inside the connector have different functions, as listed in the table:



Pin #	Signal	Description
1	AI3 / RS485-	Analog in 3 or RS485-
2	AI2 / RS485+	Analog in 2 or RS485+
3	TO0/PWR	Digital Outputs 0 or 0V/12V/24V
4	TO1/GND	Digital Outputs 1 or Ground
5	POWER	0V/12V/24V
6	TI0	Digital Inputs 0
7	TI1	Digital Inputs 1
8	GND	Ground

NOTICE

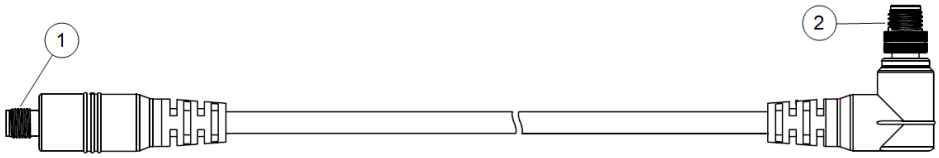
The Tool Connector must be manually tightened up to a maximum of 0.4 Nm.

Tool I/O Accessories

The UR20 tool I/O can require an accessory element to facilitate connection with tools. Depending on the tool, you can use the following tool I/O accessories: Tool Flange Adapter (see Tool Flange Accessories) and/or Tool Cable Adapter.

Tool Cable Adapter

The Tool Cable Adapter is the electronic accessory that allows compatibility between the tool I/O and e-Series tools.



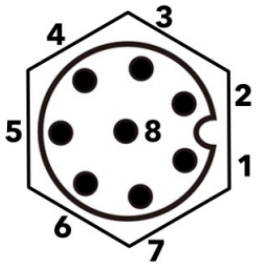
1 Connects to the tool/end effector.
2 Connects to the robot.

WARNING

Connecting the Tool Cable Adapter to a robot that is powered on can lead to injury.

- Connect the adapter to the tool/end effector before connecting the adapter to the robot.
- Do not power on the robot if the Tool Cable Adapter is not connected to the tool/end effector.

The eight wires inside the Tool Cable Adapter have different functions, as listed in the table below:

	Pin #	Signal	Description
	1	AI2 / RS485+	Analog in 2 or RS485+
	2	AI3 / RS485-	Analog in 3 or RS485-
	3	TI1	Digital Inputs 1
	4	TI0	Digital Inputs 0
	5	POWER	0V/12V/24V
	6	TO1/GND	Digital Outputs 1 or Ground
	7	TO0/PWR	Digital Outputs 0 or 0V/12V/24V
	8	GND	Ground

GROUND

The tool flange is connected to GND (Ground).

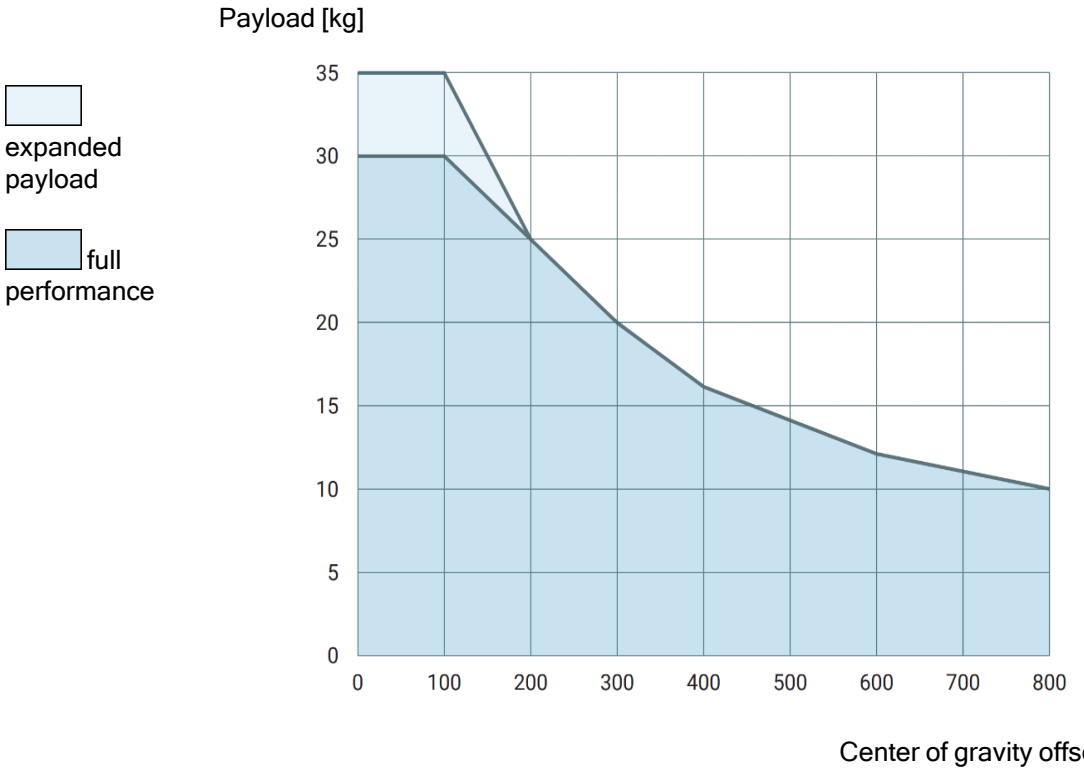
8.10.2. Maximum Payload

Description

The rated robot arm payload depends on the center of gravity (CoG) offset of the payload, as shown below. The CoG offset is defined as the distance from the center of the tool flange to the center of gravity of the attached payload.

The robot arm can accommodate a long center of gravity offset, if the payload is placed below the tool flange. For example when computing the payload mass in a pick and place application, consider both the gripper and the workpiece.

The robot's capacity to accelerate can be reduced if the payload CoG exceeds the robot's reach and payload. You can verify the reach and payload of your robot in the Technical Specifications.

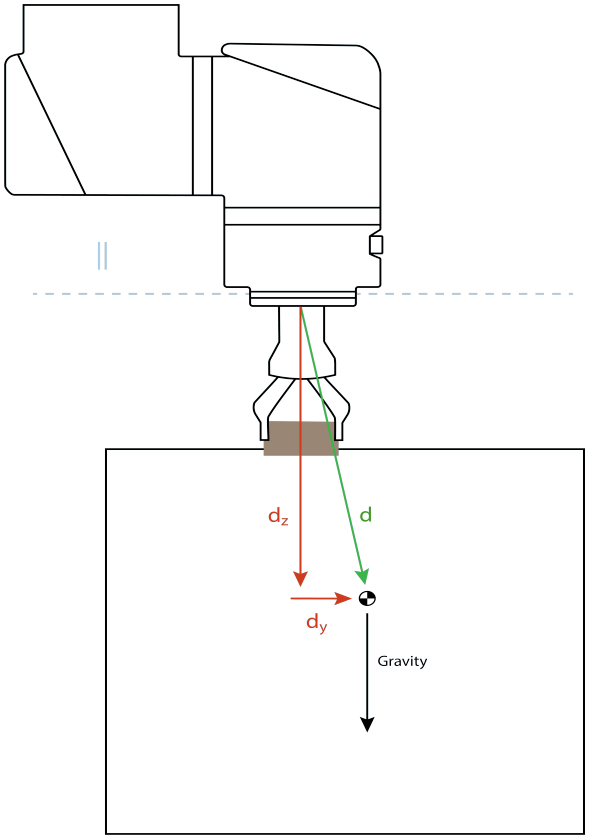


The relationship between the rated payload and the center of gravity offset.

Payload capacity increase

The robot arm can accommodate higher payloads and longer CoG offsets, if the payload is placed below the tool flange. You can increase the maximum payload capacity of the robot arm, under the following criteria:

- Movement with high payload is with tool oriented vertically downward, as is often the case in palletizing applications.
- The payload CoG is within the nominal horizontal reach of the robot.
- The CoG offset in the horizontal XY-plane does not exceed the expanded payload curve (long offsets in the Z-axis, exceeding the payload curve are not an issue).



Example of how to compute the horizontal center of gravity offset.

As illustrated above, the horizontal payload offset $\mathbf{d_y}$ should be within the payload curve.

Expanded payload is possible for any robot mounting orientation.

Increasing the maximum payload capacity can cause the robot to move at reduced speeds and lower acceleration. The higher load on the joints can limit some motions inside the working range of the robot. The robot software automatically ensures the mechanical limits of the robot are not exceeded.

NOTICE

Using the expanded payload range does not void your robot warranty for this robot.

Payload inertia

You can configure high inertia payloads, if the payload is set correctly.
The controller software automatically adjusts accelerations when the following parameters are correclty configured:

- Payload mass
- Center of gravity
- Inertia

You can use the URSim to evaluate the accelerations and cycle times of the robot motions with a specific payload.

8.10.3. Remote ON/OFF control

Description

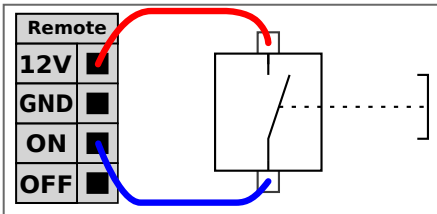
Use remote **ON/OFF** control to turn the Control Box on and off without using the Teach Pendant. It is typically used:

- When the Teach Pendant is inaccessible.
- When a PLC system must have full control.
- When several robots must be turned on or off at the same time.

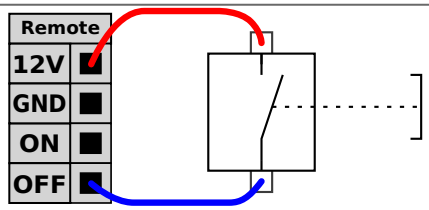
Remote Control

The remote **ON/OFF** control provides a auxiliary 12V supply, kept active when the Control Box is turned off. The **ON** input is intended only for short time activation and works in the same way as the **POWER** button. The **OFF** input can be held down as desired. Use a software feature to load and start programs automatically (see part Part II PolyScope Manual).
The electrical specifications are shown below.

Terminals	Parameter	Min	Typ	Max	Unit
[12V - GND]	Voltage	10	12	13	V
[12V - GND]	Current	-	-	100	mA
[ON / OFF]	Inactive voltage	0	-	0.5	V
[ON / OFF]	Active voltage	5	-	12	V
[ON / OFF]	Input current	-	1	-	mA
[ON]	Activation time	200	-	600	ms



This example illustrates connecting a remote **ON** button.



This example illustrates connecting a remote **OFF** button.

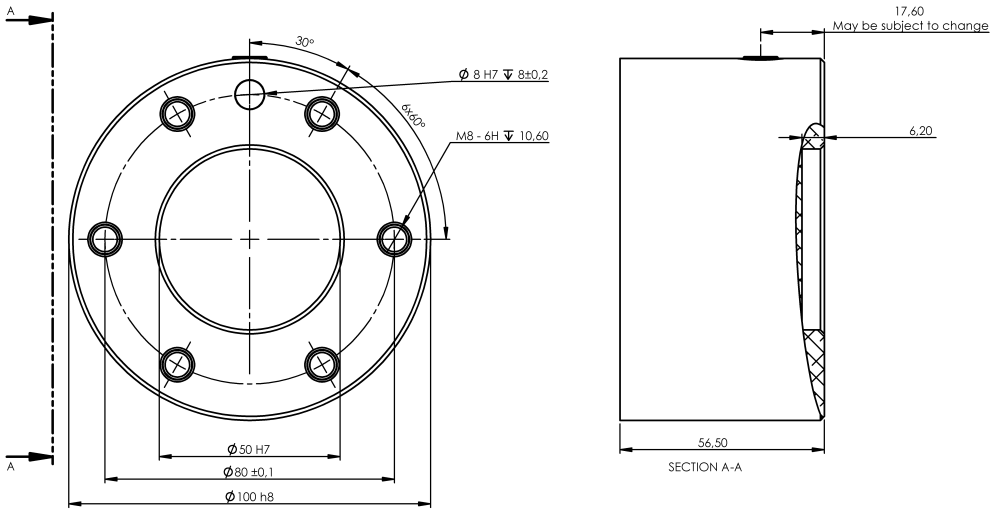
CAUTION

Maintaining a press and hold on the power button switches the Control Box OFF without saving.

- Do not press and hold the **ON** input or the **POWER** button without saving.
- Use the **OFF** input for remote off control to allow the Control Box to save open files and shut down correctly.

8.10.4. Securing Tool

Description The tool or workpiece is mounted to the tool output flange (ISO) at the tip of the robot.



Dimensions and hole pattern of the tool flange. All measurements are in millimeters.

Tool flange The tool output flange (ISO 9409-1) is where the tool is mounted at the tip of the robot. It is recommended to use a radially slotted hole for the positioning pin to avoid over-constraining, while keeping precise position.

CAUTION

Very long M8 bolts can press against the bottom of the tool flange and short circuit the robot.

- Do not use bolts that extend beyond 10 mm to mount the tool.

WARNING

Failure to tighten bolts properly cause injury due to loss of the adapter flange and/or end effector.

- Ensure the tool is properly and securely bolted in place.
- Ensure the tool is constructed such that it cannot create a hazardous situation by dropping a part unexpectedly.

8.10.5. Tool I/O Installation Specifications

Description

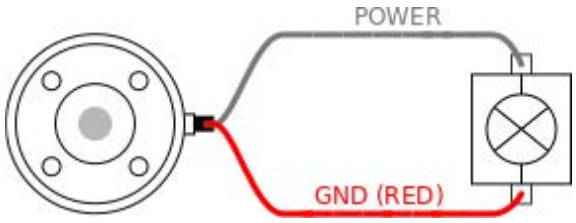
The electrical specifications are shown below. Access Tool I/O in the Installation Tab (see part Part II PolyScope Manual) to set the internal power supply to 0V, 12V or 24V.

Parameter	Min	Typ	Max	Unit
Supply voltage in 24V mode	23.5	24	24.8	V
Supply voltage in 12V mode	11.5	12	12.5	V
Supply current (single pin)*	-	600	2000**	mA
Supply current (dual pin)*	-	600	2000**	mA
Supply capacitive load	-	-	8000***	uF

* It is highly recommended to use a protective diode for inductive loads.
** Peak for max 1 second, duty cycle max: 10%. Average current over 10 seconds must not exceed typical current.
*** When tool power is enabled, a 400 ms soft start time begins allowing a capacitive load of 8000 uF to be connected to the tool power supply at start-up. Hot-plugging the capacitive load is not allowed.

8.10.6. Tool Power Supply

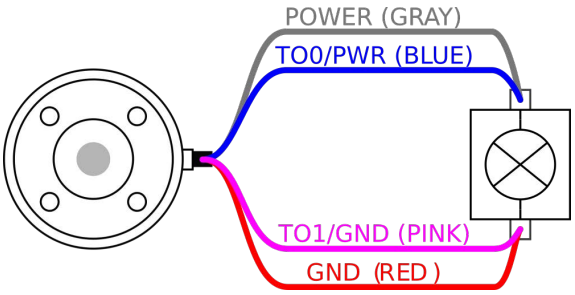
Description Access Tool I/O in the Installation Tab



Dual Pin Power Supply

In Dual Pin Power mode, the output current can be increased as listed in Tool I/O.

1. In the Header, tap **Installation**.
2. In the list on the left, tap **General**.
3. Tap **Tool IO** and select **Dual Pin Power**.
4. Connect the wires Power (gray) to TO0 (blue) and Ground (red) to TO1 (pink).



NOTICE

Once the robot makes an Emergency Stop, the voltage is set to 0V for both Power Pins (power is off).

8.10.7. Tool Digital Outputs

Description

Digital Outputs support three different modes:

Mode	Active	Inactive
Sinking (NPN)	Low	Open
Sourcing (PNP)	High	Open
Push / Pull	High	Low

Access Tool I/O in the Installation Tab to configure the output mode of each pin. The electrical specifications are shown below:

Parameter	Min	Typ	Max	Unit
Voltage when open	-0.5	-	26	V
Voltage when sinking 1A	-	0.08	0.09	V
Current when sourcing/sinking	0	600	1000	mA
Current through GND	0	1000	3000*	mA

NOTICE

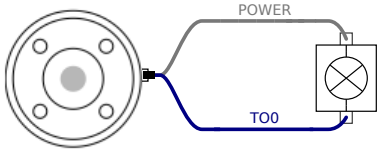
Once the robot makes an Emergency Stop, the Digital Outputs (DO0 and DO1) are deactivated (High Z).

CAUTION

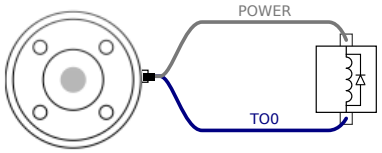
The Digital Outputs in the tool are not current-limited. Overriding the specified data can cause permanent damage.

Using Tool Digital Outputs

This example illustrates turning on a load using the internal 12V or 24V power supply. The output voltage at the I/O tab must be define. There is voltage between the POWER connection and the shield/ground, even when the load is turned off.



It is recommended to use a protective diode for inductive loads, as shown below.



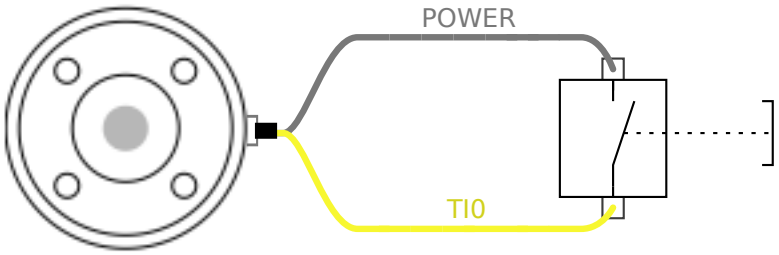
8.10.8. Tool Digital Inputs

Description The Startup screen contains settings for automatically loading and starting a default program, and for auto-initializing the Robot arm during power up.

Table The Digital Inputs are implemented as PNP with weak pull-down resistors. This means that a floating input always reads as low. The electrical specifications are shown below.

Parameter	Min	Type	Max	Unit
Input voltage	-0.5	-	26	V
Logical low voltage	-	-	2.0	V
Logical high voltage	5.5	-	-	V
Input resistance	-	47k	-	Ω

Using the Tool Digital Inputs This example illustrates connecting a simple button.



8.10.9. Tool Analogue Inputs

Description Tool Analogue Input are non-differential and can be set to either voltage (0-10V) or current (4-20mA) on the I/O tab. The electrical specifications are shown below.

Parameter	Min	Type	Max	Unit
Input voltage in voltage mode	-0.5	-	26	V
Input resistance @ range 0V to 10V	-	10.7	-	kΩ
Resolution	-	12	-	bit
Input voltage in current mode	-0.5	-	5.0	V
Input current in current mode	-2.5	-	25	mA
Input resistance @ range 4mA to 20mA	-	182	188	Ω
Resolution	-	12	-	bit

Two examples of using Analog Input are shown in the following subsections.

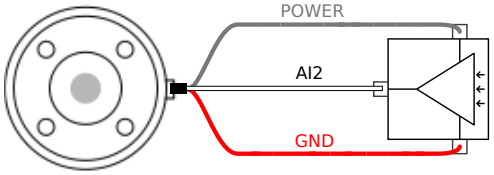
Caution

CAUTION

Analog Inputs are not protected against over voltage in current mode. Exceeding the limit in the electrical specification can cause permanent damage to the input.

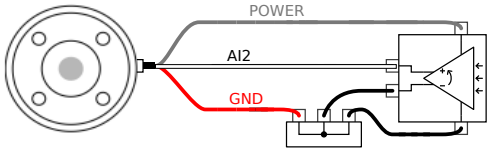
Using Tool Analog Inputs, Non-differential

This example shows an analog sensor connection with a non-differential output. The sensor output can be either current or voltage, as long as the input mode of that Analog Input is set to the same on the I/O tab.
Note: You can check that a sensor with voltage output can drive the internal resistance of the tool, or the measurement might be invalid.



Using Tool Analog Inputs, differential

This example shows an analog sensor connection with a differential output. Connecting the negative output part to GND (0V), works in the same way as a non-differential sensor.



8.10.10. Tool Communication I/O

Description

- **Signal requests** The RS485 signals use internal fail-safe biasing. If the attached device does not support this fail-safe, signal biasing must either be done in the attached tool, or added externally by adding pull-up resistors to RS485+ and pull-down to RS485-.
- **Latency** The latency of messages sent via the tool connector ranges from 2ms to 4ms, from the time the message is written on the PC to the start of the message on the RS485. A buffer stores data sent to the tool connector until the line goes idle. Once 1000 bytes of data have been received, the message is written on the device.

Baud Rates	9.6k, 19.2k, 38.4k, 57.6k, 115.2k, 1M, 2M, 5M
Stop Bits	1, 2
Parity	None, Odd, Even

9. Initialize

On the footer, to the left, the Initialize button indicates the status of the robot using colours:

- Black, Power off. The robot arm is in a stopped state.
- Orange, Idle. The robot arm is on, but not ready for normal operation.
- Green, Normal. The robot arm is on and ready for normal operation.
- Red, Error. The robot is in a fault state, such as e-stop.
- Blue, Transition. The robot is changing state, such as brake releasing.

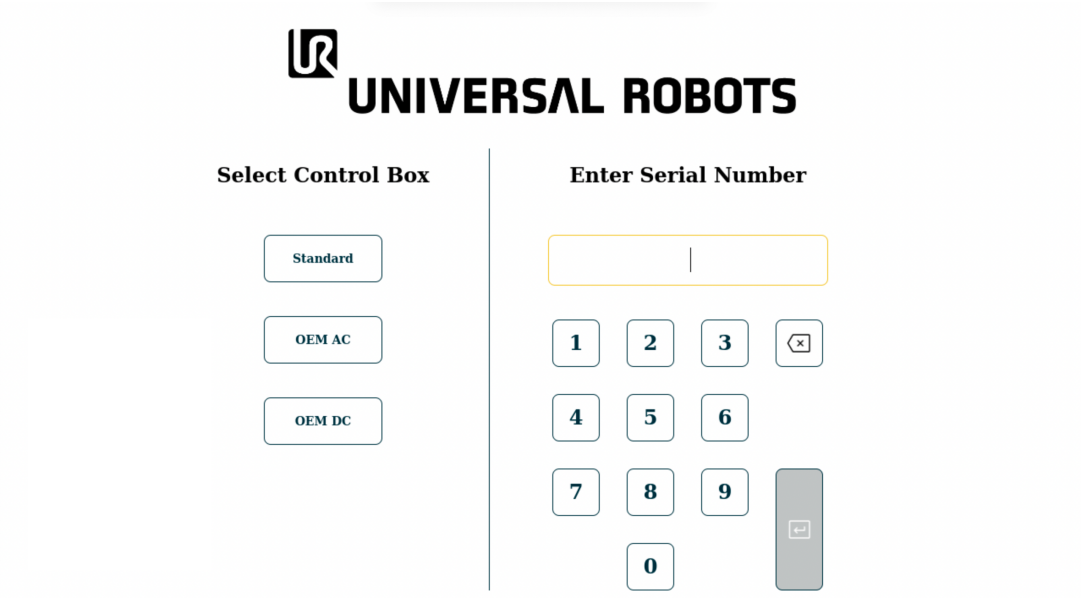
9.1. Insert Serial Number

To insert the serial number

When you install your robot for the first time, you need to configure serial number on the control box to match the robot arm.
This procedure is also required when you re-install the software on the control box, such as when receiving a software update.

When you boot the robot for the first time, please follow these steps:

1. Select the correct robot arm size.
2. Select the correct control box.
3. Add the serial number as it is written on the robot arm.
4. End with the OK button.



9.2. Starting the Robot Arm

WARNING

Always verify the actual payload and installation are correct before starting up the robot arm. If these settings are incorrect, the robot arm and Control Box will not function correctly and may become dangerous to people or equipment.

CAUTION

Ensure the robot arm is not touching an object (e.g., a table) because a collision between the robot arm and an obstacle might damage a joint gearbox.

To start the robot:

- Tap the Robot State Off, followed by the START button with the green icon to start the initialization process. Then, the icon turns orange to indicate the power is on and in Idle.
- Tap the UNLOCK button with the orange icon to release the brakes.
- Tap the POWER OFF button with the red icon to power off the robot arm.

9.3. Safely Setting the Active Payload

Before using Polyscope X, verify that the Robot Arm and Control Box are correctly installed.

1. On the Teach Pendant, press the emergency stop button.
2. On the Teach Pendant, press the power button and allow the system to start, loading Polyscope X.
3. Tap the Robot State Off button on the bottom left
4. Unlock the emergency stop button to change robot state from Emergency Stopped to Power off.
5. Step outside the reach (workspace) of the robot.
6. On the Initialize popup, tap the START button and allow robot state to change to Locked.
7. In the Payload field, in Active Payload, verify the payload mass. You can also verify the mounting position is correct, in the Robot graphic.
8. Tap the UNLOCK button, for the robot to release its brake system. The robot vibrates and makes clicking sounds indicating it is ready to be programmed

10. First Time Use

Description

This section describes how you get started using the robot. Among other things, it covers easy start-up, an overview of the Polyscope user interface and how to set up your first program. Additionally, it covers free drive mode and basic operation.

10.1. Settings

10.1.1. Admin Password

Description

All options under Security are protected by an Admin password. The Admin password protected screens are locked by a transparent overlay rendering the settings unavailable. Accessing the Security allows you to configure the settings in the following:

- Secure Shell
- Permissions
- Services

The settings can only the modified by designated administrator/s.
Unlocking any one of the options under Security, also unlocks the other options until you exit the Settings menu.

To set the Admin password

Before you can use the Admin password to unlock protected screens, you have to change the default password.

1. Access the Hamburger menu and select **Settings**
2. Under Password, tap **Admin**.
3. Change the current Admin password to a new one.
   - If this is the first time, change the default Admin password from "easybot" to a new password. The new password must be at least 8 characters long.
4. Use the new password to unlock the Settings menu and access the options under Security.

To exit the Settings menu

When one of the Security options is unlocked, the Close button in the bottom right of the Settings menu changes. The Close button is replaced by the Lock and Close button indicating security is unlocked.

1. On the Settings menu locate and tap the **Lock and Close** button.

10.1.2. Secure Shell (SSH) Access

Description

You can manage remote access to the robot using Secure shell (SSH). The Secure shell security settings screen allows administrators to enable or disable SSH access to the robot.

To enable/disable SSH

1. Access the Hamburger menu and select **Settings**.
2. Under Security, tap **Secure shell**.
3. Slide the **Enable SSH** Access to the on position.

To the far right of the Enable SSH Access toggle button, the screen shows the port used for SSH communication.

SSH Authentication

Authentication can occur with a password and/or with a pre-shared, authorized key. Security keys can be added by tapping the **Add Key** button and selecting a security key file. Available keys are listed together. Use the trash icon to remove a selected key from the list.

10.1.3. Permissions

Description

Access to the Networking, URCap Management and Updating PolyScope X screens is restricted by default, to prevent unauthorized changes to the system. You can change the permission settings to allow access to these screens. An Admin password is required to access Permissions.

To access Permissions

1. Access the Hamburger menu and select **Settings**.
2. Navigate to Security and tap **Permissions**.

Additional system permissions

You can also lock a few important screens/functionalities with the Admin password. On the Permissions screen in Security section in the Settings menu, it is possible to specify which additional screens are to be protected by the Admin password and which screens are available to all users. The following screens/functionalities can optionally be locked:

- Network settings
- Update settings
- URCaps section in the System Manager

To enable/disable system permissions

1. Access Permission as previously described. The protected screens are listed under Permissions.
2. For the desired screen, slide the On/Off toggle switch to the On position to enable it.
3. To disable the desired screen, slide the On/Off toggle switch to the Off position.

The screen locks again once the toggle is in the Off position.

10.1.4. Services

Description	Services allow administrators to enable or disable remote access to the standard UR services running on the robot, such as Primary/Secondary Client interfaces, PROFINET, Ethernet/IP, ROS2, etc. Use the Service screen to restrict remote access to the robot by only allowing external access to the services on the robot which the specific robot application is actually using. All services are disabled by default to provide maximum security. The communication ports for each service are to right of the On/Off toggle button in the list of services.
Enabling ROS2	When the ROS2 service is enabled on this screen, you can specify the ROS Domain ID (values 0-9). After changing the Domain ID, the system restarts to apply the change.

10.2. Safety Related Functions and Interfaces

Universal Robots robots are equipped with a range of built-in safety functions as well as safety I/O, digital and analog control signals to or from the electrical interface, to connect to other machines and additional protective devices. Each safety function and I/O is constructed according to EN ISO13849-1 with Performance Level d (PLd) using a category 3 architecture.

WARNING

The use of safety configuration parameters different from those determined as necessary for risk reduction, can result in hazards that are not reasonably eliminated, or risks that are not sufficiently reduced.

- Ensure tools and grippers are connected correctly to avoid hazards due to interruption of power.

WARNING: ELECTRICITY

Programmer and/or wiring errors can cause the voltage to change from 12V to 24V leading to fire damage to equipment.

- Verify the use of 12V and proceed with caution.

NOTICE

- The use and configuration of safety functions and interfaces must follow the risk assessment procedures for each robot application.
- The stopping time should be taken into account as part of the application risk assessment
- If the robot detects a fault or violation in the safety system (e.g. if one of the wires in the Emergency Stop circuit is cut or a safety limit is exceeded), then a Stop Category 0 is initiated.

NOTICE

The end effector is not protected by the UR safety system. The functioning of the end effector and/or connection cable is not monitored

10.2.1. Configurable Safety Functions

Universal Robots robot safety functions, as listed in the table below, are in the robot but are meant to control the robot system i.e. the robot with its attached tool/end effector. The robot safety functions are used to reduce robot system risks determined by the risk assessment. Positions and speeds are relative to the base of the robot.

Safety Function	Description
Joint Position Limit	Sets upper and lower limits for the allowed joint positions.
Joint Speed Limit	Sets an upper limit for joint speed.
Safety Planes	Defines planes, in space, that limit robot position. Safety planes limit either the tool/end effector alone or both the tool/end effector and the elbow.
Tool Orientation	Defines allowable orientation limits for the tool.
Speed Limit	Limits maximum robot speed. The speed is limited at the elbow, at the tool/end effector flange, and at the center of the user-defined tool/end effector positions.
Force Limit	Limits maximum force exerted by the robot tool/end effector and elbow in clamping situations. The force is limited at the tool/end effector, elbow flange and center of the user-defined tool/end effector positions.
Momentum Limit	Limits maximum momentum of the robot.
Power Limit	Limits mechanical work performed by the robot.
Stopping Time Limit	Limits maximum time the robot uses for stopping after a robot stop is initiated.[1]
Stopping Distance Limit	Limits maximum distance travelled by the robot after a robot stop is initiated.

[1]Robot stop was previously known as "Protective stop".

10.2.2. Safety Function

When performing the application risk assessment, it is necessary to take into account the motion of the robot after a stop has been initiated. In order to ease this process, the safety functions *Stopping Time Limit* and *Stopping Distance Limit* can be used.

These safety functions dynamically reduces the speed of the robot motion such that it can always be stopped within the limits. The joint position limits, the safety planes and the tool/end effector orientation limits take the expected stopping distance travel into account i.e. the robot motion will slow down before the limit is reached.

10.3. Safety Configuration

NOTICE

Safety Settings are password protected.

1. In the PolyScope X left header, tap the Application icon.
2. On the Workcell screen tap the Safety icon.
3. Observe that the Robot Limits screen displays, but settings are inaccessible.
4. Enter the safety password and tap UNLOCK to make settings accessible. Note: Once Safety settings are unlocked, all settings are now active.
5. Tap LOCK or navigate away from the Safety menu to lock all Safety item settings again.

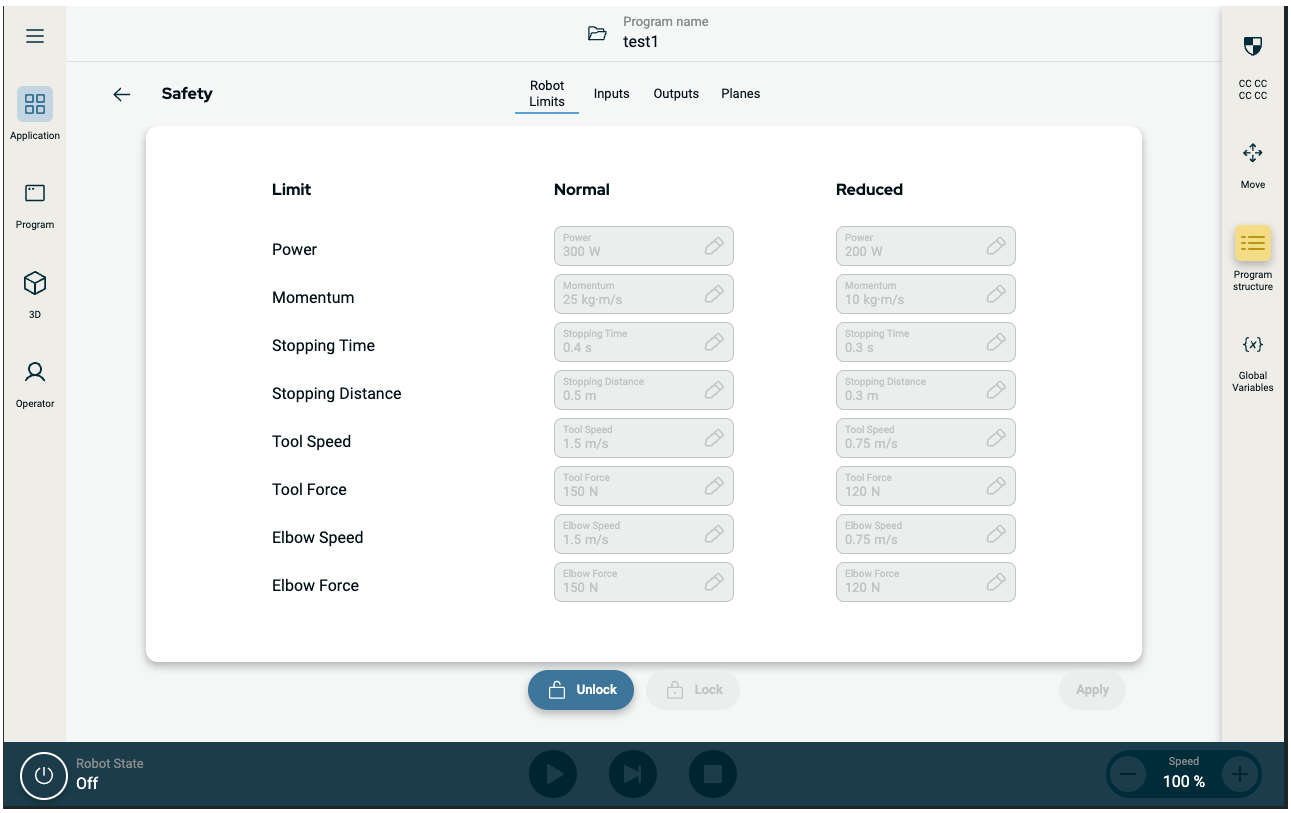
10.4. Setting a Safety Password

1. In your PolyScope X header left corner, tap the Hamburger menu and then tap Settings.
2. On the left of the screen, in the blue menu, tap Safety Password.
3. For Old Password, type the current Safety password.
4. For New Password, type a password.
5. For Repeat Password, type the same password and tap Change Password.
6. In the top right of the menu, press CLOSE to return to previous screen.

10.5. Software Safety Limits

The safety system limits are defined in the Safety Configuration. The safety system receives values from the input fields and detects any violation if any the values are exceeded. The robot controller prevents violations by making a robot stop or by reducing the speed.

10.5.1. Robot Limits



Limit	Description
Power	limits maximum mechanical work produced by the robot in the environment. This limit considers the payload a part of the robot and not of the environment.
Momentum	limits maximum robot momentum.
Stopping Time	limits maximum time it takes the robot to stop e.g. when an emergency stop is activated
Stopping Distance	limits maximum distance the robot tool or elbow can travel while stopping.
Tool Speed	limits maximum robot tool speed.
Tool Force	limits the maximum force exerted by the robot tool in clamping situations
Elbow Speed	limits maximum robot elbow speed
Elbow Force	limits maximum force that the elbow exerts on the environment

NOTICE

Restricting stopping time and distance affect overall robot speed. For example, if stopping time is set to 300 ms, the maximum robot speed is limited allowing the robot to stop within 300 ms.

NOTICE

The tool speed and force are limited at the tool flange and the center of the two user-defined tool positions

Under normal conditions, i.e. when no Robot stop is in effect, the safety system operates in a Safety Mode associated with a set of safety limits [1]:

Safety mode	Effect
Normal	This configuration is active by default.
Reduced	This configuration activates when the Tool Center Point (TCP) is positioned beyond a Trigger Reduced mode plane, or when triggered using a configurable input.

10.5.2. Safety Planes

Safety planes restrict robot workspace, the tool and the elbow.

WARNING

Defining safety planes only limits the defined Tool spheres and elbow, not the overall limit for the robot arm.

Defining safety planes does not guarantee that other parts of the robot arm will obey this type of restriction.

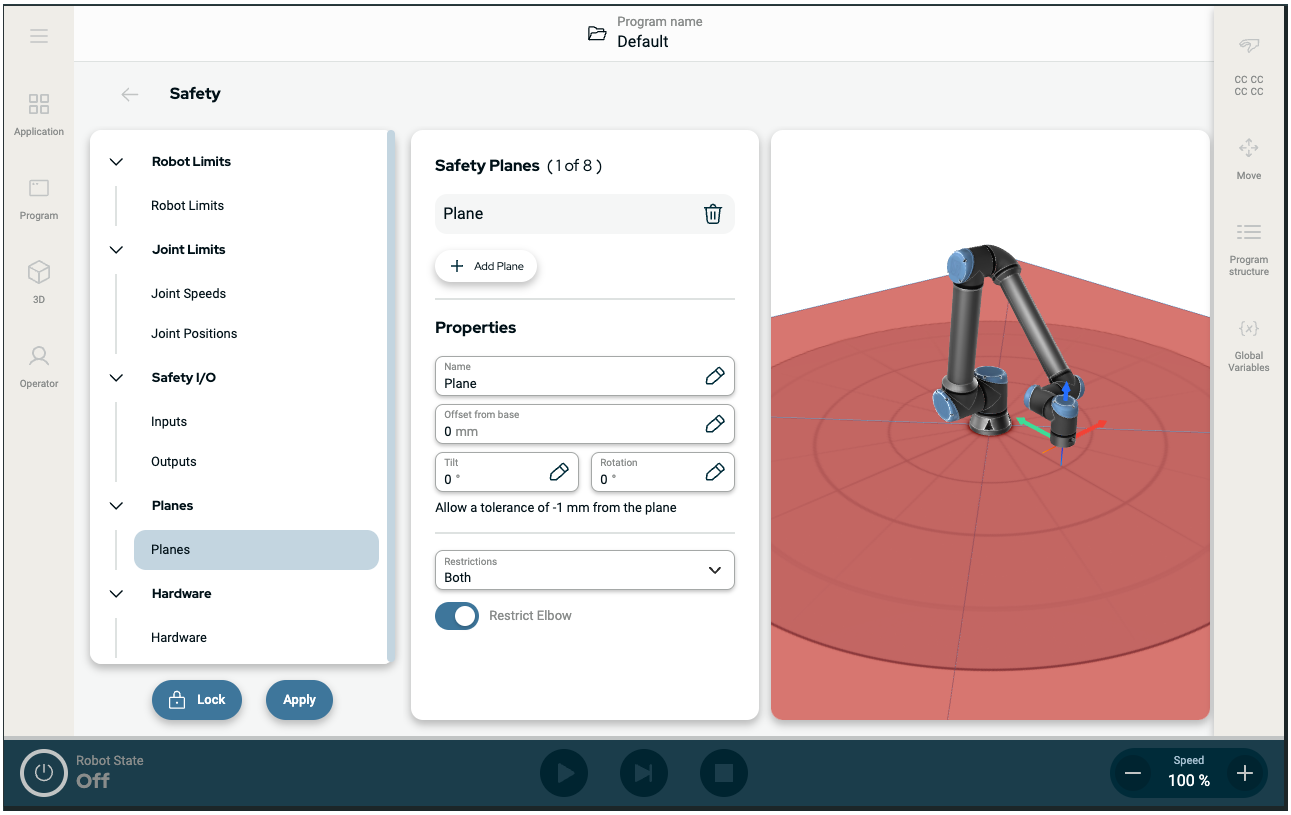


Figure 1.4: *PolyScope X screen displaying safety planes.*

[1] Robot stop was previously known as "Protective stop" for Universal Robots.

- **Disabled**: The safety plane is never active in this state.
- **Normal**: When the safety system is in Normal mode, a normal plane is active and it acts as a strict limit on the position.
- **Reduced**: When the safety system is in Reduced mode, a reduced mode plane is active and it acts as a strict limit on the position.
- **Normal & Reduced**: When the safety system is either in Normal or Reduced mode, a normal and reduced mode plane is active and acts as a strict limit on the position.
- **Trigger Reduced Mode**: The safety plane causes the safety system to switch to Reduced mode if the robot Tool or Elbow is positioned beyond it.

Configuring a safety plane

You can configure safety planes with the properties listed below:

- **Name** This is the name used to identify the safety plane.
- **Offset from base** This is the height of the plane from the base, measured in the -Y direction.
- **Tilt** This is the tilt of the plane, measured from the power cord.
- **Rotation** This is the rotation of the plane, measured clockwise.

You can configure each plane with the restrictions listed below:

- **Normal** When the safety system is in Normal mode, a normal plane is active and it acts as a strict limit on the position.
- **Reduced** When the safety system is in Reduced mode, a reduced mode plane is active and it acts as a strict limit on the position.
- **Both** When the safety system is either in Normal or Reduced mode, a normal and reduced mode plane is active and acts as a strict limit on the position.
- **Trigger Reduced Mode** The safety plane causes the safety system to switch to Reduced mode if the robot Tool or Elbow is positioned beyond it.

Elbow Joint Restriction

You can prevent the robot elbow joint from passing through any of your defined planes.

To restrict the elbow joint

1. Disable Restrict Elbow for elbow to pass through planes.

11. Cybersecurity Threat Assessment

Description

This section provides information to help you strengthen the robot against potential cybersecurity threats. It outlines requirements for addressing cybersecurity threats and provides security hardening guidelines.

11.1. General Cybersecurity

Description

Connecting a Universal Robots robot to a network can introduce cybersecurity risks. These risks can be mitigated by using qualified personnel and implementing specific measures for protecting the robot's cybersecurity.
Implementing cybersecurity measures requires conducting a cybersecurity threat assessment.
The purpose is to:

- Identify threats
- Define trust zones and conduits
- Specify the requirements of each component in the application

WARNING

Failure to conduct a cybersecurity risk assessment can place the robot at risk.

- The integrator or competent, qualified personnel shall conduct a cybersecurity risk assessment.

NOTICE

Only competent, qualified personnel shall be responsible for determining the need for specific cybersecurity measures and for providing the required cybersecurity measures.

11.2. Cybersecurity Requirements

Description

Configuring your network and securing your robot requires you to implement the threat measures for cybersecurity.
Follow all the requirements before you start configure your network, then verify the robot setup is secure.

Cybersecurity

- Operating personnel must have a thorough understanding of general cybersecurity principles and advanced technologies as used in the UR robot.
- Physical security measures must be implemented to allow only authorized personnel physical access to the robot.
- There must be adequate control of all access points. For example: locks on doors, badge systems, physical access control in general.

WARNING

Connecting the robot to a network that is not properly secured, can introduce security and safety risks.

- Only connect your robot to a trusted and properly secured network.

Network configuration requirements

- Only trusted devices are to be connected to the local network.
- There must be no inbound connections from adjacent networks to the robot.
- Outgoing connections from the robot are to be restricted to allow the smallest relevant set of specific ports, protocols and addresses.
- Only URCaps and magic scripts from trusted partners can be used, and only after verifying their authenticity and integrity

Robot setup security requirements

- Change the default password to a new, strong password.
- Disable the "Magic Files" when not actively used (PolyScope 5).
- Disable SSH access when not needed. Prefer key-based authentication over password-based authentication
- Set the robot firewall to the most restrictive usable settings and disable all unused interfaces and services, close ports and restrict IP addresses

11.3. Cybersecurity Hardening Guidelines

Description

Although PolyScope includes many features for keeping the network connection secure, you can harden security by observing to following guidelines:

- Before connecting your robot to any network, always change the default password to a strong password.

  NOTICE
  You cannot retrieve or reset a forgotten or lost password.
  - Store all passwords securely.

- Use the built-in settings to restrict the network access to the robot as much as possible.
- Some communication interfaces have no method of authenticating and encrypting communication. This is a security risk. Consider appropriate mitigating measures, based on your cybersecurity threat assessment.
- SSH tunneling (Local port forwarding) must be used to access robot interfaces from other devices if the connection crosses the trust zone boundary.
- Remove sensitive data from the robot before it is decommissioned. Pay particular attention to the URCaps and data in the program folder.
  - To ensure secure removal of highly sensitive data, securely wipe or destroy the SD card.

12. Communication Networks

Fieldbus

You can use the Fieldbus options to define and configure the family of industrial computer network protocols used for real-time distributed control accepted by PolyScope:

- Ethernet/IP
- PROFINET

12.1. Ethernet/IP

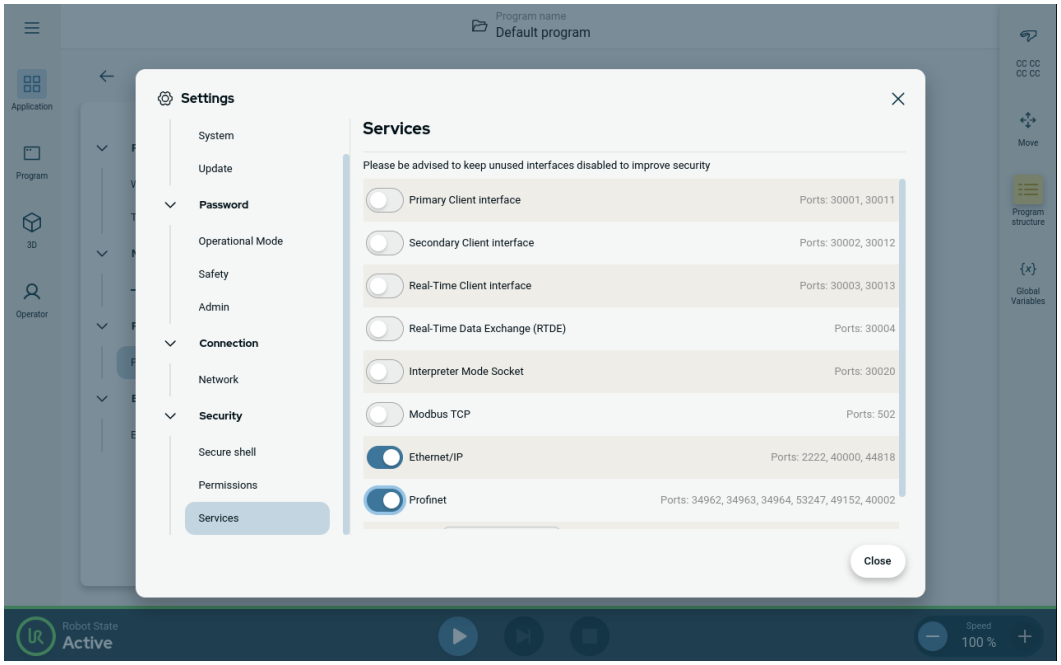
Description

EtherNet/IP is a network protocol that enables the connection of the robot to an industrial EtherNet/IP scanner device. If the connection is enabled, you can select the action that occurs when a program loses EtherNet/IP scanner device connection.

Enable Ethernet/IP

This is how you enable to Ethernet/IP function in PolyScope X.

1. In the top right of the screen, tap the Hamburger menu and then tap Settings.
2. In the menu on the left, under Security, tap Services.
3. Tap the Profinet button to switch Profinet on.



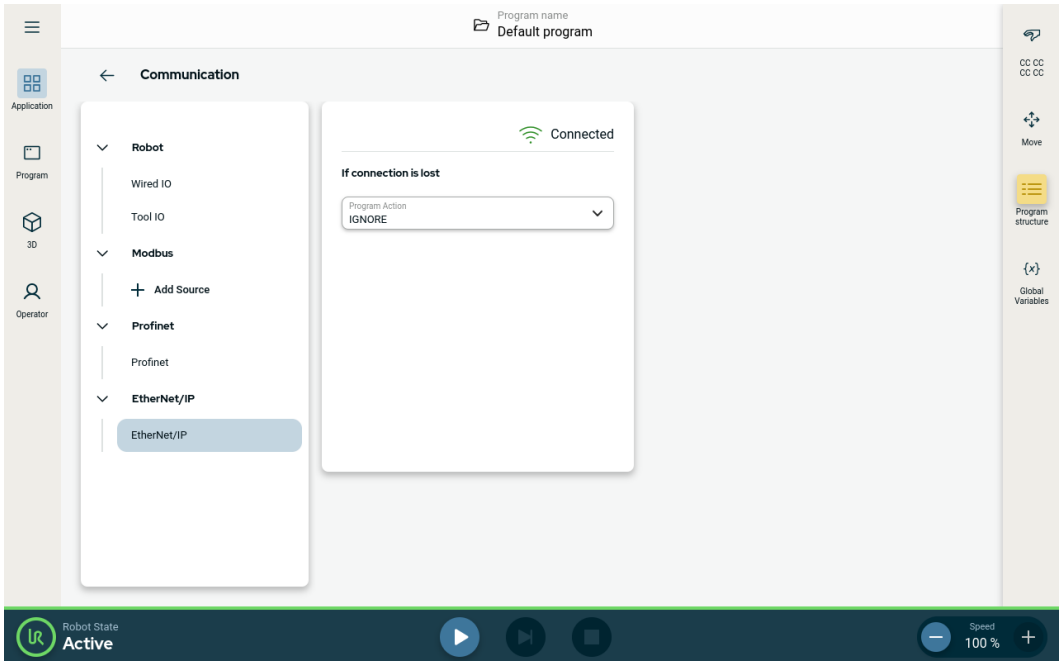
Using Ethernet/IP

Find the Ethernet/IP functions in PolyScope X:

In the PolyScope X left header.

1. Tap the Application icon.
2. Select the relevant action from the list.

Ignore	PolyScope X ignores the loss of EtherNet/IP connection, and the program continues to run.
Pause	PolyScope X pauses the current program. The program resumes from where it stopped.
Stop	PolyScope X stops the current program.



In the upper right corner of this screen, you can see the Ethernet/IP status.

Connected	The robot is connected to the Ethernet/IP Scanner Device.
No Scanner	Ethernet/IP is running, but no device is connected to the robot via Ethernet/IP.
Disabled	Ethernet/IP is not enabled.

12.2. Profinet

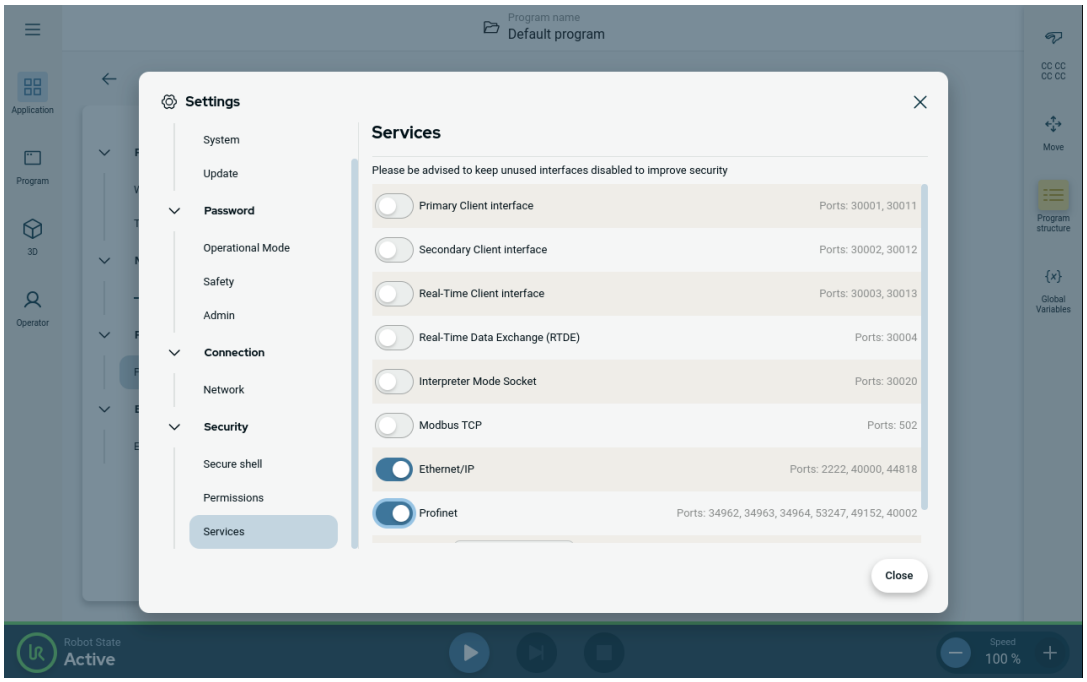
Description

The PROFINET network protocol enables or disables the connection of the robot to an industrial PROFINET IO-Controller. If the connection is enabled, you can select the action that occurs when a program loses PROFINET IO-Controller connection.

Enable Profinet

This is how you enable to Profinet function in PolyScope X.

1. In the top right of the screen, tap the Hamburger menu and then tap Settings.
2. In the menu on the left, under Security, tap Services.
3. Tap the Profinet button to switch Profinet on.



Using Profinet

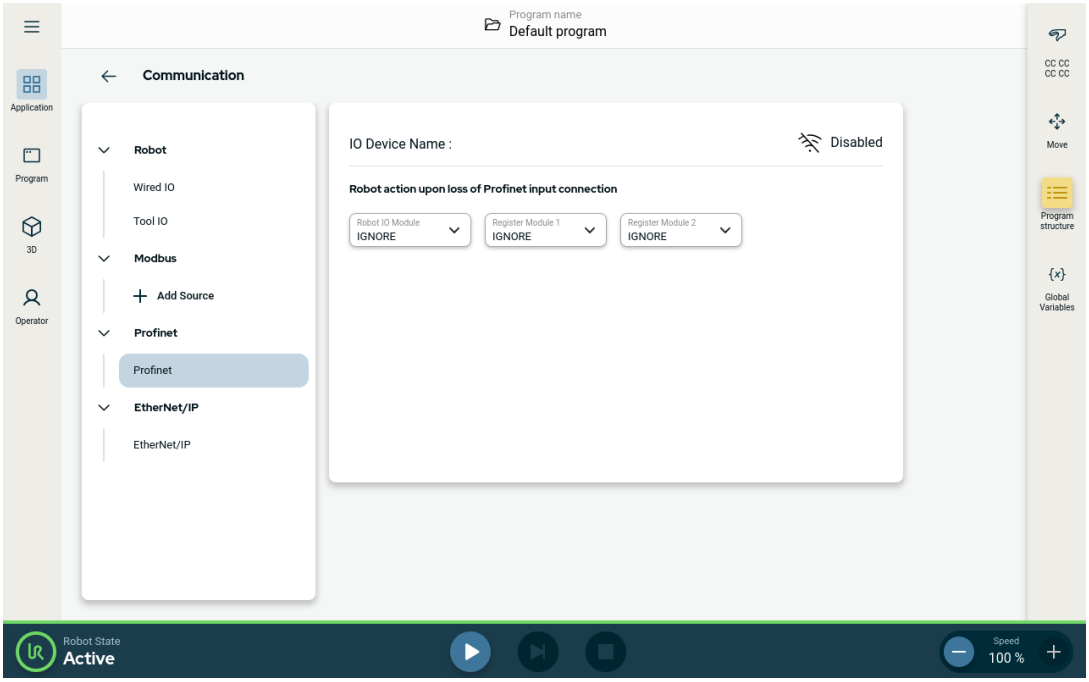
Find the profinet functions in PolyScope X:

In the PolyScope X left header.

1. Tap the Application icon.
2. Select Profinet from the left menu.

Select the relevant action from the list:

Ignore	PolyScope X ignores the loss of Profinet connection, and the program continues to run.
Pause	PolyScope X pauses the current program. The program resumes from where it stopped.
Stop	PolyScope X stops the current program.

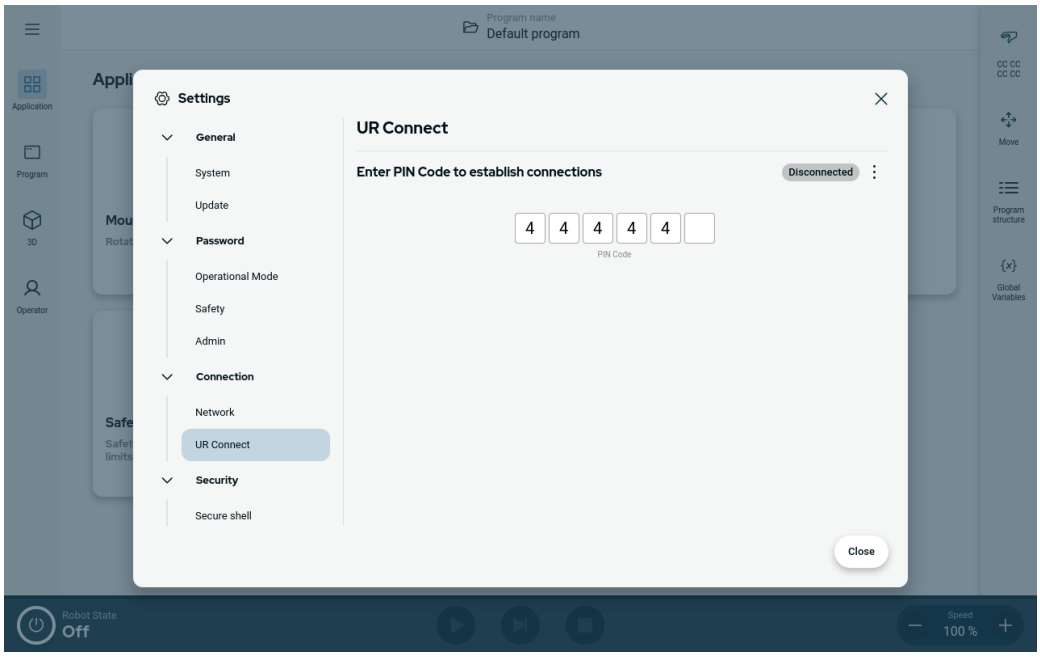


12.3. UR Connect

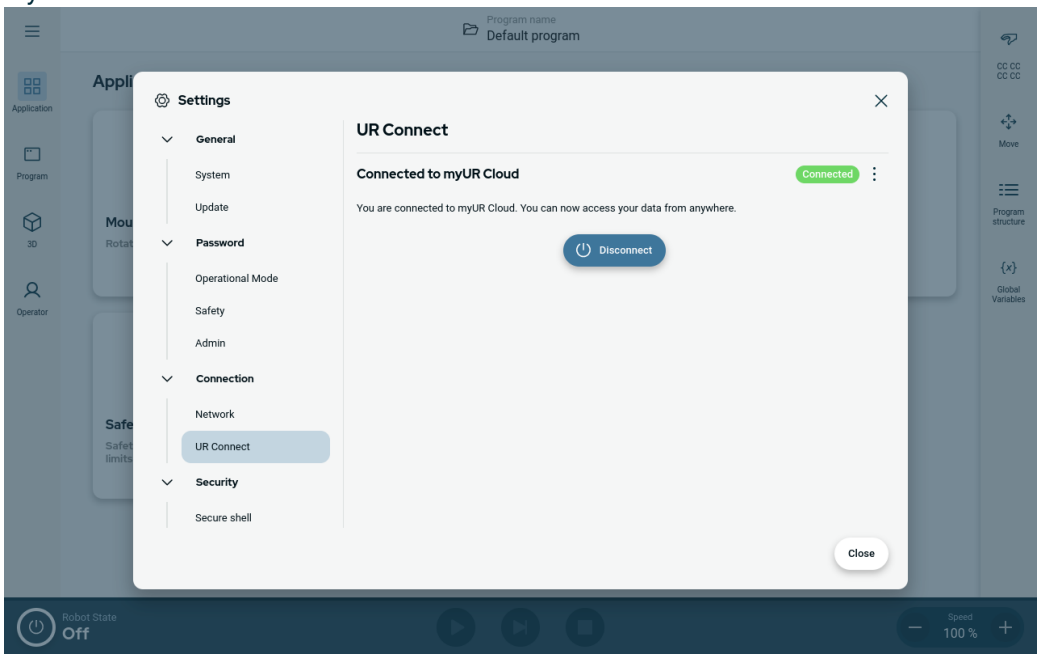
Connect PolyScope X to myUR Cloud

You have to connect your PolyScope X software to the myUR Cloud service. You need to find you PIN code in your myUR account.

1. Go to Settings.
2. Go to UR Connect.
3. Hit the "Connect" button on the main UR Connect page.
4. Add you pin code from myUR.

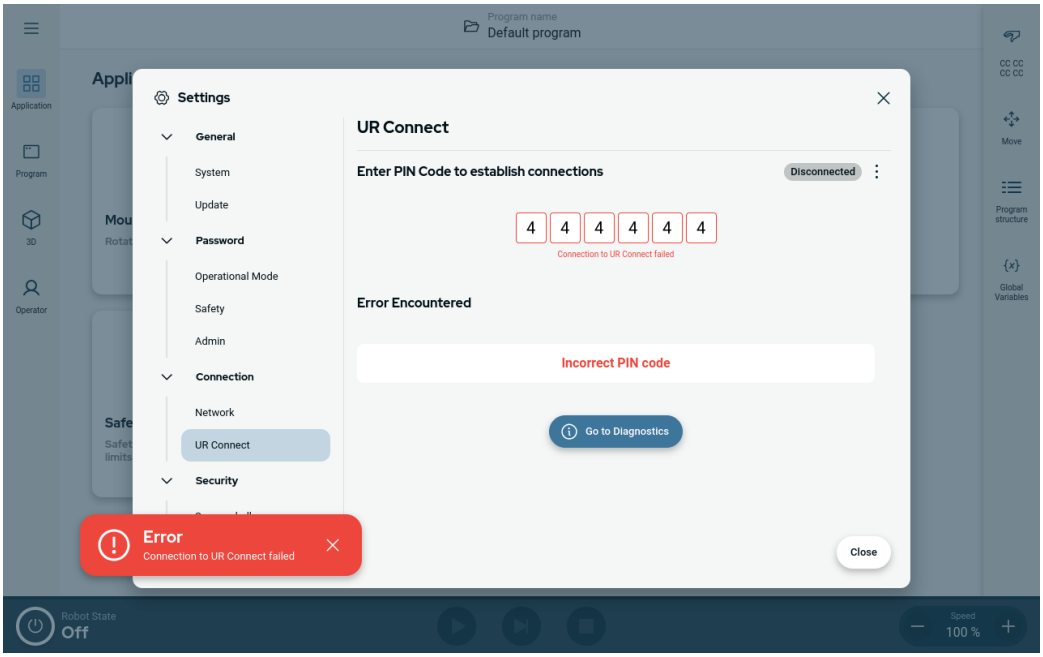


When you see the green icon in the right corner of the window, you are connected to the myUR Cloud.



Unsuccessful connect

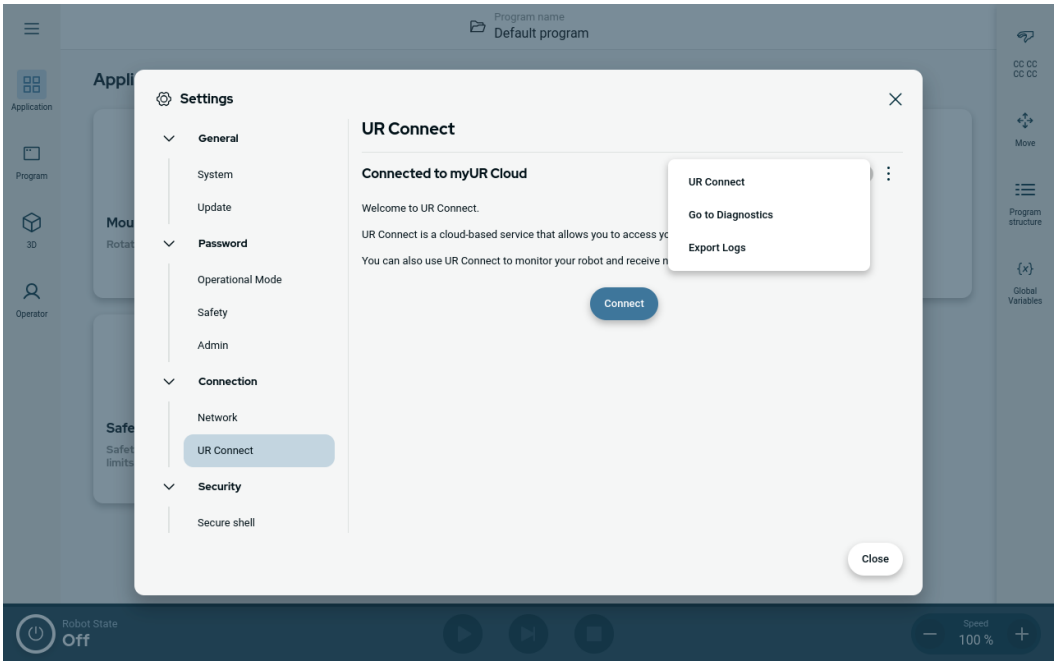
If you see the "Incorrect PIN code", please review your PIN code from myUR.

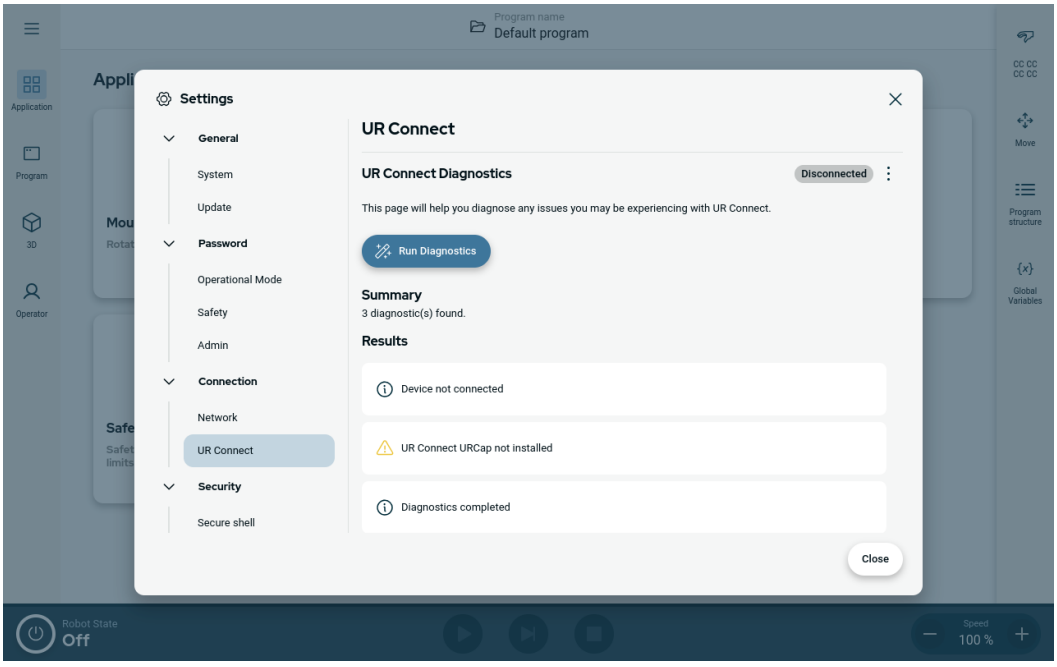


Diagnostics

If you experience any unexpected when the UR Connect is active, you can go to the Diagnostics.

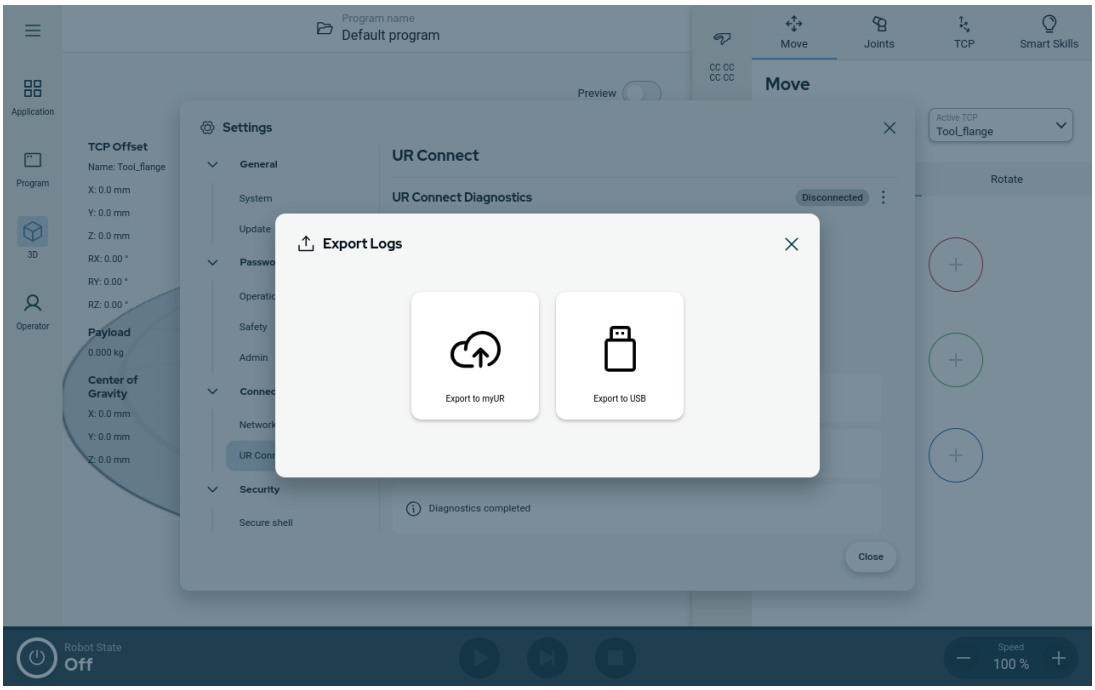
1. Go to Settings.
2. Go to UR Connect.
3. Hit the kebab menu in the top right corner.
4. Select the "Diagnostics".





Export logs It is possible to export the UR Connect logs from your PolyScope X software.

1. Go to Settings.
2. Go to UR Connect.
3. Hit the kebab menu in the top right corner.
4. Select the "Export Logs"
5. Select "Export to myUR" or "Export to USB".



13. Emergency Events

Description

Follow the instructions here to handle emergency situations, such as activating the emergency stop using the red push-button. This section also describes how to manually move the system without power.

13.1. Emergency Stop

Description

The Emergency Stop or E-stop is the red push-button located on the Teach Pendant. Press the emergency stop push-button to stop all robot motion. Activating the emergency stop push-button causes a stop category one (IEC 60204-1).
Emergency stops are not safeguards (ISO 12100).

Emergency stops are complementary protective measures that do not prevent injury. The risk assessment of the robot application determines if additional emergency stop push-buttons are required. The emergency stop function and the actuating device must comply with ISO 13850.
After an emergency stop is actuated, the push-button latches in that setting. As such, each time an emergency stop is activated, it must be manually reset at the push-button that initiated the stop.
Before resetting the emergency stop push-button, you must visually identify and assess the reason the E-stop was first activated. Visual assessment of all the equipment in the application is required. Once the problem is solved, reset the emergency stop push-button.

To reset the emergency stop push-button

1. Hold the push-button and twist clockwise until the latching disengages.

   You should feel when the latching is disengaged, indicating the push-button is reset.
2. Verify the situation and whether to reset the emergency stop.
3. After resetting the emergency stop, restore power to the robot and resume operation.

13.2. Movement Without Drive Power

Description

In the unlikely event of an emergency, when powering the robot is either impossible or unwanted, you can use forced back-driving to move the robot arm.

To perform forced back-driving you must push, or pull, the robot arm hard to move the joint. Each joint brake has a friction clutch that enables movement during high forced torque.

Performing forced back-driving requires high force and cannot be performed by one person alone. In clamping situations, two or more people are required to do the forced back-driving. In some situations, two or more people are required to disassemble the robot arm.

WARNING

Risks due to an unsupported robot arm breaking or falling can cause injury or death.

- Support the robot arm before removing power.

NOTICE

Moving the robot arm manually is intended for emergency and service purposes only. Unnecessary moving of the robot arm can lead to property damage.

- Do not move the joint more than 160 degrees, to ensure the robot can find its original physical position.
- Do not move any joint more than necessary.

13.3. Operational Mode

Description

You access and activate different modes using Teach Pendant or the Dashboard Server. If an external mode selector is integrated, it control the modes - not PolyScope or the Dashboard Server.

Automatic Mode When this mode is activated the robot can only execute a program of pre-defined tasks. You cannot modify or save programs and installations.

Manual Mode When this mode is activated you can program the robot. You can modify and save programs and installations. The speeds used in Manual Mode must be limited to prevent injury. When the robot is operating in Manual Mode, a person could be positioned within reach of the robot. The speed must be limited to the value that is appropriate for the application risk assessment.

WARNING

Injury can occur if the speed used, while the robot is operating in Manual Mode, is too high.

Recovery Mode This mode activates when a safety limit from the active limit set is violated, the robot arm performs a Stop Category 0. If an active safety limit, such as a joint position limit or a safety boundary, is violated already when the robot arm is powered on, it starts up in Recovery mode. This makes it possible to move the robot arm back within the safety limits. In Recovery mode, the movement of the robot arm is restricted by a fixed limit that you cannot customize.

The robot performs a Safeguard Stop in Manual mode, if a Three-Position Enabling Device is configured, and either released (not pressed) or it is fully compressed.

Switching between Automatic mode to Manual mode requires the Three-Position Enabling Device to be fully released and pressed again to allow the robot to move.

Mode switching

Operational Mode	Manual	Automatic
Speed Slider	x	x
Move robot with +/- on Move Tab	x	
Freedrive	x	
Execute Programs	Reduced speed***	x
Edit & save program	x	

*** When tool power is enabled, a 400 ms soft start time begins allowing a capacitive load of 8000 uF to be connected to the tool power supply at start-up. Hot-plugging the capacitive load is not allowed.

WARNING

- Any suspended safeguards must be returned to full functionality before selecting Automatic Mode.
- Wherever possible, Manual Mode shall only be used with all persons located outside the safeguarded space.
- If an external mode selector is used, it must be placed outside the safeguarded space.
- No-one is to enter, or be within, the safeguarded space in Automatic Mode, unless safeguarding is used or the collaborative application is validated for power and force limiting (PFL).

Three-Position Enabling Device

When a Three-Position Enabling Device is used and the robot is in Manual Mode, movement requires pressing the Three-Position Enabling Device to the center-on position. The Three-Position Enabling Device has no effect in Automatic Mode.

NOTICE

- Some UR robot sizes might not be equipped with a Three-Position Enabling Device. If the risk assessment requires the enabling device, a 3PE Teach Pendant must be used.

A 3PE Teach Pendant (3PE TP) is recommended for programming. If another person can be within the safeguarded space when in Manual Mode, an additional device can be integrated and configured for the additional person's use.

Switching Modes

To switch between modes, in the Right Header, select the profile icon to display the Mode Section.

- Automatic indicates the operational mode of the robot is set to Automatic.
- Manual indicates the operational mode of the robot is set to Manual.

PolyScope X is automatically in Manual Mode when the Safety I/O configuration with Three-Position Enabling Device is enabled.

14. Transportation

Description

Only transport the robot in its original packaging. Save the packaging material in a dry place if you want to move the robot later.
When moving the robot from its packaging to the installation space, hold both tubes of the robot arm at the same time. Hold the robot in place until all mounting bolts are securely tightened at the base of the robot.
Lift the Control Box by its handle.

WARNING

Incorrect lifting techniques, or using improper lifting equipment, can lead to injury.

- Avoid overloading your back or other body parts when lifting the equipment.
- Use proper lifting equipment.
- All regional and national lifting guidelines shall be followed.
- Make sure to mount the robot according to the instructions in Mechanical Interface.

NOTICE

If the robot is attached to 3rd-party application / installation during transport, please refer to the following:

- Transporting the robot without its original packaging will void all warranties from Universal Robots A/S.
- If the robot is transported attached to a 3rd-party application / installation, follow the recommendations for transporting the robot without the original transport packaging.

Disclaimer

Universal Robots cannot be held responsible for any damage caused by transportation of the equipment.
You can see the recommendations for transportation without packaging at: universal-robots.com/manuals

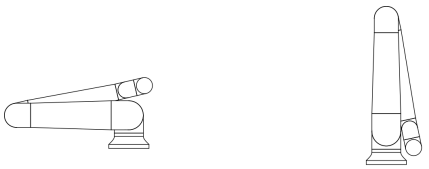
Description

Universal Robots always recommends transporting the robot in its original packaging. These recommendations are written to reduce unwanted vibrations in joints and brake systems and reduce joint rotation.
If the robot is transported without its original packaging, then please refer to the following guidelines:

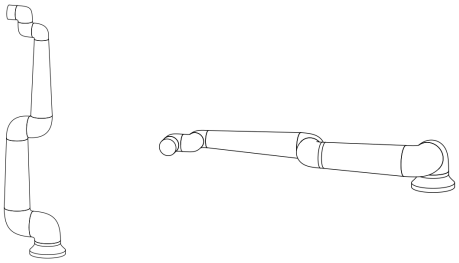
- Fold the robot as much as possible - do not transport the robot in the singularity position.
- Move the center of gravity in the robot as close to the base as possible.
- Secure each tube to a solid surface on two different points on the tube.
- Secure any attached end effector rigidly in 3 axes.

Transport

Fold the robot as much as possible.



Do not transport extended.
(singularity position)



Secure the tubes to a solid surface.
Secure attached end effector in 3 axes.

14.1. Teach Pendant Storage

Description

The operator needs to have a clear understanding about what the e-Stop on the Teach Pendant affects when pressed. For example there can be confusion with a multi-robot installation. It should be made clear if the e-Stop on the Teach Pendant stops the whole installation or only its connected robot.
If there could be confusion, store the Teach Pendant such that the e-Stop button is not visible or usable.

15. Maintenance and Repair

Description

Any maintenance work, inspection and calibration shall be conducted in compliance with all safety instructions in this manual and according to local requirements.
Repair work shall be done by Universal Robots. Client designated, trained individuals can do repair work, provided they follow the Service Manual.

Safety for Maintenance

After maintenance and repair work, checks must be done to ensure the required safety level. Checks must adhere to valid national or regional work safety regulations. The correct functioning of all safety functions shall also be tested.
The purpose of maintenance and repair work is to ensure that the system is kept operational or, in the event of a fault, to return the system to an operational state. Repair work includes troubleshooting in addition to the actual repair itself.
When working on the robot arm or control box, you must observe the procedures and warnings below.

WARNING

Failure to adhere to any of the safety practices, listed below, can result in injury.

- Unplug the main power cable from the bottom of the Control Box to ensure that it is completely unpowered. Power off any other source of energy connected to the robot arm or Control Box. Take necessary precautions to prevent other persons from powering on the system during the repair period.
- Check the earth connection before re-powering the system.
- Observe ESD regulations when parts of the robot arm or Control Box are disassembled.
- Prevent water and dust from entering the robot arm or Control Box.

WARNING: ELECTRICITY

Disassembling the Control Box power supply too quickly after switching off, can result in injury due to electrical hazards.

- Avoid disassembling the power supply inside the Control Box, as high voltages (up to 600 V) can be present inside these power supplies for several hours after the Control Box has been switched off.

15.1. Testing Stopping Performance

Description

Test periodically to determine if stopping performance is degraded. Increased stopping times can require safeguarding to be modified, possibly with changes to the installation. If stop time and/or stop distance safety functions are used and are the basis of the risk reduction strategy, no monitoring or testing of stopping performance is required. The robot does continuous monitoring.

15.2. Robot Arm Cleaning and Inspection

Description

As part of regular maintenance the robot arm can be cleaned, in accordance with the recommendations in this manual and local requirements.

Cleaning Methods

To address the dust, dirt, or oil on the robot arm and/or Teach Pendant, simply use a cloth alongside one of the cleaning agents provided below.

Surface Preparation: Before applying the below solutions, surfaces may need to be prepared by removing any loose dirt or debris.

Cleaning agents:

- Water
- 70% Isopropyl alcohol
- 10% Ethanol alcohol
- 10% Naphtha (Use to remove grease.)

Application: The solution is typically applied to the surface that needs cleaning using a spray bottle, brush, sponge, or cloth. It can be applied directly or diluted further depending on the level of contamination and the type of surface being cleaned.
Agitation: For stubborn stains or heavily soiled areas, the solution may be agitated using a brush, scrubber, or other mechanical means to help loosen the contaminants.
Dwell Time: If necessary, the solution is allowed to dwell on the surface for a up to 5 minutes to penetrate and dissolve the contaminants effectively.
Rinsing: After the dwell time, the surface is typically rinsed thoroughly with water to remove the dissolved contaminants and any remaining cleaning agent residue. It's essential to ensure thorough rinsing to prevent any residue from causing damage or posing a safety hazard.
Drying: Finally, the cleaned surface may be left to air dry or dried using towels.

WARNING

DO NOT USE BLEACH in any diluted cleaning solution.

WARNING

Grease is an irritant and can cause an allergic reaction. Contact, inhalation or ingestion can cause illness or injury. To prevent illness or injury, adhere to the following:

- PREPARATION:
  - Ensure that the area is well ventilated.
  - Have no food or beverages around the robot and cleaning agents.
  - Ensure that an eye wash station is nearby.
  - Gather the required PPE (gloves, eye protection)
- WEAR :
  - Protective gloves: Oil resistant gloves (Nitrile) impermeable and resistant to product.
  - Eye protection is recommended to prevent accidental contact of grease with eyes.
- DO NOT INGEST.
- In the event of
  - contact with skin, wash with water and a mild cleaning agent
  - a skin reaction, get medical attention
  - contact with the eyes, use an eyewash station, get medical attention.
  - inhalation of vapors or ingestion of grease, get medical attention
- After grease work
  - clean contaminated work surfaces.
  - dispose responsibly of any used rags or paper used for cleaning.
- Contact with children and animals is prohibited.

Robot Arm Inspection Plan

The table below is a checklist of the type of inspections recommended by Universal Robots. Perform inspections regularly as advised in the table. Any referenced parts found to be in an unacceptable state must be rectified or replaced.

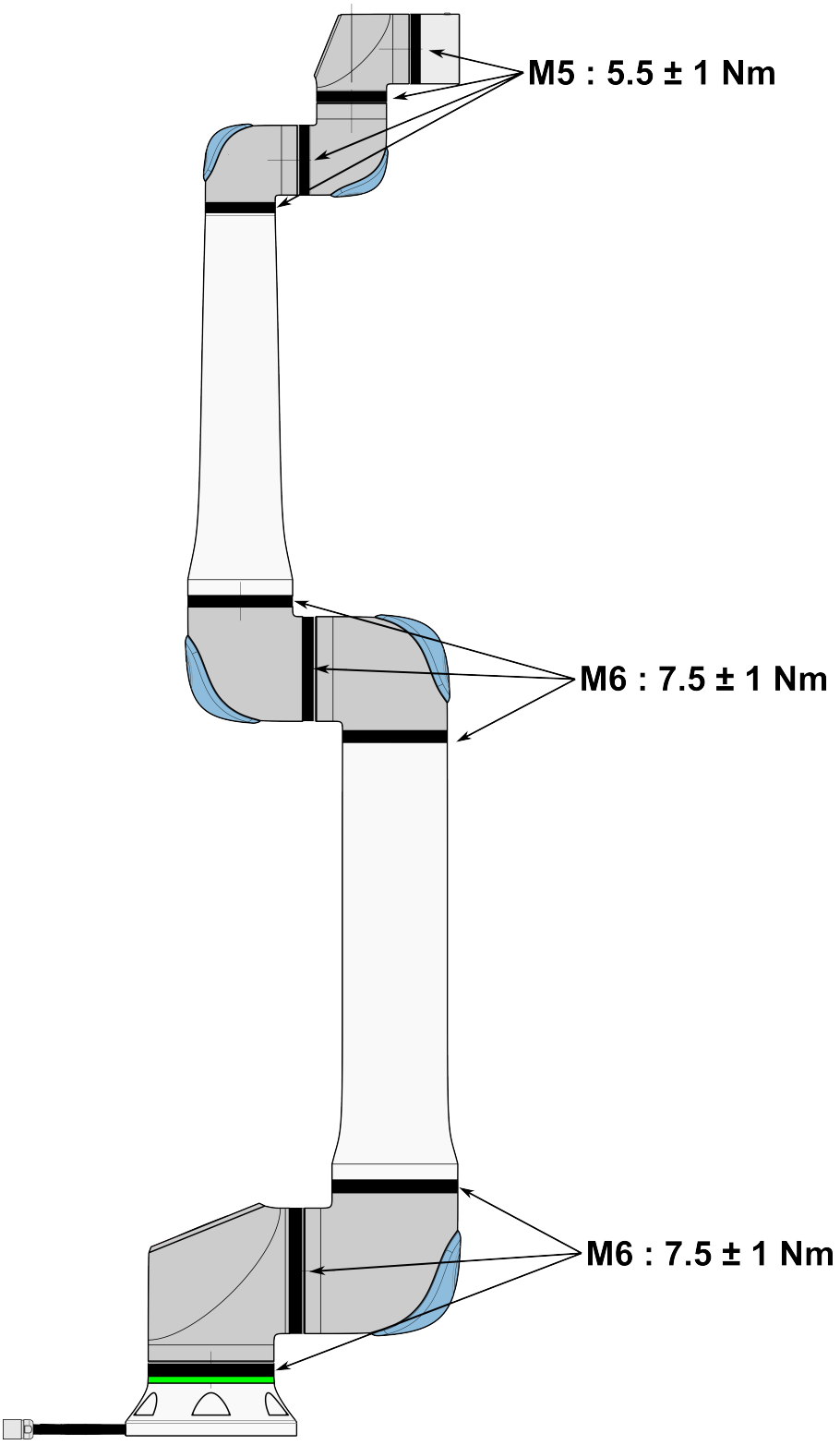
Inspection action type			Timeframe		
			Monthly	Biannually	Annually
1	Check flat rings	V		✗	
2	Check robot cable	V		✗	
3	Check robot cable connection	V		✗	
4	Check Robot Arm mounting bolts *	F	✗		
5	Check Tool mounting bolts *	F	✗		
6	Round Sling	F			✗

Robot Arm Inspection Plan

NOTICE

Using compressed air to clean the robot arm can damage the robot arm components.

- Never use compressed air to clean the robot arm.



Robot Arm Inspection Plan

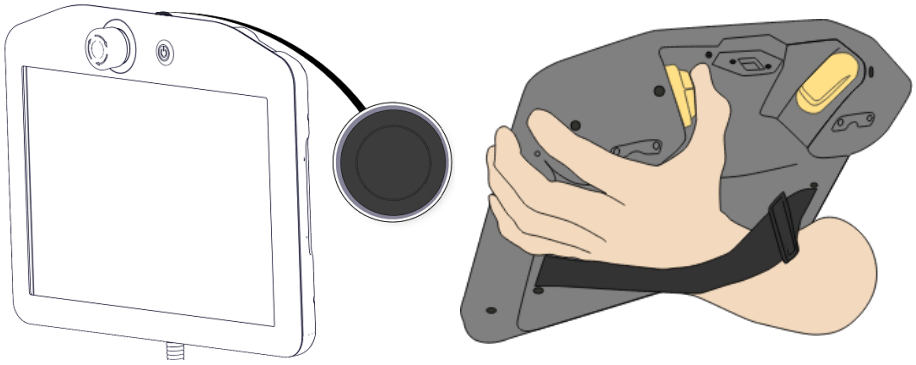
1. Move the Robot Arm to ZERO position, if possible.
2. Turn off and disconnect the power cable from Control Box.
3. Inspect the cable between Control Box and Robot Arm for any damage.
4. Check the base mounting bolts are properly tightened.
5. Check the tool flange bolts are properly tightened.
6. Inspect the flat rings for wear and damage.
   - Replace the flat rings if they are worn out or damaged.

NOTICE

If any damage is observed on a robot within the warranty period, contact the distributor where the robot was purchased.

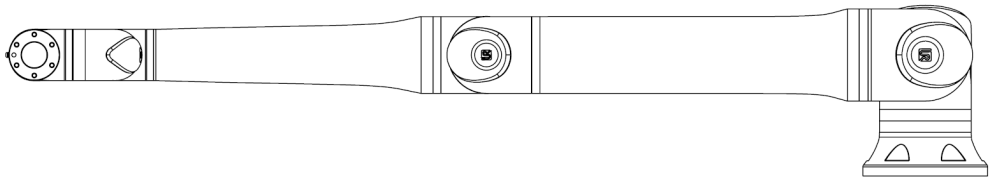
Inspection

1. Unmount any tool/s or attachment/s or set the TCP/Payload/CoG according to tool specifications.
2. To move the robot arm in Freedrive:
   - On a 3PE Teach Pendant, rapidly light-press, release, light-press again and keep holding the 3PE button in this position.



Power button 3PE button

3. Pull/Push the robot to a horizontally elongated position and release.



4. Verify the robot arm can maintain the position without support and without activating Freedrive.

16. Disposal and Environment

Description

Universal Robots robots must be disposed of in accordance with the applicable national laws, regulations and standards. this responsibility rests with the owner of the robot.

UR robots are produced in compliance with restricted use of hazardous substances to protect the environment; as defined by the European RoHS directive 2011/65/EU. If robots (robot arm, Control Box, Teach Pendant) are returned to Universal Robots Denmark, then the disposal is arranged by Universal Robots A/S.

The disposal fee for UR robots sold on the Danish market is prepaid to DPA-system by Universal Robots A/S. Importers in countries covered by the European WEEE Directive 2012/19/EU must make their own registration to the national WEEE register of their country. The fee is typically less than 1€/robot.

You can find a list of national registers here: https://www.ewrn.org/national-registers. Search for Global Compliance here: https://www.universal-robots.com/download.

Substances in the UR robot

Robot arm

- Tubes, Base Flange, Tool mounting bracket: Anodized aluminum
- Joint housings: Powder coated aluminum
- Black band sealing rings: AEM rubber
  - additional slip ring under black band: moulded black plastic
- Endcaps/ lids: PC/ASA Plastic
- Minor mechanical components e.g. screws, nuts, spacers (steel, brass, and plastic)
- Wire bundles with copper wires and minor mechanical components e.g. screws, nuts, spacers (steel, brass, and plastic)

Robot arm joints (internal)

- Gears: Steel and grease (detailed in the Service Manual)
- Motors: Iron core with copper wires
- Wire bundles with copper wires, PCB's, various electronic components and minor mechanical components
- Joint seals and O-rings contain a small amount of PFAS which is a compound within PTFE (commonly known as Teflon™).
- Grease: synthetic + mineral oil with a thickener of either lithium complex soap or Urea. Contains molybdenum.
  - Depending on model and date of production, the color of the grease could be yellow, magenta, dark pink, red, green.
  - The Service Manual details the handling precautions and Grease Safety Data Sheets

Control box

- Cabinet (enclosure): Powder coated steel
  - Standard Control Box
- Aluminum sheet metal housing (internal to the cabinet). This is also the housing of the OEM controller.
  - Standard Control Box and OEM controller.
- Wire bundles with copper wires, PCB's, various electronic components, plastic connectors, and minor mechanical components e.g. screws, nuts, spacers (steel, brass, and plastic)
- A lithium battery is mounted to a PCB. See the Service Manual for how to remove.

17. Risk Assessment

Description

The risk assessment is a requirement that shall be performed for the application. The application risk assessment is the responsibility of the integrator. The user can also be the integrator.

The robot is partly completed machinery, as such the safety of the robot application depends on the tool/end effector, obstacles and other machines. The party performing the integration must use ISO 12100 and ISO 10218-2 to conduct the risk assessment. Technical Specification ISO/TS 15066 can provide additional guidance for collaborative applications. The risk assessment shall consider all tasks throughout the lifetime of the robot application, including but not limited to:

- Teaching the robot during set-up and development of the robot application
- Troubleshooting and maintenance
- Normal operation of the robot application

A risk assessment must be conducted **before** the robot application is powered on for the first time. The risk assessment is an iterative process. After physically installing the robot, verify the connections, then complete the integration. A part of the risk assessment is to determine the safety configuration settings, as well as the need for additional emergency stops and/or other protective measures required for the specific robot application.

Safety configuration settings

Identifying the correct safety configuration settings is a particularly important part of developing robot applications. Unauthorized access to the safety configuration must be prevented by enabling and setting password protection.

WARNING

Failure to set password protection can result in injury or death due to purposeful or inadvertent changes to configuration settings.

- Always set password protection.
- Set up a program for managing passwords, so that access is only by persons who understand the effect of changes.

Some safety functions are purposely designed for collaborative robot applications. These are configurable through the safety configuration settings. They are used to address risks identified in the application risk assessment.

The following limit the robot and as such can affect the energy transfer to a person by the robot arm, end effector and workpiece.

- **Force and power limiting**: Used to reduce clamping forces and pressures exerted by the robot in the direction of movement in case of collisions between the robot and the operator.
- **Momentum limiting**: Used to reduce high transient energy and impact forces in case of collisions between robot and operator by reducing the speed of the robot.
- **Speed limitation**: Used to ensure the speed is less that the configured limit.

The following orientation settings are used to avoid movements and reduce exposure of sharp edges and protrusions to a person.

- **Joint, elbow and tool/end effector position limiting**: Used to reduce risks associated with certain body parts: Avoid movement towards head and neck.
- **Tool/end effector orientation limiting**: Used to reduce risks associated with certain areas and features of the tool/end effector and work-piece: Avoid sharp edges being pointed towards the operator, by turning the sharp edges inward towards the robot.

Stopping performance risks

Some safety functions are purposely designed for any robot application. These features are configurable through the safety configuration settings. They are used to address risks associated with the stopping performance of the robot application.

The following limit the robot stopping time and stopping distance to ensure stopping will occur before reaching the configured limits. Both settings automatically affect the speed of the robot to ensure the limit is not exceeded.

- **Stopping Time Limit**: Used to limit the stopping time of the robot.
- **Stopping Distance Limit**: Used to limit the stopping distance of the robot.

If either of the above is used, there is no need for manually performed periodic stopping performance testing. The robot safety control does continuous monitoring.

If the robot is installed in a robot application where hazards cannot be reasonably eliminated or risks cannot be sufficiently reduced by use of the built-in safety-related functions (e.g. when using a hazardous tool/end effector, or hazardous process), then safeguarding is required.

WARNING

Failure to conduct a application risk assessment can increase risks.

- Always conduct an application risk assessment for foreseeable risks and reasonably foreseeable misuse.

  For collaborative applications, the risk assessment includes the foreseeable risks due to collisions and to reasonably foreseeable misuse.

  The risk assessment shall address:

  - Severity of harm
  - Likelihood of occurrence
  - Possibility to avoid the hazardous situation

Potential hazards

Universal Robots identifies the potential significant hazards listed below for consideration by the integrator. Other significant hazards can be associated with a specific robot application.

- Penetration of skin by sharp edges and sharp points on tool/end effector or tool/end effector connector.
- Penetration of skin by sharp edges and sharp points on nearby obstacles.
- Bruising due to contact.
- Sprain or bone fracture due to impact.
- Consequences due to loose bolts that hold the robot arm or tool/end effector.
- Items falling out of, or flying from the tool/end effector, e.g. due to a poor grip or power interruption.
- Mistaken understanding of what is controlled by multiple emergency stop buttons.
- Incorrect setting of the safety configuration parameters.
- Incorrect settings due to unauthorized changes to the safety configuration parameters.

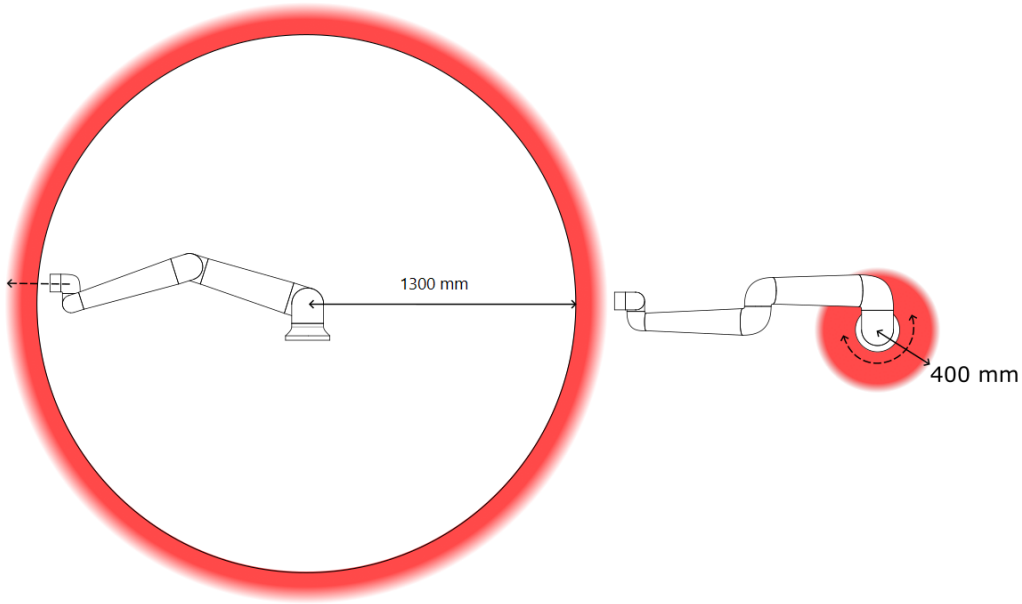
17.1. Pinch Hazard

Description

You can avoid pinching hazards by removing obstacles in these areas, by placing the robot differently, or by using a combination of safety planes and joint limits to eliminate the hazards by preventing the robot moving into this area of its workspace.

CAUTION

Placing the robot in certain areas can create pinching hazards that can lead to injury.



Due to the physical properties of the robot arm, certain workspace areas require attention regarding pinching hazards. One area (left) is defined for radial motions when the wrist 1 joint is at least 1650 mm from the base of the robot. The other area (right) is within 400 mm of the base of the robot, when moving tangentially.

17.2. Stopping Time and Stopping Distance

Description

The graphical data provided for **Joint 0 (base)**, **Joint 1 (shoulder)** and **Joint 2 (elbow)** is valid for stopping distance and stopping time:

- Category 0
- Category 1
- Category 2

The **Joint 0** test was carried out using a horizontal movement, where the rotational axis was perpendicular to the ground. During the **Joint 1** and **Joint 2** tests, the robot followed a vertical trajectory, where the rotational axes were parallel to the ground, and the stop was done while the robot was moving downward.
The Y-axis is the distance from where the stop is initiated to the final position.
You can set safety rated maximum stopping time and distance. If the user-defined settings are used, the program speed adjusts to comply with selected limits.

NOTICE

You can set user-defined safety rated maximum stopping times and distances. If user-defined settings are used, the program speed is dynamically adjusted to always comply with the selected limits.

Joint 0 (BASE)
Stopping distance in meters for 33% of 30 kg
Stopping distance in meters for 66% of 30 kg
Stopping distance in meters for maximum payload of 30 kg

Stopping distance in meters for expanded payload of 35 kg	
Joint 0 (BASE)	
Stopping time in seconds for 33% of 30 kg	
Stopping time in seconds for 66% of 30 kg	
Stopping time in seconds for maximum payload of 30 kg	
Stopping time in seconds for expanded payload of 35 kg	
Joint 1 (SHOULDER)	
Stopping distance in meters for 33% of 30 kg	
Stopping distance in meters for 66% of 30 kg	

Stopping distance in meters for maximum payload of 30 kg	
In this specific test motion only 80% of the nominal maximum speed is achievable.	
Stopping distance in meters for expanded payload of 35 kg	

Joint 1 (SHOULDER)

Stopping time in seconds for 33% of 30 kg	
Stopping time in seconds for 66% of 30 kg	
Stopping time in seconds for maximum payload of 30 kg	
In this specific test motion only 80% of the nominal maximum speed is achievable.	

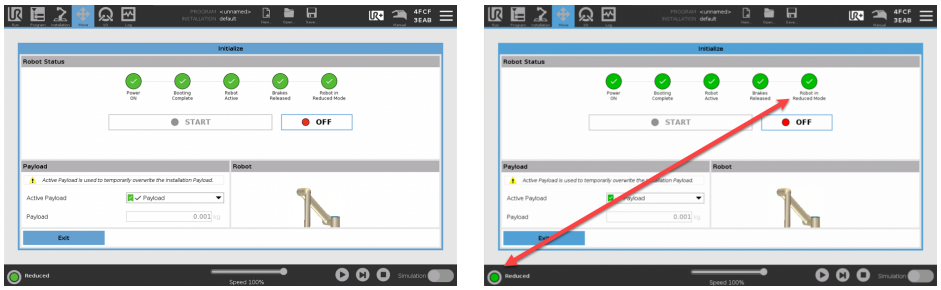
Stopping time in seconds for maximum payload of 35 kg	
Joint 2 (ELBOW)	
Stopping distance in meters for 33% of 30 kg	
Stopping distance in meters for 66% of 30 kg	
Stopping distance in meters for maximum payload of 30 kg	
Stopping distance in meters for expanded payload of 35 kg	
Joint 2 (ELBOW)	
Stopping time in seconds for 33% of 30 kg	
Stopping time in seconds for 66% of 30 kg	

Stopping time in seconds for maximum payload of 30 kg	
Stopping time in seconds for expanded payload of 35 kg	

17.3. Commissioning

Description The following tests must be conducted before using the robot application for the first time or after making any modifications.

- Verify all safety inputs and outputs are correctly connected.
- Test all connected safety input and output, including devices common to multiple machines or robots, are functioning as intended.
- Test emergency stop buttons and inputs to verify the robot stops and the brakes engage.
- Test safeguard inputs to verify the robot motion stops. If safeguard reset is configured, check that it functions as intended.
- Look at the initialization screen, activate the reduced input and verify the screen changes.



- Change the operational mode to verify the mode icon changes in top right corner of PolyScope screen.
- Test the 3-position enabling device to verify that pressing to the center on position enables motion in manual mode at a reduced speed.
- If the Emergency Stop outputs are used, press the Emergency Stop push-button and verify that there is a stop of the whole system.
- Test the system connected to Robot Moving output, Robot Not Stopping output, Reduced Mode output, or Not Reduced Mode output to verify the output changes are detected.
- Determine the commissioning requirements of your robot application.

18. Declarations and Certificates (original EN)

EU Declaration of Incorporation (DOI) (in accordance with 2006/42/EC Annex II B) original EN	
Manufacturer	Universal Robots A/S Energivej 51, DK-5260 Odense S Denmark
Person in the Community Authorized to Compile the Technical File	David Brandt Technology Officer, R&D Universal Robots A/S, Energivej 51, DK-5260 Odense S
Description and Identification of the Partially-Completed Machine(s)	
Product and Function:	Industrial robot multi-purpose multi-axis manipulator with control box & with or without teach pendant function is determined by the completed machine (robot application or cell with end-effector, intended use and application program).
Model:	UR3e, UR5e, UR7e, UR10e, UR12e, UR16e (e-Series). This declaration includes: Effective October 2020: Teach Pendants with 3-Position Enabling (3PE TP) & standard Teach Pendants (TP). Effective May 2021: UR10e specification improvement to 12.5kg maximum payload.
Note: This Declaration of Incorporation is NOT applicable when the UR OEM Controller is used.	
Serial Number:	Starting XY245000000 and higher Factory Variantyear e-Series 3=UR3e, 5=UR5e, 7=UR7e, 0=UR10e (10kg), 1=UR12e, 2=UR10e(12kg payload), 6=UR16e sequential numbering, restarting at 0 each year
Incorporation:	Universal Robots e-Series (UR3e, UR5e, UR10e and UR16e) shall only be put into service upon being integrated into a final complete machine (robot application or cell), which conforms with the provisions of the Machinery Directive and other applicable Directives.
It is declared that the above products fulfil, for what is supplied, the following directives as detailed below: When this incomplete machine is integrated and becomes a complete machine, the integrator is responsible the completed machine fulfilling all applicable Directives, applying the CE mark and providing the Declaration of Conformity (DOC).	
I. Machinery Directive 2006/42/EC II. Low-voltage Directive 2014/35/EU III. EMC Directive 2014/30/EU	The following essential requirements have been fulfilled: 1.1.2, 1.1.3, 1.1.5, 1.2.1, 1.2.4.3, 1.2.5, 1.2.6, 1.3.2, 1.3.4, 1.3.8.1, 1.3.9, 1.5.1, 1.5.2, 1.5.5, 1.5.6, 1.5.10, 1.6.3, 1.7.2, 1.7.4, 4.1.2.3, 4.1.3 Annex VI. It is declared the relevant technical documentation has been compiled in accordance with Part B of Annex VII of the Machinery Directive. Reference the LVD and the harmonized standards used below. Reference the EMC Directive and the harmonized standards used below.

Reference to the harmonized standards used, as referred to in Article 7(2) of the MD & LV Directives and Article 6 of the EMC Directive:		
(I) EN ISO 10218-1:2011 Certification by TÜV Rheinland (I) EN ISO 13732-1:2008 as applicable (I) EN ISO 13849-1:2015 Certification by TÜV Rheinland to 2015; 2023 edition has no relevant changes (I) EN ISO 13849-2:2012 (I) EN ISO 13850:2015	(I)(II) EN 60204-1:2018 as applicable (II) EN 60529:1991+A1:2000+A2:2013 (I) EN 60947-5-5:1997+A1:2005 +A11:2013+A2:2017 (I) EN 60947-5-8:2020 (III) EN 61000-3-2:2019	(II) EN 60664-1:2007 (III) EN 61000-3-3: 2013 (III) EN 61000-6-1:2019 UR3e & UR5e ONLY (III) EN 61000-6-2:2019 (III) EN 61000-6-3:2007+A1: 2011 UR3e UR5e & UR7e ONLY (III) EN 61000-6-4:2019
Reference to other technical standards and technical specifications used:		

(I) ISO 9409-1:2004 [Type 50-4-M6] (I) ISO/TS 15066:2016 as applicable (III) EN 60068-2-1: 2007 (III) EN 60068-2-2:2007	(II) EN 60320-1:2021 (III) EN 60068-2-27:2008 (III) EN 60068-2-64:2008+A1:2019	(II) EN 61784-3:2010 [SIL2] (III) EN 61326-3-1: 2017 [Industrial locations SIL 2]
The manufacturer, or his authorised representative, shall transmit relevant information about the partly completed machinery in response to a reasoned request by the national authorities. Approval of full quality assurance system (ISO 9001), by the notified body Bureau Veritas, certificate #DK015892.		

Odense Denmark, 25 October 2024

Roberta Nelson Shea, Global Technical Compliance Officer

Universal Robots A/S, Energivej 51, DK-5260 Odense S, Denmark
CVR-nr. 29 13 80 60

Phone +45 8993 8989
Fax +45 3879 8989

info@universal-robots.com
www.universal-robots.com

19. Declarations and Certificates

EU Declaration of Incorporation (DOI) (in accordance with 2006/42/EC Annex II B) original EN	
Manufacturer	Universal Robots A/S Energivej 25, DK-5260 Odense S Denmark
Person in the Community Authorized to Compile the Technical File	David Brandt Technology Officer, R&D Universal Robots A/S, Energivej 25, DK-5260 Odense S
Description and Identification of the Partially-Completed Machine(s)	
Product and Function:	Industrial robot multi-purpose multi-axis manipulator with control box & with or without teach pendant Function is determined by the completed machine (robot application or cell with end-effector, intended use and application program).
Model :	UR3e, UR5e, UR10e, UR16e (e-Series): Below cited certifications and this declaration include: • Effective October 2020: Teach Pendants with 3-Position Enabling (3PE TP) & standard Teach Pendants (TP). • Effective May 2021: UR10e specification improvement to 12.5kg maximum payload.
	Note: This Declaration of Incorporation is NOT applicable when the UR OEM Controller is used.
Serial Number:	Starting 20235000000 and higher year e-Series 3=UR3e, 5=UR5e, 3=UR3e, 0=UR10e (10kg), 2=UR10e(12.5), 6=UR16e sequential numbering, restarting at 0 each year
Incorporation:	Universal Robots e-Series (UR3e, UR5e, UR10e and UR16e) shall only be put into service upon being integrated into a final complete machine (robot application or cell), which conforms with the provisions of the Machinery Directive and other applicable Directives.
It is declared that the above products fulfil, for what is supplied, the following directives as detailed below: When this incomplete machine is integrated and becomes a complete machine, the integrator is responsible for determining that completed machine fulfils all applicable Directives and providing the Declaration of Conformity.	
I. Machinery Directive 2006/42/EC	The following essential requirements have been fulfilled: 1.1.2, 1.1.3, 1.1.5, 1.2.1, 1.2.4.3, 1.2.5, 1.2.6, 1.3.2, 1.3.4, 1.3.8.1, 1.3.9, 1.5.1, 1.5.2, 1.5.5, 1.5.6, 1.5.10, 1.6.3, 1.7.2, 1.7.4, 4.1.2.3, 4.1.3, Annex VI. It is declared that the relevant technical documentation has been compiled in accordance with Part B of Annex VII of the Machinery Directive.
II. Low-voltage Directive 2014/35/EU III. EMC Directive 2014/30/EU	Reference the LVD and the harmonized standards used below. Reference the EMC Directive and the harmonized standards used below.

Reference to the harmonized standards used, as referred to in Article 7(2) of the MD & LV Directives and Article 6 of the EMC Directive:

(I) EN ISO 10218-1:2011 TÜV Nord Certificate # 44 708 14097607 (I) EN ISO 13732-1:2008 as applicable (I) EN ISO 13849-1:2015 TÜV Nord Certificate # 44 207 14097610 (I) EN ISO 13849-2:2012 (I) EN ISO 13850:2015	(I) (II) EN 60204-1:2018 as applicable (II) EN 60529:1991+A1:2000+A2:2013 (I) EN 60947-5-5:1997+A1:2005 +A11:2013+A2:2017 (I) EN 60947-5-8:2020 (III) EN 61000-3-2:2019	(II) EN 60664-1:2007 (III) EN 61000-3-3: 2013 (III) EN 61000-6-1:2019 UR3e & UR5e ONLY (III) EN 61000-6-2:2019 (III) EN 61000-6-3:2007+A1: 2011 UR3e & UR5e ONLY (III) EN 61000-6-4:2019
Reference to other technical standards and technical specifications used:		
(I) ISO 9409-1:2004 [Type 50-4-M6] (I) ISO/TS 15066:2016 as applicable (III) EN 60068-2-1: 2007 (III) EN 60068-2-2:2007	(II) EN 60320-1:2021 (III) EN 60068-2-27:2008 (III) EN 60068-2-64:2008+A1:2019	(II) EN 61784-3:2010 [SIL2] (III) EN 61326-3-1: 2017 [Industrial locations SIL 2]
The manufacturer, or his authorised representative, shall transmit relevant information about the partly completed machinery in response to a reasoned request by the national authorities.Approval of full quality assurance system (ISO 9001), by the notified body Bureau Veritas, certificate #DK015892.		

Odense Denmark, 25 October 2024

Roberta Nelson Shea, Global Technical Compliance Officer

Universal Robots A/S, Energivej 51, DK-5260 Odense S, Denmark
CVR-nr. 29 13 80 60
Phone +45 8993 8989
Fax +45 3879 8989
info@universal-robots.com
www.universal-robots.com

20. Certifications

Description

Third party certification is voluntary. However, to provide the best service to robot integrators, Universal Robots chooses to certify its robots at the recognized test institutes listed below.
You can find copies of all certificates in the chapter: Certificates.

Certification

EN ISO 10218-1 EN ISO 13849-1 TÜVRheinland CERTIFIED www.tuv.com ID 0007000000	TÜV Rheinland	Certificates by TÜV Rheinland to EN ISO 10218-1 and EN ISO 13849-1. TÜV Rheinland stands for safety and quality in virtually all areas of business and life. Founded 150 years ago, the company is one of the world's leading testing service providers.
TÜVRheinland®	TÜV Rheinland of North America	In Canada, the Canadian Electrical Code, CSA 22.1, Article 2-024 requires equipment to be certified by a testing organization approved by the Standards Council of Canada.
25	CHINA RoHS	Universal Robots e-Series robots conform to CHINA RoHS management methods for controlling pollution by electronic information products.
KC S	KCC Safety	Universal Robots e-Series robots have been assessed and conform to KCC mark safety standards.
KC	KC Registration	The Universal Robots e-Series robots have been evaluated for conformity assessment for use in a work environment. Therefore, there is a risk of radio interference when used in a domestic environment.
DELTA	Delta	Universal Robots e-Series robots are performance tested by DELTA.

Supplier Third Party Certification

	Environment	As provided by our suppliers, Universal Robots e-Series robots shipping pallets comply with the ISMPM-15 Danish requirements for producing wood packaging material and are marked in accordance with this scheme.

Manufacturer Test Certification

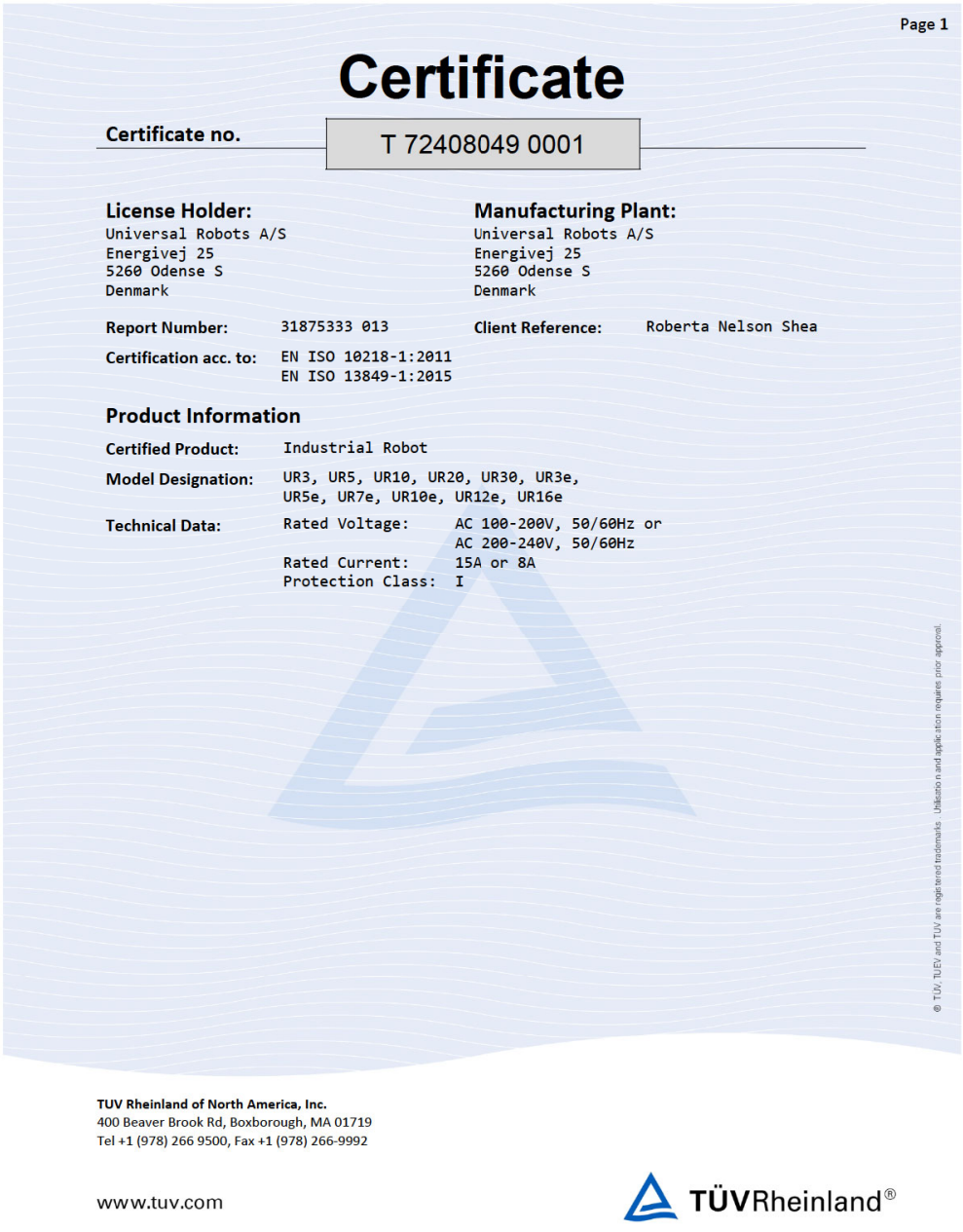
	Universal Robots	Universal Robots e-Series robots undergo continuous internal testing and end of line test procedures. UR testing processes undergo continuous review and improvement.

Declarations according to EU directives

Although EU directives are relevant for Europe, some countries outside Europe recognize and/or require EU declarations. European directives are available on the official homepage: http://eur-lex.europa.eu.
According to the Machinery Directive, Universal Robots' robots are partly completed machines, as such a CE mark is not to be affixed.
You can find the Declaration of Incorporation (DOI) according to the Machinery Directive in the chapter: Declarations and Certificates.

21. Certificates

TÜV Rheinland



Page 1

Certificate

Certificate no. T 72408049 0001

License Holder:
Universal Robots A/S
Energivej 25
5260 Odense S
Denmark

Manufacturing Plant:
Universal Robots A/S
Energivej 25
5260 Odense S
Denmark

Report Number: 31875333 013
Client Reference: Roberta Nelson Shea

Certification acc. to: EN ISO 10218-1:2011
EN ISO 13849-1:2015

Product Information

Certified Product: Industrial Robot

Model Designation: UR3, UR5, UR10, UR20, UR30, UR3e, UR5e, UR7e, UR10e, UR12e, UR16e

Technical Data:
Rated Voltage: AC 100-200V, 50/60Hz or AC 200-240V, 50/60Hz
Rated Current: 15A or 8A
Protection Class: I

TUV Rheinland of North America, Inc.
400 Beaver Brook Rd, Boxborough, MA 01719
Tel +1 (978) 266 9500, Fax +1 (978) 266-9992

www.tuv.com

TÜVRheinland®

TÜV Rheinland North America

Page 1

Certificate

Certificate no. CA 72405127 0001

License Holder:
Universal Robots A/S
Energivej 25
5260 Odense S
Denmark

Manufacturing Plant:
Universal Robots A/S
Energivej 25
5260 Odense S
Denmark

Report Number: 31875333 006
Client Reference: Roberta Nelson Shea
Certification acc. to: CAN/CSA-Z434-14 + GI1 (R2019)

Product Information

Certified Product: Industrial Robot
Model Designation: UR3e, UR5e, UR10e, UR16e, UR20, UR30

TUV Rheinland of North America, Inc.
400 Beaver Brook Rd, Boxborough, MA 01719
Tel +1 (978) 266 9500, Fax +1 (978) 266-9992

www.tuv.com

TÜVRheinland®

China RoHS

Management Methods for Controlling Pollution by Electronic Information Products
Product Declaration Table For Toxic or Hazardous Substances
表1 有毒有害物质或元素名称及含量标识格式

Product/Part Name 产品/部件名称	Toxic and Hazardous Substances and Elements 有毒有害物质或元素					
	铅 Lead (Pb)	汞 Mercury (Hg)	镉 Cadmium (Cd)	六价 Hexavalent Chromium (Cr+6)	多溴联苯 Polybrominated biphenyls (PBB)	多溴二苯醚 Polybrominated diphenyl ethers (PBDE)
UR Robots 机器人：基本系统 UR3 / UR5 / UR10 / UR3e / UR5e / UR10e UR16e / UR20 / UR30	X	O	X	O	X	X

O: Indicates that this toxic or hazardous substance contained in all of the homogeneous materials for this part is below the limit requirement in SJ/T11363-2006.
O: 表示该有毒有害物质在该部件所有均质材料中的含量均在SJ/T 11363-2006规定的限量要求以下。
X: Indicates that this toxic or hazardous substance contained in at least one of the homogeneous materials used for this part is above the limit requirement in SJ/T11363-2006.
X: 表示该有毒有害物质至少在该部件的某一均质材料中的含量超出SJ/T 11363-2006规定的限量要求。
（企业可在此处，根据实际情况对上表中打"X"的技术原因进行进一步说明。）
Items below are wear-out items and therefore can have useful lives less than environmental use period:
下列项目是损耗品,因而它们的有用环境寿命可能短于基本系统和可选项目的使用时间:
Drives, Gaskets, Probes, Filters, Pins, Cables, Stiffener, Interfaces
电子驱动器，垫圈, 探针, 过滤器, 别针, 缆绳, 加强筋, 接口
Refer to product manual for detailed conditions of use.
详细使用情况请阅读产品手册.
Universal Robots encourages that all Electronic Information Products be recycled but does not assume responsibility or liability.
Universal Robots 鼓励回收再循环利用所有的电子信息产品, 但 Universal Robots 不负任何责任或义务

To the maximum extent permitted by law, Customer shall be solely responsible for complying with, and shall otherwise assume all liabilities that may be imposed in connection with, any legal requirements adopted by any governmental authority related to the Management Methods for Controlling Pollution by Electronic Information Products (Ministry of Information Industry Order #39) of the Peoples Republic of China otherwise encouraging the recycle and use of electronic information products. Customer shall defend, indemnify and hold Universal Robots harmless from any damage, claim or liability relating thereto. At the time Customer desires to dispose of the Products, Customer shall refer to and comply with the specific waste management instructions and options set forth at www.universal-robots.com/about-universal-robots/social-responsibility and www.teradyne.com/company/corporate-social-responsibility, as the same may be amended by Teradyne or Universal Robots.

KC Safety

자율안전확인 신고증명서

신청인	사업장명	유니버설 로봇 에이에스(Universal Robots A.S)	사업장관리번호	807-84-000600
	사업자등록번호	807-84-00060	대표자 성명	JETTE BAY WITHERS(제트 베이 위더스)
	소재지	(13486) 경기도 성남시 분당구 판교로 253, B동 302호(삼평동, 판교 이노밸리)		

자율안전인증대상 기계 · 기구명	산업용로봇		
형식(규격)	UR30	용량(등급)	6 axis
자율안전확인번호	24-AH3EQ-00888		
제조자	UNIVERSAL ROBOTS		
소재지	Energivej 25, 5260 Odense S, Denmark		

「산업안전보건법」 제89조제1항 및 같은 법 시행규칙 제120조제3항에 따라
자율안전확인 신고증명서를 발급합니다.

2024년 04월 08일

한국산업안전보건공단 이사장

KC
Registration

자율안전확인 신고증명서

신청인	사업장명	유니버설 로봇 에이에스(Universal Robots A.S)	사업장관리번호	807-84-000600
	사업자등록번호	807-84-00060	대표자 성명	JETTE BAY WITHERS(제트 베이 위더스)
	소재지	(13486) 경기도 성남시 분당구 판교로 253, B동 302호(삼평동, 판교 이노밸리)		

자율안전인증대상 기계 · 기구명	산업용로봇		
형식(규격)	UR30	용량(등급)	6 axis
자율안전확인번호	24-AH3EQ-00888		
제조자	UNIVERSAL ROBOTS		
소재지	Energivej 25, 5260 Odense S, Denmark		

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자율안전확인 신고증명서를 발급합니다.

2024년 04월 08일

한국산업안전보건공단 이사장

Software Name: PolyScope X
Software Version: 10.7
Document Version: 10.9.101