8.7. End Effector Integration

Description

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

NOTICE

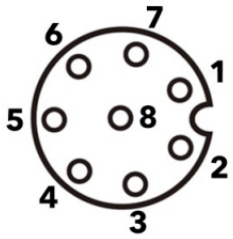
UR provides documentation for the end effector to be integrated with the robot arm.

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

8.7.1. 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

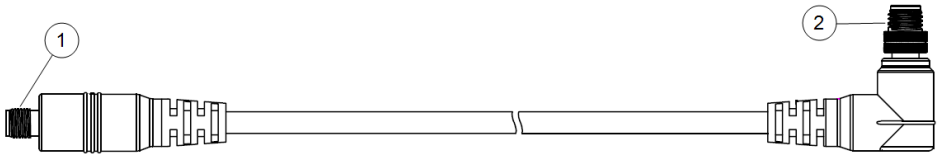
The Tool Connector must be manually tightened up to a maximum of 0.4 Nm.

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.

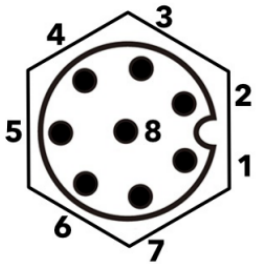
2 Connects to the robot.

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).

8.7.2. 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.

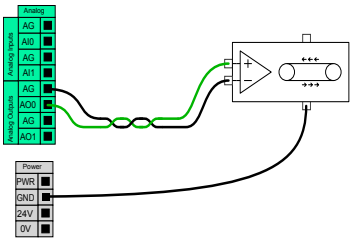
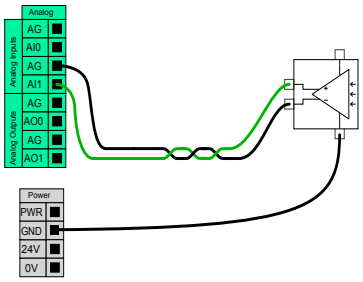
- Use the AG terminal closest to the I/O. The pair share a common mode filter.
- Use the same GND (0V) for equipment and Control Box. The analog I/O is not galvanically isolated from the Control Box.
- Use a shielded cable or twisted pairs. Connect the shield to the GND terminal at the terminal called **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 (see part Part II PolyScope Manual). 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.

8.7.3. General Purpose Digital I/O

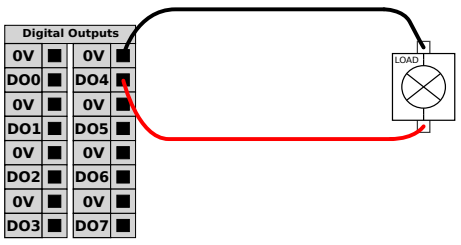
Description

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

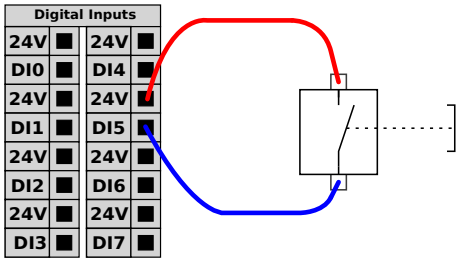
General purpose digital I/O

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 common specifications in section 8.7.3 General Purpose Digital I/O above must be observed.

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, see part Part II PolyScope Manual.
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.



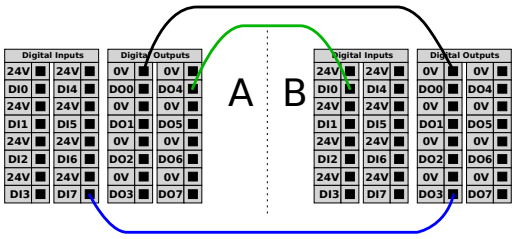
This example shows how a load is controlled from a Digital Outputs when connected.



This example shows how 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.



8.7.4. Remote ON/OFF control

Description

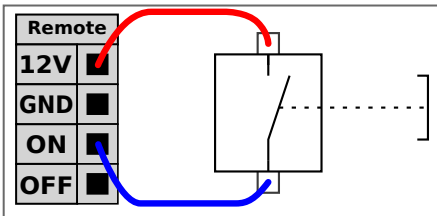
Use remote **ON/OFF** control to turn the Control Box on and off without using the Teach Pendant. It is typically used:

- 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.

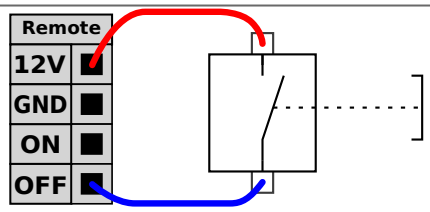
Remote Control

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.

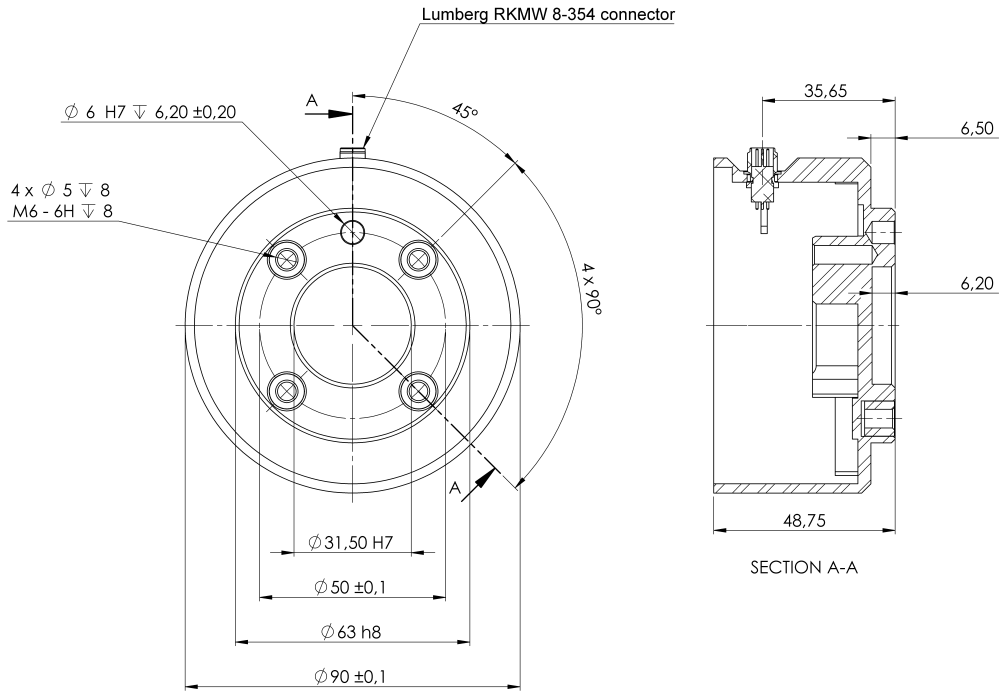
CAUTION

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.

8.7.5. 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.

8.7.6. 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.

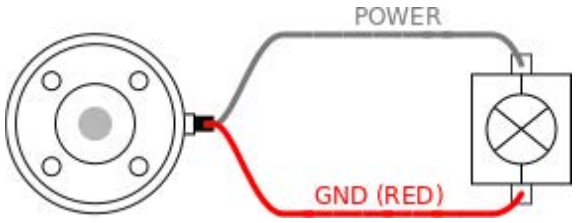
** Peak for max 1 second, duty cycle max: 10%. Average current over 10 seconds must not exceed typical current.

*** 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.

8.7.7. Tool Power Supply

Description

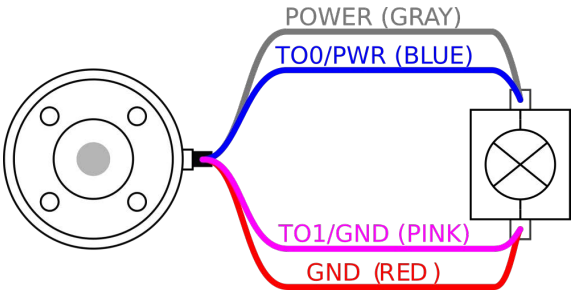
Access Tool I/O in the Installation Tab to set the internal power supply to 0V, 12V or 24V.



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).

8.7.8. 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

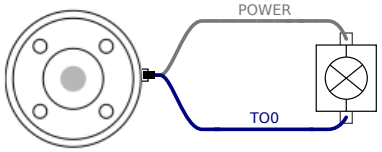
Once the robot makes an Emergency Stop, the Digital Outputs (DO0 and DO1) are deactivated (High Z).

CAUTION

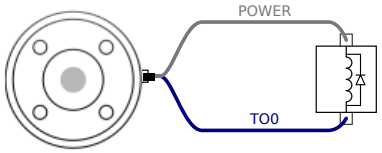
The Digital Outputs in the tool are not current-limited. Overriding the specified data can cause permanent damage.

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.



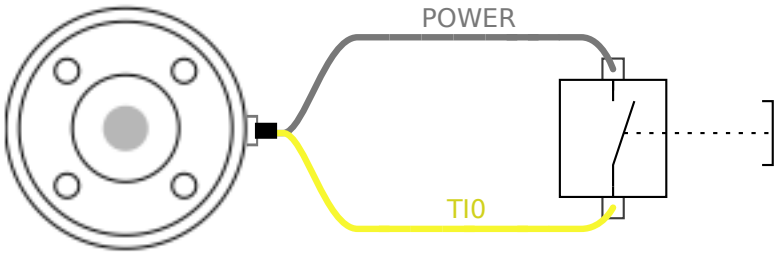
8.7.9. Tool Digital Inputs

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.



8.7.10. 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.

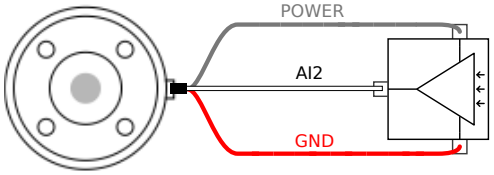
Caution

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.

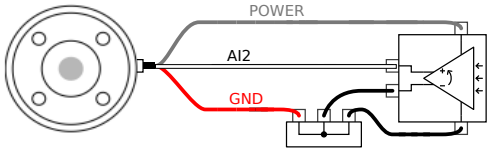
Using Tool Analog Inputs, Non-differential

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.



8.7.11. 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