



# ROBOTIQ PALLETIZING *SOLUTION*

## AX Series

Original Notice

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Robotiq Palletizing Solution - AX Series  
for Universal Robots



Instruction Manual

LEAN   
ROBOTICS

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# Revisions

Robotiq may modify this product without notice, when necessary, due to product improvements, modifications or changes in specifications. If such modification is made, the manual will also be revised, see revision information. See the latest version of this manual online at: [support.robotiq.com](https://support.robotiq.com).

## 2022/04/25

- Added warning note for Moving and Positioning the Solution (Installation section).
- Added **Add virtual planes around pallet(s)** option (Installation and Software sections).
- Added an **Avoid collision with conveyor** option in the Palletizer node and the different configurations (Software section).
- Added scripts **Get Pallet State** and **Set Palletizer State** in Software section.

## 2022/03/28

- Added Robot Limits section

## 2022/02/03

- Added Physical Clearance and Reachable Area of the Robot section
- Updated Safety Connections section

## 2022/01/04

- Added script functions
- Updated Installation on Universal Robots e-Series section
- The palletizer model is now named AX Series

## 2021/10/07

- Updated Center of mass, tool center point (TCP) table

## 2021/09/22

- Updated Safety Connections Appendix
  - Pink wire is now orange
- Updated Safety section to add information regarding Reduced mode
- Updated Software section with more details for the pick position

## 2021/08/03

- Update of the Software section
  - Added Depalletizing mode to Palletizer node
  - Updated info on the Limit height for Palletizer program node
  - Added section 5.2 (Palletizing script functions)



**2021/07/14**

- Update of the Specifications section (Center of mass, tool center point table)
- Update of the Appendix section (Safety Connections)
- Update of the Software section
- Update of the Troubleshoot section
- Update of the Warranty section
- Update of the Installation section with new cable management instructions
- Update of Spare Parts, Kits and Accessories section

**2021/03/29**

- Update of the Software section: label orientation option added.
- Update of the Specifications section
- Update of the Installation section (Robot configurations)

**2020/12/16**

- Update of the safety section
- Update of the installation section
- Update of the specifications section

**2020/11/30**

Update of the Installation section.

**2020/11/25**

Initial release



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The information contained in this document is subject to change without notice.



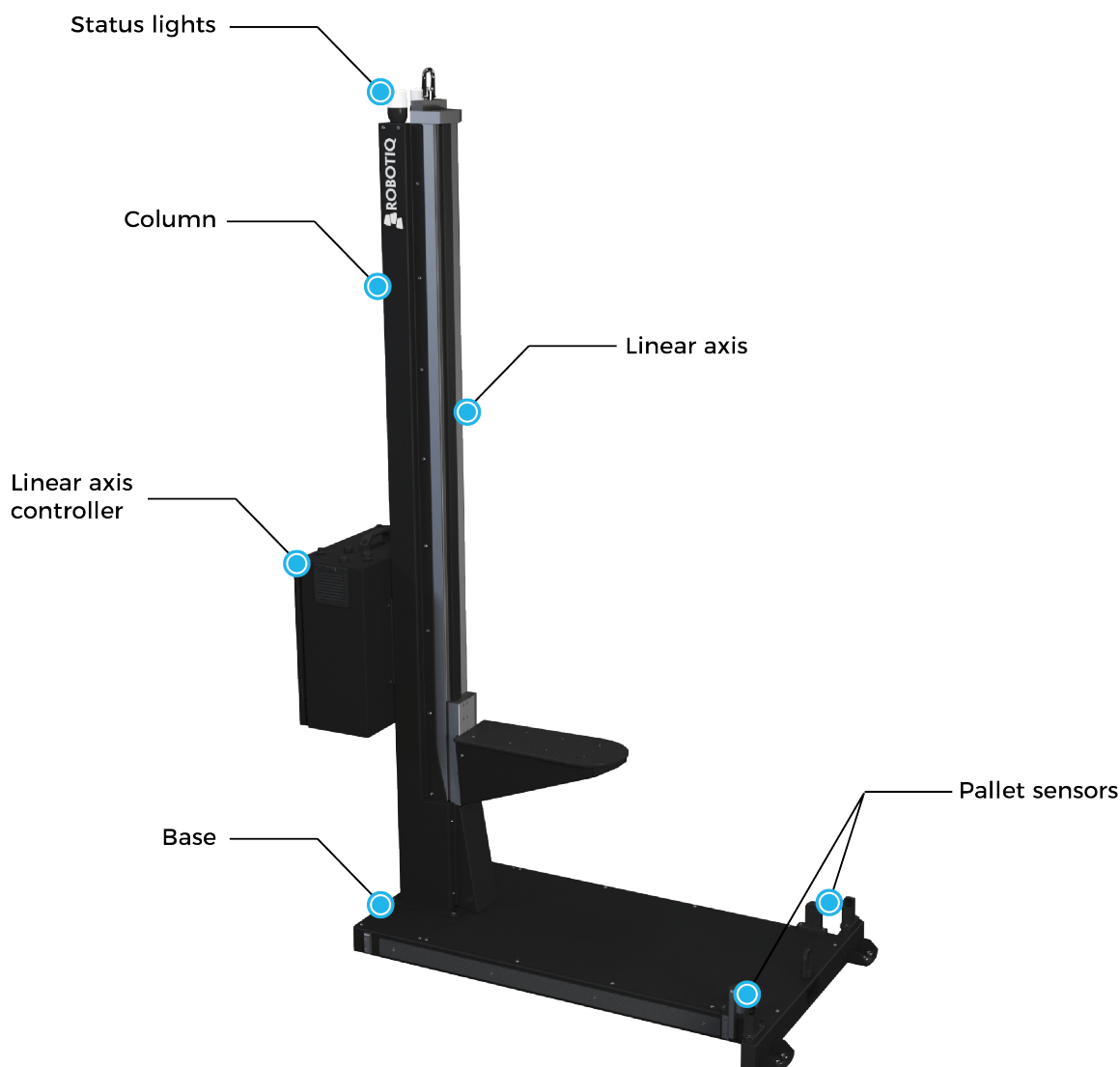
# 1. General Presentation

The terms "Palletizer", "Palletizing Solution", "Robotiq Palletizing Solution", "Solution" and "AX Series" used in this manual all refer to the AX Series Robotiq Palletizing Solution. The AX Robotiq Palletizing Solution is a hardware and software solution already connected and ready to install. It is composed of a base fully integrated with a linear axis, pallet sensors, and status lights. An extra reach gripper bracket is also included in the Solution to extend the reach of an end-of-arm tool of 200 mm from the robot's tool flange. The Material Handling Copilot software and accessories (e.g., box sensor, anchor kit, cable management system, etc.) are also part of the Solution.

## Info

The following manual uses the metric system. Unless specified, **all dimensions are in millimeters**.

## 1.1. Palletizing Solution Components



**Info**

The following section presents the key features of the Robotiq Palletizing Solution and must not be considered as appropriate to the operation of the Solution. Each feature is detailed in the appropriate section.

### 1.1.1. Base and Column

The Robotiq Palletizing Solution is composed of a base and a column on which all the components that are necessary to the good operation of the Solution are attached. The Solution is designed to facilitate the positioning of pallets. The base has to be anchored to the floor. For more details, please refer to the **Installation** section

### 1.1.2. Linear Axis

To extend the reach of the robot, a linear axis is installed inside the column. It allows the robot to move vertically in order to build high pallets.

### 1.1.3. Linear Axis Controller

All the components of the Solution are integrated and controlled via the linear axis Controller. It allows for the simultaneous motion of both the axis and the robot during a palletizing action, and the control of the pallet sensors and status lights.

### 1.1.4. Pallet Sensors

The Solution is composed of four (4) sensors to detect pallets presence (two per pallet). The sensors will allow the Solution to ensure that the pallets are well positioned on each side of the base to optimize the application process.

### 1.1.5. Status Lights

Two (2) status lights are positioned at the top of the base. Each status light is associated to the nearest pallet. The color of the light gives information on the status of the system or the state of a specific pallet. Please refer to the **Light States** section for more information.

### 1.1.6. AirPick Vacuum Gripper

The AirPick is a Vacuum Gripper that creates a vacuum via a pneumatic vacuum generator. It is equipped with one or multiple suction cups. Each suction cup can be adapted to your application and grasping needs. The AirPick Gripper is compatible with the Robotiq standard coupling interface.





Fig. 1-1: Robotiq AirPick Gripper

### 1.1.7. Suction Cup System

A Robotiq Suction Cup System can be installed directly under the Vacuum Gripper. Each Robotiq Suction Cup System includes a bracket, a manifold, air nodes, port plugs, bumpers, tubing and additional suction cups.



Fig. 1-2: Suction cup system

#### Info

Please refer to the **Installation** section for more information on how to integrate the Suction Cup System to the AirPick.

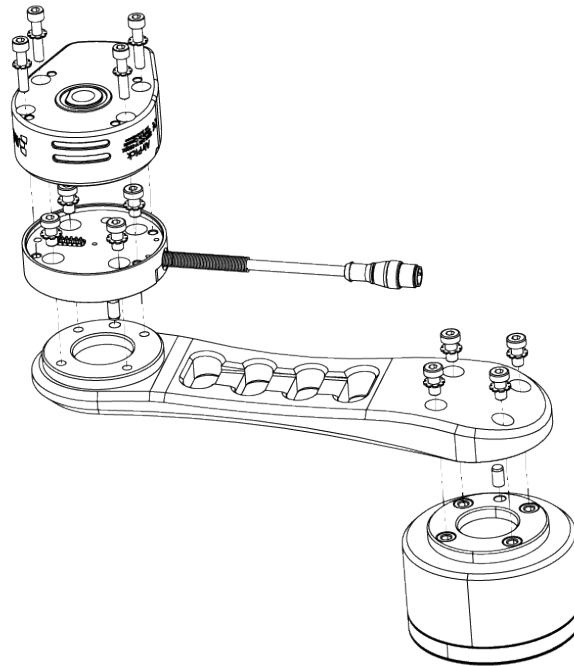
#### Tip

The owner can use a custom bracket or a mounting plate. The bracket or mounting plate can be installed directly under the manifold.



## 1.1.8. Extra Reach Gripper Bracket

The extra reach gripper bracket is included in the Solution to extend the AirPick Gripper of 200 mm from the robot tool flange. This way, the Robotiq Palletizing Solution will be able to palletize boxes on large size pallets. Please refer to the **Extra Reach Bracket** section for more details about the limitations of the extension bracket



*Fig. 1-3: AirPick Vacuum Gripper Extra Reach Bracket*

## 1.1.9. Box Detection Sensor

The Solution includes a box sensor that needs to be installed at the end of the conveyor in a way that it is triggered when a box is ready to be picked up.



*Fig. 1-4: Box Sensor*

## 1.2. Object Picking

The AirPick Gripper allows:

1. Main unit suction cup
2. Auxiliary system with multiple suction cups

### Warning

Object picking causes the compression of the suction cup(s) , which can result in pinching points between the gripper and the load. Avoid presence of body parts in this zone during operation.

### Warning

Before picking any new object or material in autonomous mode, always check that the resulting vacuum level is sufficient to ensure safe gripping, in order to prevent dropping or ejection of the load.

### 1.2.1. Main Unit Suction Cup

- In order to use only one suction cup, the single cup can be mounted right in the port of the vacuum generator.

### 1.2.2. Auxiliary System with Multiple Suction Cups

- A standard Suction Cup System can be attached to the AirPick Vacuum Gripper. The bracket normally holds two or four suction cups (corresponding to the four ports of the manifold).
- Any unused manifold port should be blocked with a mating plug to avoid air leakage.
- Other custom mounting options can also be used to benefit from a multiple suction cups solution.

### Info

For the collision avoidance algorithm, the robot control software considers a generic gripper geometric envelope that does not overlap the box.

### Caution

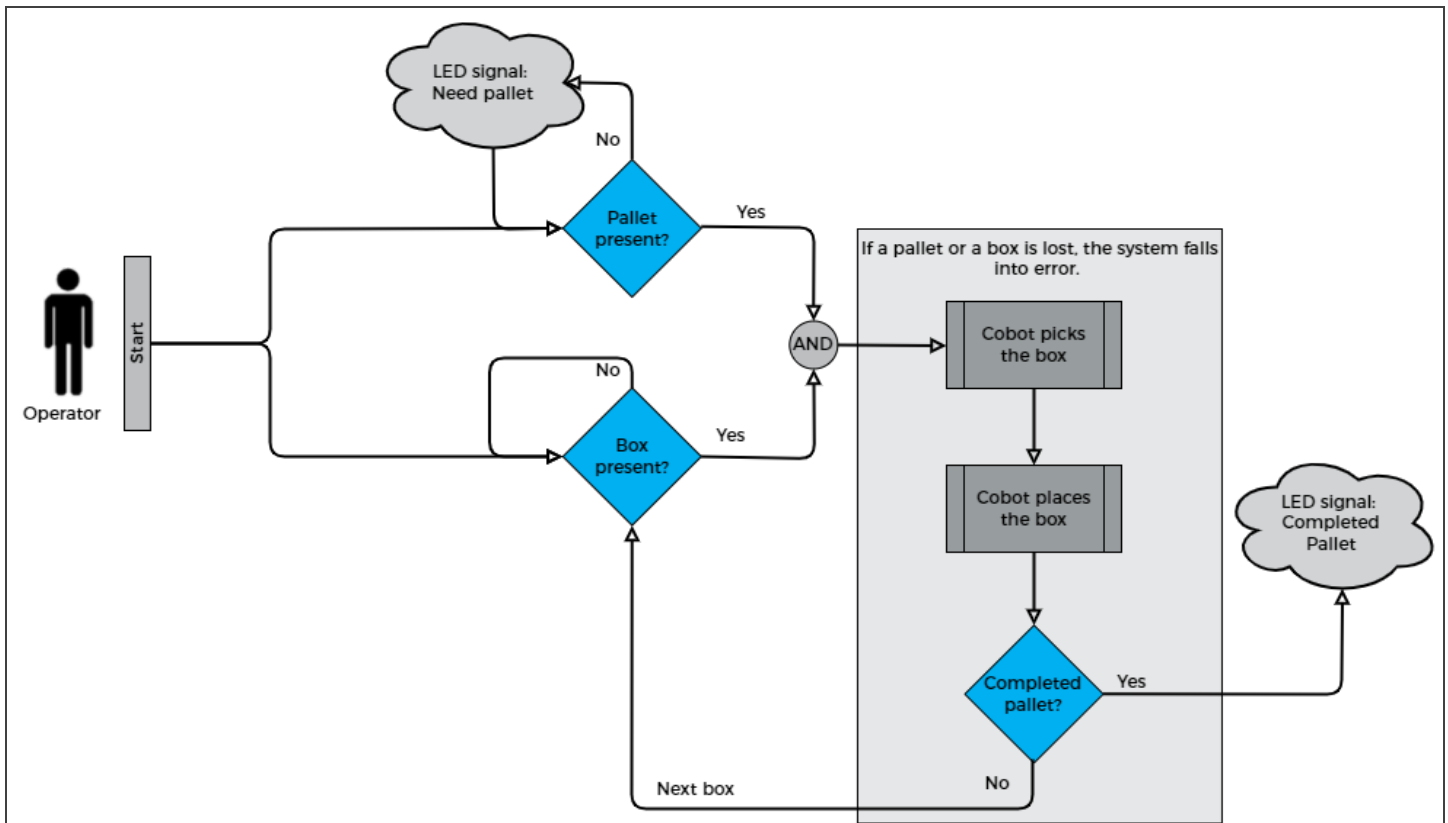
Custom brackets and plates must meet the required technical specifications (refer to the **Technical Dimensions** section).





## 1.3. Palletizing Operation Diagrams

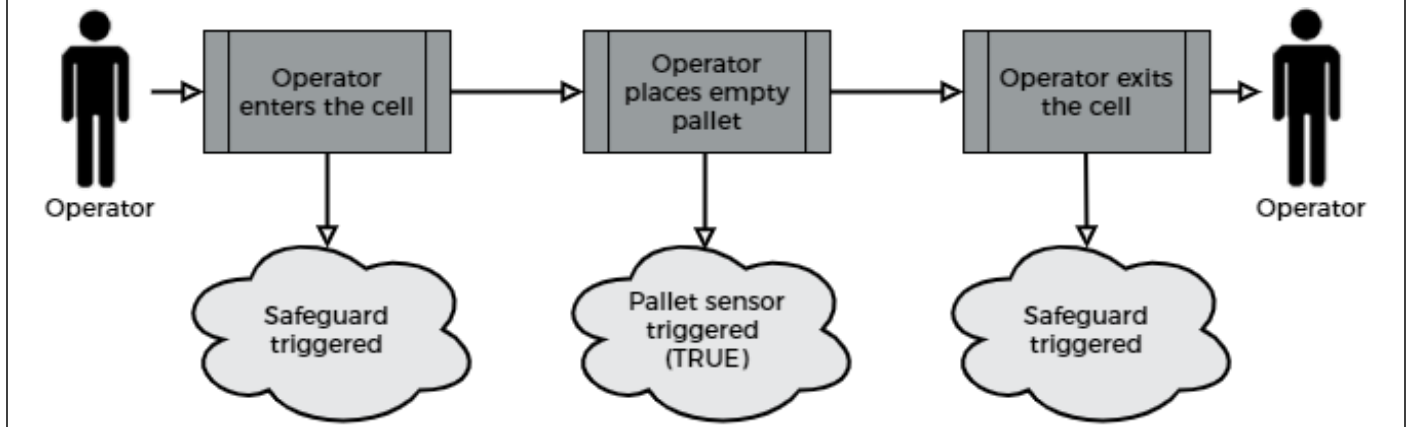
The following diagrams explain the logical operation of the Palletizing Solution based on the operator's actions, as well as responses such as signals, pallet and box sensor behaviors, etc.



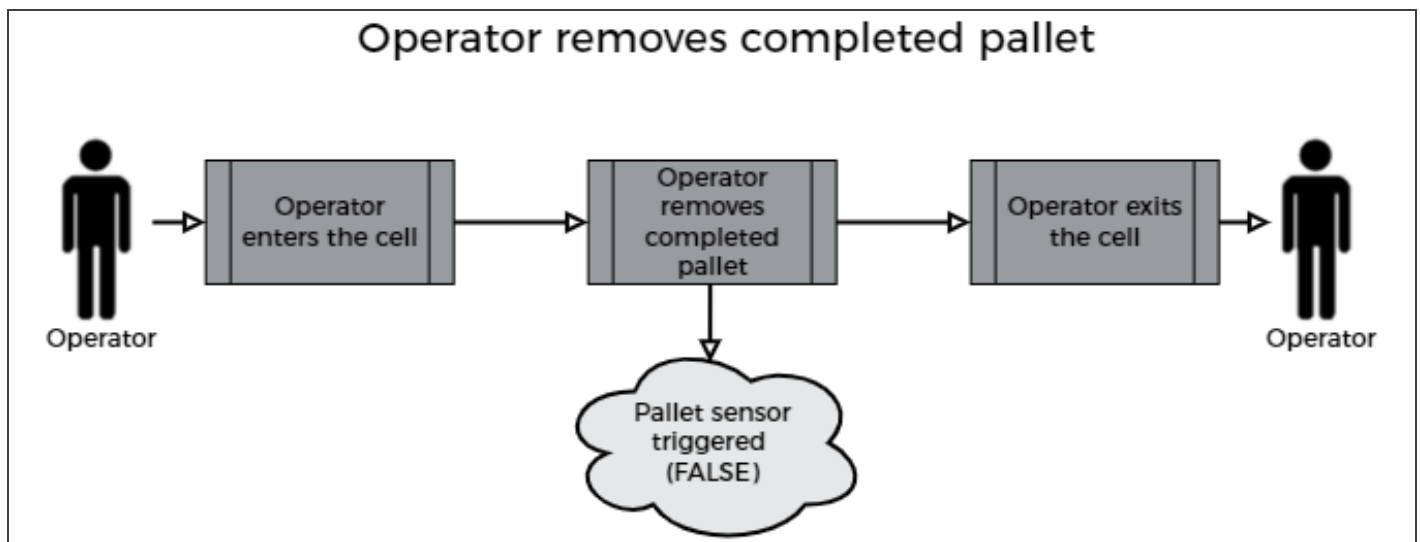
Please refer to the Status Lights section for further information about light states.



### Operator places empty pallet



### Operator removes completed pallet



## 2. Safety

### 2.1. Disclaimer

The intent of this section is to provide general guidelines for safe use of the Robotiq Palletizing Solution, always follow local regulations. The installer is responsible for the safe installation and commissioning of the Palletizing Solution. Robotiq accepts no liability for damage, injury or any legal responsibility incurred directly or indirectly from the use of this product. The user (installer and operator) shall observe safe and lawful practices including but not limited to those set forth in this document.

#### Info

The terms "operator", "installer", "commissioning" or "installation" refer to anyone responsible for any of the following operations on the Robotiq Palletizing Solution:

- Installation
- Control
- Maintenance
- Inspection
- Calibration
- Programming
- Decommissioning

The present section is based on the following international standards and technical specifications:

- **ISO 10218-1:2011** : Safety Requirements For Industrial Robots - Robots
- **ISO 10218-2:2011** : Safety Requirements For Industrial Robots - Robots Systems and Integrators
- **IEC 60204-1** : Safety Of Machinery - Electrical Equipment Of Machines
- **ISO/TS 15066:2016** : Robots and robotic devices – Collaborative robots

This manual explains various components of the Robotiq Palletizing Solution and the general operations regarding the whole life-cycle of the product, from installation to operation and decommissioning.

The drawings and photos in this manual are representative examples. However, discrepancies may be observed between the visual supports and the actual product.



## 2.2. Intended Use

The Robotiq Palletizing Solution is specifically designed for palletization.

### Warning

Only use the application in its original condition without unauthorised modifications.

### Warning

Only use the application if it is in perfect technical condition.

### Warning

The emergency stop function is intended for use in emergency conditions and not for normal condition stop.

### Info

The Solution is intended to be used with a UR10 or UR10e from Universal Robots.

### Info

Always comply with local, state, province and/or federal laws, regulation and directives automation safety and general machine safety.

### Caution

The unit should be used exclusively within the range of its technical data. Any other use of the solution is deemed improper and unintended. Robotiq will not be liable for any damages resulting from any improper or unintended uses.



## 2.3. Warnings, Risk Assessment and Final Application

### Warning

The operator must have read and understood all of the instructions in the following manual before operating the Robotiq Palletizing Solution.

### Caution

Any use of the Palletizing Solution in non-compliance with these warnings is deemed inappropriate and may cause injury or damage.

The entire cell (i.e., the robot, the AirPick Vacuum Gripper or any other gripper used, the linear axis, and any other equipment used in the final application) must go through a comprehensive risk assessment process before they can be used. Special care must be taken during this step if custom mounting options are used for the suction cups.

### Caution

It is the installer/operator's responsibility to ensure that all local safety measures and regulations are met.

The following non-exhaustive list presents risks that must be assessed during the integration process:

- Risk of load ejection resulting from loss of vacuum;
- Risk of load dropping resulting from loss of vacuum;
- Risk of pinching any moving component of the Robotiq Palletizing Solution or the robot;
- Risk of damage or breaking if using a custom suction cup bracket that does not meet the technical requirements;

Depending on the application, there may be hazards that require additional protection and/or safety measures. For instance, the workpiece handled by the gripper could be inherently dangerous to the operator.

### Warning

The linear axis is NOT power and force limited. Pinching or crushing risk must be considered seriously.



**Warning**

When the robot is not moving, the collaborative collision detection is disabled. If the linear axis moves, it can hurt people with the robot.

**Warning**

Depending on the supply sources, when an emergency stop (e-Stop) button is pressed, the following consequences may occur. The robot owner has the responsibility to do a risk assessment and choose the appropriate option.

Supply sources	e-Stop consequences
Robot tool supply (tool connector)	<p>Power failure to the Vacuum Gripper. The vacuum level will drop to ambient pressure and the object will be lost.</p> <div> <b>Caution</b>            For the Palletizing Solution, it is not recommended to connect the Gripper to the tool connector.         </div>
Robot controller supply* (Any 24V pin)	<p>Vacuum Gripper powered ON.</p> <ul style="list-style-type: none"> <li>• If an object is detected: the vacuum level will continue to be regulated and the object will not be lost.</li> <li>• If no object is detected: the Vacuum Gripper will go into a standby state 2 seconds after the e-Stop button is pressed.</li> </ul>

\*The AirPick Vacuum Gripper that comes with the Robotiq Palletizing Solution is connected via the robot controller.

**Warning**

Loss of vacuum can occur due to power failure or air supply interruption.

## 2.3.1. Expected System Behavior in Normal Operating Conditions:

- **Normal mode:** The palletizer continuously fills pallets when no human operator is within the vicinity of the palletizing cell.
- **Safeguarded mode:** The system stops when a human operator enters the vicinity of the palletizing cell to manipulate a filled pallet, place pallets in an empty pallet slot, or troubleshoot the system or any other operations requiring human intervention. In such a state the robot will maintain a Category 2 stop and the linear axis will undergo a Category 1 stop transitioning to a Category 0\* stop. When the safeguards are removed, the system will resume operation in normal mode.

**Info**

See IEC 60204-1 for definitions of stop categories.



Emergency stop mode when the emergency stop button is pressed. All components of the system will undergo stop category 1 transitioning to stop category 0.

Operation mode	Robot			Linear Axis		
	Force (N)	Power (W)	Speed (mm/s)	Force (N)	Power (W)	Speed (mm/s)
Normal mode (Up to safety limits)	up to 250	up to 1000	up to 5000	2400*	690 (nominal)	500
Protective stop	0 (Stop Cat 2)					
Safeguard stop	0 (Stop Cat 2)			N/A (Stop Cat 1 and transition to Cat 0)		
Emergency stop	N/A (Stop Cat 1 and transition to Cat 0)					
Reduced mode	Please refer to the Universal Robots user manual for more details.			The linear axis exhibits the same behavior in Reduced and Normal modes. It is not recommended to use Reduced mode since the linear axis is not safety rated for collaborative applications.		

\*Calculated using the following assumptions: static force at peak current with a 90% efficient ball screw and no friction.



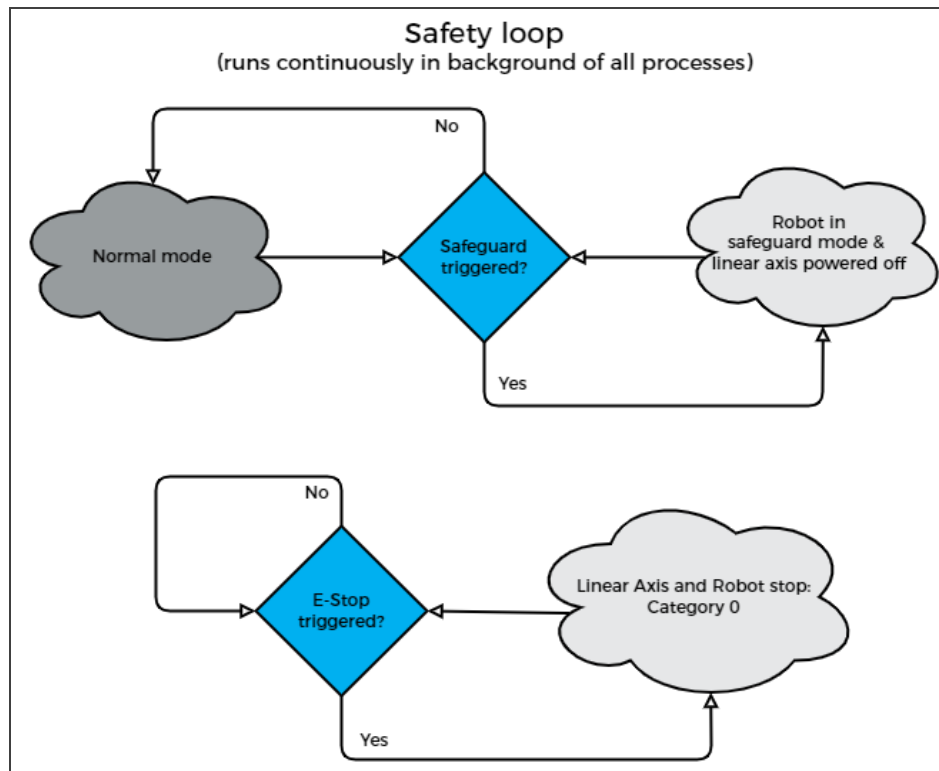


Fig. 2-1: Safety Logical Schema

### Warning

In the event of a collision or after an emergency stop, an inspection of the solution must be performed before resuming the use of the machine. Special attention must be given to the carriage assembly, the linear axis, the cable management system, and the gripper components. Please contact [Robotiq Support](#) if any sign of damage is detected.

## 2.3.2. Linear Axis Stop Category 0 and 1

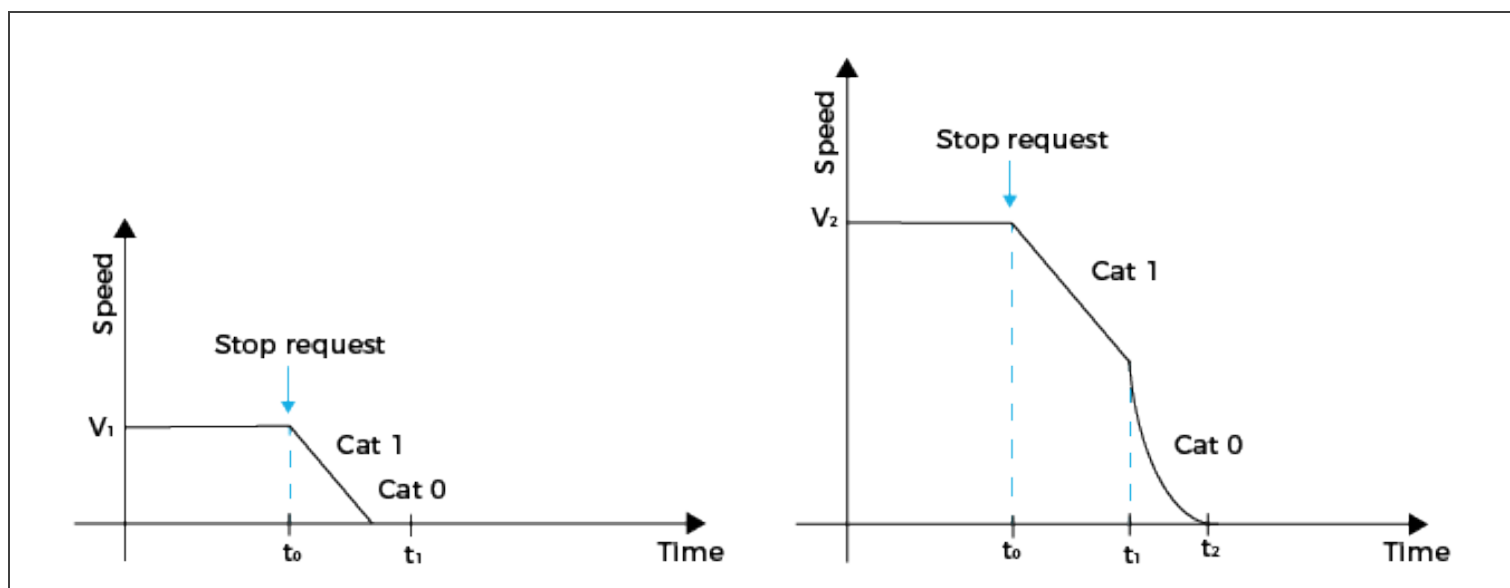
When a stop is required, the robot and the linear axis start the process at the same time, even if they are independent, so the stopping time can differ.

- For robot information, please refer to the Universal Robots documentation.
- For the linear axis:
  - Maximal stopping time for Category 1: 500 ms;
  - Maximal stopping time for Category 0: 100 ms\*;
  - Travelled distance when there is a stopping time: 33 mm (1-5/16 in)\*

\*For cases where the robot is immobile, with a payload of 8 kg and the initial speed of the linear axis is 500 mm/s, which is the maximum allowed speed.







## 3. Installation

The following subsections will guide you through the installation and general setup of your Robotiq Palletizing Solution.

### Info

Before installing:

- Read and understand the safety instructions related to the Palletizing Solution.
- Verify your package according to the scope of delivery and your order.
- Make sure to have the required parts, equipment and tools listed in Scope of delivery.

### Warning

When installing:

- Meet the recommended environmental conditions.
- Do not operate the Palletizing Solution, or even turn on the power supply, before the device is firmly anchored and the machine area is cleared. Make sure that the air supply is secured.

### Warning

Failure to properly secure and install the equipment can result in material damage and bodily injury. In addition, note that in situations where the installation is not compliant, the warranty is void.

### Warning

When assembling or moving the Solution, make sure there is enough vertical and horizontal clearance all around so you can avoid material damage and bodily injury.



### Warning

- Make sure to follow all the safety rules and regulations of your workplace while using the Robotiq Palletizing Solution.
- Always wear all recommended personal protective equipment in accordance with your workplace's safety standards, including:
  - Safety glasses;
  - Hearing protection;
  - Hard hats;
  - Steel-toe boots
- Always use proper safety precautions when working with tools that contain sharp edges, pinching surfaces, or generate heat.
- Always lift heavy objects with your legs, not your back. If you can not lift an object alone, ask for help or find another method to move it.

## 3.1. Scope of Delivery

- 1 x AX Series Palletizing Solution base including:
  - 1 x Linear axis (1500 mm stroke)
  - 1 x Motor
  - 1 x Linear axis Controller
  - 4 x Pallet sensors
  - 2 x Status lights
  - 1 x Cable management system
- 6 x 1/2" - 13 concrete anchors
- 1 x Box detection sensor
- 1 x Extra reach bracket for end-of-arm tooling
- 1 x Vacuum Gripper kit (Airpick, suction cups, brackets for 2 or 4 cups) (Optional)
- 1 x Gripper coupling kit (Optional)
- 1 x 8 mm air tube (already mounted on the column)
- 1 x Material Handling Copilot software license dongle
- 1 x Set of four (4) casters



## 3.2. Required Tools and Equipment

The following tools are required to install the Palletizing solution.

Included:

- 12.7 mm (1/2 in) concrete drill bit (for use with hammer drill)
- 19 mm (3/4 in) socket, 10 mm (3/8 in) drive size
- 17 mm socket, 10 mm (3/8 in) drive size
- 2 mm hex key
- 3 mm hex key
- 4 mm hex key
- 5 mm hex key
- 6 mm hex key
- 10 mm hex key

Not included:

- Lifting equipment (min. capacity of 200 kg) such as a gantry crane, overhead crane, jib crane, chain block or forklift with a proper lifting hook
- Power screwdriver
- #2 Phillips bit
- 2.5 mm slotted screwdriver
- Utility knife
- Ratcheting socket wrench with 10 mm (3/8 in) drive or adapter
- Torque wrench with 10 mm (3/8 in) drive or adapter, minimum torque range of 20 - 50 Nm (14.8 - 36.9 ft-lb)

Additionally, if you decide to install the type of anchors provided by Robotiq, you will need the following:

- Hammer drill
- Hammer



### 3.3. Environmental and Operating Conditions

Conditions	Value
Minimum storage/transit temperature	-25°C [-13°F]
Maximum storage/transit temperature	60°C [140°F]
Minimum operating temperature	0°C [32°F]
Maximum operating temperature	50°C [122°F]
Humidity (non-condensing)	20-80% RH, non-condensing
Food/ Clean room/ Intrinsic Safety (IS)	No
Dust and water	<ul style="list-style-type: none"> <li>• Dust: Affect the time between maintenance</li> <li>• Water : No</li> </ul>
Other	<ul style="list-style-type: none"> <li>• Free from corrosive liquids or gases</li> <li>• Free from explosive liquids or gases</li> </ul>

Table 3-1: Environmental and operating conditions of the Robotiq Palletizing Solution

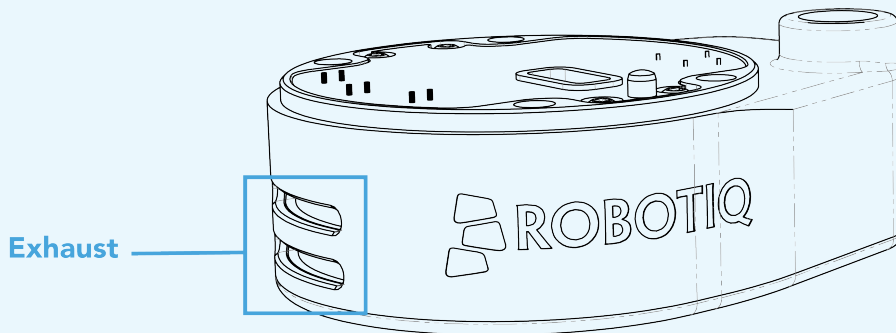
#### Caution

Use of the Robotiq Palletizing Solution is not recommended in presence of chemicals in the environment.

#### AirPick Gripper Info

The input filter prevents any dust larger than 200 µm from getting inside the gripper. Dry dust will prevent the accumulation on filters. The use of suction cups with integrated filter can be used to reduce dust accumulation.

The exhaust must not be blocked.



### 3.3.1. AirPick Gripper Air Supply

Compressed air must be supplied to the Vacuum Gripper according to the technical specifications. For maintenance and other purposes, it is recommended to install a lockout valve before connecting to the product. The air supply tubing must be connected and disconnected to, or from, the inlet port, only when the line is depressurized. When the line is pressurized, the safety clip must be at all times installed on the inlet port.

To protect against whipping hazard, the air supply tubing must be securely attached to the robot arm. An air fuse should also be installed.

### 3.3.2. Depressurizing the Supply Line

In order to safely depressurize the supply line, the air supply must first be shut off. Then, if no lockout valve is present to depressurize the line, the AirPick Gripper can be activated until the pressure is fully released.

## 3.4. Mounting and Installation

### 3.4.1. Visual Inspection

The Robotiq Palletizing Solution is shipped on a pallet. A wood crate is protecting the hardware from external elements.

Since the crate weighs 317 kg (697 lb), Robotiq recommends using a pallet truck or forklift truck to move it. The operation of such machinery should be done by qualified and authorized personnel.

#### Caution

Before disassembling the crate, inspect it to make sure there is no damage or defect. If damage or defects are discovered, please contact the [Robotiq support team](#).

### 3.4.2. Unboxing

#### Tip

A minimum of two people is recommended to perform the following steps.

#### Warning:

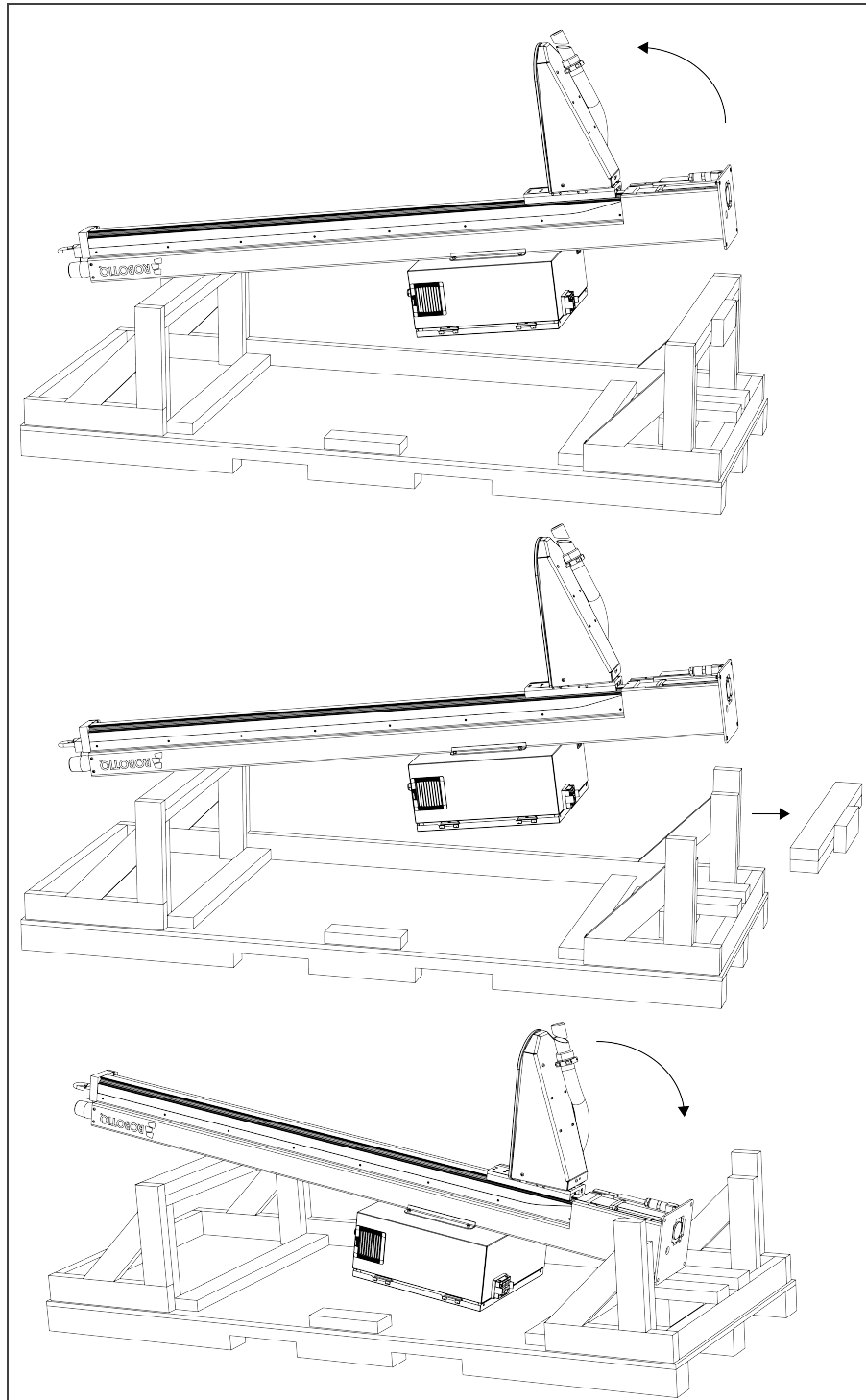
The transport, lifting, and moving of the Robotiq Palletizing Solution should be performed by qualified and authorized personnel. Failure to do so may result to material damage, bodily injury or death.

#### Warning

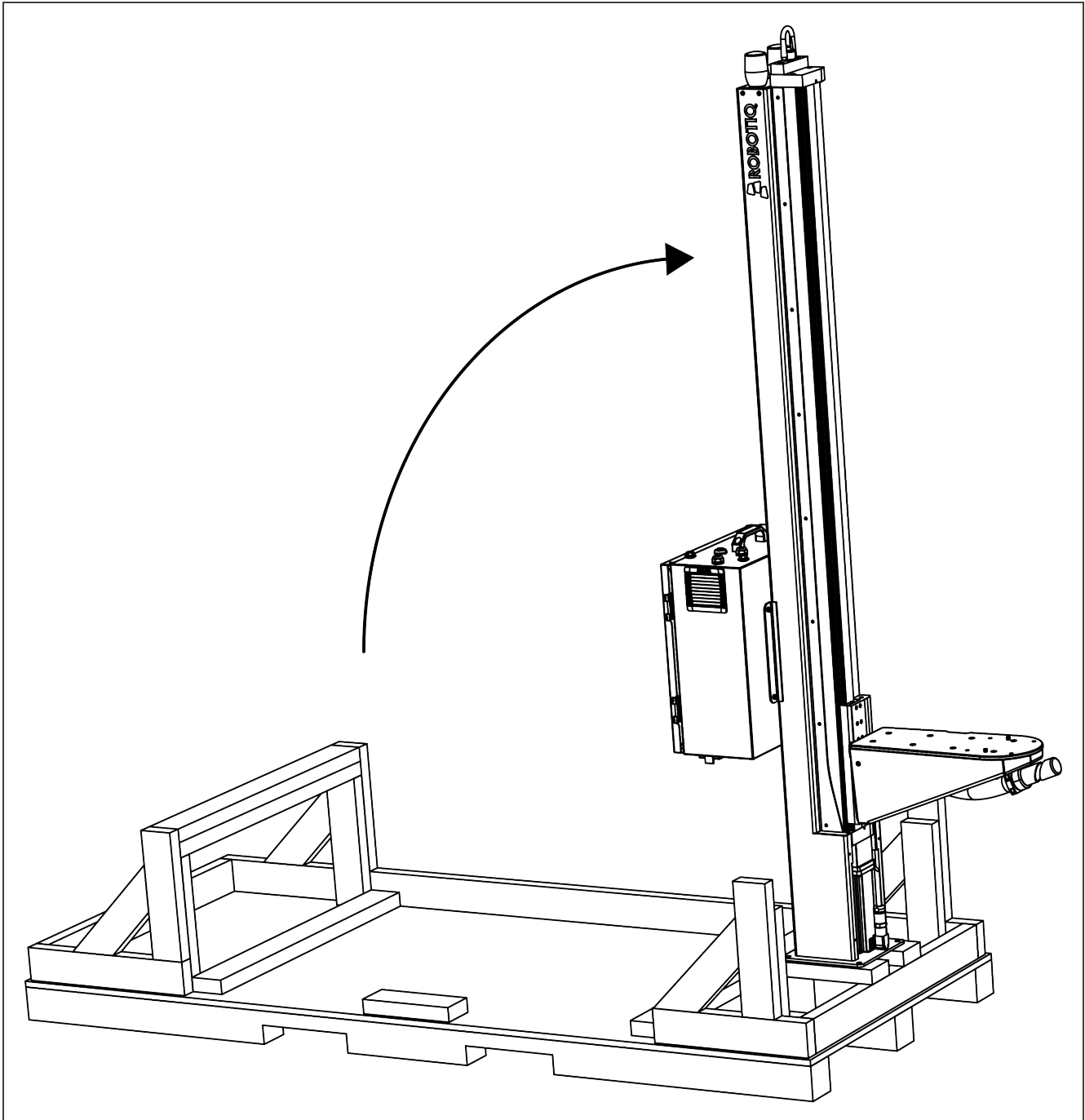
**Crush Hazard:** Keep your hands and body parts clear when lowering the column onto the base. Failure to do so could result in serious injuries or death.



1. Remove the top panel and the four (4) sides of the crate by unscrewing the screws that hold them into place.
2. Cut all the strapping material that retains the components, and take all cardboard boxes out of the crate.
3. Unscrew the four (4) bolts that retain the base into the crate.
4. Take the base out of the crate.
5. Unscrew the two (2) bolts that retain the column into the crate.
6. Lift the foot base, unscrew the piece of wood under the foot base. Remove the piece of wood and descend the Solution slowly and carefully (see the picture below).



7. Position the column vertically. Use the lift point to rotate the column.

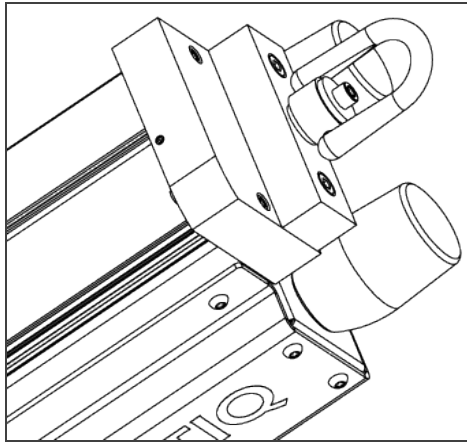


### Caution

Be careful not to pinch the cables. If necessary, secure them before lifting and placing the column on the base.





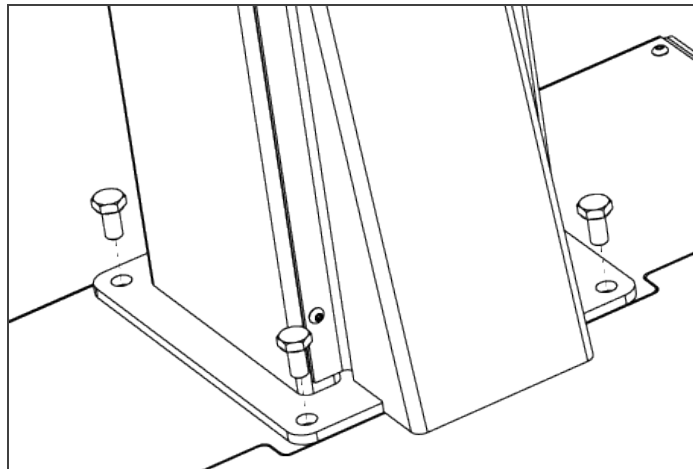


8. Lift and place the column onto the base.

**Info**

A hook is present at the top of the column. Use it to lift the column.

9. Secure the column on the base using the four (4) M10 screws provided. Tighten to a torque of 50 Nm.

**Caution**

Make sure to have all components in hand before discarding the crate and packaging.



### 3.4.3. Moving and Positioning the Solution

#### Warning

Failure to properly secure and install the equipment can result in material damage and bodily injury. In addition, note that the warranty will not cover material damage resulting from an installation that did not comply with the instructions found in this manual.

#### Warning

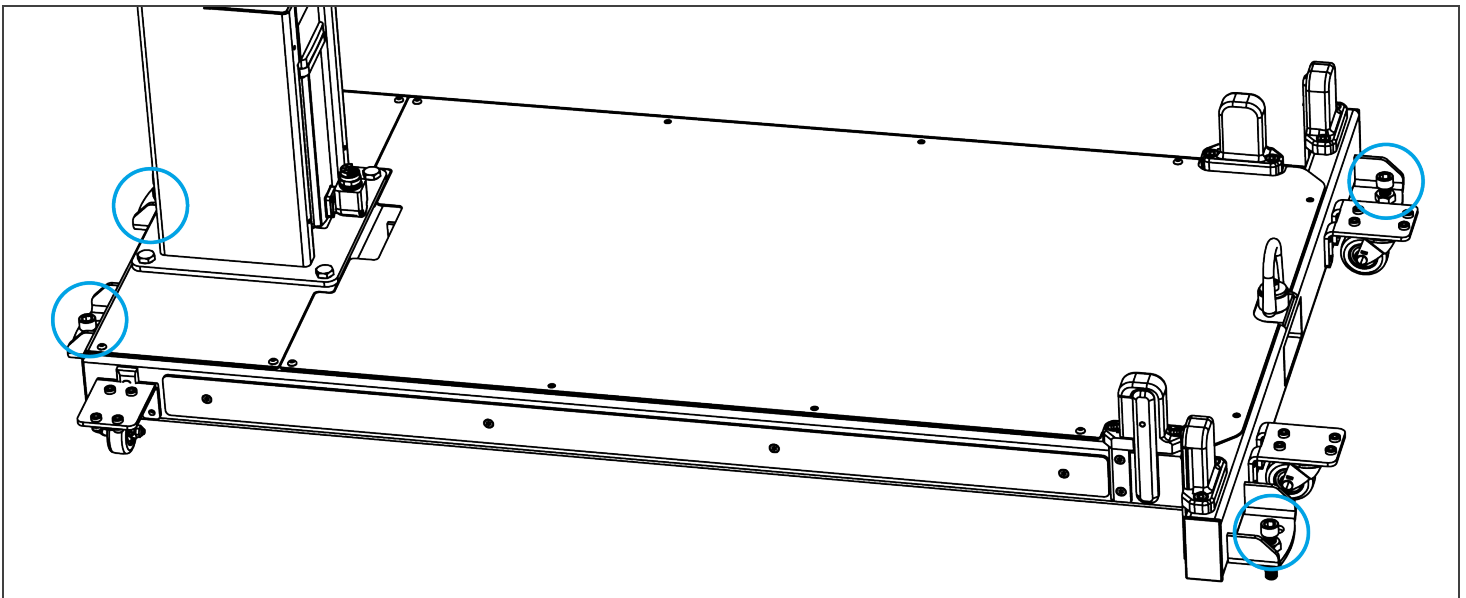
The transport, lifting, and moving of the Palletizing Solution should be done by qualified and authorized personnel. Failure to do so may result in machine damage, bodily injury or death.

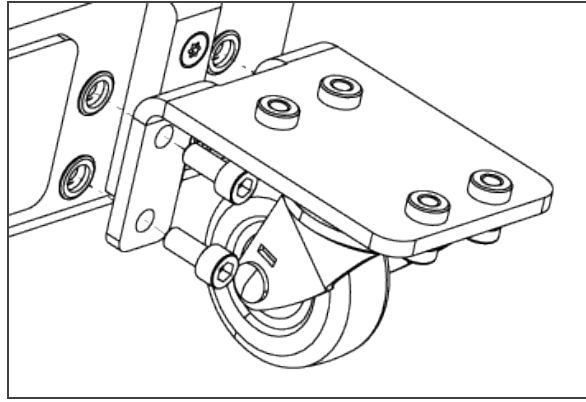
Although you can assemble the solution at the place of your choice, you will need to move it to its final location afterwards. You can use one of the two following methods to securely move the Solution:

1. Using a forklift. Pay attention to the center of gravity to prevent the equipment from tipping over. Make sure to secure and stabilize the Solution before moving it.
2. Using the set of casters provided with the Solution. To install them, screw the four (4) corner bolts highlighted in the image below to lift the Solution. Screw the four (4) casters into the base. Unscrew the corner bolts to set the solution down on its casters.

#### Warning

The casters are not designed to support the weight of the whole Solution. Do not install the robot before moving the Solution on its casters.





#### Caution

Do not use the Solution while it stands on its casters. To make the Solution stand upright, simply screw the four (4) corner bolts, remove the casters and unscrew the corner bolts.

### 3.4.4. Mechanical and Electrical Installation

#### Tip

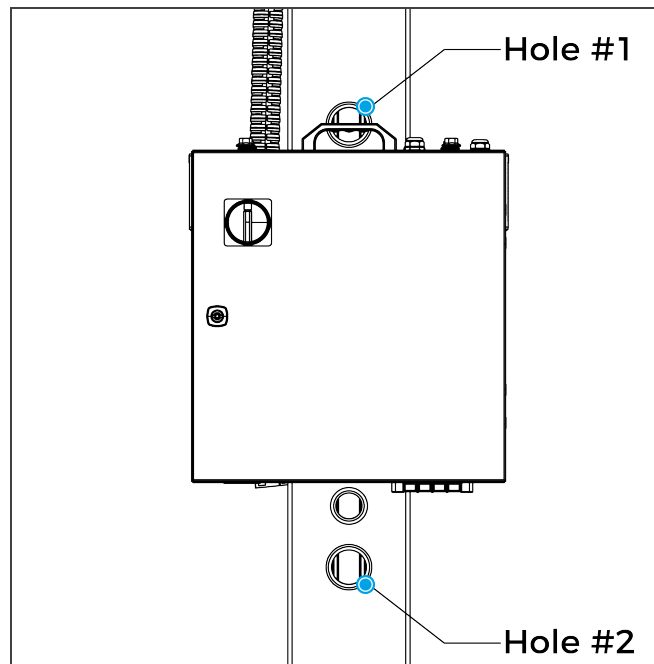
A minimum of two people is recommended to execute these steps.

### Robot Installation

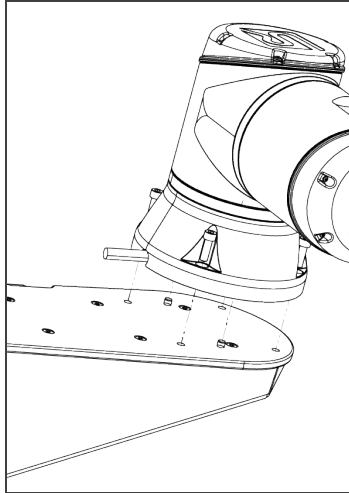
#### Info

A UR10 or UR10e cobot is required for the installation. The cobot is not included in the Robotiq Palletizing solution.

For robot installation, few cables need to be wired. The figure below resumes the identification of the column holes.



1. Place the robot on the robot base plate so its power cable is oriented towards the linear axis. Align properly with the two dowel pins (already installed on the robot base), and secure the robot using four (4) M8 screws and Belleville washers.  
**The required torque value is 20 Nm.**

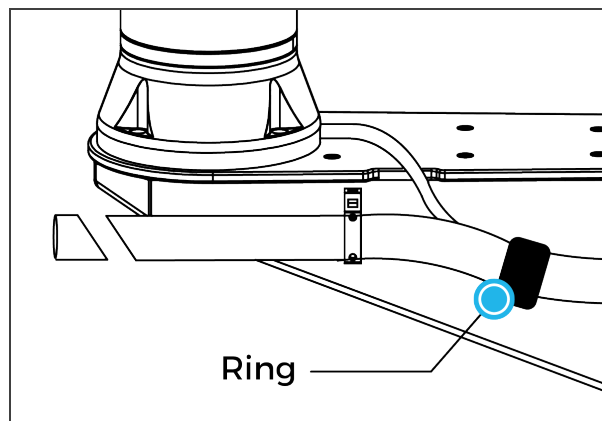


### Caution

Depending on your cobot, make sure to install screws of the right size:

- For e-Series UR: M8 x 25 mm
- For CB-Series UR: M8 x 22 mm

2. Unclip the mounting bracket of the cable management system that is right beside the column.
3. Press the robot power cable into the cable carrier up to the column. There are two separate raceways. You must use the same section as the coupling cable. Push the cable into the column (via the side hole) and bring it out by the hole #1.
4. Install the cable management system ring on the B sticker present on the cable carrier (near the carriage). The robot cable must emerge towards the top of the ring so it can be maintained (see the picture below).



5. Install the Igus R-Lock at the extremity of the cable management system before clipping the cable carrier in the bracket (on the A sticker). It will ensure the good functionality of the cable management.

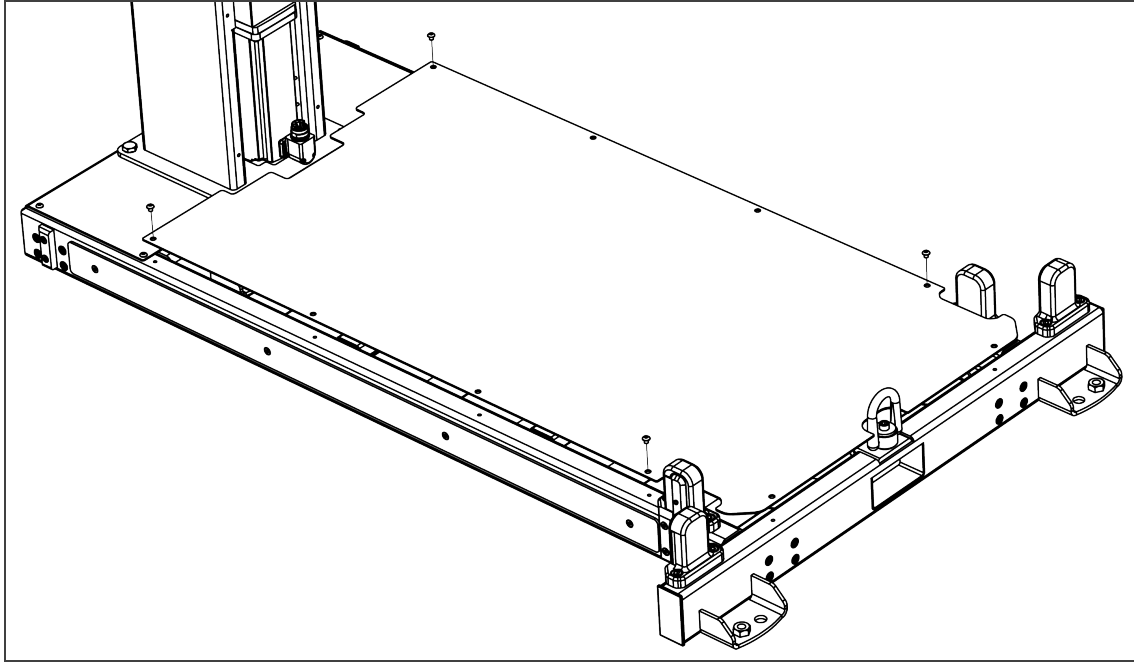
### Info

Refer to the Igus triflex® R Series TRE.40B cable routing system installation instructions for more details.



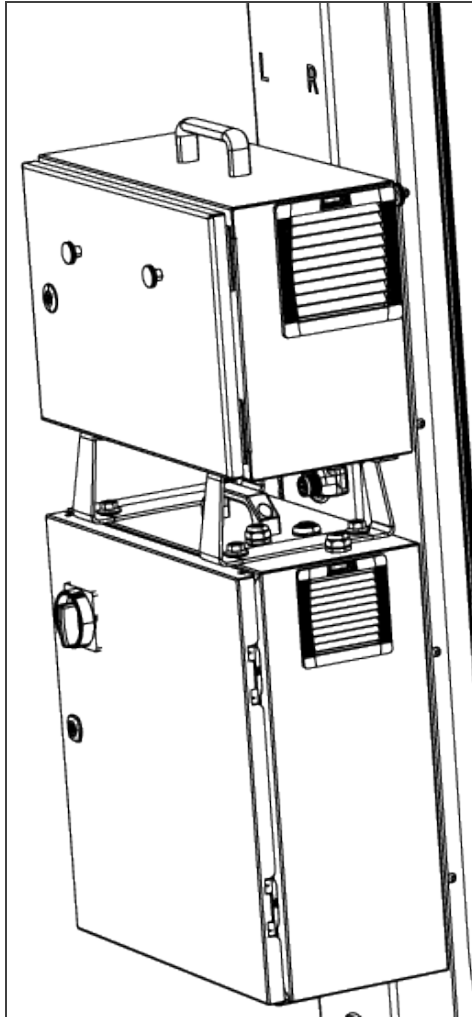
## Base Cover Plate

1. Remove the cover plate that will allow the cable management.



## Universal Robots Controller Installation

1. Remove the four screws on the top of the linear axis controller.
2. Place the UR controller on top of the linear axis controller and secure it with the four screws you previously removed.



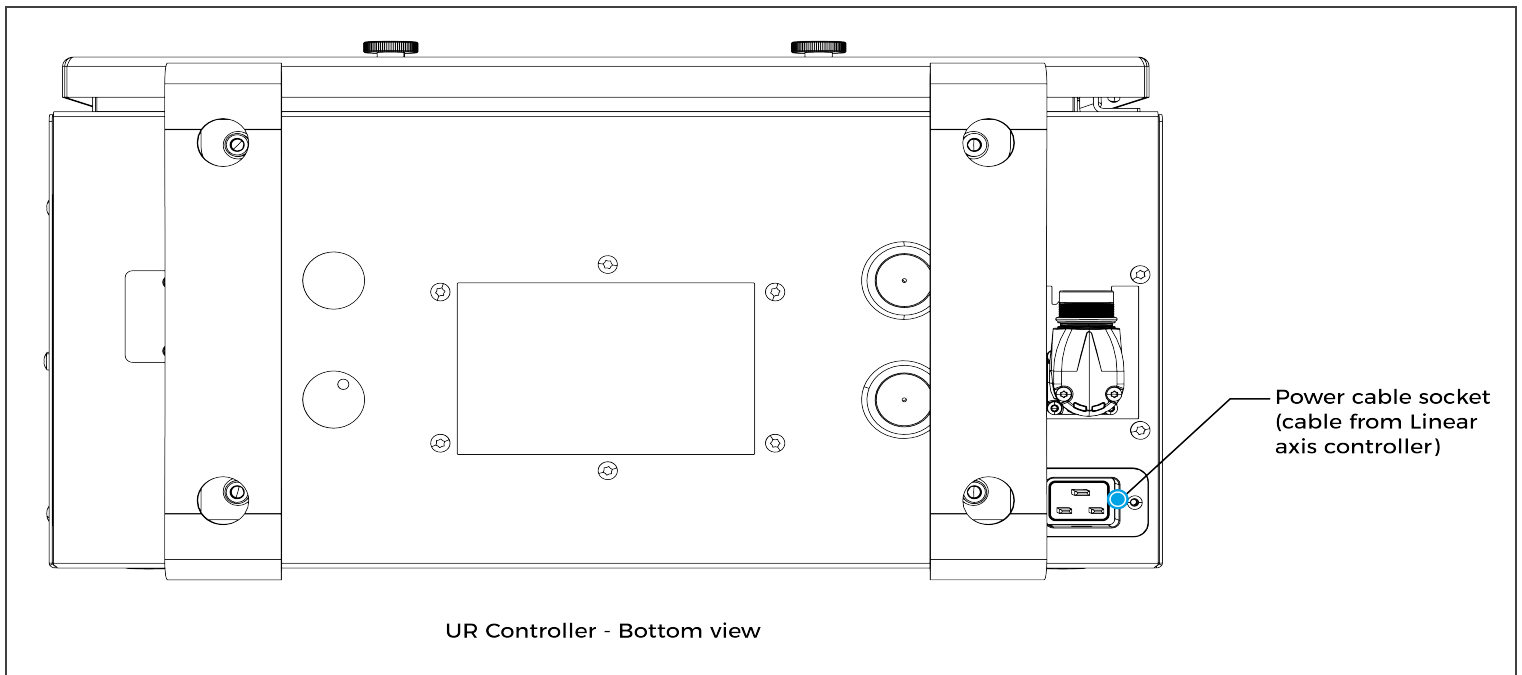
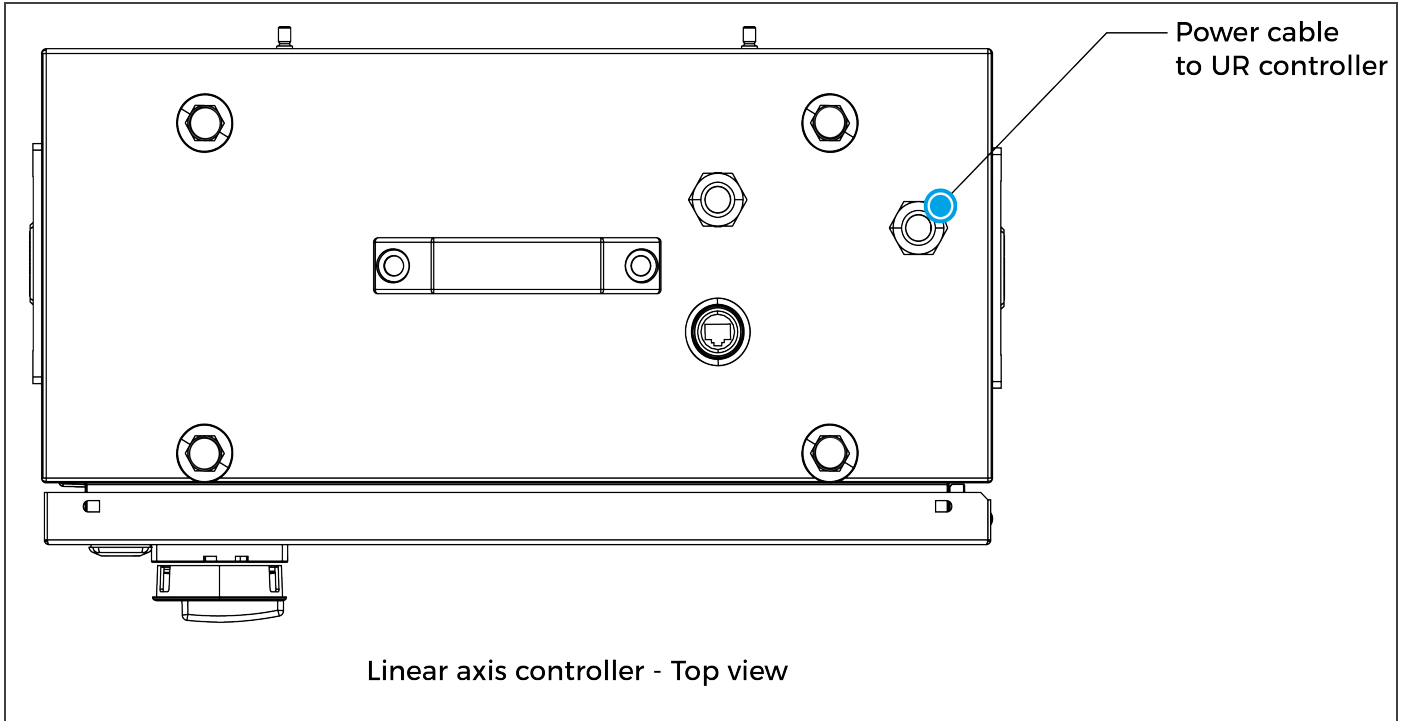
### Caution

Do NOT plug the UR controller power cable into UR controller .



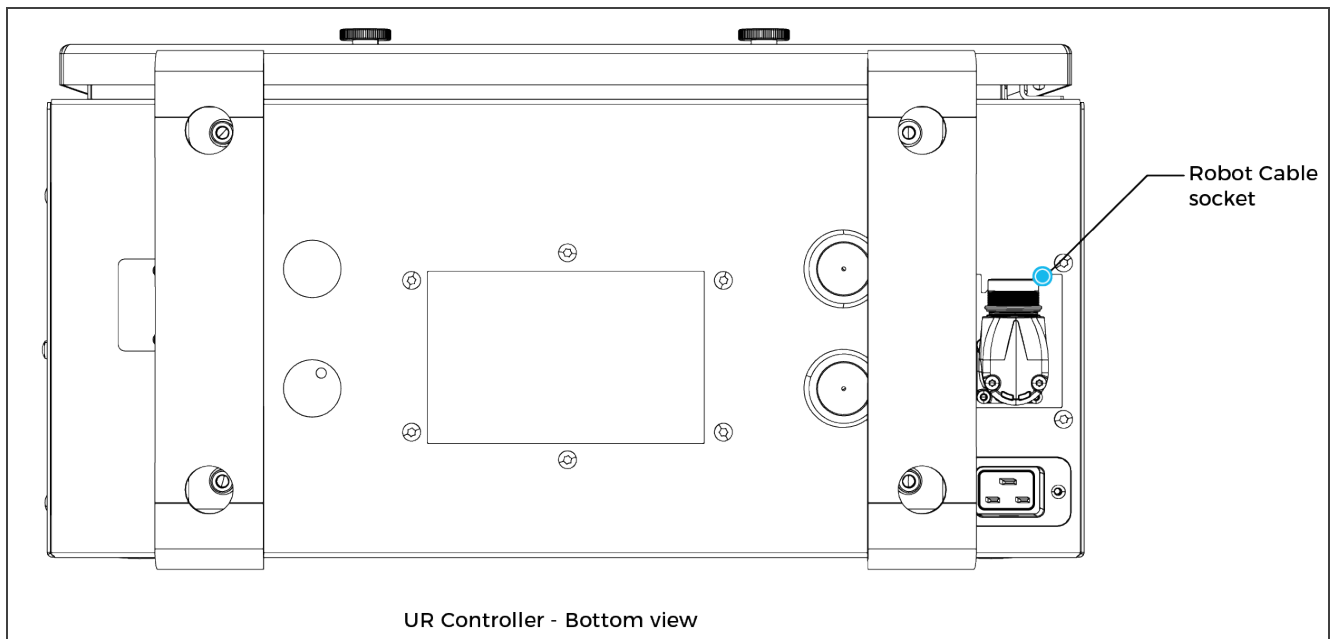
## Power Cables Connections

1. Plug the power cable output of the linear axis controller into the UR controller.



2. Plug the robot power cable into the UR controller.
3. Connect the Teach Pendant to the UR controller.

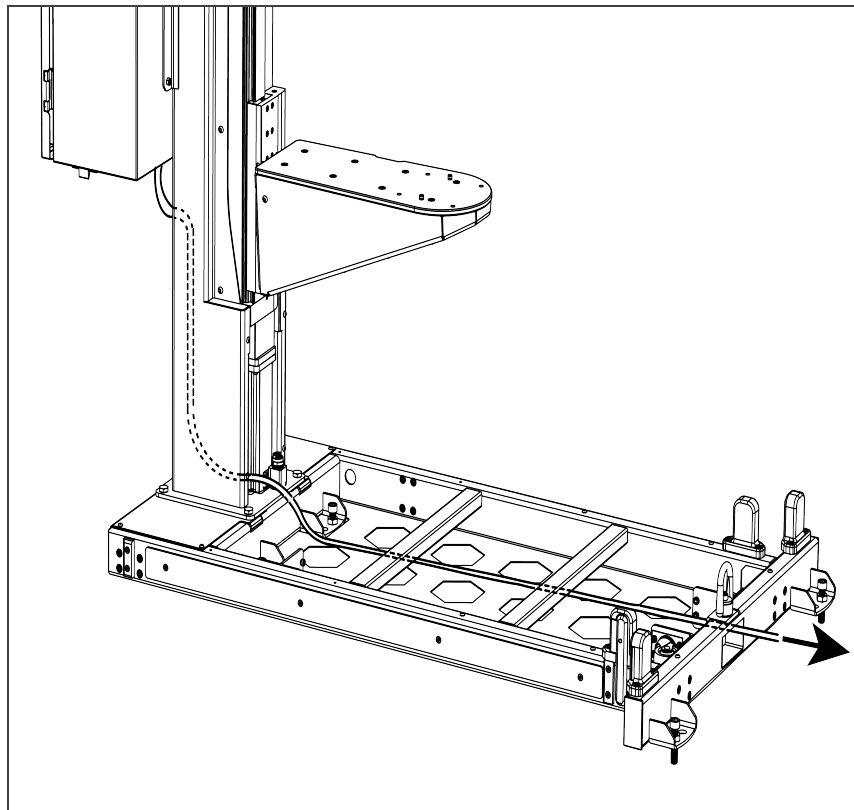




4. Plug the UR controller power cable into the linear axis controller. Pass the cable through the hole #2. Then, continue to channel the cable through the column and the base and bring it out from the other extremity of the base.

#### Info

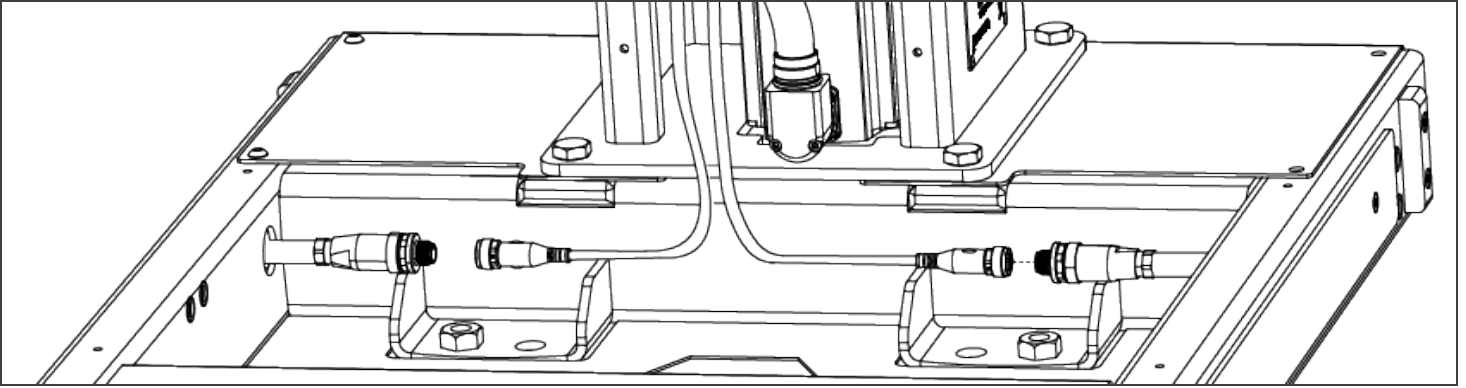
The safety signals wires sticking out of the linear axis controller are inputs only. Therefore, you can power the control box safely even if they are not yet connected.





## Pallet Sensors and Base Cables Routing

1. Connect the pallet sensors. The cables are identified for each side. Make sure to connect each pair of cables correctly.



2. Bring out the air tube and the box sensor cable from the bottom of the column and continue to channel it until you bring it out from the other extremity of the base (through the rectangle hole).
3. Plug the power cable into the wall outlet.

## Centering the Solution

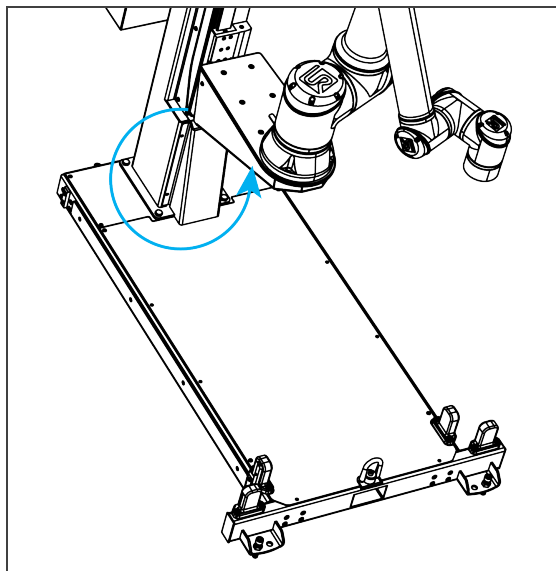
This procedure needs to be done before the AirPick Vacuum Gripper installation. It will ensure proper functioning of the solution. The goal is to properly align the column with the base by placing the robot wrist at a specific position at the same time as it touches the side of the base.

1. Unscrew half a turn the four (4) screws that secure the column onto the base.

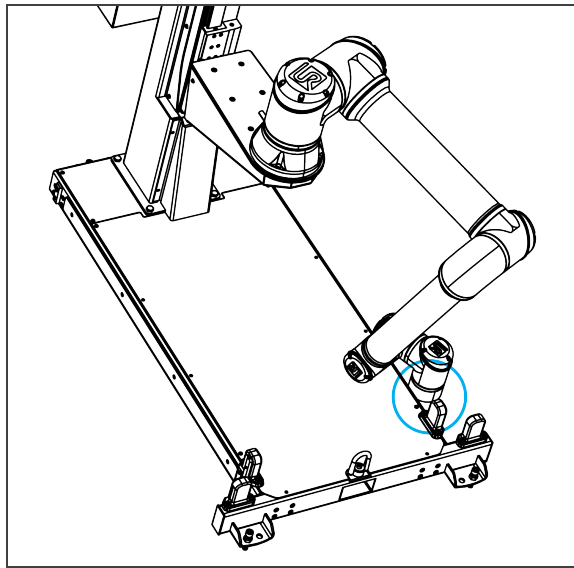
### Warning

Do not unscrew completely. Unscrew only half a turn to be able to change the orientation of the column. Completely untightening the screws can cause the column to fall and cause bodily injuries and material damages.

2. Rotate the column counterclockwise as much as possible.



3. Position the robot so that the wrist is on the outside left side of the base like shown in the figure below.

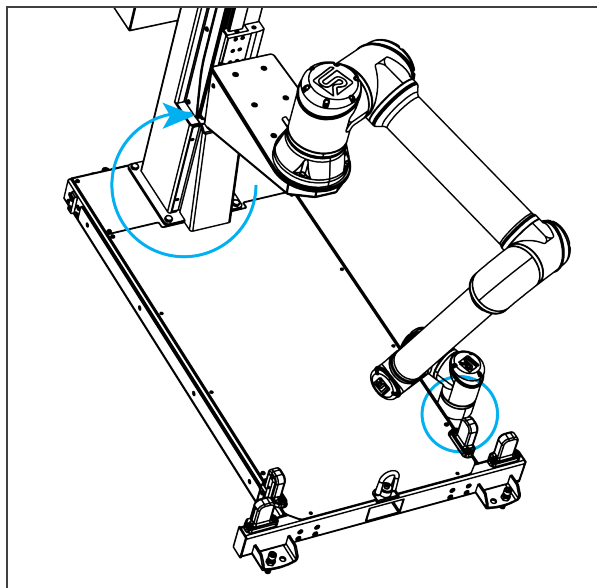


4. Move the robot so the robot tool flange is parallel to the ground: change the feature reference to Base and modify the tool position like the following:  $RX=0^\circ$ ,  $RY=180^\circ$ ,  $RZ=0^\circ$ .
5. Modify the Tool Position X value (base reference) to 333.35 mm (Make sure the TCP is set to 0 (the TCP menu can be found in the Installation tab.))

### Warning

Move the robot slowly and watch the movement to avoid collisions.

6. Rotate the column clockwise so that the side of the robot wrist touches the side of the base.



7. Tighten the four (4) screws to secure the column onto the base. **Torque must be 50 Nm.**
8. On the teach pendant, validate that the X value is still 333.35 mm.
9. Put the robot back in position of use.



## AirPick Vacuum Gripper Installation

To be able to mount the AirPick Gripper, its accessories, as well as the cable routing system, power on the robot and rotate the joints, as described in the table below. Then, shutdown the robot

Joint	Position
Base	-180°
Shoulder	-155°
Elbow	-60°
Wrist 1	-80°
Wrist 2	270°
Wrist 3	-180°

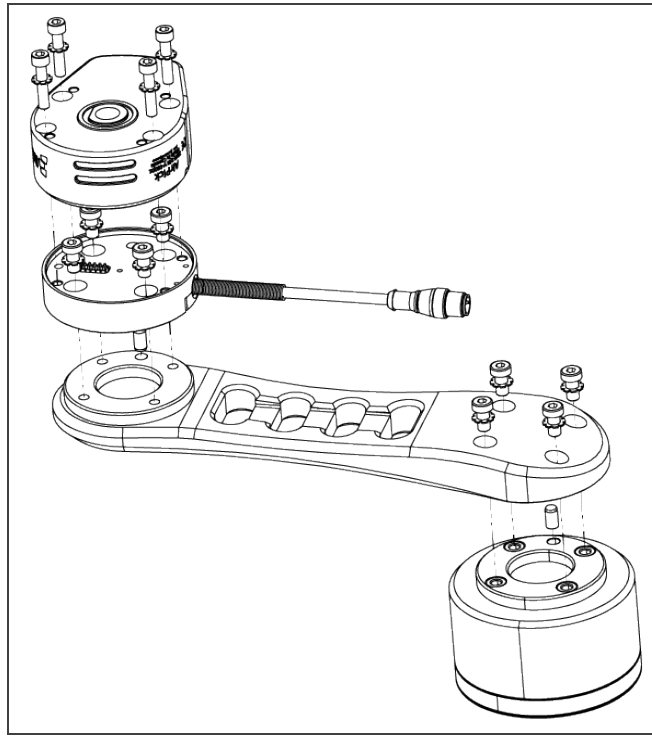
1. If additional reach is needed, install the extra reach gripper bracket on the robot tool flange using four (4) M6 screws and tooth lock washers and align properly with the dowel pin.

### Info

Install the bracket only if necessary. Consult the [Configurator](#) to find out if it is needed in your case.

2. Using four (4) M6 screws and tooth lock washers, secure the coupling on the robot tool flange or on the extra reach gripper bracket .
3. Mount the Vacuum Gripper on the gripper coupling. Align with the dowel pin.
4. Secure by inserting the M5 screws and tooth lock washers.



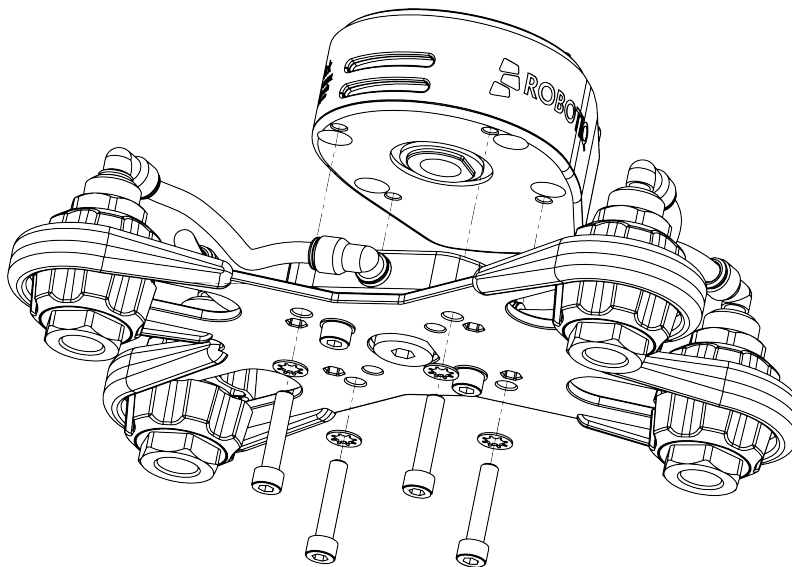


If the two or four suction cups bracket is needed:

1. Align the flat surface on the manifold with the shoulder of the vacuum generator.
2. Secure the manifold by inserting screws and tooth lock washers in a cross pattern to properly compress the O-ring of the generator.
3. Insert each suction cup, with an O-ring, into an air node. Tighten cups by hands.

### Warning

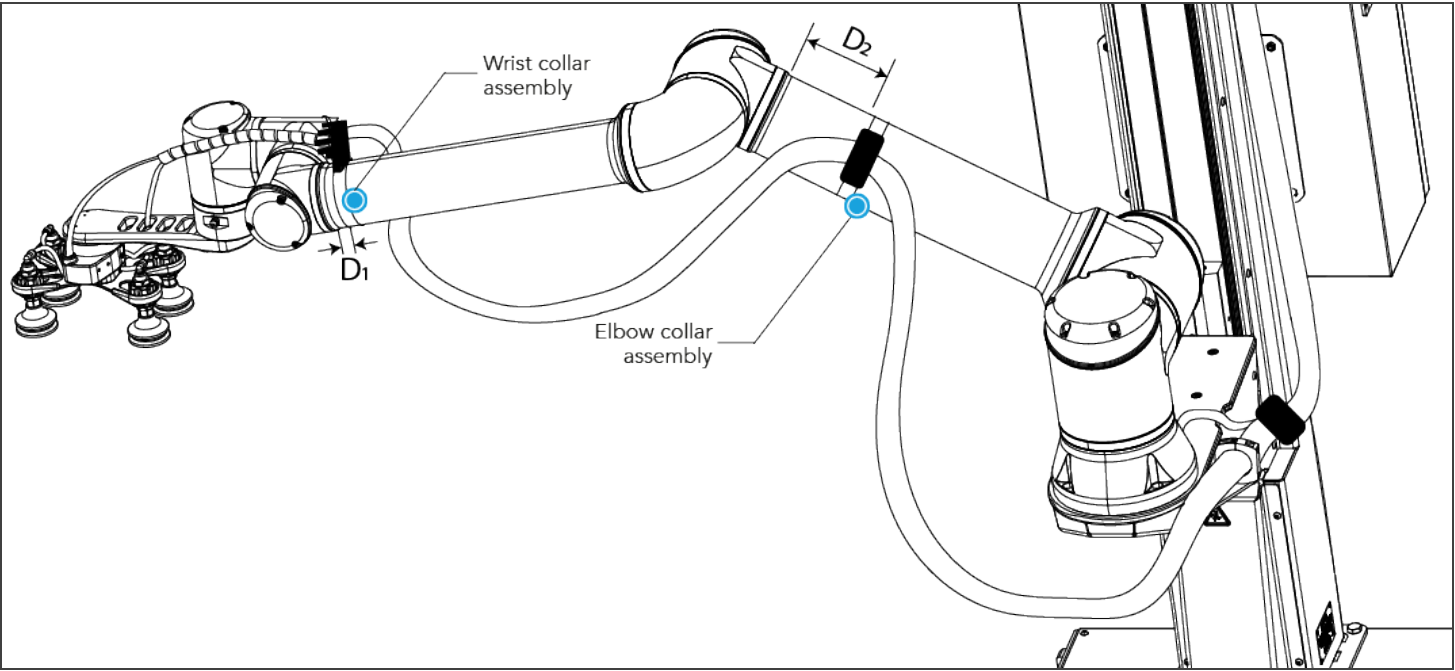
Any unused manifold port should be covered with a provided port plug to avoid air leakage.



To finish the installation, change the robot position. Refer to the table below:

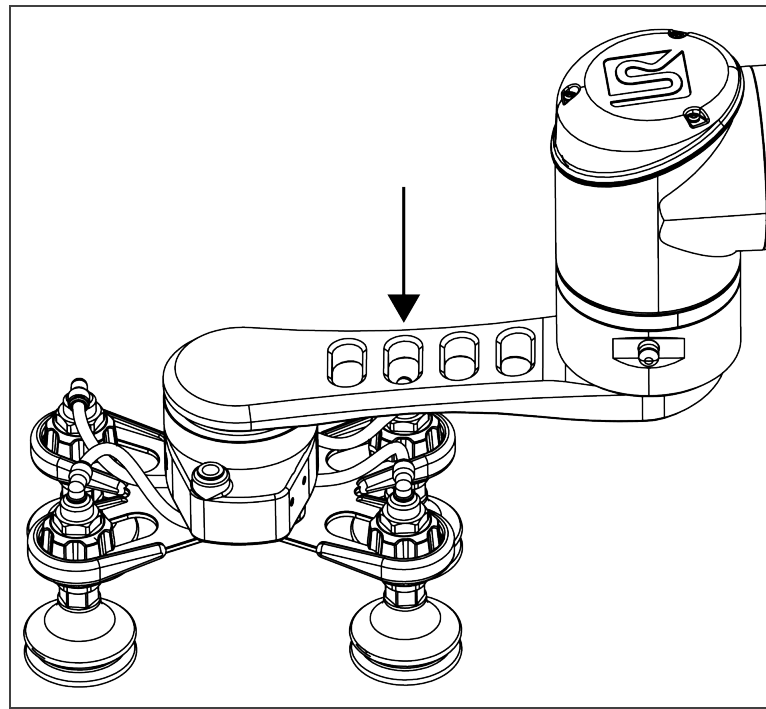
Joint	Position
Base	-180°
Shoulder	-155°
Elbow	-60°
Wrist 1	-80°
Wrist 2	90°
Wrist 3	-90°

1. Attach the Igus triflex® R Series (TRE.40B) cable routing system to the robot, as illustrated in the figure below:
- Using a 5 mm hex key, secure the elbow collar assembly (larger collar) to the arm. Account for the orientation and distance from the elbow ( $D_2$ ).
  - Clip the mounting bracket of the elbow collar assembly on the cable carrier (align the bracket with the sticker shown in the chart below).
  - Using a 5 mm hex key, secure the wrist collar assembly (smaller collar) to the arm. Account for the orientation and distance from the wrist ( $D_1$ ).

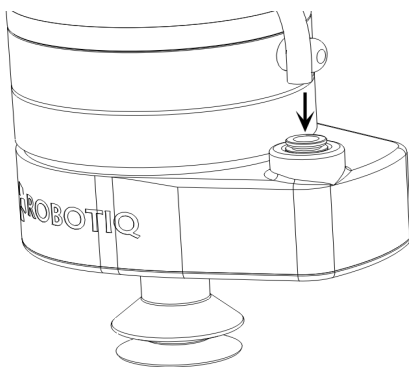


Robot model	Elbow bracket sticker	$D_2$	Wrist bracket sticker	$D_1$
UR10	D	180 mm	E	10 mm

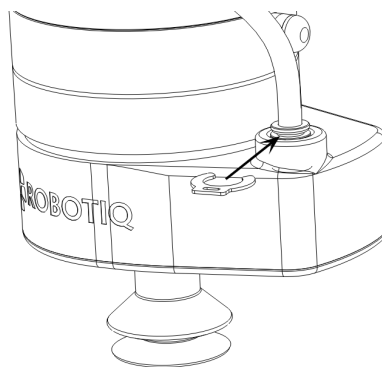




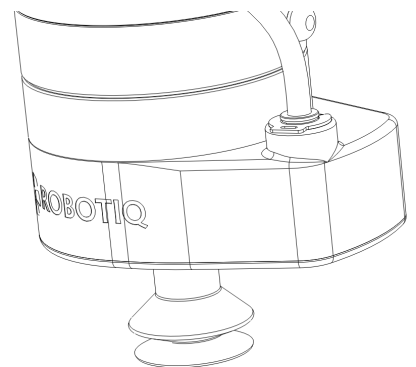
2. If you use the extra reach bracket, make sure to first run the coupling cable through the second hole of the bracket.
3. Connect the coupling cable to the connector visible at the end of the cable carrier.
4. Install Igus R-Lock clips at the end of the cable carrier before clipping it in the bracket. It will ensure the good functioning of the cable management system.
5. Clip the mounting bracket of the wrist collar assembly on the cable carrier (align the bracket with the sticker shown in the previous chart).
6. Use cable ties to attach the tubing and cable to the strain relief part of the mounting bracket. Make sure not to crush the tubing or the cable with the cable ties.
7. Cut the air tube at the right length (815 mm / 32 in) past the plastic strain relief.
8. Connect the 8 mm air tube to the vacuum generator. Follow the steps below:

**Step #1**

Insert the air tube in the AirPick port

**Step #2**

Insert the safety clip

**Step #3**

Ensure the safety clip is properly installed



**Caution**

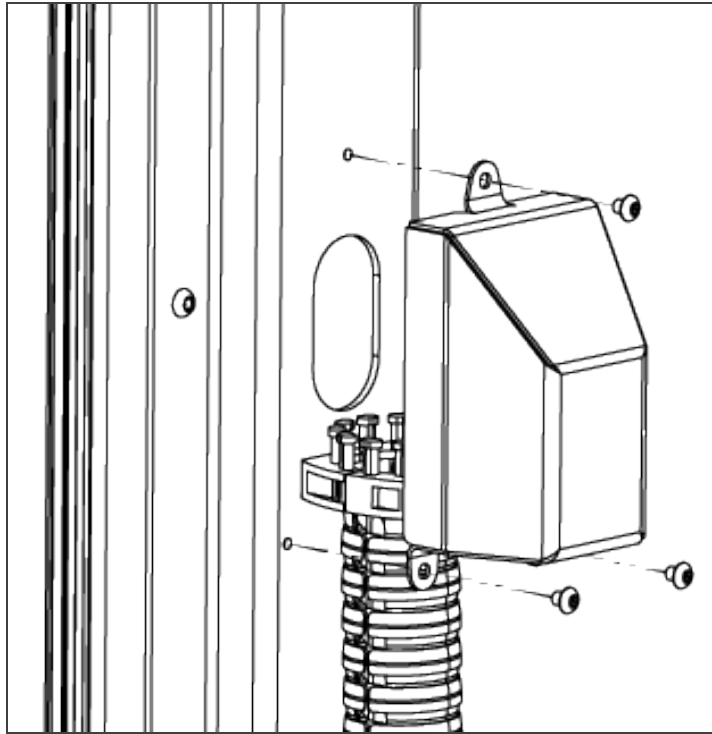
Use dry and filtered air only. Follow the **ISO 8573-1, class 3.4.3** standard. We recommend using a local pressure regulator with a filter and air dryer.

9. Use the spiral cable sleeve to keep the air tube and the coupling cable together.
10. Connect the other end of the air tube to your local air supply device.

**Caution**

- The maximum pressure allowed is 7 bar. The optimal pressure is 7 bar (6.5 bar for an AirPick with serial number  $\leq$  V-01351).
- We recommend using a local pressure regulator with a filter and an air dryer.

11. Install the small cover on the side of the column with the provided screws.



12. Shut down the robot and power off the linear axis Controller.

**Caution**

You have to shut down the robot before making inter-controller and safety signal connections.



## Inter-Controller Connections

1. Open the UR controller. Connect the USB hub to a USB port.
2. Connect the Ethernet/USB converter cable to a USB port.
3. Connect the Ethernet cable into the Ethernet socket on the top of the linear axis Controller.
4. Pass the other extremity of the cable through the hole under the UR controller and connect it into the Ethernet/USB converter cable that is already connected.

### Info

Follow cable management good practices. You can either drill a hole in the hole plug or use a grommet (not included).

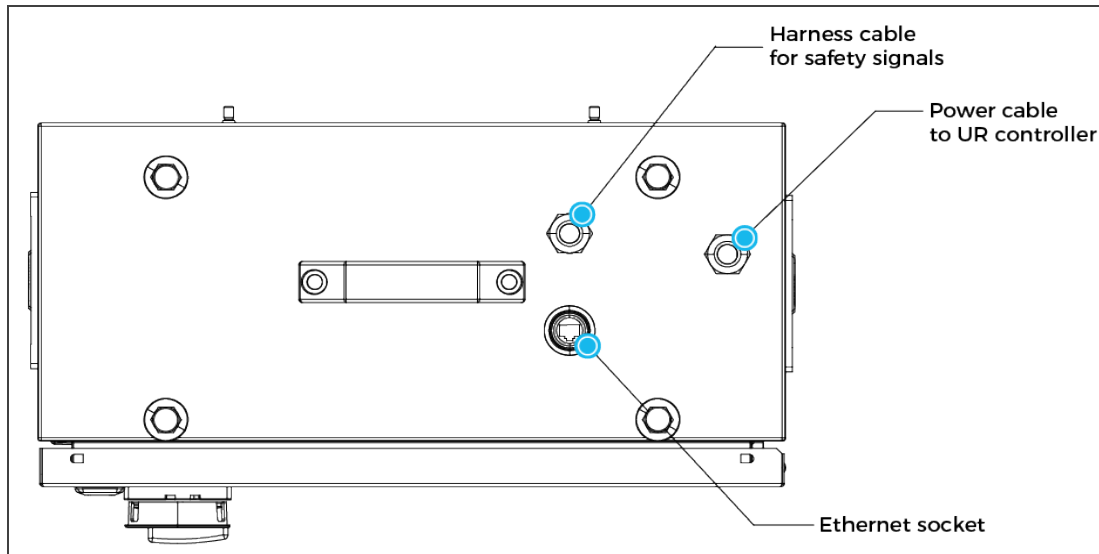


Fig. 3-1: Linear Axis Controller Cable Summary

## Safety Signal Connections

1. Take the signal safety cable and pass it through an opening under the UR controller.
2. Wire the cable by following the schema and the table available in the **Appendix** section.

### Caution

- Follow the installation guidelines in the UR manual for Emergency stop or Safeguard connections. Use the connector supplied by Robotiq for Safeguard connections.
- If the safeguard is not used, add jumpers between pin 1-2 and 3-4.
- Do not forget to connect the safety reset wire (white color) according to your safety setup. For more details, please refer to the table in the **Safety Connections** section.





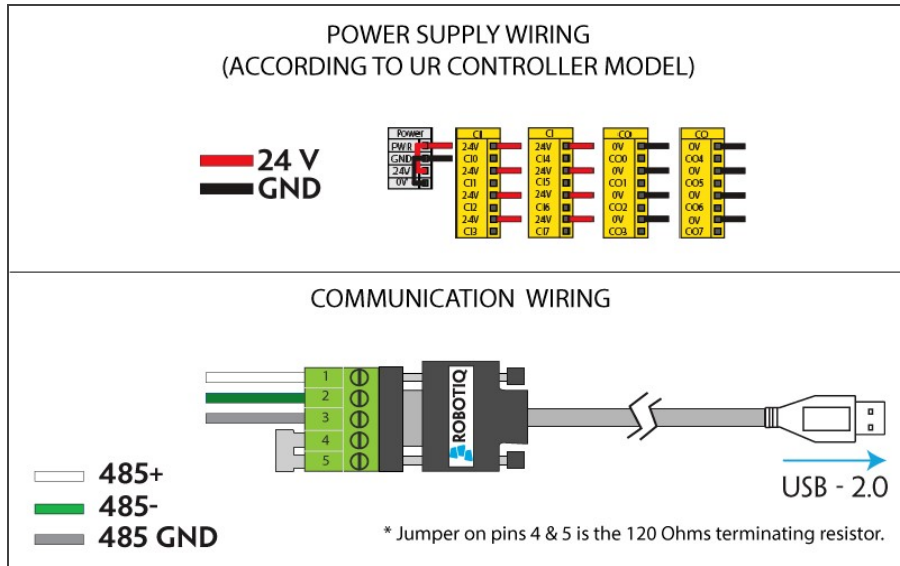
## AirPick Gripper and Copilot Connections

1. Connect the Copilot license dongle to the USB hub in the robot controller. It must be connected at all times.
2. Run the gripper's coupling cable to the robot controller.

## Info

Follow the good practices of the cable management. You can use the plate under the controller and use a grommet (not included).

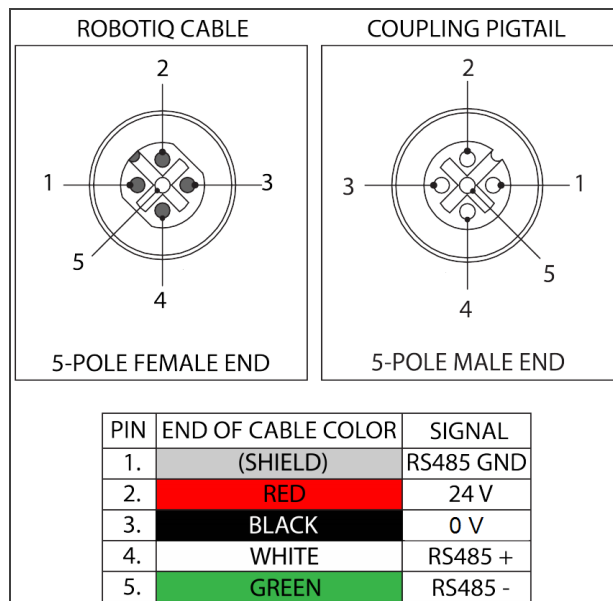
3. Connect the white, green and bare wires to the Robotiq RS-485 signal converter as shown in the figure below. Also, connect the red (24V) and black (0V) wires to the terminal blocks of the robot controller.



*Fig. 3-2: Vacuum Gripper wiring to robot controller*

4. Connect the USB cable to a USB port of the robot controller.

The figure below illustrates the device cable on the robot side (CBL-COM-2065-10-HF), the pigtail connection of the Vacuum Gripper's coupling (GRP-CPL-062 or AGC-CPL-XXX-002), and their associated pinouts.



*Fig. 3-3: Pinout of the Vacuum Gripper pigtail and device cable*

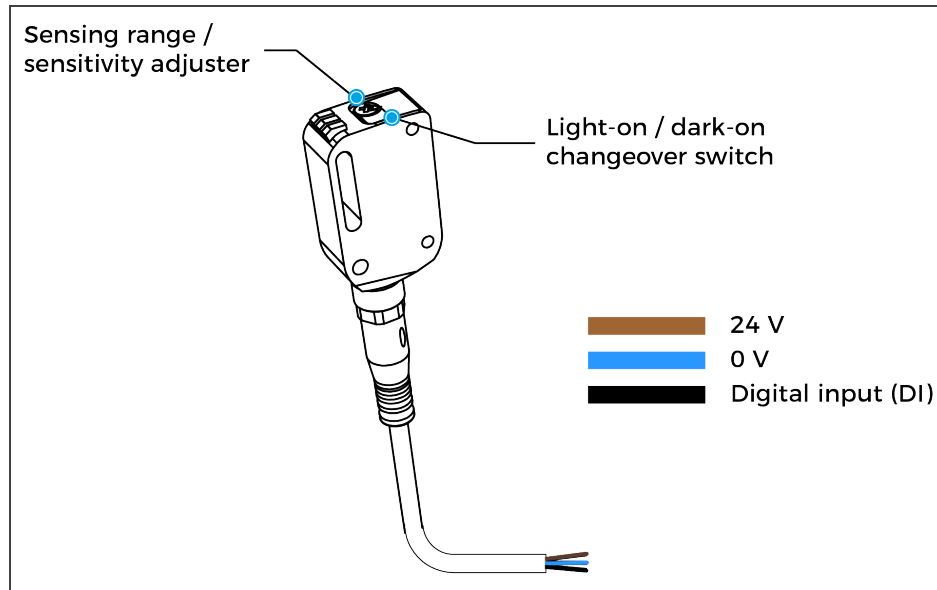


## Box Sensor

1. Run the box sensor's cable through a hole under the robot controller. Connect the brown (24V), blue (0V) and black (digital input) wires to corresponding connectors in terminal blocks.

### Info

Follow the good practices of the cable management. You can use the plate under the controller and use a grommet (not included).



## Anchoring the Solution

### Warning:

The transport, lifting, and moving of the Palletizing Solution should be done by qualified professionals. Failure to do so may result to machine damage, bodily injury or death.

### Warning

- The Solution must only be installed and anchored by qualified staff. If you use the anchors provided with the Solution, it should be installed in 28 MPa [4000 psi] undamaged concrete (minimum).
- If you choose to use other anchors, each anchor should be able to withstand at minimum the following forces (considering that the fasteners rated values are 25% of the ultimate value).



**Warning**

It is the responsibility of the end-user to ensure the final anchorage resists for:

Specifications	Metric Units	Imperial Units	Comments
Pull out strength	5200 N	1180 lbf	Ultimate value considering rated value with 4:1 safety factor: 20 800 N [4720 lbf].
Shear strength	1400 N	320 lbf	Ultimate value considering rated value with 4:1 safety factor: 5600 N [1280 lbf]

**Warning**

- Make sure to follow all the safety rules and regulations of your workplace while using the Robotiq Palletizing Solution.
- Always wear all recommended personal protective equipment in accordance with your workplace's safety standards, including:
  - Dust mask;
  - Safety glasses;
- Always use proper safety precautions when working with tools that contain sharp edges, pinching surfaces, or generate heat.
- Always lift heavy objects with your legs, not your back. If you can not lift an object alone, ask for help or find another method to move it.
- Use a vacuum cleaner if needed.

**Caution**

The Solution must be placed on a flat and leveled floor. If it is not the case, use shims to level it.

1. Position the Solution at its final position.

**Caution**

Make sure your layout is good and that all distances are respected. See the **Appendix** section.

2. Drill the six (6) holes with the provided drill bit.
3. If necessary, level the solution using shims.
4. Place the anchors into the holes and fasten the nuts flush to the screws.
5. Bang the anchors in place.
6. Secure the Solution by screwing the six (6) nuts with a **torque of 54 Nm (40 lb ft)**.



## Finalization and Power On

1. Install the box sensor on the bracket that best suits your setup with the provided screws.
2. Position the sensor box's bracket so it can detect the box to be picked.
3. Connect the M8 connector of the box sensor's cable to the sensor.
4. Reinstall the front base cover using the provided screws (10).
5. Install the column cover using the provided screws (4).
6. Connect the power cable to the power outlet.
7. Power on the linear axis Controller and the robot.

### Tip

The box sensor must be set properly. Once the system is running, adjust the detection distance with the sensitivity adjuster. To have the sensor providing a high state, when detecting a box, be sure to set it in the light-on switching mode (green light beside "L"). To do it, simply press the light-on / dark-on change-over switch for more than 1 second and less than 4 seconds.

### Warning

The column cover must be properly installed to achieve maximum structure rigidity.

### Warning

Make sure to do a risk assessment before starting to use the Solution. For more details, please refer to the **Safety** section.

## 3.4.5. Physical Clearance and Reachable Area of the Robot

The computed trajectories allow the boxes or the robot to overrun the edges of the pallet when the robot moves the boxes to their final position. Mitigation measures can be put in place to prevent a transient or quasi-static impact between a box, or the robot itself, and an operator. Below are some examples:

- Physical assets such as guardrails, bollards, etc. which prevent the operator from accessing the area
- Sensors such as light curtains or area scanners which can detect the presence of a person, and stop the system before that person reaches the danger zone.
- **Add virtual planes around pallet(s)** option available in the Settings tab of the Palletizer node of the Robotiq URCap to contain the overrun within a certain distance of the pallet. Please refer to **Palletizer Node** section to learn more about this option.

Potential overrun can be determined by the following formulae:

### Front overrun

The potential front overrun is the highest value obtained using the following formula:

Potential front overrun (mm) =  $\max \max (0.1 \times \text{box height}, 1280 - \text{pallet depth}, 180 + \text{extra bracket reach} + (0.1 \times \text{box height}) - (\text{minimum horizontal box dimension} / 2))$



Side overrun

Potential side overrun (mm) = (box diagonal/2) + robot reach + extra bracket reach - pallet width - 295

Moreover, trajectories are not limited to hovering over the picking position, the base of the Solution, and the pallets. It is thus important to implement physical safeguarding devices that must be put in place next to the picking area, depending on the palletizing cell's layout. The robot's reachable area should be clearly identified and marked on the ground.

Info

When the robot is palletizing on one side, and no pallet is present on the opposite side, the Palletizing Solution computes trajectories based on the assumption that there are no obstacles on the opposite side. The robot's elbow (joint #2) can therefore extend to the side where no pallet is present. For a UR10, the possible overrun is represented by a cylinder of 705mm radius, aligned with the robot base's Z-axis.

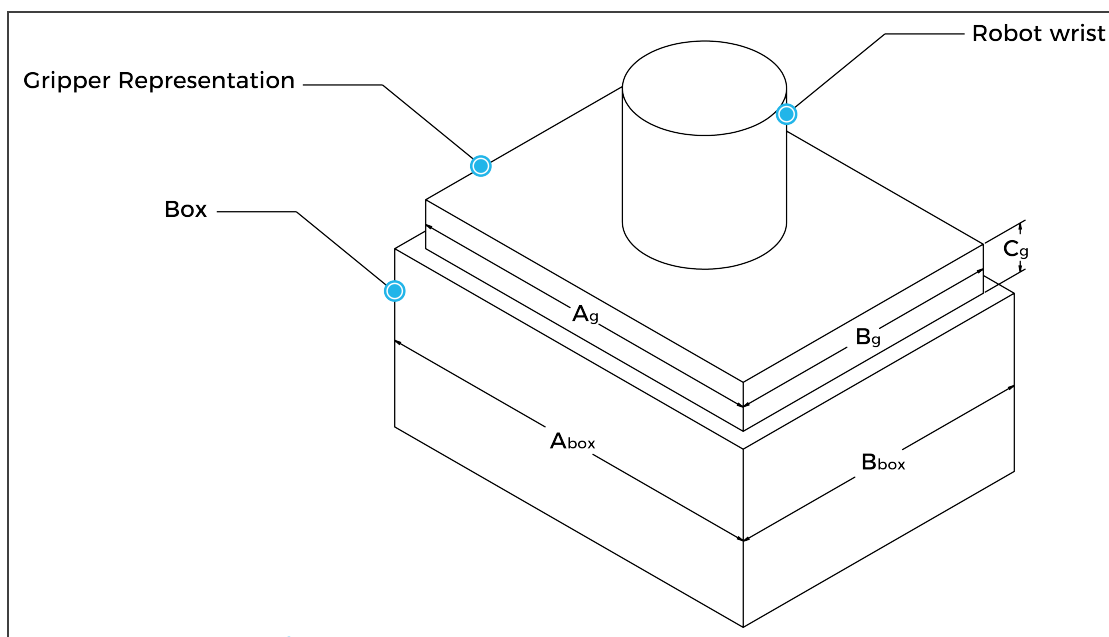
3.5. Other Grippers

It is possible to use a gripper other than the AirPick Vacuum Gripper. If another gripper is used, it is important to validate that its shape is within the gripper model used for the collision detection algorithm of the software. If your gripper does not fit the following models, it can still work, but Robotiq does not guarantee that there will be no collision.

The gripper model is depending on the box dimensions and is obtained according to these criteria:

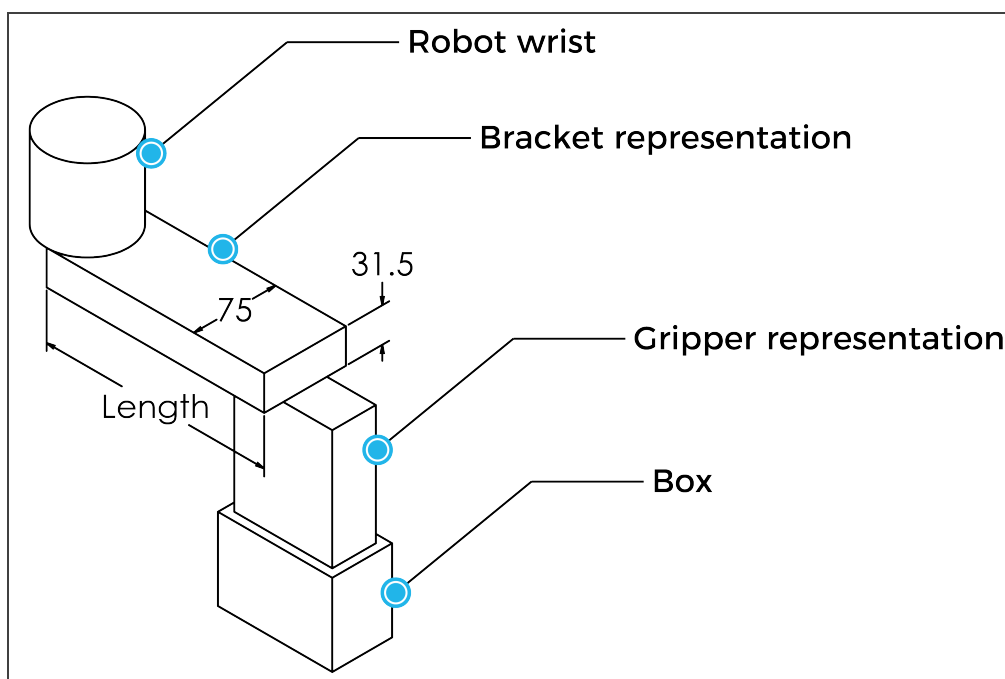
Box Footprint (A <sub>box</sub> X B <sub>box</sub> )	Gripper Footprint (A <sub>g</sub> X B <sub>g</sub> )	Gripper Height (C <sub>g</sub> )
A <sub>box</sub> < 105 mm OR B <sub>box</sub> < 55 mm	A <sub>g</sub> = A <sub>box</sub> - 1 mm B <sub>g</sub> = B <sub>box</sub> - 1 mm	110 mm
A <sub>box</sub> > 450 mm OR B <sub>box</sub> > 350 mm	A <sub>g</sub> = A <sub>box</sub> - 40 mm B <sub>g</sub> = B <sub>box</sub> - 40 mm	55 mm
Otherwise	A <sub>g</sub> = 200 mm B <sub>g</sub> = 130 mm	110 mm





If a TCP offset is added in the X and/or Y direction, it is considered that an extra reach bracket is used. A rectangular prism is then added at the end of the bracket, according to the rules mentioned above.

Bracket representation			
Height	Width	Length	Direction
31.5 mm	75 mm	Same length as TCP offset (X, Y)	Same direction as TCP offset (X, Y)



### 3.6. Installation for Universal Robots

The table below shows which Robotiq software to use with your Universal Robots’ controller. Please refer to the URCap Package section for the installation of the UR software packages for the Palletizing Solution.

**Info**

For CB-Series robots, the controller must have been produced after september 2019 (serial number > 2019301732) to be able to be installed on the Solution.

Robotiq Software	CB3.1 Controller	e-Series Controller
Robotiq Grippers URCap Package 1.5.1 and earlier versions	Incompatible	Incompatible
Robotiq Grippers URCap Package 1.6.0 and later versions	Compatible	Compatible

Table 3-2: Compatibility between Robotiq software and the robot controller

**Caution**

Please refer to the Installing URCap Package section to configure the Palletizing Solution properly before operating and programming the device.

**Info**

Upgrading to Copilot version 1.21 and above, an update of the linear axis PLC firmware might be required. A message will show after scanning the linear axis to approve the update.

### 3.7. URCap Package

Robotiq provides the user with a Universal Robots URCap package that provides a graphical user interface and enables direct serial communication to your robot controller.

**Info**

Browse to the [Palletizing Solution support page](#) to download the URCap package.

#### 3.7.1. Installing URCap Package

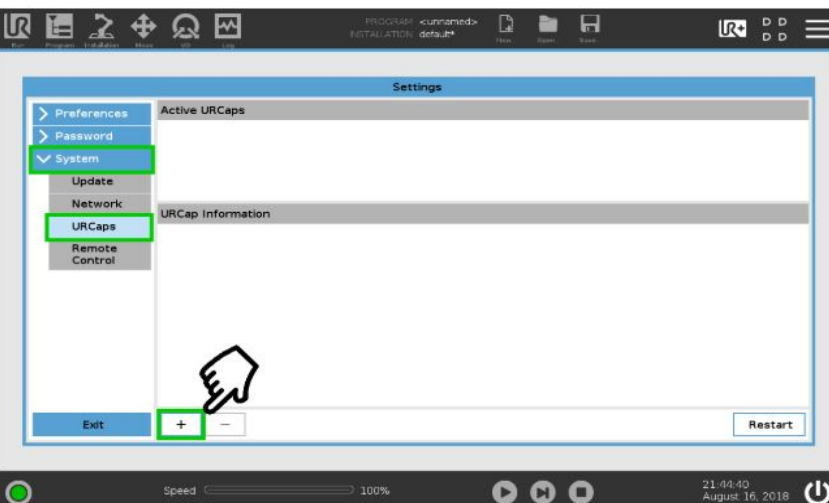
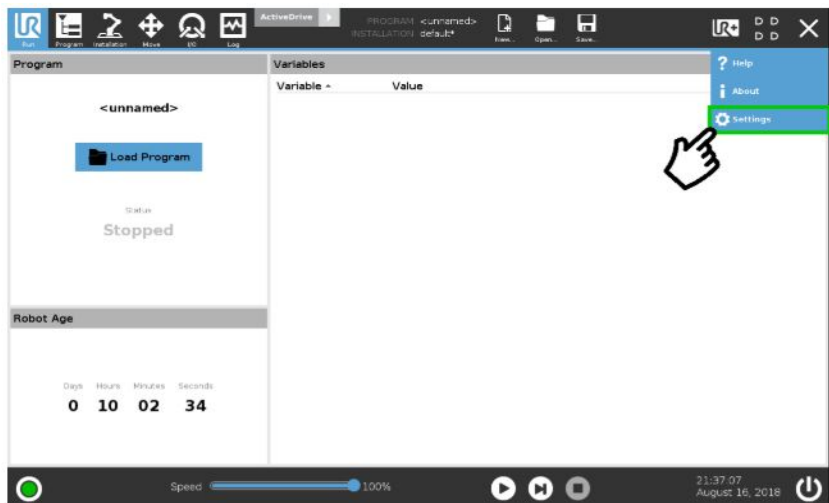
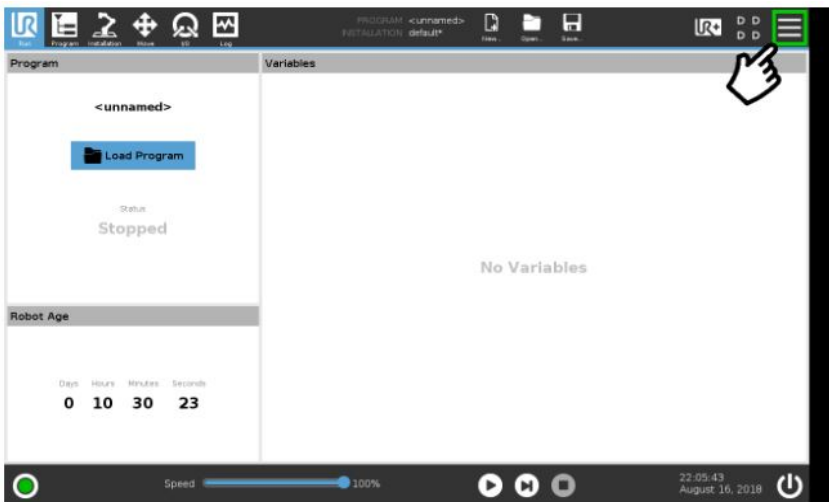
Make sure the Robotiq Paletizing solution is well installed. Refer to the **Mounting and Installation** section for detailed information. Before proceeding with the installation of the URCap package, make sure your Universal Robots controller is compatible with the package.

**Tip**

Tap the **triple bar icon** and select the **About** button to view the UR software version.



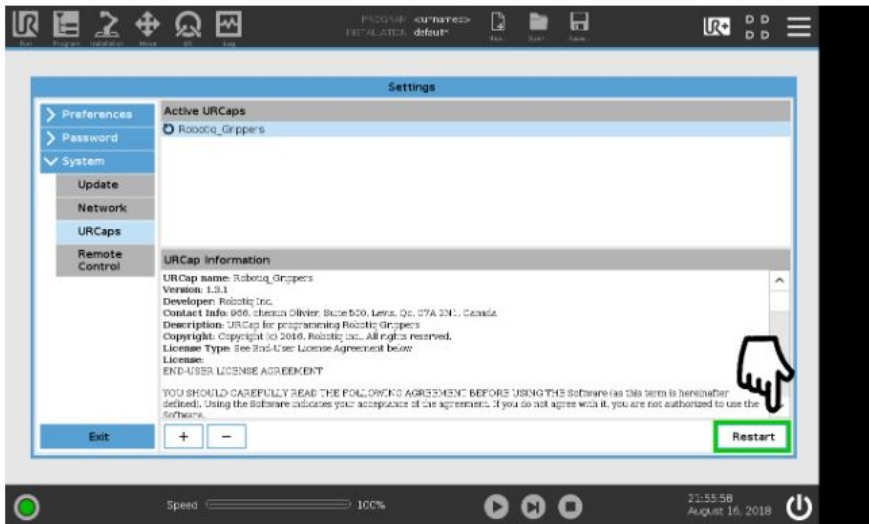
## On e-Series Universal Robots



- Make sure that your PolyScope version is up-to-date and that your Universal Robots controller is compatible with the Palletizing solution URCap package.
- Go to [support.robotiq.com](http://support.robotiq.com), and select the Universal Robots brand.
- Select **Palletizing Solution**.
- Click on **Software** → **Palletizing Solution URCaps**, download the zip of URCaps and extract them on the root of a blank USB stick.
- Insert the USB stick in the UR teach pendant or controller.
- On the teach pendant, tap the **triple bar icon** in the upper right corner of the screen.
- Tap **Settings**.
- Tap the **System** button in the navigation pane on the left.
- Select either the Gripper URCap (UCG-X.X.X.) or the Copilot URCap (UCS-X.X.X.) to install a URCap on your Teach Pendant.
- Repeat the previous step and install the second URCap.
- Tap the **plus (+)** button to look for the **.urcap files** in the available drives.

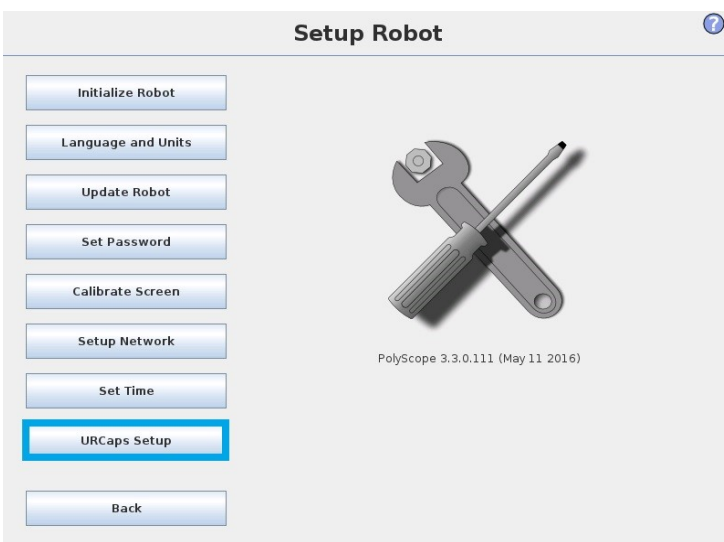
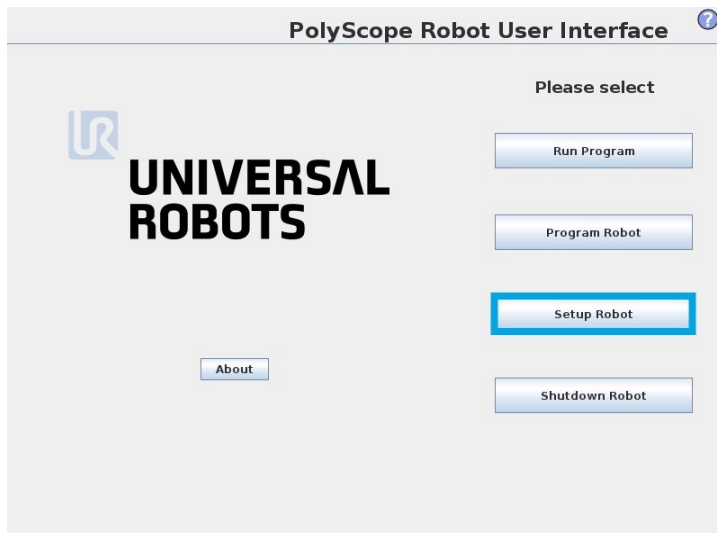






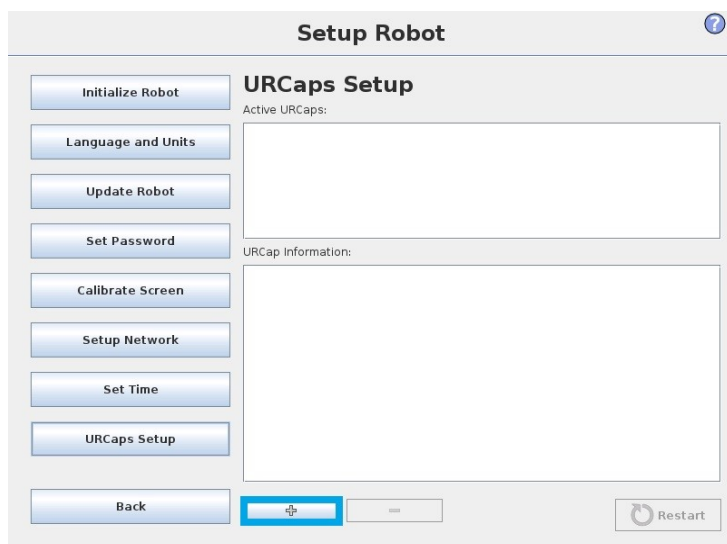
- Once the files are selected, tap the **Open** button.
- Tap the **Restart** button to complete the URCap installation. By doing so, you accept the **license agreement** detailed in the URCap information textbox.

## On CB-Series Universal Robots

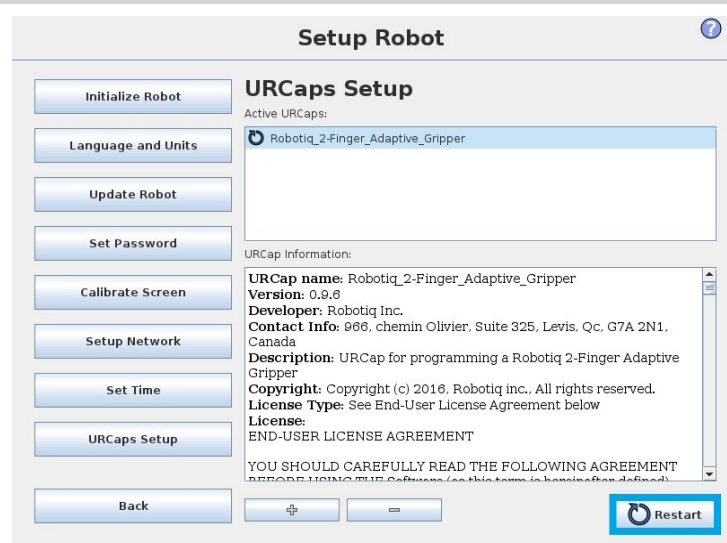


- Make sure that your PolyScope version is up-to-date and that your Universal Robots controller is compatible with the Palletizing URCap package.
- Go to [www.support.robotiq.com](http://www.support.robotiq.com), select **Browse by product**.
- Click on your **Robotiq product page** and then **Universal Robots**
- Click on **Software** → **Robotiq product URCaps** → download the zip of URCaps and extract them on the root of a blank USB stick.
- Select either the Gripper URCap (UCG-X.X.X.) or the Copilot URCap (UCS-X.X.X.) to install a URCap on your Teach Pendant.
- Repeat the previous step and install the second URCap.
- Insert the USB stick in the UR Teach pendant or controller.
- Go to Setup Robot.
- Tap URCaps Setup.

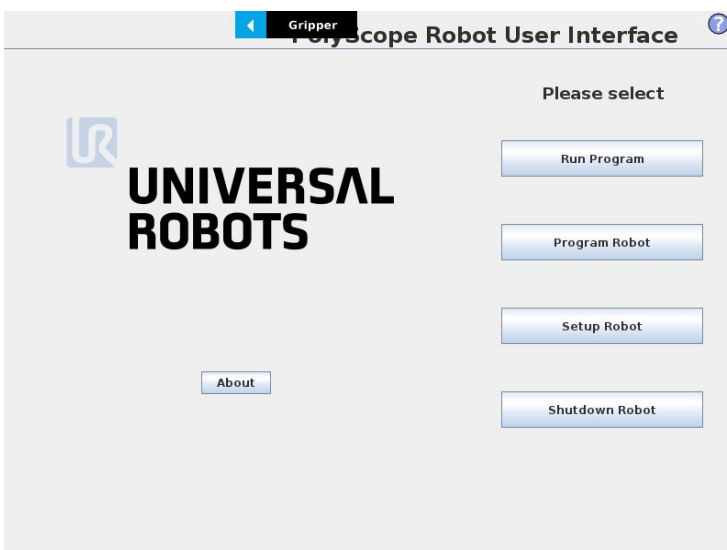




- Tap the plus (+) button to add the URCaps package.
- Open the URCaps.



- Restart PolyScope to complete the URCap installation. By doing so, you accept the License Agreement that is detailed in the URCap Information text box (see below for the License Agreement).

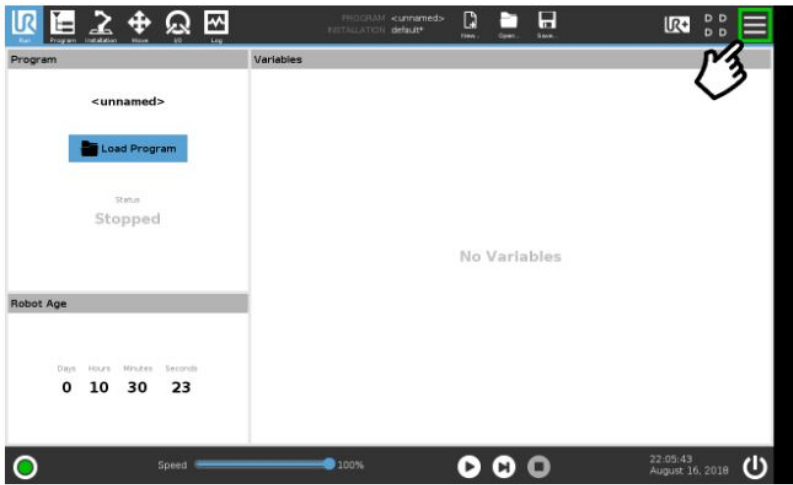


- When PolyScope reopens, the ActiveDrive toolbar will appear on the screen.

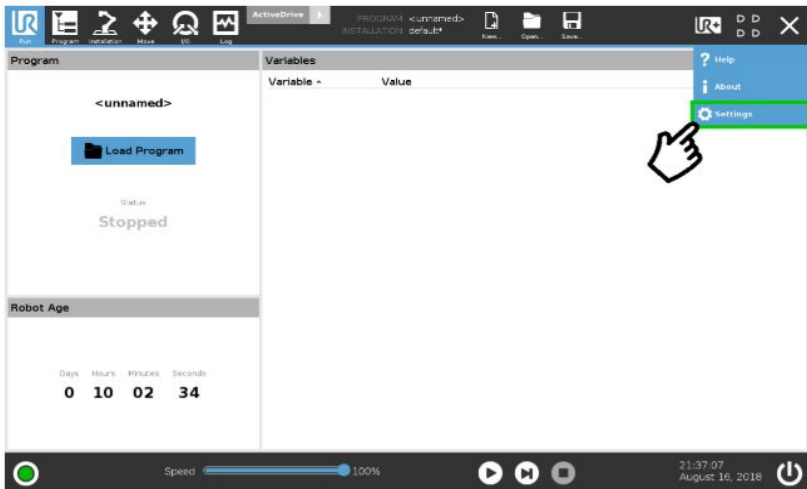


## 3.7.2. Uninstalling URCap Package

### On e-Series Universal Robots



- On the teach pendant, tap the **triple bar** icon.



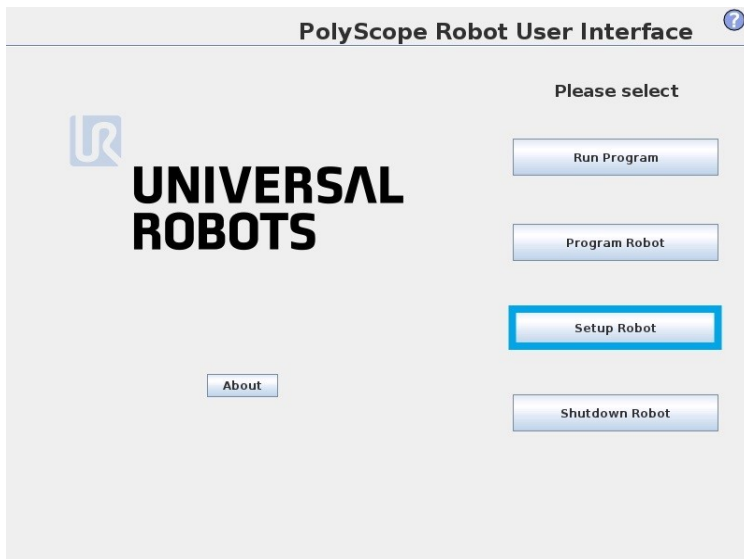
- Tap **Settings**.



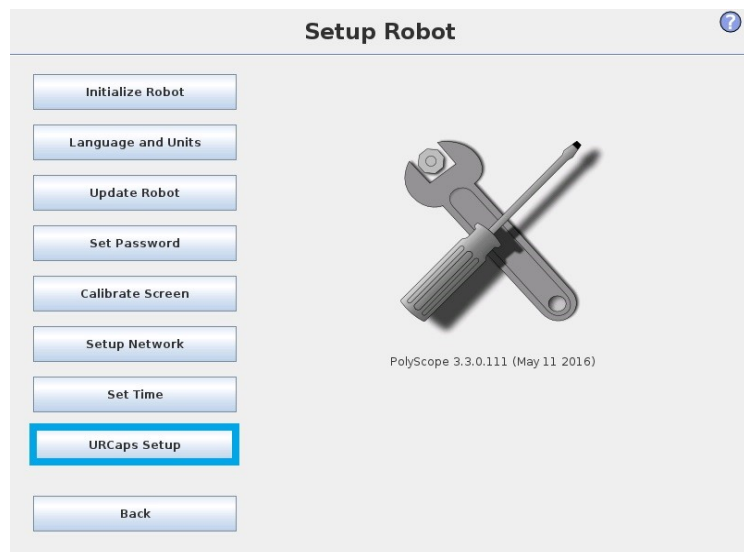
- Select **System** in the navigation pane on the left.
- Select **URCaps**.
- In the **Active URCaps** box, select the URCap to uninstall.
- Tap the **minus (-)** button to uninstall the URCap.
- Restart Polyscope to complete the uninstallation process.



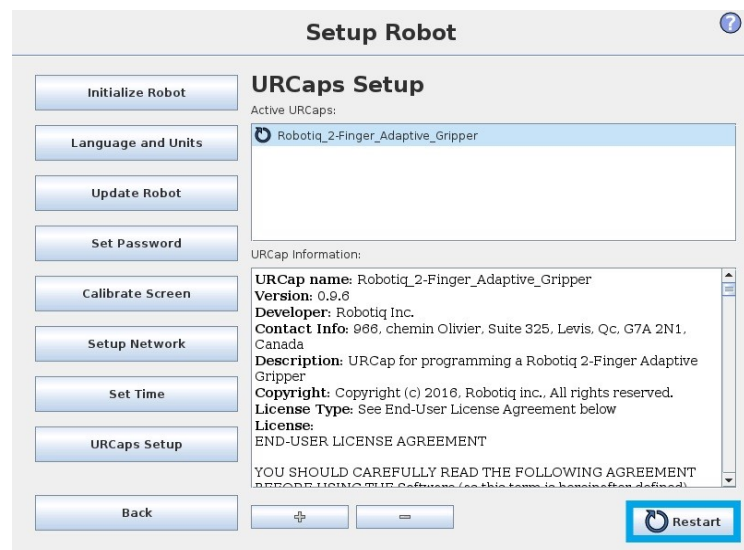
## On CB-Series Universal Robots



- Go to **Setup Robot**.



- Tap **URCaps Setup**.



- In the Active URCaps box, tap the URCap to un-install.
- Tap the **minus (-) button** to uninstall the URCap.
- Restart PolyScope to complete the uninstallation process.



## 3.8. Robot Configurations

### Info

Some configurations must be done in the Safety section of the Installation tab, to ensure the proper use of the solution.

### 3.8.1. Robot Limits

To ensure the effective operation of the Solution, Robot Limits should stay at the Least Restrictive setting. Tool speed (1) and tool force (2) can be adjusted as required. Please note that adjusting these settings will reduce the Solution's cycle time.

**! DANGER**  
Use of Safety Configuration parameters different from those defined by the risk assessment can result in hazards that are not reasonably eliminated or risks that are not sufficiently reduced.

☐ Factory Presets Most Restricted ————— Least Restricted

☒ Custom

Limit	Normal	Reduced
Power	1000 W	300 W
Momentum	100.0 kg m/s	25.0 kg m/s
Stopping Time	1000 ms	400 ms
Stopping Distance	2000 mm	500 mm
1 Tool Speed	1000 mm/s	1000 mm/s
2 Tool Force	140.0 N	150.0 N
Elbow Speed	5000 mm/s	1500 mm/s
Elbow Force	250.0 N	150.0 N

Safety password

### 3.8.2. Joint Limits

Some joint limits must be configured.

For e-Series:

1. Tap **Installation** → **Safety** → **Joint Limits**
2. Then, unlock the section with the proper password and change the values.
  - The minimum and maximum values for the Elbow will be  $-167^\circ$  and  $0^\circ$ .
  - The minimum and maximum values for the Wrist 3 will be  $-270^\circ$  and  $270^\circ$ .

Run Program Installation Move I/O Log

PROGRAM <unnamed>  
INSTALLATION default\*

Back Open Save

UR Manual CC

> General

> Safety

Robot Limits

Joint Limits

Planes

Tool Position

Tool Direction

I/O

Hardware

Three Position

Safe Home

> Features

> Fieldbus

> URCaps

**Position range**

Joints	Range	Normal Mode		Reduced Mode	
		Minimum	Maximum	Minimum	Maximum
Base	-363 — 363 °	-363	363	-363	363 +2 ° / -2 °
Shoulder	-363 — 363 °	-363	363	-363	363 +2 ° / -2 °
Elbow	-363 — 363 °	-167	0	-363	363 +2 ° / -2 °
Wrist 1	-363 — 363 °	-363	363	-363	363 +2 ° / -2 °
Wrist 2	-363 — 363 °	-363	363	-363	363 +2 ° / -2 °
Wrist 3	-363 — 363 °	-270	270	-363	363 +2 ° / -2 °

**Maximum speed**

Joints	Maximum	Normal Mode	Reduced Mode
Base	max: 131 °/s	131	131 -11 °/s
Shoulder	max: 131 °/s	131	131 -11 °/s
Elbow	max: 191 °/s	191	191 -11 °/s
Wrist 1	max: 191 °/s	191	191 -11 °/s
Wrist 2	max: 191 °/s	191	191 -11 °/s
Wrist 3	max: 191 °/s	191	191 -11 °/s

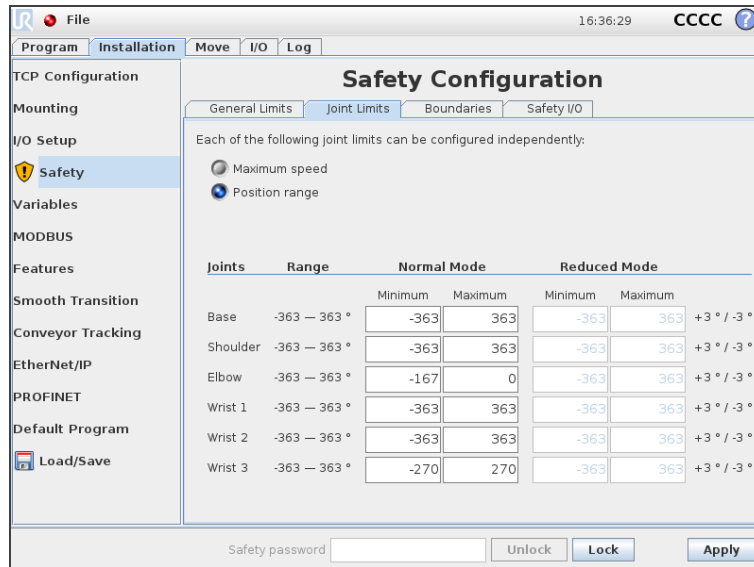
Safety password

Power off Speed 100% Simulation



### For CB-Series:

1. Tap **Installation** → **Safety** → **Joint Limits** → **Position range**
2. Then, unlock the section with the proper password and change the values.
  - The minimum and maximum values for the Elbow will be -167° and 0°.
  - The minimum and maximum values for the Wrist 3 will be -270° and 270°.

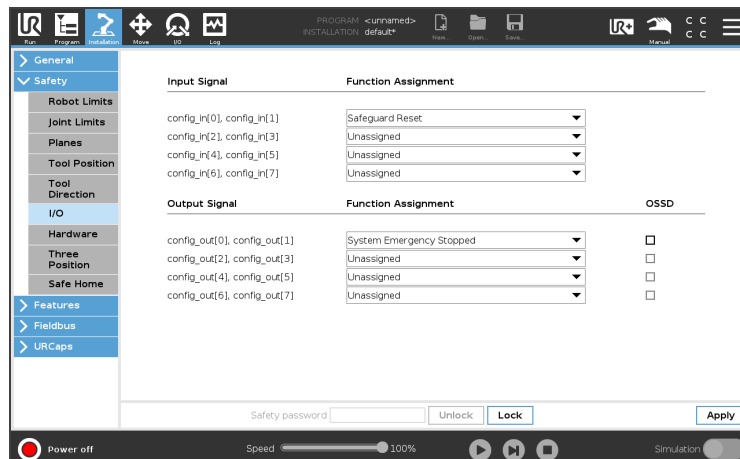


## 3.8.3. Configurable Outputs

Some configurable outputs must be set.

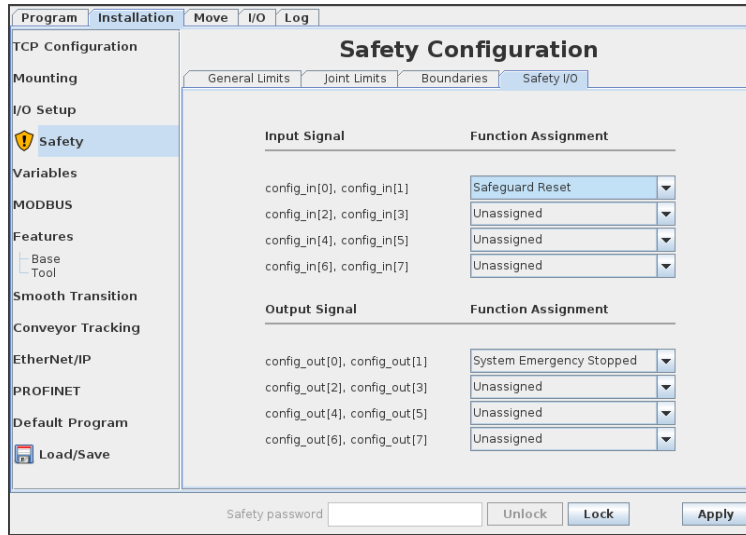
### For e-Series Universal Robots:

1. Tap **Installation** → **Safety** → **I/O**
2. Then, unlock the section with the proper password and set the **Output Signal config\_out[0]**, **config\_out[1]** at System Emergency Stopped.



## For CB-Series Universal Robots:

1. Tap **Installation** → **Safety** → **Safety I/O**
2. Then, unlock the section with the proper password and set the **Output Signal config\_out[0], config\_out[1]** at System Emergency Stopped.



The screenshot displays the 'Safety Configuration' window. On the left sidebar, the 'Safety' option is highlighted. The main panel has tabs for 'General Limits', 'Joint Limits', 'Boundaries', and 'Safety I/O'. The 'Safety I/O' tab is selected, showing two sections: 'Input Signal' and 'Output Signal'. Each section has a table for configuring signals and their functions.

Input Signal	Function Assignment
config_in[0], config_in[1]	Safeguard Reset
config_in[2], config_in[3]	Unassigned
config_in[4], config_in[5]	Unassigned
config_in[6], config_in[7]	Unassigned

Output Signal	Function Assignment
config_out[0], config_out[1]	System Emergency Stopped
config_out[2], config_out[3]	Unassigned
config_out[4], config_out[5]	Unassigned
config_out[6], config_out[7]	Unassigned

At the bottom of the window, there is a 'Safety password' field with 'Unlock' and 'Lock' buttons, and an 'Apply' button.



## 3.9. License Agreement

### END-USER LICENSE AGREEMENT

YOU SHOULD CAREFULLY READ THE FOLLOWING AGREEMENT BEFORE USING THE Software (as this term is hereinafter defined). Using the Software indicates your acceptance of the agreement. If you do not agree with it, you are not authorized to use the Software.

**IMPORTANT-READ CAREFULLY:** This End-User License Agreement (the “Agreement”) is a legal agreement between you and the Licensor (as this term is hereinafter defined), the licensor of the Software. This Agreement covers the Software. The Software includes any “on-line” or electronic documentation and all modifications and upgrades related thereto. By installing, or otherwise using the Software, you agree to be bound by the terms of this Agreement. If you do not agree to the terms of this Agreement, the Licensor cannot and does not license the Software to you. In such event, you must not use or install the Software.

#### 1. Definition.

1. “UR” means Universal Robots A/S, a corporation incorporated under the laws of Denmark, having its registered office at Energivej 25, DK-5260 Odense S, which specializes into the conception, advanced manufacturing and sale of robotic products (the “UR’s Business”);
2. “Software” means any of the Licensor’s softwares provided to its customers for the purposes mentioned in Sub-section 1.4 hereof including their modifications and upgrades and their related materials;
3. “Licensor” means Robotiq inc., a corporation incorporated under the laws of Quebec, having its registered office at 500-966 chemin Olivier, Lévis, Québec, Canada, G7A 2N1, which specializes into the conception, advanced manufacturing and sale of robotic products (the “Licensor’s Business”);
4. “End-User” means a customer authorized pursuant to this Agreement to install or use the Software in order to make a specific product from the Licensor’s Products compatible and functional with a specific product of the UR’s Product
5. “Licensor’s Products” means those products developed by the Licensor in the course of the Licensor’s Business;
6. “UR’s Products” means those products developed by UR in the course of the UR’s Business;
7. “Licensor’s Authorized Representatives” means and includes the Licensor and Licensor’s authorized vendors, resellers, distributors and licensors;
8. “Purchase Agreement” means an agreement between the End-User and the Licensor pursuant to which the End-User purchased one or more of the Licensor’s Products.

2. License. Subject to the terms and conditions hereof, the Licensor grants to the End-User a personal, temporary, non-exclusive, non-assignable and non-transferable and revocable license to use the Software in accordance with the terms and conditions hereof.

3. Software and Documentation. The Licensor may provide, if applicable, all documentation containing the detailed specifications for operation and use of the Software, which Software shall be used in accordance with such documentation. This documentation, if applicable, will be provided, wholly or in part, within (i) this Agreement, (ii) the Licensor’s Web site <http://robotiq.com/> (iii) the Licensor’s Products and the Purchase Agreement therewith, or (iv) any other agreement, document, support, whatsoever decided by the Licensor.

The use of the Software requires the Licensor’s Products, UR’s Products , compatible systems and certain software (which may require some expenses), may require periodical updating and may be affected by such elements. Most equipment will be compatible with the Software. However, the Software may not function on certain types of equipment.

4. Modifications and Upgrades. The Licensor shall be under no obligation to provide any upgrade or modification to the Software. However, the End-User shall be entitled to receive free of charge all modifications and upgrades of the Software provided by the Licensor if, at such time, the End-User is not in default in respect of any of its obligation contained herein. Such modifications and upgrades of the Software shall be installed by the End-User itself by consulting the Licensor’s





Website <http://robotiq.com/> where a link to proceed to such installation will be made available thereof. A new version of the Software shall not be covered by this Section 4 but shall require that a new End-User Software License Agreement be entered into between the Licensor and the End-User.

5. Fees. The grant by Licensor to the End-User of the present license shall be free to the extent that the End-User agrees and complies to the term and conditions herein at all time.
6. Maintenance. During the term of this Agreement, the Licensor will maintain the Software in an operable condition and will make available any corrections and improvements as are generally incorporated in the Software by the Licensor without additional charge to the End-User. The Licensor may temporarily and without notice suspend or limit access to the Software if necessary or desirable in order to maintain, restore, modify or repair any part of the Software or for any reason related to business. During such works, the Software will not be available but the Licensor undertakes to deploy its best efforts to perform such works at appropriate times and to limit any inconvenience arising therefrom.
7. Title to Software. The licensed Software is composed of confidential data and trade secrets and is proprietary to and constitutes trade secret information and intellectual property of the Licensor. Title and ownership rights to the Software, including the intellectual property rights related thereto, shall remain with the Licensor. The End-User agrees to maintain the confidential nature of the Software and related materials provided for the End-User's own internal use under this Agreement. The license granted herein does not include the right to sublicense to others, and may not be assigned to others, in whole or in part, without the prior written consent of the Licensor. The End-User may not or allow others to modify or prepare directive works, copy (except for normal backups for recovery purposes), reproduce, republish, reverse engineer, upload, post, transmit, or distribute, in any manner, the Software.
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11. Training, Maintenance and Support There is no entitlement to training, maintenance and support under this license unless otherwise specified in the Purchase Agreement or any other written agreement between the End-User and the Licensor. The End-User may provide the Licensor with details regarding any bug, defect or failure in the Software promptly and with no delay from such event; the End-User shall comply with the Licensor's request for information regarding bugs, defects or failures and furnish him with information, screenshots and try to reproduce such bugs, defects or failures upon Licensor's demand.



12. **Expiration and Termination.** The Licensor may terminate this Agreement for default by the End-User. This Agreement will also be automatically terminated upon the election of such by the Licensor or the official launch of the Software, whichever event comes first. Upon termination of this Agreement for any reason, the End-User shall promptly uninstall the Software on any UR's Products and Licensor's Products, computer, or server on which it has been installed, deliver to the Licensor all CDs, DVDs, magnetic tapes, cards, and other tangible items and materials embodying the Software, and return to the Licensor all copies thereof or destroy such copies and warrant in writing that all copies thereof have been destroyed. In the event of termination of this Agreement, all obligations of the parties under this Agreement due for performance on the date of termination shall survive the termination, and the party terminating shall not be liable to the other party for any damages arising out of the termination.

13. **Miscellaneous.**

1. This Agreement constitutes the entire understanding and agreement between the Licensor and the End-User and replaces any prior agreement relating to the same subject matter.
2. This Agreement shall be governed and construed in accordance with the laws of the province of Quebec and the federal laws of Canada applicable therein. Any legal action or proceeding between the Licensor and the End-User for any purpose concerning this Agreement or the parties' obligations hereunder shall be brought exclusively in a court of competent jurisdiction sitting in the judicial district of Trois-Rivières, Quebec.
3. The Licensor's failure to insist upon or enforce strict performance of any provision of this Agreement shall not be construed as a waiver of any provision or right. Neither the course of conduct between the parties nor trade practice shall act to modify any provision of this Agreement.
4. The Licensor may assign its rights and duties under this Agreement to any party at any time without notice to the End-User. The End-User may not assign this Agreement without the prior written consent of the Licensor.
5. If any part of this Agreement is null, illegal or non-enforceable, this Agreement shall be interpreted as if this part was never part of this Agreement.
6. The provisions of this Agreement are for the benefit of the Licensor and its officers, directors, employees, agents, licensors and suppliers. Each of these individuals or entities shall have the right to assert and enforce those provisions directly against the End-User on its own behalf. This Agreement is also for the benefit of, and binds, the End-User and its heirs, successors, legal representatives and permitted assigns.
7. Any rights not expressly granted herein are reserved.
8. The parties confirm that they have agreed that this Agreement and all related documents be drafted in English only. Les parties aux présentes confirment qu'elles ont accepté que la présente convention et tous les documents y afférents soient rédigés en anglais seulement.



## 4. Operation

### 4.1. Starting Up

After the mechanical and electrical installation, follow these steps:

1. Make sure you have installed the URCaps. Please refer to the **Installing URCap Package** section
2. Configure the TCP. Use the proper values depending on if you use the extra reach bracket or not.
3. Open the Gripper Toolbar (top right of your screen). To make sure that the Toolbar is always displayed, tap **Installation** → **URCaps** → **Vacuum** and tick the **Show Vacuum Toolbar** checkbox.
4. Test the box sensor and the digital input : Tap the **I/O** tab and place an object in front of the box sensor to validate if the signal changes.
5. Test the Vacuum Gripper: Tap **Installation** → **URCaps** → **Vacuum** → **Scan**. Then, test the grip and release functions of the Vacuum in the Gripper Toolbar.
6. Activate and test the linear axis: Tap the **UR+** icon → **ActiveDrive** toolbar → **Extra Axis** → **Scan** (you may have to press the **Start** button). Use the arrows to test the linear axis action.

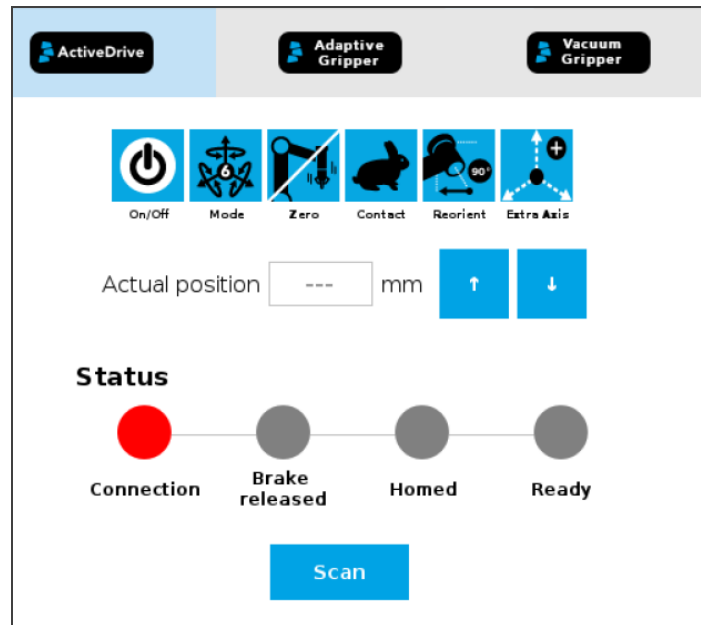


Fig. 4-1: Scan for the linear axis in the ActiveDrive toolbar



## 4.2. Light States

### Light States Legend

- **Blink fast:** 2 Hz (0.25s ON, 0.25s OFF)
- **Blink slow:** 0.5 Hz (1s ON, 1s OFF)

Color and signal type	Condition status	Cause or action needed (troubleshooting for e-Series)
RED Fast blink	The linear axis controller (PLC) is unable to communicate with the Robot controller (UR).	<ul style="list-style-type: none"> <li>• The robot has been started and needs time to boot up (Polyscope has not loaded yet)</li> <li>• Make sure your Ethernet/USB adapter is properly connected: the LED on the Ethernet adapter should be ON.</li> <li>• Make sure the Ethernet cable between the PLC and robot controller is properly connected (to the USB adapter) .</li> <li>• Try pressing the Scan button in the installation tab.</li> <li>• Try powering off the system (both the robot and the linear axis Controller). Wait 1 minute. Power up the system again.</li> </ul>
RED Slow blink	Communication between the robot and the linear axis controller (PLC) is established, but Copilot has not established the communication yet with the linear axis controller.	<ul style="list-style-type: none"> <li>• Tap <b>Installation</b> → <b>URCaps</b> → <b>Copilot</b> → <b>Linear Axis</b> and click on <b>Scan</b> button.</li> </ul>
RED Solid	An axis error happened.	<ul style="list-style-type: none"> <li>• Tap <b>Installation</b> → <b>URCaps</b> → <b>Copilot</b> → <b>Linear Axis</b>. Then, check the error message and act accordingly.</li> </ul>
RED Solid	A Protective or Emergency stop has occurred.	<ul style="list-style-type: none"> <li>• Follow the procedures required by the system to recover from either a Protective or Emergency stop.</li> </ul>
YELLOW Solid	<ul style="list-style-type: none"> <li>• When the Scan has succeeded, but the axis brakes are not released (Start not done yet)</li> <li>• A program is running without Palletizer node.</li> </ul>	<ul style="list-style-type: none"> <li>• Tap <b>Installation</b> → <b>URCaps</b> → <b>Copilot</b> → <b>Linear Axis</b> and click on <b>Start</b> button. You may need to press the safeguard reset button (if you have one in your specific safety setup).</li> </ul>
YELLOW Slow blink	A Safeguard Stop has occurred.	Press the safeguard reset button.



Color and signal type	Condition status	Cause or action needed (troubleshooting for e-Series)
BLUE Solid	<ul style="list-style-type: none"> <li>The pallet is complete or missing;</li> </ul> <p>AND</p> <ul style="list-style-type: none"> <li>The system is palletizing on the other side.</li> </ul>	Place a new pallet
BLUE Fast blink	<ul style="list-style-type: none"> <li>The pallet is complete and the system is idle;</li> </ul> <p>OR</p> <ul style="list-style-type: none"> <li>The pallet is not detected and the system is idle.</li> </ul>	Place a new pallet
WHITE Solid	<ul style="list-style-type: none"> <li>The linear axis is activated and brake is released;</li> <li>The Robotiq Controller (PLC) is connected to the robot controller</li> <li>A program is running without a Palletizer node.</li> </ul>	N/A
GREEN Solid	A program with a Palletizer node is running but the pallet present is not completed.	N/A



## 5. Software

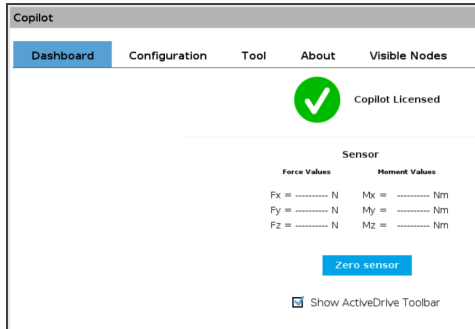
### 5.1. Installation on e-Series Universal Robots

#### Caution

To ensure normal operation, make sure the Copilot license dongle remains connected at all times.

1. Connect the license dongle to the USB hub in the UR controller. Make sure your Copilot license is activated:

- a. Tap **Installation** tab > **URCaps** > **Copilot**.



- b. The Copilot license activation will display under the **Dashboard** tab.

2. Set up the Copilot software based on your configuration and application

#### For e-Series Universal Robots

Tap Installation → URCaps → Copilot → Configuration

#### For CB-Series Universal Robots

Tap Installation → Copilot → Configuration

Then,

- a. Select the Palletizer model used
  - i. In the Configuration tab, under Palletizing Solution, select Linear Axis
- b. If required, deactivate the **Use Copilot to manage a soft speed transition when resuming from a Safeguard stop** option. This is required when another URCap or a Polyscope option (for example, ProfiNET or Ethernet/IP) needs to control the speed slider.
- c. If required, select the **Start linear axis at program start (Palletizer, Linear axis move)** option. It will scan and start the linear axis when the program starts.
- d. If required, activate the **Limit height for Palletizer program node (low ceiling)** option and enter the maximum height that can be reached by the moves automatically generated by the Palletizing solution. Make sure to keep a clearance to prevent a collision with the ceiling.



Warning

Activating the **Limit height for Palletizer program node** option does not limit the linear axis range outside of the Palletizer node. Therefore, caution must be observed when operating the linear axis with the ActiveDrive toolbar or the Linear Axis move node.

Dashboard

Configuration

Tool

About

Visible Nodes

General

☒ Use Copilot to manage a soft speed transition when resuming from a Safeguard stop

Palletizing Solution

Model

☒ AX Series

☐ Start linear axis at program start

☐ PE Series

Pedestal height 

1500

 mm

☐ Enable "Confirm new pallet(s) ready" button

☐ Add 25 mm minimum distance between robot arm and base

☐ Limit height for Palletizer program node (low ceiling) 

3.5

 m

Force Torque Sensor

☒ Show collision detection options

Causes a program to stop when the forces and torques monitored by the FT sensor exceed the defined limits.

☐ Start monitoring

☒ Stop monitoring

3. In the **ActiveDrive** toolbar, click on **Extra Axis**, then **Scan**, and make sure your linear axis is ready.

ActiveDrive

Adaptive Gripper

Vacuum Gripper

On/Off

Mode

Zero

Contact

Reorient

Extra Axis

Actual position

732

mm

Status

Connection

Brake released

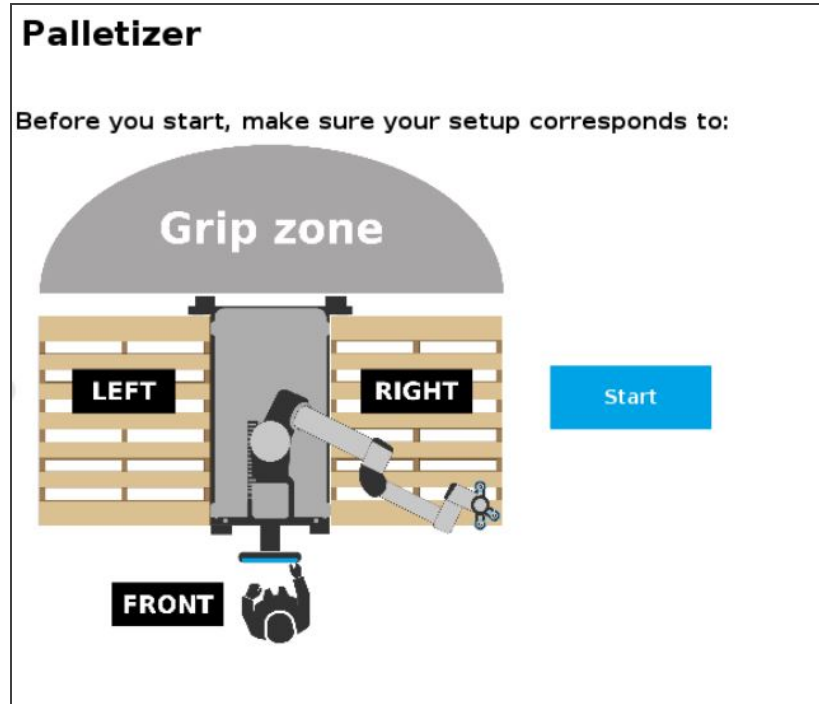
Homed

Ready

Brake

## 5.1.1. Palletizer Node

- 1 Before you start programing your features, make sure that your Robotiq Palletizing Solution is set this way:



- 2 On the Teach Pendant, tap the **Program** button.
- 3 Select **URCaps** in the navigation pane on the left.
- 4 Tap the **Palletizer** button.

### Info

To use the palletizer node in its **depalletizing mode**, see figure in step 13.

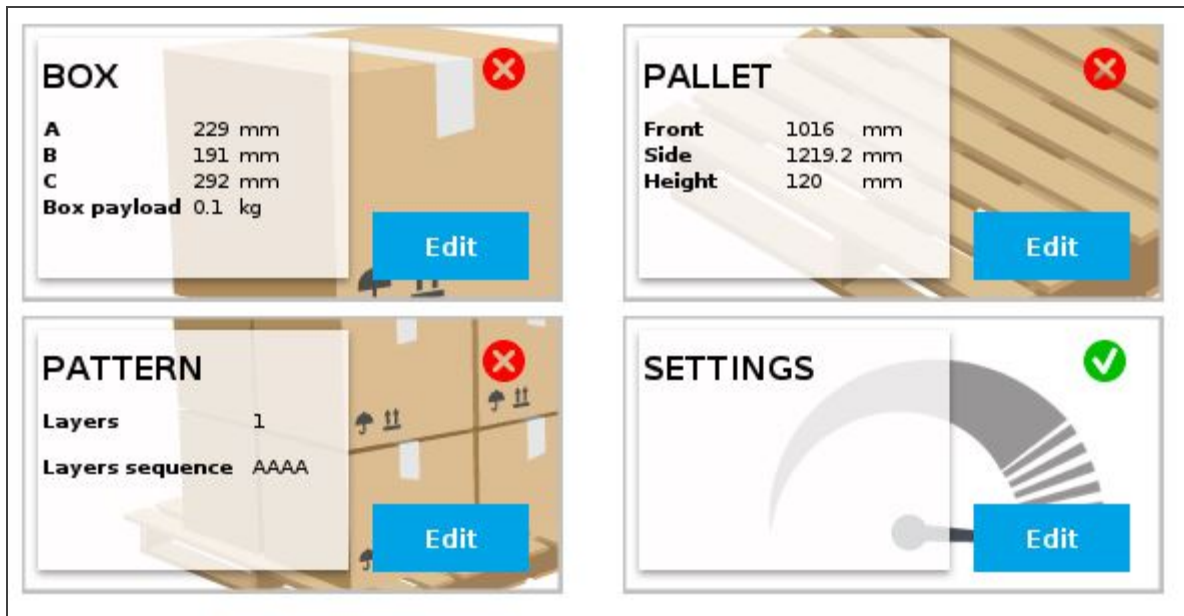
### Info

You will have to configure **four (4) parameters** to program your Palletizing Solution.




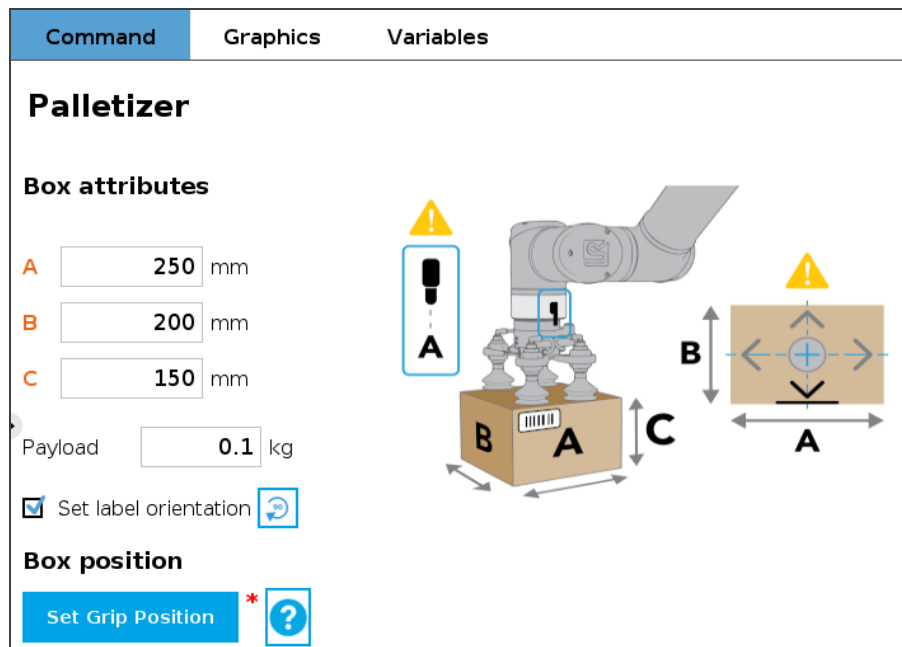


5 To begin, click on **BOX** to set your box dimensions.



6 In the **Box attributes** parameter, you have to set the box's:

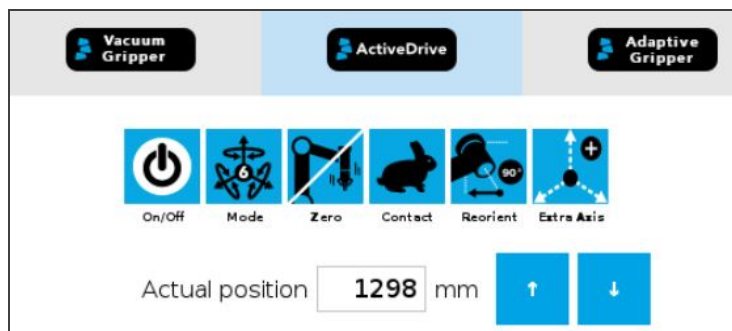
- Width (A)
  - Depth (B)
  - Height (C)
  - Payload
- If you have labels that need to be oriented on your pallets, check the **Set label orientation** box.
- You can choose the side on which the label will appear on your box, by clicking on the  button.



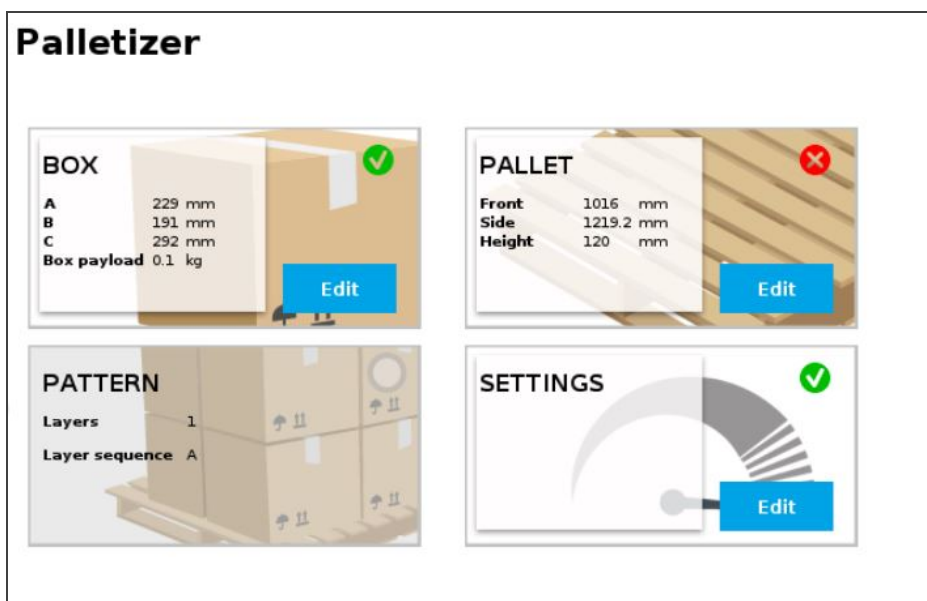
7 By clicking on the **Set Grip Position** (palletizing mode) or the **Set Drop Position** (depalletizing mode) button, you will have access to determine the coordinates in **X, Y and Z** of your robot, in which the grip or drop position (on a conveyor, for instance) will be:

- Position the robot tool flange connector on side A (same side as the robot wrist), as shown in the picture above. Robot joints should be positioned as close as possible to the center of their motion range.
- Make sure to align the TCP with the center of the box.
- Once you are done, click on **Ok**.

- You can also move the linear axis and to do so : click on **Active Drive** → **Extra Axis**.



8 The **BOX** parameter is now completed. Click on **PALLET** to continue the configuration.



9 For the **Pallet dimensions** parameter you will have to:

a Select the desired pallet:

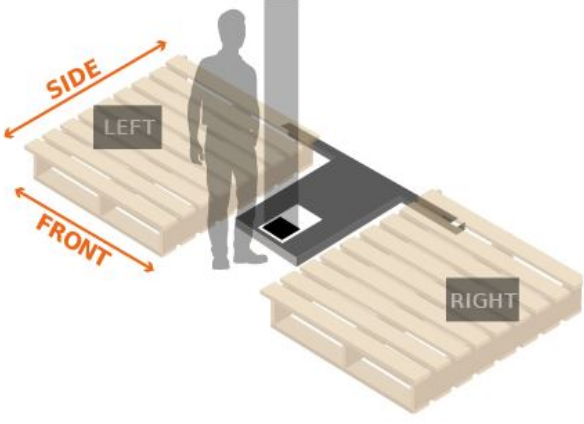
- Right or left
- Both pallets

b Determine the dimensions of the:

- Front
- Side
- Height

### Palletizer

#### Pallet dimensions



Front  mm

Side  mm

Height  mm

#### Pallet selection \*

☐ Pallet LEFT

☐ Pallet RIGHT

10 The **PALLET** and **BOX** parameters are now completed. Click on **PATTERN** to continue the configuration.

### Palletizer

#### BOX

A 229 mm  
B 191 mm  
C 292 mm  
Box payload 0.1 kg

#### PALLET

Front 1016 mm  
Side 1219.2 mm  
Height 120 mm

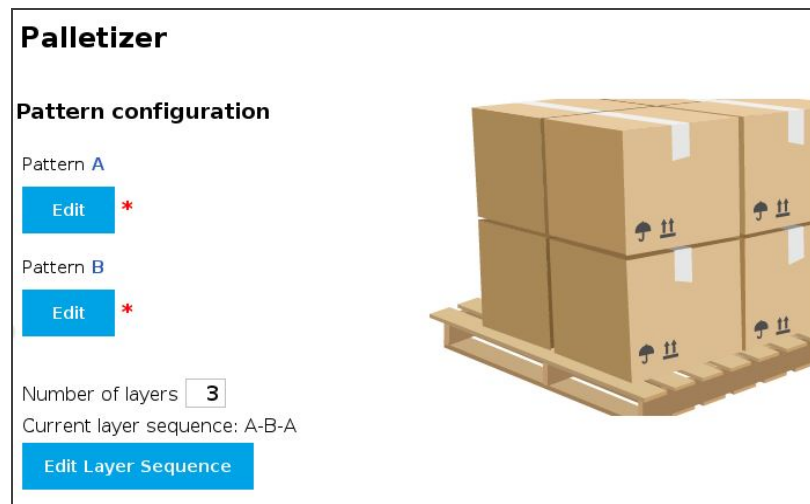
#### PATTERN

Layers 1  
Layer sequence A

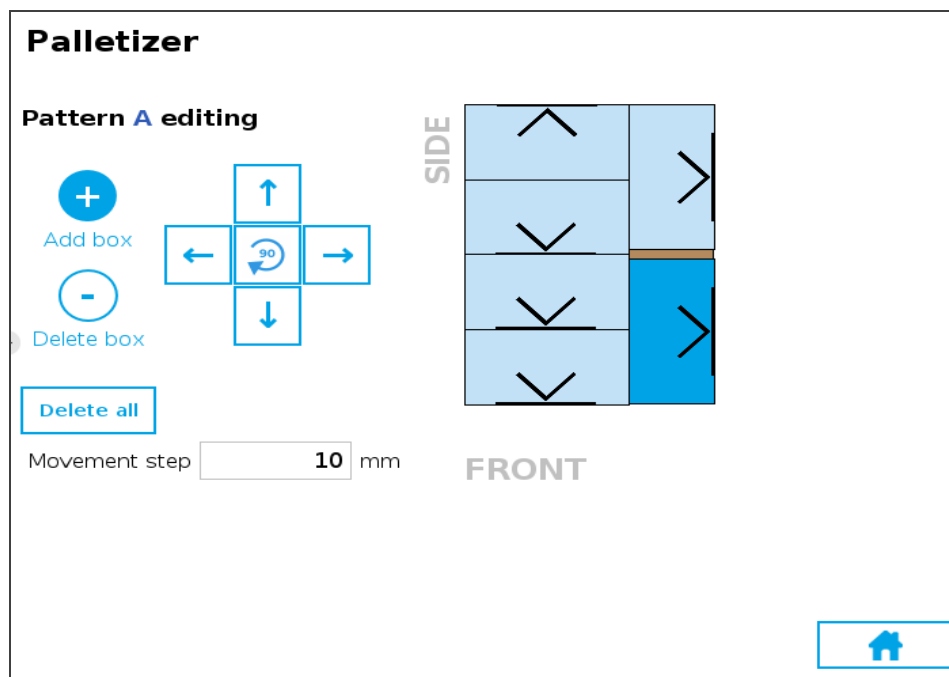
#### SETTINGS



**11** The **PATTERN** parameter allows you to set the number and sequence of your layer's boxes.



- You can create and use a maximum of two patterns: the **Pattern A** and the **Pattern B**. Make sure to select the desired ones.
- Click on **Edit** to configure your pattern.
  - Configure the pattern you chose (A, B or both):
    - i. Click on the **+** button to add boxes.
    - ii. Use the arrows to move and position the boxes on the pallet, as desired.
  - If you have ticked the **Set label orientation** checkbox in the box parameters, the side of the box with the label will be identified.



- Enter the number of layers needed.

### Palletizer

#### Pattern configuration

Pattern A

Edit \*

Pattern B


Edit \*

Number of layers

3

Current layer sequence: A-B-A

Edit Layer Sequence



- Your current layer sequence is represented. Click on **Edit Layer Sequence** to modify it.

### Palletizer

#### Layer Sequence

Select the pattern used for each layer:

3

☒ A

☐ B

2


☐ A

☒ B

1

☒ A

☐ B





- 12 Three (3) of your parameters are now set. Click now on the **SETTINGS** button and complete your configuration as indicated below.

## Palletizer

### Settings

Acceleration and speed are also limited by UR safety settings

	Tool speed	Tool acceleration
1 With box	500 mm/s	750 mm/s <sup>2</sup>
Without box	1000 mm/s	750 mm/s <sup>2</sup>

2 Box presence input digital\_in[0]

3 Palletizer mode ☒ Palletizing ☐ Depalletizing

Box and pallet display units ☒ Metric ☐ Imperial

4 ☒ Validate pallet state at program startup

5 Allow gripper to pick the box at different angles ☐ 90° ☒ 180°

6 ☒ Avoid collision with conveyor Configure

7 ☒ Add virtual planes around pallet(s)  
Distance 0 mm

### Info

The term **Tool** refers to the Gripper.

- Set tool speed and acceleration, with or without the box.
- Select the digital input for the box sensor.
- To use the Palletizer node in the depalletizing mode, select **Depalletizing**.
- The checkbox **Validate pallet state at program startup** is checked by default. If you unselect it :
  - The first time the program is run, the system will consider that the pallets are empty (palletizing mode) or full (depalletizing mode).
  - If the program is interrupted, the current status (number of boxes processed on each pallet) will be kept.
  - If the program is saved, the status will be saved with it and the next time the program will be loaded, it will restart from this status.
  - If you start a program where the checkbox is checked by default, you can have either one of these pop-up information.



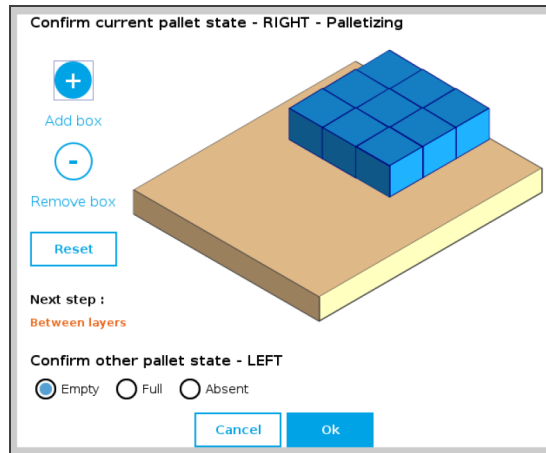
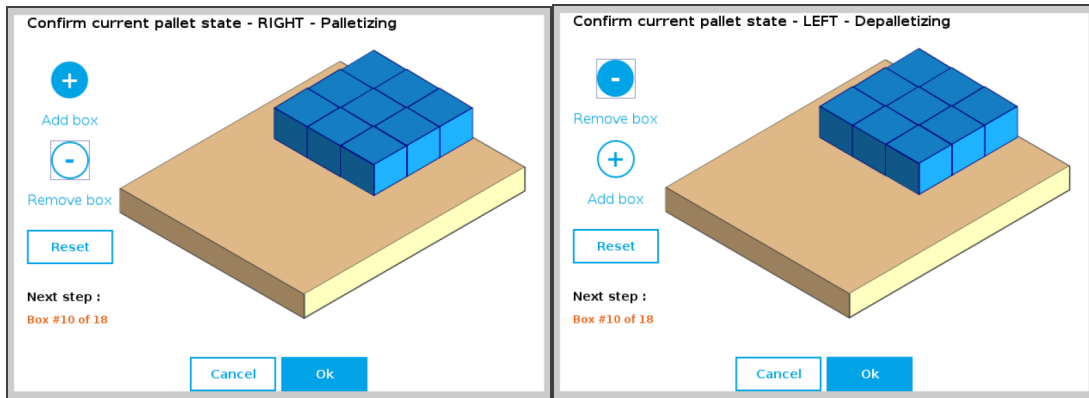


Fig. 5-1: Using pallets on both side requires confirming the other pallet state.

5. By default, the 90° and 180° checkboxes (**Allow gripper to pick the box at different angles**) are ticked. This allows the gripper to perform rotations of 90° or 180° around the Z-axis for trajectory optimization. It can be unticked if it is not possible for the gripper to pick the box at 90° or 180° relative to the gripping position originally taught.
6. To configure a collision avoidance with a conveyor, select the **Avoid collision with conveyor** checkbox. Choose the applicable configuration (perpendicular, parallel or custom) and fill in the fields following the indications on the associated image.



## Palletizer

**Conveyor** ☒ Perpendicular ☐ Parallel ☐ Custom

C1  mm

C2  mm

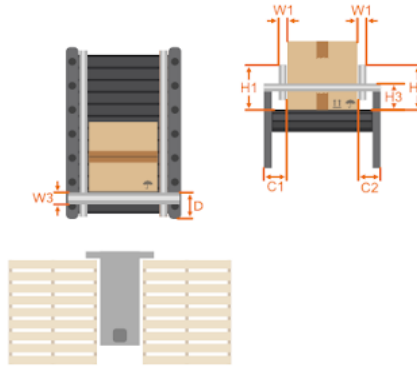
D  mm

H1  mm

H3  mm

W1  mm

W3  mm



## Palletizer

**Conveyor** ☐ Perpendicular ☒ Parallel ☐ Custom

Direction

☒ From left

☐ From right

C1  mm

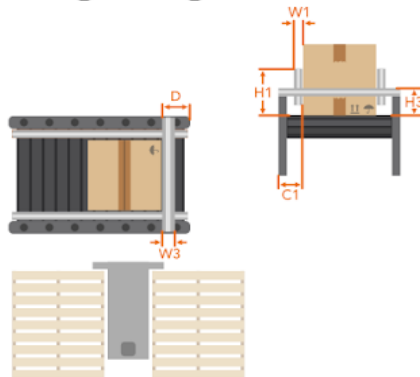
D  mm

H1  mm

H3  mm

W1  mm

W3  mm



## Palletizer

**Conveyor** ☐ Perpendicular ☒ Parallel ☐ Custom

Direction

☐ From left

☒ From right

C2  mm

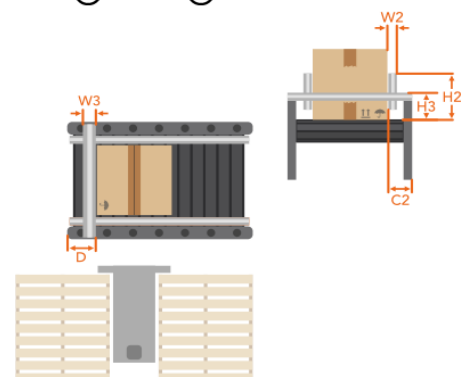
D  mm

H2  mm

H3  mm

W2  mm

W3  mm



## Palletizer

**Conveyor** ☐ Perpendicular ☐ Parallel ☒ Custom

A  °

C1  mm

C2  mm

D  mm

H1  mm

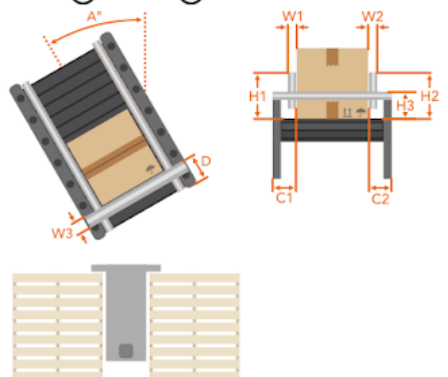
H2  mm

H3  mm

W1  mm

W2  mm

W3  mm

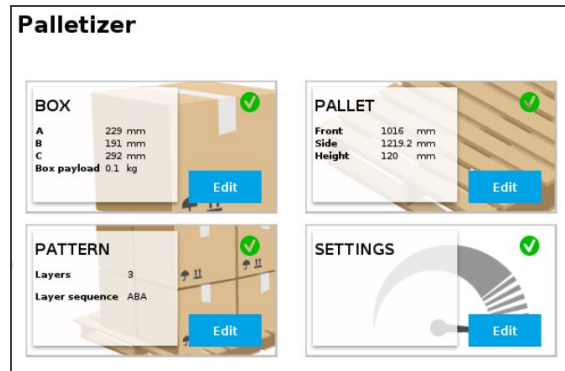


- If required, select the **Add virtual planes around pallet(s)** option. When ticked, this feature adds virtual planes when the trajectories are computed, in order to prevent the boxes and the robot from extending too far beyond the edges of the pallet during approach. To ensure a proper operation of the Solution, a minimum distance of 50 mm is recommended.





- 13 All your Palletizer parameters have been configured. You are now ready to start your Solution.



## 5.1.2. Linear Axis Move node

- The **Linear axis move** node can be used to move the linear axis to a specific position. It can be used inside or outside the Palletizer node. You can command the axis to move at a:
  - Fixed position**
  - Relative position** : the position is relative to the current position. The entered value can be positive or negative.
  - Variable position**: the position is dictated by a variable (global or local).

**Linear axis move**

**Position**

Current position 570 mm

Move Fixed position ▼ 0 mm Move Here

**Motion**

Speed Fixed position 200 mm/s

Acceleration Relative position 1000 mm/s<sup>2</sup>

☒ Wait for motion completed

**Linear axis move**

**Position**

Current position 570 mm

Move Fixed position ▼ 0 mm Move Here

**Motion**

Speed 200 mm/s

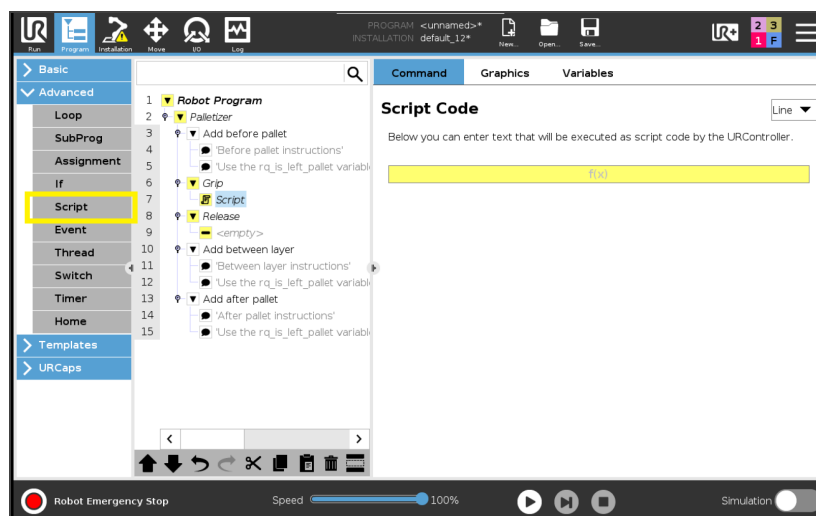
Acceleration 1000 mm/s<sup>2</sup>

☒ Wait for motion completed

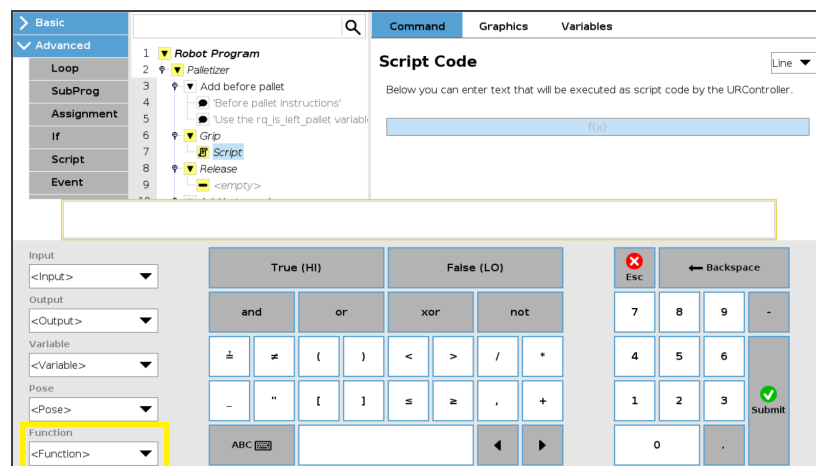


## 5.2. Palletizing Script Functions

- 1 Palletizing functions are made available in the **Script** drop-down menu.



- 2 Tapping on the Script Code textbox (f(x)), then on the drop-down **Function** menu gives access to the script functions list.



## 5.2.1. Get Linear Axis Position

### Description

This function can be used anywhere in the program and returns the linear axis position measured from the lowest point of the axis.

### Declaration

```
rq_get_linear_axis_pos( )
```

### Return value

This function returns a float which expresses the linear axis position in meters.

## 5.2.2. Disable Linear Axis

### Description

The linear axis decelerates to a complete stop but remains powered (the brake is not applied). The communication between the robot controller and the linear axis controller remains active.

### Declaration

```
rq_linear_axis_disable( )
```

### Return value

The `rq_linear_axis_disable( )` or `rq_linear_axis_disable(True)` function returns True when it succeeds. If the function fails, it returns an error message and the program stops. When the function returns True, the event is recorded in the **UR Log** tab.

The `rq_linear_axis_disable(False)` function returns True when it succeeds, and returns False when it fails (the program is not stopped). The event, whether successful or failed, is recorded in the **UR Log** tab.

## 5.2.3. Start Linear Axis

### Description

This function is the equivalent of the **Start** button. The linear axis brake is released.

Use this function before a palletizer or a linear axis move node. The linear axis must be scanned before the use of this function.

### Declaration

```
rq_linear_axis_start( )
```

### Return value

The `rq_linear_axis_start( )` or `rq_linear_axis_start(True)` function returns True when it succeeds. If the function fails, it returns an error popup and the program stops. When the function returns True, the event is recorded in the **UR Log** tab.

The `rq_linear_axis_start(False)` function returns True when it succeeds and returns False when it fails (the program is not stopped). The event, whether it is successful or failed, is recorded in the **UR Log** tab.



## 5.2.4. Number of Processed Boxes

### Description

This function must be used inside the palletizer node in order to work properly (see example) and returns the number of processed boxes.

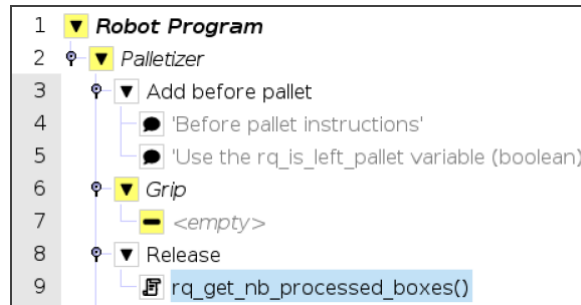
### Declaration

```
rq_get_nb_processed_boxes()
```

### Return value

This function returns an integer which expresses the number of processed boxes.

### Example of use



## 5.2.5. Set Pallet Completed

### Description

Use this function inside a **Grip** or **Release** folder. The palletizer will process the current box and go directly to the **Add after pallet** folder. The **Add between layer** folder will not be executed.

### Declaration

```
rq_set_pallet_completed()
```

### Return value

There is no return value with this function.

## 5.2.6. Get Pallet State

### Description

This function can be used anywhere in the program. It returns the state of a pallet.

### Declaration

```
rq_get_pallet_state(is_pallet_left)
```

### Parameters

- Enter **True** to get the state of the **left** pallet.
- Enter **False** to get the state of the **right** pallet.

### Return value

This function returns an integer from 0 to 3 :



- 0 = Waiting, Idle : Solution is waiting for a new pallet or a user confirmation that the pallet is ready.
- 1 = Ready : Pallet is ready to begin the palletizing or depalletizing process.
- 2 = In progress : Palletizing/depalletizing is in progress on the pallet.
- 3 = Completed : Pallet is full (palletizing) or empty (depalletizing).

## 5.2.7. Set Palletizer State

### Description

This function must be used outside the palletizer node in order to work properly. It configures the state of a Palletizer node.

### Declaration

`rq_set_palletizer_state(palletizer_index, processed_boxes, next_step, other_pallet_state=INACTIVE, current_pallet=CURRENT)`

### Parameters

- **palletizer\_index** : Palletizer nodes for which the state will be numerically ordered, beginning from 0 (the first node number will be 0, the second node number will be 1 and so on).
- **processed\_boxes** : Number of boxes palletized or depalletized on the current pallet.
- **next\_step** : Next step on the current pallet.
  - BOX : The robot will place a box on next step.
  - BEFORE\_PALLET : The robot will execute the **Add before pallet** on next step.
  - BETWEEN\_LAYERS : The robot will execute the **Add between layer** on next step.
  - AFTER\_PALLET : The robot will execute the **Add after pallet** on next step.
  - NEXT\_PALLET : On next step, the robot will start processing the other pallet.
- **other\_pallet\_state** : State of the other pallet (not currently processed).
  - EMPTY : There is no box on the pallet.
  - FULL : The pallet is full of boxes.
  - ABSENT : The pallet is not in place.
  - INACTIVE : When the Palletizer node does not use the other pallet.
- **current pallet** : The pallet on which the robot is currently working on.
  - LEFT : The current pallet is the left one.
  - RIGHT : The current pallet is the right one.
  - CURRENT : The current pallet is the same as before calling this function.

### Return value

There is no return value with this function.



## 5.3. Vacuum Gripper Behavior

Workpiece gripping /releasing is performed by changing the values of the gripper input registers. While the control is very simple, some behaviors deserve a better explanation. The Vacuum Gripper can work in two different mode: the **Automatic** and **Advanced** modes. For more details, please refer to the AirPick Vacuum Gripper instructions manual.

## 5.4. AirPick Vacuum Control over Universal Robots with URCaps

### Info

Please refer to the AirPick Vacuum Gripper instructions manual to have all the information about the URCap.



## 6. Specifications

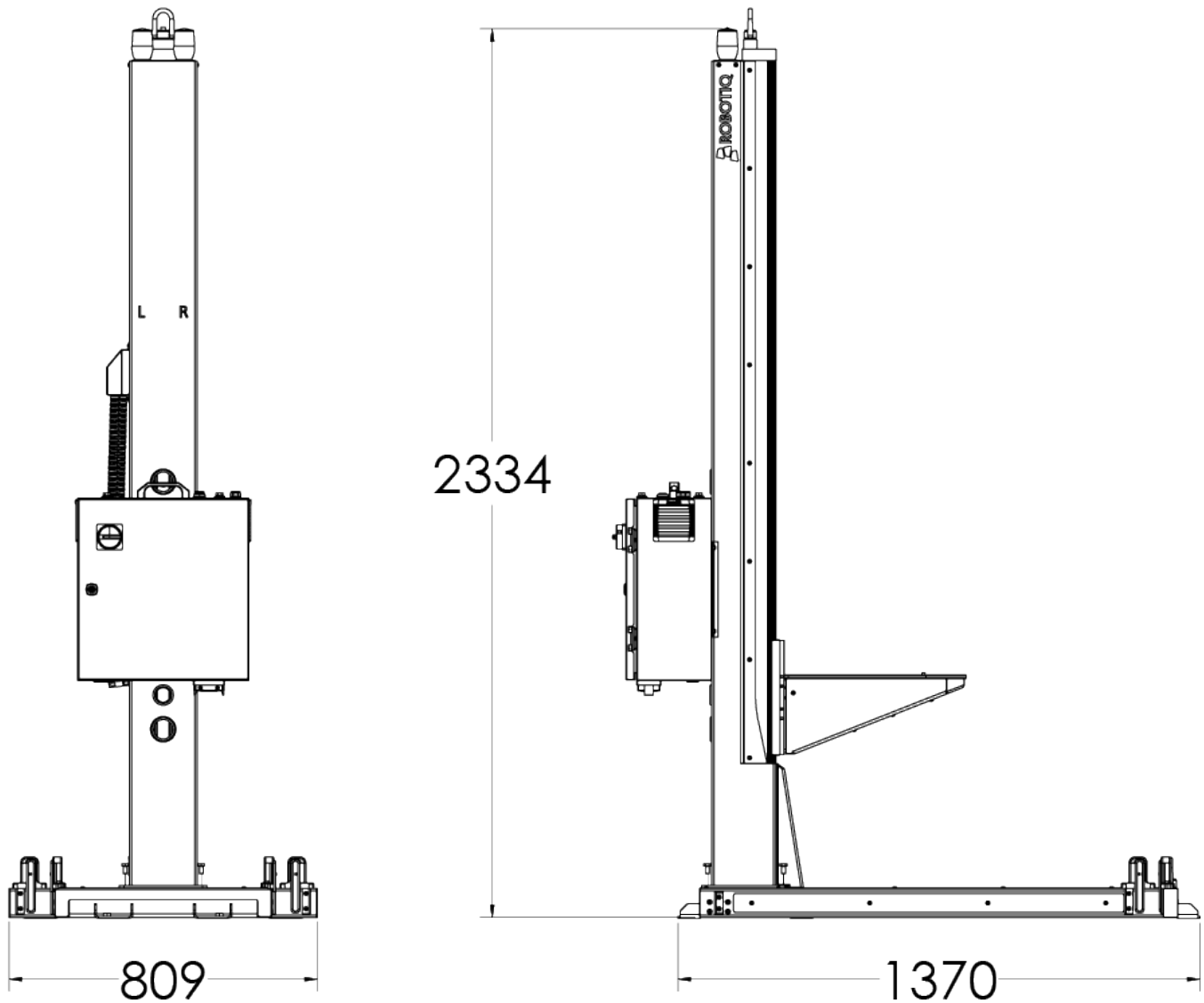
### Caution

This manual uses the metric system, unless specified, **all dimensions are in millimeters.**

The following subsections provide data on the various specifications for the Robotiq Palletizing Solution.

### 6.1. Technical Dimensions

#### 6.1.1. Linear Axis Base with Controller



### 6.1.2. AirPick Vacuum Gripper

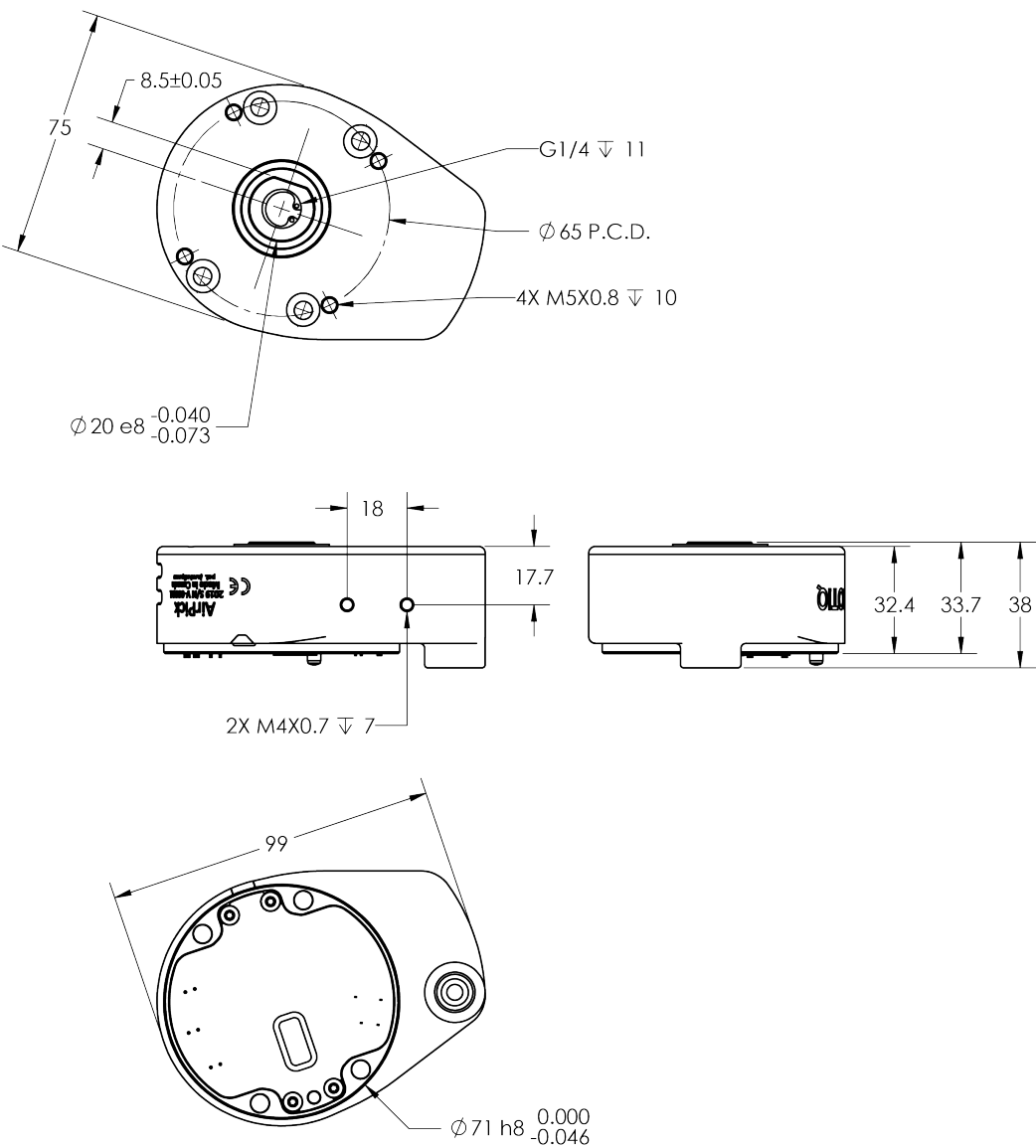
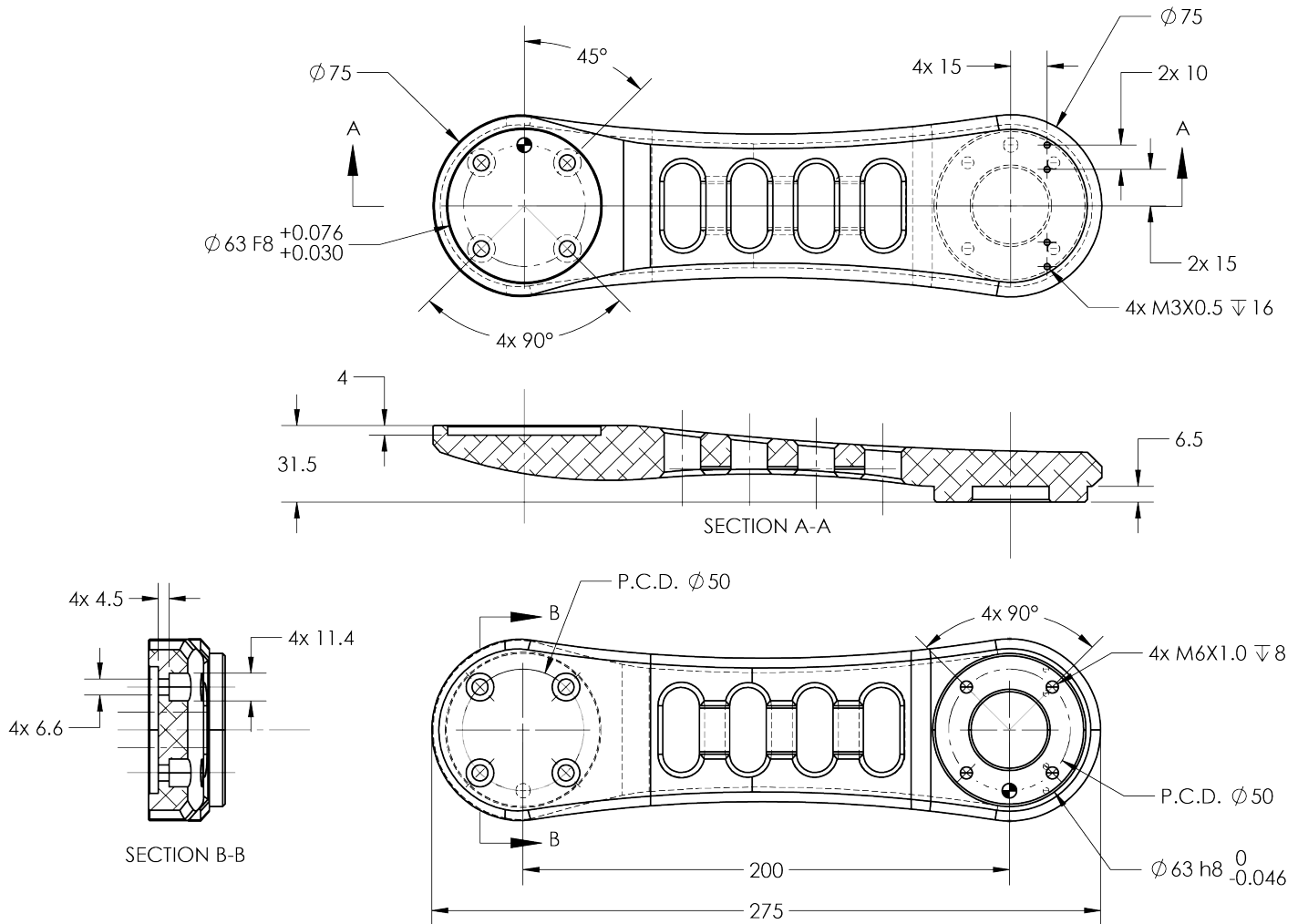


Fig. 6-1: AirPick general dimensions





## 6.1.3. Extra Reach Bracket



## 6.1.4. Bracket for Two (2) Suction Cups

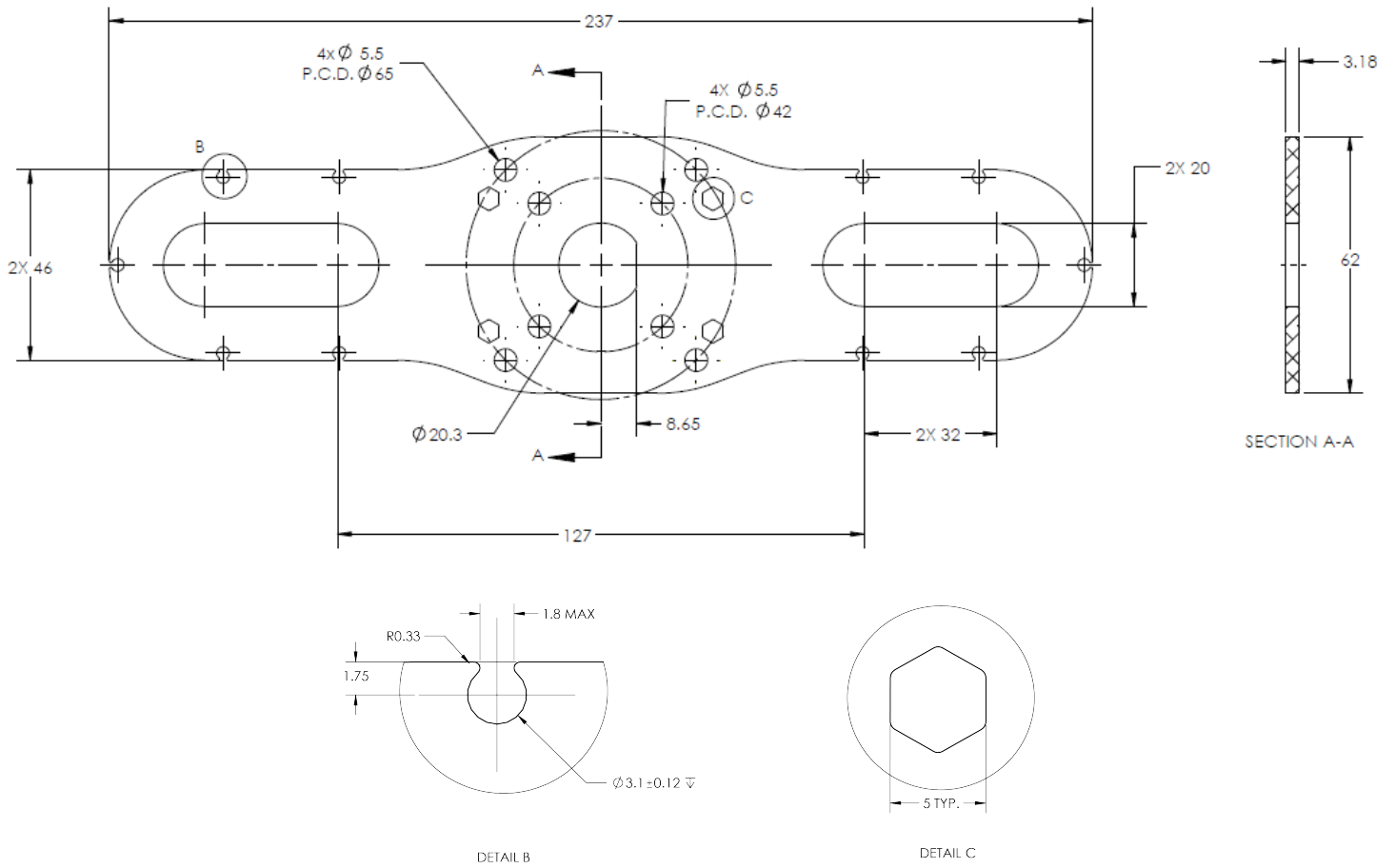


Fig. 6-2: Two air nodes bracket's dimensions



## 6.1.5. Bracket for Four (4) Suctions Cups

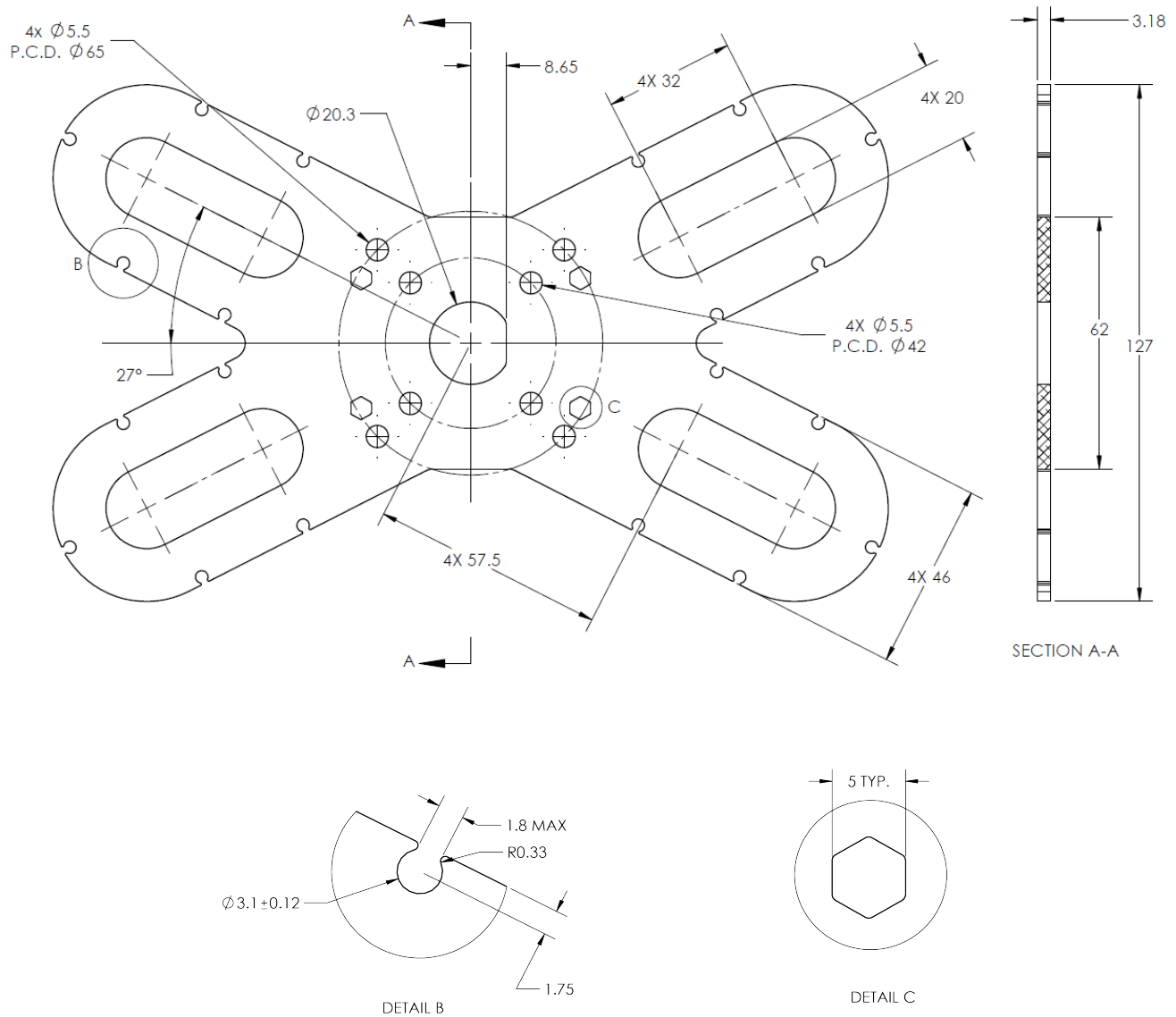


Fig. 6-3: Four air nodes bracket's dimensions

## 6.2. Mechanical Specifications

### 6.2.1. Palletizing Solution (Without AirPick Vacuum Gripper)

Parameter	Specification	
	Metric	Imperial
Net product weight (without robot and gripper)	155 kg	340 lb
Base weight	45 kg	98 lb
Column weight	110 kg	242 lb
Maximum box weight <sup>1</sup>	Up to 16 kg	Up to 35 lb
Minimum box dimensions <sup>2</sup>	See explanations below	
Minimum pallet width and depth	300 mm	12 in
Maximum pallet dimensions width and depth <sup>3</sup>	See explanations below	
Minimum pallet height (empty)	50 mm	2 in
Maximum pallet height (filled)	Up to 2750 mm	Up to 108 in
Shipping crate dimensions	[2380, 950, 1250 ] mm (L, W, H)	[93-7/8, 37-3/8, 49-1/16] in (L, W, H)
Gross shipping weight	317 kg	697 lb
Maximal acceleration in operating conditions	2 g	
Maximum box throughput	Up to 13 boxes/min <sup>4</sup>	
Maximum number of box patterns	2	
Energy source	Electricity	

<sup>1</sup> Maximum box weight depends on the robot model and gripper used.

<sup>2</sup>The minimum box dimensions depend on pallet dimensions. See section below for more details.

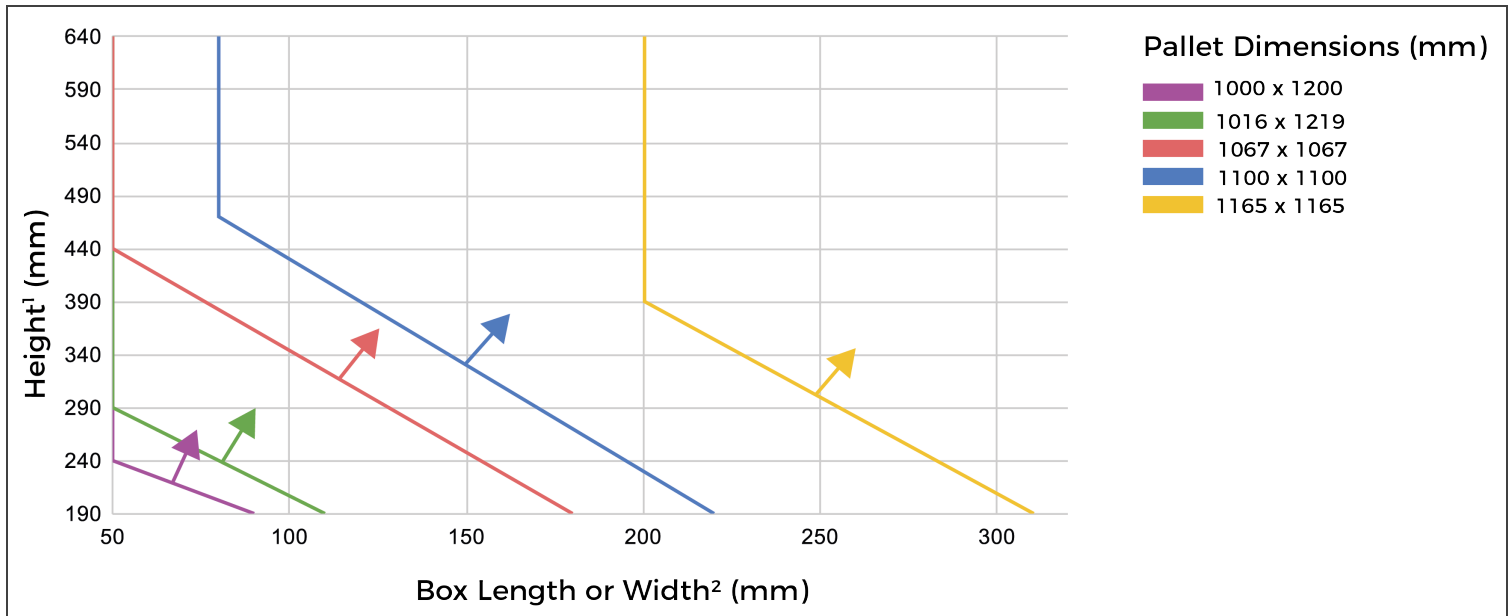
<sup>3</sup>The maximum pallet dimensions depend on your box dimensions. See section below for more details.

<sup>4</sup>The maximum box throughput depends on box weight, box dimensions, box surface, pallet dimensions, and pallet layout.

*Table 6-1: Mechanical Specifications of the Robotiq Palletizing Solution*



- The maximum pallet and the minimum box dimensions are interdependent. The figure below shows box compatibility for different pallet dimensions when using the extra reach bracket (TCP offset in X direction of 200 mm).
- Each color line in the graphic represents pallet dimensions. To figure out if your box dimensions will fit with the pallet dimensions, note that all combinations on the right of each line are available possibilities. For example, if you have a pallet of 1165 x 1165 mm (yellow line) and a total height<sup>1</sup> of 300 mm, all boxes with a length/width  $\geq 250$  will work.
- The pallet 800 mm x 1200mm is not represented in the figure, as all box sizes are possible.



<sup>1</sup>The sum of the pallet and box heights plus the TCP offset in Z direction.

<sup>2</sup>Boxes imprint is square. If your box is not, the figure can be used using the smaller dimension.

- Please refer to **Center of Mass, Tool Center Point (TCP)** section to know the TCP offset you have to use, depending on your gripper configuration.
- Here are a few examples of some common pallet dimensions while using a pallet of 100 mm of height and the AirPick with 4 suction cups and the extra reach bracket.



Region	Dimensions (mm) (Width x Depth)	Examples of box dimensions <sup>1</sup> (mm)
North America	1016 x 1219	50 x 50 x 50
Australia	1165 x 1165	210 x 210 x 140
Asia	1100 x 1100	150 x 150 x 85
Europe, Asia	1000 x 1200	50 x 50 x 50
North America, Europe, Asia	1067 x 1067	110 x 110 x 85
Europe	800 x 1200	50 x 50 x 50

<sup>1</sup>Possible box dimensions. Any size larger than those listed will work.

## 6.2.2. AirPick Vacuum Gripper

Specifications	AirPick Vacuum Gripper	
	Metric Units	Imperial Units
Energy source	Electricity and compressed air	
Gripper mass (including coupling)	545 g	1.20 lb
Minimum Feed pressure	3 bar	43.5 PSI
Maximum Feed pressure	7 bar	101.5 PSI
Optimal feed pressure <sup>1</sup>	6.5 bar / 7 bar	95 PSI / 101.5 PSI
Air consumption at optimal pressure <sup>1</sup>	135.9 SLPM / 106.7 SLPM	35.9 gpm / 28.2 gpm
Maximum torque permissible by custom suction cup bracket	150 Nm	110 lbf-ft
Air supply connection type	8 mm OD Tube	5/16 in OD Tube
AirPick Gripper noise level	70.5 dBa	
Maximum Vacuum level at optimal pressure <sup>1</sup>	85 % / 80%	



Specifications	AirPick Vacuum Gripper	
	Metric Units	Imperial Units
Blow off flow at 0.65 MPa feed pressure	130 SLPM	
Maximum acceleration in operating condition	2 g	
Contaminants and purity classes	ISO 8573-1 class 3.4.3	

1Data is presented as follows : for serial number  $\leq$  V-01351 / for serial number  $\geq$  V-01352.

### 6.2.3. Center of Mass, Tool Center Point (TCP)

Products	Center of mass (mm)			TCP (mm)			Mass (g)
	X	Y	Z	X	Y	Z	
AirPick (without suction cup)	-0.5	-9.0	21.0	0.0	0.0	44.7	545
AirPick (with 1 suction cup)	-0.5	-8.5	23.4	0.0	0.0	76.7	580
AirPick (with 2 suction cups)	-0.3	-5.1	40.3	0.0	0.0	127.7	955
AirPick (with 4 suction cups)	-0.2	-4.2	46.7	0.0	0.0	127.7	1180
AirPick (without suction cup) + extra reach bracket	145.8	-4.1	27.9	200.0	0.0	72.2	1192
AirPick (with 1 suction cup) + extra reach bracket	147.3	-4.0	29.6	200.0	0.0	104.2	1227
AirPick (with 2 suction cups) + extra reach bracket	159.6	-3.0	44.7	200.0	0.0	155.2	1602
AirPick (with 4 suction cups) + extra reach bracket	164.6	-2.7	51.6	200.0	0.0	155.2	1827
Extra reach bracket (alone)	100.5	0	10.5	200	0	27.5	647



## 6.3. Electrical Specifications

### 6.3.1. Linear Axis Controller

Parameter	Specification
Operating supply voltage	100-240 Vac 60/50 Hz
Quiescent power (minimum power consumption)	290 Wmax 205 Wrms
Peak current	12.8A at 120Vac 6.4A at 240Vac

Fig. 6-4: Linear Axis Controller electrical specifications

**Info**

These are the specifications of the Robotiq Controller, excluding the robot. The overall voltage consumption will vary depending on the robot used.

**Warning**

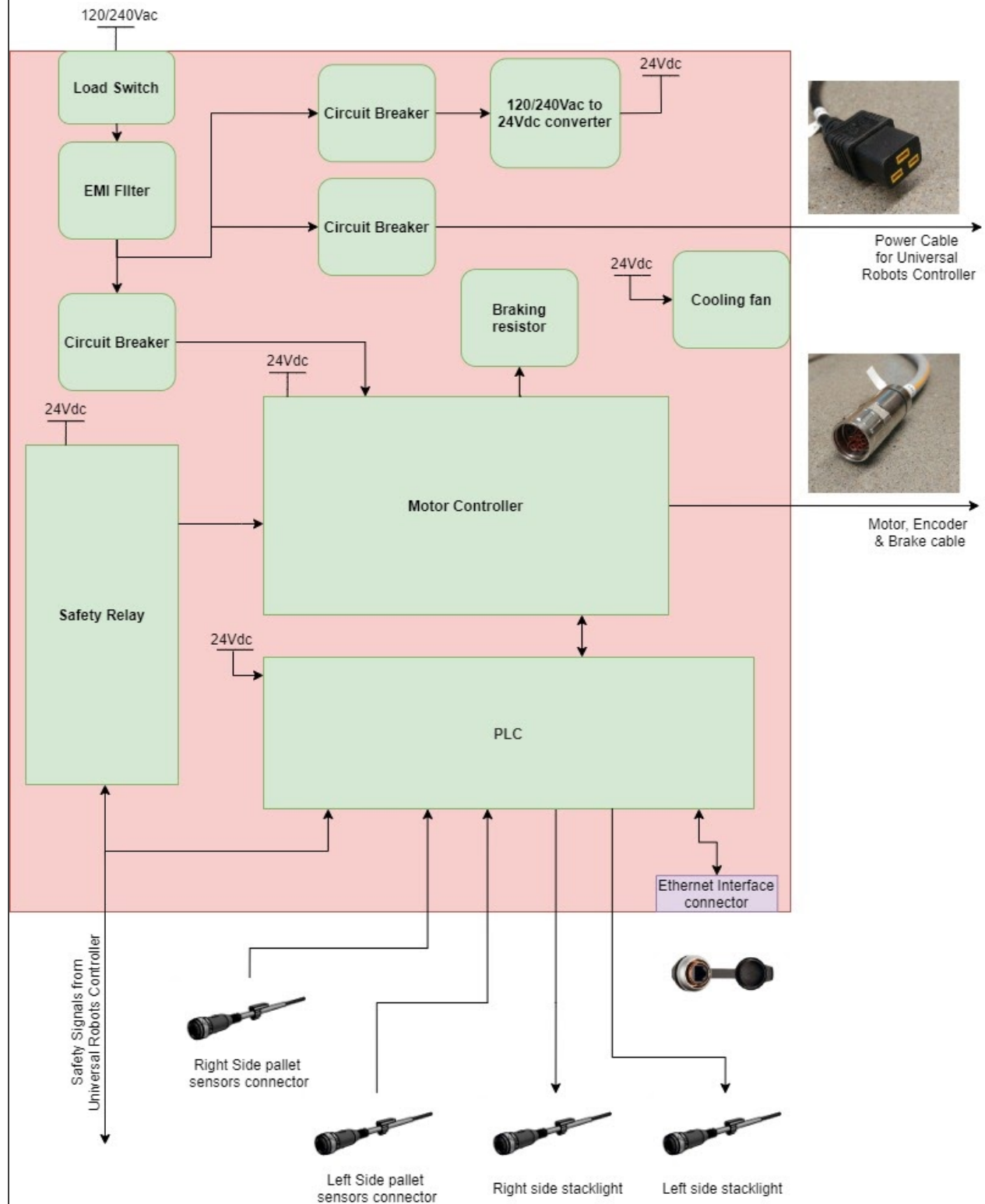
The linear axis controller is CE marked and cCSAus certified. Any modification will void the certification.

The following diagram illustrates the basic connections of the linear axis Controller. For more information, download the electrical package on the [Robotiq support website](#). Do not modify the wiring unless you can recertify the linear axis Controller with local authorities.





## Palletizer Control Box Diagram



### Info

The complete electrical diagram is available on our the [Robotiq support website](#).



## 6.3.2. AirPick Vacuum Gripper

### Info

For all information about AirPick Vacuum Gripper specifications, please consult its instruction manual available on the [Robotiq support website](#).

## 6.3.3. Universal Robots Controller

Please, refer to the **Installation** section for more details about all connections in the UR controller.



## 7. Maintenance

Following the maintenance interval will ensure:

- Correct functioning of the equipment;
- Validity of the warranty;
- Proper lifetime of the equipment.

### Caution

Maintenance operations are for the average normal usage of the Robotiq Palletizing Solution, the maintenance intervals must be adjusted according to the environmental conditions such as:

- Operating temperature
- Humidity
- Presence of chemical(s)
- Presence of physical objects (debris, scraps, dust, grease, etc.)
- Interaction with operated parts (sharp or rough)
- Dynamics of the operation (accelerations)

### Caution

Always turn off the Palletizing Solution and depressurize the air supply tube before performing any maintenance operation on it. For more details about the depressurization, please refer to **Depressurizing the Supply Line** section.

### Caution

The Palletizing Solution is not waterproof or water resistant without additional protection. Only clean the equipment with a dry towel.

### Caution

Maintenance operator must be grounded to prevent electrostatic discharge that could damage electronic equipments.



## 7.1. Linear Axis

### Caution

For every maintenance operation, please verify the axial backlash in the ball screw. If it is greater than 0.2 mm, the linear axis must be replaced.

### 7.1.1. Components lubrication

#### Info

If needed, clean the components before the lubrication.

#### Info

Recommended lubricant : LUB-KC1.

### Ball Screw and Bearing Guide Lubrication

Lubrication of the axis should be done every 2 years considering a typical use of 80h/week. When lubricating, move the carriage all over the axis stroke to distribute the lubricant uniformly.

### Cover Strip and Guide Rail Lubrication

Lubrication have to be done if it is needed or when the component doesn't have its grease film anymore.



## 7.2. Fasteners

Periodically ensure that the bolts are tightened all over the Solution. If necessary, tight again according to the specified torques represented in the table below.

Designation	Location	Tightening Torque	
		(Nm)	[ft-lb]
M6	Column-Axis interface	10.5	7.7
M6	Linear axis carriage interface	9.9	7.3
M8	Pallet sensors	15.0	11.1
M10	Base - Column	50.0	36.9
1/2"-13	Wedge anchors	54.2	40.0
M8	Hoist ring	9.5	7.0
M8	Robot-carriage link	20.0	14.8
M8	Lifting bracket - Linear axis link	9.5	7.0
Motor Coupling	Coupling collar	8.0	5.9

*Table 7-1: Torque Settings - Palletizing Solution*



## 7.3. AirPick Vacuum Gripper

The Vacuum Gripper only requires external maintenance with limited downtime. Maintenance is required after specified usage, measured in cycles (workpiece pick-up and release) or use time (hours).

**Warning**

Unless specified, any **repairs** done on the Vacuum Gripper will be done by Robotiq.

Operation	Daily	Monthly	1 M cycles or 1000 hours
Gripper Cleaning	Dirty conditions	Normal conditions	
Periodic Inspection			X

**Info**

For more details about the AirPick Vacuum Gripper maintenance, please consult its instruction manual available at [robotiq.com/support](https://robotiq.com/support).



## 7.4. Cleaning

### 7.4.1. Air Filter Cleaning

Periodically clean the control panel air filters.

### 7.4.2. Solution Cleaning

Clean the mechanical parts (including the guide rail of the linear axis) with a soft cloth, as required. Cleaning agents include all non-abrasive media.

#### Caution

Do not use compressed air to clean the Vacuum Gripper. Doing so can result in a damage to the check valve or the release valve.

For more information about the AirPick Gripper filter cleaning, please refer to the maintenance section of its instruction manual.

## 7.5. Solution Storage

Ensure short storage times. Choose cool, dry, wellshaded, corrosion-resistant locations.



## 8. Spare Parts, Kits and Accessories

### Info

The following list is up to date at print time and is subject to change, check online for updates.

Item	Description	Ordering Number
Vacuum Cups 1.5 Bellows 55 mm (Silicone)	<ul style="list-style-type: none"><li>• 4 x Vacuum Cups 1.5 Bellows 55 mm (white silicone)</li></ul>	VAC-CUP-55-SI
Cable Management Kit for UR10	<ul style="list-style-type: none"><li>• 1 x Cable Management Kit for UR10 robots</li></ul>	PAL-CBL-MNG-KIT
Status Light for Palletizing Solution	<ul style="list-style-type: none"><li>• 1 x Status Light for the Robotiq Palletizing Solution</li></ul>	PAL-STAT-LIGHT
Type A Pallet sensor - Palletizing Solution	Type A Pallet Sensor Kit for the Robotiq Palletizing Solution <ul style="list-style-type: none"><li>• 1 x Type A Pallet Sensor</li><li>• 1 x screw kit</li></ul> Used for: <ul style="list-style-type: none"><li>◦ Left pallet, back sensor</li><li>◦ Right pallet, side sensor</li></ul>	PAL-SENS-A
Type B Pallet Sensor - Palletizing Solution	Type B Pallet Sensor Kit for the Robotiq Palletizing Solution <ul style="list-style-type: none"><li>• 1 x Type B Pallet Sensor</li><li>• 1 x screw kit</li></ul> Used for: <ul style="list-style-type: none"><li>◦ Left pallet, side sensor</li><li>◦ Right pallet, back sensor</li></ul>	PAL-SENS-B
Box Sensor Kit - Palletizing Solution	Box Sensor Kit for the Robotiq Palletizing Solution <ul style="list-style-type: none"><li>• 1 x Box Sensor</li><li>• 1 x Cable</li><li>• 1 x Mounting Brackets</li></ul>	PAL-BOX-SENS-KIT





# 9. Troubleshooting

## 9.1. Palletizing Solution (except the AirPick Gripper)

Symptom / Issue	Cause	Solution
The robot was brought to a protective stop after a few layers	A collision occurred between the gripped box and a box on the pallet. A minor palletizing error carried over from previous layers.	<ul style="list-style-type: none"><li>• Increase the box height value to compensate for box size discrepancies.</li><li>• A good practice to determine box height is to measure the height of a full pallet (boxes only), and divide it by the number of layers on the pallet.</li></ul>
The robot started dropping boxes from a great height	A minor palletizing error carried over from previous layers.	Decrease the box height value.
	The TCP entered is incorrect.	Confirm that the TCP is located above the box, at the picking position.
	The pallet height value entered is too low.	Increase the pallet height value.
The robot entered in collision with a box already placed on the pallet	A collision occurred between the gripped box and a box on the pallet. A minor palletizing error carried over from previous layers.	<ul style="list-style-type: none"><li>• Increase the box height value to compensate for box size discrepancies.</li><li>• A good practice to determine box height is to measure the height of a full pallet (boxes only), and divide it by the number of layers on the pallet.</li></ul>
	One or several faces of the box are rounded.	Increase the box width and/or box length value.
	The pallet state in the pallet viewer does not correspond to the actual pallet state.	Inspect the pallet viewer at program start and confirm that the virtual layout corresponds with the actual layout.
	The pallet height value entered is too high.	Decrease the pallet height value.



The robot triggered a protective stop when placing a box on the first layer	The box height value entered is too high.	Verify the box height value.
	The pallet height value entered is too high.	Verify the pallet height value.
	The TCP entered is incorrect.	Confirm that the TCP has been set correctly.
Boxes are not consistently placed straight on the pallet	The picking position is not stable.	Make sure your conveyor stop consistently places boxes in the same position. Box position should be consistent in order to ensure a reliable picking.
	The picking position is incorrect.	Make sure that the picking position places the vacuum gripper so that it is squared and centered with the box.
Error Message "Collision detected" during trajectory.	The layout in the pallet viewer does not correspond with the actual layout. The robot detected a collision with an object that is not actually present.	<ul style="list-style-type: none"> <li>Restart the program and select the right box step.</li> <li>Verify the TCP position and orientation values.</li> </ul>
Error Message "Discontinuous path / joint solution impossible detected, please change your starting point."	A singularity was reached on a planned trajectory.	<ul style="list-style-type: none"> <li>Go to PolyScope's Move tab, and verify if the joints are at the center of their range (<math>0^\circ</math>) when the robot is at the picking position. The algorithm will adjust wrist 3 automatically at program start.</li> <li>If the box position is too close to robot base, discontinuous path issues can occur. Verify that the picking zone is respected.</li> <li>If this situation only occurs with pallets on one side of the Solution, try centering the layer pattern on the pallet.</li> <li>Verify TCP position and orientation values.</li> <li>The robot may have reached a singularity or be closed to reaching a singularity. Move the robot to the Home position and restart the program.</li> <li>Should none of the above steps solve the issue, please contact the Robotiq support department.</li> </ul>



Collisions occur with the pallet sensor on one side, but not on the other	The column is not centered on the base.	Execute the centering procedure found in the <b>Installation</b> section.
An actual collision occurred	The TCP entered is incorrect.	Confirm that the TCP has been configured correctly
	The TCP entered is incorrect since it does not account for the bracket used.	Configure the TCP correctly.
	The gripper is bigger than the box.	The size of the surface covered by the gripper or suction device should always be equal or smaller than the size of the face of the box that is being gripped. Please refer to the <b>Other Grippers</b> section for more details.
The robot waits indefinitely over the picking position	The box presence sensor is misused or not connected.	<ul style="list-style-type: none"> <li>• Verify that the correct box presence input has been selected.</li> <li>• Verify that the sensor used is active-high if a sensor other than the sensor provided is being used.</li> </ul>



Error message: "Please use the Safeguard reset before starting the linear axis"	Power off and power on the Linear Axis Controller.	Power off and power on the Linear Axis Controller.
	The cables of the Linear Axis are not properly connected to the UR controller.	Inspect the connections. Please refer to the Safety Connections section.
	The "Safety configuration" and/or "System Emergency Stopped" functions were not configured correctly.	Verify that the "Safeguard reset" and "System Emergency Stopped" functions are configured correctly.  Installation tab > Safety > I/O
	No safeguard measure is being used, but none have been bypassed.	Even if the safeguard function is not used, both the safeguard wire and reset wire from the Linear Axis should be connected to a 24V terminal block in the UR controller (bypass).  Please refer to the Safety Connections section for more information.
	A safeguarding OSSD is connected directly to the robot.	OSSD signals are <b>not</b> compatible with the Linear Axis (even if the e-Series UR controller can be compatible).  A special relay is required to convert OSSD signals to standard signals.
	The emergency output from the UR controller is set to OSSD signal. (e-Series only)	Verify that the OSSD checkbox for the "System Emergency Stopped" output is unticked. (Installation tab > Safety > I/O)  OSSD signals are not compatible with the Linear Axis.
The robot was brought to a protective stop while palletizing	A joint limit has been exceeded.	<ul style="list-style-type: none"> <li>• Verify that the joint speed and position limit have been configured correctly. Please refer to the <b>Robot Configurations</b> section for more information.</li> <li>• Decrease the value of the acceleration parameter in the Palletizer node.</li> </ul>



<p>Error message: "RTDE interface cannot initialize. Make sure that Ethernet/IP adapter and Profinet are disabled, and that no tother URCaps use the RTDE interface."</p>	<p>We employ registers that cannot be used with Ethernet/IP or Profinet at the same time when the following function checkbox is ticked:</p> <p>Installation &gt; URCaps &gt; Copilot &gt; Configuration &gt; General: "Use Copilot to manage a soft speed transition when resuming from a Safeguard stop"</p>	<ul style="list-style-type: none"> <li>• Update to the latest version of the Copilot software.</li> <li>• Untick the "Use Copilot to manage a soft speed transition when resuming from a Safeguard stop" checkbox.</li> </ul>
<p>Error message: "org.apache.xmlrpc.CmlRpcException: One parameter is invalid in the fromjson request"</p>	<p>The Linear Axis may be below its home position (0 mm).</p>	<ul style="list-style-type: none"> <li>• Bring the Linear Axis above its home position (0 mm) before starting the program.</li> <li>• Update to the latest version of the Copilot software.</li> </ul>

## 9.2. AirPick Vacuum Gripper

### 9.2.1. Communication

When using AirPick Vacuum gripper with USB to RS485 serial converter:

Troubleshooting from the Gripper LED:

1. LED is not lit, Gripper not powered.
  - a. Check Gripper power supply and electrical setup
2. LED is solid blue and red, Gripper is in fault.
  - a. Disconnect the communication and power cycle the Gripper. The LED should turn solid red when powered.
  - b. While powered with red LED, connect the communication, LED should turn solid blue when connection is established.
3. Flashing blue and red LED, Gripper is in fault.
  - a. Gripper may be in auto-release, wait for auto-release to be completed, then turn off auto-release and initialize the Gripper.
  - b. Gripper may have a major fault, check the error from fault status and contact support.
4. Solid blue, no fault and communicating.
  - a. If you can control the Gripper from the GUI on the pendant, check your program structure.
  - b. If you can not control the Gripper from the pendant, contact support.



5. Solid red, no fault, but Gripper is not communicating.

a. USB-RS485 converter LEDs are :

1.

- Not lit, no USB communication.
  - i. Check USB connection.
  - ii. Re-install drivers.
  - iii. Contact support.
- Red flashes at slow rate.
  - i. Check the DB-9 connector.
  - ii. Check the cable.
  - iii. Check the communication parameters from the Robotiq User Interface, see recovery procedure.
  - iv. Contact support.
- Red and green flashing at high speed.
  - i. Check fault status, maximum operating temperature could be exceeded.
  - ii. Contact support.

When using AirPick vacuum gripper with Universal Robots package:

Troubleshooting from the previous section (LED references) still applies.

From the UR teach pendant:

URCap install:

1. Verify that the latest URCap is installed from the **Robot Setup** menu, inside the **URCaps** tab
  - a. URCaps installation instructions are in the **Installation** section
  - b. Inside the URCaps tab, if you select the appropriate URCap file, you can see the current software version
  - c. Gripper toolbar should appear if installed properly
2. URCap is installed but Gripper cannot be controlled :
  - a. If Gripper LED is not blue, follow the steps in the first section above
  - b. If Gripper LED is blue, URCap is installed with the latest available version, contact [support@robotiq.com](mailto:support@robotiq.com)
3. Verify that the latest URCap is installed by tapping the **triple bar icon** in the upper right corner, selecting **Settings**, then tapping the **System** menu and the **URCaps** button in the navigation pane on the left
  - a. URCaps installation instructions are in the **Installation** section
  - b. Inside the URCaps menu, if you select the appropriate URCap file, you can see the current software version
  - c. The Gripper toolbar should appear if installed properly



4. URCap is installed but Gripper cannot be controlled :

1. If Gripper LED is not blue, follow the steps in the first section above
2. If Gripper LED is blue, URCap is installed with the latest available version, contact [support@robotiq.com](mailto:support@robotiq.com)

Driver package install:

1. Driver checkup :

- a. Use the latest driver version available at [support.robotiq.com](http://support.robotiq.com)
  - Use the installation instruction from the **Installation** section
- b. To check your driver version :
  - With the Gripper unplugged
  - From the UR teach pendant screen, click the "Gripper" button
    - i. Driver version will be shown
    - ii. If Gripper button is not displayed, driver package is not properly installed, see instruction from the

2. Driver is installed but Gripper cannot be controlled :

- a. If Gripper LED is not blue, follow the steps in the first section above
- b. If Gripper LED is blue, driver is installed with the latest available version, contact [support@robotiq.com](mailto:support@robotiq.com)

## 9.2.2. Vacuum Gripper Verification

If you are not able to attain the desired vacuum level or if a diminution of the vacuum level occurs, verify:

- The suction cups status
- That the air path is clean and not obstructed (including the manifold)
- If a filter cleaning is necessary



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# 10. Warranty

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Robotiq warrants the Robotiq Palletizing Solution and all its components against defects in material and workmanship for a period of one year from the date of reception when utilized as intended. Robotiq also warrants that this equipment will meet applicable specifications under normal use.

## Warning

Warranty applies under the following conditions:

- Usage respects the operating and storage conditions specified in the Environmental and Operating Conditions section.
- Proper installation of all the components as specified in the Installation section and the following subsections.
- Until one of these condition is reached:
  - 1 year;
  - For AirPick only : 2 000 000 cycles performed (boxes or objects manipulated). Once one of the components reaches the count, the warranty is not applicable anymore.
- Usage respects maintenance specified in the Maintenance section.
- Usage respects recommended payload, force, acceleration and speed specified in the Mechanical specifications section.

During the warranty period, Robotiq will repair or replace any defective component of the Palletizing Solution, as well as verify and adjust the component free of charge if the equipment should need to be repaired or if the original adjustment is erroneous. If the component is sent back for verification during the warranty period and found to meet all published specifications and work as intended, Robotiq will charge standard verification fees.

The component is considered defective when at least one of the following conditions occurs:

- The component feedback necessary for the robot program is not accessible.
- If applicable, the component cannot be controlled from the robot teach pendant
- Wear of the components due to direct contact with the workpiece or obstacles is not covered by the warranty.





### **Caution**

The warranty will become null and void if the :

- Unit has been tampered with, repaired or worked on by unauthorized individuals.
- Screws, other than as explained in this guide, have been removed.
- Unit has been opened other than as explained in this guide.
- Unit serial number has been altered, erased, or removed.
- Unit has been misused, neglected, or damaged by accident.

This warranty is in lieu of all other warranties expressed, implied, or statutory, including, but not limited to, the implied warranties of merchantability and fitness for a particular purpose. In no event shall Robotiq be liable for special, incidental, or consequential damages.

Robotiq shall not be liable for damages resulting from the use of the Palletizing Solution, nor shall Robotiq be responsible for any failure in the performance of other items to which the Palletizing Solution is connected or the operation of any system of which the Palletizing Solution may be a part.

### **Exclusions**

This warranty excludes failure resulting from: improper use or installation, normal wear and tear, accident, abuse, neglect, fire, water, lightning or other acts of nature, causes external to the Palletizing Solution or other factors beyond Robotiq's control. It also excludes all consumable parts, such as suction cups, and their normal wear.

Robotiq reserves the right to make changes in the design or construction of any of its products at any time without incurring any obligation to make any changes whatsoever on units already purchased.



# 11. Harmonized Standards

## 11.1. Applied Standards

This section describes all applied harmonized standards for the design and production of the Robotiq Palletizing Solution and the AirPick Vacuum Gripper. For more information on the standards used for each individual product, please refer to their respective declaration of conformity.

### Caution

Compliance of the product is only met if all instructions of the current user manual are followed, which include, but are not limited to, appropriate installation, compliance with safety measures, and normal usage. A risk assessment specific to the user's final application must also be carried out.

The following standards have been applied:

ISO 12100	2010	Safety of machinery – General principles for design – Risk assessment and risk reduction
ISO 9409-1	2004	Manipulating industrial robots - Mechanical interfaces - Part 1: Plates
ISO 4414	2010	Pneumatic fluid power - General rules and safety requirements for systems and their components
IEC 61000-6-2	2016	Generic standards - Immunity standard for industrial environments
IEC 61000-6-4	2018	Generic standards - Emission standard for industrial environments
EN 60204-1	2018	Safety of machinery - Electrical equipment of machines - Part 1: General requirements



## 11.2. EC Declaration of Incorporation

### 11.2.1. Robotiq Palletizing Solution

#### Info

For all information about the EC Declaration of Incorporation for the Robotiq Palletizing Solution, please refer to the [Robotiq support website](#). The declarations are available for download (Robotiq Palletizing Solution > Universal Robots > Documents > Standards, Declarations and Certificates).

### 11.2.2. AirPick Vacuum Gripper

#### Info

For all information about the EC Declaration of Incorporation for the AirPick Vacuum Gripper, please refer to the instruction manual of the device, available on the [Robotiq support website](#). The declarations are available for download (Vacuum Grippers> Universal Robots > Documents > AirPick Standards, Declarations and Certificates).



# 12. Appendix

## 12.1. Anchoring Pattern

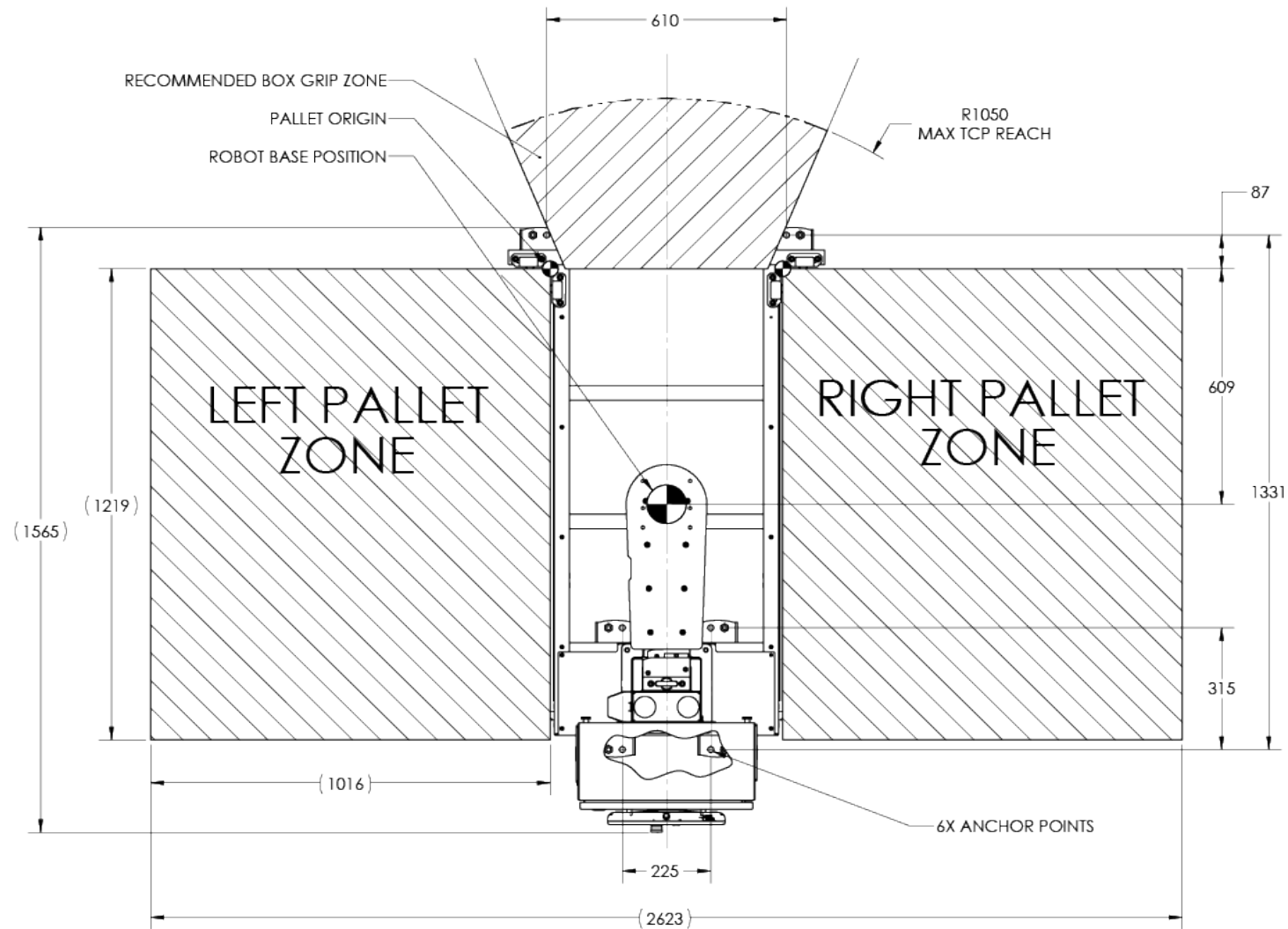


Fig. 12-1: Palletizing Work Zones Schema for UR10



## 12.2. Safety Connections

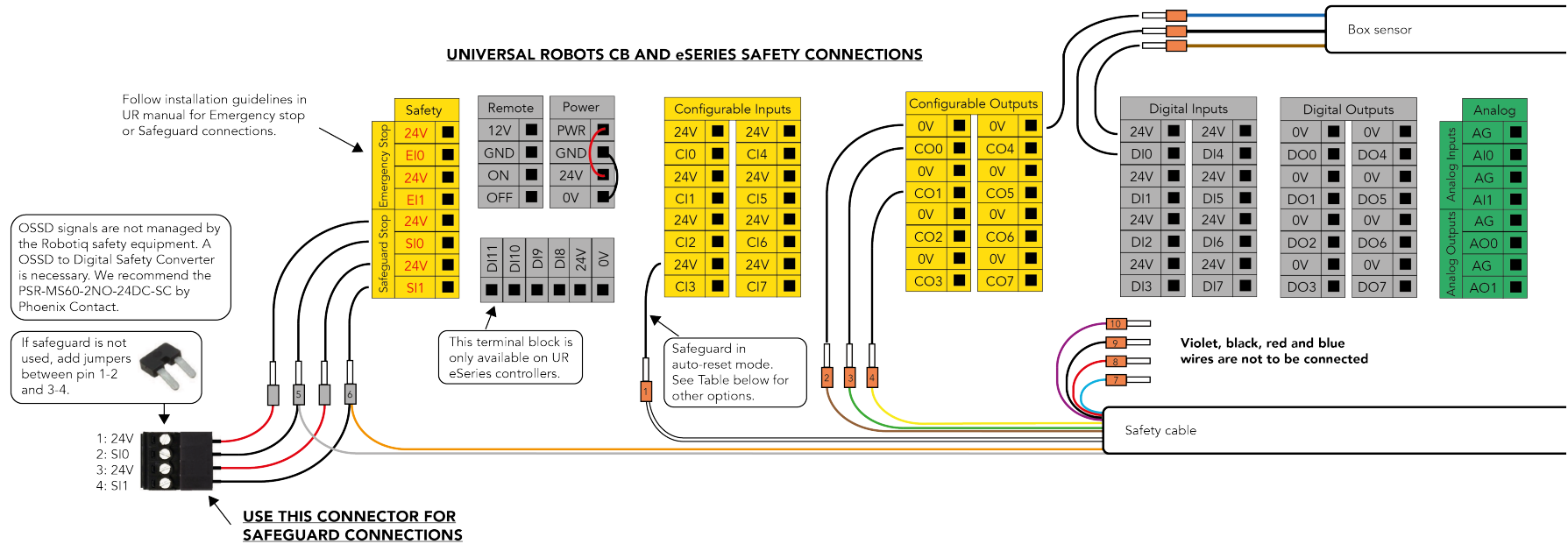


Fig. 12-2: Universal Robots Controller Safety Connections Schema



Wire #	Color	Function	Description
1	White	Safeguard Reset	<p>When using a safeguard reset button, connect wire #1 to the same configurable input as the button.</p> <p>To enable an automatic safeguard reset of the Solution using an area scanner:</p> <ul style="list-style-type: none"> <li>Connect wire #1 to an available 24 V terminal in the UR controller. The system will auto-start when no safeguard signal is triggered.</li> </ul>
2	Brown	0V	0V link between both electrical enclosures.
3	Green	UR E-Stop Status 1	E-Stop status signal when an emergency signal is applied to EI0.
4	Yellow	UR E-Stop Status 2	E-Stop status signal when an emergency signal is applied to EI1.
5	Grey	UR Safeguard input 1	UR does not support safeguard statuses in configurable outputs. Connect this pin to the regular safeguard input SI0 for status.
6	Orange	UR Safeguard input 2	UR does not support safeguard statuses in configurable outputs. Connect this pin to the regular safeguard input SI1 for status.

*Table 12-1: Safety Wires Description*



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# 13. Contact

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[www.robotiq.com](http://www.robotiq.com)

## Contact Us

### Phone

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