COMMISSIONING INSTRUCTIONS

Comfort app
for Fanuc CRX
GuideZ for Laptop for SCM-F/SCM-C

DDOC01747

MOTCH

THE KNOW-HOW FACTORY

ZIMMER group

Content

DDOC01747 / d EN / 2026-02-02

1 Introduction

1.1 Supporting documents

NOTICE

Read through the instructions before installing or working with the product.

The instructions contain important notes for your personal safety. They must be read and understood by all persons who work with or handle the product during any phase of the product lifetime.

The documents listed below are available for download on our website www.zimmer-group.com.

- Instructions
- Catalogs, drawings, CAD data, performance data
- Information on accessories
- Technical data sheets
- General Terms and Conditions, including warranty information.

⇨ Only those documents currently available on the website are valid.

In these instructions, "product" refers to the product designation on the title page!

1.2 Notices and graphics in the instructions

DANGER

This notice warns of an imminent danger to the life and health of people. Ignoring these notices can lead to serious injury or even death.

► You absolutely must comply with the described measures for avoiding these dangers!

⇨ The warning symbols are assigned according to the type of danger.

WARNING

This notice warns of a situation that is potentially hazardous to personal health. Ignoring these notices can cause serious injury or damage to health.

► You absolutely must comply with the described measures for avoiding these dangers!

⇨ The warning symbols are assigned according to the type of danger.

CAUTION

This notice warns of a situation that is potentially hazardous to persons. Ignoring these notices can cause minor, reversible injuries.

► You absolutely must comply with the described measures for avoiding these dangers!

⇨ The warning symbols are assigned according to the type of danger.

NOTICE

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

► You absolutely must comply with the described measures for avoiding these dangers!

⇨ The warning symbols are assigned according to the type of danger.

INFORMATION

This category contains useful tips for handling the product efficiently. Failure to observe these tips will not result in damage to the product. This information does not include any information relevant to health or workplace safety.

2 Proper use

NOTICE

Material damage and malfunction in case of non-compliance

The product is only to be used in its original state with its original accessories, with no unauthorized changes and within the stipulated parameter limits and operating conditions.

Any other or secondary use is deemed improper.

- ▶ Operate the product only in compliance with the associated instructions.
- ▶ Operate the product only when it is in a technical condition that corresponds to the guaranteed parameters and operating conditions.
- ⇨ Zimmer Group GmbH shall accept no liability for any damage caused by improper use. The operator bears sole responsibility.

The product is intended for installation and operation on the robot control panel *Tablet Teach Pendant* of the *R-30iB Mini Plus* robot control system.

3 Personnel qualification

WARNING

Inadequate qualification can cause injury and material damage

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

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

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

3.1 Electricians

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

3.2 Specialists

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

3.3 Instructed personnel

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

3.4 Service personnel

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

3.5 Additional qualifications

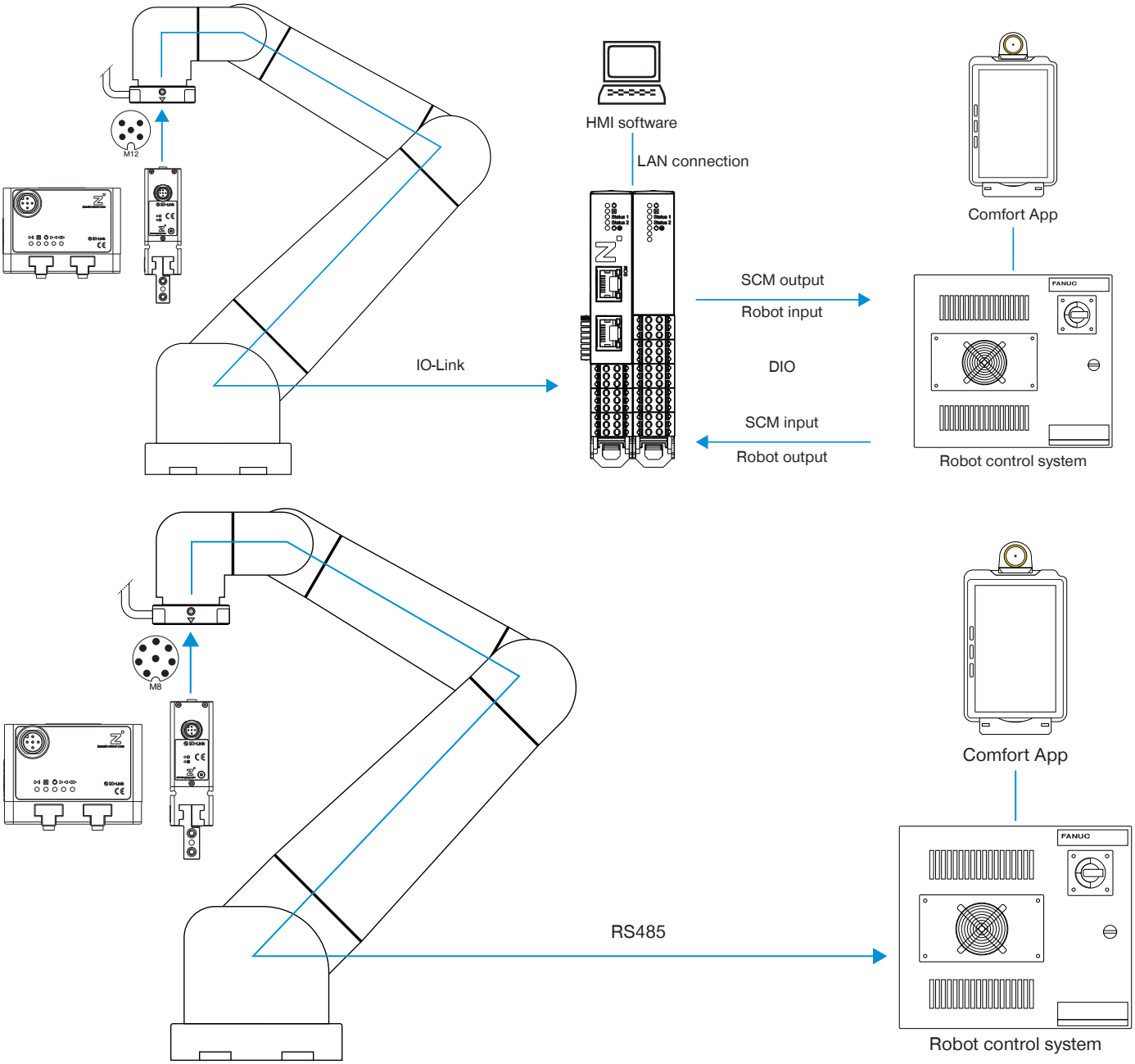
Persons who work with the product must be familiar with the valid safety regulations and laws as well as the standards, guidelines and laws listed in this document.

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

4 Product description

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

The image shows a simplified view of the structure of the overall system. All parts for the electrical connection of a gripper with the robot are included or are available from Zimmer Group GmbH as optional accessories.



5 Functional description

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

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

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

6 Accessories/scope of delivery

INFORMATION

If any accessories not sold or authorized by Zimmer Group GmbH are used, the function of the product cannot be guaranteed. Zimmer Group GmbH accessories are specifically tailored to the individual products.

▶ For optional accessories and those included in the scope of delivery, refer to our website.

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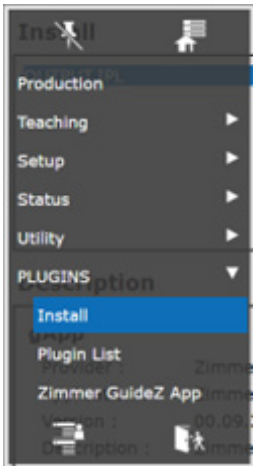
7 Installation

7.1 Installing the Comfort App

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

- ► Download the Comfort App from our website.
- ► Copy the installation file to a USB memory device.
  - ► Ensure that the installation file is located at the top level of the USB stick.
- ► Make sure that the robot control panel is already connected to the robot control system.
- ► Switch off the voltage supply on the robot tool I/O via the emergency stop button.
- ► Plug the USB memory stick with the installation file into the robot control panel.

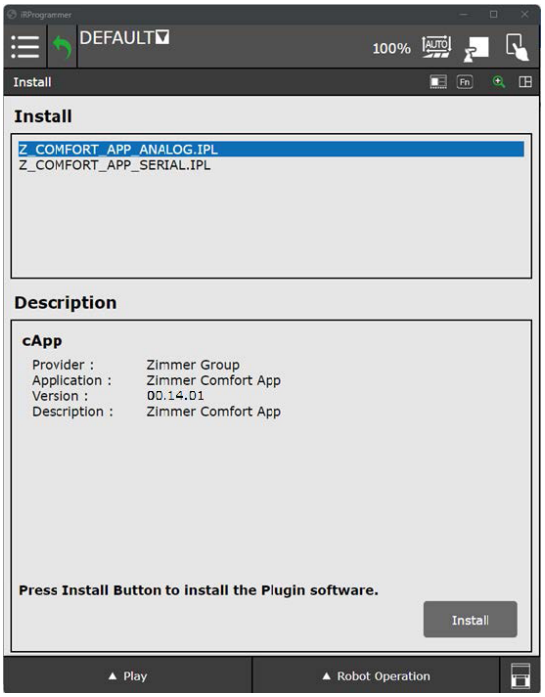
- ► Press the ☰ button.
- ► In the *PLUGINS* menu, press *Install*.



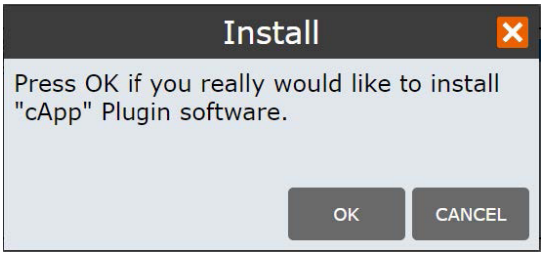
INFORMATION

You require the *Z_Comfort_App_Serial.ipl* installation file for grippers that are connected via a controller IO.

- ► Select the installation file.
- ► Press the *Install* button.
- ► If the installation fails, make sure that there is only one file on the USB stick and try again.



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

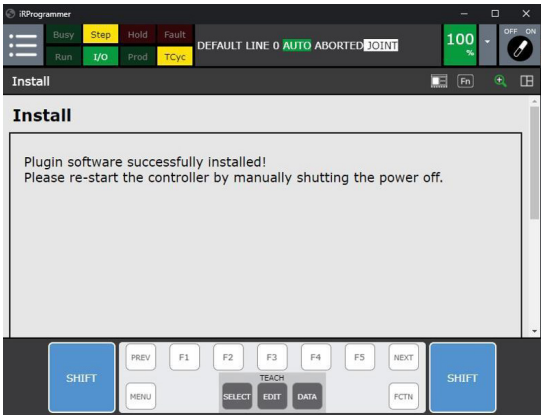


⇨ The installation is complete.

► Switch off the power supply of the robot control system and robot control panel.

► After a few seconds, switch on the power supply of the robot control system and robot control panel again.

► Switch on the robot control system and robot control panel.



8 Commissioning

CAUTION

Risk of injury, material damage and malfunctions in case of non-compliance

The Comfort App uses registers 138 to 200. If these registers are changed, this could lead to malfunctions, material damage and injuries.

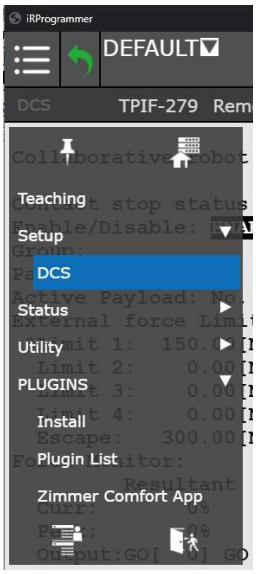
► Do not use registers 138 to 200 in your program.

NOTICE

► Switch on the robot so that you can use the Comfort App.

► Press the ☰ button.

► In the *PLUGINS* menu, press *MATCH Comfort App*.



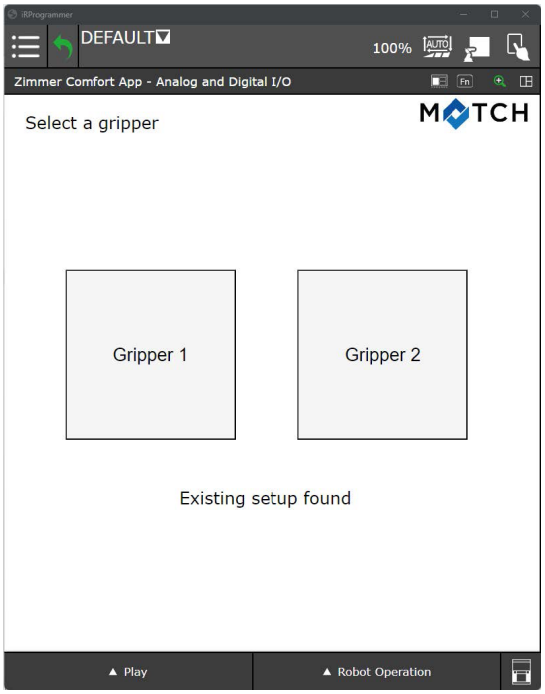
8.1 Deleting existing setups

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

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

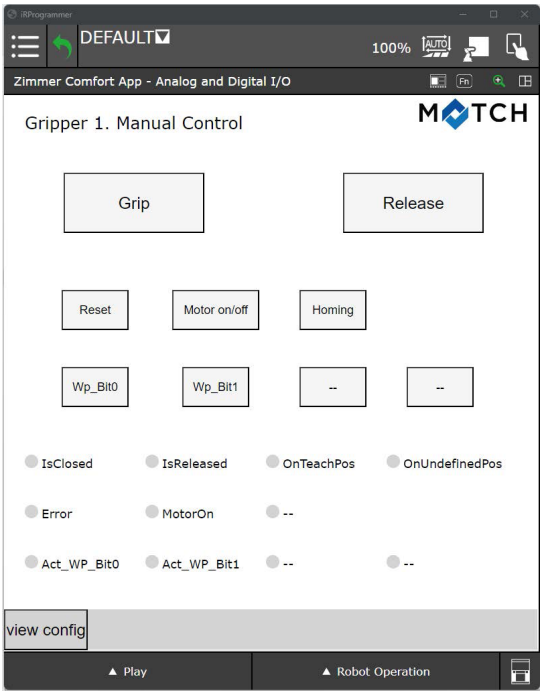
► Click the button of the desired gripper.

⇨ The *Manual control* screen for the manual control is displayed.



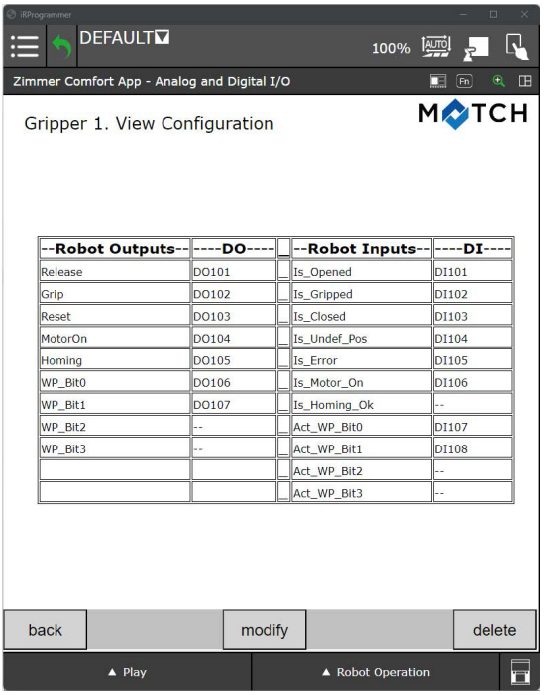
In the *Manual control* screen, you can operate the gripper manually and display the status.

► Click the *view config* button.



⇨ The *View Configuration* screen for editing the gripper configuration is displayed.

► Click the *delete* button.

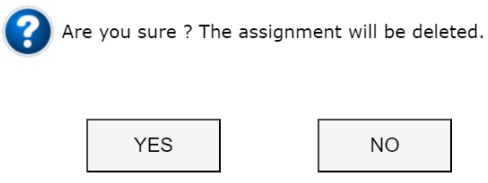


--Robot Outputs--	----DO----		--Robot Inputs--	----DI----
Release	DO101		Is_Opened	DI101
Grip	DO102		Is_Gripped	DI102
Reset	DO103		Is_Closed	DI103
MotorOn	DO104		Is_Undef_Pos	DI104
Homing	DO105		Is_Error	DI105
WP_Bit0	DO106		Is_Motor_On	DI106
WP_Bit1	DO107		Is_Homing_Ok	--
WP_Bit2	--		Act_WP_Bit0	DI107
WP_Bit3	--		Act_WP_Bit1	DI108
			Act_WP_Bit2	--
			Act_WP_Bit3	--

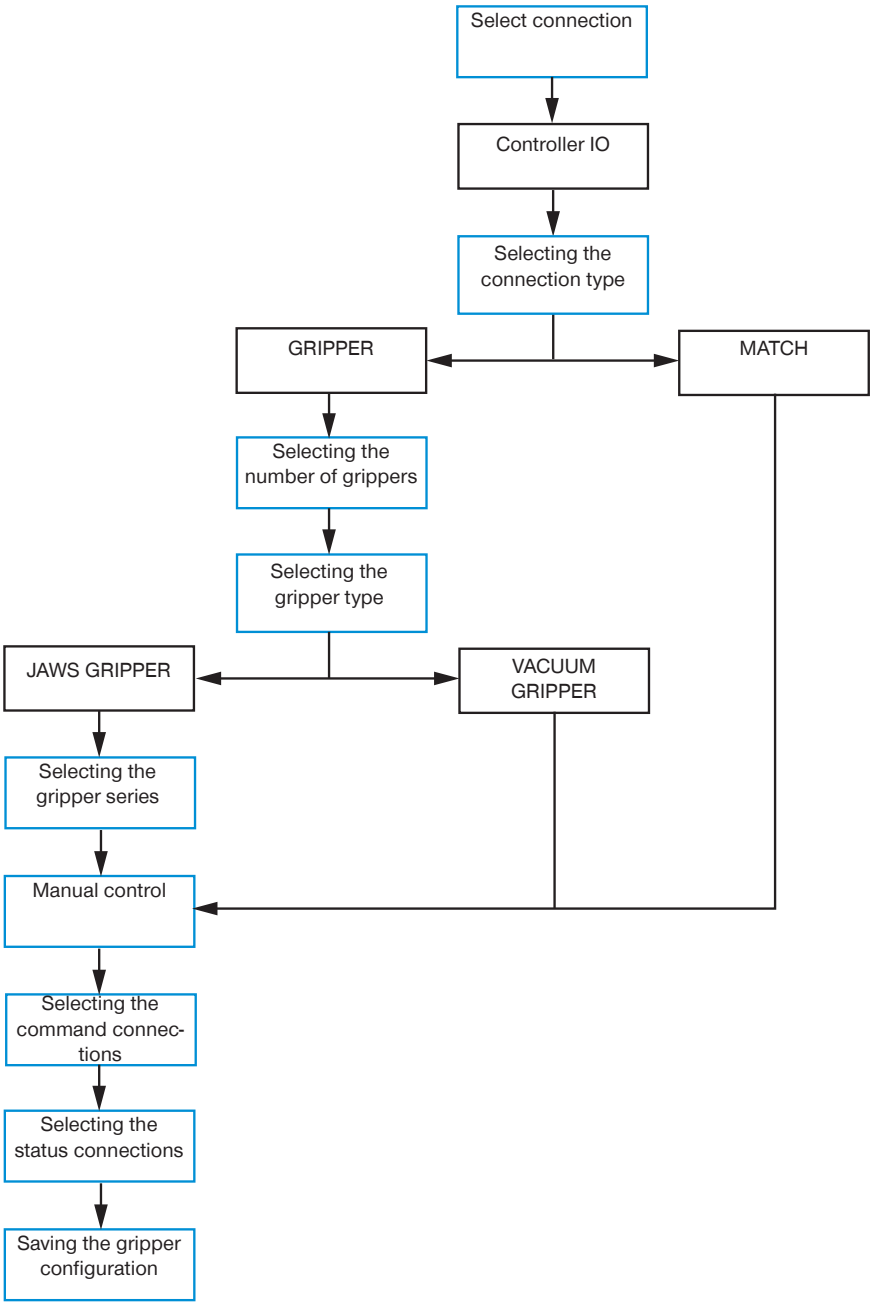
► In the prompt, click the *YES* button.

⇨ The existing setup is deleted.

⇨ The screen sequence for configuring new grippers is displayed.

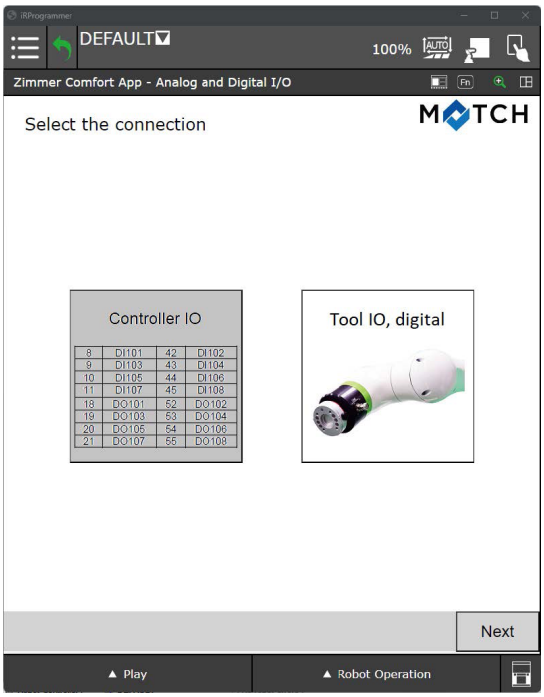


8.2 Creating a gripper configuration



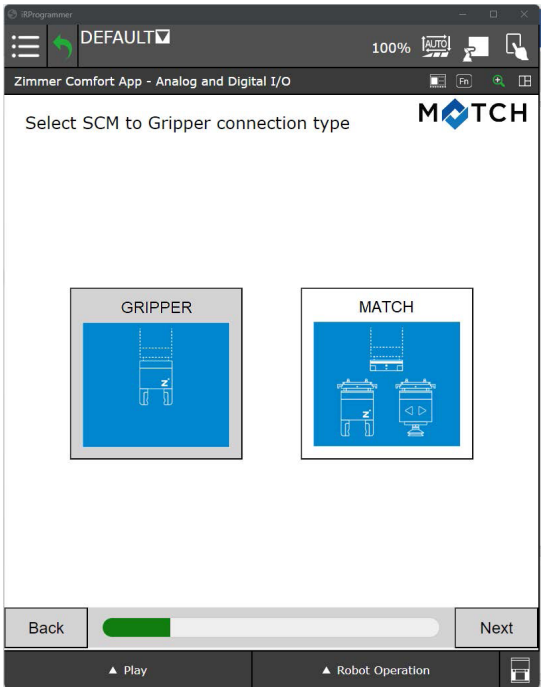
8.2.1 Selecting the connection

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



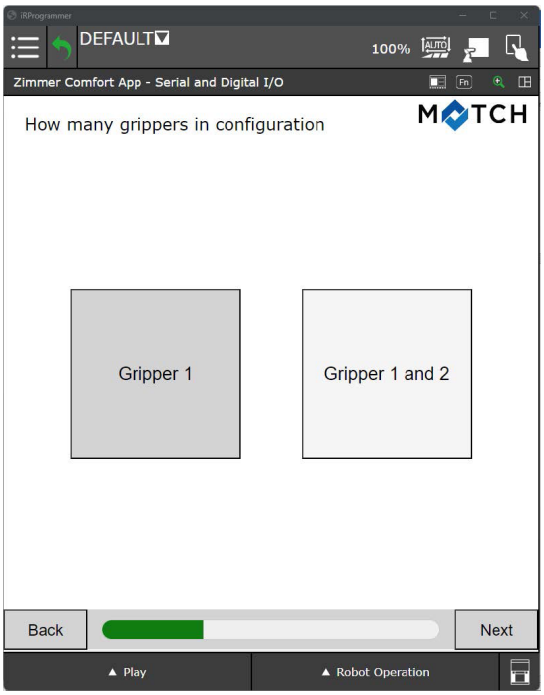
8.2.2 Selecting the connection type

- ► Click *GRIPPER* if you have connected a gripper.
- ► Click *MATCH* if you have connected a MATCH gripper.
- ► Click the *next* button.



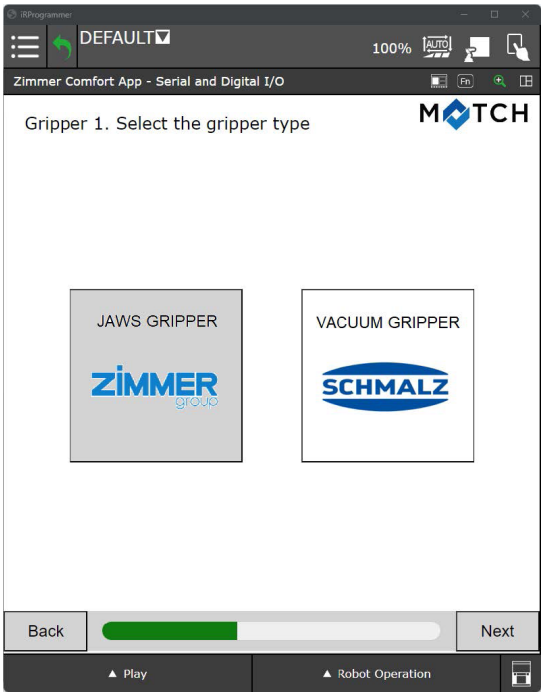
8.2.3 Selecting the number of grippers

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



8.2.4 Selecting the gripper type

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



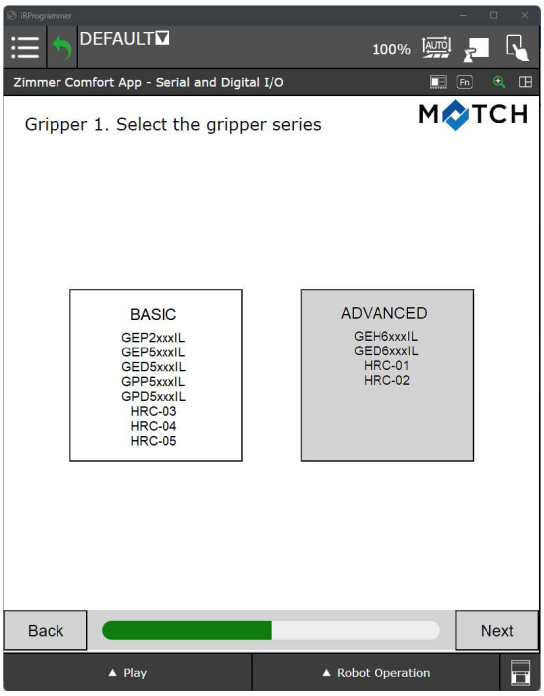
8.2.5 Selecting the gripper series

INFORMATION

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

► Click the class of your gripper.

► Click the *next* button.



8.2.6 Manual control

NOTICE

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

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

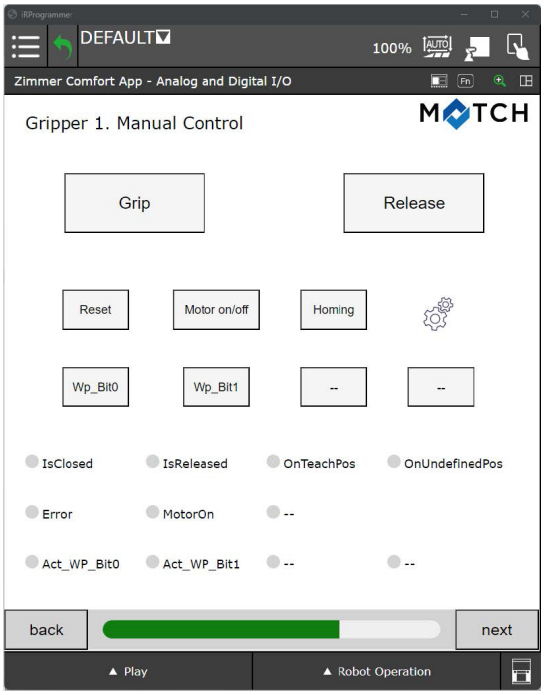
INFORMATION

The ⚙ button is only displayed for the connection via a controller IO.

Connection type: Gripper

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

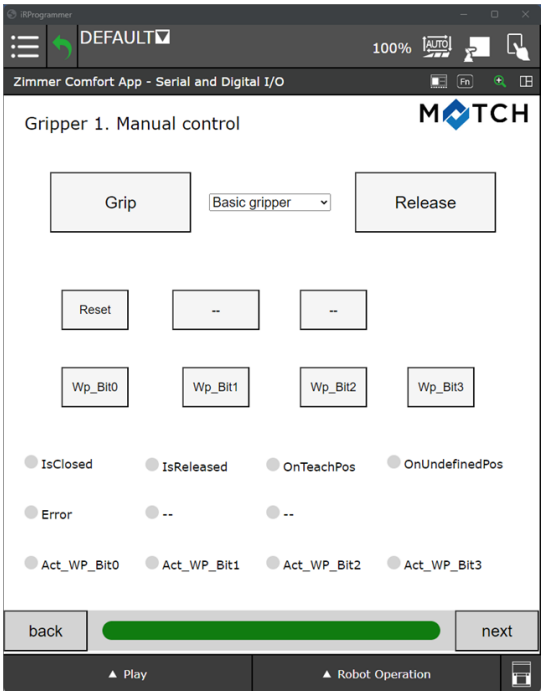
► Press the ⚙ button to select command connections and status connections.



Connection type: MATCH

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

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



► Click the *next* button.

8.2.7 Selecting the command connections

NOTICE

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

NOTICE

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

► Complete the wiring precisely as shown on this screen.

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

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

You can accept the default assignment or change it.

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

Editing the command connection

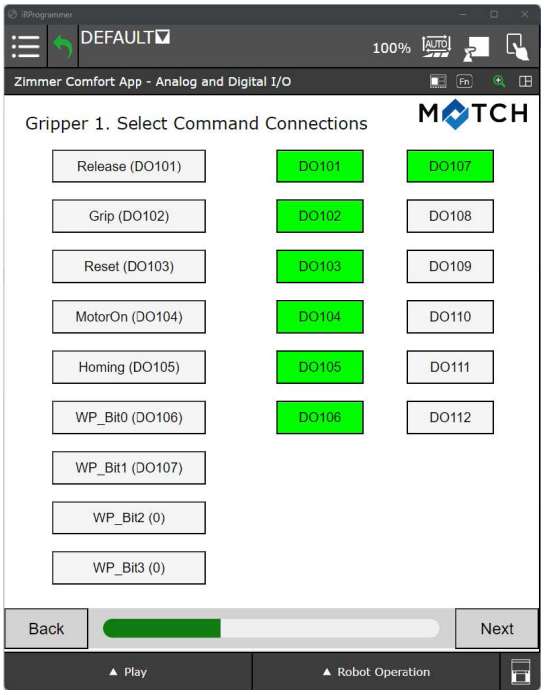
► Click the button of the desired signal.
- e.g. Release

► Click the desired output.
- e.g. DO7

⇨ The output has been assigned to the signal.

⇨ The button of the signal is expanded by adding the output.
- e.g. Release (DO7)

► Press the *Next* button.



8.2.8 Selecting the status connections

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

NOTICE

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

► Complete the wiring precisely as shown on this screen.

You can accept the default assignment or change it.

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

Editing the status connections

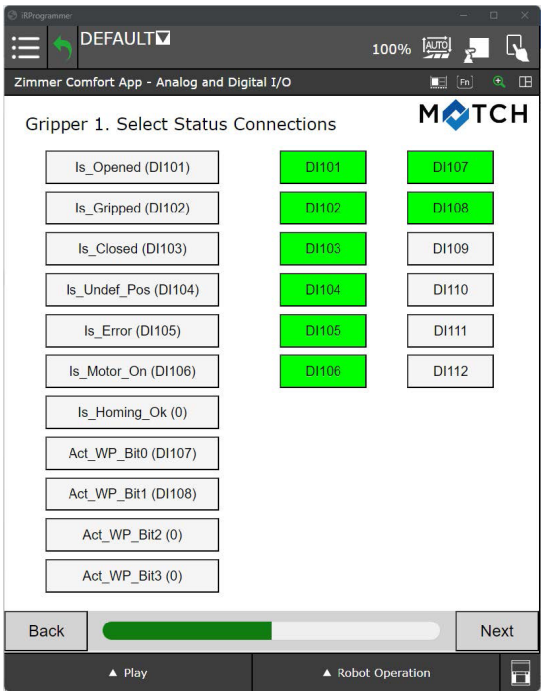
► Click the button of the desired signal.
- e.g. Is_Closed

► Click the desired input.
- e.g. DI107

⇨ The input has been assigned to the signal.

⇨ The button of the signal is expanded by adding the input.
- e.g. Is_Closed (DI107)

► Press the *Next* button.



8.2.9 Saving the gripper configuration

NOTICE

The settings are temporary.

► Save the settings to the installation file.

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

⇨ The gripper configuration has been stored.

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

⇨ The gripper configuration is complete.

⇨ The function blocks/subprograms have been created and are available for programming.

9 Operation

9.1 Control principle of the gripper

- ▶ Prepare *Advanced* grippers for the control system:
  - ▶ If necessary, do a reference run (IPL_ZIMMER_CAPP_HOMING).
  - ▶ Check if the reference run was done(IPL_ZIMMER_CAPP_ISHOMINGOK or IPL_ZIMMER_CAPP_ISHOMING-SUCCESS).
  - ▶ Switch on the motor (IPL_ZIMMER_CAPP_MOTORON).
  - ▶ Check whether the motor is switched on (IPL_ZIMMER_CAPP_ISMOTORON).
  - ⇨ The gripper is prepared for the control system if no error is present (IPL_ZIMMER_CAPP_ISERROR).
- ▶ Set a workpiece configured with the HMI software (IPL_ZIMMER_CAPP_CHANGEWP) if more than one workpiece is used.
- ▶ Check whether a workpiece has changed (IPL_ZIMMER_CAPP_ISWPCHANGED).
- ▶ Grip (IPL_ZIMMER_CAPP_GRIP) or release (IPL_ZIMMER_CAPP_RELEASE) the workpiece.
- ▶ Check the position of the gripper jaw (IPL_ZIMMER_CAPP_ISONTEACHPOS, IPL_ZIMMER_CAPP_ISOPENED, IPL_ZIMMER_CAPP_ISCLOSED or IPL_ZIMMER_CAPP_ISONUNDEFPOS).

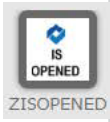
9.2 Overview of generated robot jobs

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

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

Generated robot job name		Parameter In	Parameter Out	Function
	IPL_ZIMMER_CAPP_GRIP(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.*	Gripping
			= *0*, if no error is present	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *X*, all other values are errors	
	IPL_ZIMMER_CAPP_RELEASE(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.*	Release
			= *0*, if no error is present	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *X*, all other values are errors	
	IPL_ZIMMER_CAPP_MOTORON(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.*	Switch on motor for *Advanced* grippers.
			= *0*, if no error is present	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *X*, all other values are errors	

Generated robot job name		Parameter In	Parameter Out	Function
	IPL_ZIMMER_CAPP_MOTOROFF(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.* = *0*, if no error is present = *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured = *104*, if command cannot be used with gripper configuration = *X*, all other values are errors	Switch off motor if gripper is present.
	IPL_ZIMMER_CAPP_HOMING(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.* = *0*, if no error is present = *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured = *104*, if command cannot be used with gripper configuration = *X*, all other values are errors	Perform reference run for *Advanced* grippers.
	IPL_ZIMMER_CAPP_RESET(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.* = *0*, if no error is present = *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured = *104*, if command cannot be used with gripper configuration = *X*, all other values are errors	Reset if gripper is present.
	IPL_ZIMMER_CAPP_CHANGEW-P(workpiece number, register number)	Workpiece number = 1 to 15	*Register No.* = *0*, if no error is present = *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured = *104*, if command cannot be used with gripper configuration = *X*, all other values are errors	Set workpiece number (n) for use with SCM.

Generated robot job name		Parameter In	Parameter Out	Function
	IPL_ZIMMER_CAPP_ ISWPCHANGED(workpiece number, register number)	Workpiece number = 1 to 15	*Register No.*	Checks whether the workpiece number(s) is/are activated.
			= *1*, TRUE Workpiece number(s) activated = *2*, FALSE Workpiece number(s) not activated	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *110*, timeout while waiting for feedback	
			= *X*, all other values are errors	
	IPL_ZIMMER_CAPP_ ISOPENED(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.*	Checks once whether the gripper is open.
			= *1*, TRUE Gripper open = *2*, FALSE Gripper closed	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *110*, timeout while waiting for feedback	
			= *X*, all other values are errors	
	IPL_ZIMMER_CAPP_ ISCLOSED(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.*	Checks once whether the gripper is closed.
			= *1*, TRUE Gripper closed = *2*, FALSE Gripper open	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *110*, timeout while waiting for feedback	
			= *X*, all other values are errors	

Generated robot job name		Parameter In	Parameter Out	Function
	IPL_ZIMMER_CAPP_ISONTEACH-POS(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.* = *1*, TRUE Gripper at TeachPosition = *2*, FALSE Gripper not at TeachPo-sition = *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured = *104*, if command cannot be used with gripper configuration = *110*, timeout while waiting for feedback = *X*, all other values are errors	Checks once whether the gripper is at the TeachPosition.
	IPL_ZIMMER_CAPP_ISONUNDEF-POS(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.* = *1*, TRUE Gripper at UndefinedPo-sition = *2*, FALSE Gripper not at Undefined-Position = *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured = *104*, if command cannot be used with gripper configuration = *110*, timeout while waiting for feedback = *X*, all other values are errors	Checks once whether the gripper is at the UndefinedPosition.
	IPL_ZIMMER_CAPP_ISERROR(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.* = *1*, TRUE Gripper in error state = *2*, FALSE Gripper not in error state = *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured = *104*, if command cannot be used with gripper configuration = *X*, all other values are errors	Checks whether the gripper is in error state.
	IPL_ZIMMER_CAPP_ISMOTORON(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.* = *1*, TRUE Motor switched on = *2*, FALSE Motor switched off = *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured = *104*, if command cannot be used with gripper configuration = *110*, timeout while waiting for feedback = *X*, all other values are errors	Check whether the motor is switched on.

Generated robot job name		Parameter In	Parameter Out	Function
	IPL_ZIMMER_CAPP_ISHOMIN-GOK(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.*	Checks whether the referencing of the gripper is OK.
			= *1*, TRUE Referencing of gripper OK = *2*, FALSE Referencing of gripper not OK	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *110*, timeout while waiting for feedback	
			= *X*, all other values are errors	
	IPL_ZIMMER_CAPP_ISHOMINGSUC-CESS(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.*	Checks whether the referencing of the gripper is successful.
			= *1*, TRUE Referencing of gripper successful = *2*, FALSE Referencing of gripper not successful	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *110*, timeout while waiting for feedback	
			= *X*, all other values are errors	
	IPL_ZIMMER_CAPP_ERRORWARNIN-GON(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.*	Enables Error/ Warning for robot if gripper is present.
			= *0*, if no error is present	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *X*, all other values are errors	
	IPL_ZIMMER_CAPP_ERRORWARNIN-GOFF(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.*	Disables Error/ Warning for robot if gripper present.
			= *0*, if no error is present	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *X*, all other values are errors	

Generated robot job name		Parameter In	Parameter Out	Function
	IPL_ZIMMER_CAPP_ISPARTDE-TACHED(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.*	Checks whether the part is detached.
			= *1*, TRUE Part detached from gripper = *2*, FALSE Part not detached from gripper	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *110*, timeout while waiting for feedback	
			= *X*, all other values are errors	
	IPL_ZIMMER_CAPP_ISPARTPRE-SENT(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.*	Checks whether the part is present.
			= *1*, TRUE Part present on gripper = *2*, FALSE Part not present on gripper	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *110*, timeout while waiting for feedback	
			= *X*, all other values are errors	
	IPL_ZIMMER_CAPP_ISREADY(gripper number, register number)	*1*: Address gripper 1 *2:* Address gripper 2	*Register No.*	Checks whether the gripper is ready.
			= *1*, TRUE Gripper ready = *2*, FALSE Gripper not ready	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *110*, timeout while waiting for feedback	
			= *X*, all other values are errors	
	IPL_ZIMMER_CAPP_MSTART-CHANGE(gripper number, register number)	-	*Register No.*	Is output before the gripper is changed for *MATCH* .
			= *0*, if no error is present	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *X*, all other values are errors	

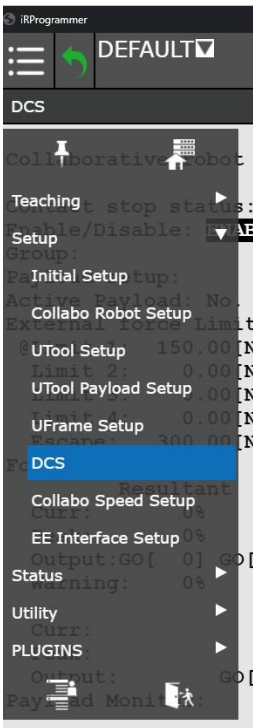
Generated robot job name		Parameter In	Parameter Out	Function
	IPL_ZIMMER_CAPP_ ISMCHG-DONE(gripper number, register number)	-	*Register No.*	Checks whether the gripper has been connected successfully.
			= *1*, TRUE Gripper connected successfully = *2*, FALSE Gripper not connected successfully	
			= *101*, if an error has occurred = 102, if incorrect settings have been made = *103*, if gripper has not be configured	
			= *104*, if command cannot be used with gripper configuration	
			= *110*, timeout while waiting for feedback	
			= *X*, all other values are errors	

9.3 Creating programs via drag & drop commands

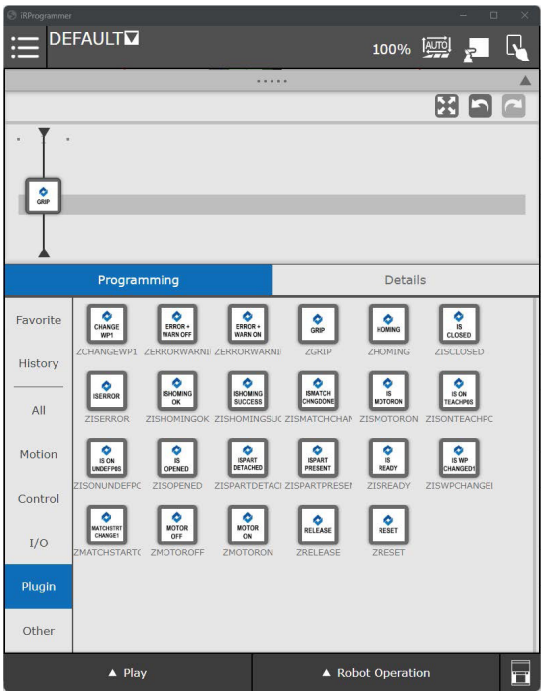
► Press the ☰ button.

► Press the ⌂☰ button.

⇨ A new program has been created.

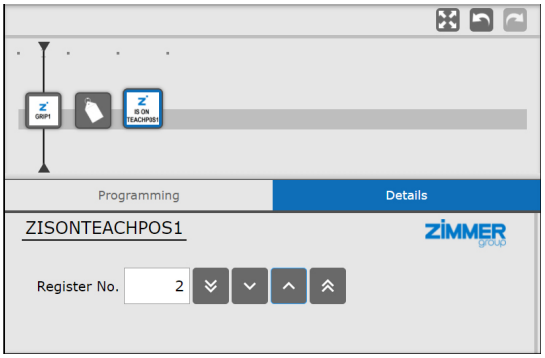


► Move the commands to the upper area via drag & drop.

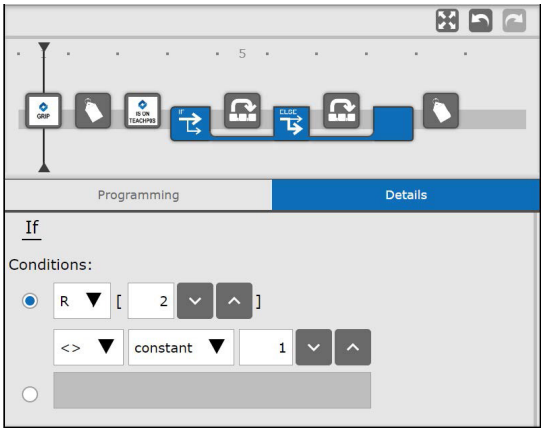


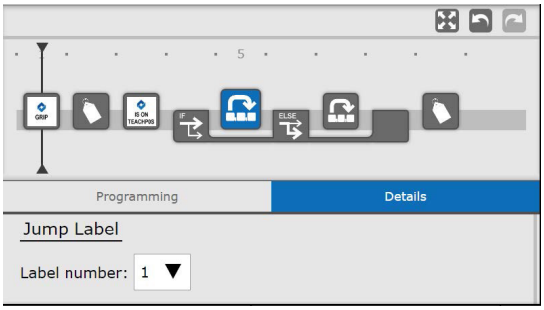
In this example, Register 2 receives the result of the command after executing the *ZISONTEACHPOS* command.

- A number 1 is displayed in the *Register No.* field: Gripper is in the TeachPosition.
- A number 2 is displayed in the *Register No.* field: Gripper is not in the TeachPosition.



The content of Register 2 can be checked via a constraint-based jump.





INFORMATION

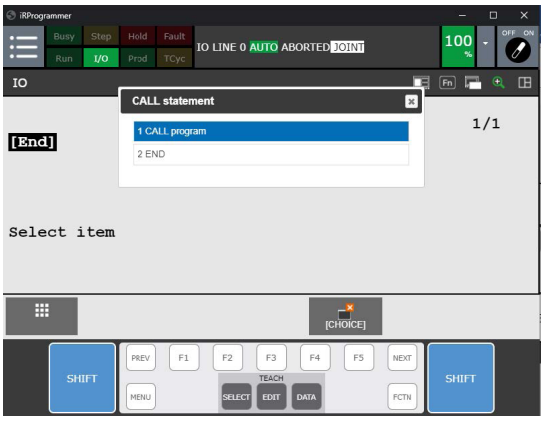
This initial situation is required for the following example:

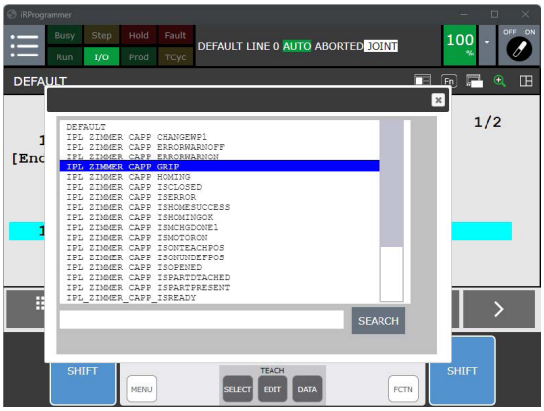
- Gripper is open and ready for gripping.
- Taught workpiece is located centered between the gripper fingers.

9.4 Creating programs via text input

The setting for the *IPL_ZIMMER_CAPP_GRIP* command is used as an example.

- Grip workpiece.
- Wait until the gripper detects that it is in the TeachPosition.





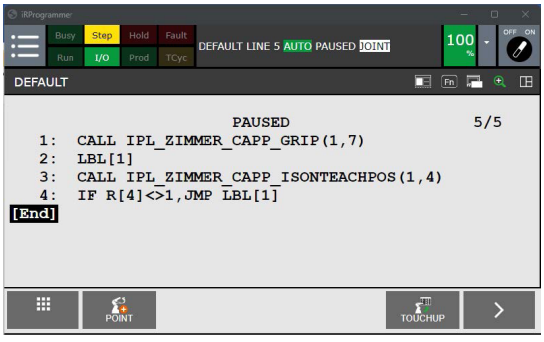
The *IPL_ZIMMER_CAPP_GRIP(1,7)* command queries the gripper 1 and register 7.

Line 1 and 3 address gripper 1 (gripper number).

Line 4 indicates the result of the command (register number).

If register 4 has the value 1 in line 3 after executing the command, gripper 1 is in the TeachPosition. The command was executed and the loop is complete.

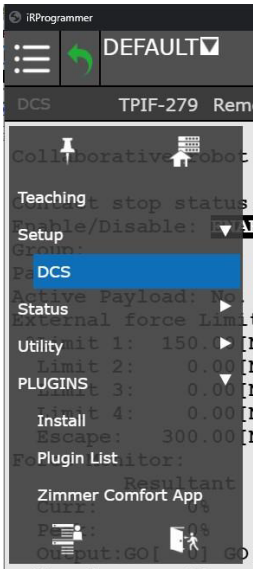
If register 4 has the value 2 in line 3 after executing the command, gripper 1 is not in the TeachPosition.



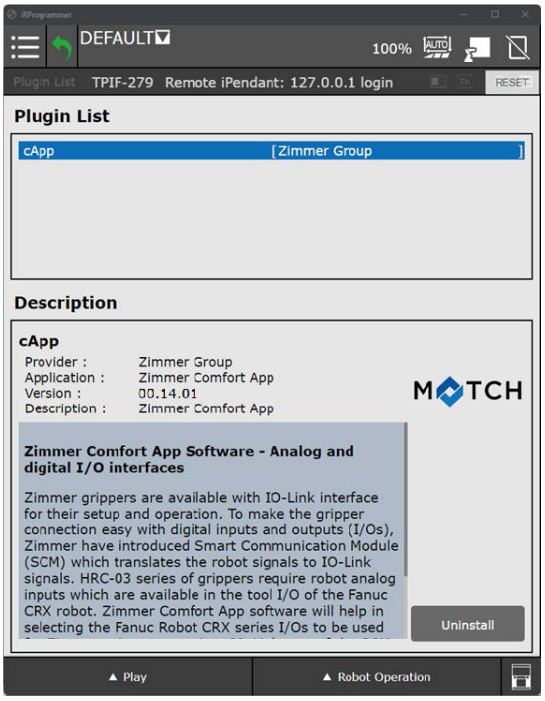
10 Uninstalling the Comfort App

► Press the ☰ button.

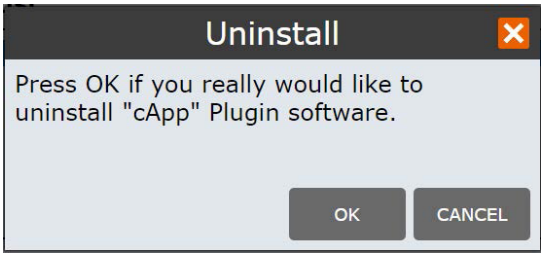
► In the *PLUGINS* menu, press *Plugin List*.



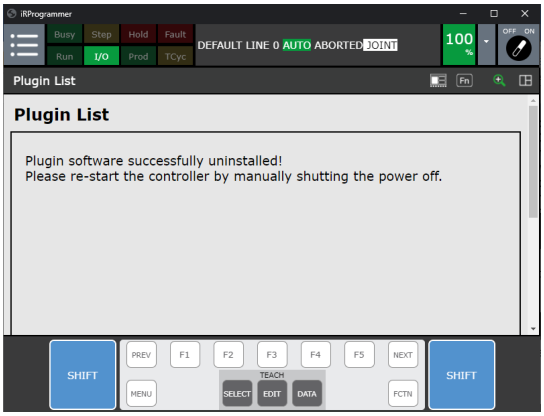
► Press the *Uninstall* button.



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



⇨ Uninstallation is complete.



11 Error diagnosis

INFORMATION

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