



## INSTALLATION AND OPERATING INSTRUCTIONS

MATCH robot module

LWR50F-01-03-A  
LWR50F-09-03-A

DDOC01360

THE KNOW-HOW FACTORY



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## 1 Supporting documents

### NOTICE



Read through the installation and operating instructions before installing or working with the product.

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



The documents listed below are available for download on our website [www.zimmer-group.com](http://www.zimmer-group.com).

- Installation and operating instructions
  - Catalogs, drawings, CAD data, performance data
  - Information on accessories
  - Technical data sheets
  - General Terms and Conditions, including warranty information.
- ⇒ Only those documents currently available on the website are valid.

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

### 1.1 Notices and graphics in the installation and operating instructions

#### DANGER



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

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

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

#### WARNING



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

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

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

#### CAUTION



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

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

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

### NOTICE



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

### INFORMATION



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

## 2 Safety notices

### CAUTION



#### **Risk of injury and material damage in case of non-compliance**

Installation, commissioning, maintenance and repairs may only be performed by qualified specialists in accordance with these installation and operating instructions.

The product is state-of-the-art.

It is fitted to industrial machines and is used to hold, transport and store workpieces.

The following are examples of situations in which the product may cause a hazard:

- The product is not properly installed, used or maintained.
- The product is not used for its designated purpose.
- The locally applicable regulations, laws, directives or guidelines are not observed.
- ▶ The product may only be used in accordance with these installation and operating instructions and the product's technical data. Any changes or additions to the intended use of the product, as well as modifications to the product, such as those in the following examples, require the written permission of the manufacturer:
  - Use of the product under extreme conditions, such as aggressive fluids or abrasive dusts
  - Additional drilled holes or threads
- ⇒ Zimmer GmbH shall accept no liability for any damage caused by improper use. The operator bears sole responsibility.
- ▶ Make sure that the power supply is disconnected before you mount, adjust, modify, maintain or repair the product.
- ▶ Whenever work is carried out on the product, make sure that the product cannot be actuated by mistake.
- ▶ Perform maintenance tasks, renovation work or attachment work outside of the machine's danger zone when possible.
- ▶ Do not reach into the operational range of the product.
- ▶ Observe the specified maintenance intervals and specifications regarding the quality of the operating material.
- ▶ When using the product under extreme conditions, adjust the maintenance interval according to the degree of contamination.

## CAUTION



### Notes and handling regulations for electrostatically sensitive components

Electrostatically sensitive components are individual components, integrated circuits or assemblies that can be damaged by electrostatic fields or electrostatic discharge.

- ▶ When handling electrostatic components, make sure that persons, the work area and packaging are all fully grounded.
- ▶ Touch electronic components only in appropriately identified areas with conductive flooring and only if:
  - You are grounded by means of special bracelets.
  - You wear shoes that are suitable and approved for the discharge of electrostatic charges.
- ▶ Do not bring electronic assemblies into contact with plastics and parts of clothing that have plastic content.
- ▶ Store electronic assemblies on conductive underlays only.
- ▶ Do not install electronic assemblies in the vicinity of data back-up devices or monitors (monitor distance > 100 mm).
- ▶ Perform measurements on electronic assemblies only if:
  - The measuring instrument is grounded (e.g. via a ground conductor).
  - The measuring head is momentarily discharged before measuring with a floating measuring instrument.

## 3 Proper use

### NOTICE



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

Any other or secondary use is deemed improper.

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

- The product is designed specifically for (cooperative/collaborative) use on robot systems and in combination with the MATCH quick-change system.
- The product is designed exclusively for electric operation using a 24 V DC power supply.
- The product must always be mounted on materials that dissipate heat.
- The product is intended for industrial use.
- The product is to be used as intended in enclosed rooms for handling and holding.
- Direct contact with perishable goods/food is not permitted.
- Observance of the technical data and of the installation and operating instructions are part of proper use.

## 4 Personnel qualification

### WARNING



#### Injuries and material damage due to inadequate qualification

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

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

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

#### 4.1 Electricians

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

#### 4.2 Specialists

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

#### 4.3 Instructed personnel

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

#### 4.4 Service personnel

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

#### 4.5 Additional qualifications

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

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



## 5 Product description

The MATCH End-of-Arm Ecosystem is equipped with an extensive range of functions and universal communication interfaces. MATCH is compatible with all common lightweight robots. The system can be mounted on the robot flange and set up with a few manual adjustments.

This product is a safe quick-change system (MATCH robot module) with an integrated Smart Communication Module (SCM).

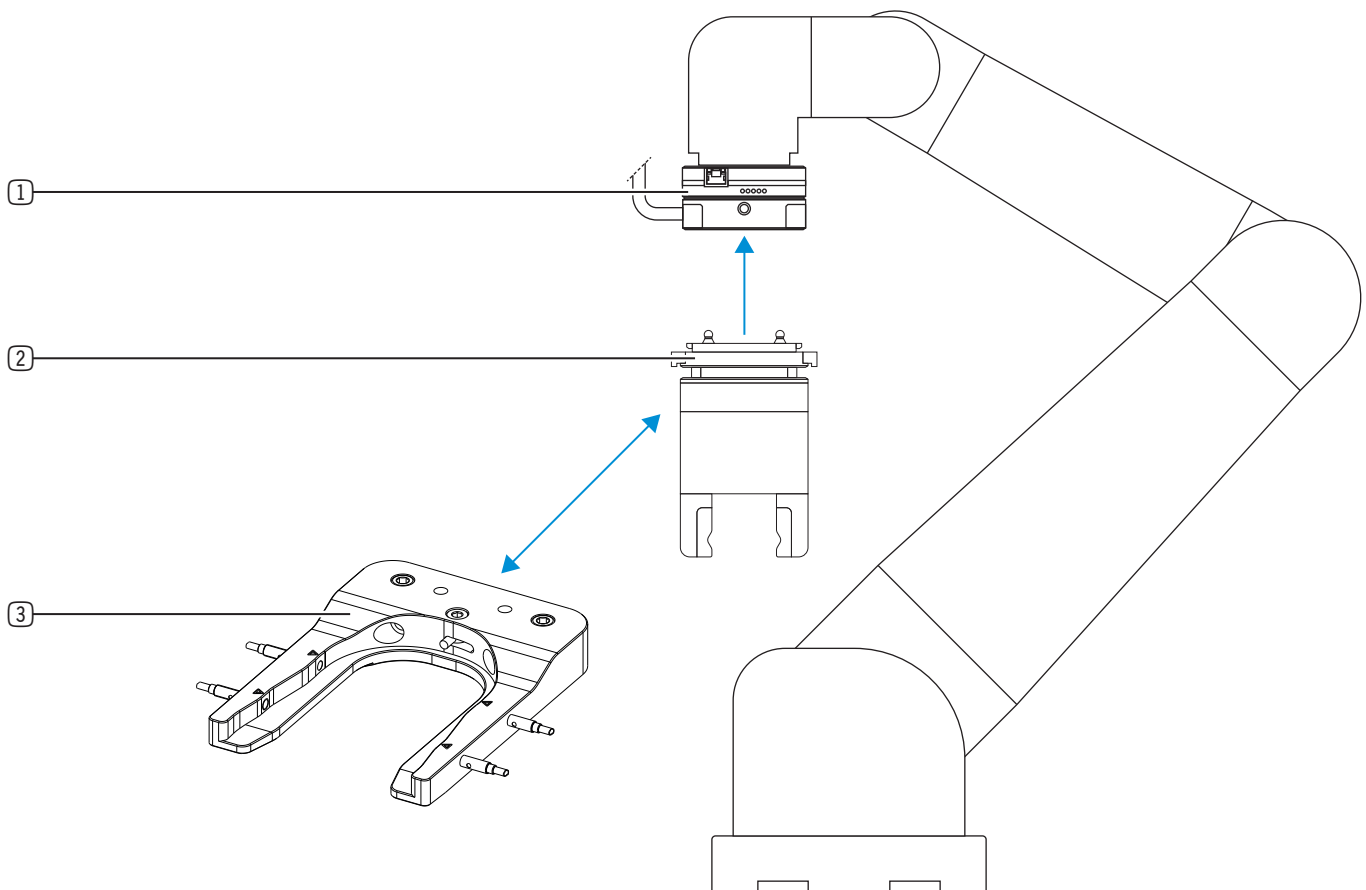
The Smart Communication Module (SCM) is a gateway between the grippers and the robot control system. The SCM can be configured via the HMI software or MATCH Comfort App. The grippers can be controlled using the MATCH Comfort App on the robot control panel.

The basic and proven safety principles from EN ISO 13849-1 can be complied with only if original parts from Zimmer GmbH are used.

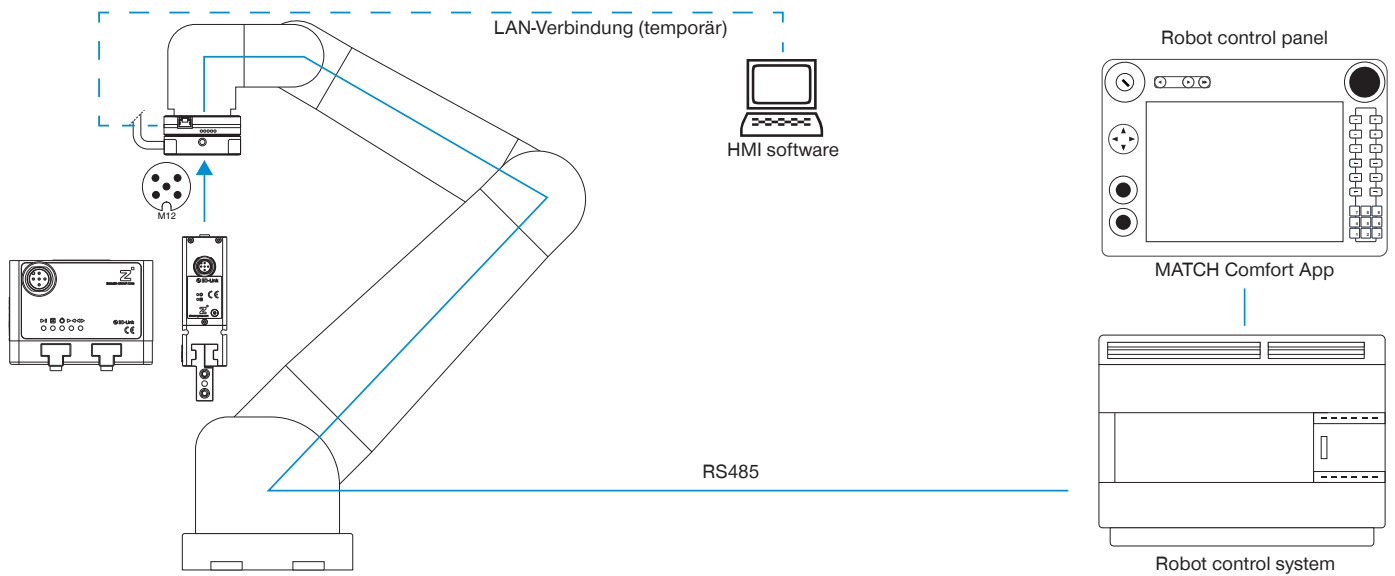
The original parts from Zimmer GmbH required for the safety principles are:

- ① MATCH robot module (LWR50F-xx)
- ② MATCH gripper (LWR50L-xx)
- ③ MATCH storage station (ALWR1-50-A) (sensors optional)

For the overall safety of the function, all three components (MATCH robot module, MATCH gripper, and MATCH storage station) must be taken into account (see "Functional Safety" section).



The image shows a simplified view of the schematic structure of the overall system in the MATCH version.



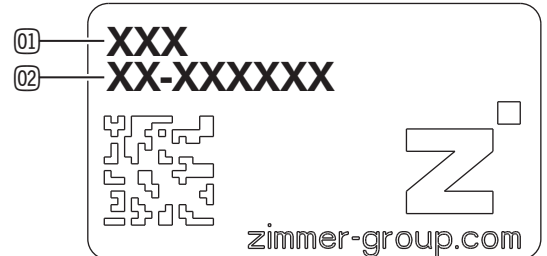
Installation steps:

- ▶ Install the hardware.
- ▶ Establish the electrical connections at the robot control system.
- ▶ Install the HMI software and teach in the workpieces.
- ▶ Install the MATCH Comfort App, see the operating instructions for the robot-specific MATCH Comfort App.

## 5.1 Type plate

A type plate is attached to the housing of the product.

The article number and confirmation number are shown on the type plate.



- 01 Article number
- 02 Confirmation number

## 6 Functional description

The product is installed on a robot system. It is used to mechanically hold a MATCH gripper as well as for intelligent control via the integrated SCM.

The MATCH gripper automatically locks with the product during automatic extending out of the MATCH storage station. As an alternative, the MATCH gripper can be manually installed on the product.

When the MATCH robot module and MATCH gripper are joined, the internal spring-pin contacts for signal transmission are contacted. Then, the Connect LED changes color from red to green and a Connect signal (depending on the variant) is passed to the higher-level control system.

The product can be operated with a wide variety of MATCH grippers. The prerequisite for this is a compatible MATCH gripper.

Due to the differently sized centering pins and marks on the MATCH grippers, they cannot be installed backwards on the MATCH robot module.

The product has the hot plug function, which enables changing a MATCH gripper while electrified.

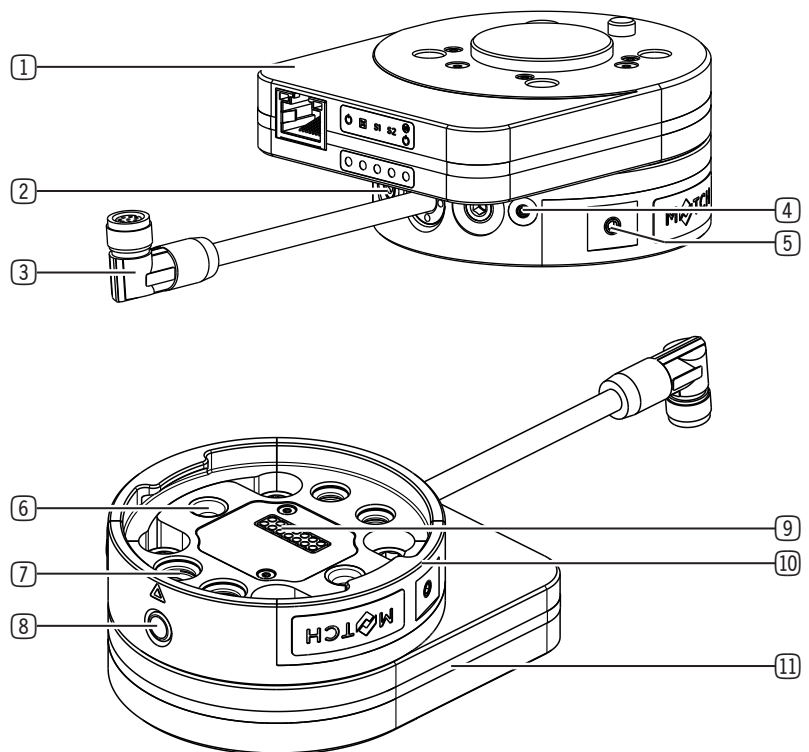
The MATCH gripper is designed in such a way that incorrect insertion into the MATCH storage station is impossible.

### INFORMATION



Freedrive is only available for installation size LWR50F-01-03-A.

- ① Smart Communication Module
- ② Pneumatic connection
- ③ Voltage supply, robot / MATCH robot module
- ④ Grounding
- ⑤ Strain relief
- ⑥ Positioning the MATCH gripper
- ⑦ Pneumatic feedthrough
- ⑧ Connect LED, Freedrive
- ⑨ Spring pin contacts
- ⑩ Locking
- ⑪ LED ring



### INFORMATION



► For information on the compatible MATCH grippers, refer to our website.

The SCM is the intelligent gateway between the grippers and the robot control system. It is used for the easy control of a gripper.

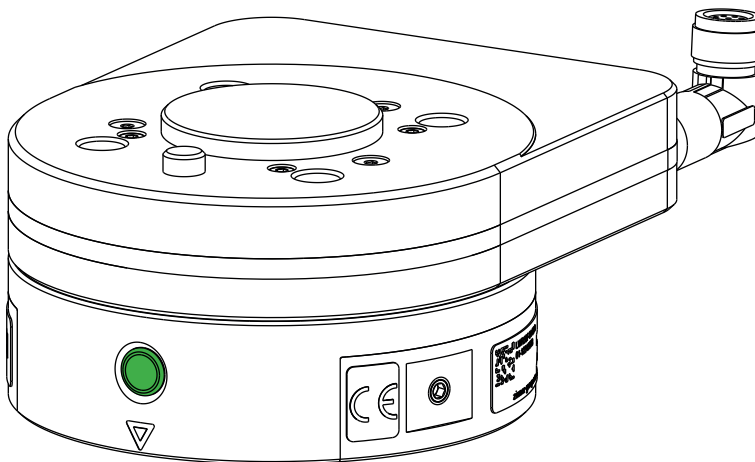
Up to 15 workpieces can be configured and saved via the workpiece number in SCM in the SCM setup for grippers. The workpiece numbers are available externally via bit coding in the form of digital SCM inputs and SCM outputs.

When using a gripper with SCM, the desired workpieces can be selected via a connection of the robot inputs and robot outputs in order to define the correct workpiece bit numbers. If there is no connection of robot inputs, workpiece 1 is set by default.

Work piece	Cmd_WP_			
	Bit0	Bit1	Bit2	Bit3
1	0	0	0	0
1	1	0	0	0
2	0	1	0	0
3	1	1	0	0
4	0	0	1	0
5	1	0	1	0
6	0	1	1	0
7	1	1	1	0
8	0	0	0	1
9	1	0	0	1
10	0	1	0	1
11	1	1	0	1
12	0	0	1	1
13	1	0	1	1
14	0	1	1	1
15	1	1	1	1

## 6.1 LED status display

### 6.1.1 Connect LED

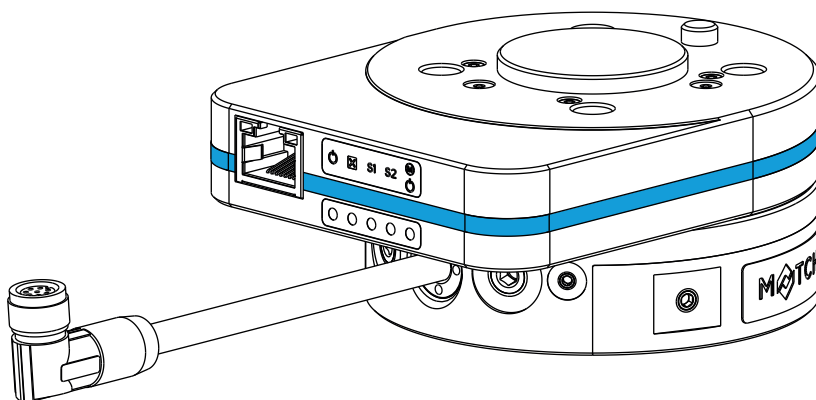


LED state	Function	Measure
off	No supply voltage	► Connect the supply voltage.
Continuous light	No MATCH robot module coupled.	► Couple the MATCH robot module.
Continuous light	One MATCH robot module coupled.	-

### 6.1.2 LED ring

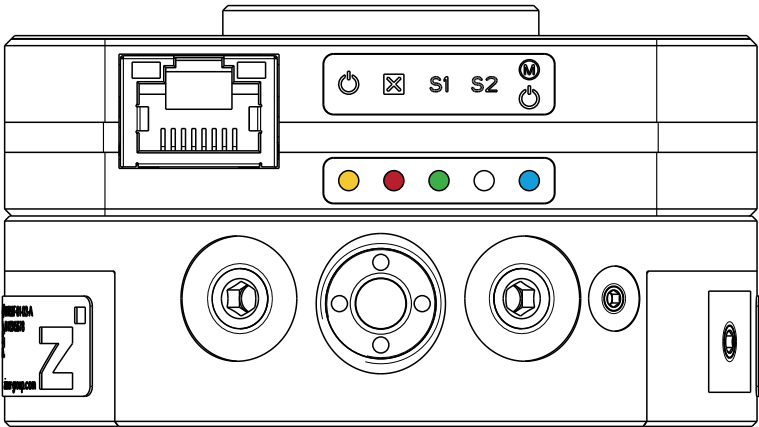
The product has an LED ring.

The colors of the LED ring reflect the status of the IO-Link device in the MATCH gripper. The LED ring enables a 360° status display.



LED state	Function of the Zimmer IO-Link products	Function of the Schmalz IO-Link	Measure for Zimmer	Measure for Schmalz
off	<ul style="list-style-type: none"> <li>No supply voltage</li> </ul>	<ul style="list-style-type: none"> <li>Connect the supply voltage.</li> </ul>	<ul style="list-style-type: none"> <li>No supply voltage</li> </ul>	<ul style="list-style-type: none"> <li>Connect the supply voltage.</li> </ul>
Flashing	<ul style="list-style-type: none"> <li>An error is present</li> </ul>	<ul style="list-style-type: none"> <li>Check the IO-Link device.</li> </ul>	<ul style="list-style-type: none"> <li>An error is present</li> </ul>	<ul style="list-style-type: none"> <li>Check the IO-Link device.</li> </ul>
Continuous light	<ul style="list-style-type: none"> <li>IO-Link device is disconnected.</li> </ul>	<ul style="list-style-type: none"> <li>Establish a connection to the IO-Link device.</li> </ul>	<ul style="list-style-type: none"> <li>IO-Link device is disconnected.</li> </ul>	<ul style="list-style-type: none"> <li>Establish a connection to the IO-Link device.</li> </ul>
2x flashing	<ul style="list-style-type: none"> <li>SCM starts with high SCM input.</li> <li>IO-Link device switches with high SCM input.</li> </ul>	<ul style="list-style-type: none"> <li>Set the SCM input = 0.</li> </ul>	<ul style="list-style-type: none"> <li>SCM starts with high SCM input.</li> <li>IO-Link device switches with high SCM input.</li> </ul>	<ul style="list-style-type: none"> <li>Set the SCM input = 0.</li> </ul>
3x flashing	<ul style="list-style-type: none"> <li>Workpiece invalid for connected IO-Link device.</li> <li>No workpiece defined.</li> </ul>	<ul style="list-style-type: none"> <li>Select a valid workpiece.</li> <li>Teach the workpiece.</li> </ul>	<ul style="list-style-type: none"> <li>Workpiece invalid for connected IO-Link device.</li> <li>No workpiece defined.</li> </ul>	<ul style="list-style-type: none"> <li>Select a valid workpiece.</li> <li>Teach the workpiece.</li> </ul>
4x flashing	<ul style="list-style-type: none"> <li>IO-Link device not recognized.</li> </ul>	<ul style="list-style-type: none"> <li>Use a compatible IO-Link device.</li> </ul>	<ul style="list-style-type: none"> <li>IO-Link device not recognized.</li> </ul>	<ul style="list-style-type: none"> <li>Use a compatible IO-Link device.</li> </ul>
5x flashing	<ul style="list-style-type: none"> <li>Communication error</li> </ul>	<ul style="list-style-type: none"> <li>Restart the SCM.</li> <li>Please contact Customer Service.</li> </ul>	<ul style="list-style-type: none"> <li>Communication error</li> </ul>	<ul style="list-style-type: none"> <li>Restart the SCM.</li> <li>Please contact Customer Service.</li> </ul>
6x flashing	<ul style="list-style-type: none"> <li>Communication error</li> </ul>	<ul style="list-style-type: none"> <li>Restart the SCM.</li> <li>Please contact Customer Service.</li> </ul>	<ul style="list-style-type: none"> <li>Communication error</li> </ul>	<ul style="list-style-type: none"> <li>Restart the SCM.</li> <li>Please contact Customer Service.</li> </ul>
Flashing	<ul style="list-style-type: none"> <li>Unknown IO-Link device</li> </ul>	-	<ul style="list-style-type: none"> <li>Unknown IO-Link device</li> </ul>	-
Continuous light	<ul style="list-style-type: none"> <li>IO-Link device at UndefinedPosition</li> </ul>	-	-	-
Continuous light	<ul style="list-style-type: none"> <li>Taught-in workpiece gripped</li> </ul>	-	<ul style="list-style-type: none"> <li>Warning is present.</li> </ul>	<ul style="list-style-type: none"> <li>Check the IO-Link device.</li> </ul>
Continuous light	<ul style="list-style-type: none"> <li>IO-Link device at end position</li> <li>No taught-in workpiece gripped.</li> </ul>	-	<ul style="list-style-type: none"> <li>Workpiece vacuummed (vacuum &gt; H2)</li> </ul>	-
Continuous light	<ul style="list-style-type: none"> <li>IO-Link device moving</li> </ul>	-	<ul style="list-style-type: none"> <li>Neutral state (vacuum &gt; H2)</li> </ul>	-

6.1.3 Basic module LED display



Name	LED state	Status	Measure
⏻	Continuous light	• Supply voltage OK	-
	Flashing	• HMI is connected, the SCM is teaching the IO-Link device.	-
	Flashing	• HMI assumes control, the IO module LEDs are off.	-
	off	• Supply voltage not OK	► Actuator voltage not OK
⊗	Continuous light	• An error is present	► Connect the supply voltage.

Name	LED state	Status	Measure
Status 1/2 (IO-Link device)	off	<ul style="list-style-type: none"> <li>No supply voltage</li> </ul>	<ul style="list-style-type: none"> <li>▶ Restart the SCM.</li> <li>▶ Please contact Customer Service.</li> </ul>
	Continuous light	<ul style="list-style-type: none"> <li>An error is present</li> </ul>	<ul style="list-style-type: none"> <li>▶ Connect the supply voltage.</li> </ul>
	Flashing	<ul style="list-style-type: none"> <li>IO-Link device is disconnected.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Check the IO-Link device.</li> </ul>
	2x flashing	<ul style="list-style-type: none"> <li>SCM starts with high SCM input.</li> <li>IO-Link device switches with high SCM input.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Establish a connection to the IO-Link device.</li> </ul>
	3x flashing	<ul style="list-style-type: none"> <li>Workpiece invalid for connected IO-Link device.</li> <li>No workpiece defined.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Set the SCM input = 0.</li> </ul>
	4x flashing	<ul style="list-style-type: none"> <li>IO-Link device not recognized.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Select a valid workpiece.</li> <li>▶ Teach the workpiece.</li> </ul>
	5x flashing	<ul style="list-style-type: none"> <li>Communication error</li> </ul>	<ul style="list-style-type: none"> <li>▶ Restart the SCM.</li> <li>▶ Please contact Customer Service.</li> </ul>
	6x flashing	<ul style="list-style-type: none"> <li>Communication error</li> </ul>	<ul style="list-style-type: none"> <li>▶ Restart the SCM.</li> <li>▶ Please contact Customer Service.</li> </ul>
	Flashing	<ul style="list-style-type: none"> <li>Unknown IO-Link device</li> </ul>	-
	Continuous light	<ul style="list-style-type: none"> <li>Gripper in end position or no taught-in part gripped.</li> </ul>	-
	Continuous light	<ul style="list-style-type: none"> <li>Taught-in workpiece gripped</li> </ul>	-
	Continuous light	<ul style="list-style-type: none"> <li>IO-Link device moving</li> </ul>	-
	Continuous light	<ul style="list-style-type: none"> <li>IO-Link device at UndefinedPosition</li> </ul>	-
(P 24 V)	Continuous light	<ul style="list-style-type: none"> <li>Actuator voltage OK</li> </ul>	-
	off	<ul style="list-style-type: none"> <li>Actuator voltage not OK</li> </ul>	<ul style="list-style-type: none"> <li>▶ Use a compatible IO-Link device.</li> </ul>



## 6.2 Functional safety

For the overall safety of the function, all three components (MATCH robot module, MATCH gripper and MATCH storage station) must be taken into account.

The safety function that ensures secure locking between the MATCH robot module and MATCH gripper of the product is implemented via two redundant action channels that consist of a mechanical locking and springs.

Technical supplementary safety measures (sensors) provide a high degree of diagnostic coverage. The product can thus be classified into control category 3 in accordance with Chapter 6.2.6 of DIN EN ISO 13849-1. According to Figure 5, Chapter 4.5.4 of the specified standard, the PL d can be achieved with this product.

Fault elimination in accordance with DIN EN ISO 13849-2, Annex A, Table A2 and A3 for the helical compression springs used can be given.

## 7 Technical data

### INFORMATION



- ▶ You can find the information in the technical data sheet on our website.
- This data varies within the series, depending on the specific design.
- ▶ Please contact Customer Service if you have any questions.

## 8 Accessories/scope of delivery

### INFORMATION



- If any accessories not sold or authorized by Zimmer GmbH are used, the function of the product cannot be guaranteed. Zimmer GmbH accessories are specifically tailored to the individual products.
- ▶ For optional accessories and those included in the scope of delivery, refer to our website.

## 9 Transportation/storage/preservation

- ▶ Store the product in its original packaging.
- ▶ If the product has already been installed on the superordinate machine unit, care must be taken during transport to ensure that no unexpected movements can occur.
  - ▶ Before commissioning the product and after transport, check all power and communication connections as well as all mechanical connections.
- ▶ If the product is stored for an extended period, the following points are to be observed:
  - ▶ Keep the storage location as dust-free and dry as possible.
  - ▶ Avoid temperature fluctuations.
  - ▶ Avoid wind/drafts/water condensation formation.
  - ▶ Pack the product and do not expose it to direct sunlight during storage.
- ▶ Clean all components. There must be no soiling left on the components.
- ▶ Visually inspect all components.
- ▶ Remove all foreign substances.
- ▶ Close electrical connections using suitable covers.

## 10 Installation

### WARNING



#### Risk of injury due to uncontrolled movements

Risk of injury in case of unexpected movement of the machine or system into which the product is to be installed.

- ▶ Switch off the energy supply of the machine before any work.
- ▶ Secure the power supply against being switched on unintentionally.
- ▶ Check the machine for any residual energy that may be present.

### CAUTION



#### Risk of injury due to uncontrolled movements

Risk of injury in the event of uncontrolled movement of the product when the power supply is connected.

- ▶ Switch off the power supply to the machine before carrying out any work.
- ▶ Secure the power supply against being switched on unintentionally.
- ▶ Check the machine for any residual energy that may be present.

### NOTICE



Installation may only be carried out by qualified personnel in accordance with these installation and operating instructions.

- ▶ Switch off the power supply before any assembly, installation or maintenance work.

#### Assembly requirements

Permissible unevenness [mm]	0,03
Strength class (DIN EN ISO 4762)	8.8

### INFORMATION



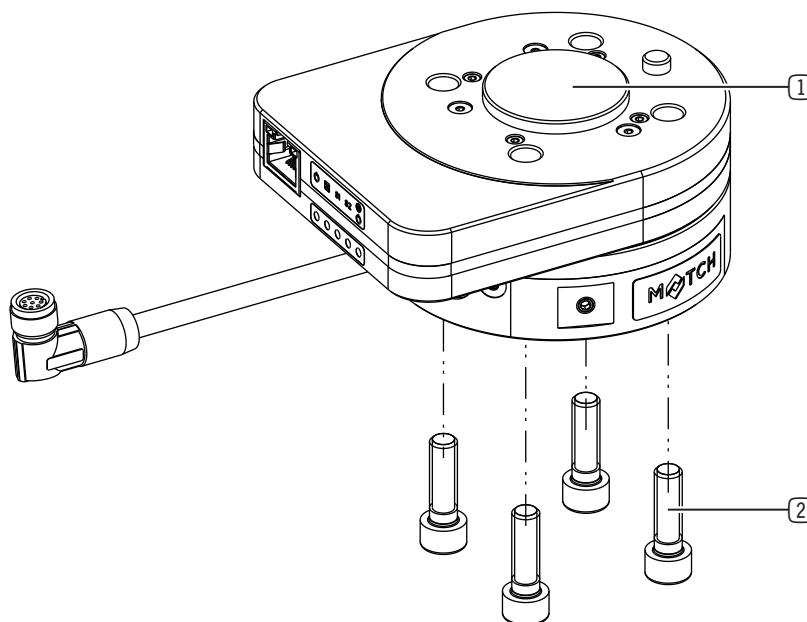
Further installation information:

- The mounting screws are not included in the scope of delivery.

- ▶ Install the product on an appropriate mounting surface in accordance with the flatness specifications.
- ▶ Observe the tightening torque of the mounting screws.
- ▶ Verify the permitted load capacity of the required screw connections in accordance with VDI 2230.

## 10.1 Installing the product

- ▶ Insert the product into the robot arm by the connection.
- ▶ Loosely attach the mounting screws.
- ▶ Tighten the mounting screws crosswise.

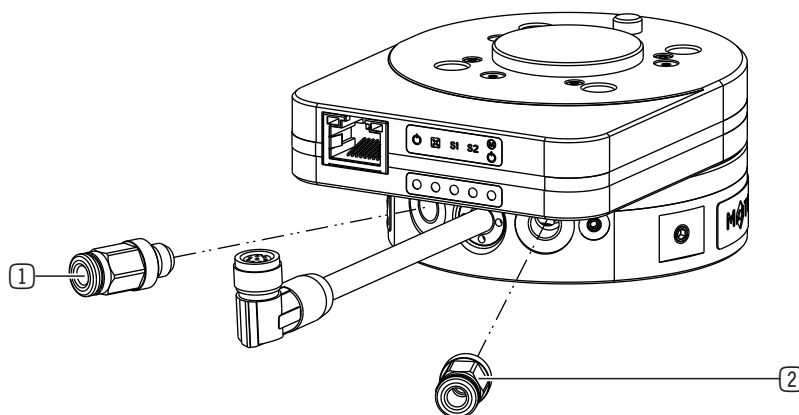


- ① Connection
- ② Mounting screw

## 10.2 Installing the energy supply

### 10.2.1 Installing the pneumatic system

- ▶ Unscrew the grub screws.
- ▶ Mount the screw fittings in the provided connections.



- ① Close gripper
- ② Open gripper

## 10.2.2 Installing the wiring

### CAUTION



#### Risk of injury from getting caught in the connecting cable

While the robot is moving, hair or limbs can be caught in the connecting cable.

- ▶ Route the connecting cable as close as possible to the robot arm.
- ▶ Avoid the danger zone.

### NOTICE



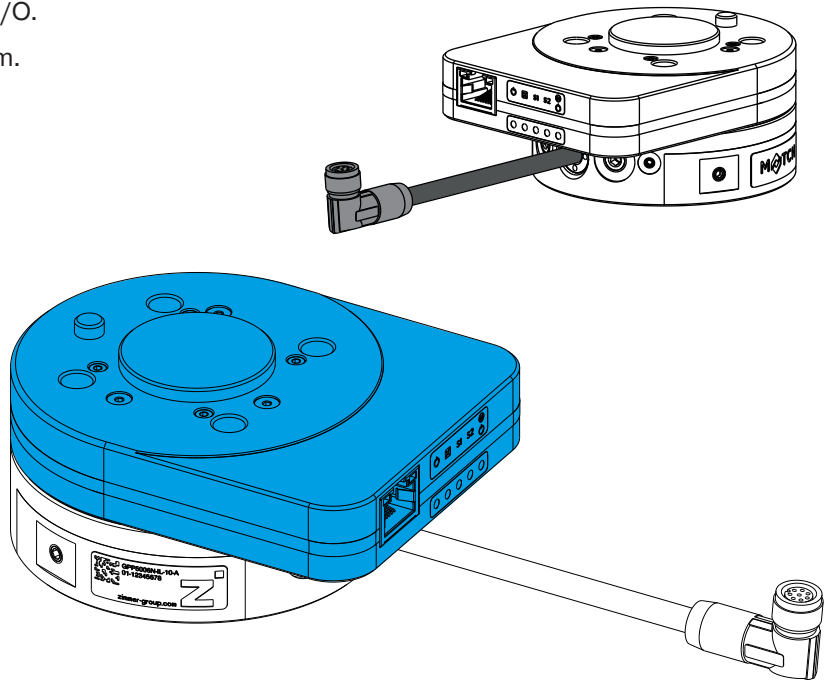
#### Non-compliance may result in material damage.

The cable mounted on the product can be subjected to a torsional angle of +50°.

- ▶ Do not route the cable so that it is strained.
  - ▶ You must meet the minimum bending radius of 10x the outer diameter.
  - ▶ Secure free-hanging cables to prevent excessive motion loads or pinching.
  - ▶ The contacts of the energy supply must be dry, clean and undamaged at all times.
- ⇒ Damage to the contacts can result in malfunction of the product.

- ▶ Switch off the voltage supply on the robot tool I/O.
- ▶ Connect the product to the robot control system.

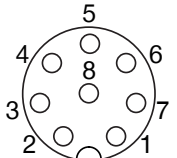
The selected MATCH robot module is equipped with an integrated Smart Communication Module (SCM) with RS485 interface.



## INFORMATION



Freedrive is only available for installation size LWR50F-01-03-A.

pin	Color	Function	Explanation	 <p>M8, 8-pin Socket/bracket</p>
1	White	signal	RS485+	
2	Brown	signal	RS485-	
3	Green	Output 2	Connect signal: 24 V DC if MATCH gripper is coupled.	
4	Yellow	Output 1	Freedrive signal: 24 V DC if Freedrive button is pressed.	
5	Gray	PWR	24 V DC supply voltage	
6	Pink	Input 1	Inward move command: Jaws move inward	
7	Blue	Input 2	Outward move command: Jaws move outward	
8	Red	GND	0 V DC supply voltage	

### 10.3 Static charge

#### CAUTION



**Non-compliance may result in material damage.**

Grounding the product is recommended if ESD sensitive parts come into contact with the product.  
Grounding is also recommended in applications that require high EMC shielding.

### 10.4 Heat dissipation

In the event of high ambient temperatures, the product must be installed on heat-dissipating materials.

If the product is operated under very high ambient temperatures and with fast clock cycles on an ongoing basis, this might reduce its service life.

### 10.5 Installing accessories

#### NOTICE



- Before installing an accessory, make sure it is suitable for use with the selected variant.
- You can find information on our website.
- Please contact Customer Service if you have any questions.

## 11 Installation

### 11.1 Setting up the Ethernet connection

The Ethernet port is connected to a Windows PC to configure the product.

#### INFORMATION



Factory setting:

- IP: 10.0.0.5
- Network mask: 255.0.0.0

- ▶ Adapt your network card.
- ▶ Check whether your firewall supports communication with the product.

#### INFORMATION



The communication protocol used is UDP. Therefore, integration into a network is possible only with limitations.

- ▶ For more information on changing the IP address, refer to the section "SCM network settings".
- ▶ For information on resetting the IP address, see the operating instructions for the robot-specific MATCH Comfort App.
- ▶ Please contact Customer Service if you have any questions.

### 11.2 Downloading software

Every SCM device is delivered with a digitalZ document including a download code.

- ▶ Download the HMI software *ZG\_IO\_LINK\_HMI* using the reference link specified in the digitalZ document or the QR code.
- ▶ Install the HMI software *ZG\_IO\_LINK\_HMI* on a Windows PC.

#### INFORMATION



- ▶ For more information, see the operating instructions for the robot-specific MATCH Comfort App.

## 12 Commissioning

This section describes how to configure the gripper using the product.

### NOTICE



- ▶ All workpiece recipes must be taught in the *guideZ* control level.
- ▶ At least the first workpiece recipe must be assigned with a taught-in workpiece in the product.

The product boots if it is wired correctly, the desired grippers are connected and the power supply is switched on.

Depending on the most recently stored configuration on the product, the power LEDs light up in green. Then Status 1 and Status 2 flash on the basic module as long as the grippers are being searched for.

### NOTICE



- ▶ When cold booting the SCM, ensure that all digital SCM inputs are not connected so that the initialization sequence can finish successfully.
- ▶ Disconnect the SCM from the power supply only if both grippers are no longer moving.

### INFORMATION



- ▶ This information applies only to installation size LWR50F-01-03-A.
- ▶ If you test the product via the MATCH Comfort App using the *GuideZ For-Robot* function, the settings in the following sections are not necessary.
- ▶ For more information, see the operating instructions for the robot-specific MATCH Comfort App.

## 12.1 Establishing the connection

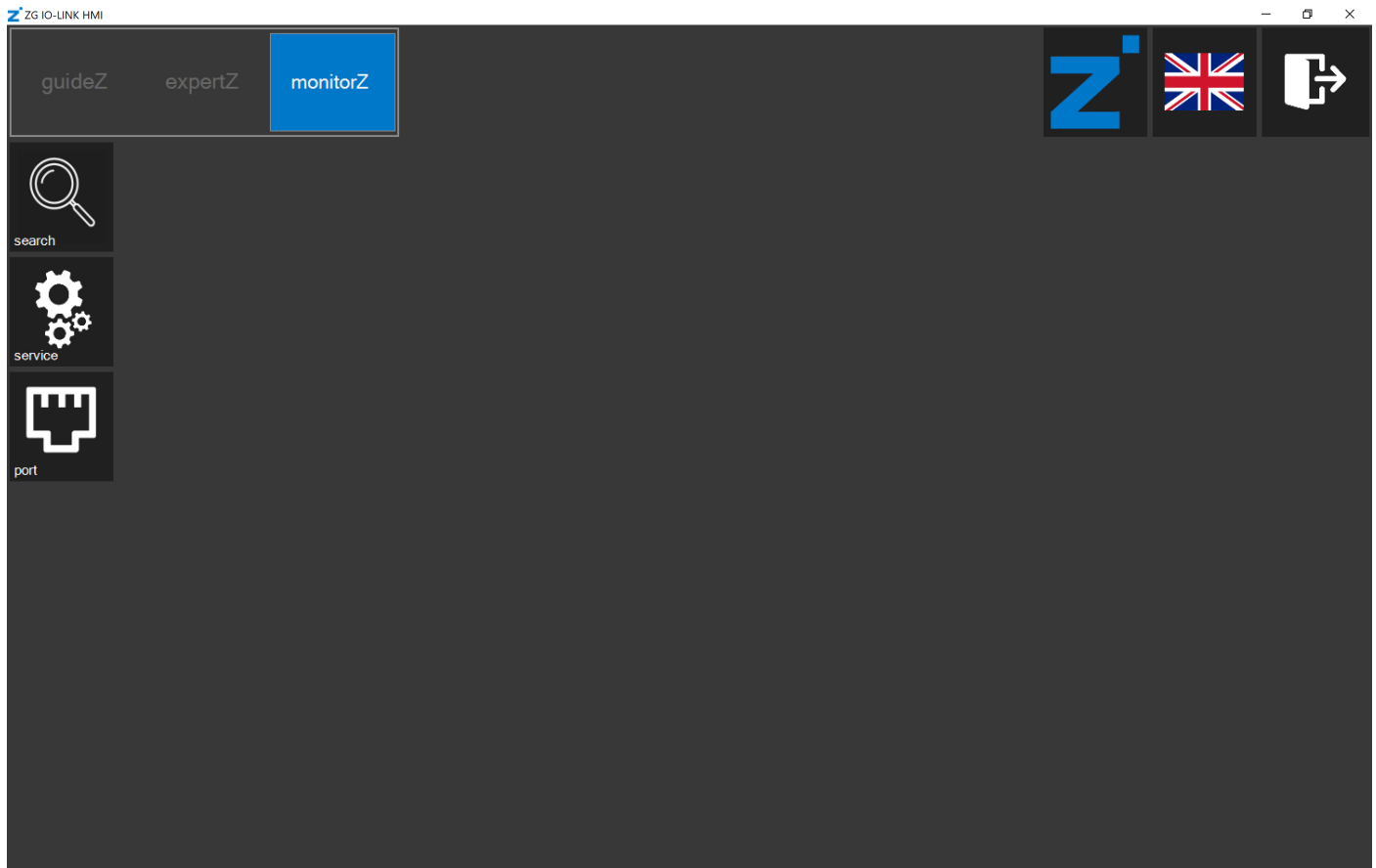
### INFORMATION



You need the HMI software *ZG\_IO\_Link\_HMI* from Zimmer GmbH in Version 2.0.3.10 or higher.

The three control levels are located in the top menu bar:

- *expertZ*: expert level where all gripper data can be accessed.
- *guideZ*: configuration level where the gripper can be taught in to the desired workpiece.
- *monitorZ*: diagnostic and observation level for monitoring the gripper during operation.

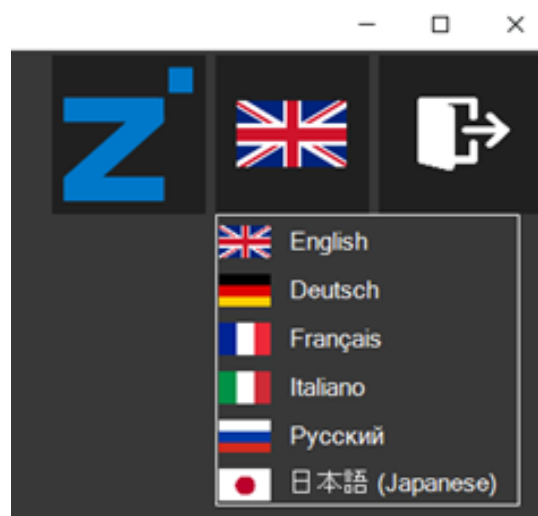


► Connect the Windows PC with the installed HMI software *ZG\_IO\_Link\_HMI*.



## 12.2 Selecting the language

- Click the flag to change the language of the HMI software.



## 12.3 Checking the version

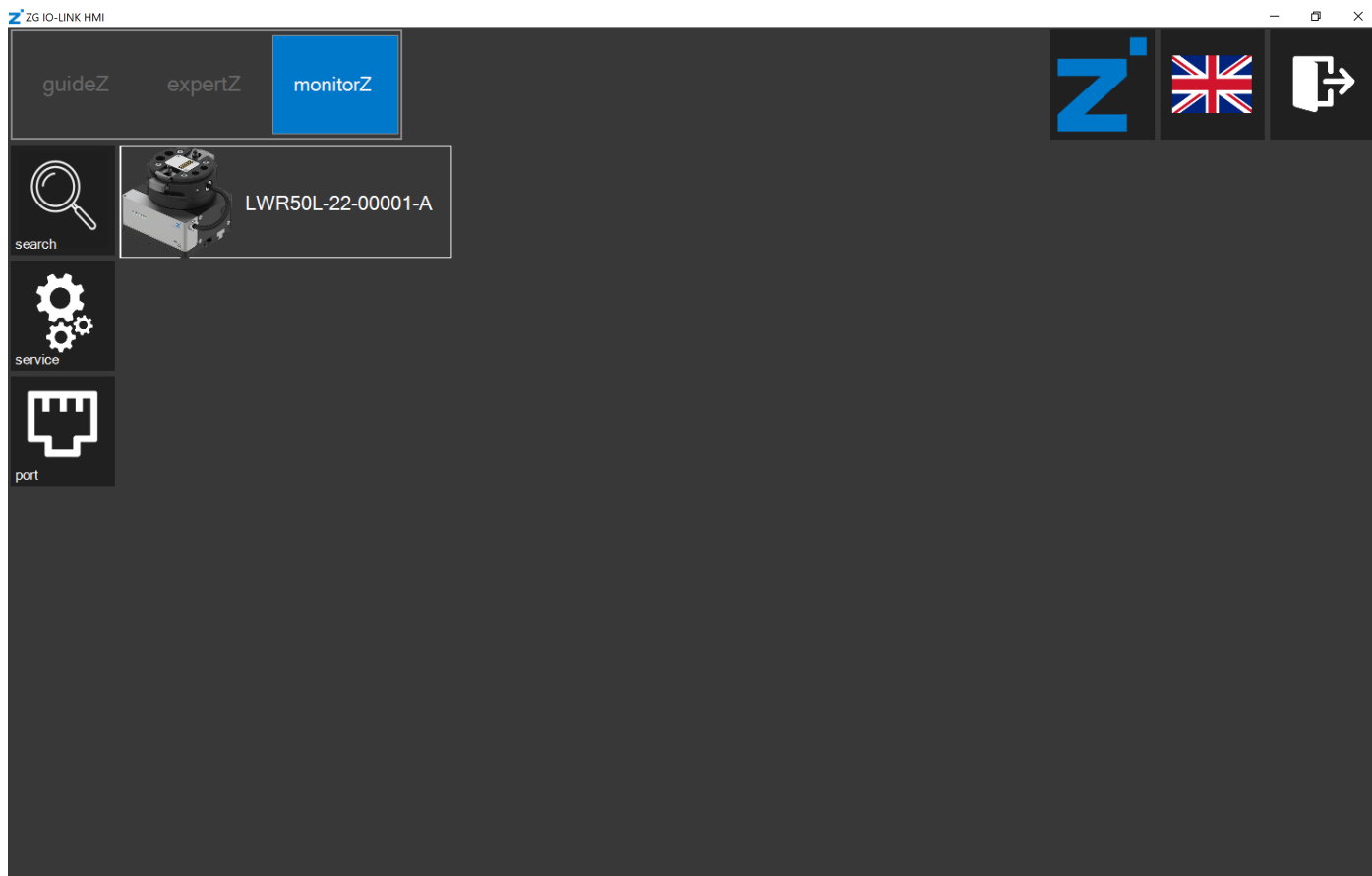
- Click the Zimmer logo to view information about the HMI software.



## 12.4 Selecting the gripper

► Click the *search* button.

⇒ The connected grippers are listed.



► Click the desired gripper to teach this in to the workpiece.

⇒ The *guideZ* control level opens.

## 12.5 Switching on and referencing the motor

### NOTICE



- Switch on the motor in the robot control panel also.

- Connect the actuator voltage.
- ⇒ The *power supply* LED lights up green if the actuator voltage is connected.
- Click the *on* button to switch on the motor.
- Click and hold the > < button for referencing the gripper.
- ⇒ This also references the gripper towards the outside or inside.

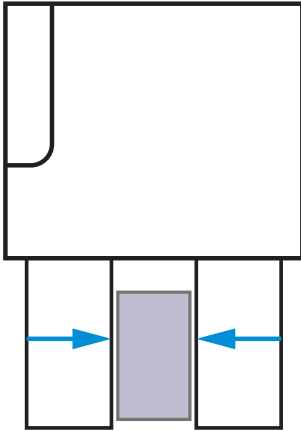


- Click the > button.

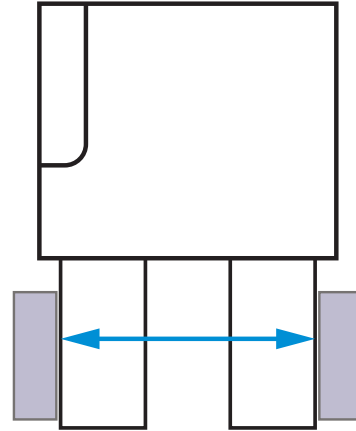
## 12.6 Selecting the gripping direction

- Select the gripping direction.

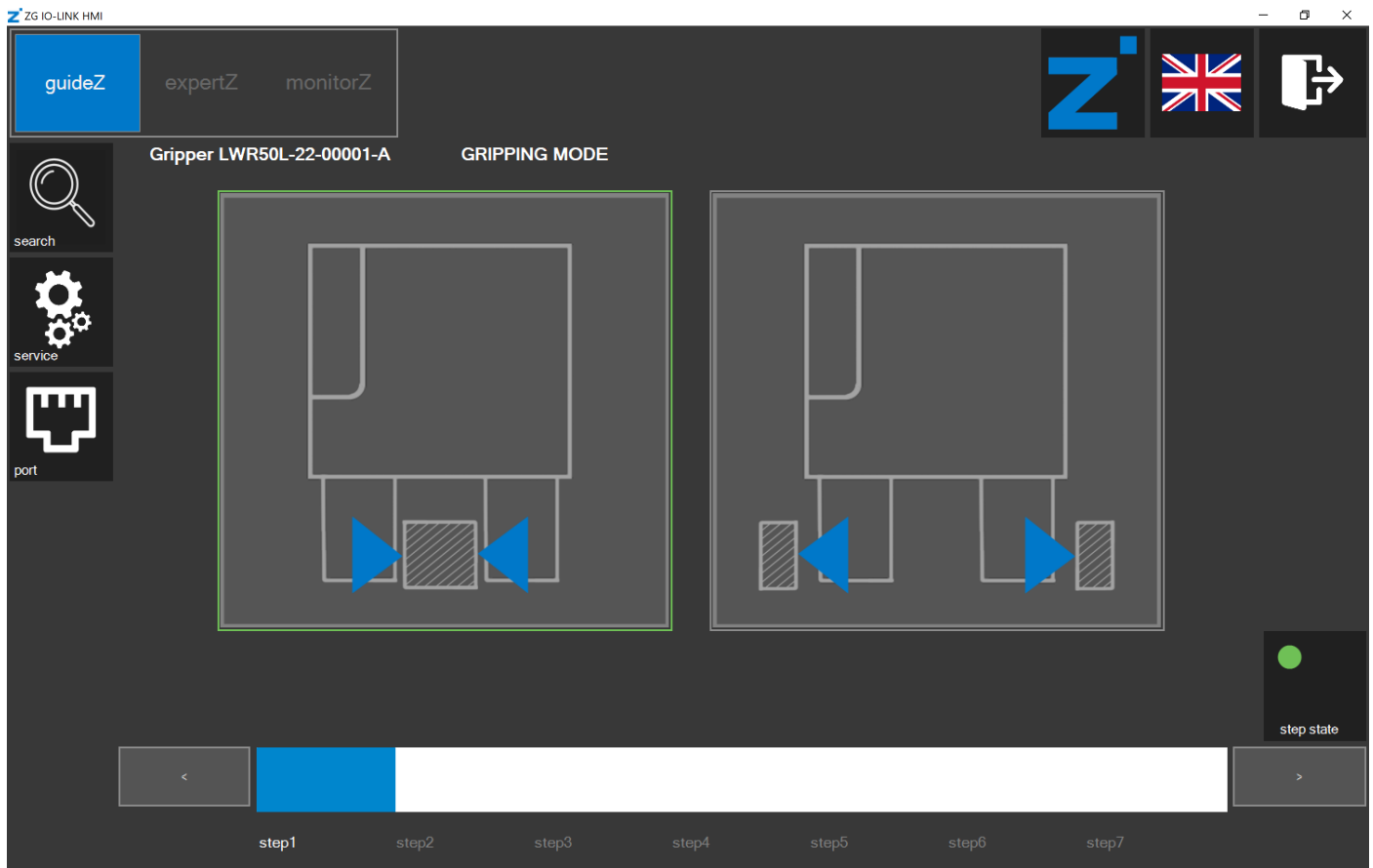
### Outside gripping



### Inside gripping



⇒ The parameters are set for the gripper automatically.



⇒ The *step state* LED lights up green.

- Click the > button.

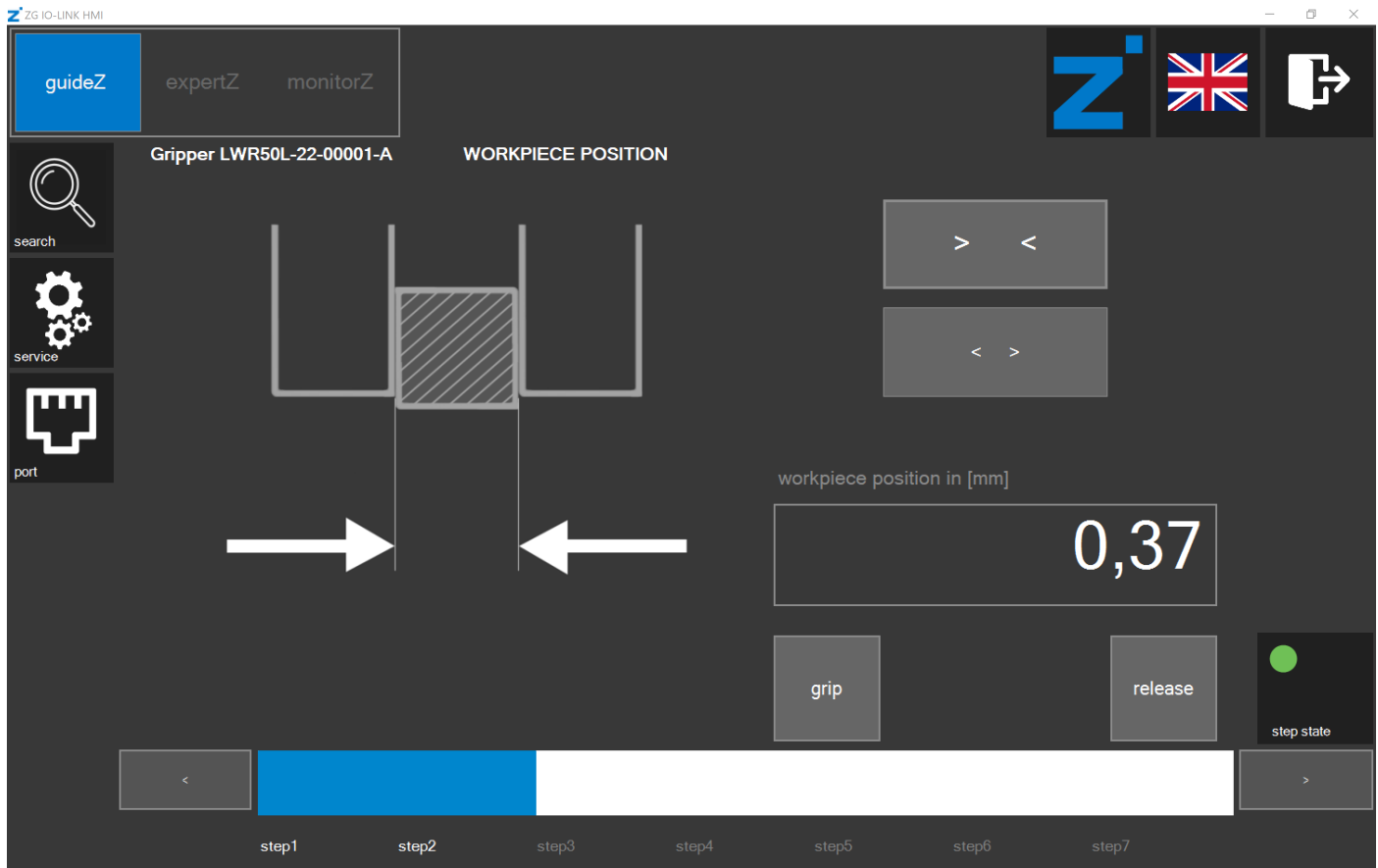
## 12.7 Teaching in the workpiece

### INFORMATION



The buttons for the preferred setting are highlighted visually.

- ▶ Click and hold the > < and < > buttons to teach in the workpiece parameters for the gripper.
- ⇒ The gripper detects the standstill and remembers the workpiece position.



### INFORMATION



You can use the *grip* button and the *release* button to test the settings.

- ▶ Click the > button.

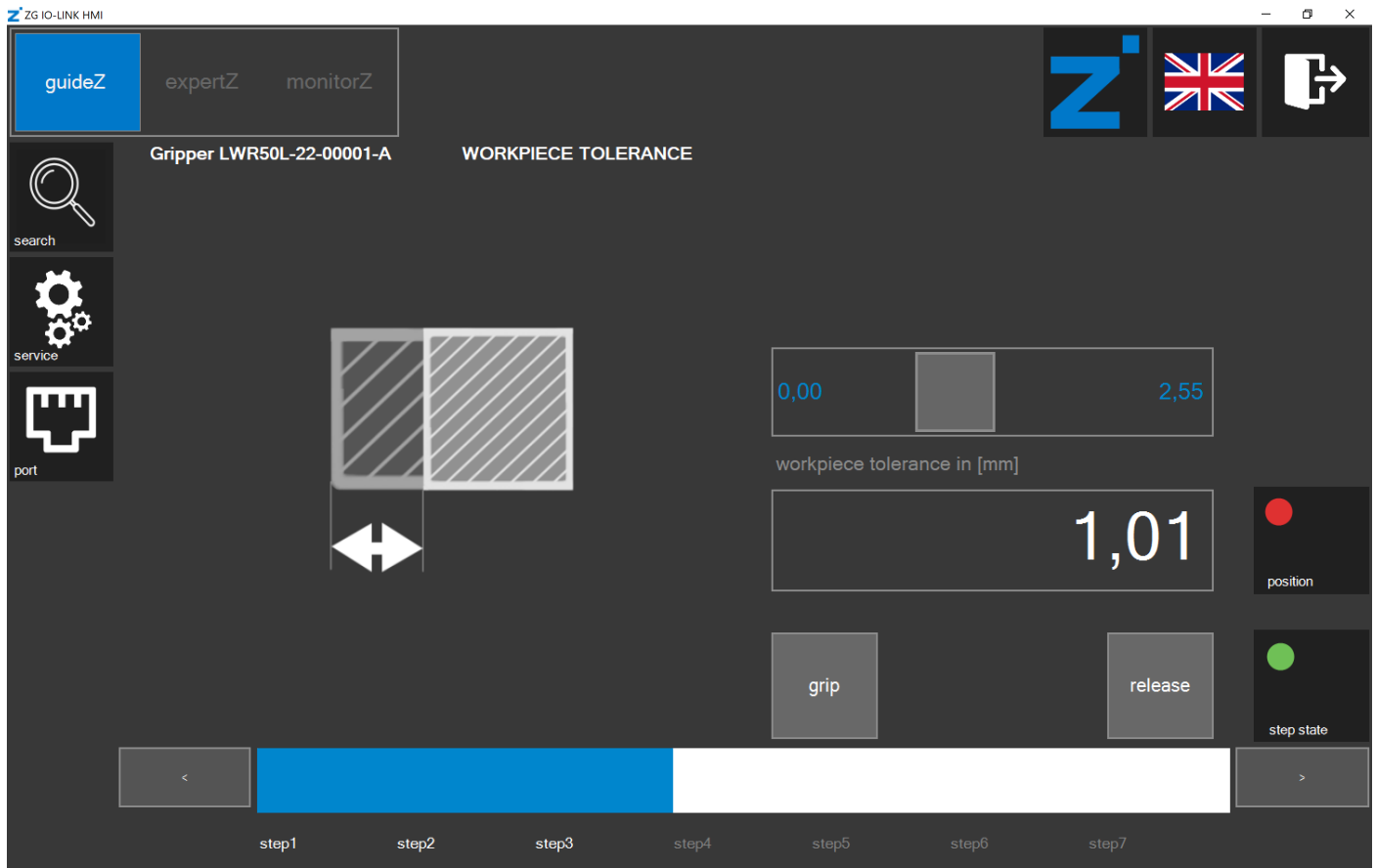
## 12.8 Setting the workpiece tolerance

- Slide the bar to a tolerance of 0.00 mm to 2.55 mm.

### INFORMATION



A gripper with servo function automatically sets its closed position just after the workpiece tolerance.



- Click the > button.

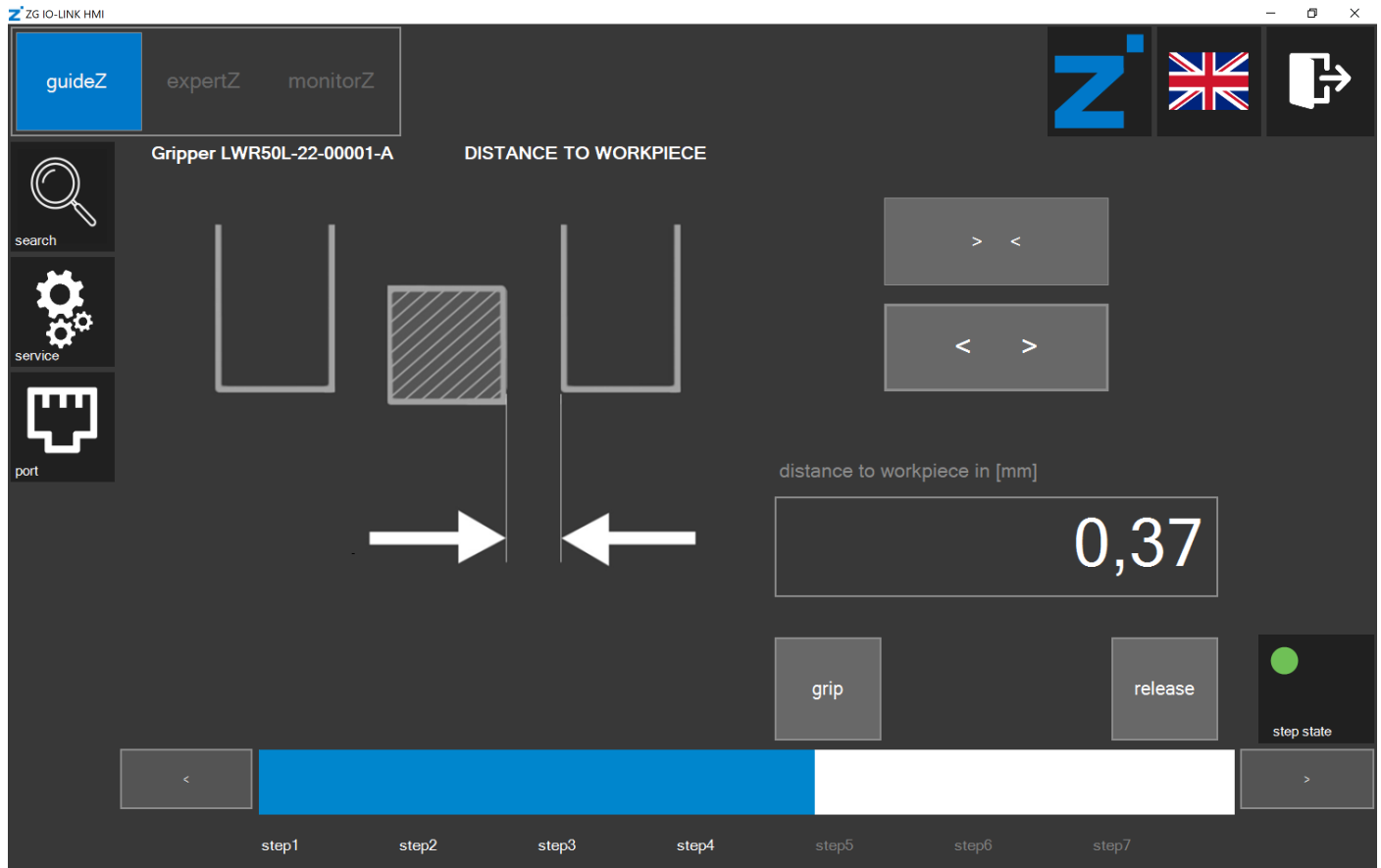
## 12.9 Setting the open position

### INFORMATION



The open position can only be set for grippers with a servo function.

- Click and hold the > < and < > buttons to set the position at which the gripper is to be open.

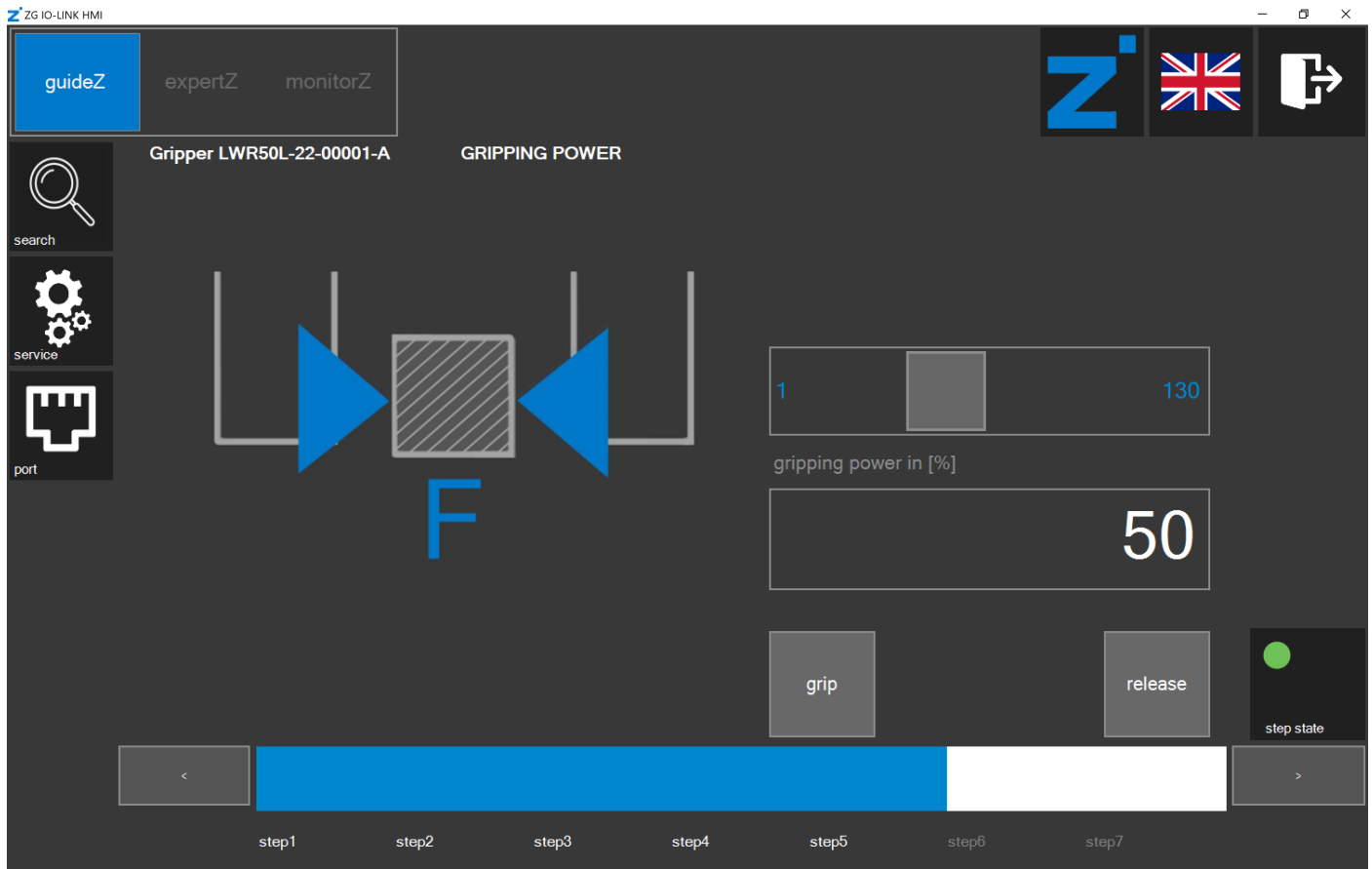


- Click the > button.

## 12.10 Setting the gripping force

Depending on the gripper, the gripping force can be configured and in addition, the speed for closing can be configured.

- Slide the bar to the desired gripping force.



- Click the > button.



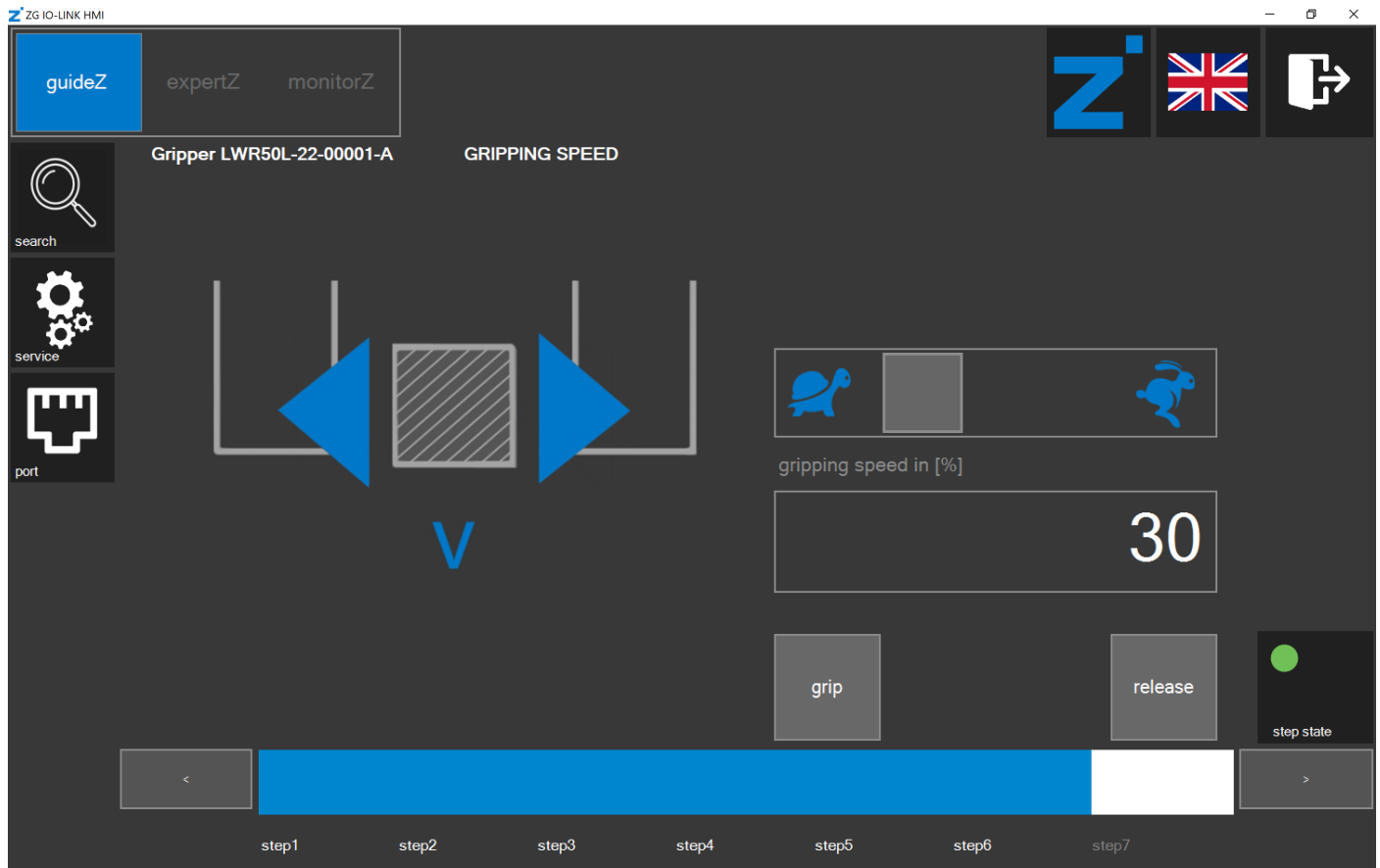
## 12.11 Setting the speed for opening the gripper

### INFORMATION



Setting the speed for opening the gripper is only possible for grippers with a servo function.

► Slide the bar to the desired speed.



► Click the > button.

## 12.12 Checking the settings

Workpiece training for the gripper is ended when the data is saved in the corresponding workpiece recipe.

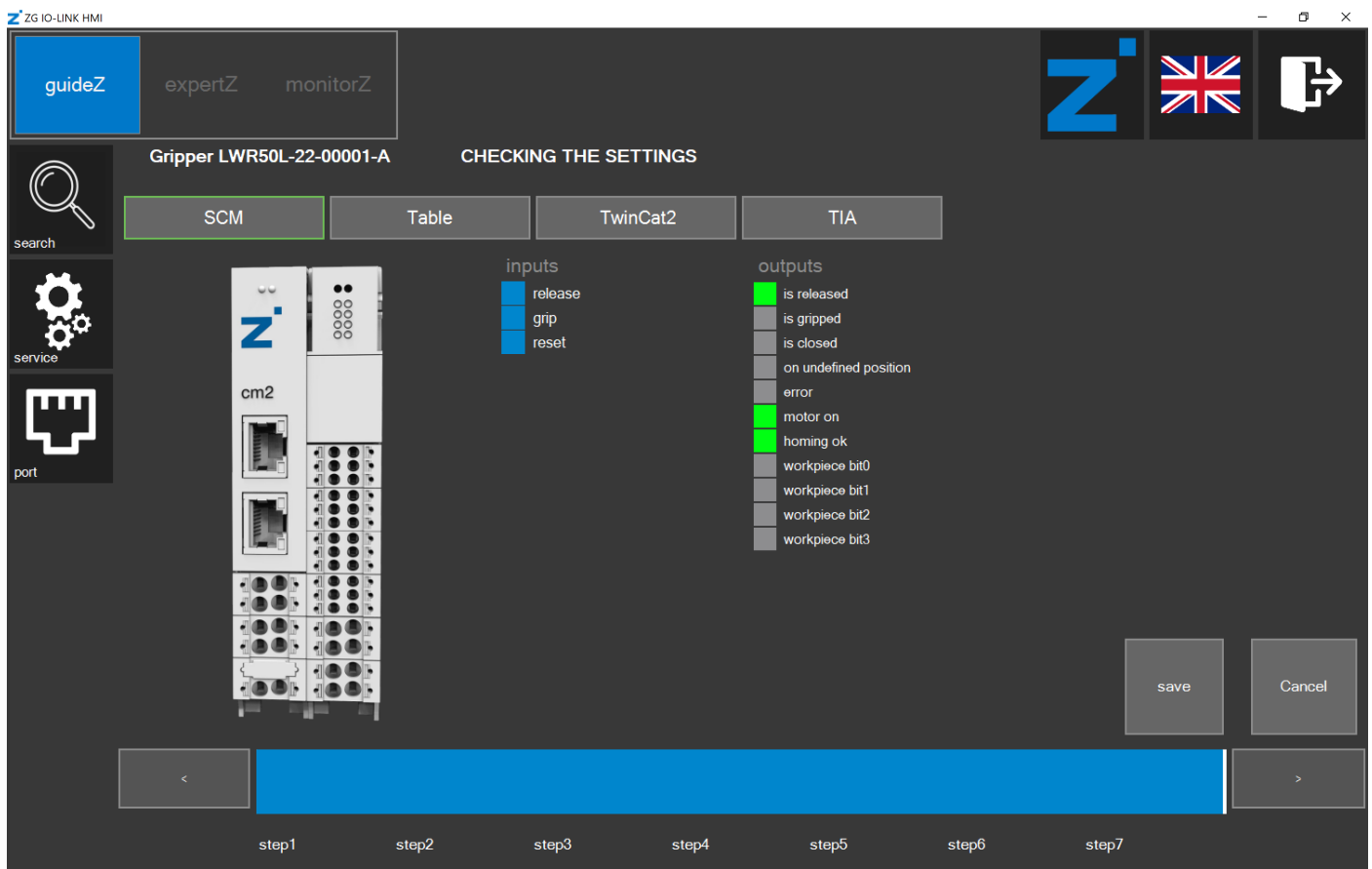
### INFORMATION



At this point, the set parameters are not yet saved in the corresponding workpiece recipe.

The settings can also be checked without the robot inputs and robot outputs of the robot control system.

- *inputs:*
  - ▶ Click the fields to set a command.
  - ⇒ The yellow commands are set.
- *outputs:*
  - ▶ The fields indicate the status of the gripper.
  - ⇒ The green statuses are active.



### INFORMATION



The *Table* view shows the parameters of the corresponding gripper generated in the background.

The *TwinCat2* and *TIA* views show the wiring of the PLC function blocks to fit the parameters of the gripper.

- ▶ Click the Save button.
- ⇒ The window for saving the workpiece recipe opens.

## 12.13 Saving the workpiece recipe

### INFORMATION



The highlighted digit in the workpiece number shows the respective selected workpiece recipe number.

The workpiece recipe numbers in a green frame show stored recipes of the current gripper.

The workpiece recipe numbers in an orange frame show stored recipes of another gripper.

ZG IO-LINK HMI

guideZ expertZ monitorZ

Gripper LWR50L-22-00001-A CHECKING THE SETTINGS

SCM Table TwinCat2 TIA

device mode 62 62 1 2 3 4

base position 75 3575 5 6 7 8

shift position 116 3675 9 10 11 12

teach position 426 4075 13 14 15

work position 536 4075

gripping power 65 65

gripping speed 50 50

position tolerance 10 100

Application specific tag LWR50L-22 LWR50L-22

Comment

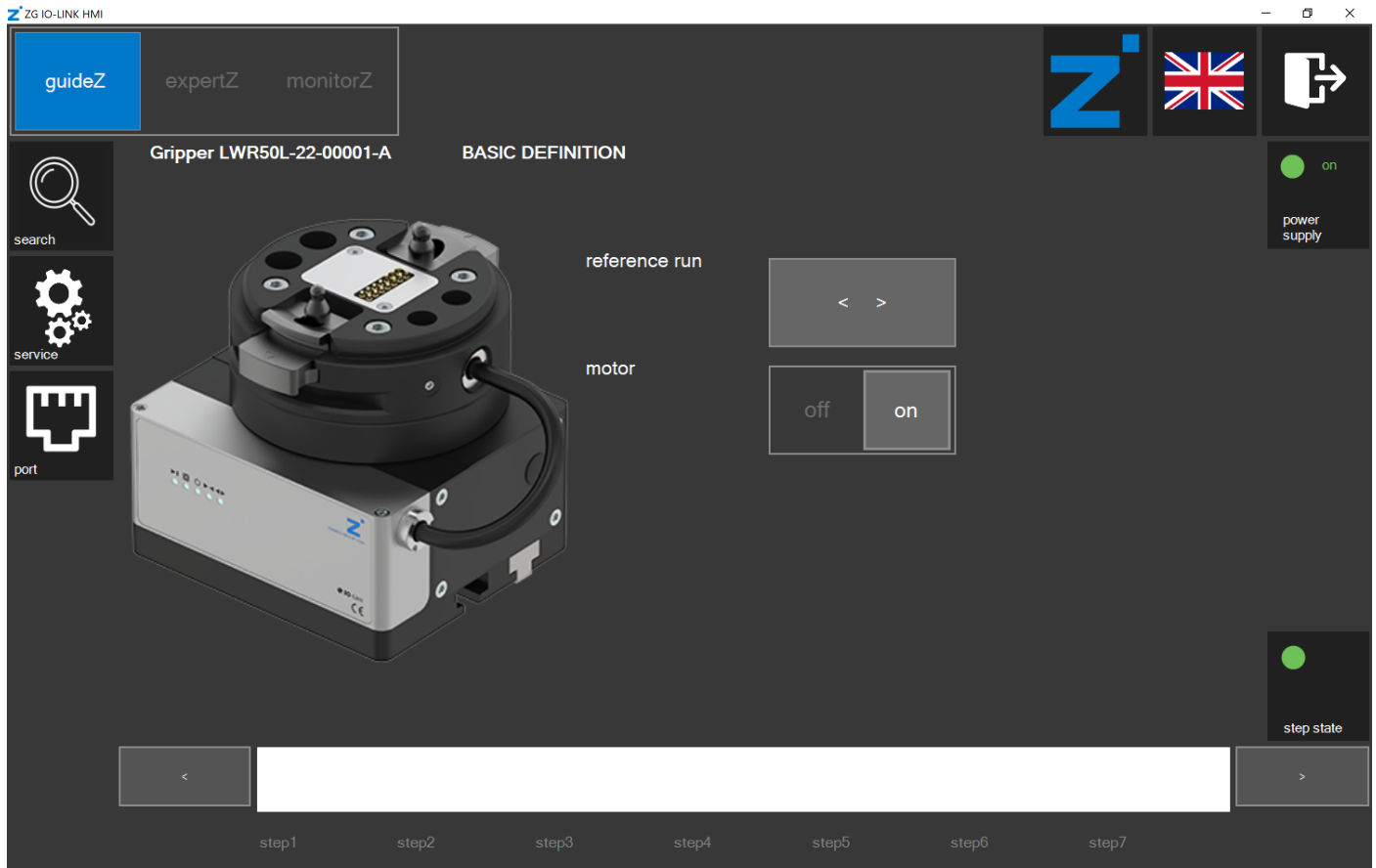
export all import all delete WP save WP

step1 step2 step3 step4 step5 step6 step7

- Click the desired workpiece recipe number.
- Click the save *WP* button.

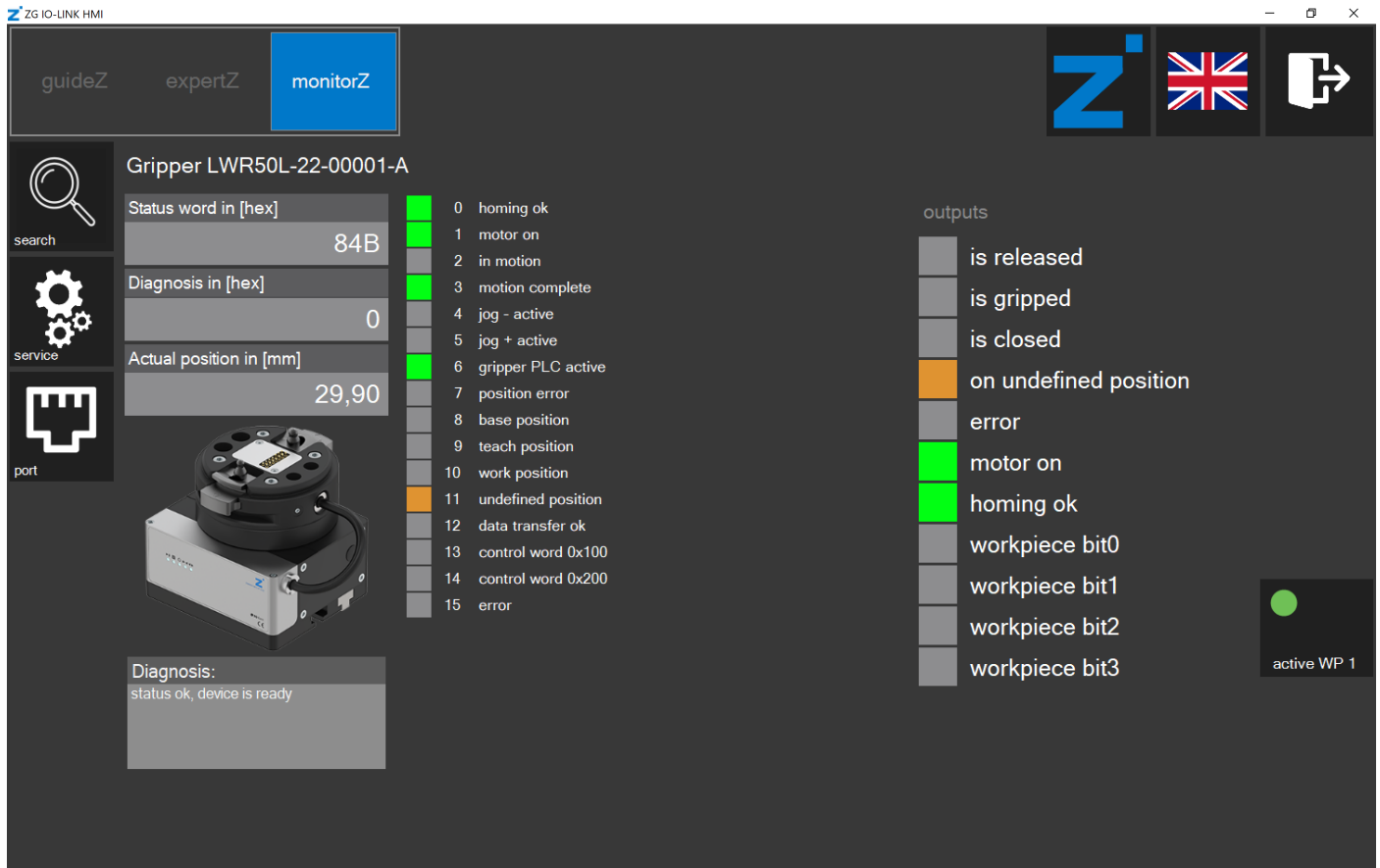
## 12.14 Data storage ended

- ▶ After successful data storage, the window for teaching in a new workpiece is displayed, see the section "Teaching in the workpiece".
- ▶ Click the *monitorZ* button if you want to switch to the *monitorZ* control level instead.



## 12.15 monitorZ control level

- Click the *plug HMI* button to transfer the control ability to the digital robot inputs and robot outputs.
- ⇒ The LED lights up red.
- ⇒ The control system of the gripper with the HMI software *ZG\_IO\_LINK\_HMI* is no longer possible because the input and output signals now have control.
- ⇒ You can move the gripper with the external control system and the saved settings.



## 12.16 expertZ control level

In the *expertZ* control level, fine tuning of the gripping parameters as well as access to all process data (PDU), service data (ISDU) and workpieces is possible.

ZG IO-LINK HMI

guideZ
**expertZ**
monitorZ

search
service
port

Gripper LWR50L-22-00001-A

Actual position in [mm]  

7,19

**Diagnosis:**  
position values not plausible

is released  
is closed  
is gripped  
on undefined position  
error

position tolerance in [mm]

gripping power in [%]

gripping speed in [%]

base position in [mm]

shift position in [mm]

teach position in [mm]

work position in [mm]

0,00

1

1

0,75

0,75

0,75

0,75

Outward

Mode	Type
50	HARD
62	HARD
82	PREPOSITION_HOLDING

plug HMI
motor
auto

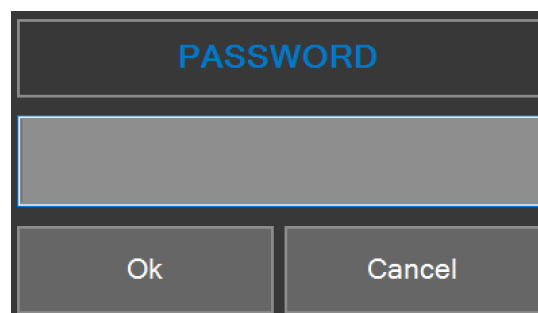
w.piece
PDU
ISDU
release
acquire
grip

By default, the *fine tuning* setting is active. This is a view based on the parameters configured in the *guideZ* control level. You can optimize these parameters in this view.

- Slide the bar to the desired value to change it.
  - In the *Outward* area, click the desired *mode* to change it.
  - Click the *release* button or the *grip* button to apply the changes and run the motion task.
- ⇒ The HMI software checks whether the value can be processed by the gripper and, if necessary, adapts these to its limit values.

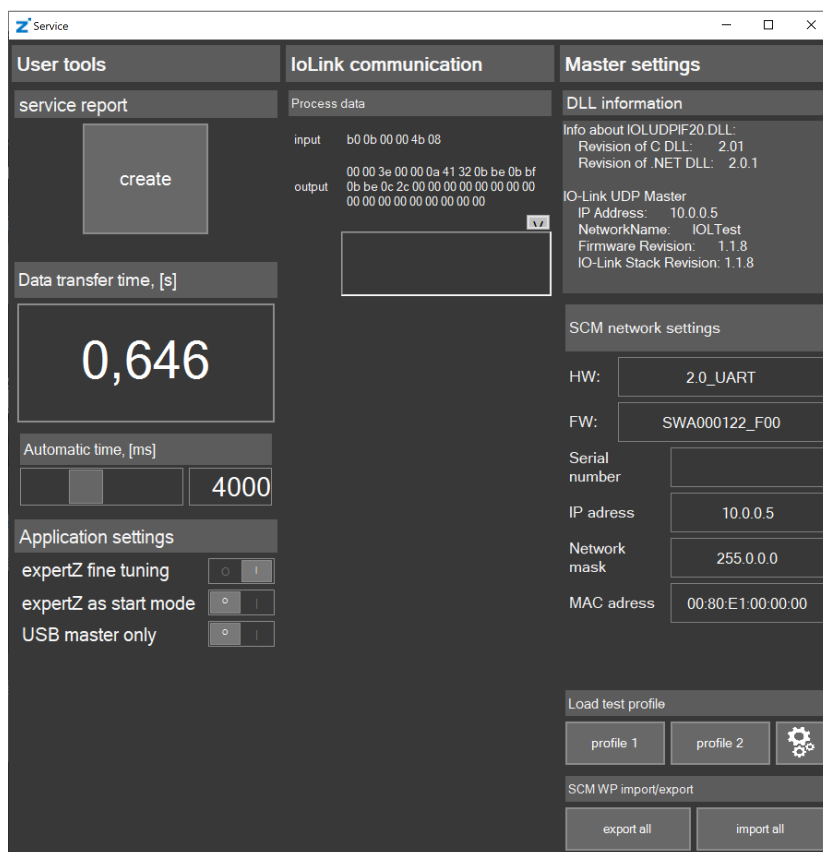
### 12.16.1 Service

- Click the *service* button.
- ⇒ A login window opens.
- Enter the password: *Service*



A login window titled "PASSWORD" with a large text input field and two buttons at the bottom: "Ok" and "Cancel".

⇒ The *Service* window opens.



The *Service* window is divided into three main sections: **User tools**, **IoLink communication**, and **Master settings**.

- User tools:** Contains a "service report" section with a "create" button, a "Data transfer time, [s]" display showing "0,646", an "Automatic time, [ms]" slider set to "4000", and "Application settings" for expertZ fine tuning, expertZ as start mode, and USB master only.
- IoLink communication:** Shows "Process data" with input and output hex values.
- Master settings:** Includes "DLL information" (Info about IOUDPIF20 DLL, Revision of C DLL: 2.01, Revision of .NET DLL: 2.0.1), "IO-Link UDP Master" (IP Address: 10.0.0.5, NetworkName: IOLTest, Firmware Revision: 1.1.8, IO-Link Stack Revision: 1.1.8), "SCM network settings" (HW: 2.0\_UART, FW: SWA000122\_F00, Serial number, IP address: 10.0.0.5, Network mask: 255.0.0.0, MAC address: 00:80:E1:00:00:00), "Load test profile" (profile 1, profile 2, settings icon), and "SCM WP import/export" (export all, import all).

#### 12.16.1.1 Service report

- In the *service report* area, click the create button to create a service report.

#### 12.16.1.2 Data transfer time

The *Data transfer time* is the time needed for data transmission to the gripper.

#### 12.16.1.3 Automatic time

The *Automatic time* is the pause time of the automatic sequence.

- Slide the bar to the desired time.

#### 12.16.1.4 Application settings

- Enable the option *expertZ as start* if *expertZ* is to be displayed as the new start view.
- To get full access to all the parameters, *expertZ fine tuning* mode must be switched off.
- Disable the option *expertZ fine tuning*.

**Gripper LWR50L-22-00001-A**

Status word in [hex]: 84B

Diagnosis in [hex]: 0

Actual position in [mm]: 29,92

Diagnosis: status ok, device is ready

Functions:

0	homing ok
1	motor on
2	in motion
3	motion complete
4	jog - active
5	jog + active
6	grripper PLC active
7	position error
8	base position
9	teach position
10	work position
11	undefined position
12	data transfer ok
13	control word 0x100
14	control word 0x200
15	error

Parameters:

- device mode: 62
- workpiece no: 0
- position tolerance in [mm]: 0,10
- gripping power in [%]: 65
- gripping speed in [%]: 50
- base position in [mm]: 30,06
- shift position in [mm]: 30,07
- teach position in [mm]: 30,06
- work position in [mm]: 31,16

Outward and Inward modes:

Mode	Type	Mode	Type
50	POSITION	72	HARD
62	HARD	92	PREPOSITION
82	PREPOSITION		

Buttons: plug HMI, motor, auto, w.piece, PDU, ISDU, to base, acquire, to work

- In the *Application settings* area, enable the *USB master only* option if network communication is to be switched off.
  - Enable the option only if you have a Zimmer PrepBox with a USB cable.
- ⇒ The HMI software searches for USB nodes only.

#### 12.16.1.5 SCM network settings

- In the *IP address* area, click the field to change the IP address of the SCM.
- Close the *Service* window.
- Run out a cold boot.



### 12.16.2 Starting the automatic sequence

In the automatic sequence, the gripper makes cyclical opening and closing movements.

- Click the *auto* button.

### 12.16.3 Workpiece recipe management

In workpiece recipe management, the previously adapted parameters can be stored to the workpiece database again. In the *in work piece* area, the data with workpiece recipe numbers that are currently selected in the *work piece number* is displayed. In the *to save* area, the data that can be stored to the selected workpiece recipe number with the *save WP* button is displayed.

- Click the *w.piece* button to open workpiece recipe management.

ZG IO-LINK HMI

guideZ
**expertZ**
monitorZ

search

service

port

Gripper LWR50L-22-00001-A

	in work piece	to save
device mode	62	82
base position	317	692
shift position	961	1525
teach position	1256	1874
work position	1927	2625
gripping power	13	47
gripping speed	47	67
position tolerance	31	65
Application specific tag	LWR50L-22	LWR50L-22
Comment	LWR	

1

2

3

4

5

6

7

8

9

10

11

12

13

14

15

work piece number

export all

import all

delete WP

load from WP

save WP

plug HMI

motor

auto

w.piece

PDU

ISDU

to base

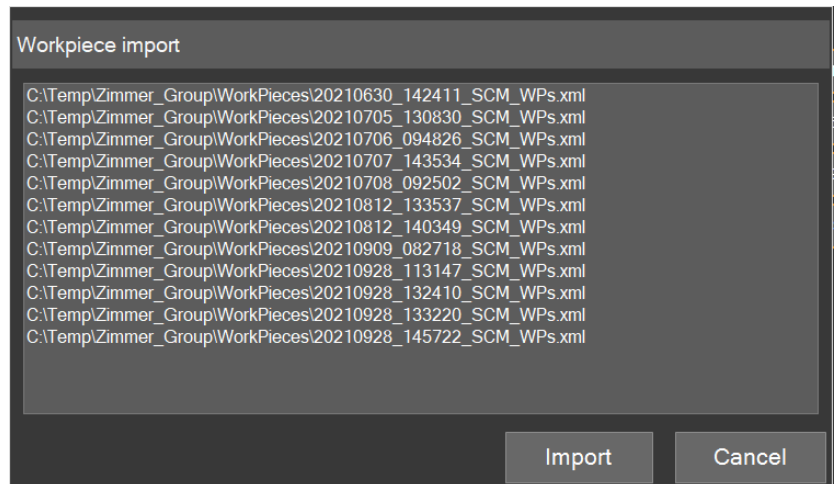
acquire

to work

### 12.16.3.1 Importing workpiece recipes

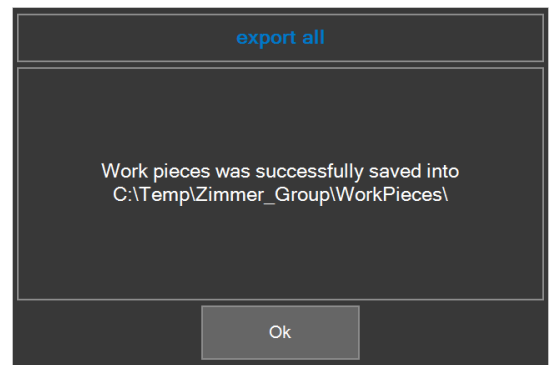
Only the entire data set can be loaded. All 15 workpiece recipes are overwritten during import.

- ▶ Click the *import all* button.
- ⇒ The *Workpiece import* window with the previously stored data sets is displayed.
- ▶ Click the desired data set.
- ▶ Click the *Import* button.



### 12.16.3.2 Exporting workpiece recipes

- ▶ Click the *export all* button.
- ⇒ All workpiece recipes are stored on the hard drive: *C:\Temp\Zimmer\_Group\WorkPieces*



## 12.16.4 ISDU

The ISDU is acyclic service data that is written directly to the memory of the gripper. This data is thus not stored in the SCM. Acyclic service data that is writable can be adapted here.

► Click the ISDU button to view the acyclic service data.

ZG IO-LINK HMI

guideZ **expertZ** monitorZ

search service port

Gripper LWR50L-22-00001-A

Status word in [hex] **884B**

Diagnosis in [hex] **301**

Actual position in [mm] **7,69**

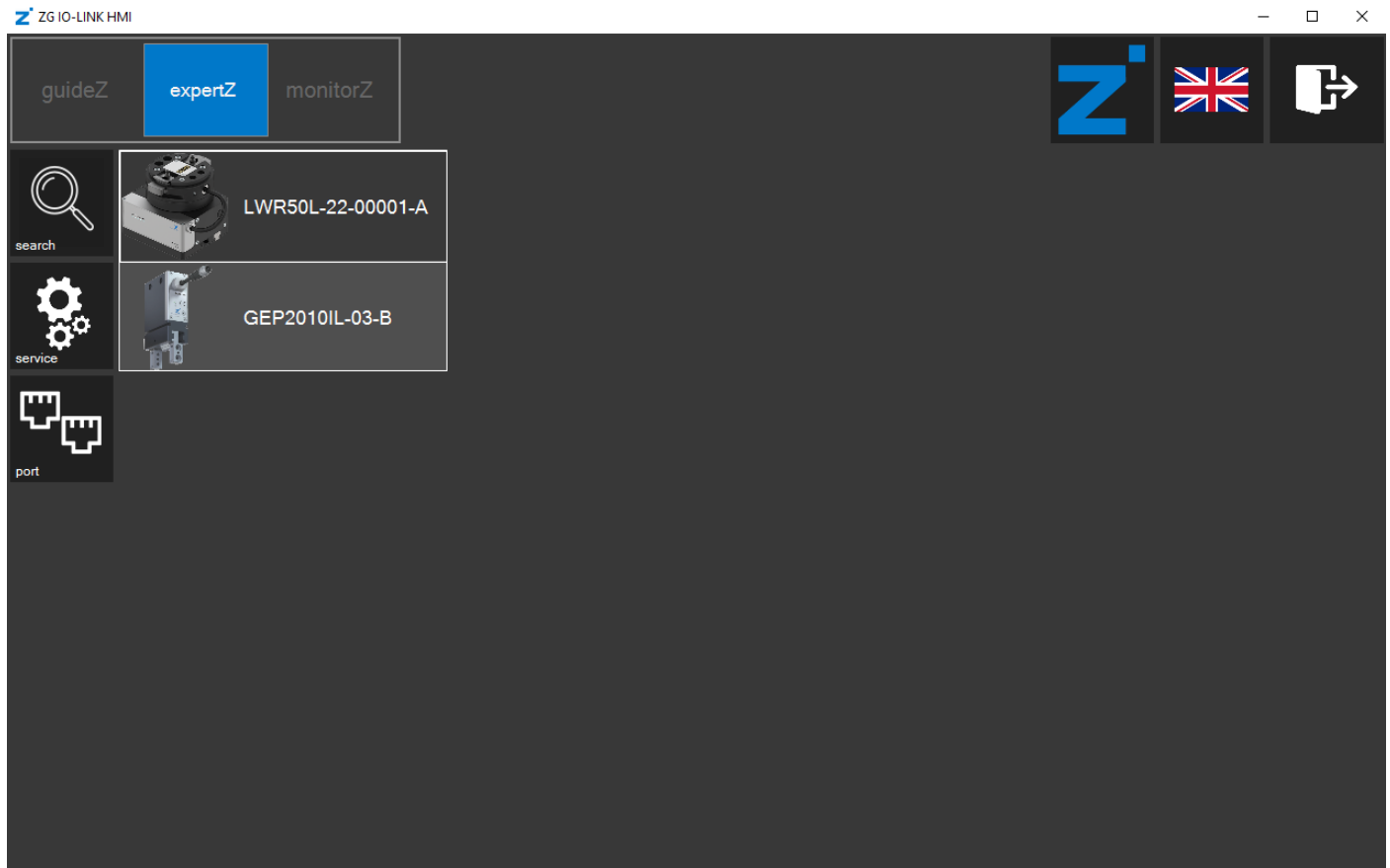
Diagnosis:  
position values not plausible

idx	sdx	name	value	rights	type	iol_type
+	0	Direct Parameters - Page 1		rw	0	recordt
+	1	Direct Parameters - Page 2		rw	0	recordt
	2	System Command		wo	uint8	std_d_system
+	12	Device Access Locks		rw	0	recordt
	16	Vendor Name	Zimmer GmbH	ro	string	stringt
	17	Vendor Text	www.zimmer-group.c	ro	string	stringt
	18	Product Name	LWR50L	ro	string	stringt
	19	Product ID	LWR50L-22-00001-	ro	string	stringt
	20	Product Text	gripper electric: 2-jar	ro	string	stringt
	21	Serial Number	01-00025505	ro	string	stringt
	22	Hardware Revision	BG00104 F00	ro	string	stringt
	23	Firmware Revision	SWA000058 Q00+5	ro	string	stringt

plug HMI motor auto w.piece PDU **ISDU** to base acquire to work

## 12.17 Selecting the active gripper(s)

If two grippers are connected, you can select whether both are to be active or only one of the two.

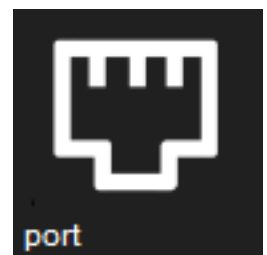


Both connected grippers are active.



Only one of the two connected grippers is active.

► Click the corresponding gripper to select it.



## 13 Operation

### 13.1 Operating Freedrive

#### INFORMATION

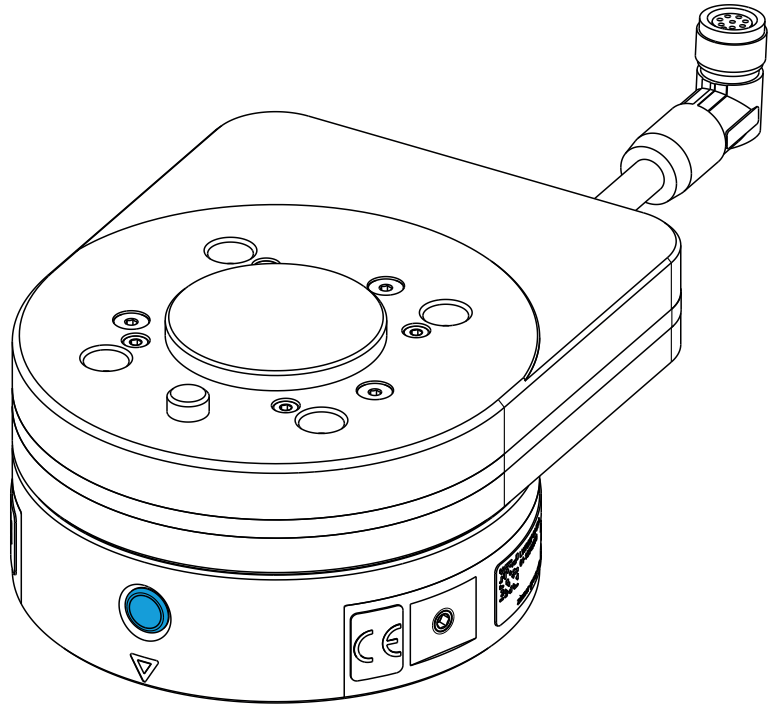


Freedrive is only available for installation size LWR50F-01-03-A.

For manual soft-switching of the robot, the product is equipped with a Freedrive button ●.

The following work steps must be observed for manually teaching in the robot position:

- ▶ To soft-switch the robot, press the Freedrive button.
- ⇒ The robot can be moved manually.
- ⇒ The robot is moved with the product to the desired position.
- ▶ Release the Freedrive Button again as soon as you have reached the desired position.
- ⇒ The robot and product stop at their position.
  - ▶ Observe the information from the robot manufacturer for teaching in and activating the position of the robot and product in the control system.



#### INFORMATION



- ▶ Details about activation can be found in the information from the robot manufacturer.

## 14 Error diagnosis

#### INFORMATION



- ▶ For further information on troubleshooting for grippers, refer to the current installation and operating instructions of the gripper on our website.
- ▶ Please contact Customer Service if you have any questions.

## 15 Maintenance

### NOTICE



#### **Material damage resulting from blowing out with compressed air**

Blowing out the product with compressed air can cause malfunctions and pose a risk of accidents.

- ▶ Never purge the product with compressed air.

### NOTICE



#### **Material damage caused by liquid and solvent-based cleaners**

Liquid and solvent-based cleaning agents can cause malfunctions and pose a risk of accidents.

- ▶ Do not clean the product with any cleaning agents that are liquid or contain solvents.

Operation of the product is maintenance-free.

- ▶ Even though the product is maintenance-free as mentioned above, perform a regular visual inspection to check for any corrosion, damage or contamination.
  - ▶ Have maintenance work that requires disassembly of the product performed by customer service if possible.
- ⇒ Dismantling and reassembling the product without authorization may result in complications, as special installation equipment is required in some cases. Zimmer GmbH accepts no liability for any resulting malfunctions or damage.

## 16 Resetting to factory settings

### NOTICE



When a reset to factory settings is performed, all saved information is deleted.

- ▶ For more information, see the operating instructions for the robot-specific MATCH Comfort App.

## 17 Decommissioning/disposal

### INFORMATION



When the product reaches the end of its operational phase, it can be completely disassembled and disposed of.

- ▶ Disconnect the product completely from the power supply.
- ▶ Dispose of the components properly according to the material groups.
- ▶ Comply with the locally applicable environmental and disposal regulations.

## 18 RoHS declaration

in terms of the EU Regulation 2011/65/EU

### Name and address of the manufacturer:

#### Zimmer GmbH

📍 Im Salmenkopf  
77866 Rheinau, Germany  
☎ +49 7844 9138 0  
✉ [info@zimmer-group.com](mailto:info@zimmer-group.com)  
💻 [www.zimmer-group.com](http://www.zimmer-group.com)

We hereby declare that the incomplete machine described below

**Product designation:** MATCH robot module

**Type designation:** LWR50F-01-03-A, LWR50F-09-03-A

conforms to the requirements of the directive in its design and the version we put on the market.

Michael Hoch

Authorized representative for the  
compilation of relevant technical  
documents

Rheinau, Germany, 2021-04-01

(Place and date of issuance)



Martin Zimmer  
(Legally binding signature)  
Managing Partner

## 19 REACH declaration

In terms of the EC Regulation 1907/2006

### Name and address of the manufacturer:

#### Zimmer GmbH

📍 Im Salmenkopf  
77866 Rheinau, Germany  
☎ +49 7844 9138 0  
✉ [info@zimmer-group.com](mailto:info@zimmer-group.com)  
💻 [www.zimmer-group.com](http://www.zimmer-group.com)

REACH stands for **R**egistration, **E**valuation, **A**uthorisation and **R**estriction of **C**hemicals.

A full declaration of REACH can be obtained from the manufacturer due to the duty to notify in accordance with Art. 33 of the REACH regulation ("Duty to communicate information on substances in articles").

Michael Hoch

Authorized representative for the  
compilation of relevant technical  
documents

Rheinau, Germany, 2021-04-01

(Place and date of issuance)



Martin Zimmer  
(Legally binding signature)  
Managing Partner

## 20 Declaration of Incorporation

In terms of the EU Machinery Directive 2006/42/EC (Annex II 1 B)

### Name and address of the manufacturer:

**Zimmer GmbH**

Im Salmenkopf  
77866 Rheinau, Germany  
+49 7844 9138 0  
[info@zimmer-group.com](mailto:info@zimmer-group.com)  
[www.zimmer-group.com](http://www.zimmer-group.com)

We hereby declare that the incomplete machine described below

**Product designation:** MATCH robot module  
**Type designation:** LWR50F-01-03-A, LWR50F-09-03-A

conform to the requirements of the Machinery Directive, 2006/42/EC, Article 2g, Annex VII.b – Annex II.b, in its design and the version we put on the market.

Basic health and safety requirements:

No. 1.1.2, No. 1.1.3, No. 1.5, No. 1.3.2, No. 1.3.4, No. 1.3.7, No. 1.5.3, No. 1.5.4, No. 1.5.8, No. 1.6.4, No. 1.7.1, No. 1.7.4

A full list of applied standards can be obtained from the manufacturer.

We also declare that the specific technical documents were produced in accordance with Annex VII Part B of this Directive. We undertake to provide the market supervisory bodies with electronic versions of special documents for the incomplete machine through our documentation department, should they have reason to request them.

**The incomplete machine may only be commissioned if it has been ascertained, if applicable, that the machine or system in which the incomplete machine is to be installed satisfies the requirements of Directive 2006/42/EC on Machinery and an EC Declaration of Conformity has been drawn up in accordance with Annex II 1 A.**

Kurt Ross

Authorized representative for the  
compilation of relevant technical  
documents

Rheinau, Germany, 2021-04-01

(Place and date of issuance)



Martin Zimmer  
(Legally binding signature)  
Managing Partner



## 21 Declaration of Conformity

As defined by the EC Directive 2014/30/EU on electromagnetic compatibility

### Name and address of the manufacturer:

#### Zimmer GmbH

📍 Im Salmenkopf  
77866 Rheinau, Germany  
☎ +49 7844 9138 0  
✉ [info@zimmer-group.com](mailto:info@zimmer-group.com)  
💻 [www.zimmer-group.com](http://www.zimmer-group.com)

We hereby declare that the products described below

**Product designation:** MATCH robot module

**Type designation:** LWR50F-01-03-A, LWR50F-09-03-A

conform to the requirements of the Electromagnetic Compatibility Directive 2014/30/EU in its design and the version we put on the market.

The following harmonized standards have been used:

DIN EN ISO 12100	Safety of machinery - General principles for design - Risk assessment and risk reduction
DIN EN 61000-6-3	EMC Generic standard, Emission standard for residential, commercial and light-industrial
DIN EN 61000-6-2	EMC Generic standard, Emission standard for industrial environments
DIN EN 61000-6-4	EMC Generic standard, Immunity for industrial environments

A full list of applied standards can be obtained from the manufacturer.

Kurt Ross

Authorized representative for the compilation of relevant technical documents

Rheinau, Germany, 2021-04-01

(Place and date of issuance)



Martin Zimmer  
(Legally binding signature)  
Managing Partner