



# MATCH

## INSTALLATION AND OPERATING INSTRUCTIONS

2-jaw parallel gripper with  
quick-change system  
LWR50L-02 series

DDOC01067

THE KNOW-HOW FACTORY

## Parameter explanation (glossary)

Parameter	Explanation
ActualPosition	Value of the current position of the product [1/100 mm]
BasePosition	BasePosition is the outer jaw position. Depending on the gripper profile, this can also be a work position.
ControlWord	Activation of the product Only one bit is permitted to be active in the word. The value "0" is also permitted.
DeviceMode	Used to select gripping profiles as well as the additional help modes in the product.
Diagnosis	If an error occurs, outputs a diagnostic code that can be compared with the error list.
DIR	Direction/24 V cable connection - Depending on the product, this signal is used to move the product.
Error	Fault
GND	Abbreviation for ground connection
GripForce	Setting the gripping force
Offset	Correction value
PositionTolerance	Tolerance range for TeachPosition, BasePosition and WorkPosition The value of the parameter acts in both directions.
ShiftPosition	ShiftPosition is a switching position between pre-positioning and gripper movement.
StatusWord	In its bits, returns the most important information about the status of the product to the control system.
Teach/Adjust	Programming/Adjusting With this signal, depending on the gripper type, the current position of the gripper jaws can be taught in as the new workpiece position. Adjust is used to define the reachable end positions of the gripper jaws.
TeachPosition	Actual workpiece position
Traversing routine	Defined procedure for movement of the gripper jaws
Travel path	Path on which the gripper jaws travel.
WorkpieceNo	Selection of the workpiece recipes stored in the product
WorkPosition	Inner jaw position on the product Depending on the application, this can also be the standby position.

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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 for people or that may result in material or environmental damage. Ignoring these notices may result in slight, temporary injuries or damage to the product or to 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.

#### NOTICE



General notices contain usage tips and valuable information, but no warnings of dangers to health.

#### 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.

**WARNING****Risk of injury caused by suspended loads**

Improper handling of suspended loads can cause serious injury.

- ▶ Always keep an adequate safety distance from suspended loads.
- ▶ Never walk underneath a suspended load.

### 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 temporary gripping, handling and holding.

The product is not suitable for clamping workpieces during a machining process.

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

Installation, commissioning and maintenance may only be performed by trained specialists. These persons must have read and understood the installation and operating instructions in full.



## 5 Product description

### CAUTION



**Reduction of the gripping force can cause personal injury and material damage**

When flexible components are gripped, the gripping force of the product is reduced.

Reduced gripping force can lead to personal injury or material damage, because the components that are being gripped can no longer be securely gripped and transported.

### NOTICE



► Make sure that the setting of the gripping force and the selection of the gripper finger length are correct to prevent incorrect bracing of the gripper jaws.

⇒ An incorrect configuration or selection can lead to malfunction

The end-of-arm platform of Zimmer Group is equipped with an extensive portfolio of functions and with universal communication interfaces. MATCH is compatible with any lightweight construction robot. The system can be mounted to the robot flange and set up conveniently with just a few manual adjustments.

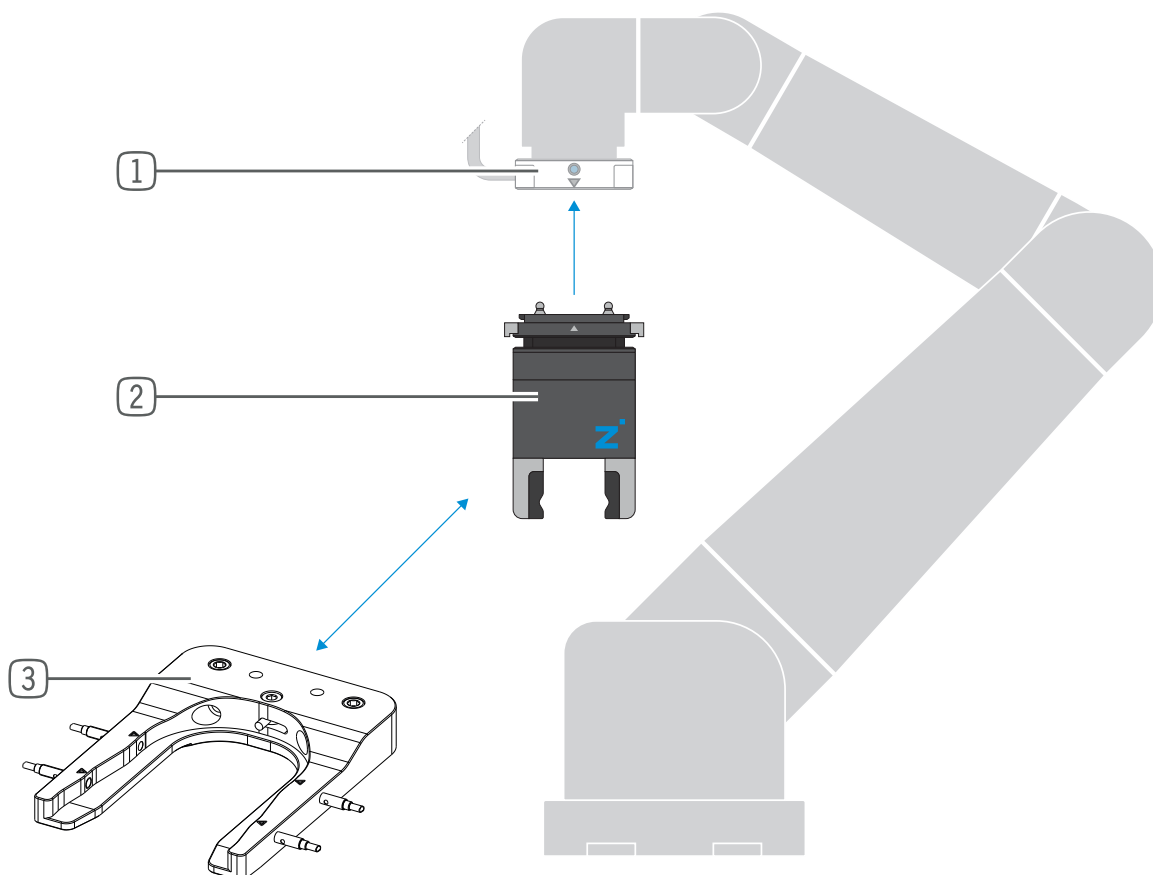
The product is a safe quick-change system (end effector with loose part).

The basic and proven safety principles from DIN EN 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 Stationary part (LWR50F-XX)
- ② End effector with loose part (LWR50L-XX)
- ③ Storage station (ALWR1-50-A) (sensors optional)

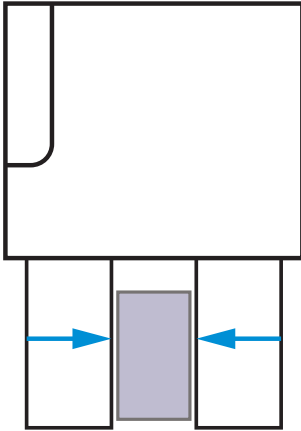
For the overall safety of the function, all three components (stationary part, end effector with loose part, and storage station) must be taken into account (see "Functional Safety" section).



### 5.1 Possible applications

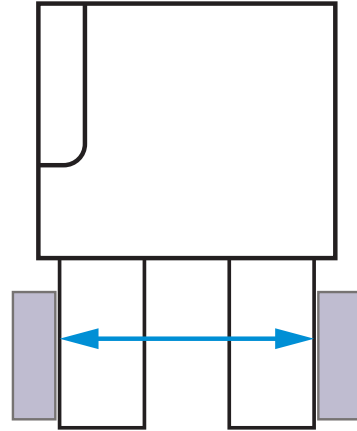
#### outside gripping

The product can be used for outside gripping.



#### inside gripping

The product can be used for inside gripping.



### 5.2 Forces and torques

#### INFORMATION



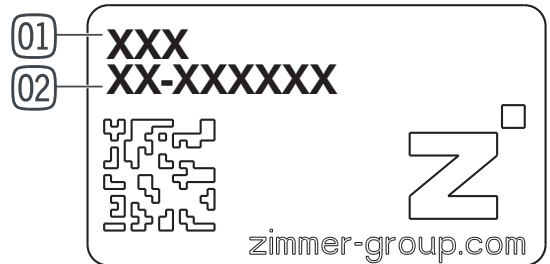
- ▶ You can find the information in the technical data sheet on our website.
- ▶ Please contact Zimmer Customer Service if you have any questions.

### 5.3 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.

- ① Article number
- ② Confirmation number



### 5.4 Product variants and compatibility

#### INFORMATION



- ▶ You can find information about product variants and their compatibility on our website.
- ▶ Please contact Zimmer Customer Service if you have any questions.

## 5.5 Use in applications

The criteria listed below justify the suitability of the product for use in collaborative applications:

- The product has been designed in accordance with the specifications of ISO/TS 15066.
- The power of the motor in combination with the transmission design and the pre-assembled gripper jaws is not sufficient to generate a gripping force > 140 N upon vulnerable areas of the body.
- The gripping forces generated when gripping soft objects are significantly reduced, since the amount of dynamic force is lowered. Compliance with the maximum permitted gripping force has been verified using a suitable measuring instrument.
- The product is engineered to be inherently safe and is designed with rounded edges and shapes that prevent crushing and shearing points from being created.

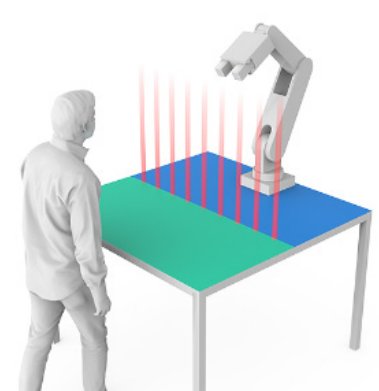
### Automation cell

Separated workspaces



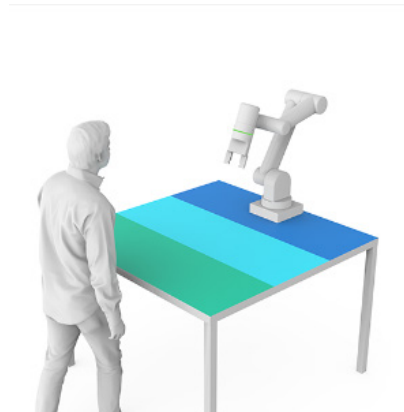
### Coexistence

Detection of presence



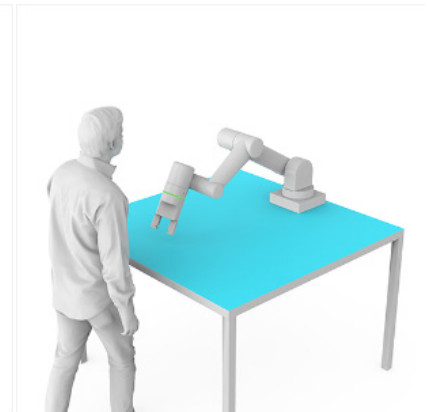
### Cooperation

Zones of action



### Collaboration

Shared workspaces



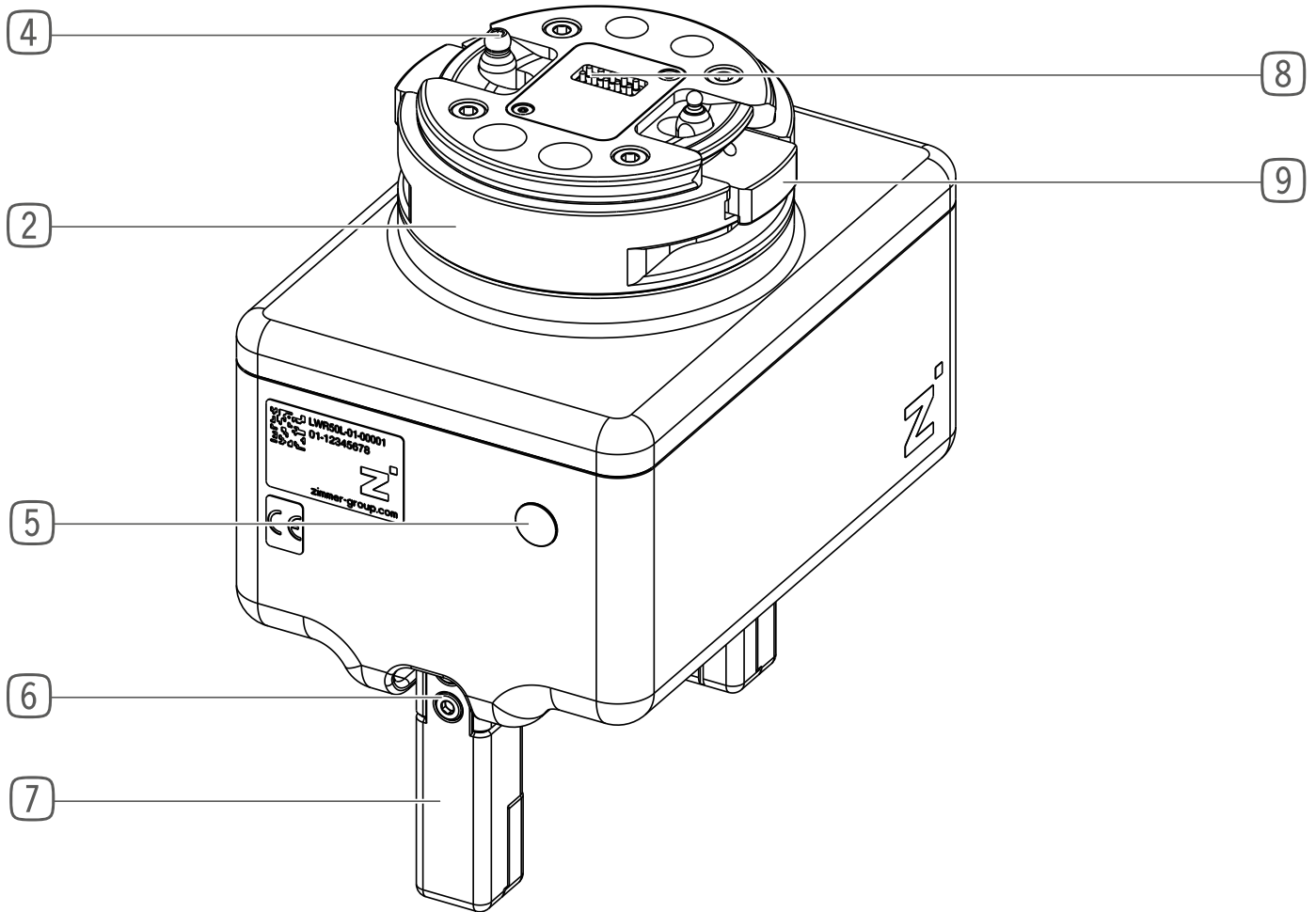
## 6 Functional description

An electric motor uses a gearbox to transfer torque to the gripper jaws. This results in the jaw movement and gripping force.

- Simple data exchange with the higher-level control system via IO-Link
- Brushless DC servomotor with an absolute encoder system
- The gripper jaws run on parallel guide rails arranged side by side.
- The gripper jaws are mechanically coupled to each other.

The product is equipped with a hot-plug function, which allows for the replacement of an end effector with loose part while electrically live.

The end effector with loose part is designed in such a way that incorrect insertion into the storage station is impossible.



- |  |                       |
|--|-----------------------|
| ② End effector with loose part for quick-change system | ⑦ Gripper jaw         |
| ④ Rotation prevention/torque absorption                | ⑧ Signal transmission |
| ⑤ Emergency release                                    | ⑨ Locking             |
| ⑥ Removable centering sleeve                           |                       |

## 6.1 LED status display

### INFORMATION



- ▶ For information on the LED display, refer to the installation and operating instructions of the fixed part on our website.
  - LWR50F

The LED display is optionally available on the fixed part.

## 6.2 Sensors

Example image of a combination consisting of a stationary part, end effector with loose part, and storage station.

Check up to two sensors in the storage position to see whether the end effector with loose part is present in the storage station.

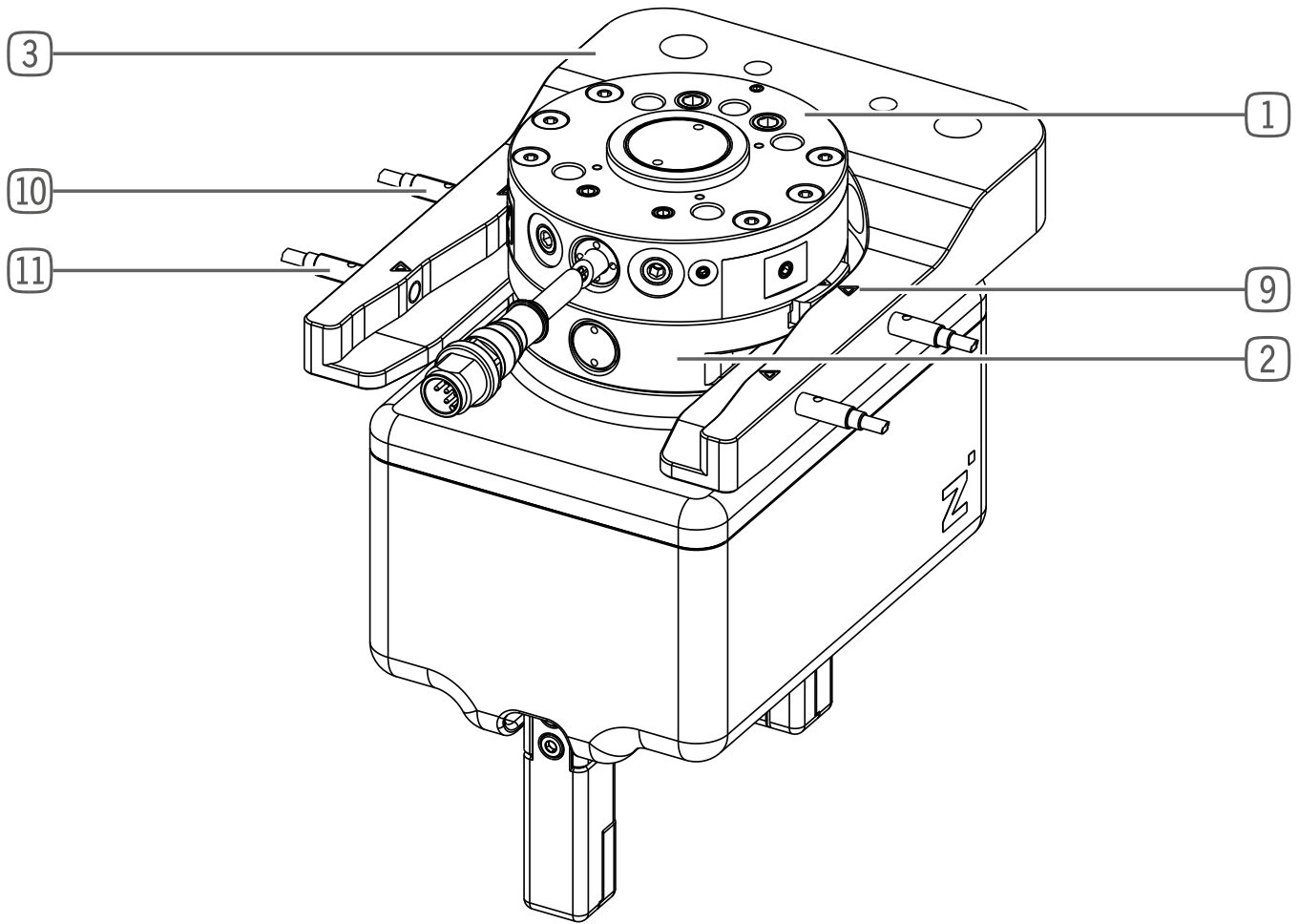
Then move the stationary part onto the end effector with loose part from above. The centering pins of the end effector with loose part help in insertion.

The robot, along with the stationary part and end effector with loose part, moves to the inspection position sensors in the storage station.

The two sensors in the inspection position (test channel) respond if the lockings are extended and make contact in the stationary part.

When the stationary part and end effector with loose part are joined, the internal spring-pin contacts for signal transmission are contacted.

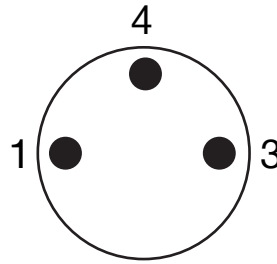
Then the Connect LED changes color from red to green and a Connect signal (depending on the variant) is passed to the higher-level control system.



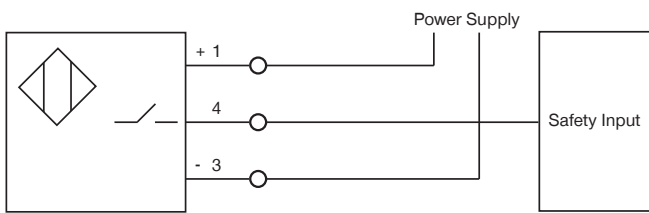
- |  |   |
|--|---|
| ① Fixed part for quick-change system                   | ⑨ Locking   |
| ② End effector with loose part for quick-change system | ⑩ Sensor in storage position (end effector with loose part present) |
| ③ Storage station                                      | ⑪ Sensor in inspection position (test channel, locking extended)    |

**6.2.1 Wiring diagram sensor system**

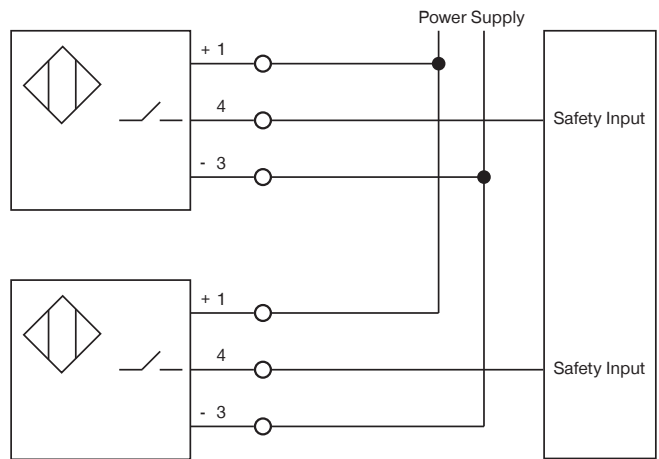
Sensor plug connection M8 3-pin:



**Graphical symbol for sensor in storage position**



**2 sensors in inspection position connected in series**



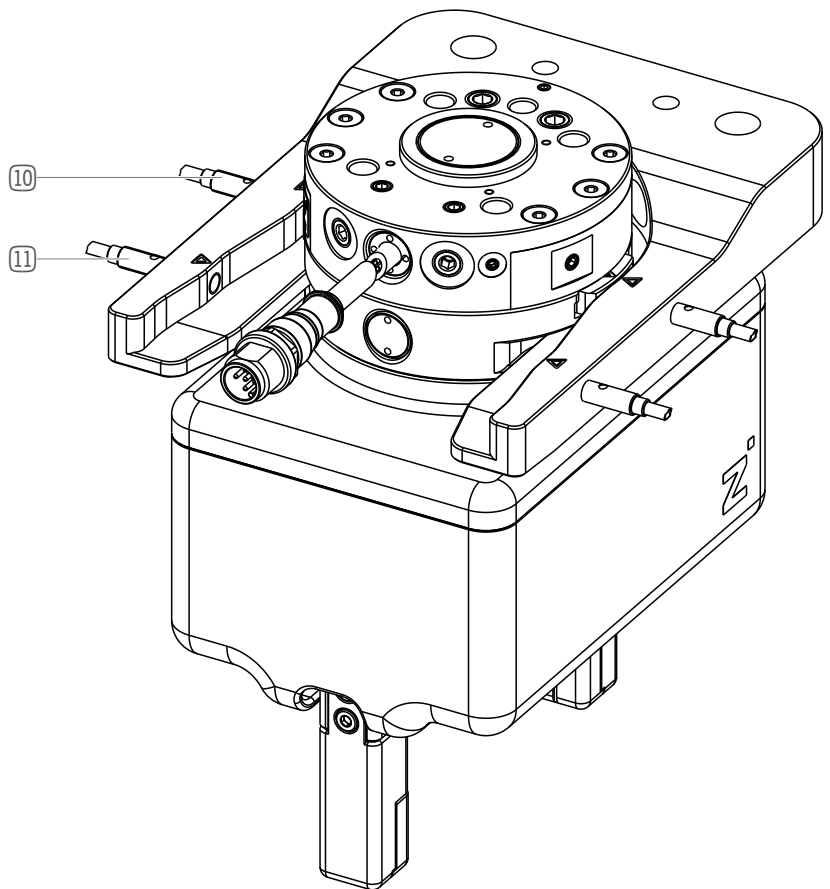
**6.2.2 Adjust the sensors in the inspection position**

- ▶ Bring the markings on the locking elements of the end effector with loose part to the position of the front markings of the storage station.
- ▶ Turn in the sensors until they emit a signal.
- ▶ Fasten the sensors at this position.
- ▶ Coat the sensors with sealing lacquer.

**6.2.3 Adjust the sensors in the storage position**

- ▶ Position an end effector with loose part in the storage station.
- ▶ Turn in the sensors until they emit a signal.
- ▶ Coat the sensors with sealing lacquer.

- ⑩ Sensor in storage position (end effector with loose part present)
- ⑪ Sensor in inspection position (test channel, locking extended)



### 6.3 Functional safety

For the overall safety of the function, all three components (stationary part, end effector with loose part and storage station) must be taken into account.

The safety function that ensures secure locking between the stationary part and end effector with loose part 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.

### 6.4 Control

#### INFORMATION



- ▶ You can find the information in the technical data sheet on our website.
- ▶ Please contact Zimmer Customer Service if you have any questions.

### 6.5 Verified configuration examples

#### INFORMATION



- ▶ You can find the information in the technical data sheet on our website.
- ▶ Please contact Zimmer Customer Service if you have any questions.



## 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 Zimmer Customer Service if you have any questions.

### 7.1 Electrical specifications

#### 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 Zimmer Customer Service if you have any questions.

### 7.2 Protection class

#### NOTICE



The product achieves protection class IP40 in all mounted positions of installation.

## 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

- ▶ Transport and storage of the product must be done only with the 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/observe and adhere to the temperature range.
  - ▶ Avoid wind/drafts/water condensation formation.
  - ▶ Cover the product with a weatherproof, tear-resistant foil to prevent dust.
  - ▶ 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.
- ▶ Properly remove potential corrosion spots.
- ▶ 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 unintentional switch-on.
- ▶ Check the machine for any residual energy.
- ▶ 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.

#### 10.1 Installing the product

Fasten the product on the stationary part. No assembly work is necessary for the product. The end effector is already connected to the loose part.

### INFORMATION



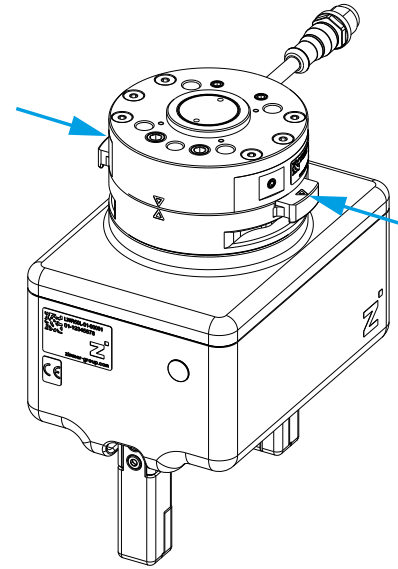
- ▶ For information, refer to the installation and operating instructions of the fixed part on our website.
  - LWR50F

### 10.1.1 Installing the stationary part and end effector with loose part

Example image of a combination consisting of a stationary part, end effector with loose part, and storage station.

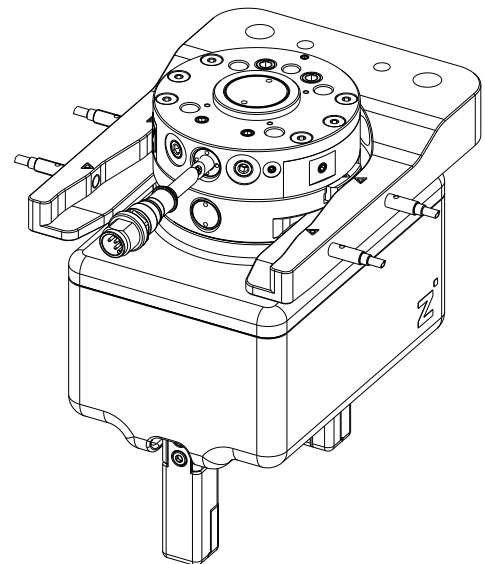
#### Manual exchange:

The end effector with loose part can be installed on the fixed part and locked manually.



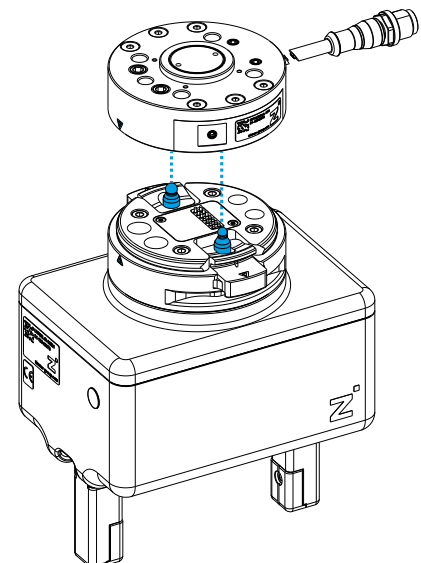
#### Automatic exchange:

The stationary part is moved to the end effector with loose part in the storage station and locked by means of the storage station (see "Sensors" section).



#### Rotation prevention:

The design rules out incorrect joining, as the end effector with loose part is equipped with two different bolts.



## 10.2 Installing the energy supply

### NOTICE



Installation of voltage supply is done internally. This means that the end effector with loose part is equipped with internal contacts. These contacts transmit all signals.

- ▶ 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.

## 10.3 Installing the sensors

### NOTICE



- ▶ For more information please refer to the "Sensors" section.
- ▶ Please contact Zimmer Customer Service if you have any questions.

## 10.4 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.

The movement of the gripper jaws creates low voltages as a result of static charging. These charges cannot be dissipated if the product is mounted on an insulating surface and if discharge is also not possible through the workpiece.

## 10.5 Installing accessories

### NOTICE



- Before installing an accessory, make sure it is suitable for use with the selected variant.
- ▶ Please contact Zimmer Customer Service if you have any questions.

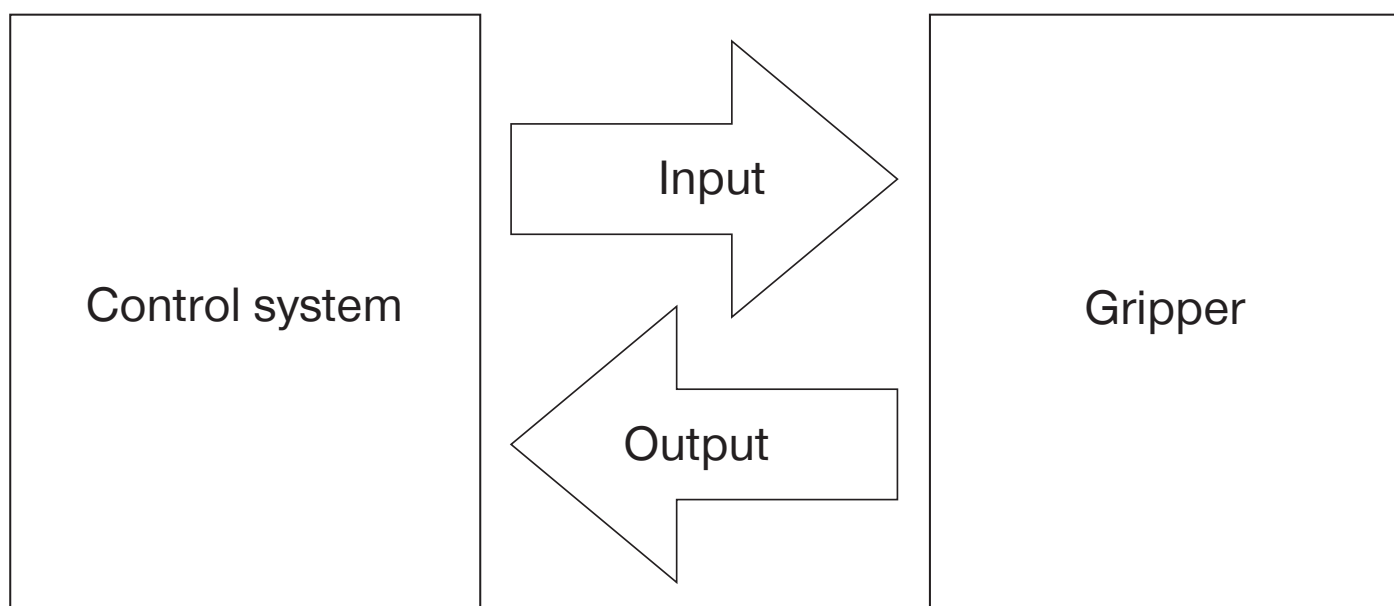
## 11 Commissioning

### 11.1 Process data

There is an option to control the product only with the process data that is transmitted in each cycle.

Outputs: Process data from the IO-Link master to the product!

Name	Data type
ControlWord	UINT16
DeviceMode	UINT8
WorkpieceNo	UINT8
Reserve	UINT8
PositionTolerance	UINT8
GripForce	UINT8
DriveVelocity	UINT8
BasePosition	UINT16
ShiftPosition	UINT16
TeachPosition	UINT16
WorkPosition	UINT16



Name	Data type
StatusWord	UINT16
Diagnosis	UINT16
ActualPosition	UINT16

## 11.2 IODD Import

- ▶ Import the IODD (device description) into the control system.
  - ▶ Go to our website.
  - ▶ Select the desired product.
  - ▶ Download the corresponding .zip file via the Download IODD link.
- ⇒ You will need the .zip file for import into the control system.
- ⇒ As soon as the hardware configuration is complete and the IO-Link connection to the product is established, data will be displayed in the process input data.
- ⇒ Some control systems demand a byte swap to bring this process data into a logical sequence.
- ▶ Look at bit 6 (GripperPLCActive) in the StatusWord to determine whether a byte swap is necessary.
  - ▶ Determine whether bit 6 is active in the first or second byte of the StatusWord.
    - ⇒ Bit 6 is active in the first byte: The bytes already have the correct sequence.
      - ▶ Continue with the commissioning.
    - ⇒ Bit 6 is active in the second byte.
      - ▶ Apply a byte swap, refer to the "StatusWord" section.

### INFORMATION



The product is controlled via IO-Link by means of the cyclical process data as well as the acyclic service data with a cycle time of 10 ms.

- ▶ It is mandatory to verify the process data!

## 11.3 Handshake Data Transfer Method

The handshake method makes it possible to transfer the process data about the product. All process data described in the following sections must be transferred with the handshake.

- ▶ Send the ControlWord = 0x0001 to the product.
- ⇒ The data transfer was started.
- ▶ Check the response of the product by using Statusbit 12 = TRUE (data transfer OK).
- ▶ Send the ControlWord = 0x0000 to stop the data transfer.
- ⇒ The data transmission is complete when the product sends back Statusbit 12 = DataTransferOK = FALSE.

### INFORMATION



- ▶ For examples, refer to the "Quickstart Basic Parameters" section.

## 11.4 Parameters

### 11.4.1 ControlWord

#### NOTICE



In the ControlWord parameter, only one single bit or the value 0 may be set at a time. Only the values listed in the following table are valid.

Parameter	Decimal value	Hexadecimal value
DataTransfer	1	0x0001
WritePDU	2	0x0002
ResetDirectionFlag	4	0x0004
Teach	128	0x0080
MoveToBase	256	0x0100
MoveToWork	512	0x0200
JogToWork +	1024	0x0400
JogToBase -	2048	0x0800

Name	ControlWord
Data format	UINT16
Permission	Write
Transfer	Cyclical
Value range	0 ... 65535

	Bit 15	Bit 14	Bit 13	Bit 12	Bit 11	Bit 10	Bit 9	Bit 8
Byte 1	ErrorReset	-	-	-	JogToBase	JogToWork	MoveToWork	MoveToBase
	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
Byte 0	-	-	-	-	Teach	ResetDirectionFlag	WritePDU	DataTransfer

#### Bit 0: DataTransfer

When this bit is set, the product accepts the data transferred in the process data.

#### Bit 1: WritePDU

Setting this bit tells the product that it should write the current process data to the selected workpiece recipe.

#### Bit 2: ResetDirectionFlag

Setting this bit tells the product that the direction flag needs to be reset. This makes a repeated movement to a position possible. This is logical during a switchover of workpiece recipes.

#### Bit 7: Teach

Setting this bit tells the product to save the current position as the TeachPosition in the selected WorkpieceNo. This only works if there is no "0" that is transmitted in the workpiece number.

**Bit 8: MoveToBase**

Setting this bit tells the product to move toward the BasePosition.

**Bit 9: MoveToWork**

Setting this bit tells the product to move toward the WorkPosition.

**Bit 10: JogToWork**

Setting this bit in the ControlWord puts the product in jog mode and slowly moves it toward the WorkPosition. If the bit is reset, the product stops.

**Bit 11: JogToBase**

Setting this bit in the ControlWord puts the product in jog mode and slowly moves it toward the BasePosition. If the bit is reset, the product stops.

**11.4.2 DeviceMode**

Name	DeviceMode
Data format	UINT8
Permission	Write
Transfer	Cyclical
Value range	0 ... 256

**Basic commands**

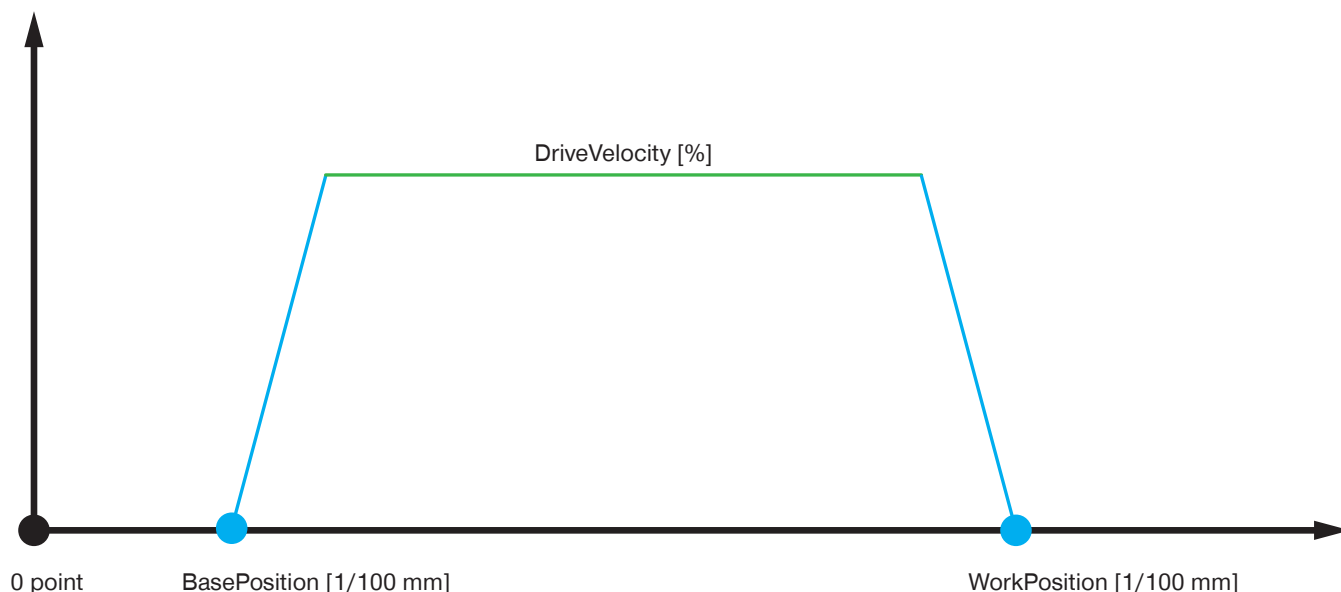
These modes control the basic product actions.

DeviceMode	Action	ControlWord
0	Not sent to the motor control system.	dc
1	Idle	0x0001
2	Gripper reset	0x0001
3	Switch on the motor.	0x0001
5	Switch off motor/stop gripping movement.	0x0001
10	Start homing (necessary only if the product was moved without a voltage supply).	0x0001
11	Activate jog mode.	0x0400/0x0800



### 11.4.3 Movement profiles

#### 11.4.3.1 PositionProfile



This mode is used to move the product into the PositionProfile.

The movement speed is configured using the DriveVelocity parameter.

The TeachPosition does not have any significance in this mode, because the BasePosition or WorkPosition is always approached precisely.

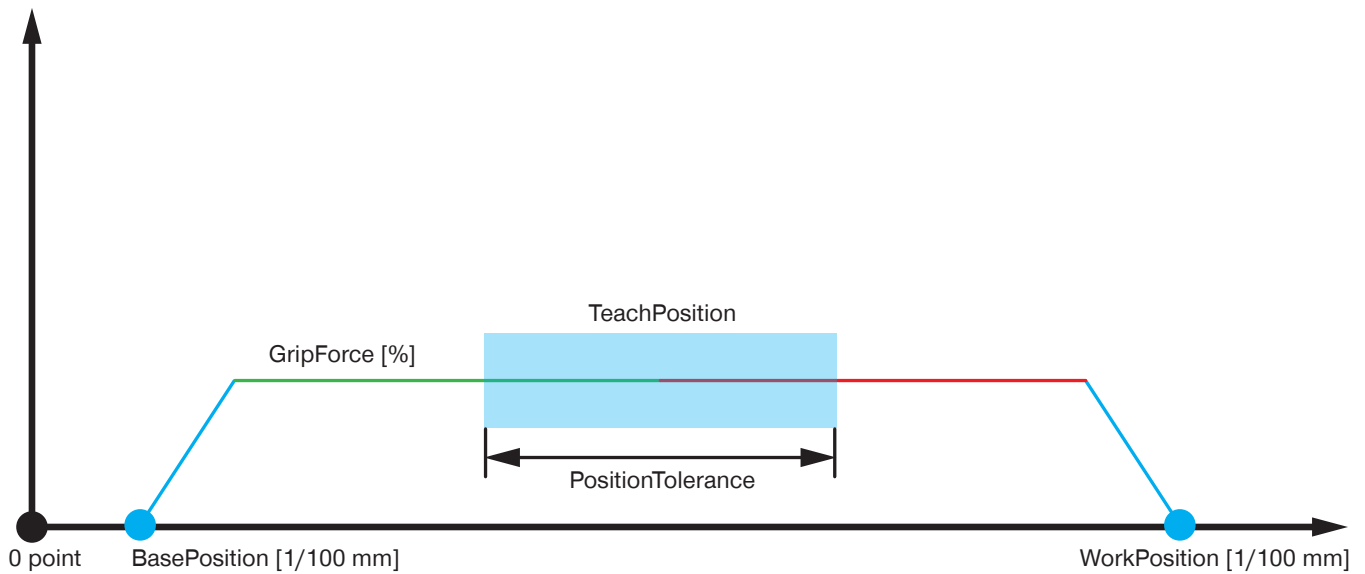
If the product encounters an obstacle in this mode while moving, it stops and issues an error message.

The product can be moved from the obstacle back to the starting position if the command is switched in the ControlWord.

No defined gripping forces can be generated in this mode. As a result, friction-locked gripping is not permitted in this mode.

DeviceMode	Action	ControlWord
50	Move to the BasePosition.	0x0100
50	Move to the WorkPosition.	0x0200
51	Move to the BasePosition. Special movement profile for a faster movement of the product. The product must never be jammed, i.e. neither be stopped at the end stop nor have gripped a workpiece.	0x0100
51	Move to the WorkPosition. Special movement profile for a faster movement of the product. The product must never be jammed, i.e. neither be stopped at the end stop nor have gripped a workpiece.	0x0200

### 11.4.3.2 ForceProfile



In this mode, the product moves onto the workpiece in the ForceProfile.

GripForce is used to configure the desired gripping force.

TeachPosition is used to define the position of the workpiece.

Since gripping typically only occurs in one direction, there is a distinction made between the two mode groups 62 and 72.

In Mode Group 62, the product in the ForceProfile moves from the BasePosition toward the WorkPosition onto the workpiece with ControlWord 0x0200.

If the ControlWord 0x0100 is written in Mode Group 62, then the product moves away from the workpiece to the BasePosition in the PositionProfile without the need for any prompts from the user. Here, the gripper moves at the speed set in the DriveVelocity parameter.

This procedure is reversed in the Mode Group 72. Mode Group 62 is therefore used for outside gripping and the Mode Group 72 for inside gripping.

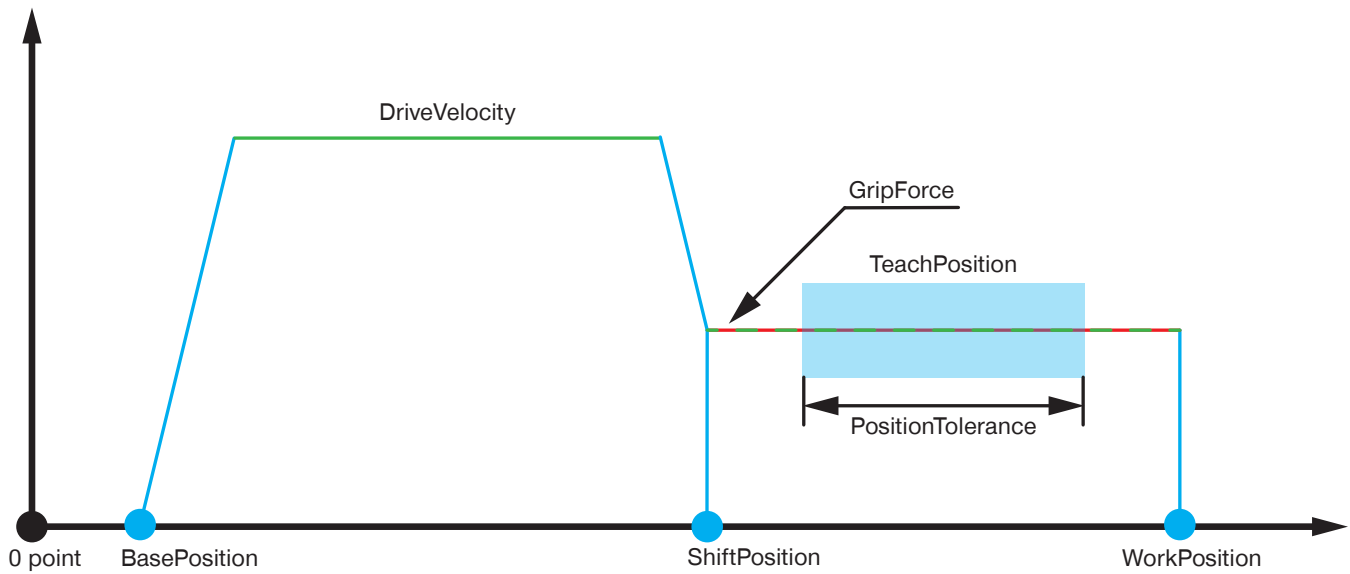
#### Mode Group 62 – typically used for outside gripping

DeviceMode	Action	ControlWord
62	Move toward the WorkPosition until this position or the workpiece is reached.	0x0200
62	Move toward the BasePosition to open the product.	0x0100

#### Mode Group 72 – typically used for inside gripping

DeviceMode	Action	ControlWord
72	Move toward the WorkPosition until this position or the workpiece is reached.	0x0100
72	Move toward the BasePosition to open the product.	0x0200

### 11.4.3.3 PrePosition-ForceProfile



This mode is an extension of the ForceProfile. This means that a typically quick prepositioning process occurs until the ShiftPosition is reached.

When it reaches the ShiftPosition, the product switches over to the ForceProfile without stopping the motor. Therefore, the BasePosition, ShiftPosition and WorkPosition have to be defined for ForceProfile.

The DriveVelocity and GripForce parameters also have to be configured.

Here, the TeachPosition also defines the workpiece position with adjustable tolerance.

Just as in the ForceProfile, the product moves away from the workpiece using the PositionProfile at the speed specified with the DriveVelocity parameter.

#### Mode Group 82 – typically used for outside gripping

DeviceMode	Action	ControlWord
82	Move with $v = \text{DriveVelocity}$ to the ShiftPosition and then with GripForce until the workpiece or the WorkPosition is reached.	0x0200
82	Move toward the BasePosition to open the product.	0x0100

#### Mode Group 92 – typically used for inside gripping

DeviceMode	Action	ControlWord
92	Move with $v = \text{DriveVelocity}$ to the ShiftPosition and then with GripForce until the workpiece or the BasePosition is reached.	0x0100
92	Move toward the WorkPosition for opening the product.	0x0200

### 11.4.4 WorkpieceNo

The workpiece number is used for selecting the previously stored workpiece data, as well as for selecting the WorkpieceNo data record in which the current process data is stored.

WorkpieceNo enables individual workpieces to be taught in to the product very quickly if the recipes are not managed on the control system.

#### INFORMATION



For example codes, refer to the "Quickstart Basic Parameters" and "Recipe Examples" sections.

Name	WorkpieceNo
Data format	UINT8
Permission	Write
Transfer	Cyclical
Value range	0 ... 32

At a value > 0, the corresponding workpiece recipe is loaded in the product.

### 11.4.5 PositionTolerance

Used to configure the position tolerance with a resolution of 0.01 mm.

Thus, the value range of 0 to 255 can be used to set a maximum tolerance of 2.55 mm in both directions.

#### INFORMATION



Example:

For TeachPosition 1500 (15.00 mm), PositionTolerance 150 lets you configure a tolerance of 1.50 mm in both directions.

This means that the TeachPosition range starts at 13.50 mm and goes all the way up to 16.50 mm.

Name	PositionTolerance
Data format	UINT8
Permission	Write
Transfer	Cyclical
Value range	0 ... 255

### 11.4.6 GripForce

The product can use various gripping forces for an optimized process sequence. The gripping force is indicated as a percent from the minimum to the maximum gripping force. The user can transmit the required gripping force in increments of 1%.

#### INFORMATION



When the product reaches 100% gripping force, it switches to a higher maximum permitted peak current.

This means that, in the range of 100% to 130%, the product can draw a maximum current of 7.5 A for a brief period.

Name	GripForce
Data format	UINT8
Permission	Write
Transfer	Cyclical
Value range	1 ... 100 %

### 11.4.7 DriveVelocity

The product can work at various movement speeds for an optimized process sequence.

This parameter determines the movement speed of the product in both directions in PositionProfile.

In the other modes, this parameter determines the movement speed from the workpiece.

In PrePosition-ForceProfile mode, it determines the movement speed to the switching position.

The positioning speed is specified as a percentage value (1% to 100%). The product converts this information to its maximum movement speed.

#### INFORMATION



Example:

To set a movement speed of 75%, a value of 75 (DriveVelocity = 75) must be transmitted.

Name	DriveVelocity
Data format	UINT8
Permission	Write
Transfer	Cyclical
Value range	1 ... 100 %

### 11.4.8 BasePosition

The BasePosition defines the target position in the MoveToBase direction. It must always be less than the ShiftPosition.

The product verifies this and, if necessary, displays an error message.

If the current position of the product within the tolerance range is in the vicinity of the BasePosition, bit 8 is set in the StatusWord.

Name	BasePosition
Data format	UINT16
Permission	Write
Transfer	Cyclical
Value range	0.75 to max. jaw stroke of the product + 0.75 mm

#### 11.4.9 ShiftPosition

The ShiftPosition must always be larger than the BasePosition and smaller than the WorkPosition. The product verifies this and, if necessary, displays an error message.

Name	ShiftPosition
Data format	UINT16
Permission	Write
Transfer	Cyclical
Value range	0.75 to max. jaw stroke of the product + 0.75 mm

#### 11.4.10 TeachPosition

The TeachPosition defines the target position of the workpiece and its use is optional. If the current position of the product within the tolerance range is around the TeachPosition, bit 9 is set in the Status. The size of the tolerance range is defined using the PositionTolerance parameter.

Name	TeachPosition
Data format	UINT16
Permission	Write
Transfer	Cyclical
Value range	0.75 to max. jaw stroke of the product + 0.75 mm

#### 11.4.11 WorkPosition

The WorkPosition defines the maximum travel path of the product and has to be greater than the ShiftPosition. In the PositionProfile, this position is precisely approached because the product is in positioning mode. In the PrePosition-ForceProfile or ForceProfile modes, the product is stopped, starting from this position. The product will move past the WorkPosition slightly. A maximum of 2 mm, depending on the movement speed and gripper finger dimensions. A maximum of 2 mm, depending on the movement speed and gripper finger dimensions. For DeviceMode 70/90, the same applies for the BasePosition.

Name	WorkPosition
Data format	UINT16
Permission	Write
Transfer	Cyclical
Value range	0.75 to max. jaw stroke of the product + 0.75 mm

## Outputs: Process data from the product to the IO-Link master

### 11.4.12 StatusWord

StatusWord structure:

	Bit 15	Bit 14	Bit 13	Bit 12	Bit 11	Bit 10	Bit 9	Bit 8
Byte 1	Error	ControlWord 0x0200	ControlWord 0x0100	"DataTransferOK"	"Undefined- Position"	WorkPo- sition	TeachPo- sition	BasePo- sition
	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
Byte 0	Control- lerError	Gripper- PLCActive	JogWork- Active +	JogBase- Active -	Movement- Complete	InMotion	MotorON	HomingPo- sition OK

#### Bit 0: HomingPosition OK

The product has its reference. This bit is mandatory. If the bit is FALSE, a reference run must be carried out. Refer to "Referencing by Homing" section.

#### Bit 1: MotorON

This bit is active when the motor is switched on by the DeviceMode = 3 (decimal) parameter. The motor is automatically switched on during a Homing run (DeviceMode 10 (decimal)).

#### Bit 2: InMotion

This bit is active during the run.

#### Bit 3: MovementComplete

This bit is active after the movement is complete.

#### Bit 4: JogBaseActive -

Confirmation during the Jog run in the direction of BasePosition.

#### Bit 5: JogWorkActive +

Confirmation during the Jog run in the direction of WorkPosition.

#### Bit 6: GripperPLCActive

Active as soon as the product has booted up after the cold boot. This bit can be used to verify a "byte swap."

#### Bit 7: ControllerError

Error in the controller.

#### Bit 8: BasePosition

Active if the product is set to BasePosition.

#### Bit 9: TeachPosition

Active if the product is set to TeachPosition.

#### Bit 10: WorkPosition

Active if the product is set to WorkPosition.

**Bit 11: UndefinedPosition**

Active if the product is not set to TeachPosition, WorkPosition or BasePosition.

**Bit 12: DataTransferOK**

This bit is used for data transmission using the handshake. Active as soon as the product has taken over the data using the parameter ControlWord = 1 (decimal).

**Bit 13: ControlWord 0x0100**

This bit is a direction flag. Active if the last motion task was carried out toward BasePosition.

**Bit 14: ControlWord 0x0200**

This bit is a direction flag. Active if the last motion task was carried out toward WorkPosition.

**Bit 15: Error**

Active if the product has an active error. The error message can be determined using Diagnosis.

**11.4.13 Diagnosis**

The value returned in Diagnosis corresponds to the error code (see "Error Diagnosis" section).

Name	Diagnosis
Data format	UINT16
Permission	Read
Transfer	Cyclical
Value range	0 ... 65535

**11.4.14 ActualPosition**

ActualPosition corresponds to the current position of the gripper jaws relative to the full stroke.

The value is specified with a resolution of 0.01 mm.

Name	ActualPosition
Data format	UINT16
Permission	Read
Transfer	Cyclical
Value range	0 to max. jaw stroke of the product

**INFORMATION**



- ▶ The ActualPosition of the product should be used to check whether a workpiece has been gripped correctly.
  - The position measurement resolution is 0.01 mm.
  - The position measurement accuracy is 0.1 mm.
- ▶ If the ActualPosition is used to detect the workpiece, then fluctuations around the exact value must be taken into account during commissioning.



### 11.5 Cold start

For proper function, Zimmer GmbH recommends that the actuator and sensor voltage be supplied with power separately. The sensor supply must be switched on first.

As soon as the product is communicating with the PLC, the actuator power supply can be switched on. Depending on the application, simultaneous activation of both voltages is also possible.

#### INFORMATION



If the sensor supply is disconnected, the C/Q signal (IO-Link) must be disconnected as well.

### 11.6 Minimum travel path

The product requires a certain minimum travel path to move to the desired position.

The minimum travel path depends on the desired gripping force and the dimensions of the gripper fingers.

Design size	Minimum travel path per gripper jaw [mm]
LWR50L-02 series	3

### 11.7 Referencing by Homing

#### NOTICE



► Before each homing command, make sure that the product is able to move freely and easily and that it cannot be blocked by the gripper jaws or interfering edges.

When blocking, the reference position is set. A Homing command is not permitted in the gripped state.

There are various Homing commands available.

#### NOTICE

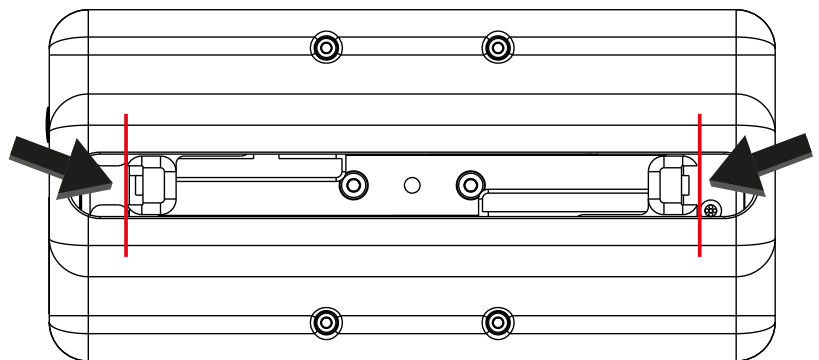


DeviceModes 16 and 17 are not valid for products with safety gripper jaws!

DeviceMode	Action
10	Outside homing – to the internal end stop of the product (see "DeviceMode 10" section)
14	Inside homing – to the internal end stop of the product (see "DeviceMode 14" section)
16	Special outside homing – to the external end stop (see "DeviceMode 16" section)
17	Special inside homing – to the external end stop (see "DeviceMode 17" section)

The product has reached its zero position if the gripper jaws are at the pictured position when referencing (Homing DeviceMode 10).

Depending on installation size, the gripper jaws move slightly beyond the edge of the gripper housing when moving to home position (Homing).



### 11.7.1 DeviceMode 10

- ▶ Assign "DeviceMode 10.
- ▶ Transmit this value to the product with a handshake.
  - The motor can be switched on or off.

#### WARNING



#### Risk of injury due to uncontrolled movements

Transmitting the value might cause the product to move.

- ▶ Always keep an adequate safety distance.
- ▶ Do not reach into the operational range of the product.

- ⇒ The gripper jaws move to the outside at low speed until they encounter the internal mechanical end stops.
- ⇒ If the gripper jaws encounter resistance, they stop at this spot.
  - ⇒ In the process, the ActualPosition is referenced to the value of 0.
- ⇒ The motor is switched on.

### 11.7.2 DeviceMode 14

- ▶ Assign DeviceMode 14.
- ▶ Transmit this value to the product with a handshake.
  - The motor can be switched on or off.

#### WARNING



#### Risk of injury due to uncontrolled movements

Transmitting the value might cause the product to move.

- ▶ Always keep an adequate safety distance.
- ▶ Do not reach into the operational range of the product.

- ⇒ The gripper jaws move to the inside at low speed until they encounter the internal mechanical end stops.
- ⇒ If the gripper jaws encounter resistance, they stop at this spot.
  - ⇒ In the process, the ActualPosition is referenced to the maximum jaw stroke of the product.
- ⇒ The motor is switched on.

### 11.7.3 DeviceMode 16

**WARNING**



**Risk of injury due to increased force of the product during homing**

The product force during the reference run is very high with the new DeviceMode.

- ▶ Make sure that an external end stop is installed in the machine or system into which the product is being installed.
- ⇒ If the internal end stop of the product is used, this will result in higher wear.

- ▶ Set the DriveVelocity to a low value before starting homing.
  - Recommendation: DriveVelocity **10**
  - ▶ Increase the value if a higher force is required for homing.
- ▶ Assign DeviceMode 3.
- ▶ Transmit this value to the product with ControlWord 1.
- ⇒ The motor is switched on.
- ▶ Transmit the following values.

Parameter	Value	Unit
DeviceMode	16	-
WorkpieceNo	0	-
PositionTolerance	50	0.01 mm
DriveVelocity	<b>10</b>	%
BasePosition	<b>100</b>	0.01 mm
WorkPosition	4000	0.01 mm

- ▶ Transmit the parameters to the product with a handshake.
  - ControlWord 1
  - BasePosition must not be smaller than 75.
- ⇒ The gripper jaws move outward until they are stopped by an external end stop or the maximum jaw position.
  - ⇒ The product takes over the BasePosition value as the new ActualPosition.
- ⇒ For example, this would be the new ActualPosition **100** (see table).
- ⇒ After homing, the motor is switched off.
  - ▶ Switch the motor on using DeviceMode 3 and the handshake.
  - ▶ Change the movement profile.
  - ▶ Start the operation.
- ⇒ The product responds with DiagnosisWord 0x0000.
  - ⇒ The product is ready.

**WARNING**



**Product jamming and damage**

Since the ActualPosition in this DeviceMode has an offset, the product does not know the position of the internal end stop.

- ⇒ This makes it possible to move against the internal end stop at high speed, which can result in jamming of and damage to the product.

### 11.7.4 DeviceMode 17

**WARNING**



**Risk of injury due to increased force of the product during homing**

The product force during the reference run is very high with the new DeviceMode.

- ▶ Make sure that an external end stop is installed in the machine or system into which the product is being installed.
- ⇒ If the internal end stop of the product is used, this will result in higher wear.

- ▶ Set the DriveVelocity to a low value before starting homing.
  - Recommendation: DriveVelocity **10**
  - ▶ Increase the value if a higher force is required for homing.
- ▶ Assign DeviceMode 3.
- ▶ Transmit this value to the product with ControlWord 1.
- ⇒ The motor is switched on.
- ▶ Transmit the following values.

Parameter	Value	Unit
DeviceMode	17	-
WorkpieceNo	0	-
PositionTolerance	50	0.01 mm
DriveVelocity	<b>10</b>	%
BasePosition	100	0.01 mm
WorkPosition	<b>4000</b>	0.01 mm

- ▶ Transmit the parameters to the product with a handshake.
  - ControlWord 1
  - WorkPosition must not be greater than 75.
- ⇒ The gripper jaws move inward until they are stopped by an external end stop or the maximum jaw position.
  - ⇒ The product takes over the WorkPosition value as the new ActualPosition.
- ⇒ For example, this would be the new ActualPosition **4000** (see table).
- ⇒ After homing, the motor is switched off.
  - ▶ Switch the motor on using DeviceMode 3 and the handshake.
  - ▶ Change the movement profile.
  - ▶ Start the operation.
- ⇒ The product responds with DiagnosisWord 0x0000.
  - ⇒ The product is ready.

**WARNING**



**Product jamming and damage**

Since the ActualPosition in this DeviceMode has an offset, the product does not know the position of the internal end stop.

- ⇒ This makes it possible to move against the internal end stop at high speed, which can result in jamming of and damage to the product.

### 11.8 Interruption of the power supply

During an interruption of the voltage supply (e.g. when using a tool changer), make absolutely sure that the product stores the last position in the controller.

- ▶ Carry out a handshake before switching off the power supply.
  - ▶ Use a timer to delay the shutoff of the power supply by 2 seconds.
- ⇒ This ensures that no change of position occurs during a restart.

#### INFORMATION



For example codes, refer to the "Quickstart Basic Parameters" and "Recipe Examples" sections.

### 11.9 Easy Startup

Describes the process from switching on the product to the initial movement.

- ▶ Connect the product according to its assignment diagram.
- ⇒ The product reports the process parameters StatusWord, Diagnosis and ActualPosition immediately after the internal controller is booted up.
- ⇒ As soon as the PLCActive bit is registered in the StatusWord, the communication process can start.
- ▶ Transmit the process parameters to move the product.
    - DeviceMode
    - WorkpieceNo
    - PositionTolerance
    - GripForce
    - DriveVelocity
    - BasePosition
    - ShiftPosition
    - TeachPosition
    - WorkPosition
  - ▶ Transmit the parameters to the product with a handshake.

#### INFORMATION



▶ For information and an example code for the handshake, refer to the "Quickstart Basic Parameters" and "Recipe Examples" sections.

### 11.10 Starting the data transfer

- ▶ Start the data transmission with the ControlWord = 1 (decimal).
- ⇒ As soon as the process parameter has been transmitted to the product, the product will report this back in the StatusWord with the DataTransferOK bit.
- ⇒ The product is ready to operate.

#### INFORMATION



▶ For information about data transfers, refer to the "StatusWord" section.

### 11.11 Quickstart Basic Parameters

In the following example, you see the first initialization of the product, the activation of the motor and the transmission of the process parameters.

```
// Initialization of the product
// Motor switch-on
// Initial move command
// = EasyStartUp Example

5:
  IF StatusBit.6 THEN                // Query for PLCActive bit in the StatusWord
    ControlWord := 1;                // Sends the DataTransfer bit in the ControlWord for initialization
    iStep := 10;                     // Jump to the next step
  END_IF

10:
  IF StatusBit.12 THEN               // Query for DataTransferOK bit in the StatusWord
    ControlWord := 0;                // Reset of the initialization
    iStep := 20;                     // Jump to the next step
  END_IF

20:
  DeviceMode := 3;                   // Command to switch on the motor
  ControlWord := 1;                  // Data transfer to the product
  iStep := 30;                       // Jump to the next step

30:
  IF StatusBit.1 THEN                // Query for the MotorON bit in the StatusWord
    iStep := 40;                     // Jump to the next step
  END_IF

40:
  DeviceMode := 82;                  // Loading a DeviceMode
  WorkpieceNo := 0;                  // 0 = current process parameters are being used
  PositionTolerance := 50;
  GripForce := 50;
  DriveVelocity := 50;
  BasePosition := 100;
  ShiftPosition := 2000;
  TeachPosition := 4000;
  WorkPosition := 4000;
  iStep := 50;                       // Jump to the next step

50:
  ControlWord := 1;                  // Begins with the handshake
  iStep := 60;                       // Jump to the next step

60:
  IF StatusWord.12 THEN              // Queries the bit DataTransferOK=TRUE from StatusWord,
    // Response of the product to transferred data
    ControlWord := 0;                // Reset the ControlWord
    iStep := 70;                     // Jump to the next step
  END_IF;

70:
  IF StatusWord.12 THEN              // Query for completion of the data transfer,
    // DataTransferOK = FALSE
    ControlWord := 512;              // Handshake is completed,
    // Product moves to WorkPosition (0x0200 or 512(decimal) = MoveToWork)
    iStep := 80;                     // Jump to the next step
  END_IF;

80:
  ...
```

### 11.12 Starting the gripping movement

- ▶ Send ControlWord 0x0200 so that the product moves towards the WorkPosition.
- ⇒ The gripper jaws move towards the inside.
- ▶ Send ControlWord 0x0100 so that the product moves towards the BasePosition.
- ⇒ The gripper jaws move towards the outside.
  - The motion task must be pending for as long as it takes until the desired position is reached.
  - The current motion task is canceled as a result of a new handshake.
- ⇒ When the product reaches the corresponding position, this is displayed in the StatusWord as follows:
  - The product is at the BasePosition: StatusWord bit 8 = TRUE
  - The product is at the TeachPosition: StatusWord bit 9 = TRUE
  - The product is at the WorkPosition: StatusWord bit 10 = TRUE

### 11.13 Repeated movements in the same direction

The StatusWord includes two static flag bits, each of which is set in alternation when the product moves in one direction. This prevents uncontrolled movements of the product in case of faulty data transmission.

Depending on the location of the positions, it is possible that the product may move multiple times in the same direction. For this purpose, the direction flags must be reset.

- ▶ Send the ControlWord = 0x0004 to delete the direction flags.
- ⇒ The direction flags are reset when the product answers with status bit 13 AND 14 = FALSE.

Program example for repeated movements in the same direction:

```
// Multiple movement in one direction in Structured Text (ST)
// In this example, the motor is switched on,
// The movement profile
// Transfer gripping forces and speeds
// The product is at BasePosition = 1000.

10:
    BasePosition      := 100;    // Assignment of a new BasePosition
    ControlWord       := 1;     // Start handshake (DataTransfer bit =TRUE in the ControlWord)
    iStep             := 20;    // Jump to the next step

20:
    IF StatusWord.12 THEN          // Queries the bit DataTransferOK=TRUE from StatusWord,
                                   // Response of the product to transferred data
        ControlWord       := 0;    // Reset the ControlWord
        iStep             := 30;    // Jump to the next step
    END_IF;

30:
    IF StatusWord.12 THEN          // Query for completion of the data transfer,
                                   // DataTransferOK = FALSE
        ControlWord       := 4;    // Reset direction flag
                                   // (DataTransfer bit =TRUE in the ControlWord)
        iStep             := 40;
    END_IF;

40:
    IF NOT StatusWord13 AND NOT   // Query whether both direction flags
    StatusWord14 THEN             // (Bit ControlWord 0x0100 AND
                                   // ControlWord 0x0200 = FALSE in ControlWord)
        ControlWord       := 256;  // Moves back toward BasePosition
        iStep             := 50;
    END_IF;

50:
...

```

## 11.14 Recipe examples

### 11.14.1 Save recipe

The following example code shows how process parameters can be stored in the internal workpiece recipe.

// Store tool workpiece recipes in Structured Text (ST)

```

10:
    DeviceMode           := 82;    // Assignment of desired process parameters
    WorkpieceNo          := 3;     // Recipe is to be stored as the third workpiece recipe
    PositionTolerance    := 50;
    GripForce            := 50;
    DriveVelocity         := 50;
    BasePosition         := 100;
    ShiftPosition        := 2000;
    TeachPosition        := 4000;
    WorkPosition         := 4000;
    iStep                := 20;    // Jump to the next step

20:
    ControlWord          := 1;     // Begins with the handshake
    iStep                := 30;    // Jump to the next step

30:
    IF StatusWord.12 THEN          // Queries the bit DataTransferOK=TRUE from StatusWord,
                                   // Response of the product to transferred data
        ControlWord            := 0; // Reset the ControlWord
        iStep                  := 40; // Jump to the next step
    END_IF;

50:
    IF StatusWord.12 THEN          // Queries the DataTransferOK = TRUE bit from StatusWord
        ControlWord            := 0; // Reset the ControlWord
        iStep                  := 60; // Jump to the next step
    END_IF;

60:
    IF NOT StatusWord.12 THEN      // Query for completion of the data transfer,
                                   // DataTransferOK = FALSE
        // Do other things...      // Storage is completed
    END_IF;
  
```



### 11.14.2 Loading a recipe

The following example code shows how process parameters can be loaded to the internal workpiece recipe.

```
// Load workpiece recipes in Structured Text (ST)
```

```
10:      WorkpieceNo      := 3;      // Load third workpiece recipe
        iStep           := 20;     // Jump to the next step

20:      ControlWord     := 1;      // Begins with the handshake
        iStep           := 30;     // Jump to the next step

30:      IF StatusWord.12 THEN      // Queries the bit DataTransferOK=TRUE from StatusWord,
                                   // Response of the product to transferred data
        ControlWord     := 0;      // Reset the ControlWord
        iStep           := 40;     // Jump to the next step
      END_IF;

40:      IF NOT StatusWord.12 THEN  // Query for completion of the data transfer,
                                   // DataTransferOK = FALSE
        // Do other things...      //Handshake is completed,
                                   // Parameters from the third recipe have been taken over into the current process parameters.
      END_IF;
```

## 12 Operation

### NOTICE



In the event of a power failure, the gripper jaws remain in their positions and the gripping force of the product stays constant.

The gripper jaws can be opened using the emergency release if the energy supply drops off.

► Please contact Zimmer Customer Service if you have any questions.

### 12.1 Adjustable gripping force

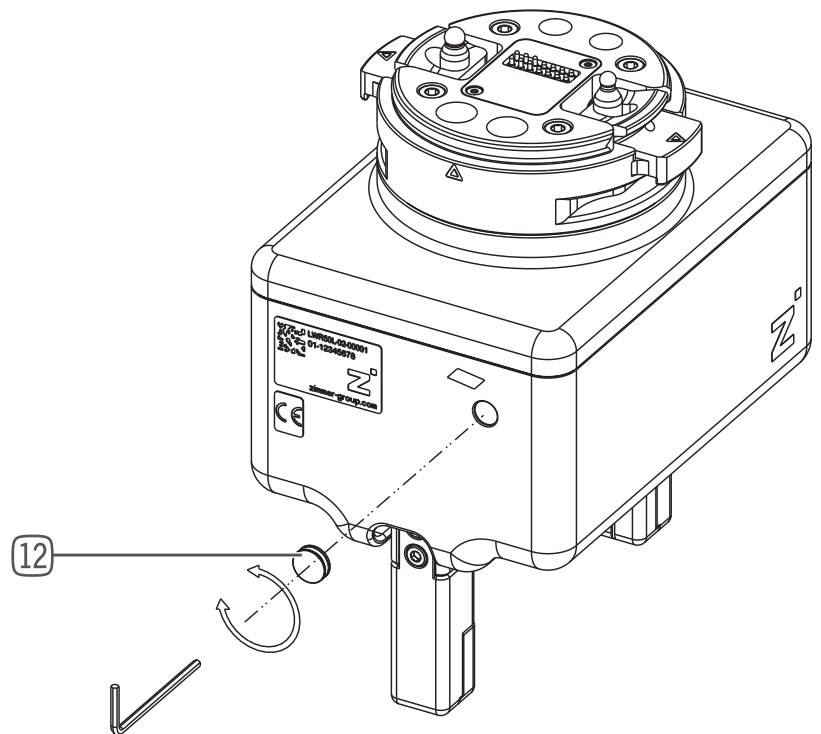
For the IO-Link variant, you can adjust the gripping force conveniently by using the control system.

### 12.2 Emergency release

The product features an emergency release that can be mechanically opened with an Allen key in the event of a power failure.

► Remove the protective cap to reach the emergency release.

Design size	Wrench size [mm]
LWR50L-02 series	2



12 Protective cap

### INFORMATION



- Carry out another reference run after any emergency release.
- Please contact Zimmer Customer Service if you have any questions.

## 13 Gripping force charts

### INFORMATION



- You can find information on our website.
- Please contact Zimmer Customer Service if you have any questions.

## 14 Error diagnosis

Error code	Error	Possible cause	Measure
0x0000	Device is ready for operation.	-	-
0x0001	Motor controller is switched off.	<ul style="list-style-type: none"> <li>Motor controller has not yet been activated.</li> <li>Motor controller has been switched off.</li> <li>Motor controller was switched off for device protection.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Switch on the motor controller.</li> </ul>
0x0100	Actuator power supply is not present or is too low.	<ul style="list-style-type: none"> <li>Actuator power supply is not connected</li> <li>Actuator power supply is not sufficient</li> <li>Cable break</li> <li>STO input circuit is interrupted.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Check the actuator power supply.</li> <li>▶ Switch on the STO input circuit.</li> </ul>
0x0101	Temperature above maximum permitted temperature.	<ul style="list-style-type: none"> <li>Ambient temperature is too high.</li> <li>Overload of the products.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Provide sufficient ventilation/cooling/connection.</li> <li>▶ Check that the product moves freely.</li> </ul>
0x0102	Max. permitted temperature undershot.	<ul style="list-style-type: none"> <li>Ambient temperature is too low.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Provide an adequate operating temperature.</li> </ul>
0x0206	Motion task cannot be executed (CRC error).	<ul style="list-style-type: none"> <li>Internal error</li> </ul>	<ul style="list-style-type: none"> <li>▶ Apply the process data via a handshake.</li> <li>▶ Please contact Zimmer Customer Service.</li> </ul>
0x0300	ControlWord is not plausible.	<ul style="list-style-type: none"> <li>Multiple bits were set in the ControlWord.</li> </ul>	<ul style="list-style-type: none"> <li>▶ In the ControlWord, check that only one bit is set.</li> </ul>
0x0301	Positions are not plausible.	<ul style="list-style-type: none"> <li>Transmitted positions are not plausible.</li> <li>Modified process data were not taken over.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Check the transmitted process data.</li> <li>▶ Apply the process data via a handshake.</li> </ul>
0x0302	GripForce is not plausible.	<ul style="list-style-type: none"> <li>Transmitted GripForce is not plausible.</li> <li>Modified process data were not taken over.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Check the transmitted process data.</li> <li>▶ Apply the process data via a handshake.</li> </ul>
0x0303	DriveVelocity is not plausible.	<ul style="list-style-type: none"> <li>Transmitted DriveVelocity is not plausible.</li> <li>Modified process data were not taken over.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Check the transmitted process data.</li> <li>▶ Apply the process data via a handshake.</li> </ul>
0x0304	PositionTolerance is not plausible.	<ul style="list-style-type: none"> <li>Transmitted PositionTolerance is not plausible.</li> <li>Modified process data were not taken over.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Check the transmitted process data.</li> <li>▶ Apply the process data via a handshake.</li> </ul>
0x0305	Position measuring system not referenced.	<ul style="list-style-type: none"> <li>Position measuring system is not referenced.</li> <li>A reference run is being performed.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Reference the product.</li> <li>▶ Wait until the reference run is complete.</li> </ul>

Error code	Error	Possible cause	Measure
0x0306	DeviceMode is not plausible.	<ul style="list-style-type: none"> <li>Transmitted DeviceMode is not plausible.</li> <li>Modified process data were not taken over.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Check the transmitted process data.</li> <li>▶ Apply the process data via a handshake.</li> </ul>
0x0307	Motion task cannot be executed.	<ul style="list-style-type: none"> <li>Multiple motion tasks in the same direction. <ul style="list-style-type: none"> <li>In DM6x, MoveToWork if ActualPosition &gt; WorkPosition</li> <li>In DM7x, MoveToBase if ActualPosition &lt; BasePosition</li> <li>In DM8x, MoveToWork if ActualPosition &gt; ShiftPosition</li> <li>In DM9x, MoveToBase if ActualPosition &lt; ShiftPosition</li> </ul> </li> </ul>	<ul style="list-style-type: none"> <li>▶ Reset the direction flag. <ul style="list-style-type: none"> <li>▶ Send the move command again.</li> </ul> </li> <li>▶ Position the product correctly before gripping.</li> </ul>
0x0308	WorkpieceNo cannot be selected.	<ul style="list-style-type: none"> <li>Transmitted workpiece number is outside the permitted range.</li> <li>Modified process data were not taken over.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Check the transmitted process data.</li> <li>▶ Apply the process data via a handshake.</li> </ul>
0x0313	Calculated ShiftPosition exceeded.	<ul style="list-style-type: none"> <li>Start position is not permitted for the selected motion task.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Move to the BasePosition with DeviceMode 60.</li> <li>▶ Move to the WorkPosition with DeviceMode 70.</li> </ul>
0x0402	Jam	<ul style="list-style-type: none"> <li>Gripper jaws are blocked.</li> <li>Gripper jaws are tensioned incorrectly.</li> </ul>	<ul style="list-style-type: none"> <li>▶ Check that the product moves freely.</li> <li>▶ Send a motion task in the opposite direction.</li> </ul>
0x0404	Position sensor error	<ul style="list-style-type: none"> <li>Fault of the integrated position sensor</li> </ul>	<ul style="list-style-type: none"> <li>▶ Reference the product with a homing command.</li> <li>▶ Please contact Zimmer Customer Service.</li> </ul>
0x0406	Internal error	<ul style="list-style-type: none"> <li>Internal error</li> </ul>	<ul style="list-style-type: none"> <li>▶ Please contact Zimmer Customer Service.</li> </ul>
0x040B	Internal error	<ul style="list-style-type: none"> <li>Internal error</li> </ul>	<ul style="list-style-type: none"> <li>▶ Please contact Zimmer Customer Service.</li> </ul>
0x040C	Internal error	<ul style="list-style-type: none"> <li>Internal error</li> </ul>	<ul style="list-style-type: none"> <li>▶ Please contact Zimmer Customer Service.</li> </ul>
0x040D	Internal error	<ul style="list-style-type: none"> <li>Internal error</li> </ul>	<ul style="list-style-type: none"> <li>▶ Please contact Zimmer Customer Service.</li> </ul>
0x040E	Internal error	<ul style="list-style-type: none"> <li>Internal error</li> </ul>	<ul style="list-style-type: none"> <li>▶ Please contact Zimmer Customer Service.</li> </ul>
0x040F	Internal error	<ul style="list-style-type: none"> <li>Internal error</li> </ul>	<ul style="list-style-type: none"> <li>▶ Please contact Zimmer Customer Service.</li> </ul>

## 15 Table with acyclic data (ISDU)

### INFORMATION



IO-Link distinguishes between cyclical process data (PDU) and acyclic data (ISDU).

Access to acyclic data is not arranged very conveniently for all control system and IO-Link master combinations. For this reason, the product can be used without acyclic data. This makes it as easy as possible to control the product.

Zimmer Customer Service is available to provide you with assistance if you have any further questions.

Index	Name	Data format	Access rights	Values	Description
0x0064 (64)	Status	UINT16	Read	0 ... 65535	Reflection of the process data
0x0041 (65)	Diagnosis	UINT16	Read	0 ... 65535	Reflection of the process data
0x0042 (66)	Cycle counter	UINT32	Read	0 ... 4294967295	Current numbers of cycles
0x0043 (67)	Temperature	UINT16	Read	0 ... 100 °C	Current temperature
0x0044 (68)	ControlWord	UINT16	Read	0 ... 65535	Reflection of the process data
0x0045 (69)	Error code	STRING	Read	1 ... 32	Current error code
0x0046 (70)	Error counter	UINT32	Read	0 ... 4294967295	Current error counter
0x0100 (256)	Actual position	UINT16	Read	0 to max. jaw stroke of the product	Reflection of the process data
0x0101 (257)	TeachPosition	UINT16	Read	0 to max. jaw stroke of the product	Reflection of the process data
0x0102 (258)	WorkpieceNo	UINT8	Read	0 ... 32	Reflection of the process data
0x0103 (259)	DeviceMode	UINT8	Read	1 ... 95	Reflection of the process data
0x0104 (260)	PositionTolerance	UINT8	Read	0 ... 255	Reflection of the process data
0x0105 (261)	GripForce	UINT8	Read	1 ... 130 %	Reflection of the process data
0x0107 (263)	DriveVelocity	UINT8	Read	1 ... 100 %	Reflection of the process data
0x0108 (264)	BasePosition	UINT16	Read	0 to max. jaw stroke of the product	Reflection of the process data
0x0109 (265)	ShiftPosition	UINT16	Read	0 to max. jaw stroke of the product	Reflection of the process data
0x010A (266)	WorkPosition	UINT16	Read	0 to max. jaw stroke of the product	Reflection of the process data

## 16 Maintenance

### CAUTION



**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.

### CAUTION



**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.

Maintenance-free operation of the tool changer (end effector with loose part) is guaranteed for up to **100,000 change cycles** (hot plug).

Maintenance-free operation of the gripper is guaranteed for up to **5 million cycles**.

The maintenance interval may be shortened under the following circumstances:

- Dirty environment
  - Improper use and use that does not comply with the power specifications.
  - Ambient temperature is too high.
  - ▶ 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 be performed by Zimmer Customer Service whenever 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.

## 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:** 2-jaw parallel gripper with quick-change system

**Type designation:** LWR50L-02 series

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

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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:** 2-jaw parallel gripper with quick-change system

**Type designation:** LWR50L-02 series

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:

Nr.1.1.2, Nr.1.1.3, Nr.1.1.5, Nr.1.3.2, Nr.1.3.4, Nr.1.3.7, Nr.1.5.3, Nr.1.5.4, Nr.1.5.8, Nr.1.6.4, Nr.1.7.1, Nr.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**

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77866 Rheinau, Germany  
☎ +49 7844 9138 0  
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🌐 [www.zimmer-group.com](http://www.zimmer-group.com)

We hereby declare that the products described below

**Product designation:** 2-jaw parallel gripper with quick-change system  
**Type designation:** LWR50L-02 series

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 12100:2011-03	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