

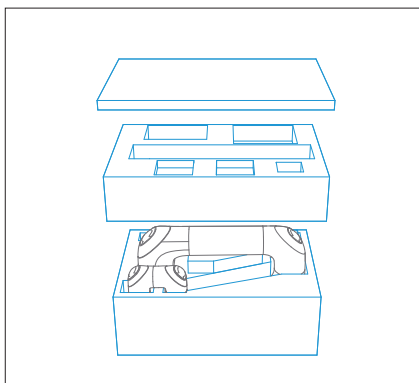
DOBOT CR 30H系列协作机器人快速安装说明



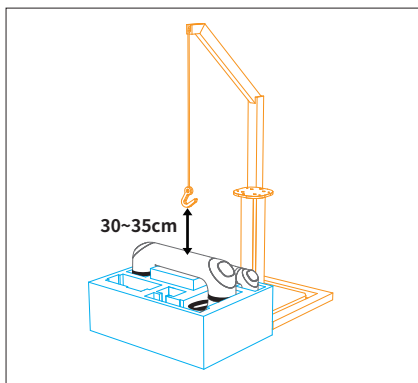
⚠ 注意

- ★ 请将机械臂安装于室内,通风良好且空气中无灰尘、油雾、油烟、盐分、铁屑、腐蚀性气体等。
- ★ 请勿在阳光照射、强电磁、可燃物附近、有切削液或磨削液的烟雾环境、过度振动和冲击的环境、或封闭环境下使用。
- ★ 必须将机械臂固定在足够结实的基座上,基座需要能够承受至少10倍的J1关节的最大扭矩,以及至少5倍机械臂的重量。
- ★ 吊装过程中,须安排专人在机械臂旁侧扶稳机身,直至机械臂底座的全部螺栓紧固完成。
- ★ 吊装过程中,禁止任何人员在机械臂下方停留或穿行。

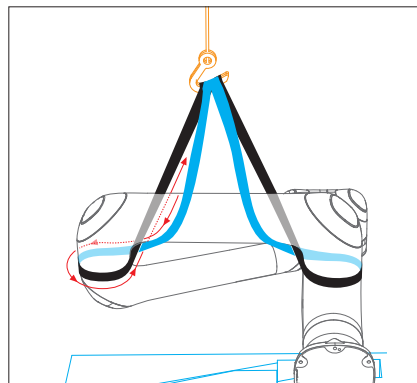
一.安装机械臂



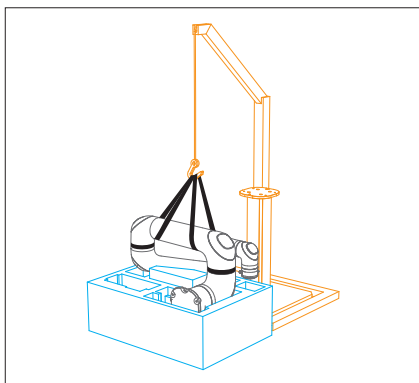
- 1 开箱后,对照发货清单检查内容物是否有遗漏。如有缺失,请联系您的供应商。



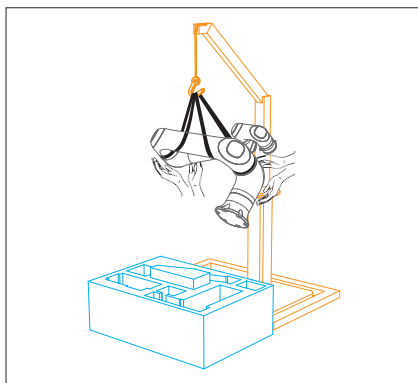
- 2 拆开包装箱内衬,移动吊机使挂钩对齐机械臂中轴线且距离机械臂约30~35cm。



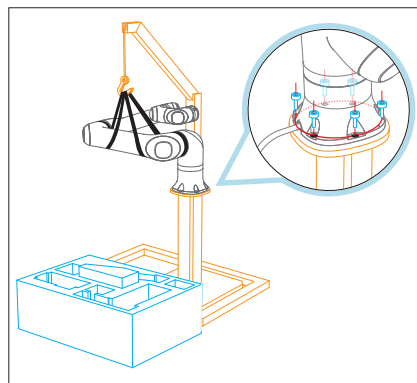
- 3 如图“8字绕线法”缠绕吊装带。



- 4 将机械臂上的吊装带挂在挂钩上。

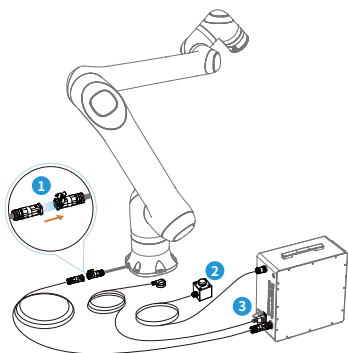


- 5 控制吊机缓慢升起机械臂,全程需有人员扶住机械臂。



- 6 将机械臂吊至安装平台,对准安装孔位后用6颗M10内六角螺栓拧紧固定机械臂。

二.系统接线



- 1 通过重载线连接控制柜与机械臂。

⚠ 注意

对于NSF机型,请将重载线的航插接头放置在密闭空间内,切勿直接暴露在食品生产环境中。

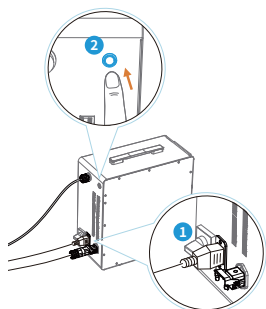
- 2 将急停开关线缆插入控制柜的急停开关接口。连接时将线缆接头上的白色点与接口上的白色点对齐插入,并顺时针旋转蓝色塑料环固定连接。
- 3 连接控制柜电源线至市电插座。



📖 说明

拆除重载线时,如果重载线插头卡扣太紧无法打开,可参考下图,使用内六角扳手抵住卡扣后用力推开。

三.开机使用



- 1 开启外部市电后,将控制柜的电源开关顺时针旋转90°接通控制柜电源。
- 2 按一下控制柜上方的圆形按钮后松开。

📖 说明

待机械臂末端和控制柜圆形按钮的指示灯都变为蓝色常亮后,测试急停按钮是否正常。然后可通过操作终端连接机械臂,使能并点动机械臂进行调试。具体操作方法请参考DobotStudioPro的用户手册。

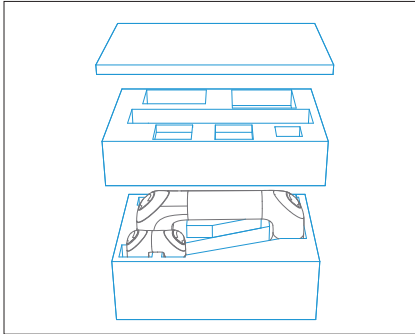
DOBOT CR 30H Collaborative Robot Quick Start

NOTICE

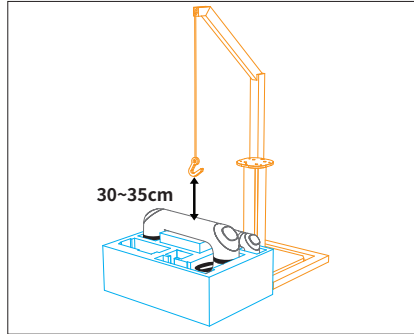
- ★ Ensure the robot arm is installed indoors in a well-ventilated area free of dust, oil mist, smoke, salt, metal shavings, and corrosive gases.
- ★ Do not use in environments with direct sunlight, strong electromagnetic fields, proximity to flammable materials, exposure to mist from cutting or grinding fluids, excessive vibration or impact, or in enclosed spaces.
- ★ The robot arm must be fixed to a sufficiently sturdy base, which needs to withstand at least 10 times the maximum torque of the J1 joint and at least 5 times the weight of the robot arm.
- ★ During the hoisting process, dedicated personnel must be arranged to steadily support the body of the robot arm from the side until all bolts of the base are fully tightened.
- ★ During the hoisting process, personnel are prohibited from staying or passing underneath the robot arm.



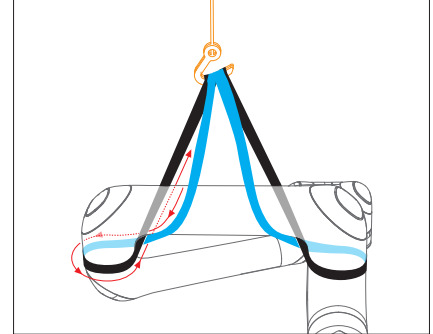
1. Robot Installation



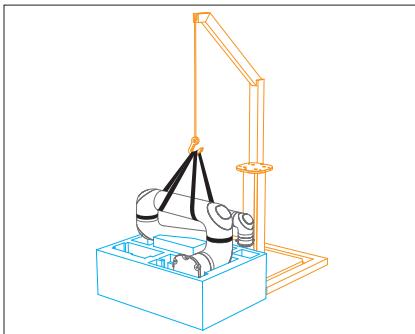
- 1 Upon unpacking, check the attached shipping list to ensure that all items are included. In case of any discrepancies, contact your supplier promptly.



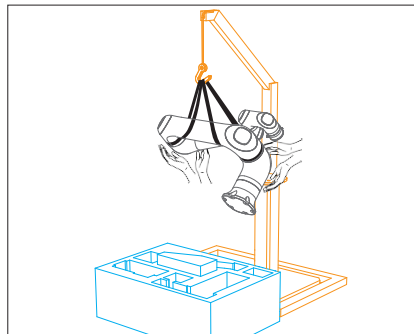
- 2 Remove the inner packaging liner, then move the hoist so that the hook aligns with the central axis of the robot arm and is positioned approximately 30~35 cm away from the arm.



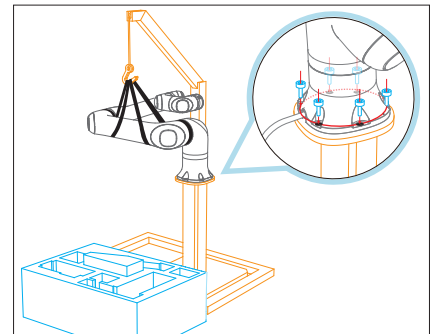
- 3 Wrap the sling using the "Figure-8 winding method" as described below.



- 4 Attach the slings of the robot arm onto the hook.

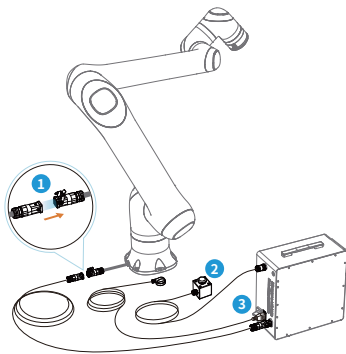


- 5 Control the hoist to slowly lift the robot arm. The robot arm must be supported by personnel throughout the entire process.



- 6 Lift the robot arm to the installation platform, align it with the holes, and securely fasten the robot in place using six M10 hex bolts.

2. System Wiring

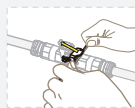


- 1 Connect the controller to the robot arm using a heavy-duty cable.

NOTICE

For the NSF model, ensure the heavy-duty cable's aviation connector is housed within an enclosed space and is not directly exposed to the food production environment.

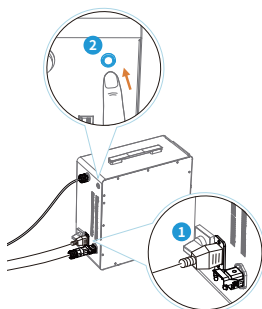
- 2 Connect the emergency stop switch cable to the emergency stop interface on the controller. When connecting, align the white dot on the connector with the white dot on the interface, then rotate the blue plastic ring clockwise to secure the connection.
- 3 Connect the controller power cable to a mains power outlet.



NOTE

When disconnecting the heavy-duty cable, if the latch of the heavy-duty plug is too tight to release, refer to the figure below. Use a hex wrench to press against the latch and firmly push it away.

3. Power On and Operation



- 1 After enabling the external mains power, rotate the power switch of the controller 90° clockwise to turn on the power to the controller.
- 2 Press and immediately release the round button on the top of the controller.

NOTE

Once the indicator lights on both the robot arm's end effector and the round button on the controller turn solid blue, test whether the E-stop button is functioning properly. The robot arm can then be connected via the operation terminal, enabled, and jogged for debugging purposes. For detailed operation instructions, refer to DobotStudio Pro User Guide.