

**Delta Robot  
CR\_UGD5 Series**

# **Delta Robot 5 Axes**

## **USER'S MANUAL**

**OMRON**



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## Safety Instructions

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# 1. Attention

Information in this document can change without prior notice.

OMRON EUROPE B.V. cannot be held responsible for any damage to the environment, to the machine or to the functioning of the machine occurred by errors or missing data in the illustrations, drawing or specifications.

No part of this manual and added documentation may be copied, reproduced or translated into another language without prior written approval.

Read and understand the material contained in this user's manual before you work on the CR\_UGD5 robot for the first time. This user's manual is supposed to help you use the capabilities of the CR\_UGD5 robot safely and properly.

## 2. Explanation of warnings and notes

This manual uses the following safety alert symbols and signal words to provide safety instructions that must be observed and to describe handling precautions, prohibited actions, and compulsory actions. Make sure you understand the meaning of each symbol and signal word and then read this manual.



### DANGER

THIS INDICATES AN IMMEDIATELY HAZARDOUS SITUATION WHICH, IF NOT AVOIDED, WILL RESULT IN DEATH OR SERIOUS INJURY.



### WARNING

THIS INDICATES A POTENTIALLY HAZARDOUS SITUATION WHICH, IF NOT AVOIDED, COULD RESULT IN DEATH OR SERIOUS INJURY.



### NOTE

Explains the key point in the operation in a simple and clear manner.

## 3. Safety information

### 3.1 General

This '3. Safety information' subchapter contains information regarding working with the CR\_UGD5 robot. Qualified personnel working with the CR\_UGD5 robot must have read and understood the CR\_UGD5 robot documentation, including the safety information chapter.

### 3.2 Qualified personnel

These are people who, due their specialist training, knowledge and experience, and their familiarization with the relevant standards, are able to assess the work to be carried out and detect any potential hazards.

### 3.3 Liability

The CR\_UGD5 robot is build using state-of-the-art technology and in accordance with the recognized safety rules. Nevertheless, misuse of the CR\_UGD5 robot may constitute a risk to life and limb or cause damage to the CR\_UGD5 robot and to other material property.

### 3.4 Installation and operating conditions

You may only use the components in accordance with the installation and operating conditions described in the documentation. The operating conditions at the installation location must be checked and maintained in accordance with the required technical data. Within the meaning of the Machinery Directive the CR\_UGD5 robot is an incomplete machine. Commissioning is prohibited until the usable machine or system in which the CR\_UGD5 robot is installed meets all requirements of the Machine directive 2006/42/EC.

For the CR\_UGD5 robot you have to observe the following standards, directives and regulations:

- EN ISO 10218-1:2011 Robots and robotic devices - Safety requirements for industrial robots - Part 1: Robots.
- EN ISO 10218-2:2011 Robots and robotic devices - Safety requirements for industrial robots - Part 2: Robot systems and integration.

### 3.5 Residual risks

Safety and health risks arising from the robot mechanics have been reduced by means of safety technology and design engineering. However a residual risk remains, since the robot mechanics will be move by an automated control system.

The following are typical warnings concerning residual risks which cannot be assigned to a specific action. The expression of safety labels is identical to the safety information.

### 3.5.1 Release device

The robot mechanics are not supplied with an release switch to control the brakes of the motors.



#### WARNING

- MOUNT A RELEASE SWITCH ON THE MACHINE SO THE ARMS (MOTOR) OF THE ROBOT COULD BE MANUALLY MOVED.
- MOVING AN AXIS WITH AN IMPROPERLY WORKING RELEASE SWITCH CAN DAMAGE THE MOTOR BRAKE. THIS CAN RESULT IN PERSONAL INJURY AND MATERIAL DAMAGE.
- BEFORE RELEASING THE BRAKE, YOU HAVE TO BE SURE THAT NO ONE IS IN THE HAZARD AREA OF THE ROBOT.

### 3.5.2 Transport

The prescribed transport position of the robot must be observed. Transportation must be carried out in accordance with the transportation instructions or assembly instructions of the robot.



#### WARNING

- ONLY USE AUTHORIZED HANDLING EQUIPMENT WITH A SUFFICIENT LOAD-BEARING CAPACITY TO TRANSPORT THE ROBOT.
- WEAR SUITABLE PROTECTIVE CLOTHING IF NECESSARY.

### 3.5.3 Assembly and start-up

Before starting up systems and devices for the first time, a check must be carried out to ensure that the system and devices are completed and operational, that they can be operated safely and that any damage is detected.

The valid national or regional work safety regulations must be observed for this check. The correct functioning of all safety circuits must also be tested.

The following tests must be carried out before start-up and recommissioning. It must be ensured that:

- The robot is correctly installed and fastened in accordance with the specifications in the assembly instructions.
- There are no foreign bodies or loose parts on the robot.
- All required safety equipment is correctly installed and operational.



#### WARNING

- A WRONG INSTALLED ROBOT MAY THROW OFF HIS ARMS.
- WEAR SUITABLE PROTECTIVE CLOTHING IF NECESSARY.

### 3.5.4 Maintenance and repair

After maintenance and repair work, checks must be carried out to ensure the required safety level. The valid national or regional work safety regulations must be observed for this check. The correct functioning of all safety circuits must also be tested.

The purpose of maintenance and repair work is to ensure that the system is kept original or, in the event of a fault, to return the system to an operational state. Repair work includes troubleshooting in addition to the actual repair itself.

The following safety measures must be carried out when working on the robot:

- Switch of the machine (system) where the robot is built-in (e.g. with a padlock) to prevent it from being switched on again
- Label the machine (system) with a sign indication that work is in progress. This sign must remain in place, even during temporary interruptions to the work.
- The emergency stop from the machine (system) must remain active. If safety functions or safeguards are deactivated during maintenance or repair work, they must be reactivated immediately after the work is completed.

### 3.5.5 System integrator

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The robot is safely integrated into a complete system by the system integrator. The system integrator is responsible for the following tasks:

- Installing the robot
- Performing risk assessment
- Implementing the required safety functions and safeguards
- Issuing the declaration of conformity
- Attaching the CE mark
- Creating the operating instructions for the complete system

# Chapter 1 Introduction

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# 1. Introduction

Congratulations with the purchase of your high speed Delta robot 5 axes.

This manual should be read before the commissioning of the robot. By mechanical engineers in the design phase during the integration of the robot in the machine and by software engineers to check the performance envelope of the robot.

This manual describes the main versions of the CR\_UGD5 robot, and all options. Where applicable check the appropriate data for your robot type, the type can be found on the identification tag of the robot.



## 1.1 Description of the robot

The CR\_UGD5 Delta robot is a high speed pick and place robot which uses state-of-the-art carbon composite materials and the latest servo drive technology to be put in use in the most demanding pick and place applications. The robot is designed as a 5-axis Delta kinematic system.

Characteristics of the robot:

- Requires very low maintenance
- 5 degrees of freedom
- Compact design for mounting in a machine
- Low noise level < 68 dB (A)

## 1.2 Type code explanation

CR\_UGD5\_XL: 5 axes, 1300 mm working range, max. payload: 1 kg

CR\_UGD5: 5 axes, 1100 mm working range, max. payload: 1 kg

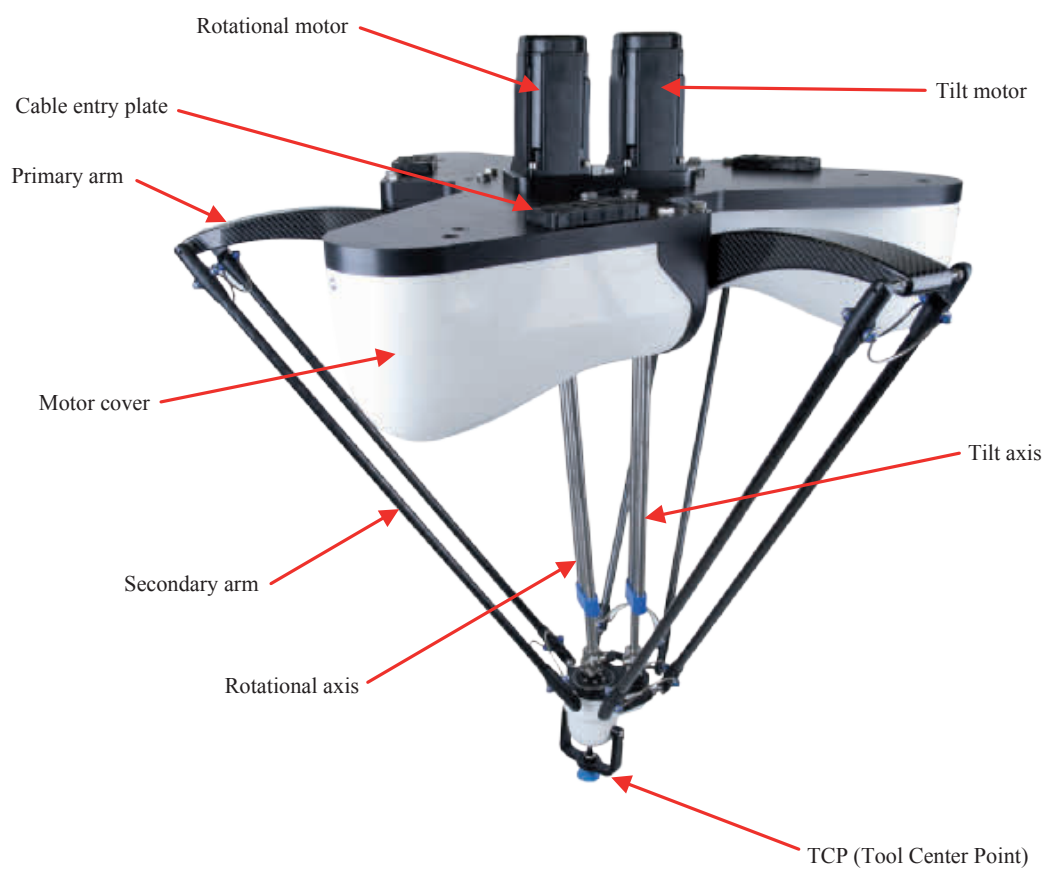
# 2. Identification

On the robot base plate an identification tag is mounted, important data on this plate:

- Robot type
- Total weight of the robot
- Month and year of production
- Serial number, important for ordering spareparts

### 3. Part names

#### CR\_UGD5 series





## Chapter 2 Model overview

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1. Overview

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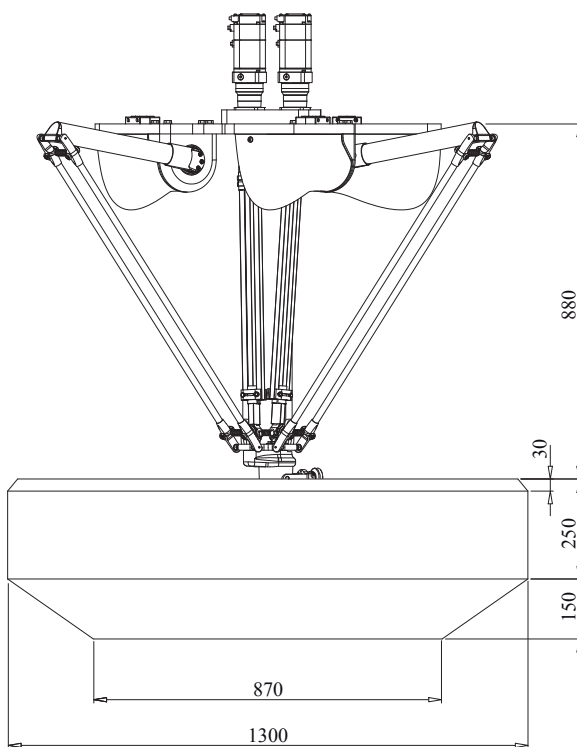


# 1. Overview

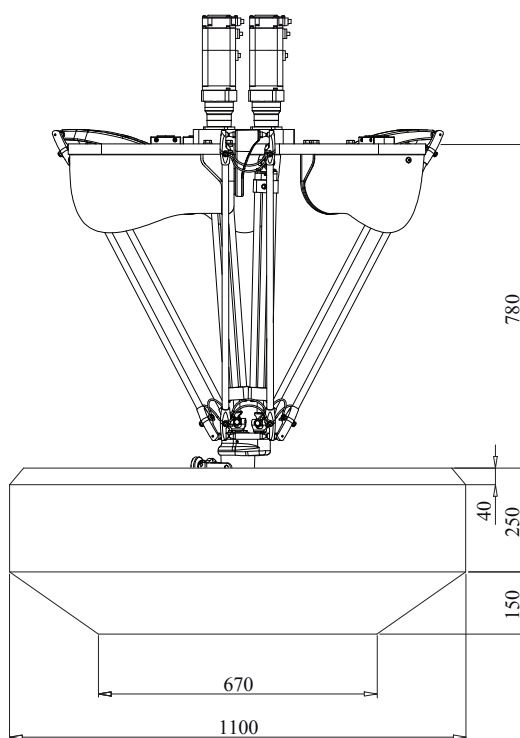
The CR\_UGD5\_XL/CR\_UGD5 has a working range of 1300/1100 mm.

The specifications are given in the below figure, if specifications differ for models, it is indicated in the specification list. The Delta robot 5 axes is delivered standard with sanitary secondary arms, this means they are fully closed to prevent any contamination on the inside of the secondary arms.

## CR\_UGD5\_XL (1300 mm)



## CR\_UGD5 (1100 mm)





# Chapter 3 Installation

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# 1. Unpacking

## 1.1 Unpacking the shipping box

The robot comes in a special shipping box.

The following step must be carried out to remove the cover from the box:

- Unscrew the screws from the cover of the wooden box
- Now remove the cover

## 1.2 Check the damage

First take out the individual components from the package and check that everything is complete according to the following list:

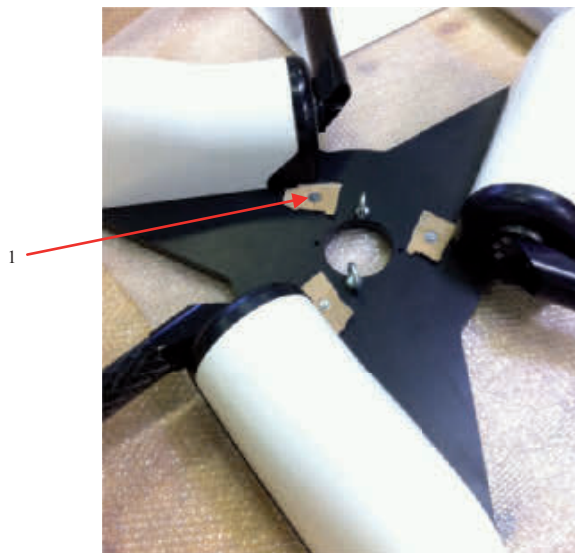
- 1 x rotational axis including head
- 1 x tilt axis including head
- 1 x adaptor plate for the rotational axis gear
- 1 x adaptor plate for the tilt axis gear
- 6 x secondary arms
- 1 x spring package (12 x spring)

Check all the components and the robot for transportation damage.

## 1.3 Lifting and transportation

Before the robot is lifted, it must be ensured that it is free from obstructions.

Remove all the screws where the robot is mounted with in the box.

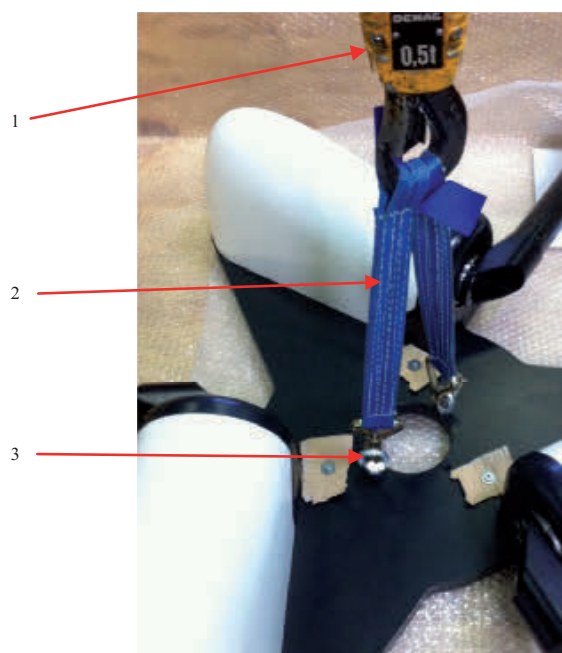


No.	Description
1	3 x screws with protection material

The robot must be lifted and transported by using lifting tackle or a forklift truck. Two lifting straps has to be attached into two eyebolts that are screwed into the baseplate. The lifting straps has to be long enough and must be routed in such a way that the robot is not damaged.

**WARNING**

- THE ROBOT MAY TILT DURING TRANSPORTATION.
- ADDITIONAL SAFEGUARDING MEASURE MUST BE TAKEN.
- WEAR SUITABLE PROTECTIVE CLOTHING IF NECESSARY.
- WHEN USING A FORKLIFT TRUCK, DRIVE EXTREMELY SLOWLY AND CAREFULLY.



No.	Description
1	Lifting tackle
2	2 x lifting straps
3	2 x eyebolts

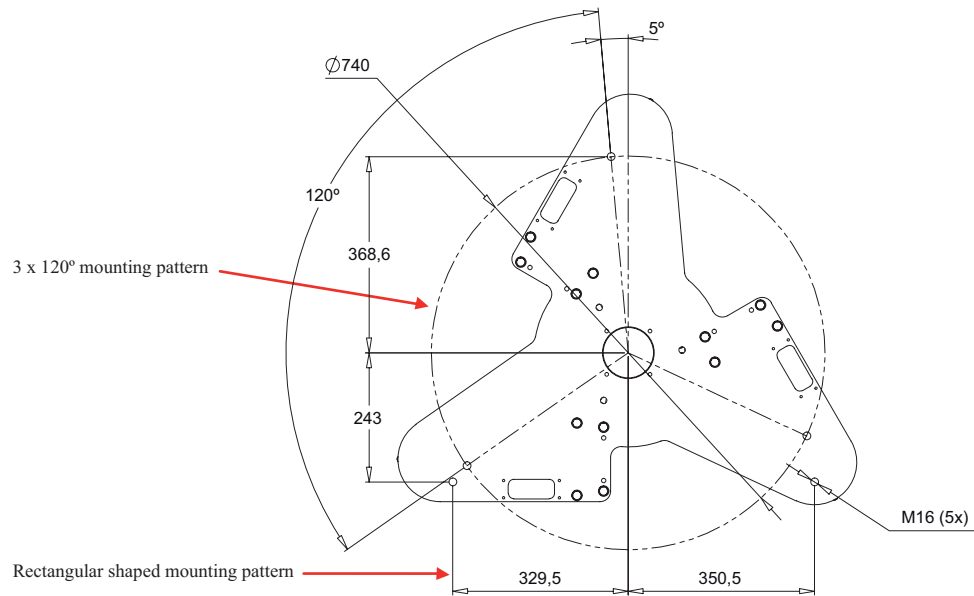


## 2. Mounting the robot

The mounting surface for the robot must be machined and of an appropriate quality. It's also possible to use a levelling element to align the robot.

Three M16 bolts are needed to mounting the robot to the frame, exact bolt length depends on frame layout. The tightening torque of a M16 6.8 bolt is 140Nm.

The below figure shows the mounting pattern from the robot.



## NOTE

It is advisable to put one motor of the robot in line with the direction of the transport belt to make programming easier.

## 3. Mounting the motors and cabling

### 3.1 Mounting the motors

When your robot is delivered without motors, you have to mount them by yourself. First of all you have to remove the three motor covers from the robot.

The following steps must be carried out to remove the motor covers from the robot. Please see also the following picture:

- Remove the M6 Allen bolt



No.	Description
1	1 x M6 Allen bolt
2	Motor cover

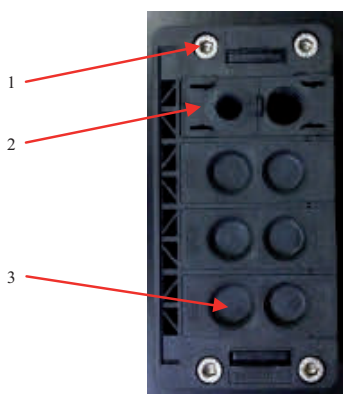
- Remove the motor cover
- Repeat this process for the other two motor covers

### 3.2 Connecting the cables

The robot is delivered with 3 cable entry plates. They are mounted above every primary arm motor to feed his cables through.

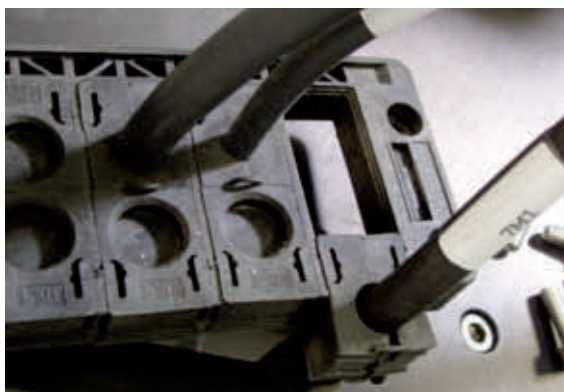
The following steps must be carried out to feed the cables trough the entry plates. Please see also the below pictures:

- Remove the 4 bolts of the cable entry plates
- Remove the cable entry glands



No.	Description
1	4 x M5 Allen bolt
2	Cable entry glands
3	Blind thule

- Insert the cables into the opening of the robot baseplate
- Connect the cables



- Clamp the cable entry glands around the cable and slide it back into the cable entry plate. Afterwards also slide the blind thule back into the cable entry plate
- Mount the cable entry plate on the baseplate, using the 4 M5 Allen bolts

### 3.3 Mounting the motor covers

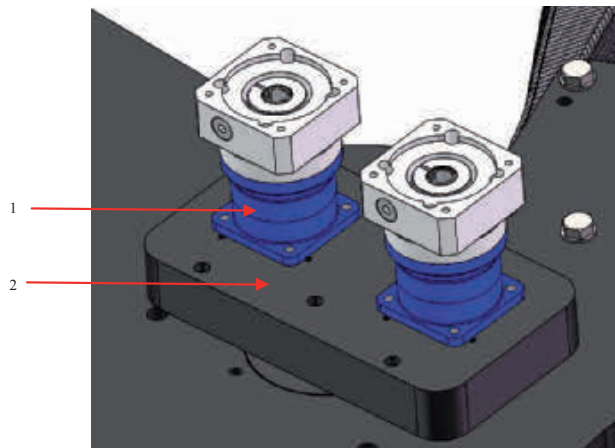
- Mount the cover in the machined groove
- Install the Allen M6 bolt in the cover bracket and tighten
- Repeat the process for the other two motor covers
- The motor covers are now mounted



No.	Description
1	Cover bracket
2	Machined groove

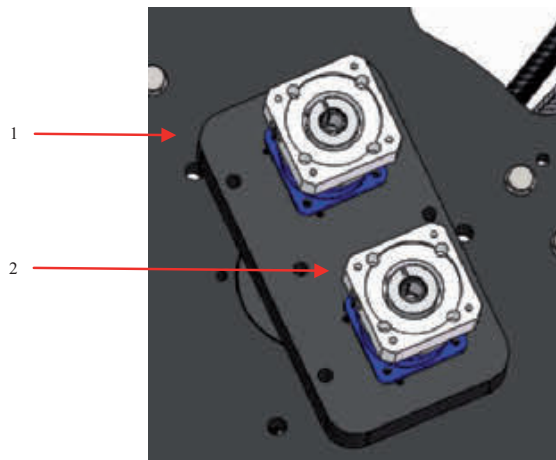
### 3.4 Mounting the rotational and tilt gearbox with their adaptor plate

Dependent on the type of rotational and tilt gearbox, a special adaptor plate for mounting is included.



No.	Description
1	Gearbox or motor
2	Adaptor ring

Now mount the adaptor plate with the gearboxes on the top of the baseplate from the robot with the included bolts and rings.

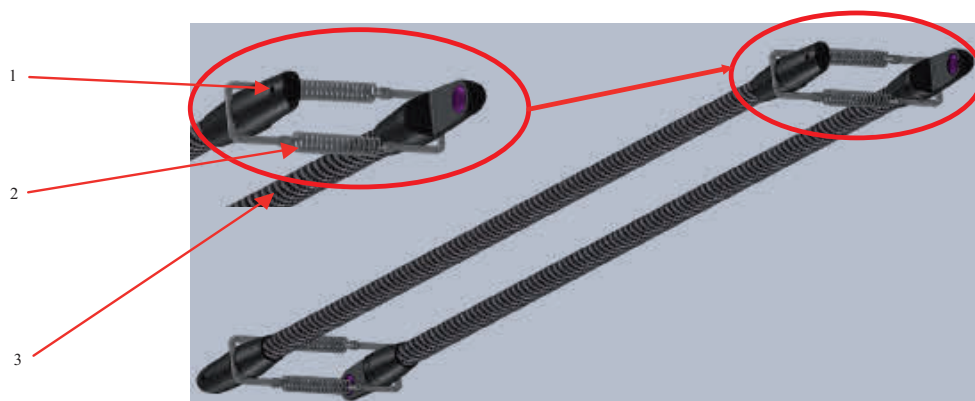


No.	Description
1	Top of the baseplate
2	Rotation adaptor ring with motor or gearbox

## 4. Assembling the secondary arms

### 4.1 Make an assembly

Before mounting the secondary arms on the robot, we have to pre-assemble them as shown on the below figure, so that we get an arm assembly.



No.	Description
1	Sanitary cup holder incl. ball bearing cup
2	Spring package
3	Secondary arm

Repeat this action for the other 2 arm sets.



#### WARNING

- INCORRECT MOUNTED SPRINGS CAN JUMP AWAY.
- WEAR SUITABLE PROTECTIVE CLOTHING AND SAFETY GLASSES.
- NEVER PULL THE SPRINGS FURTHER APART THAN NECESSARY WHEN MOUNTING THE ARM ASSEMBLY ON THE PRIMARY ARM OR TCP BALL JOINTS.
- REPLACE SPRINGS AFTER OVERSTRETCHING.

## 4.2 Mount the arm assembly on the robot

For mounting, pull a secondary arm with his cup holder over the ball joint of the primary arm. Now pull the arms apart against the force of the spring in order to pull the second arm over the second ball joint of the primary arm. Then repeat this action for the TCP (see below picture).



No.	Description
1	TCP - Tool Center Point

Repeat this action for the other 2 secondary arm assembly's.  
Now your robot mechanic is completely installed.

## 5. Mounting the rotational and tilt axis on the gearbox shafts

Please perform the following steps first.

- Extend the rotational and tilt axis to its entire length, then retract the same and check whether it is easy to operate or whether some resistance occurs



### NOTE

A light irregular resistance is normal and caused by the manufacturing tolerances of the tubes. The axis is run in during the first 150 hours of operation. In case of problems, please check the axis for damage or contact your OMRON representative.

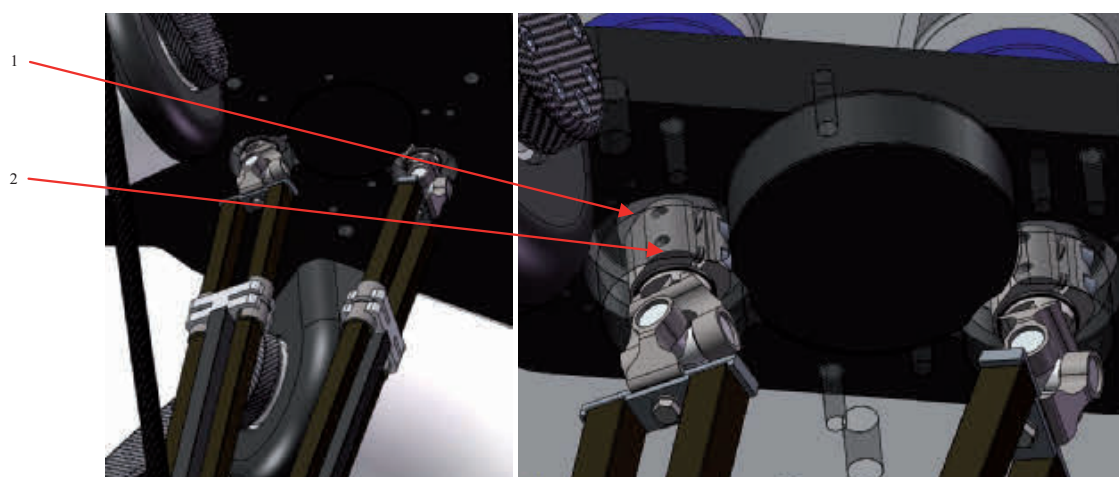


No.	Description
1	Clamping bush with bolts
2	Tilt axis
3	Rotational axis

Release the two M5 Allen bolts which are mounted into the clamping bush (see above picture).

In delivery condition, an extra fill bush is located in the clamping bush.

Measure your motor/gearbox axis and determine if you need the extra fill bush.



No.	Description
1	Motor or gear shaft
2	Top connector rotational axis

Now push the top connector into the shaft until the top connector comes into its stop position on the shaft. Tighten the two M5 Allen bolts with 7 Nm.

The rotational and tilt axis are now mounted.

## 6. Calibration

No every robot that is delivered is calibrated.

If you want to calibrate the robot by yourself, 2 calibration sets with a special tool are available (shown in the below picture).

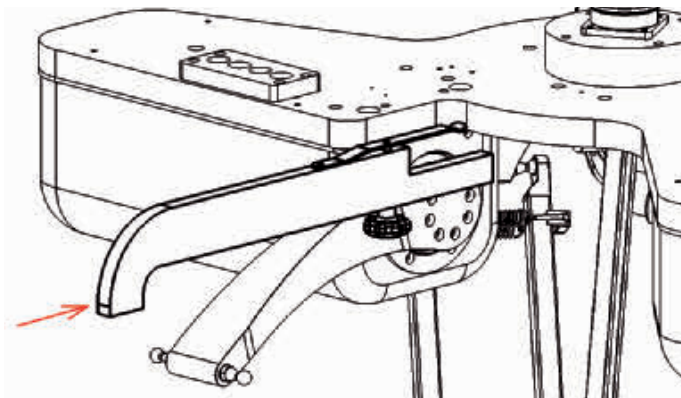
The calibration set for the primary arms can be ordered as CR\_ART.1415 for CR\_UGD5\_XL robot or CR\_ART.1396 for CR\_UGD5 robot.

The calibration set for the rotational and tilt axis can be ordered as CR\_ART.1281.



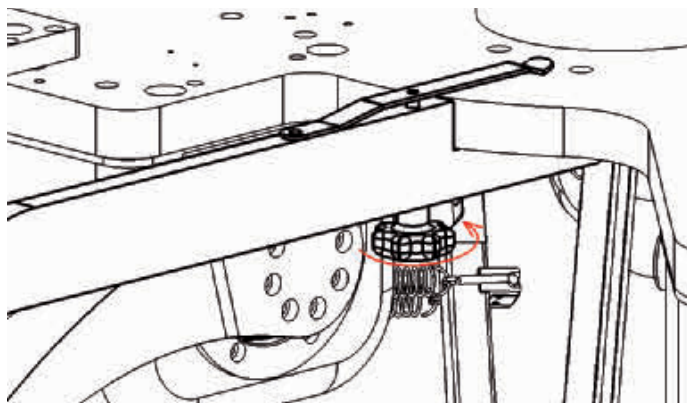
No.	Description
1	Calibration set for the primary arms
2	Calibration set for the rotational and tilt axis

The following steps must be carried out to put the three upper arms from the robot in the zero position. Please see also the below pictures:

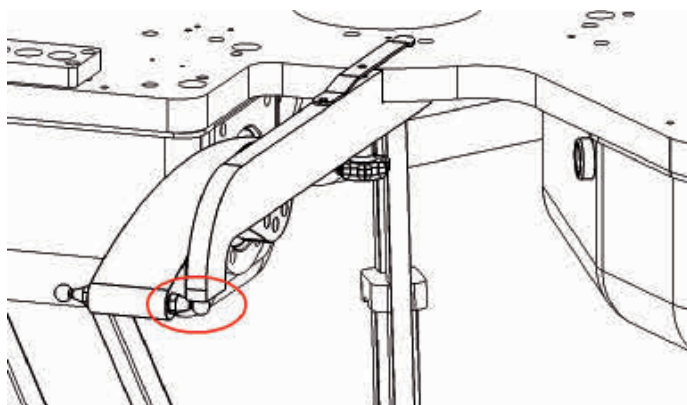


- Make sure all the secondary arms are disassembled
- Release the motor brake and make sure all the primary arms are rotated down far enough, so the calibration tool could be mounted
- Slide the calibration tool on the baseplate as shown in the above picture





- Now tighten the star nut until the tool is fixed



- Release the motor brake from the selected motor and push the upper arm with his ball joint against the calibration tool as shown in the above picture
- Now fix the motor brake from the selected motor
- Repeat the calibration steps for the other two primary arms
- Remove the tool
- Now all the primary arms are in zero position from the kinematic model
- Now put the encoder values from the servo motors in  $0^\circ$
- Check that the angle indicated for the three motors is  $0^\circ (\pm 0.1^\circ)$

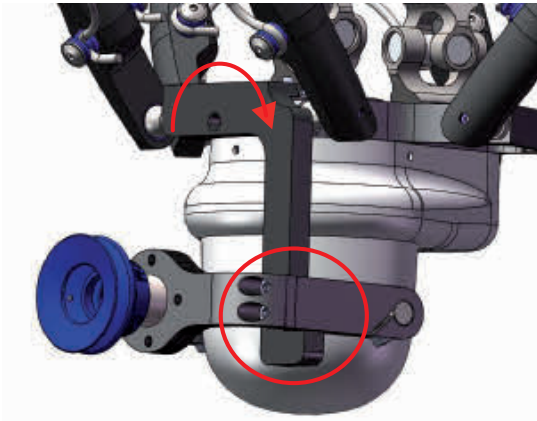
The following steps must be carried out to put the rotational and tilt axis from the robot in the zero position. Please see also the below pictures:



- First put the swivel in the position as shown in the above picture.



- Now mount the calibration tool on the TCP as shown in the above picture.



- Now tighten the star nut until the tool is fixed
- Release the motor brake from both axis and push the swivel arm against the calibration tool as shown in the above picture
- Now fix the motor brake from the selected motor
- Now both axis are in zero position from the kinematic model
- Now put the encoder values from the servo motors in  $0^\circ$
- Check that the angle indicated for the two motors is  $0^\circ (\pm 0.1^\circ)$
- Remove the tool
- Your robot is now calibrated



#### WARNING

- CALIBRATING THE ROBOT MUST BE CARRIED OUT BY QUALIFIED PROGRAMMING PERSONNEL ONLY, AS THIS REQUIRES AN EXCELLENT LEVEL OF KNOWLEDGE OF THE CONTROL SYSTEM.
- WHEN CARRYING OUT THE HOMING YOURSELF, THIS MUST BE CARRIED OUT EXACTLY IN THE WAY AND THE ORDER THAT THEY ARE DESCRIBED.

# Chapter 4 Maintenance

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# 1. Periodic maintenance

Before working on the robot, please be ensured that the machine where the robot is built in, is totally switched off.



## DANGER

- SWITCH OFF THE MACHINE ( SYSTEM ) WHERE THE ROBOT IS BUILT IN (E.G. WITH A PADLOCK) TO PREVENT IT FROM BEING SWITCHED ON AGAIN.
- LABEL THE MACHINE (SYSTEM) WITH A SIGN INDICATION THAT WORK IS IN PROGRESS. THIS SIGN MUST REMAIN IN PLACE, EVEN DURING TEMPORARY INTERRUPTIONS TO THE WORK.
- THE EMERGENCY STOP FROM THE MACHINE (SYSTEM) MUST REMAIN ACTIVE. IF SAFETY FUNCTIONS OR SAFEGUARDS ARE DEACTIVATED DURING MAINTENANCE OR REPAIR WORK, THEY MUST BE REACTIVATED IMMEDIATELY AFTER THE WORK IS COMPLETED.

## 1.1 Springs

How to maintain the springs:

- The springs has to be replaced every 3800 working hours or once a year
- When the robot is fall apart, check the springs on damages
- Only use springs delivered by OMRON, otherwise the guarantee will expire
- Replace springs after overstretching
- For spare parts, see **Section 3 Spare parts** in this chapter



## WARNING

- INCORRECT MOUNTED SPRINGS CAN JUMP AWAY.
- WEAR SUITABLE PROTECTIVE CLOTHING AND SAFETY GLASSES.
- NEVER PULL THE SPRINGS FURTHER APART THAN NECESSARY WHEN MOUNTING THE ARM ASSEMBLY ON THE PRIMARY ARM OR TCP BALL JOINTS.

How to disassemble the springs:

- Disassemble the secondary arms from the robot
- Replace the springs
- For re-assembling the secondary arms, see **Section 4 Assembling the secondary arms** in Chapter 3

## 1.2 Ball bearing cups

The ball bearing cups has the same lifetime as the springs. We recommend to exchange these at the same time as the springs.

How to maintain the ball bearing cups:

- The ball bearing cups has to be replaced every 3800 working hours or once a year
- When the ball bearing cups make squeaking noises, take of the secondary arm assembly's and clean the cups with pressed air
- **Do not lubricate the ball bearing cups!**

For instructions to replace the ball bearing cups, see the below picture:



No.	Description
1	M5 bolt

- Screw an M5 bolt in the backside from the cup holder
- Now the ball bearing cup will come out

## 1.3 Rotational and tilt axis

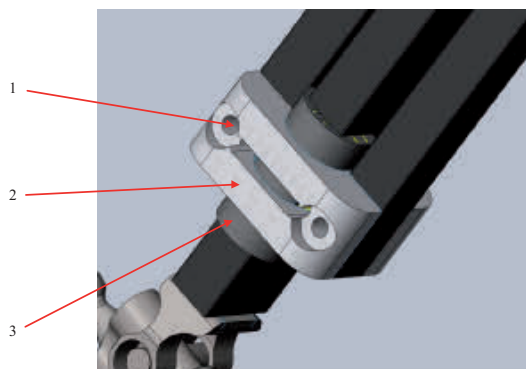
The plain bearings on the rotational and tilt axis wear with time so that backlash starts to occur on the rotational and tilt axis. How fast the plain bearings become worn depends strongly on the following factors:

- The working path
- The payload
- The speed of the robot
- The rotation actions

When do I have to exchange the plain bearings?

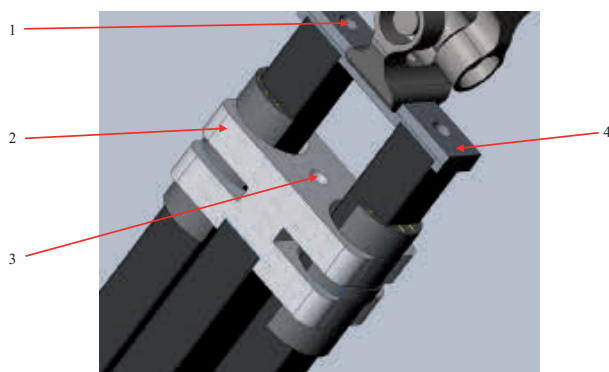
- If there is a lot of play on the rotational axis
- Every 3000 working hours or once a year

For instructions to replace the plain bearings, see the below picture:



No.	Description
1	M5 bolt with washer
2	Slider clamp bottom
3	Plain bearing

- Unscrew the two M5 bolts with washer and take of the slider clamp bottom
- Now exchange the old bearing with a new one
- Put back the slider clamp bottom and the two M5 bolts with washer
- Repeat this for the other side of the axis



No.	Description
1	2 x M5 bolt with washer
2	Slider clamp top
3	1 x M5 bolt with washer
4	Top connector

- Unscrew the three M5 bolts with washer from the top connector and the slider clamp top
- Remove the top connector from the tubes
- Remove the slider clamp top with the plain bearings
- Now exchange the old plain bearings with the new ones
- Put back the slider clamp top and the M5 bolt with washer
- Mount the top connector with the two M5 bolts with washer on the two tubes



#### WARNING

- PLAIN BEARINGS HAS TO BE MOUNTED VERY CAREFULLY.
- WRONG MOUNTED PLAIN BEARINGS MAY DAMAGE.
- EXTEND THE ROTATIONAL AXIS TO ITS ENTIRE LENGTH, THEN RETRACT THE SAME AND CHECK WHETHER IT IS EASY TO OPERATE OR WHETHER SOME RESISTANCE OCCURS.

## 2. Cleaning the robot

Clean the robot by washing with soft cloth or sponge. Use soap or mild detergent and warm water followed by clear water rinse.

For oil and grease stains use alcohol with soft cloth.

Do not use a high pressure water cleaner, or any other high pressure cleaning device.

## 3. Spare parts

Description		OMRON Part No.	
		CR_UGD5_XL	CR_UGD5
Primary arm set	2 x ball bearing / 1 x dowel pin / 1 x primary arm	CR_ART.1413	CR_ART.1394
Ball bearing cups	12 x ball bearing cups	CR_ART.1395	
Spring package	6 x spring / 12 x springholder	CR_ART.1156	
Secondary arm assembly	2 x spring / 4 x spring holder / 2 x secondary round arm	CR_ART.1414	CR_ART.1157
Calibration set for the primary arms	1 x calibration tool / 1 x suitcase	CR_ART.1415	CR_ART.1396
Calibration set for the rotational and tilt axis	1 x calibration tool	CR_ART.1281	
Hinge rollers	24 x hinge rollers	CR_ART.1325	
Steel ball bearing package	6 x steel ball bearing	CR_ART.1398	
Motor cover	1 x motor cover	CR_ART.1236	
Rotational axis	1 x complete rotational axis	CR_ART.1417	CR_ART.1399
Lower side rotational axis	1 x lower cardan and tube / 1 x TCP axis	CR_ART.1418	CR_ART.1400
Upper side rotational axis	1 x upper cardan / 1 x connection strip	CR_ART.1401	
Spline part rotational axis	2 x square tube / 4 x plain bearing / 1 x connection strip / 4 x plastic blocks	CR_ART.1419	CR_ART.1402
Rotary cover	1 x dome	CR_ART.1403	
Belt cover	1 x cover	CR_ART.1404	
Fork	1 x fork	CR_ART.1405	
Gripperflange	1 x gripperflange	CR_ART.1406	
Plain bearing rotational axis	1 x plain bearing	CR_ART.1020	
Secondary arm	1 x complete secondary arm (without springs and brackets)	CR_ART.1420	CR_ART.1407
Springs	6 x spring	CR_ART.1158	



# Chapter 5 Robot settings

## Contents

1. Kinematics	5-1
2. Workspace	5-2
3. Software limits	5-3



# 1. Kinematics

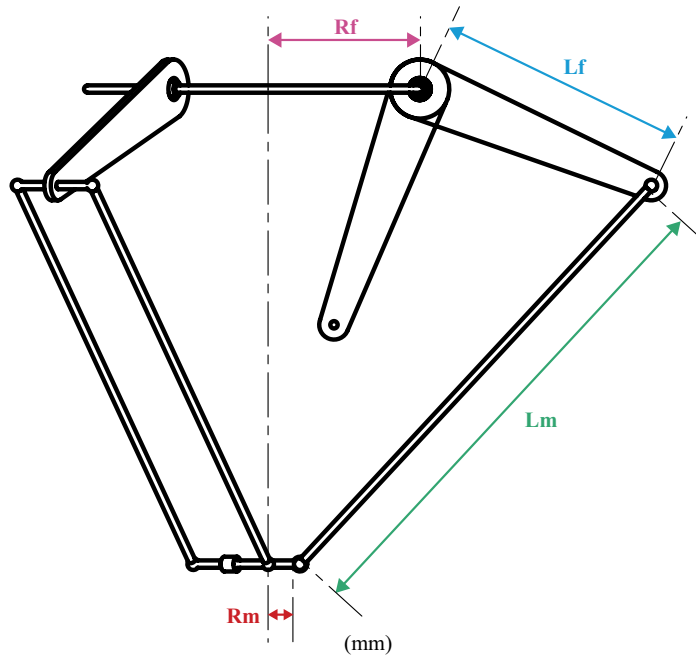
The kinematics parameters for the CR\_UGD5 robot are shown below. Set these parameters corresponding to the controller settings.



## WARNING

IF THE KINEMATICS PARAMETERS ARE NOT SET PROPERLY, THIS MAY CAUSE THE ROBOT TO MALFUNCTION. SO, BE SURE TO SET THESE PARAMETERS CORRECTLY.

## Kinematics parameters



### CR\_UGD5\_XL

- Rf:** 200 mm Distance (radius) from the center of the fixed frame to the motor of the axis
- Rm:** 60 mm Distance (radius) from the center of the moving frame to the connection point of Link 2
- Lf:** 420 mm Length of Link 1
- Lm:** 950 mm Length of Link 2

### CR\_UGD5

- Rf:** 200 mm Distance (radius) from the center of the fixed frame to the motor of the axis
- Rm:** 60 mm Distance (radius) from the center of the moving frame to the connection point of Link 2
- Lf:** 320 mm Length of Link 1
- Lm:** 850 mm Length of Link 2

## 2. Workspace

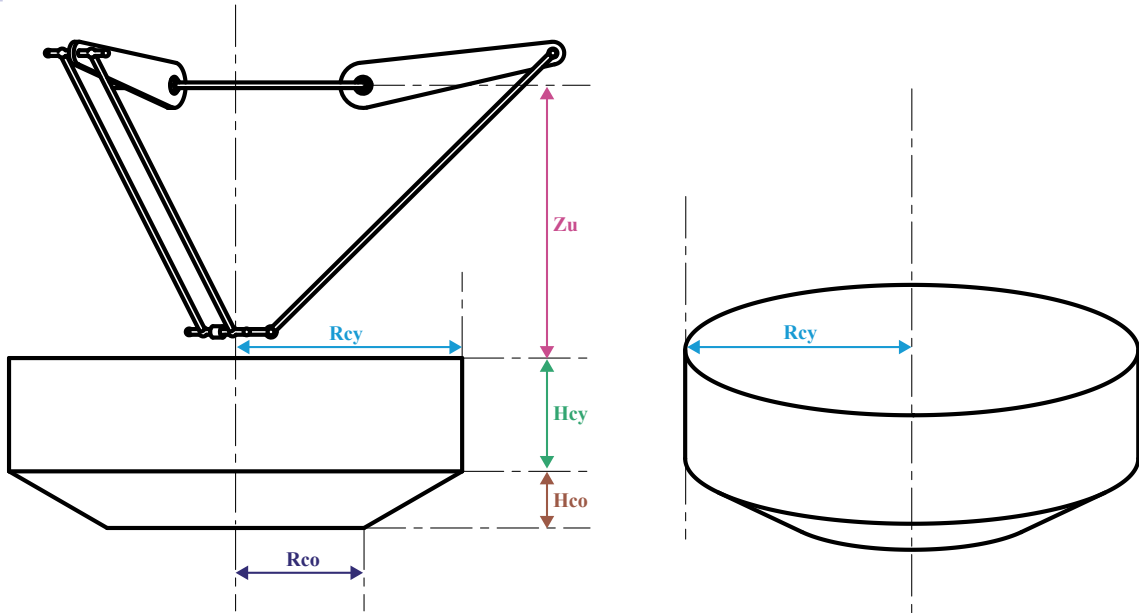
The workspace parameters for the CR\_UGD5 robot are shown below. Set these parameters corresponding to the controller settings.



### WARNING

IF THE WORKSPACE PARAMETERS ARE NOT SET PROPERLY, THIS MAY CAUSE THE ROBOT TO MALFUNCTION. SO, BE SURE TO SET THESE PARAMETERS CORRECTLY.

### Workspace parameters



#### CR\_UGD5\_XL

- Zu:** -790 mm Distance from the Z-axis origin position
- Rcy:** 650 mm Radius of the cylinder
- Hcy:** 250 mm Height of the cylinder
- Rco:** 435 mm Radius of the frustum cone of underside
- Hco:** 150 mm Height of the frustum cone

#### CR\_UGD5

- Zu:** -690 mm Distance from the Z-axis origin position
- Rcy:** 550 mm Radius of the cylinder
- Hcy:** 250 mm Height of the cylinder
- Rco:** 335 mm Radius of the frustum cone of underside
- Hco:** 150 mm Height of the frustum cone

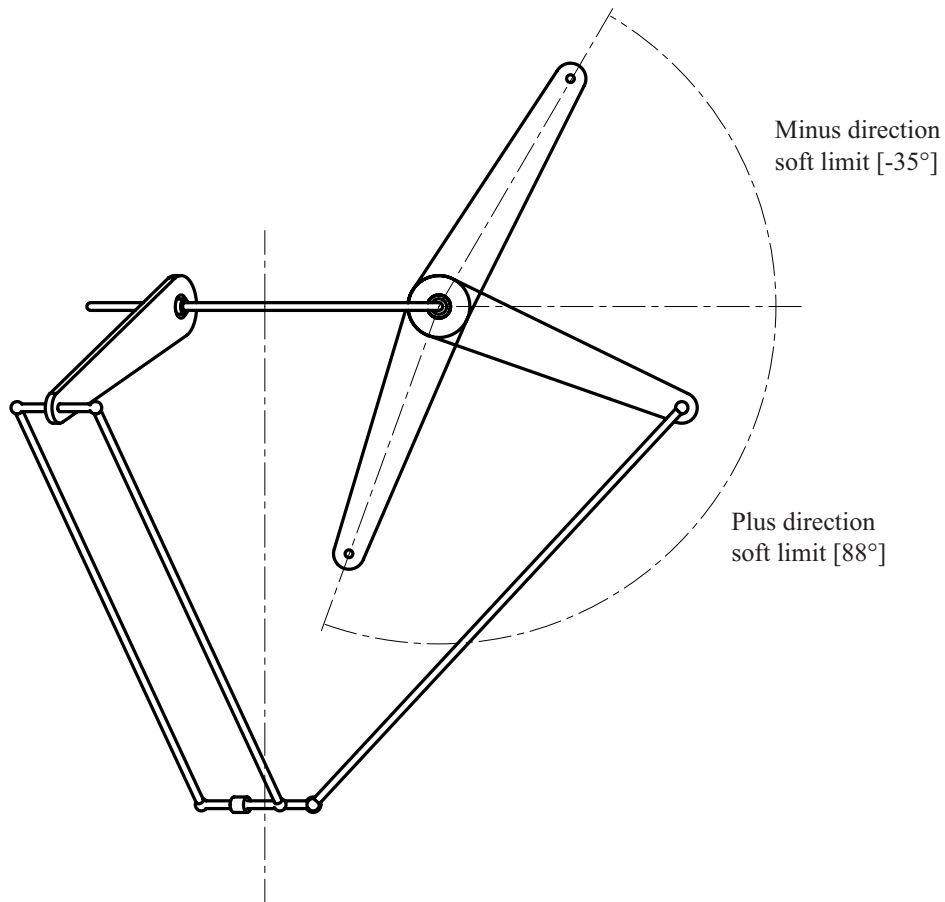
### 3. Software limits

The software limits for the CR\_UGD5 robot are shown below.



#### WARNING

IF THE  $\alpha$ -,  $\beta$ - OR  $\gamma$ - AXIS SOFT LIMIT IS SET INCORRECTLY, THE ARM MAY COLLIDE WITH THE ROBOT BASE OR BASE PREPARED BY THE USER, CAUSING BREAKAGE. SO, BE SURE TO SET THE SOFT LIMITS CORRECTLY.





# Chapter 6 Specifications

## Contents

<b>1. Basic specifications</b>	<b>6-1</b>
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# 1. Basic specifications

Robot model			CR_UGD5_XL	CR_UGD5
Working volume	X, Y axis	Stroke	Ø1300mm	Ø1100mm
	Z axis	Stroke	250mm (max. Ø1300mm)/ 400mm (center Ø870mm)	250mm (max. Ø1100mm)/ 400mm (center Ø670mm)
	θ axis	Rotation range	±180° (default setting, it can be changed)	
	Tilt axis		Mechanically limited	
Servo motor		Arm 1, 2, 3	1000W	
		Rotational axis 4	750W	
		Tilt axis 5	750W	
Repeatability *1		X, Y, Z axis	±0.2mm	
		θ axis	±0.3°	
Maximum through-put *2			120 CPM*4	125 CPM*4
Maximum payload			1kg	
Rotational and tilt axis moment of inertia *3			According to the servo motor	
Travel limit			Soft limit	
Noise level			< 68 dB (A)	
Ambient temperature			5°C to 45°C	
Relative humidity			Max. 90%	
Protection class			IP65	
Weight			70kg	

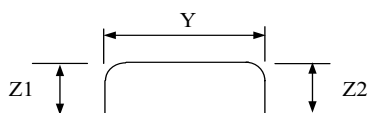
\*1: This is the value at a constant ambient temperature.

\*2: With 0.1kg payload. When reciprocating 305mm in horizontal and 25mm in vertical directions.

\*3: There are limits to acceleration coefficient settings.

\*4: CPM: Cycle per minutes. Check the note 2 for the cycle definition.

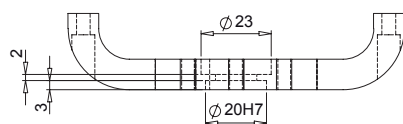
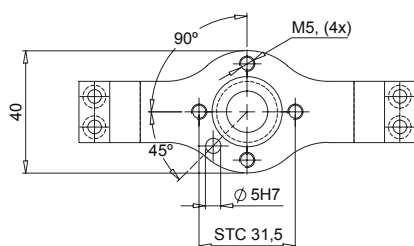
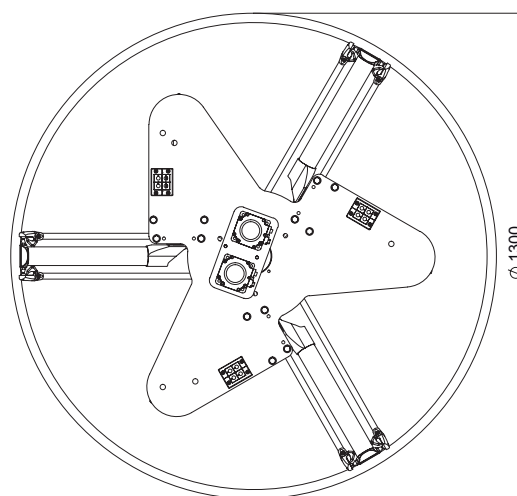
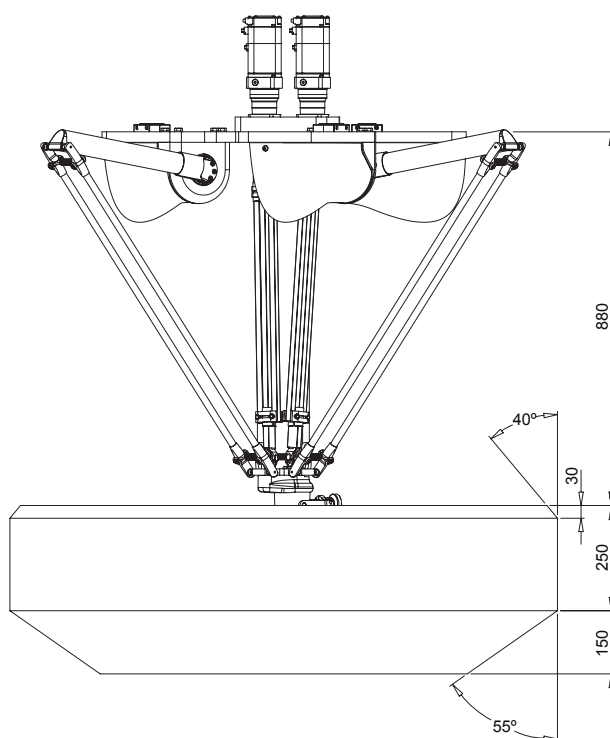
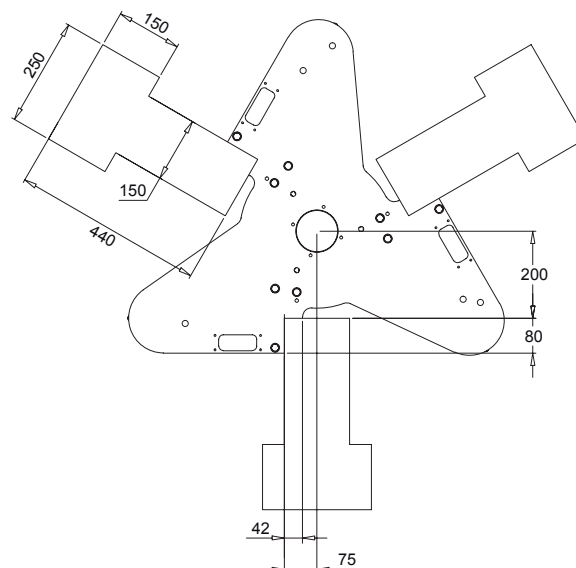
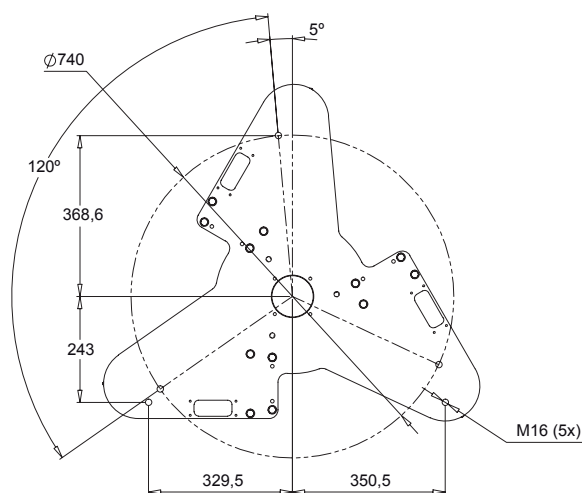
## 1.1 Cycle time



P&P path	Payload	CR_UGD5_XL cycle time	CR_UGD5 cycle time
25 x 305 x 25 mm (Z1 x Y x Z2)	0.1 kg	0.50 s	0.48 s
	0.5 kg	0.57 s	0.55 s
	1 kg	0.69 s	0.67 s

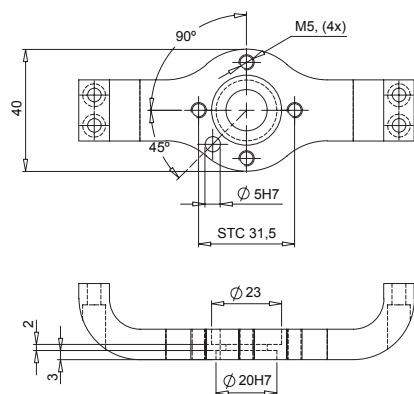
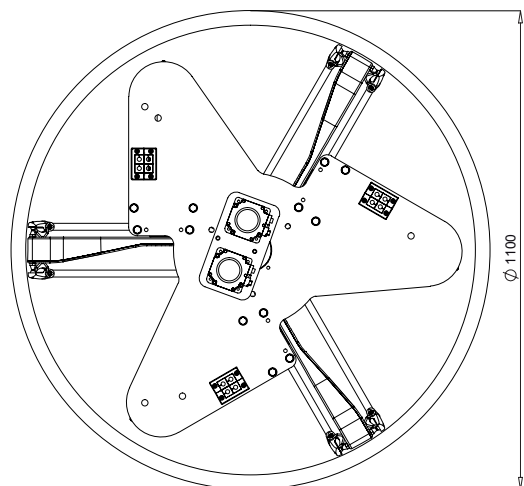
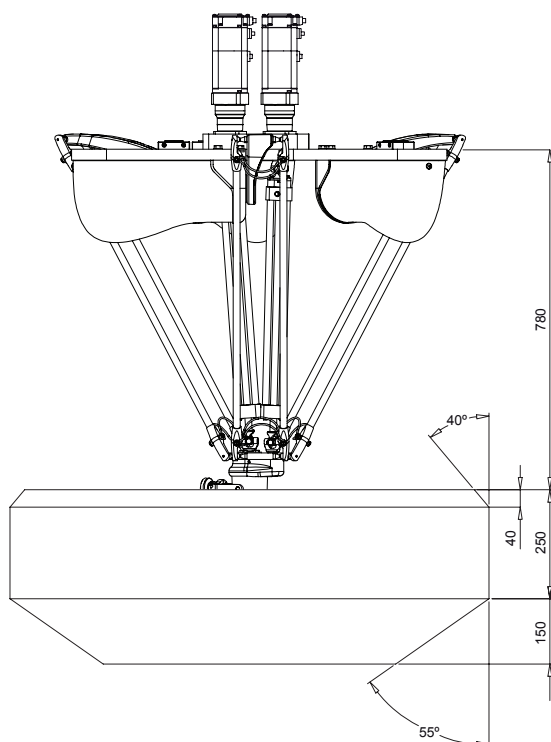
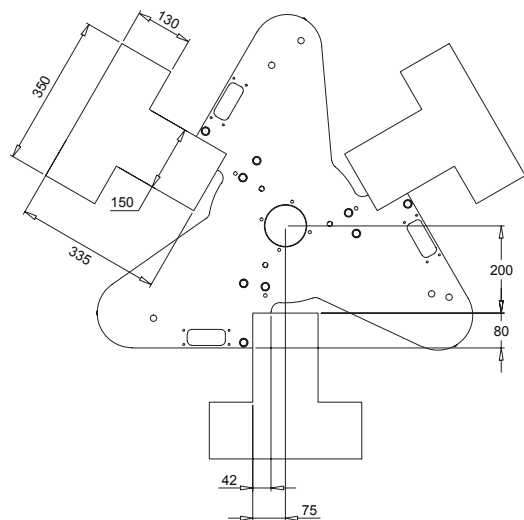
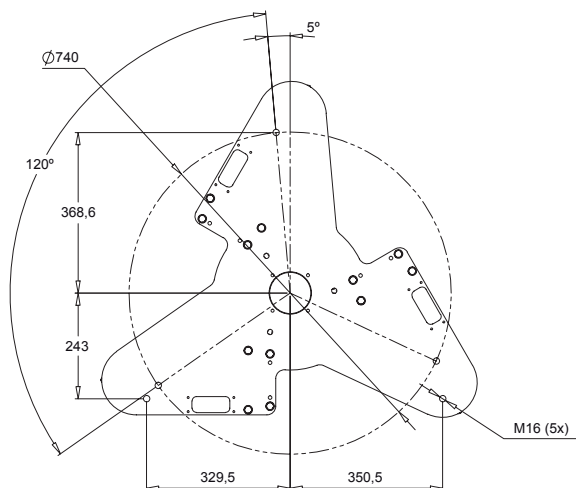
## 2. External view and dimensions

### 2.1 CR\_UGD5\_XL



Gripper dimensions

## 2.2 CR\_UGD5



Gripper dimensions

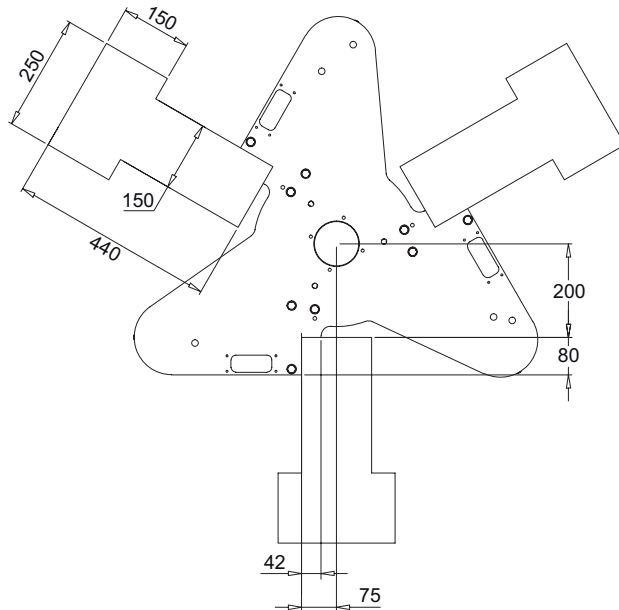
## 3. Design specifications

### 3.1 Occupation area of robot

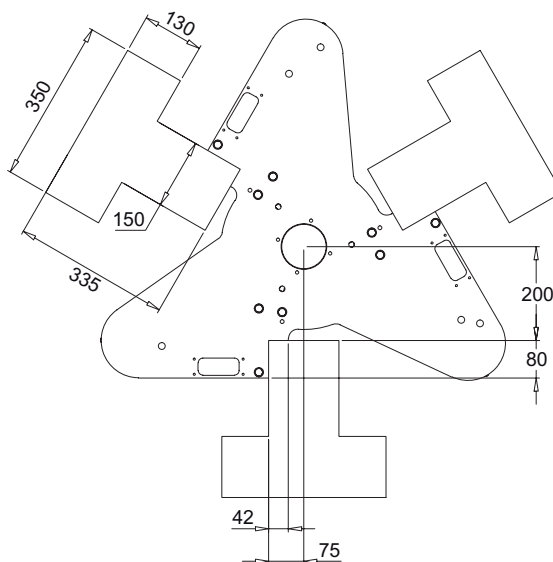
If the robot is integrated into the machine it must be considered what the reach is of all robot parts to prevent collision with other parts in the machine.

When the TCP moves to its outer positions, the primary and secondary arms can rise above the baseplate, take care that no mechanical obstructions are in the areas indicated in the below picture.

CR\_UGD5\_XL



CR\_UGD5

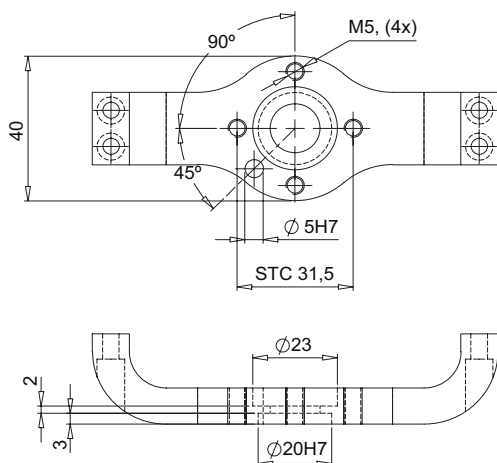


**WARNING**

IF MECHANICAL OBSTRUCTIONS ARE IN THE INDICATED AREA, THE ROBOT OR THE OTHER MACHINE PARTS COULD BE DAMAGED.

### 3.2 Gripper interface

The below picture shows you the gripper connection sizes according to ISO 9409-1-A31,5.



The design of the gripper that is mounted under the robot have great influence on the performance of the robot. Both the weight of the gripper and the distance of the center of gravity of the gripper to the TCP base point have negative influence on the final performance of the robot.

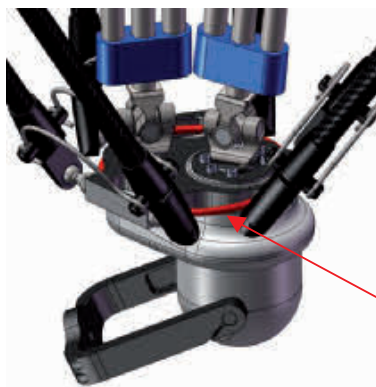
If you need to install cabling for the gripper, please follow the following steps:

- Mount the cables on the baseplate or frame, near the turning point from the primary arm on the gearbox
- Mount the cables on the primary arm, with ty-raps or clamping parts
- Keep a big loop at the hinge point from the primary and secondary arm
- Mount the cables on the secondary arm, with ty-raps or clamping parts
- Keep a big loop from the lowest mounting point at the secondary arm till the connection on the gripper

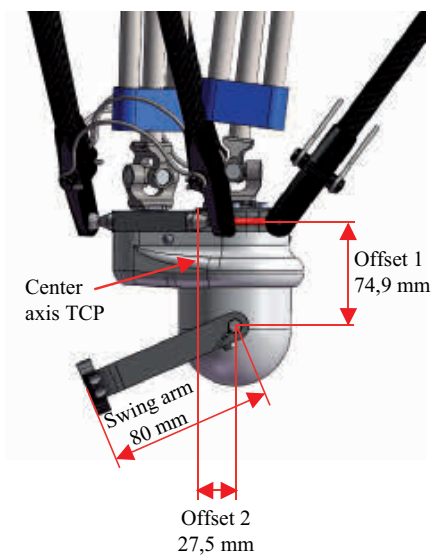
### 3.3 Software design

The arm lengths and pitch circles of the rotation points are shown in the below picture.



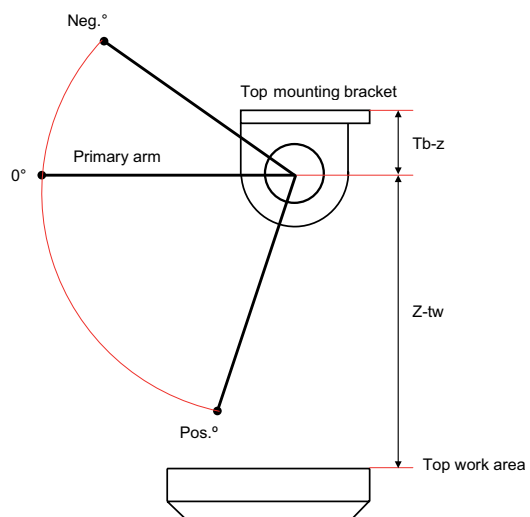


Lower arm rotation points  
circle diameter 120 mm



### 3.3.1 Dimensions and limits

Description	CR_UGD5_XL	CR_UGD5
Negative software limit	-35°	
Positive software limit	88°	
Tb-z (top baseplate to zero position)	90 mm	
Z-tw (zero position to top work area)	790 mm	690 mm



3.3.2 Gear ratio

Description	Ratio	Comments
Rotational axis 4	1:2	Gear ratio achieved by a belt with pulleys.
Tilt axis 5	1:2	The rotation of the swing arm is linked to the vertical rotation (rotational axis 4). The swing arm rotates with a ratio of 1:4 between the swing arm and the motor of rotational axis 4.



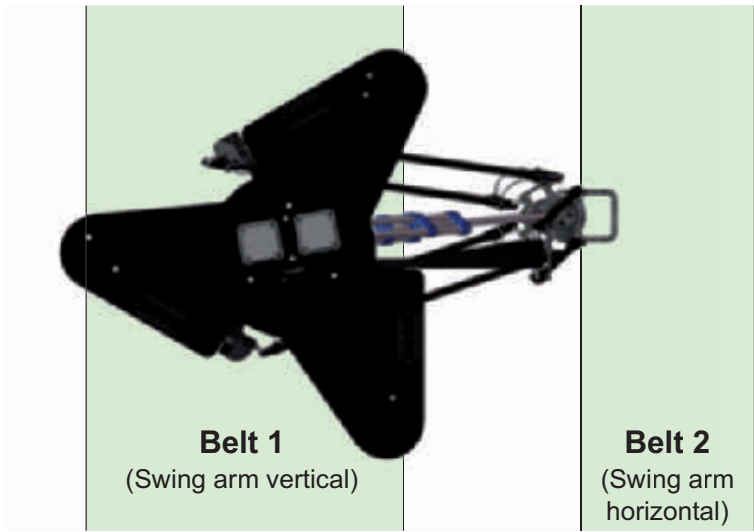
WARNING

THE DIRECTION OF ROTATION OF THE SWING ARM DEPENDS ON THE POSITION OF THE INTERNAL GEARBOX. THERE ARE TWO POSSIBLE POSITIONS FOR THE GEARBOX (ROTATED 180 DEGREES FROM EACH CONTROLLER). THE POSITION OF THE GEARBOX CANNOT BE DETERMINED FROM THE INSIDE OR OUTSIDE OF THE STRUCTURE. THE POSITION HAS TO BE DETERMINED BY ROTATING TILT AXIS WHEN THE ROBOT IS COMPLETELY INSTALLED. PLEASE, TAKE NOTE THAT THE POSITION OF THE GEARBOX HAS TO BE REDETERMINED WHEN THE ROTATION AXES ARE DISCONNECTED AND THE CALIBRATION IS LOST.

3.4 Recommended robot position

It is recommended to place the robot in such way that there is no risk of the product or gripper hitting the lower arm of the robot in the situation where the swing arm is rotated to the horizontal position. This issue occurs due to the fact that the dome in which the swing arm is mounted isn't placed in the center of the TCP. Therefore the optimal position of the baseplate (in terms of rotation) is the position where there is the most space for the swing arm to move around (when the swing arm is placed horizontal).

**Example:** The optimal position of the base plate for the below situation is when the upper arm closest to tilt axis is placed closest and perpendicular to belt 2.







## Revision history

A manual revision code appears as a suffix to the catalog number on the front cover manual.

Cat. No. I205E-EN-01



The following table outlines the changes made to the manual during each revision.

Revision code	Date	Description
01	October 2016	Original production



**Authorized Distributor:**