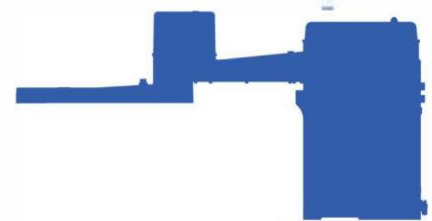


Hermes Robot

User Manual



QKM 

User Manual

Hermes Robot

HM3-0800-0652-0000

HM8-0500-0652-0000

QKM Technology (Dongguan) Co., Ltd.

Version: V3.0

Date: 01/11/2023

Preface

Thank you for purchasing the robot produced by QKM!

This manual describes the matters needing attention for properly use of Hermes Robot.

Read this manual carefully before using Hermes Robot.

Please keep this manual properly for future reference

General

This manual provides detailed information on product features, main components, installation guide, system debugging and technical specifications of Hermes Robot so that users can fully understand and properly use the robot.

Target reader

This manual applies to:

Customer engineer

Technical support engineer

Application engineer





Installation and Debugging Engineer

Definition of Signs

The signs in this document clearly indicate any dangers, warnings, cautions and notes that may occur while users perform the operations described in this

manual. Pay attention to the following signs when they appear in the document.

The signs appearing in this manual are shown in the following table:


Figures	Description
	<p>It indicates an imminently hazardous situation, which if not avoided, will result in death or serious injury.</p>
	<p>It indicates that a potentially dangerous situation would occur and cause personal injuries or equipment damage if it is not avoided.</p>
	<p>It indicates that an unpredictable situation would occur and cause equipment damage, performance degradation, data loss, etc. if it is not avoided.</p>
	<p>It gives the description on key information and operation tips.</p>

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QKM Technology (Dongguan) Co., Ltd. (Head Office)

Block A, Building 17, No.1 Head Office, No.4 Xinzhu Road, Songshanhu High-tech
Industrial Development Zone, Dongguan City

Tel.: +86 0769-27231381

Fax: +86 0769-27231381-8053

Post code: 523808

Email: service@qkmtech.com

Website: www.qkmtech.com

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The most recent version of the document contains the updated contents of all previous document versions.

Document version	Issued on	Revised content
V1.0	01/14/2022	The first version
V2.0	07/08/2022	Modified Chapter 3, subsection 3.3.1 Horizontal Workspace And add a description of the hard limit
V2.1	07/29/2022	In subsection 6.7.2, add a description of the robot motion speed.
V2.2	11/14/2022	Modified the front pinout picture of the 9-pin header of the communication interface (RS-232) in section 4.3.4 Modified the picture description of the front pinout of the 9-core hole holder of the communication interface (RS-485) in Chapter 4.3.5

V2.3	11/24/2022	<p>Modify Table 4-6 MCP Definition of MCP pins;</p> <p>Modify Figure 4-4 Wiring diagram of E-stop device.</p>
V3.0	01/11/2023	<p>Modify Chapter 6 Robot Operation:</p> <ol style="list-style-type: none"> 1. Modify Section 6.1,add an overview of the QRL language. 2. Modify the pictures of the ARM installation process in Section 6.2. 3. Modify the interface picture and operation steps of the new version of ARM in Section 6.3. 4. Modify Section 6.4 Macro Command Debugger Function Introduction and Operation Procedures. 5. Added Section 6.5 QRL Mode Description and Operation Content. 6. Modify the manual teaching interface picture and operation steps in Section 6.6. 7. Modify Section 6.7 Servo power-up pictures and content. 8. Modify the picture and content of the robot

		<p>speed adjustment control in Section 6.8.</p> <p>9. Added 6.10 Robot power-off method 1 and method 2 operation steps, and added method 3.</p>
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Chapter 1 Safety Precautions

This chapter describes the safety precautions for using Hermes Robot. Please read this manual carefully before using the robot. Improper use of the robot may cause injuries to operators and damage to the system, and even cause personal deaths. Users must strictly follow the safety precautions in this manual. QKM shall not be responsible for any personal and equipment losses caused by illegal operations.

Personnel who use this product for system design, operation and maintenance must be trained by QKM or relevant institutions or have the same professional skills. Personnel must read this manual carefully before conducting operation, maintenance, teaching, programming and system development of HM3 Robot and use it in strict accordance with the safety precautions in this manual.

1.1 Precautions for general safety



The safety precautions in this manual only serve as a supplement to safety specifications. Personnel using the robot shall also comply with local safety regulations or specifications.

Personnel who use this series of robots for system design and manufacturing

shall observe the following safety rules:

- Use the robot and its component products in an environment that meets the design specifications, otherwise the robot may fail.
- Please use the robot within the specified operation environment. If it is used beyond its specifications and load conditions, the service life of the robot would be shortened or the robot would even be damaged.
- Users should ensure that the robot operates under safety conditions. There should be no objects around the robot, which may cause damage to it. As the robot may be scratched and bumped due to the motion of its movable mechanical parts, users should carry out risk assessment of the operation environment on site and set up special facilities for protection.
- To prevent personnel from entering the motion area of the robot by mistake, be sure to install a safety fence to stop personnel from entering the dangerous area.
- When the ambient temperature is close to 0°C, operate the robot at the speed of 10% or less for more than 10 minutes to preheat it; perform other operations after preheating the robot.
- Detergents with strong corrosion are not suitable for cleaning the robot. Anodized parts should not be cleaned by immersion.

- Non-professionals shall not repair the faulty products or disassemble the electronic control cabinet without permission. If the product fails, please contact QKM Customer Service Department.
- Personnel responsible for installation, operation and maintenance of QKM robots must receive rigorous training to understand all safety precautions and proper methods of operation and maintenance before operating and maintaining the robot.
- Users should carry out regular inspection and maintenance of the robot according to the manual and related requirements and timely replace damaged parts to ensure safe operation and service life of the robot.
- Before operating, maintaining and testing the robot, be familiar with the specific location of the workplace where the robot emergency stop device is located, and ensure that the emergency stop switch can be pressed quickly in case of an emergency.
- Do not plug or unplug the power and communication wires and cables or press the emergency stop switch arbitrarily during normal operation of the robot.
- Users shall operate the robot by following the instructions marked on it. Do not enter the dangerous area where the robot operates to avoid personal injuries and robot damage.

- If users request for transport, please adopt the standard packaging required by QKM.

1.2 Precautions for safe operation



- Shut off the power when installing and maintaining the robot to prevent accidents.
 - Do not enter the work area of the robot after it is powered on to prevent danger.
-

Please observe the following safety rules when conducting installation, teaching and programming of the robot:

- Only qualified designated personnel who correctly understand the precautions for safe operation, master the using method and receive specialized training can operate, maintain and repair the robot.
- Do not change the hardware facilities and software configuration of the robot arbitrarily, otherwise damage to the robot or harm to the user would be easily caused.
- The robot needs to be connected to the main ground wire of the factory for proper grounding to prevent static electricity damage; be sure to use special insulated tools for maintenance.
- Confirm that the entire robot system is in a safe environment before

performing daily inspection and regular maintenance of the robot.

- Do not plug or unplug the power and communication wires and cables during normal operation of the robot.
- Regularly train operators on operation rules, industrial safety, safety instructions and environmental protection.
- Users should carry out regular inspection and maintenance of the robot according to the manual and related requirements and timely replace damaged parts to ensure safe operation and service life of the robot.
- If the robot and its components are scrapped and shall be discarded, please handle the industrial waste properly in accordance with relevant laws and regulations to protect the environment.





1.3 Safety signs

The main body of the robot is labeled with the following warning signs.

There are corresponding dangers and warnings near the location where the signs are labeled, so take sufficient care when operating.

In order to operate and maintain the robot system safely, be sure to observe the cautions and contents on the warning signs.

Table 1-1 Warning signs

No.	Labeling	Notes
1		<p>A triangle sign for warning of high voltage</p>
2		<p>Grounding sign</p>
3		<p>Do not disassemble the robot to prevent failures.</p>
4		<p>A sign for protection from residual voltage</p>

Chapter 2 Product Overview

2.1 Introduction

Hermes Robot is a SCARA robot (adopting a new generation of distributed controller) independently developed by QKM. It has heavy load, large arm length, high precision, high speed, and adopts the AIO drive-control-power design highly integrating drive components, control components, IO ports and power supply into the robot body; the robot with 2-DOF can be flexibly used in automatic production lines of new-energy vehicles, appliance parts and other products regarding their assembly, handling, sorting, screwing, 3C (computer, communication, consumer electronics) packaging, etc.

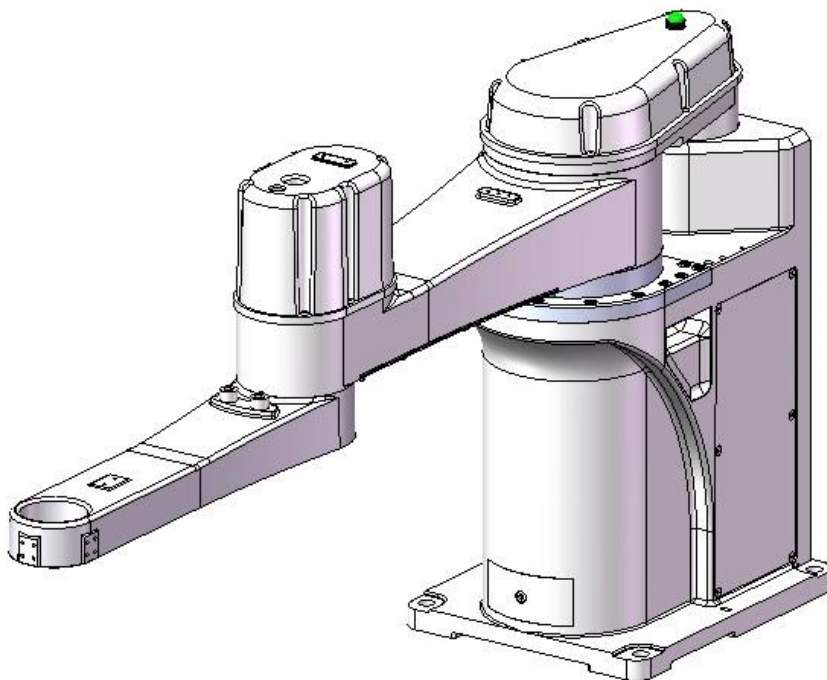


Figure 2-1 Appearance of HM3 Robot

2.2 Product Features

- AIO design without separate control cabinet for less space and easy installation. By adopting a new generation of distributed architecture control system, it is more stable, smoother and easier to use.
- Built-in controller improves electromagnetic compatibility (EMC/EMI) and system stability.
- High precision is perfectly fitting for high-precision laminating and assembly applications.

2.3 Model implication

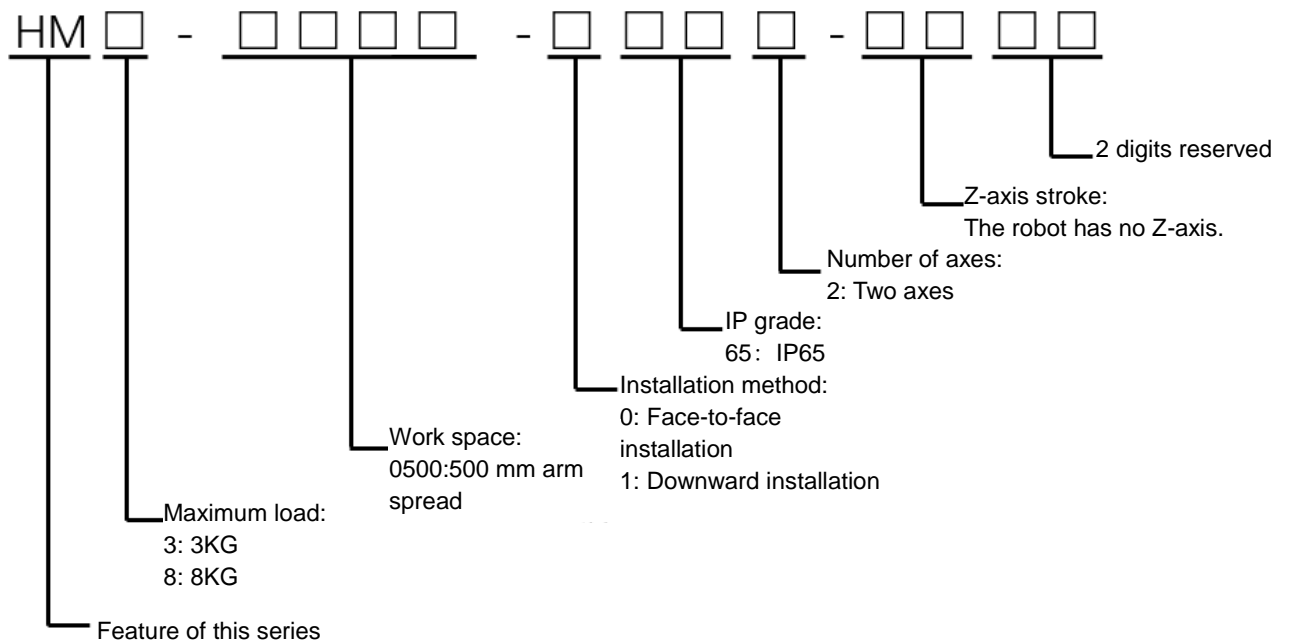


Figure 2-2 Model implication

Table 2-1 Model preview

Model Name	Rated Load (kg)	Maximum Load (kg)	Horizontal Work Space (mm)	Installation	Protection Grade	Operating environment
HM3-0800-0652-000	1	3	800	Tabletop mounting	IP 65	Standards
HM8-0500-0652-000	3	8	500	Tabletop mounting		

Chapter 3 Components and Functional Description

3.1 Introduction to main body

Hermes Robot is mainly composed of a base, a first mechanical arm, a second mechanical arm, and a terminal flange. By taking HM3-0800-0652-0000 as an example, it is introduced below with its appearance and structure shown in Figure 3-1.

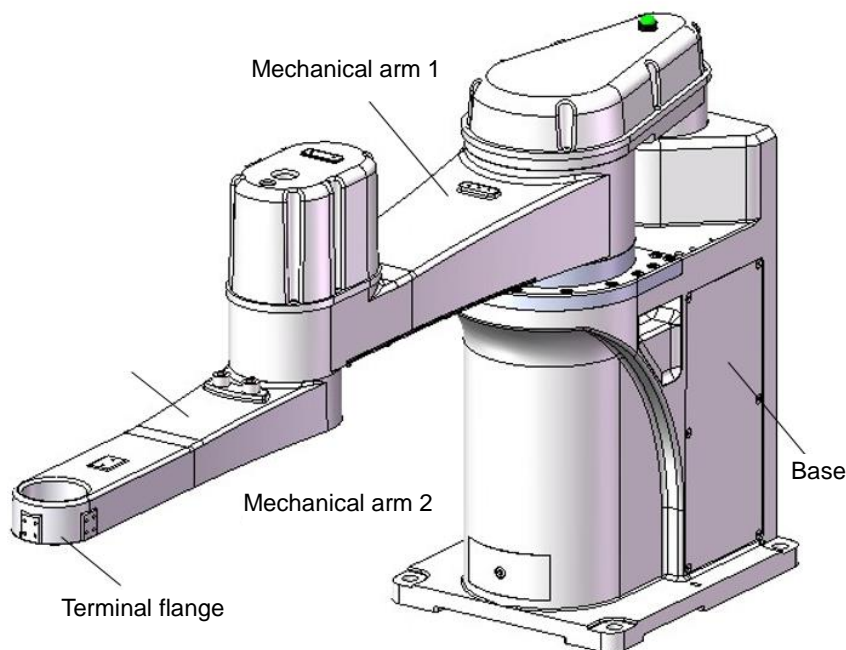


Figure 3-1 Overall structure of Hermes Robot



Hermes Robot has mechanical arms with a length of 500 mm (HM8-0500-0652-0000) and 800 mm (HM3-0800-0652-0000) respectively, which are equipped with the first joint and the second joint of different lengths.

3.1.1 Base

The base control cabinet of Hermes Robot is integrally formed by casting, and a power plug, a power indicator light, communication connectors, etc. are arranged on the interface board of the base back.

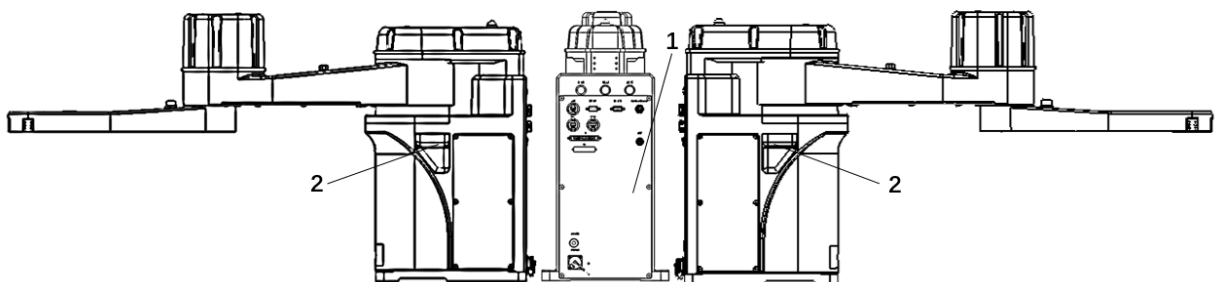
Four through-holes and two pin holes are provided at the installation location of the base for accurate fixation of the robot.

3.1.2 Mechanical arm 2

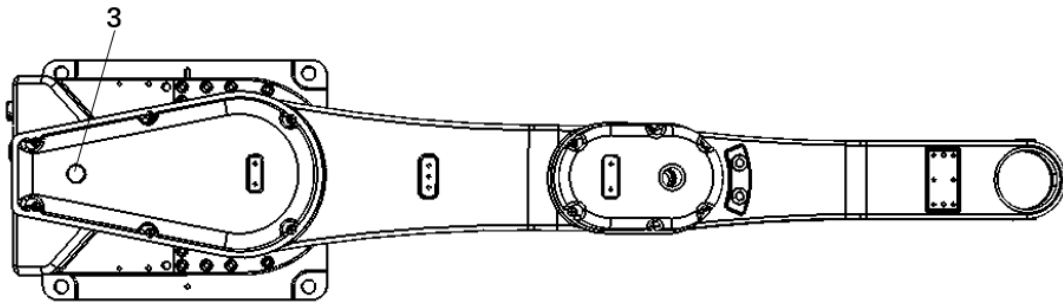
Casting design with light weight is used for improving the performance of the robot.

3.1.3 Cable

Hermes Robot adopts torsion-resistant and high-flexibility cables which can ensure smooth signal transmission of the robot.



(a)



(b)

Figure 3-2 Main view of HM3 Robot

Table 3-1 Components of HM3 Robot

SN	Name	Description
1	Electrical interface panel	For connecting power, Ethernet cables, etc.
2	Grooved handrail	Convenient for users to handle the robot
3	LED Indicators	It indicates the status of the robot. Refer to Section 4.1 for details.



NOTE

For details on the electrical interface panel, please refer to Section 4.1 Introduction of interface panel.

3.2 Trajectory

Joint coordinate of robot control system: The posture of the robot is

represented by rotation angle of each axis.



The "+" and "-" indicating directions of the axes are applicable to the joint coordinate system.

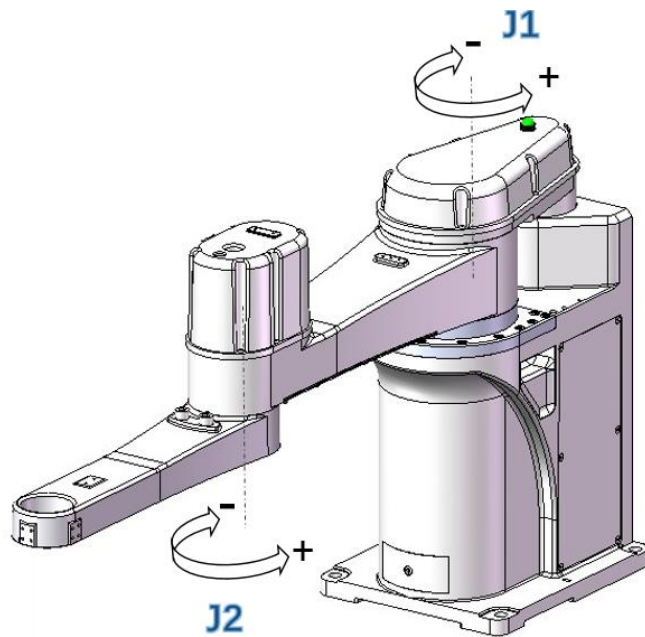


Figure 3-3 Trajectories of each axis

3.3 Work space

3.3.1 Horizontal Work Space

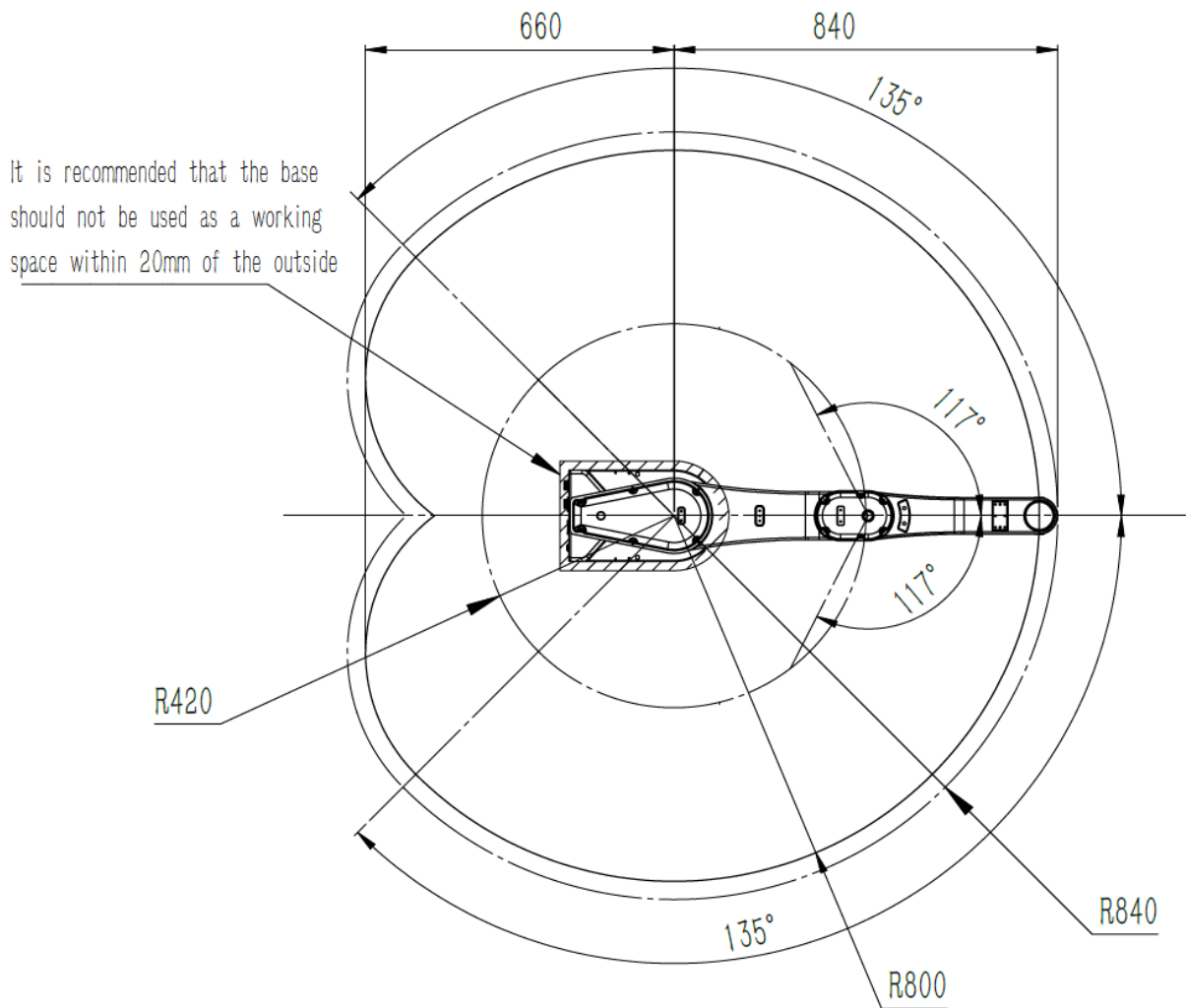


Figure 3-4 HM3-0800-0652-0000 (no hard limit)

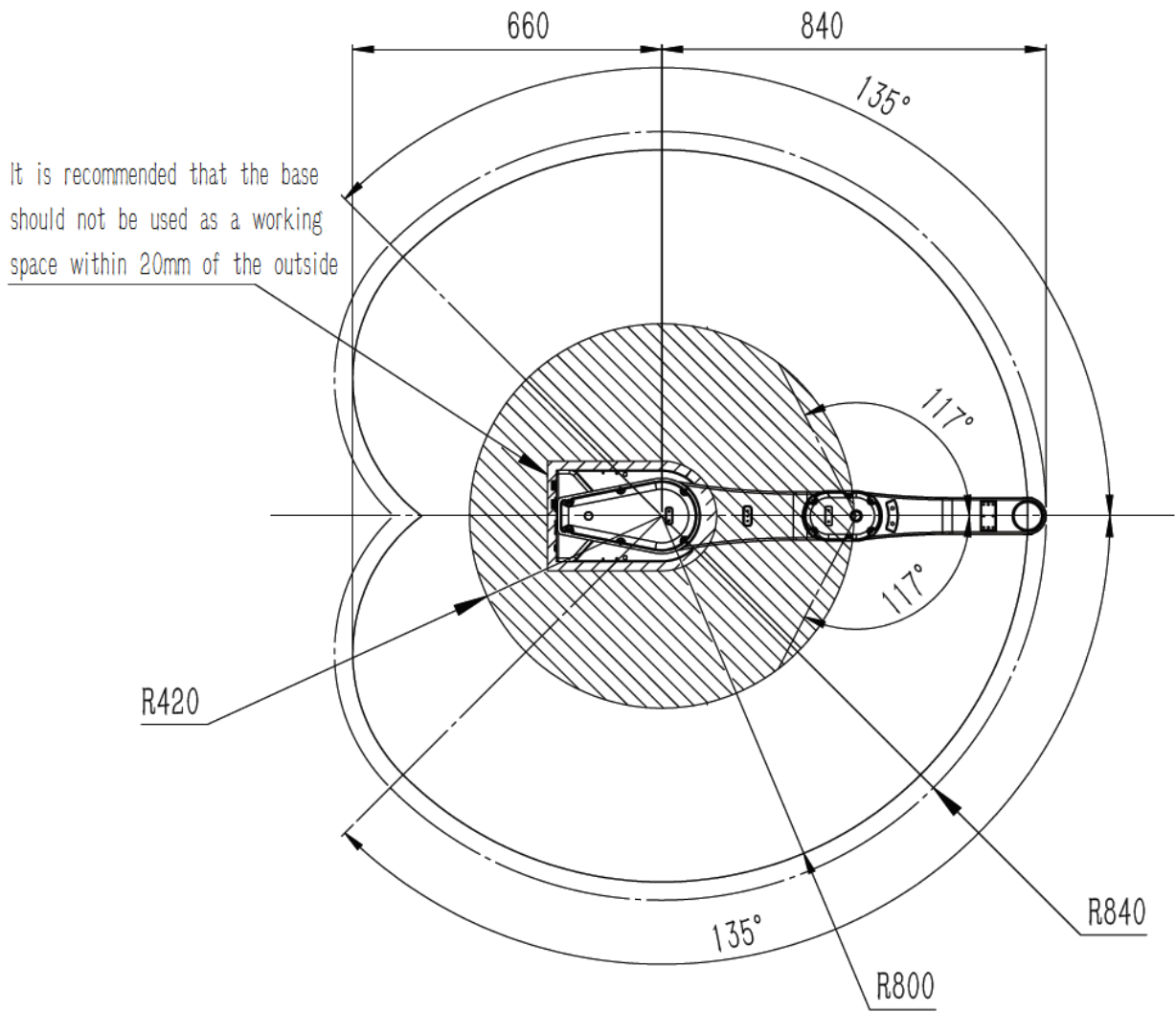


Figure 3-5 HM3-0800-0652-0000 (with hard limit)

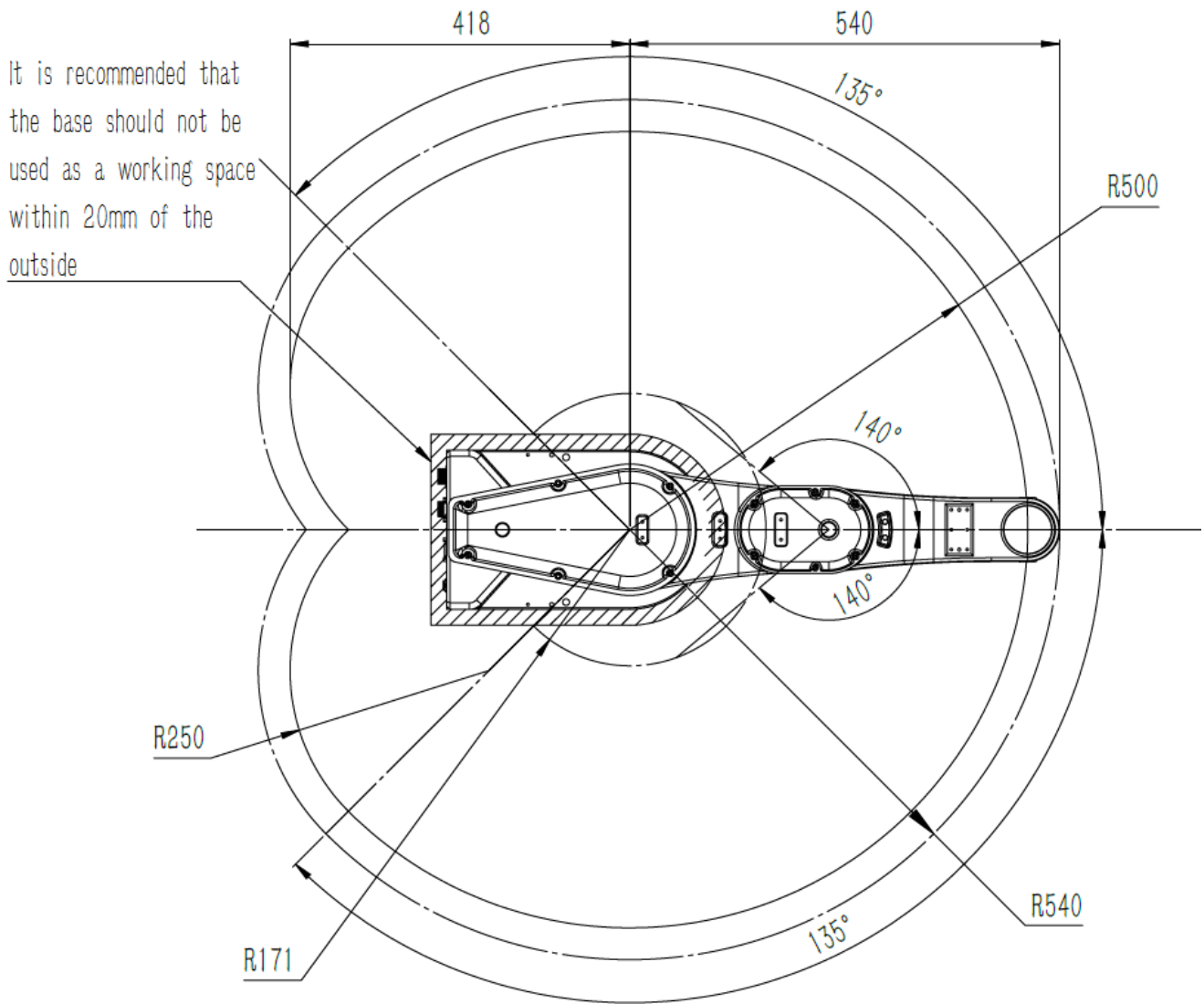


Figure 3-6 HM8-0500-0652-0000(no hard limit)

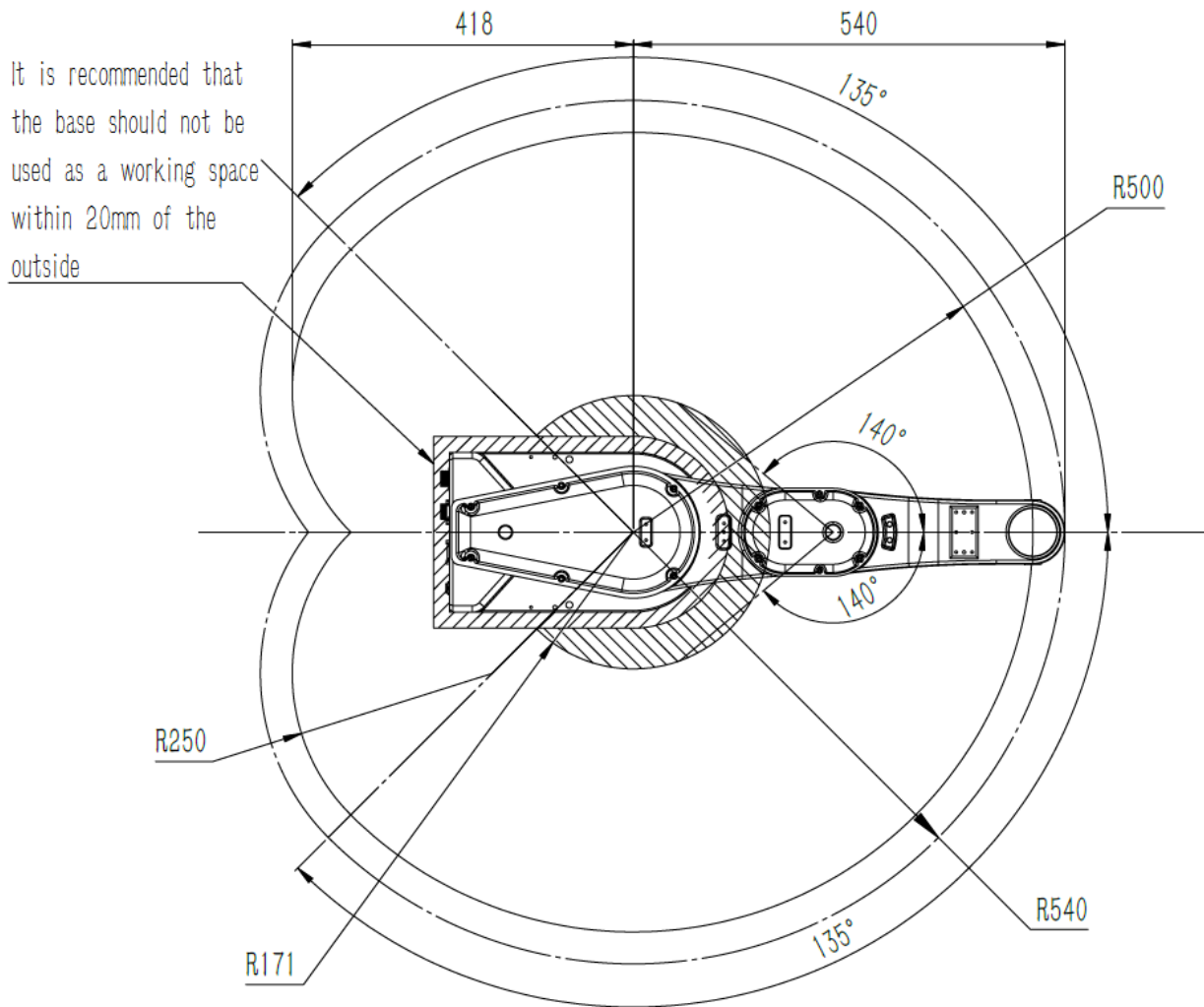


Figure 3-7 HM8-0500-0652-0000(with hard limit))

**NOTICE**

The factory default of the robot is no hard limit. Users can add the hard limit according to the actual situation, and the materials related to the hard limit are not provided for the time being. The screws used for hard limit are 2 * M10*10

3.4 Robot coordinate system

**NOTICE**

The "+" and "-" indicating directions of the axes are

applicable to the cartesian coordinate system.

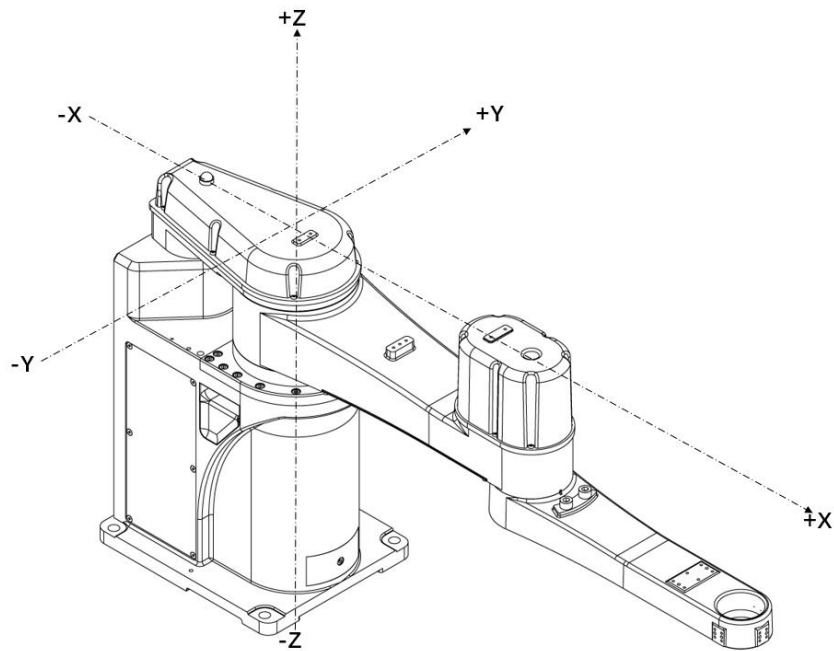
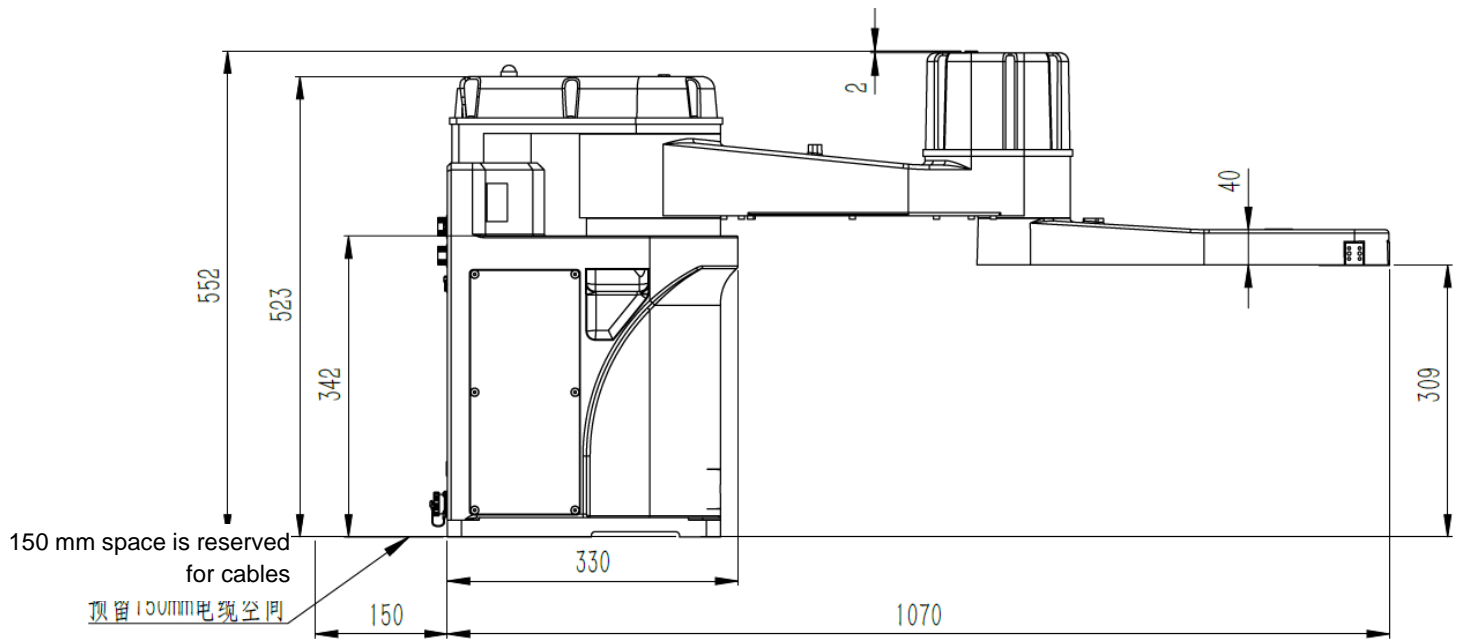


Figure 3-8 World coordinate system

3.5 Specification and dimension

3.5.1 Overall dimension



• HM3-0800-0652-0000

Figure 3-9 Dimensions of HM3 Robot with an arm length of 800 (Unit: mm)

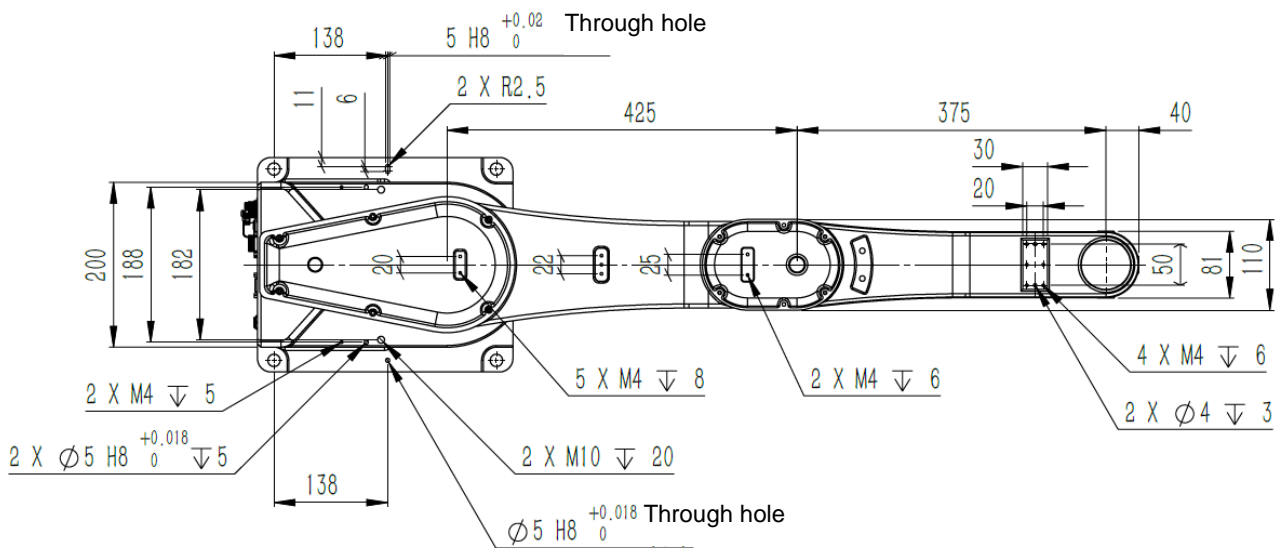


Figure 3-10 Dimensions of HM3 Robot with an arm length of 800 (Unit: mm)

- HM8-0500-0652-0000

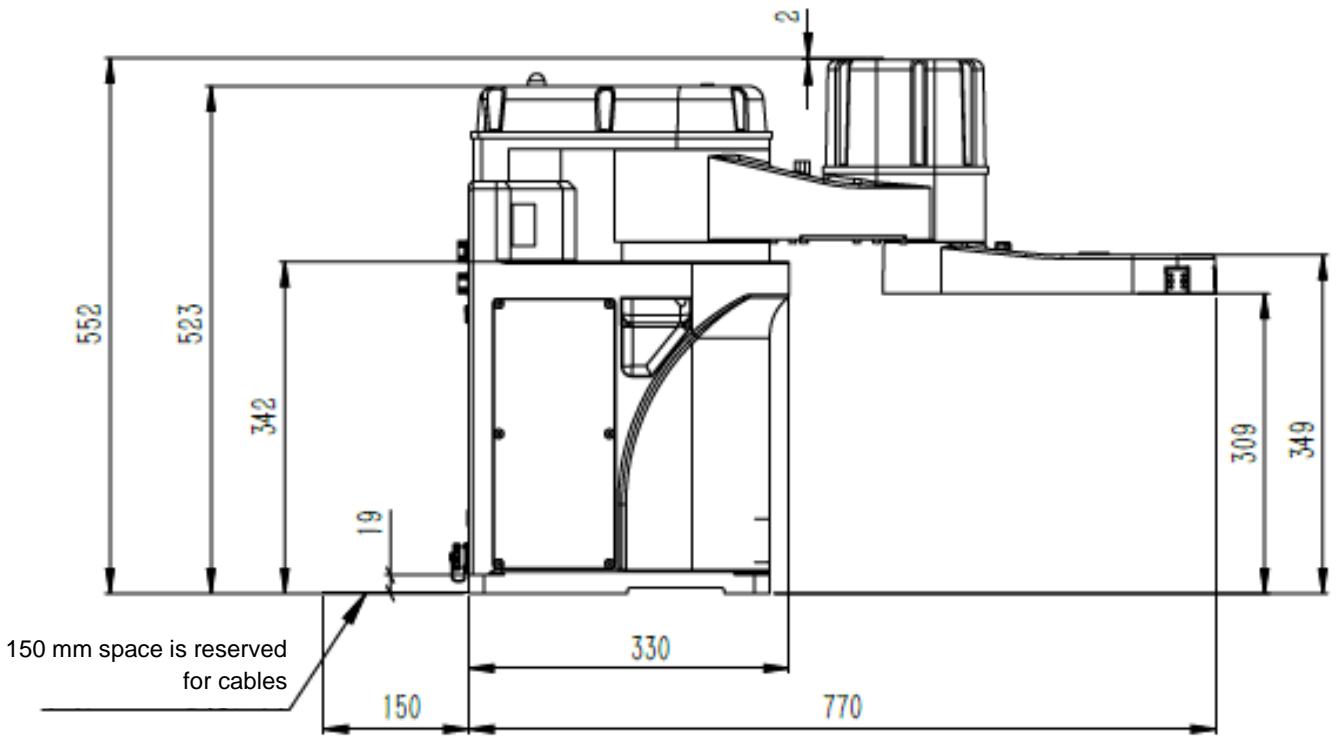


Figure 3-11 Dimensions of HM8 Robot with an arm length of 500 (Unit: mm)

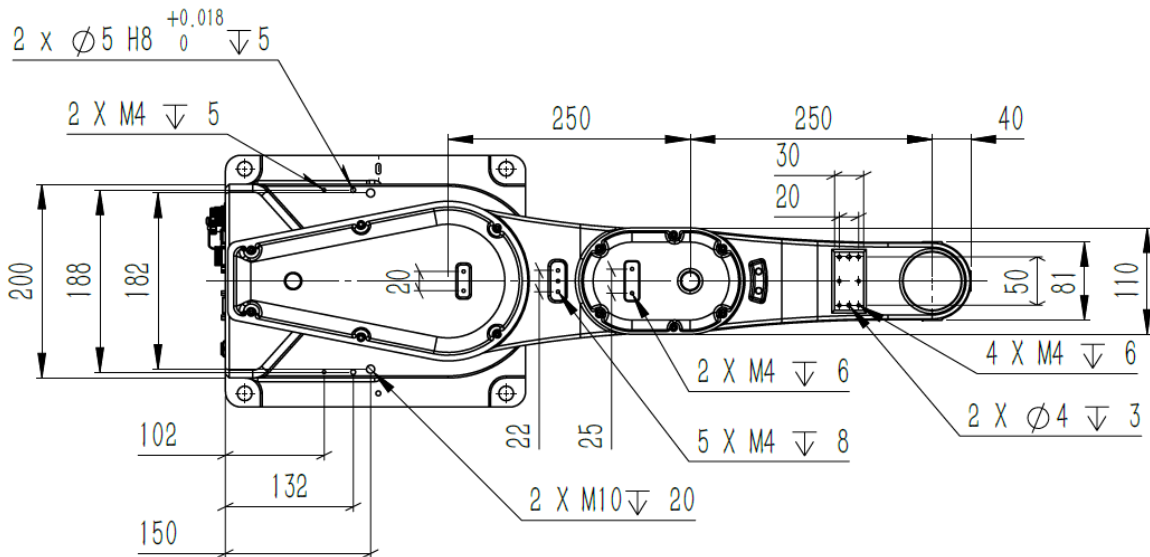


Figure 3-12 Dimensions of HM8 Robot with an arm length of 500 (Unit: mm)

3.5.2 Base dimensions

- HM3-0800-0652-0000

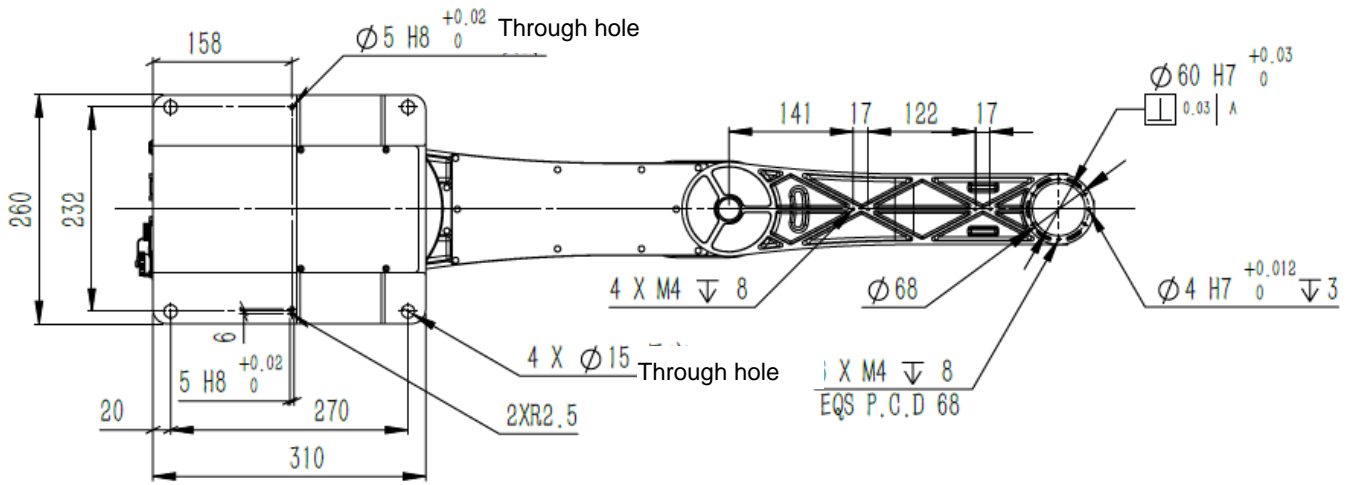


Figure 3-13 Dimensions of HM3 Robot with an arm length of 800 (Unit: mm)

- HM8-0500-0652-0000

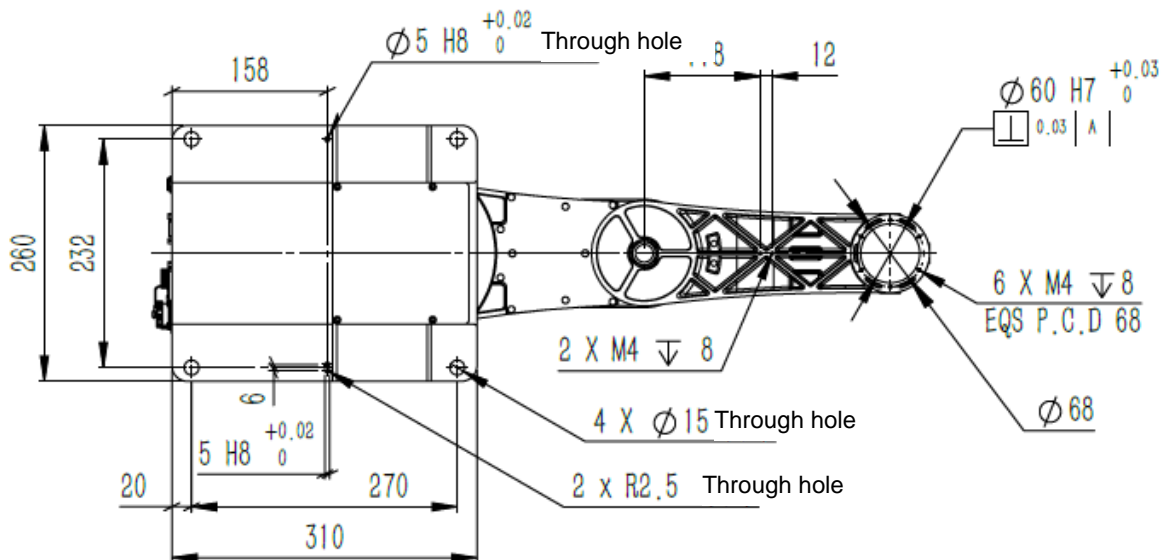


Figure 3-14 Dimensions of HM8 Robot with an arm length of 500 (Unit: mm)

3.6 Technical parameters

Table 3-2 Technical parameters of Hermes Robot

Model Number		HM3-0800-0652-0000	HM8-0500-0652-0000
Arm length (mm)	Full arm length	800	500
	J1	425	250
	J2	375	250
Maximum speed	J1+J2 (mm/s)	11000	7000
Work space	J1(°)	±132	±135
	J2(°)	±135	±140
Repeated positioning accuracy	J1+J2 (mm)	±0.03	±0.025
Rated load (Kg)		1	3
Maximum load (Kg)		3	8
Total weight (kg)		36	35

3.7 Environmental parameters

Install the robot system in an environment that meets the following conditions to exert/maintain the performance of the robot and to ensure safe use.

Table 3-3 Environmental parameters

Installation Environment	Notes
Ambient temperature	0 ~ 40°C
Ambient relative humidity	10% ~ 90%, non-condensing
Ambient environment	Located indoors
	No flammable gas, dust or liquid
	No corrosive gas or substance
	Free from electromagnetic interference source, electrostatic discharge, etc. in the vicinity
Vibration	Free from influence by strong impact and vibration

The robot is not suitable for work in harsh environmental conditions. If used in a place that does not meet the above conditions, we welcome your inquiry.

- If used in an environment where temperature and humidity change greatly, fogging may be caused inside the mechanical arm.



- Do not use it in corrosive environments such as acids or alkalis, otherwise the normal use of the robot would be affected.

3.8 Electrical parameters

Table 3-7 Robot electrical parameters

Item	Parameter
Rated voltage	230V a.c. 50/60Hz
Rated Power	2 kW
Motor brake voltage	24 V d.c.
I/O interface	20 universal digital inputs, 6 high-speed inputs, 2 analog inputs, 18 universal digital outputs
Communication interface	Ethernet, RS-232, RS-485
Noise level	≤ 80dB

Chapter 4 Introduction to Electrical Interfaces

4.1 External electrical interface

The electrical interfaces of Hermes Robot mainly include power interface, communication interface and user interface, etc., which are distributed on the base, as shown in the Figure 4-1.

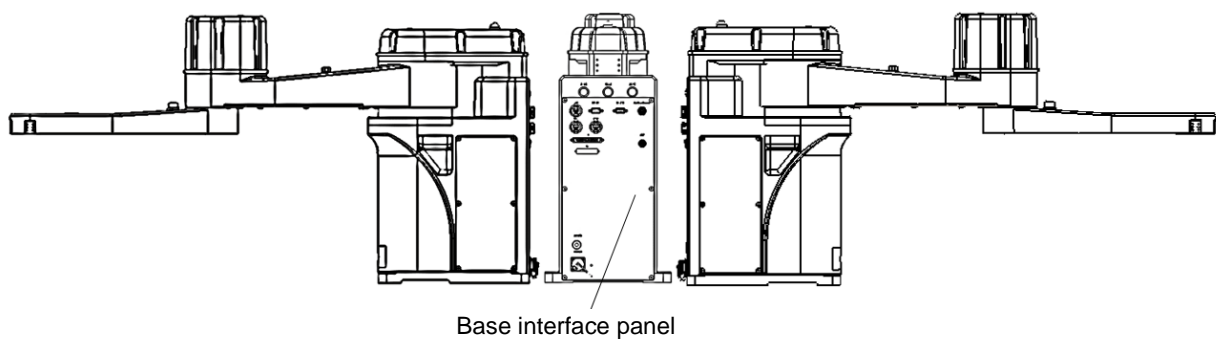


Figure 4-1 External interface panel

4.1.1 Base interface panel

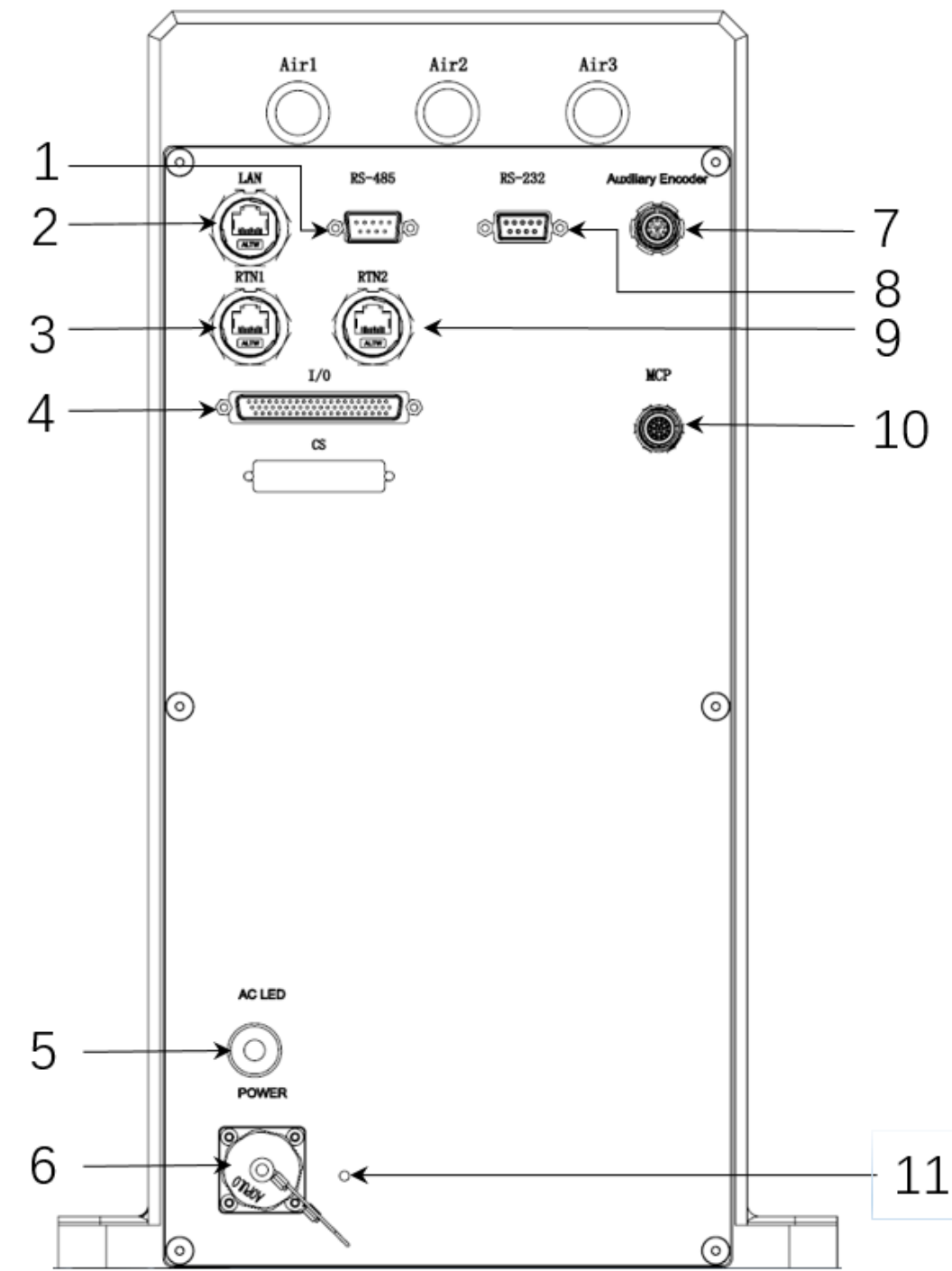


Figure 4-2 Schematic diagram of interface panel

Table 4-1 Introduction of interface panel

SN	Name	Description
1	RS-485	Communication interface
2	LAN	Ethernet interface
3	RTN1	Real-time Ethernet interface 1
4	I/O	Digital input/output interface and analog input interface
5	AC LED	Main power indicator
6	POWER	Power interface
7	Auxiliary Encoder	Auxiliary encoder interface
8	RS-232	Communication interface
9	RTN2	Real-time Ethernet interface 2
10	MCP	Emergency stop component interface/teach pendant interface
11	Grounding screw hole	Common ground terminal for housing protective grounding

4.2 Indicator description

Hermes Robot is equipped with AC LED light on the base interface panel and system indicator light of the first mechanical arm. The status of the indicators is described below.

4.2.1 Main power indicator

Table 4-2 Description of power indicator

State	Description
OFF	Indicates that the robot is not powered on.
ON (red)	Indicates that the robot is powered on.

4.2.2 System indicator (Mechanical arm 1)

The system indicator is located at the top of the first mechanical arm of the robot. It is a circular LED light and shows different colors when the robot works. The status of the system indicator is described below.

Table 4-3 Description of system indicator status

State	Description
OFF	Indicates that the robot is not in the servo state.
Flashing	Indicates that the robot system is starting or being servoed.
ON (green)	Indicates that the robot has entered the servo state.

4.3 Definition of interface pins

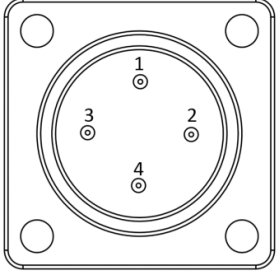


This section provides functions and descriptions of pins on each interface of the interface panel. The operations must be performed in accordance with the descriptions of the

pins.

4.3.1 Power interface (POWER)

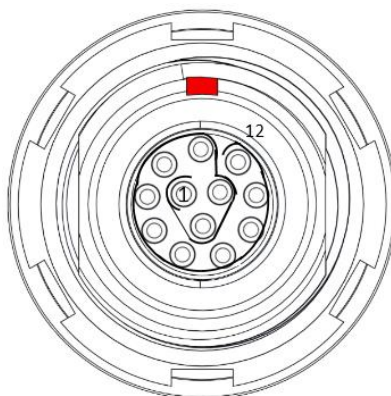
Table 4-4 Definition of power interface pins

Pin	Function	Description	230 V a.c. Power Interface
1	L	Live wire	 <p>4-pin male front pinout</p>
2	N	Neutral wire	
3	PE	Ground wire	
4	/	Idle	

4.3.2 Auxiliary encoder

Table 4-5 Definition of auxiliary encoder pins

Auxiliary Encoder			
Axis No.	Pin	Function	Description
Axis 1	01	Output +5 V d.c.	5 V d.c. output power
	02	GND	Common ground
	03	1A+	Axis 1 A+
	04	1B+	Axis 1 B+
	05	1Z+	Axis 1 Z+
	06	F.G	Shielded wire
Axis 2	07	Output +5 V d.c.	5 V d.c. output power
	08	GND	Common ground
	09	2A+	Axis 2 A+
	10	2B+	Axis 2 B+
	11	2Z+	Axis 2 Z+
	12	F.G	Shielded wire



12-pin female front pinout

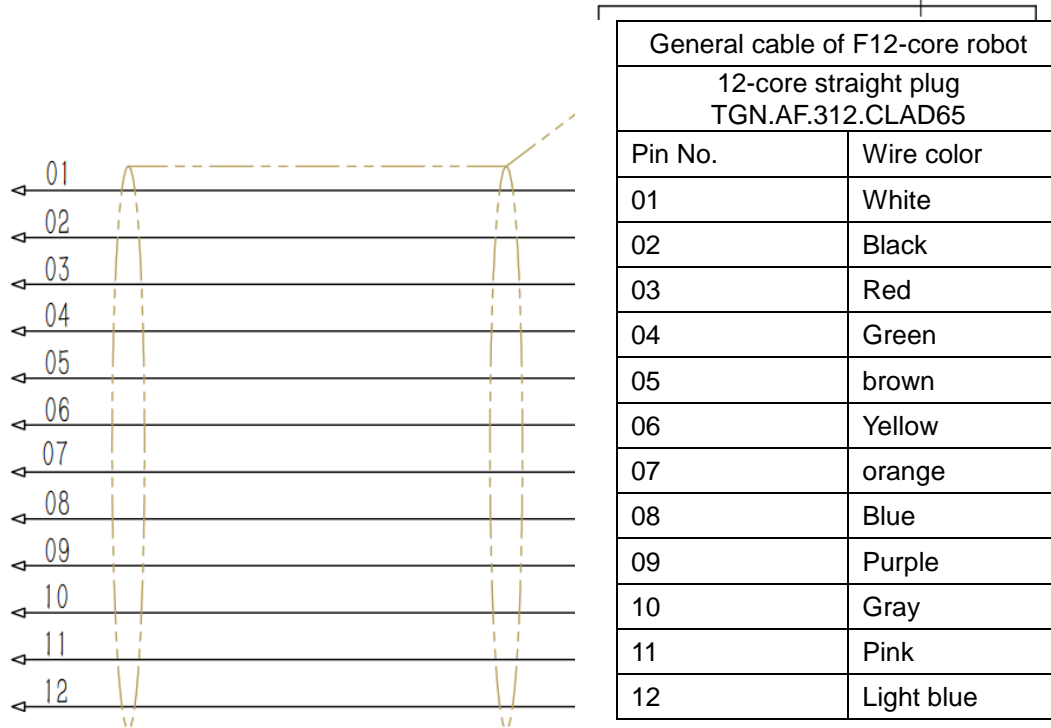


Figure 4-3 Auxiliary encoder

- The 5V pin in the auxiliary encoder interface indicates a DC output power supply.
- Do not connect external power supply to the 5V auxiliary encoder pin, otherwise the internal circuit of the robot will be burnt.



- The auxiliary encoder and main encoder on the same axis share one-way 5V power supply, with maximum continuous output current of 500 mA; typical overcurrent protection of 1A lower limit: 0.75A, upper limit: 1.25A)

4.3.3 MCP interface (MCP/E-stop)

The MCP interface pins are defined as follows, where function 1 is enabled when an external manual control pendent (MCP) is connected, and function 2 is enabled under emergency conditions.



NOTE

- MCP/emergency stop is classified as type 1

Table 4-6 MCP Definition of MCP pins

MCP interface			
19-pin female interface			
Pin	Function 1 (MCP)	Function 1 description	Function 2 (emergency stop)
01	Auto/Manual 2	Auto/manual mode 2	/
02	Output 24 V d.c.	24 V d.c. output	/

		power	
03	Auto/Manual 1	Auto/manual mode 1	/
04	Output 24 V d.c.	24 V d.c. output power	/
05	BI_D4+	Two-way data +	/
06	BI_D4-	Two-way data -	/
07	E-STOP_0	Emergency stop contact 0	E-STOP_0
08	GND	Common ground	GND
09	/	/	/
10	/	/	/
11	E-STOP_2	Emergency stop contact 2	E-STOP_2
12	GND	Common ground	/
13	GND	Common ground	GND
14	BI_D3+	Two-way data +	/
15	BI_D3-	Two-way data -	/
16	TX_D1+	Transmit data +	/
17	TX_D1-	Transmit data -	/
18	RX_D2+	Receive data +	/

19	RX_D2-	Receive data -	/
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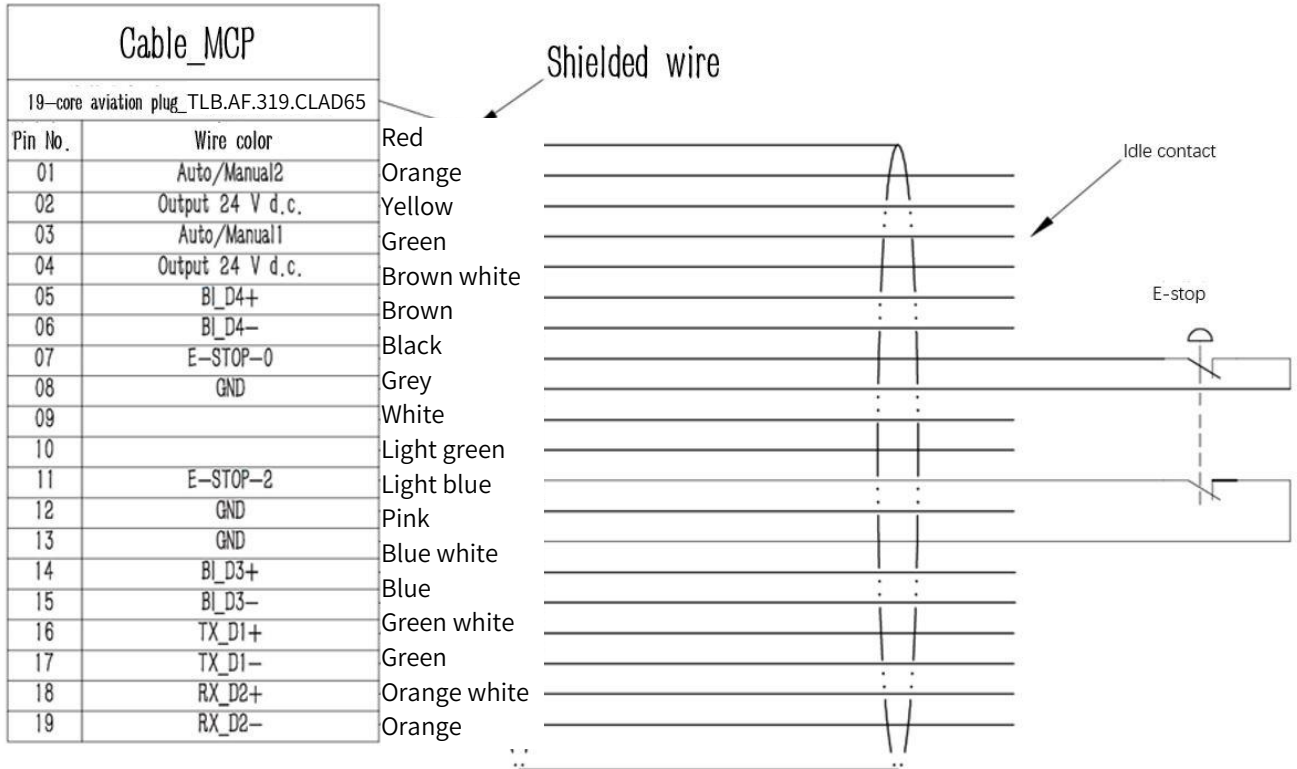


Figure 4-4 Wiring diagram of E-stop device

4.3.4 Communication interface (RS-232)

Table 4-7 Definition of RS-232 pins

Definition of RS-232 pins		
Pin	Function	Description
01	/	Unused
02	RXD	Receive data
03	TXD	Transmit data
04	/	Unused
05	GND	Ground terminal

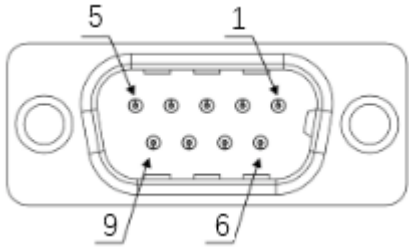
9-pin male front pinout

06	/	Unused	
07	/	Unused	
08	/	Unused	
09	/	Unused	

4.3.5 Communication interface (RS-485)

Table 4-8 Definition of RS-485 pins

Definition of RS-485 pins		
Pin	Function	Description
01	/	Unused
02	/	Unused
03	/	Unused
04	/	Unused
05	/	Unused
06	/	Unused
07	GND	Ground terminal
08	RS485+	RS485+
09	RS485-	RS485-

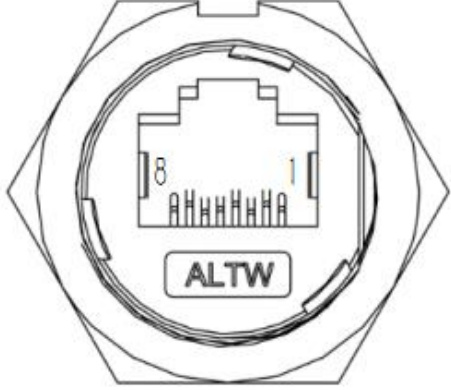


9-pin female front pinout

4.3.6 Ethernet interface (LAN/RTN1/RTN2)

Table4-9 Definition of Ethernet interface pins

Ethernet interface		
Pin	Signal name	Description
01	TX_D1+	Transmit data
02	TX_D1-	Transmit data
03	RX_D2+	Receive data +
04	BI_D3+	Two-way data
05	BI_D3-	Two-way data
06	RX_D2-	Receive data -
07	BI_D4+	Two-way data
08	BI_D4-	Two-way data

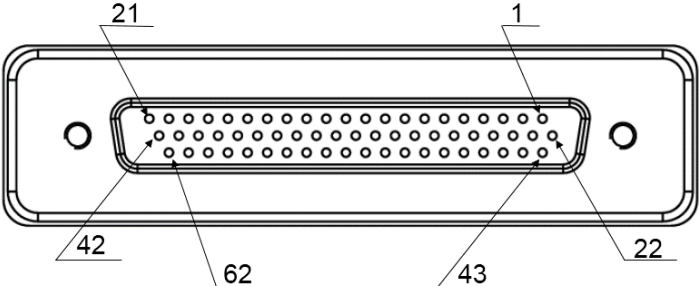


8-core positive pinout

4.3.7 Digital input/output interface (I/O)

For easy programming, each pin of the IO interface is defined with a corresponding number. The following provides the definition, function, corresponding signal code and description of each pin on the interface, as shown in Figure 4-11.

Table 4-10 Definition of I/O interface pins

Definition of I/O interface pins			
 <p>62-core female front pinout</p>			
Pin	Function	Signal code	Description
01	E-DO_1	20101	General output 1
02	E-DO_2	20102	General output 2
03	Output 24 V d.c. ^①	/	24 V d.c. output power
04	GND	/	Common ground
05	E-DO_3	20103	General output 3
06	E-DO_4	20104	General output 4
07	E-DO_5	20105	General output 5
08	E-DO_6	20106	General output 6

09	Output 24 V d.c. ^①	/	24 V d.c. output power
10	GND	/	Common ground
11	E-DO_7	20107	General purpose output 7
12	E-DO_8	20108	General purpose output 8
13	E-DO_9	20109	General output 9
14	E-DO_10	20110	General purpose output 10
15	Output 24 V d.c. ^①	/	24 V d.c. output power
16	GND	/	Common ground
17	E-DO_11	20111	General output 11
18	E-DO_12	20112	General purpose output 12
19	E-DO_13	20113	General output 13
20	E-DO_14	20114	General output 14
21	Output 24 V d.c. ^①	/	24 V d.c. output power
22	GND	/	Common ground
23	E-DO_15	20115	General output 15
24	E-DO_16	20116	General output 16
25	E-DO_17	20117	General output 17

26	E-DO_18	20118	General output 18
27	Output 24 V d.c. ^①	/	24 V d.c. output power
28	GND	/	Common ground
29	E-HDI_1	30101	High speed input 1
30	E-HDI_2	30102	High speed input 2
31	E-HDI_3	30103	High speed input 3
32	E-HDI_4	30104	High speed input 4
33	HGND	/	High speed input common ground
34	E-DI_1	10101	General input 1
35	E-DI_2	10102	General input 2
36	E-DI_3	10103	General input 3
37	E-DI_4	10104	General input 4
38	E-DI_5	10105	General input 5
39	E-DI_6	10106	General input 6
40	E-DI_7	10107	General input 7
41	E-DI_8	10108	General input 8
42	GND	/	Common ground
43	E-DI_9	10109	General input 9
44	E-DI_10	10110	General input 10
45	E-DI_11	10111	General input 11

46	E-DI_12	10112	General input 12
47	E-DI_13	10113	General input 13
48	E-DI_14	10114	General input 14
49	E-DI_15	10115	General input 15
50	E-DI_16	10116	General input 16
51	E-DI_17	10117	General input 17
52	E-DI_18	10118	General input 18
53	E-DI_19	10119	General input 19
54	E-DI_20	10120	General input 20
55	GND	/	Common ground
56	E-HDI_5	30105	High speed input 5
57	E-HDI_6	30106	High speed input 6
58	HGND	/	High speed input common ground
59	Ain	60101	Analog input 1
60	AGND1	/	Analog input common ground 1
61	Ain2	60102	Analog input 2
62	AGND2	/	Analog input common ground 2

Note 1: The rated current of one-way 24V DC output power supply is 1A;
 The 24V DC output power supply cannot be connected to external devices, but can only be used for I/O output.

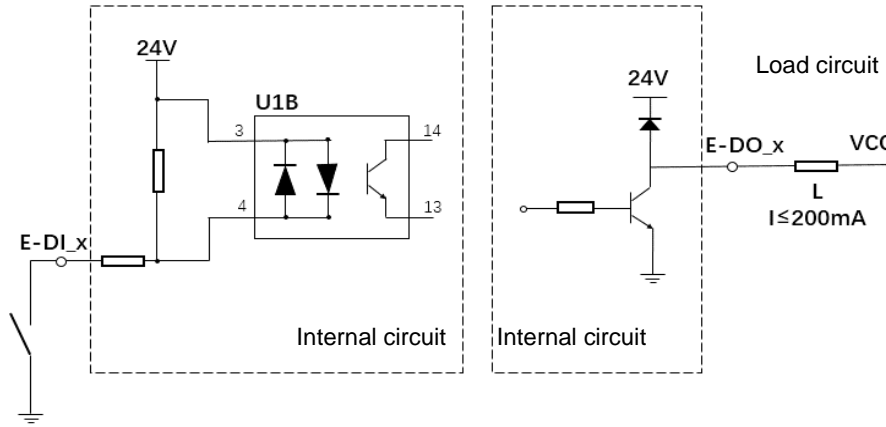


Figure 4-5 Diagram of input circuit (left) and output circuit (right)

1. The ordinary digital output DO indicates NPN output in open-circuit mode, with a maximum operating frequency of 1kHz, and a maximum current of less than 200mA;

2. The ordinary digital input DI indicates input in PNP mode, with a maximum operating frequency of 1kHz;



3. The high-speed digital input HDI indicates input in PNP mode, with a maximum operating frequency of 1MHz;

4. Range of DI/HDI trigger level: logic 1 (relative to the reference pin) > 11V; logic 0 (relative to the reference pin) <

5V;

5. The analog input AI is $\pm 10V$, with a maximum operating frequency of 10kHz, a sampling rate of 100kSPS, and a peak sampling accuracy of $\pm 2\%$;
 6. When the 24V DC output power supply of the I/O interface is used in conjunction with the DO, it serves as an active output to provide energy to the outside and can be connected to resistive, inductive and capacitive loads. The one-way 24V DC power supply has a maximum output current of less than 1A, and can be used for up to 4-way DO at the same time, otherwise the internal protection circuit of the system would be burned out due to overcurrent.
 7. To ensure reliable and stable operation of the load, it should be connected to an external 24V power supply in conjunction with DO.
-

Chapter 5 Product Installation

The installation of the robot is critical to its function. Special attention should be paid to the fixing of the base and the foundation needs to be able to withstand the impact load generated from the acceleration of the robot. Install this robot according to the following requirements.

5.1 Installation requirements

Users should design and produce the rack for fixing the robot by themselves. The shape and size of the rack may vary depending on the purpose of the robot system.

The rack must withstand the weight of the robot and the dynamic force produced when the robot acts at the maximum acceleration. More crosspieces should be installed to provide sufficient strength. The requirements for installing the rack are as follows.

- The bottom surface of the robot is parallel to the mounting surface.
- The area of the mounting surface is not less than that of the bottom surface of the robot.
- Fix the rack externally (on the ground) and ensure that it will not move.
- The holes on the rack for installing the mechanical arm should be M12

threaded holes. When installing the mechanical arm, use bolts with a strength meeting ISO898-1 property class 10.9 or 12.9.



If 4040 square tube is used for welding, ground screws (not less than M12) should be used for fixation.

In order to suppress vibration, the installation panel of the mechanical arm should be iron plate with a thickness of 20 mm or more, a surface roughness of 25 μm or less and a flatness of less than 0.5 mm.

- The poor accuracy of the installation surface would degrade the positioning accuracy of the robot.



- If the stiffness or stability of the rack is insufficient, or sheet metal is mounted on the rack, the robot would vibrate (resonate) during operation, which may adversely affect the operation.
-

To ensure enough space for installation of cables, a space of more than 150 mm must be reserved at the back of the base.

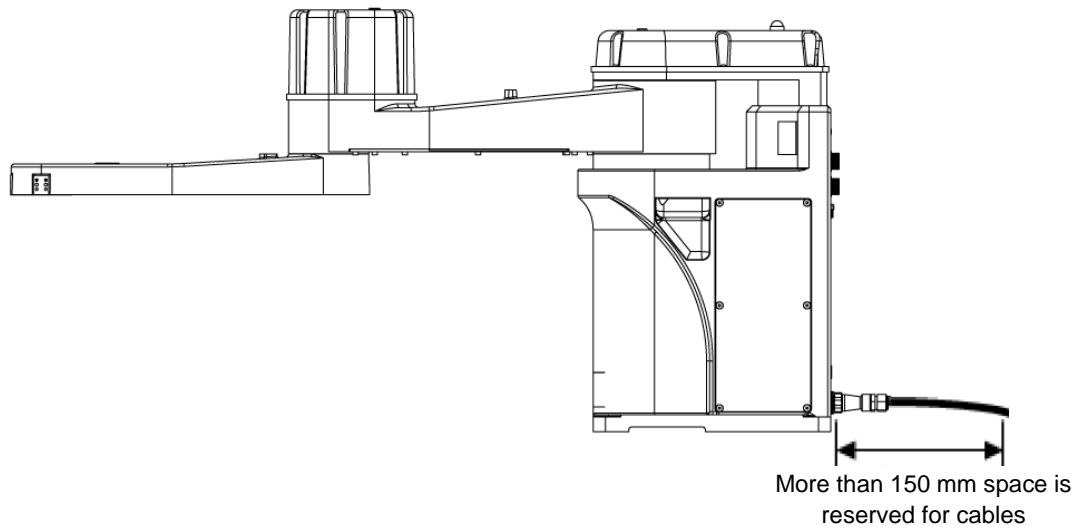


Figure 5-1 Reserved space at the back of the base

- Installation example

Fix the bottom plate on the ground with anchor bolts (M12 or more). The bottom plate must be sufficiently strong and rigid. The bottom plate with a thickness of 20mm or more is recommended.

Position and install the robot base through four installation holes and two pin holes. Then use the hex socket bolts (M12*40), spring washers and flat washers to fix the robot base. To prevent the hex socket bolts from loosening during the operation of the robot, please follow the method described to tighten them.

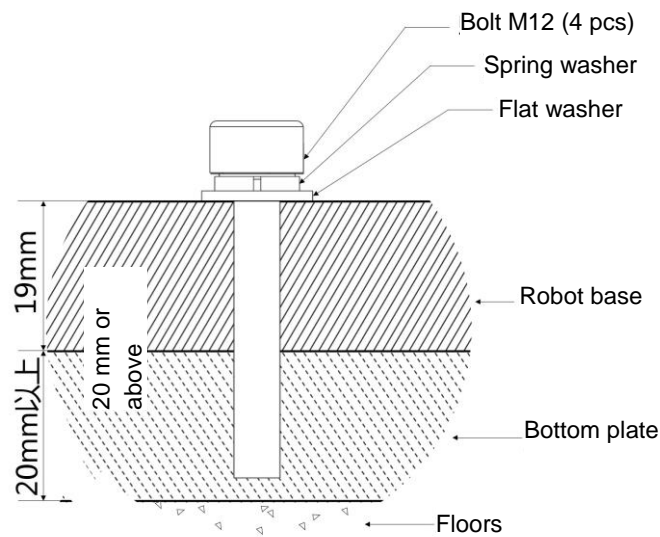


Figure 5-2 Installation diagram

5.2 Product confirmation

After unpacking, confirm the product components and status according to the packing list. The standard packing list should contain:

- HM3 Robot body
- Accessories box (containing user manual)



In case of any damage or component incompleteness after unpacking, please contact QKM or local office.

5.3 Installation site and environment

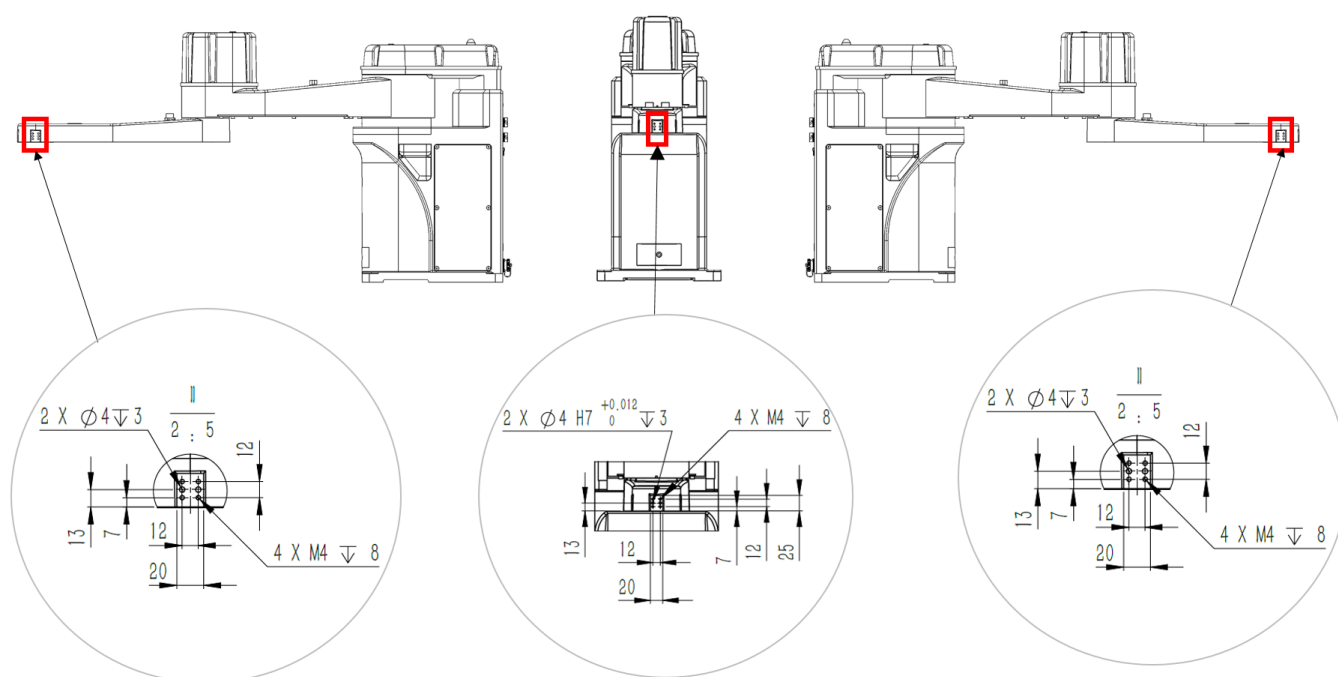
The installation of HM3 Robot shall meet the following conditions:

- The ambient temperature during transportation maintains at 0 ~ 40°C.

- In a dry place with low humidity. With relative humidity of 10% ~ 90% and free from dewing.
- The site causes small vibration and impact to the robot (vibration of less than 0.5G)
- The robot must be installed away from flammable or corrosive liquids or gases and sources of electrical interference.

5.4 Installation of external parts

External equipment, such as vision camera, solenoid valve, etc. can be installed through the three sets of holes at the front side of the second mechanical arm



of Hermes Robot. The installation dimensions for the fixing position are shown in Figure 5-3.

Figure 5-3 Installation position of external parts (unit: mm)

5.4.1 Installation of camera (optional)

Install the camera as shown in the figure. The figure only shows one installation method. You can install the camera as required. If you use the installation method as shown in the figure, M4 screw holes are available here, and you should prepare the screws and camera fasteners by yourself.

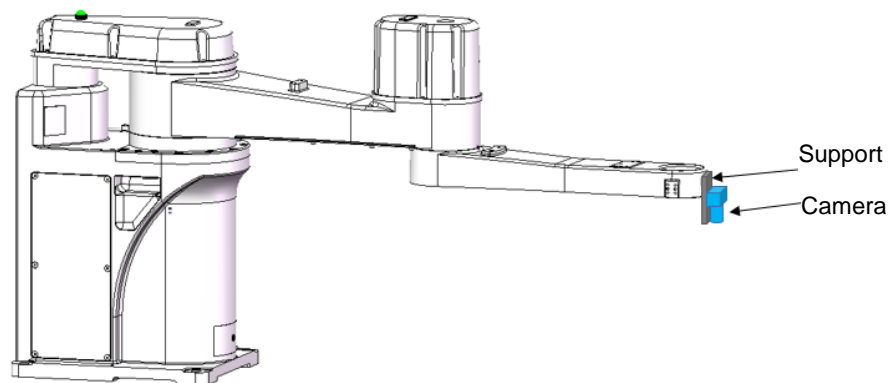


Figure 5-4 Camera installation diagram

5.5 Handling of robot

Use a forklift or the like to handle the robot in a packed state as far as possible. Comply with the following requirements when handling and unpacking the robot.

The installation should be performed by qualified personnel. Take care not to impact the equipment when unpacking.



- The robot should be lifted with crane or handled with forklift by professionals. Serious injuries or damage would be caused if the operation is performed by non-professionals.

- When lifting the robot, hold it by hand to ensure balance. If the lifting is unstable, serious injury or major damage may be caused due to the falling of the robot.
- The packing box of the robot should be placed vertically upwards. Handle it with care and prevent it from damage due to collision.
- Do not remove the fixing bolts, or the robot fixed on the handling pallet would roll over. Be careful to avoid clamping your hands or feet by the robot.
- The robot must be held by at least two persons with their hands when handling it with a forklift or a crane.

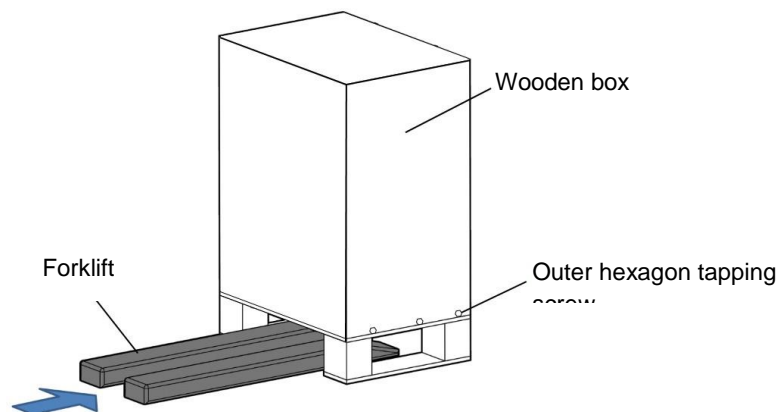


Figure 5-5 Schematic diagram of packaging and transportation

After transporting to the designated site, use an adjustable wrench to remove the self-tapping screws from the bottom side of the wooden box, then take out the wooden box upwards and store it properly.

5.6 Base installation

Table 5-1 Tightening torque

Model Number	Fixing bolt (Hex socket bolt)	Tightening torque
HM3-0500-0652-0000 HM3-0800-0652-0000	M12*40	100 N·m

Use bolts, elastic washers and flat washers to install the base. The dimensions and installation of the bolts and washers are shown in Figure 5-6.

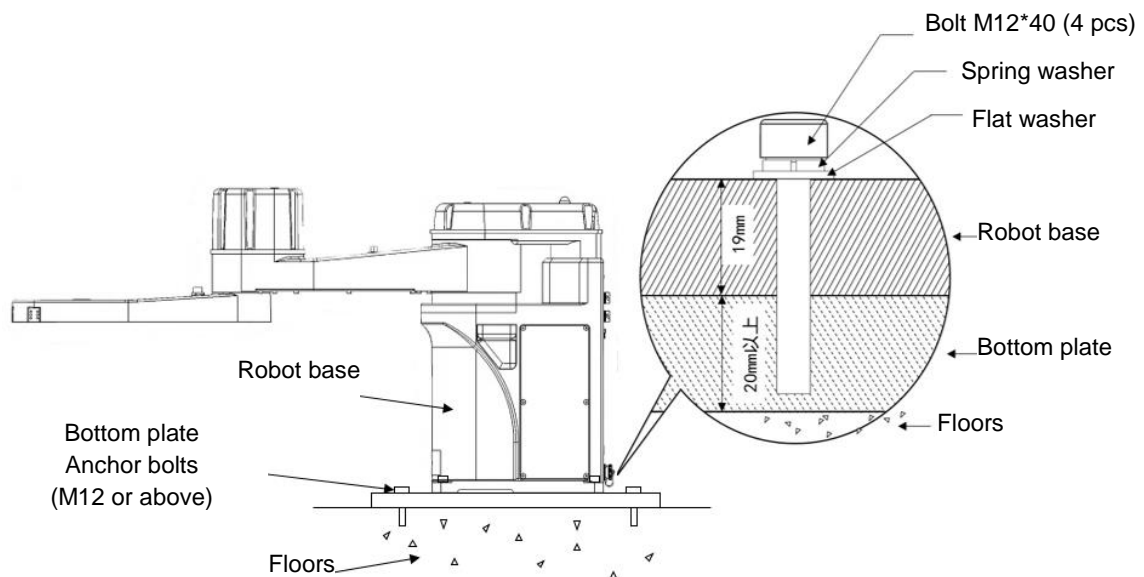


Figure 5-6 Install bolts on the base



注意 • The base of the robot must be installed by at least two
CAUTION professionals. Pay full attention to avoid damage due to

mechanical arm movement or to prevent hands or feet from being clamped.

- Fix the robot onto the rack with specified number of bolts meeting the requirement of tightening torque. The robot would tilt if failing to observe the rules.

5.7 Installation of robot cable

- Connect the robot to other equipment when the robot is powered off.
- The bending or breaking of cable connector pins and cable damage may cause anomalies when connecting to the robot. Check whether the above conditions exist before connection.
- When cabling the robot, do not interfere with the motion of the robot. Interference would be caused in the area where the robot cable is located and load is applied at the front end of the robot. Do not regard it as the work area to avoid damage to the cable of the robot.



Do not plug or unplug the cable connector when the robot is powered on, or the internal circuit may be burnt out.

5.8 Ground protection

Each Hermes Robot is labeled with a "Ground Protection" sign and equipped with a ground terminal. Connect the ground terminal of the robot base to the external protective conductor.

- Be sure to ground the robot to prevent electric shock.



NOTICE

- Perform grounding operations before turning on the power.

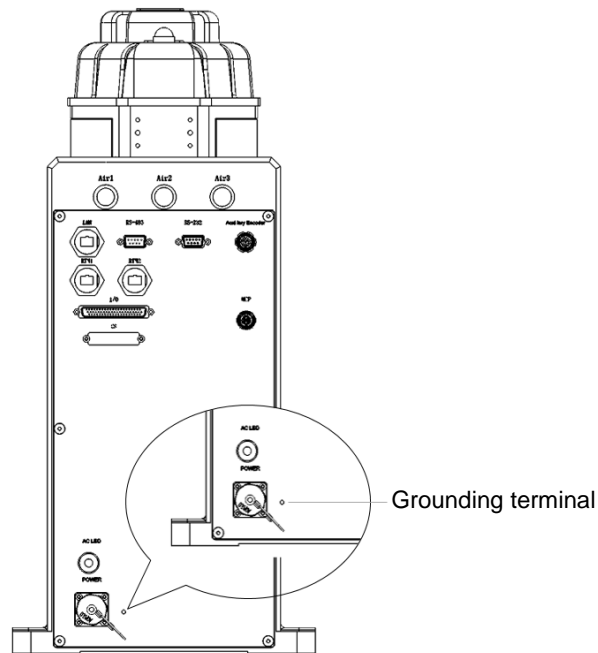


Figure 5-7 Grounding diagram

5.8.1 Communication connection

Hermes Robot communicates via Ethernet.

Cable to be used: CAT5E network cable

Step 1 Install one end of the network cable to the "Ethernet" interface on the interface panel of the robot back.

Step 2 Insert the other end of the network cable into the PC or IPC port as shown in Figure 5-9.

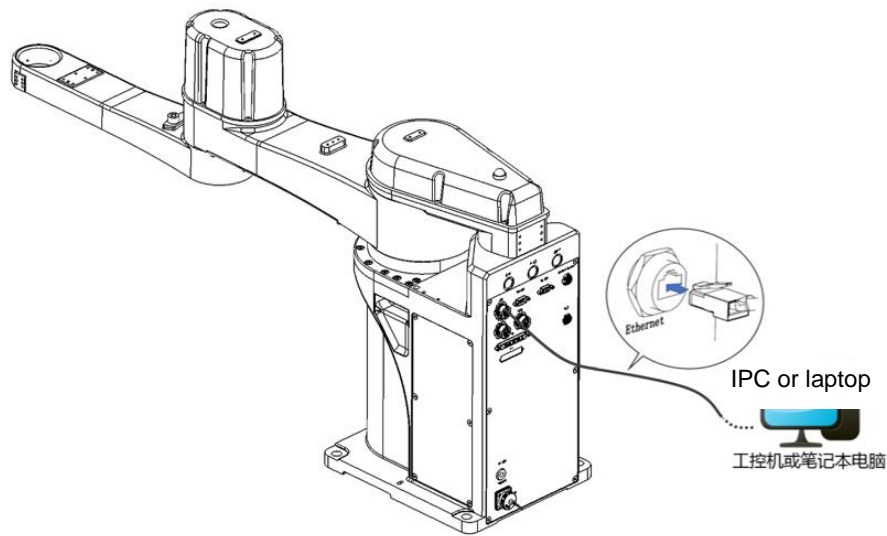


Figure 5-8 Schematic diagram of communication connection

5.8.2 Connection of emergency stop device

HM3 Robot is provided with an E-stop device with cable at delivery.



NOTE

If a teach pendant is purchased, you need to prepare the teach pendant, and then install and use the cables according to the teach pendant user manual.

Cable to be used: cable for emergency stop device

The wiring steps are shown below.

Step 1 Take out the provided emergency stop device and install its aviation plug at the "MCP" interface on the interface panel of the robot.

Step 2 Place the emergency stop button box in a position that will allow easy operation by users.

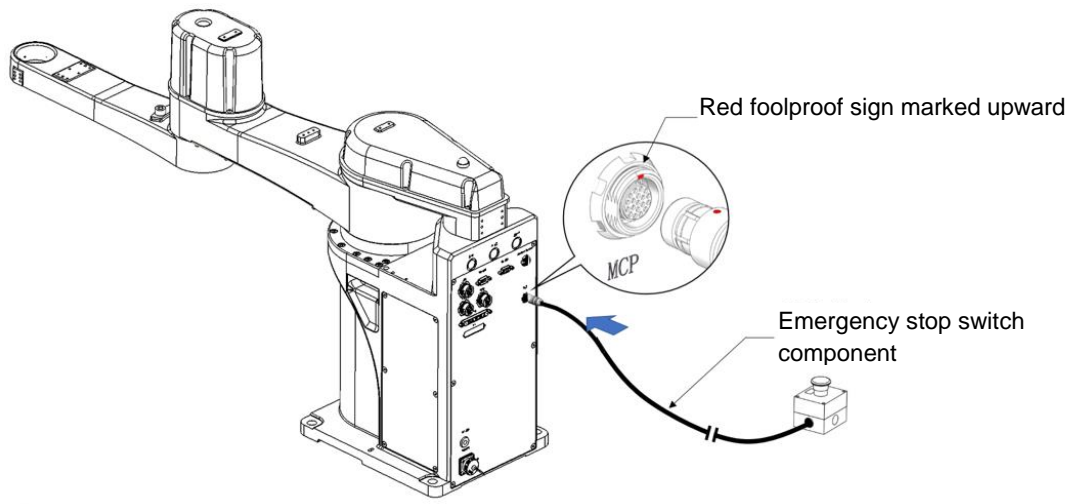


Figure 5-9 Schematic diagram of emergency stop device connection

5.8.3 Power connection

Hermes Robot has achieved integrated design without power supply box for power connection, which is convenient for use.

Cable to be used: Power cable

The wiring steps are shown below.

Step 1 Take the power cable out of the accessories box. Install the aviation plug end of the power cable at the "POWER" interface of the robot.

Step 2 Tighten the screw cap of the aviation plug clockwise.

Step 3 Plug the other end of the power cable into the 230 V a.c. socket.

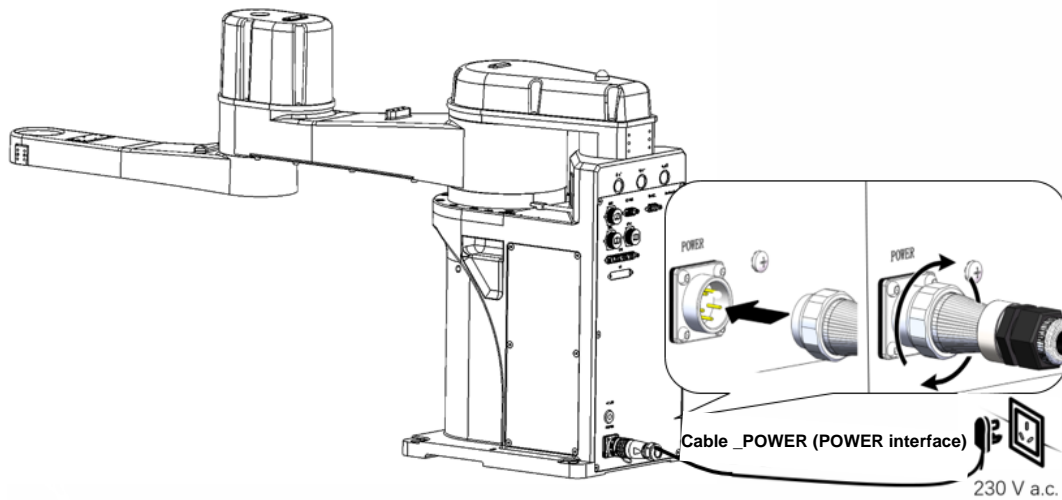


Figure 5-10 Connect the power

- It is dangerous to perform cable wiring while the robot is powered on. Before wiring, turn off the relevant equipment that provides power and mark with warning signs, e.g "Do not turn on the power".
- Avoid poor contact and ensure that the screw cap of the power connector is rotated to the end without loosening.
- Provide 220 V a.c. power supply as required;
- Do not connect directly to the factory power supply. The connection of a servo plug to the factory power supply would cause failure in the robot system.



5.8.4 Check after installation

Users need to check whether the robot is in an operable state after installing the cables. The checks are as follows:

- Check whether the plugs at all cable interfaces are loose or not.
- Make sure that the robot is in a safe work space and nobody is within the movable range of the robot.

5.8.5 Check before power-on

Ensure that:

- 1) each fastener of the robot is free from loose connection.
- 2) necessary protective devices have been properly installed and functioned well.
- 3) the voltage level of the energized electrical equipment is equal to that of the power supplied.
- 4) the power plug of the equipment is not shorted when checked with a multimeter before power-on.
- 5) all cable heads are correctly connected to buses and they are securely installed.

Check safety functions to ensure that:

- 1) the equipment is in a well-insulated environment.
- 2) the main power cable is grounded and the triangle plug is firmly inserted

into the socket to prevent electric shock.

3) the E-stop button is connected to the robot.

5.9 Installation of end fixture

Users should produce end fixtures by themselves.

Turn off the power before installing the end fixture.

- If the end fixture installation is conducted under the condition that the power is not turned off, damage to the robot system and unnecessary personnel injuries may be caused.



- When the weight of the end fixture is more than 1 kg, pay attention to the falling of the end fixture due to its own weight. The dimensions are shown in Figure 5-14.
-

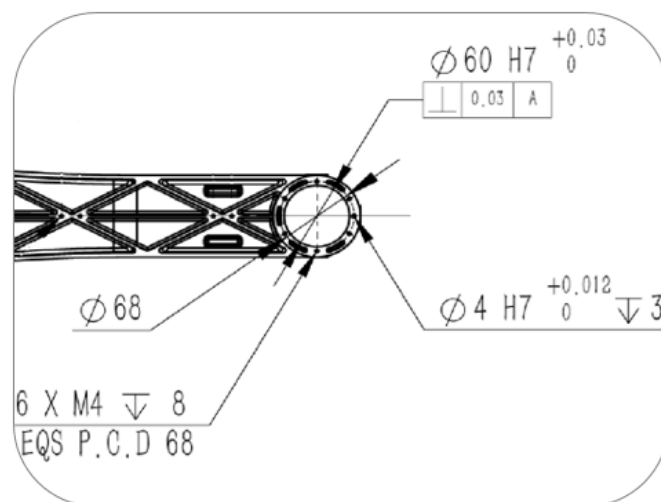


Figure 5-11 Flange installation dimensions (unit: mm)

5.10 Robot movement and storage

Pay attention to the following points when moving, storing and transporting the robot.



- When transporting the robot, fix it on a handling equipment to prevent it from rolling over as it would clamp hands or feet of the operators.
 - When lifting the robot, hold it by hand to ensure balance. The loss of balance may cause the robot to fall resulting in personal injury and damage to the robot.
-

To reassemble the robot after long-term storage and reinstall its system for use, conduct a test run and then start normal operation after confirming that there is no abnormality.

Transport and store the robot according to the robot installation site and environmental requirements.

If fog forms in the robot during transportation and storage, eliminate the fogging before turning on the power.

Chapter 6 Robot Operation

Hermes Robot need to be used in the ARM (Automation Resource Manager) software programming environment. ARM software is suitable for the robot software programming environment produced by QKM. Users can write programs based on the software to send instructions to control the robot.

This chapter mainly introduces the prerequisites and installation of ARM, the functions and usage of macro language development interface, the functions of jog teach interface, servo power-on, speed adjustment, emergency stop and recovery, and robot power-off operation.

Users can write programs based on the software and send commands to operate the robot. For specific robot program programming operations, please refer to the “QKM Robot Command Manual” and “QKM Robot (QRL Language) Programming Manual” . Users can download the latest version of the manual through the company's official website.



NOTE

If the robot reports an error during use, you can refer to the QKM Robot Error Code Manual for abnormal information.

Users can download the latest version of the manual through the official website.

6.1 Prerequisites

- 1) Familiar with macro instructions.

QKM macro instructions indicate the robot secondary development language independently developed and defined by QKM based on the QKM motion control system, which is called Macro instruction set. Macro instructions can be used to automatically execute defined commands and perform functions such as complex operations, string processing, interactions between users and projects, etc.

- 2) Proficiency in QRL language.

QRL (QKM Robot Language) is a robot secondary development language based on Lua language and independently defined on the Lie group motion control system platform. The QRL language is simple and easy to program, not only supports single statement instruction execution, but also supports mathematical arithmetic operations, logical operations, conditional control, loop statement control, thread control and other functions. It can automatically execute defined commands by performing complex operations, string processing, performing interaction between users and projects, and other functions; Users can easily and conveniently develop robot integration

projects by editing and sending command programs

- 3) Familiar with the mode of motion of the robot.

6.2 Programming environment installation

In the application development of robots, the interactions of Windows with QKM robots or equipment system are required. QKMLink provides the interface for such interactions.

You can download QKMLink using the two methods as follows:



NOTE

- Download the QKMLink installation package at the official website of QKM and install QKMLink.
 - The ARM installation package has integrated QKMLink, so QKMLink will be installed automatically when ARM is installed.
-

QKMLink is designed according to the QKM Protocol. The format of data from the interactions conforms to the protocol. Currently, QKMLink supports TCP communication and can be installed on Windows of different devices. Its interface supports C#, VB, C++ call and development.

QKMLink is an application software development component under Windows. Users use this component for software development to complete

data interactions with Robot and other devices.

Requirements for download environment and memory:

- 1) Win7, Win8, Win10 systems;
- 2) Memory: 2G or more.

6.2.1 Installation steps

Step 1 Download an ARM installation package at the official website of QKM, as shown in Figure 6-1.

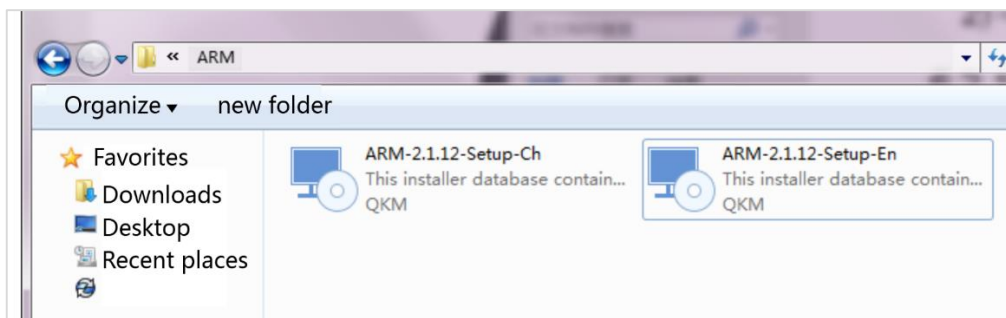


Figure 6-1 Installation package

Step 2 Double-click the left button to install the software, as shown in Figure 6-2.

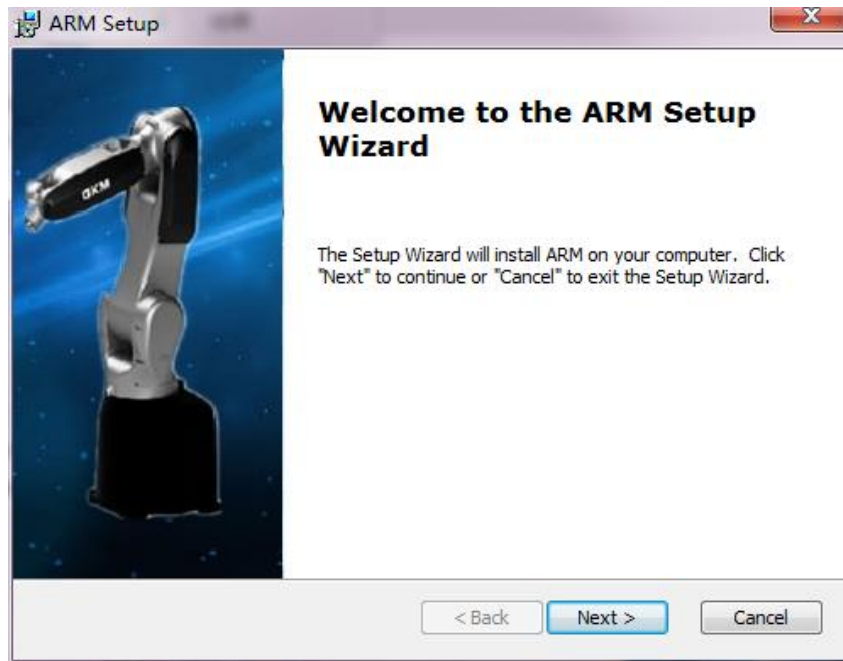


Figure 6-2 Start installation

Step 3 Click on "Next", as shown in Figure 2-3.

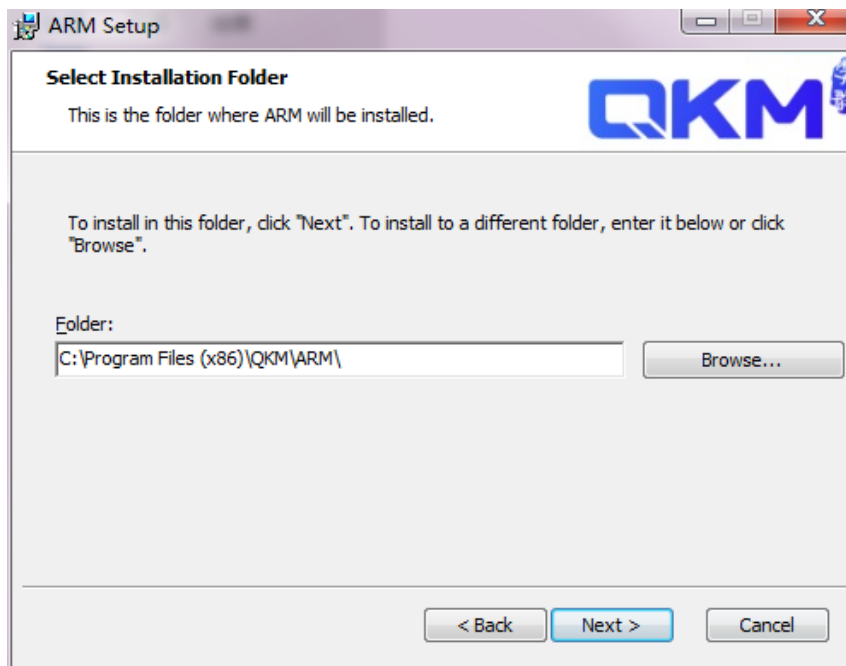


Figure 6-3 Choose installation path

Step 4 Choose the installation path and click on "Next", as shown in

Figure 6-4.

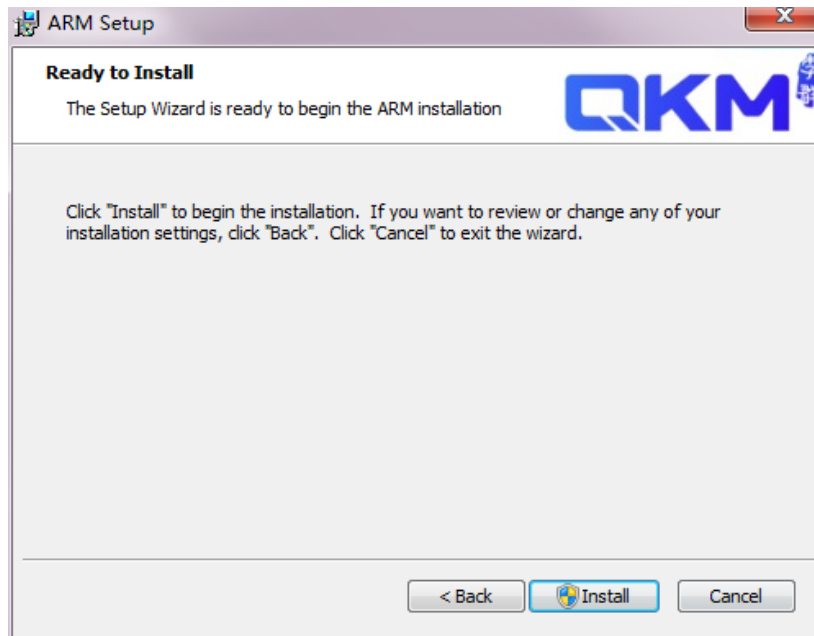


Figure 6-4 Successful installation

Step 5 Click on "Install" to complete the installation.

6.3 Open Macro Command Debugger

Step 1 Double-click the installed ARM to open the ARM interface, and then click <window> on the menu bar to switch to <Pallas> mode, as shown in Figure 6-5.

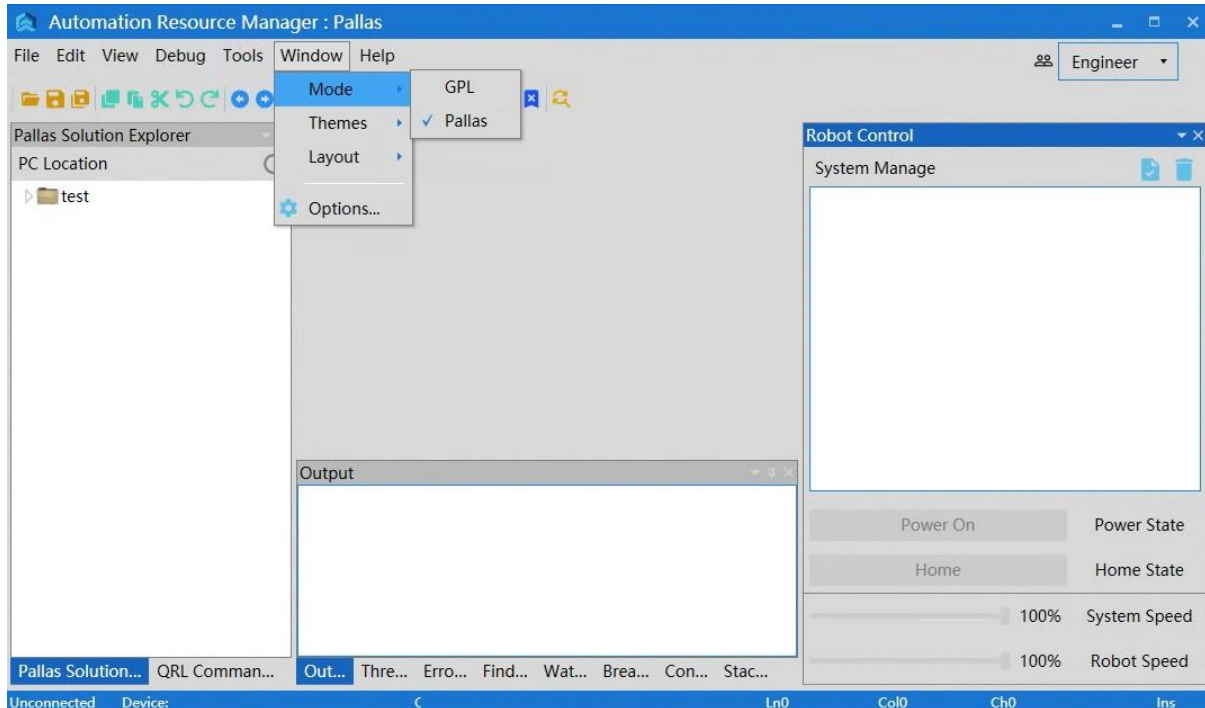


Figure 6-5 ARM interface

Step 2 On the interface of ARM in Pallas mode, click <Tools> on the menu bar and select <Macro Command Debugger >in< Debugging and Analyzing Tools >, as shown in Figure 6-6.

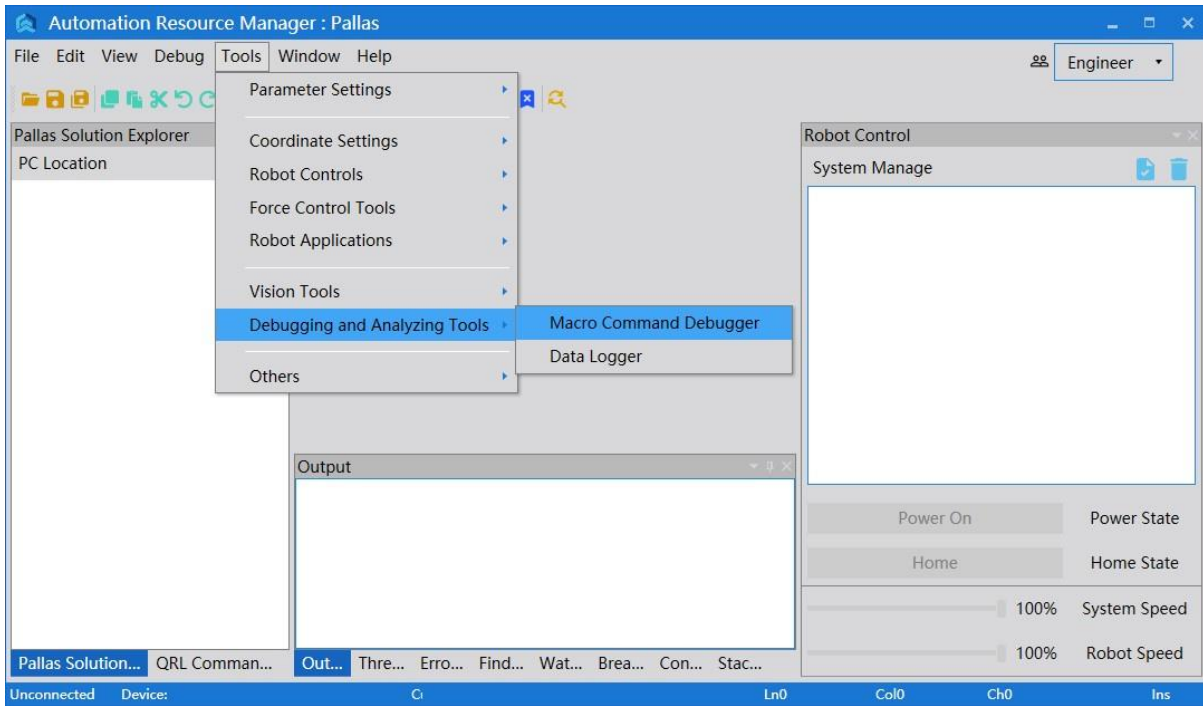


Figure 6-6 ARM interface

Step 3 The macro command debugger is shown in Figure 6-7.

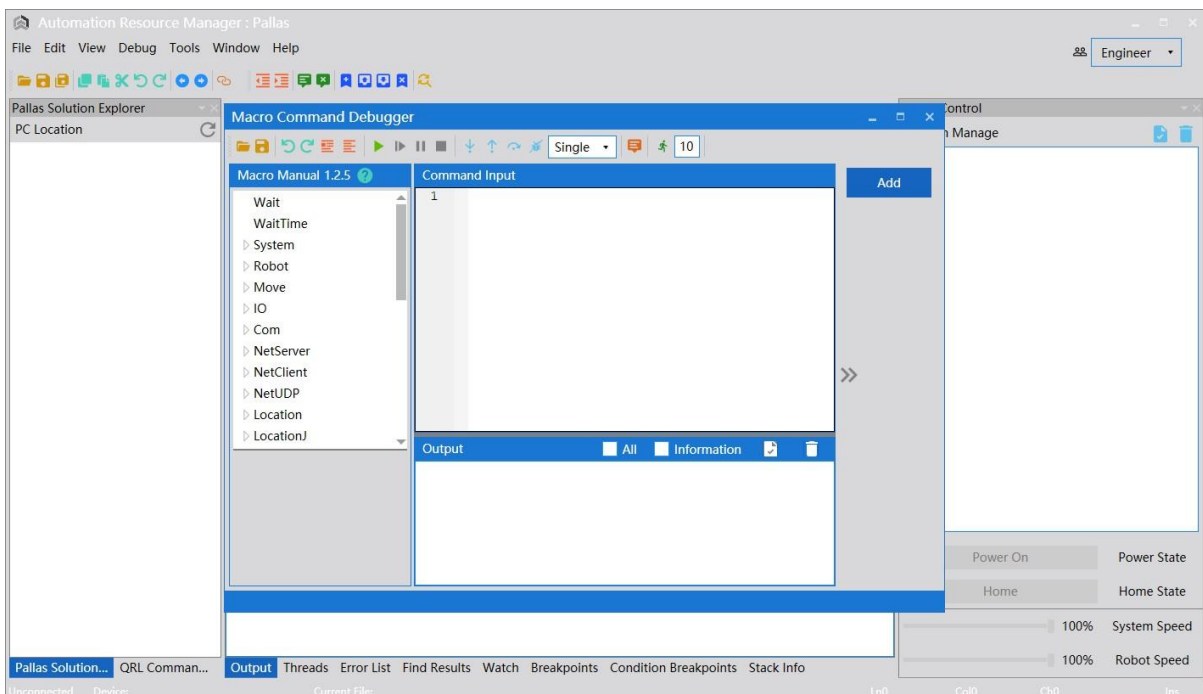


Figure 6-7 Macro Command Debugger

6.4 Functions of macro command debugger



NOTE The macro command debugger is used in the installed ARM programming environment.

6.4.1 Macro Command Debugger interface

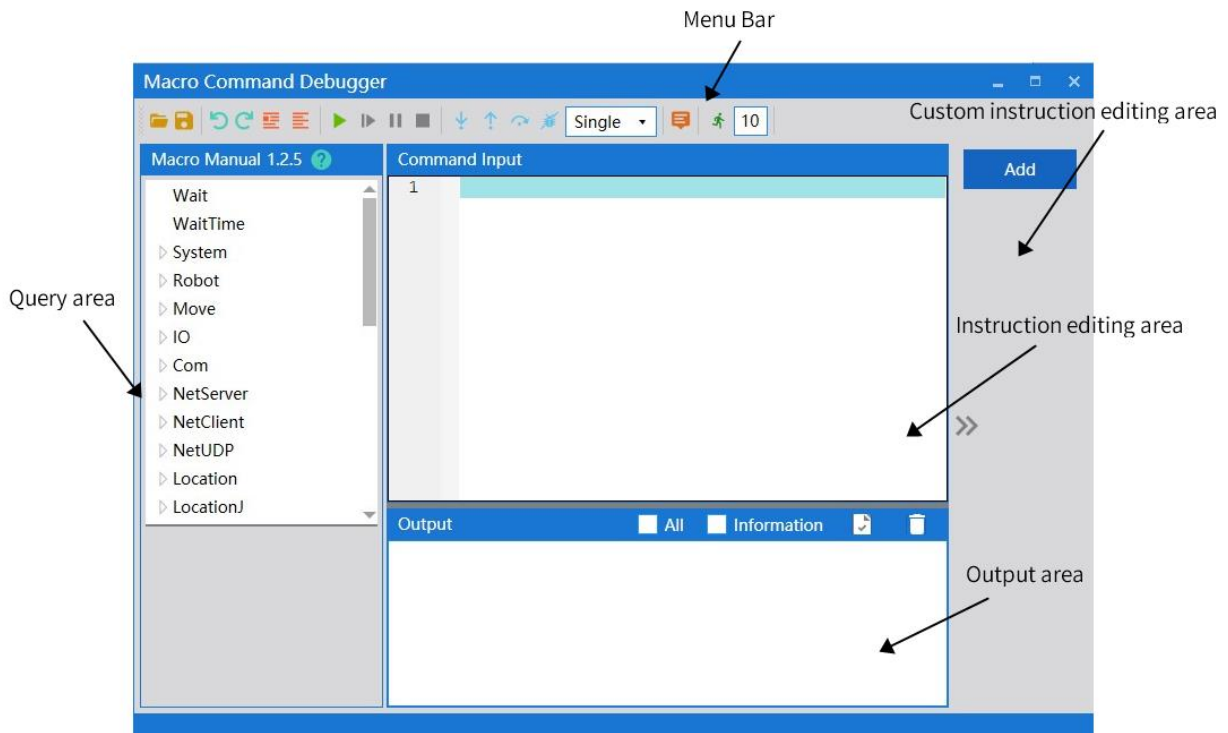


Figure 6-8 Macro Command Debugger

6.4.2 Menu bar

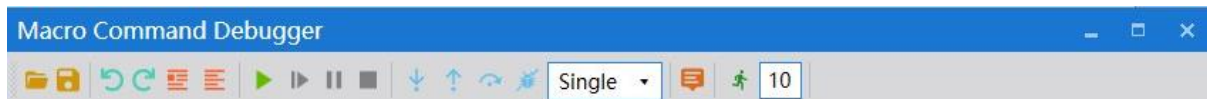














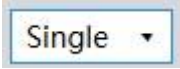





Figure 6-9 Menu bar of macro command debugger (ARM)

Table 6-1 Functions of tools on the macro command debugger

Introduction to menu bar on the macro command debugger (ARM)

	Open		Save
	Undo		Resume
	Comment out the selected lines		Uncomment out the selected lines
	Start (Note: Run all instructions in order.)		Continue
	Pause		Stop
	Single step		Previous
	Jump		Clear
	There are two options, i.e. "Single" and "Cycle". Click on the inverted triangle to select.		Hide and show
	10 instructions are sent at a time, the purpose is to increase the speed of continuous sending.		Sending multiple commands at once: After the number 10 is

	<p>“10” is the number that needs to be set by the user, and can be set to other numbers.</p>		<p>set, click here to start execution</p>
--	--	--	---

6.4.3 Introduction to user defined instruction editing area

Users can add common instructions to the < macro command debugger> interface through the user-defined instruction editing function according to their needs. After editing, the required instructions will be added to the right side of the interface for easy access next time

For example, add the command of "servo power on" in the interface:

Step 1 Click the arm software debugging environment, and then click <Tools> →<Debugging and Analyzing Tools>→<macro command debugger> to enter the debugging interface.

Step 2 Click the < add > button on the right to open the operation instruction dialog box. Type the instruction name "servo power on", the operation instruction content "robot. Powerenable 1,1" and the comment "robot servo motor power on" in the input box of the interface to edit the required instructions,as shown in Figure 6-10.

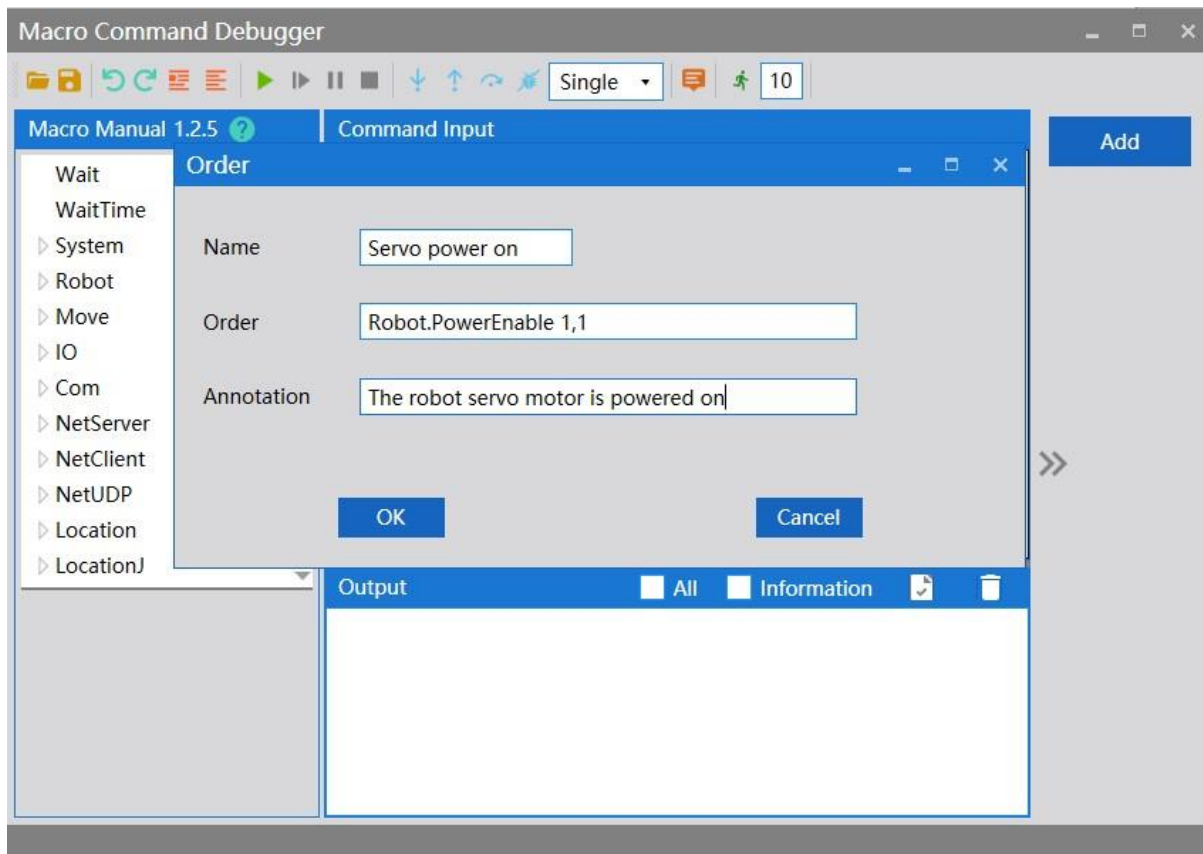


Figure 6-10 Customize the editing interface(ARM)

Step 3 Click < OK >, and the command shortcut key < servo power on >, just added, will appear on the right side of the macro command debugge.

To call the command of "servo power on" again, the user can directly click the shortcut key of < servo power on > on the right side of < macro command debugger>, and the specific content of the command "robot. Powerenable 1,1" will be sent to the robot. The sent command and execution result can be seen in the < output > window, without manual input a,as shown in Figure 6-11.

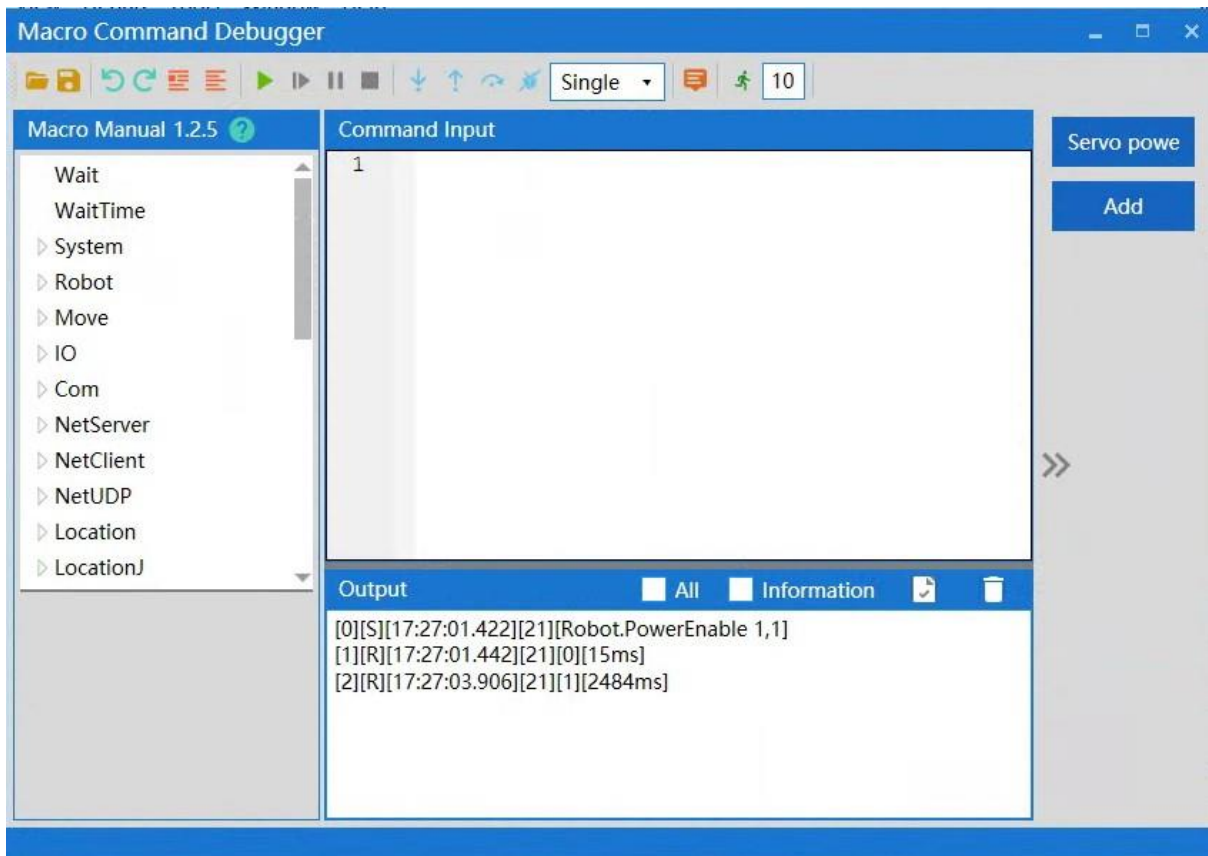


Figure 6-11 call the command shortcut interface(ARM)

6.4.4 Establish IP communication

Step 1 Open the ARM debugging environment, then click the button in the menu bar < Connect or disconnect quickly >to enter the connection interface.

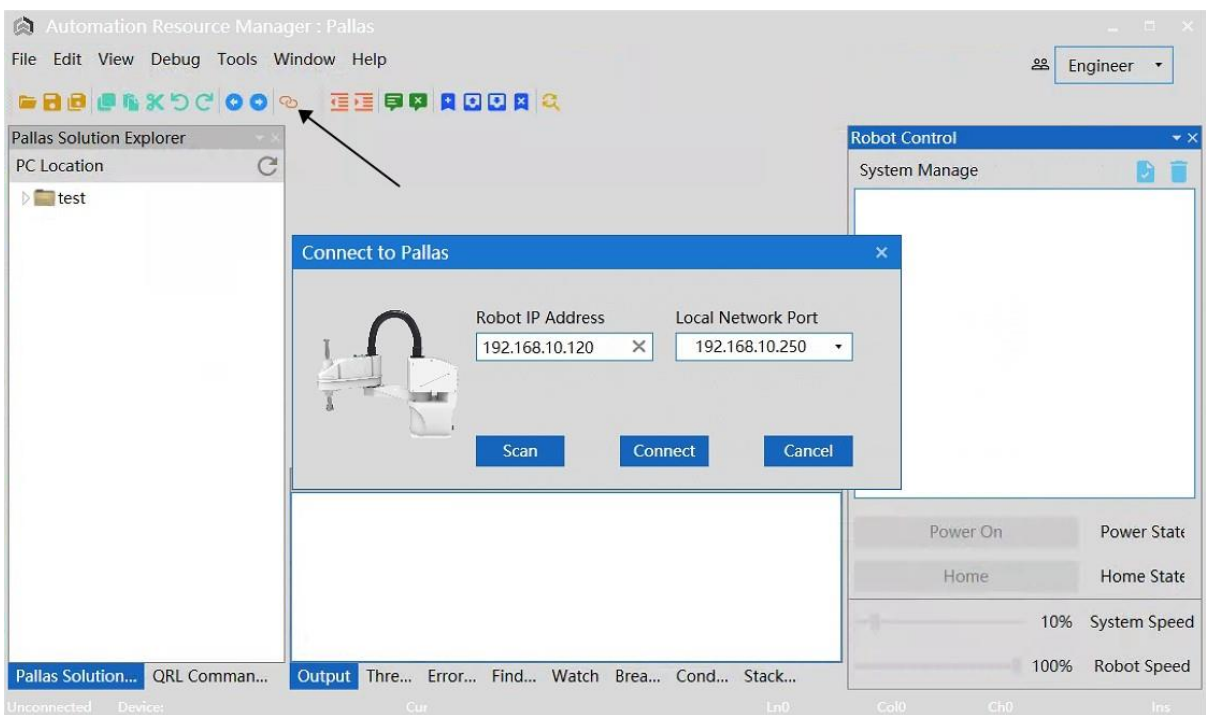


Figure 6-12 connection interface

Step 2 Click the lower left corner to enter the scanning interface, the <Scan>interface will automatically scan the IP address of the robot, click the IP address and click the lower right corner<Select>

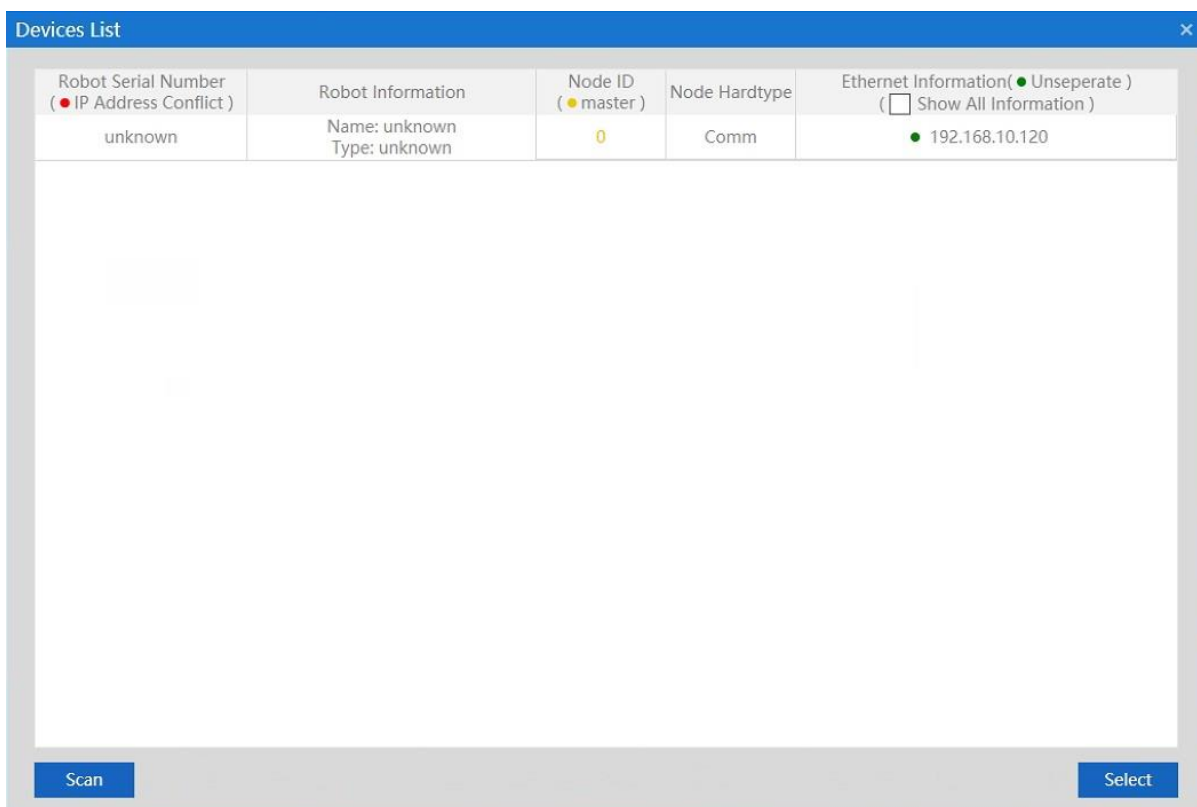


Figure 6-13 scanning interface

Step 3 The IP address of the robot: 192.168.10.120, then click <Connect>the button below,as shown in Figure 6-14.

- The IP addresses of the robot and the host computer must remain on the same network segment.
- The IP of the robot is 192.168.10.120, then that of the host computer can be set to 192.168.10.1, that is, the IP addresses of the two must be the same in the first three digits and different in the last digit. The last digit of the IP of the host computer ranges from 1 to 256.



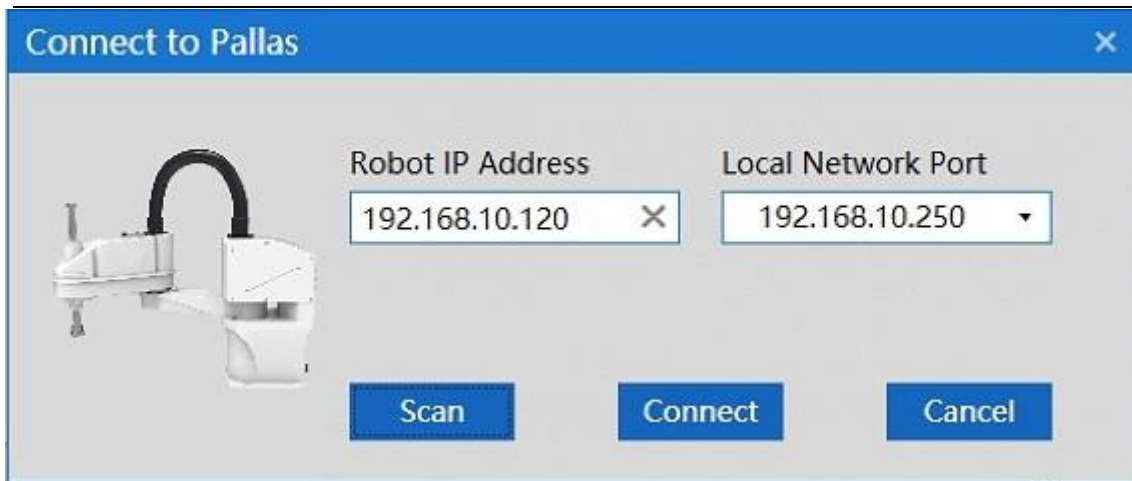


Figure 6-14 IP connection

6.4.4.1 Successful IP connection

The premise of successful IP connection is that the IP addresses of the robot and the host computer are on the same network segment. Upon successful connection, there is a prompt of " Connected Device: 192.168.10.120" in the lower left corner of ARM interface, as shown in Figure 6-15.

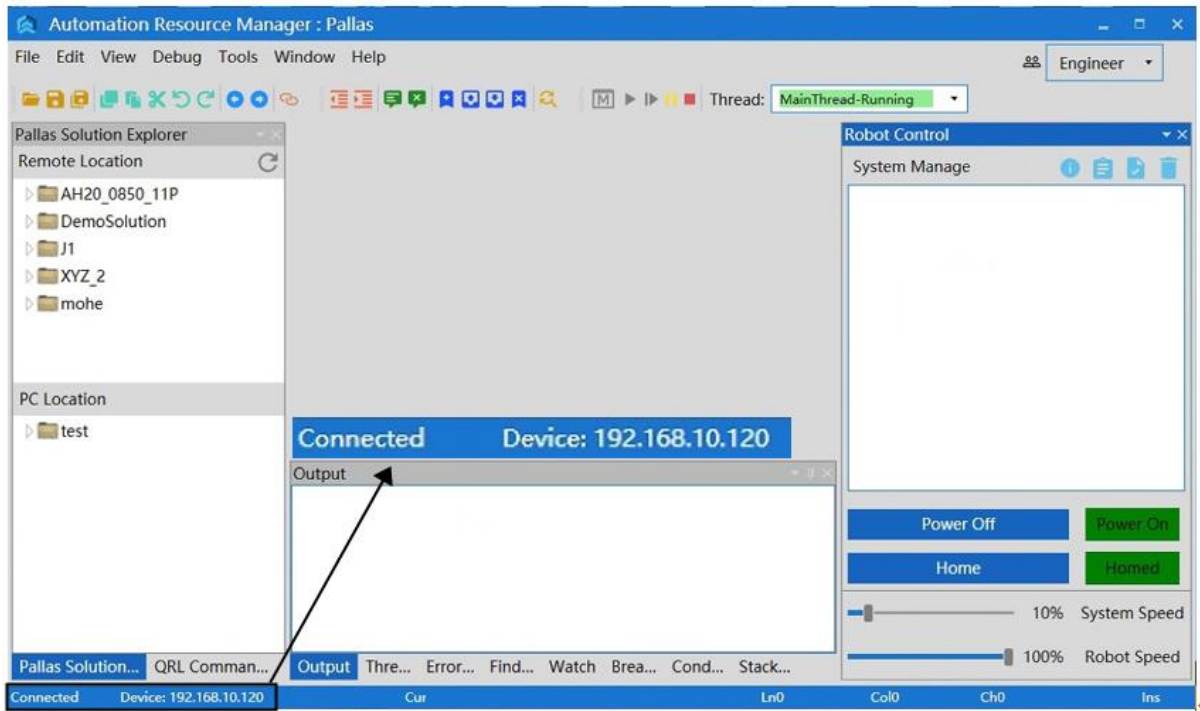


Figure 6-15 Successful connection

6.4.4.2 IP connection failure

When the connection fails, the "Error" prompt dialog box will pop up, as shown in Figure 6-16.

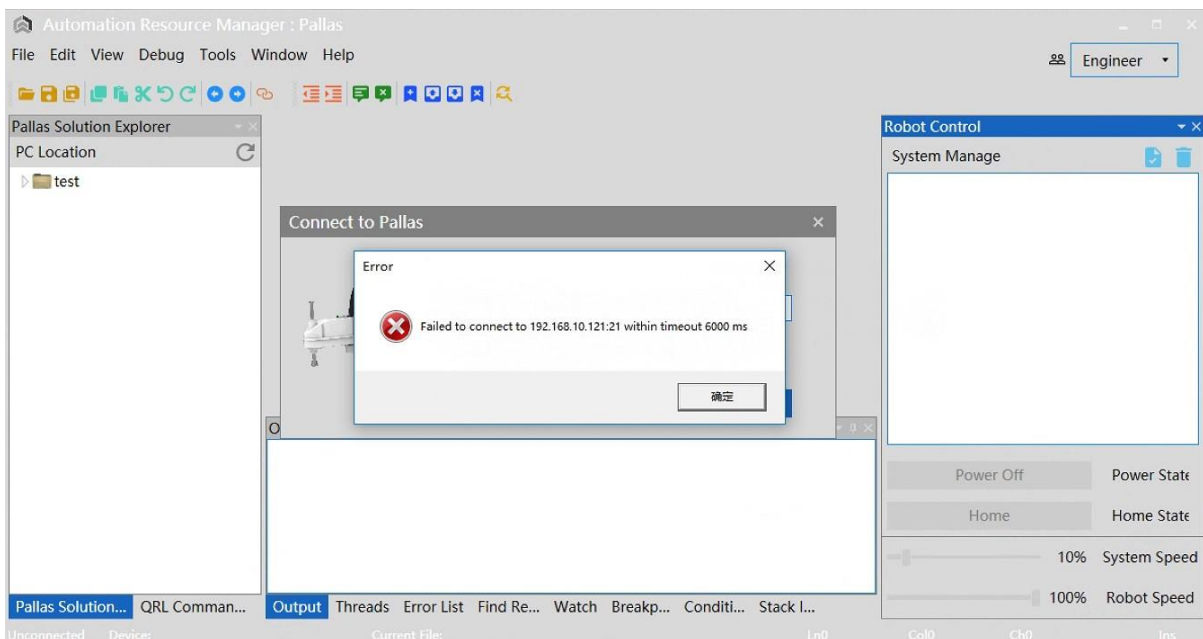


Figure 6-16 Connection failure

Solution to connection failure:

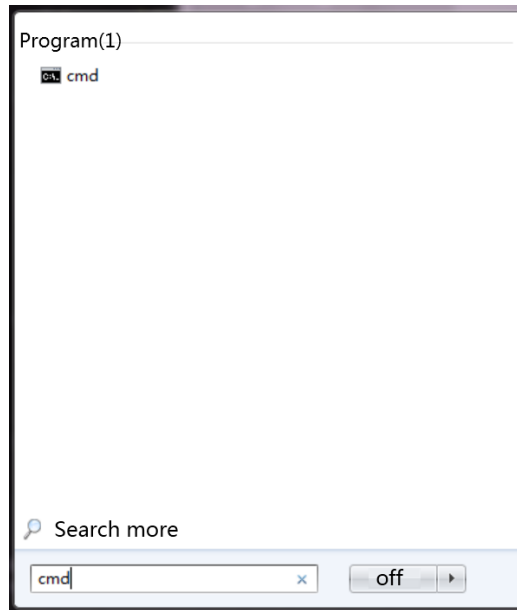
Step 1 Rescan the robot's IP address; If the IP address of the robot can be scanned, try to reconnect to the robot; If the IP address of the robot cannot be scanned, check whether the network cable between the host computer and the robot is connected normally, or whether the network port connected to the robot is correct, and the network port connected to the robot by the network cable is a LAN port.



NOTE

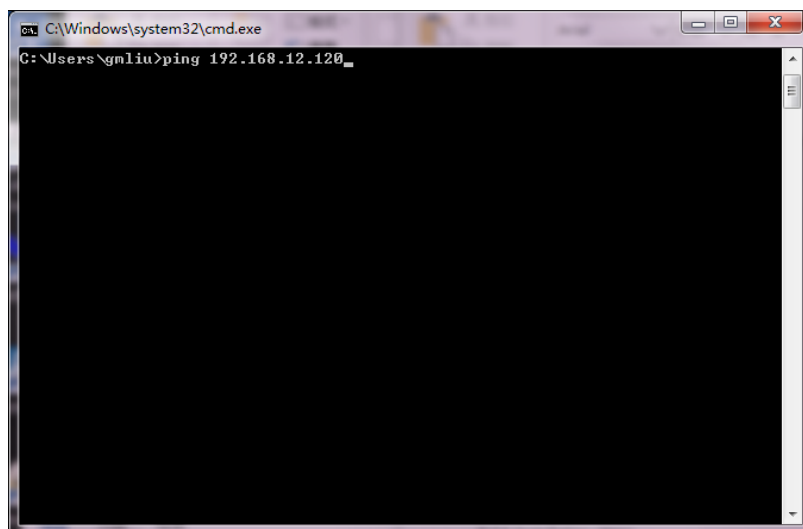
Step 2 If the robot can be scanned in Step 1 but the connection fails, check whether the IP addresses of the host computer and the robot are in the same network segment. Make sure that the IP addresses of the host computer and the robot are in the same network segment.

Step 3 Execute system search and run cmd as shown in the figure:




Step 4 Directly input "ping + Robot IP" after >. If the specific values of the parameters of byte, time and TTL are returned, it indicates that the network is connected as shown in the figure.

(Note: The IP in the figure is just an example. The correct IP is subject to the actual IP of the robot.)



Step 5 Connect the robot again in the ARM interface.

6.4.5 Query on description of macro language instructions

The macro command debugger includes a macro manual, which lists the macro language instructions that need to be used during robot debugging. For details, please refer to the "QKM Robot Instruction Manual". Double-click the button  in the interface to open the "QKM Robot Command Manual".

When you click a corresponding macro language instruction, the list automatically pops up a description of this instruction set, as shown in Figure 6-17.

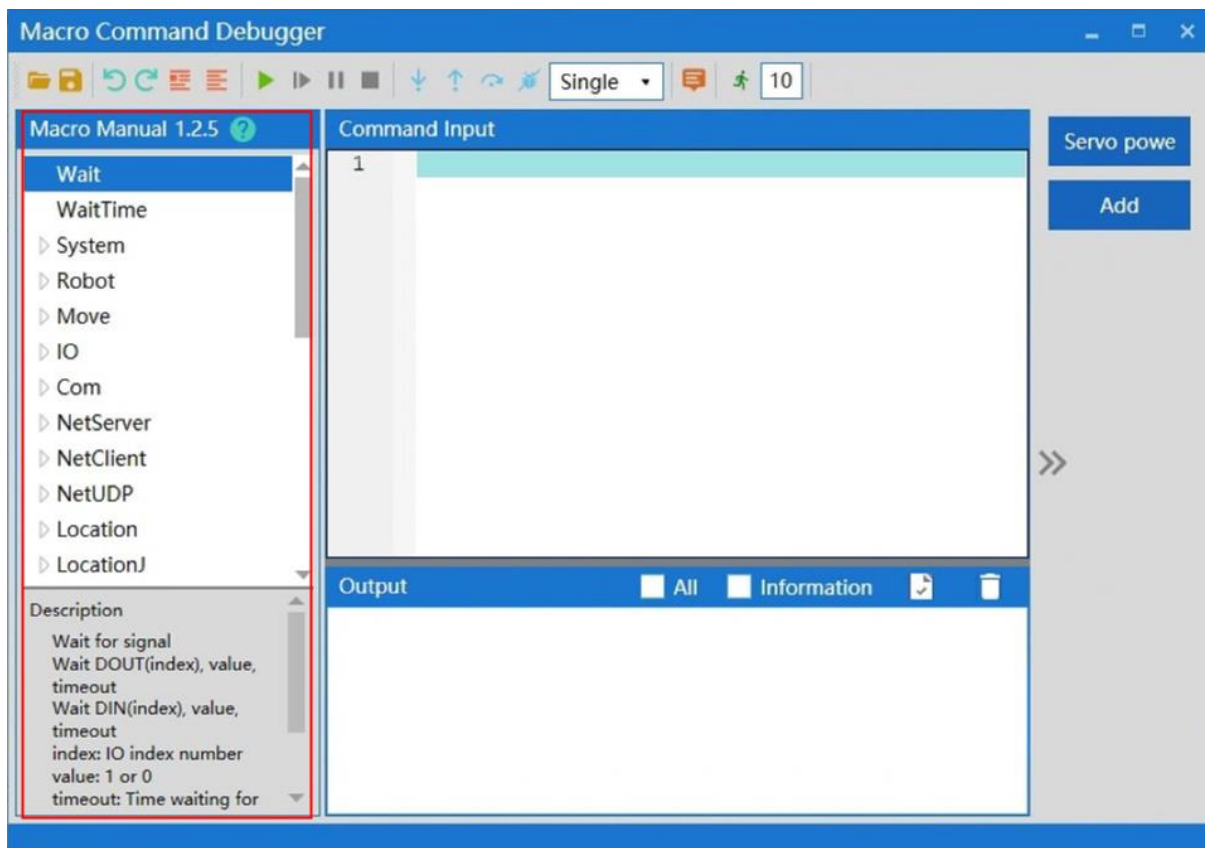


Figure 6-17 Macro manual

6.4.6 Input instructions

The "instruction editing area" is the area where instructions are input and

edited as shown in Figure 6-18.

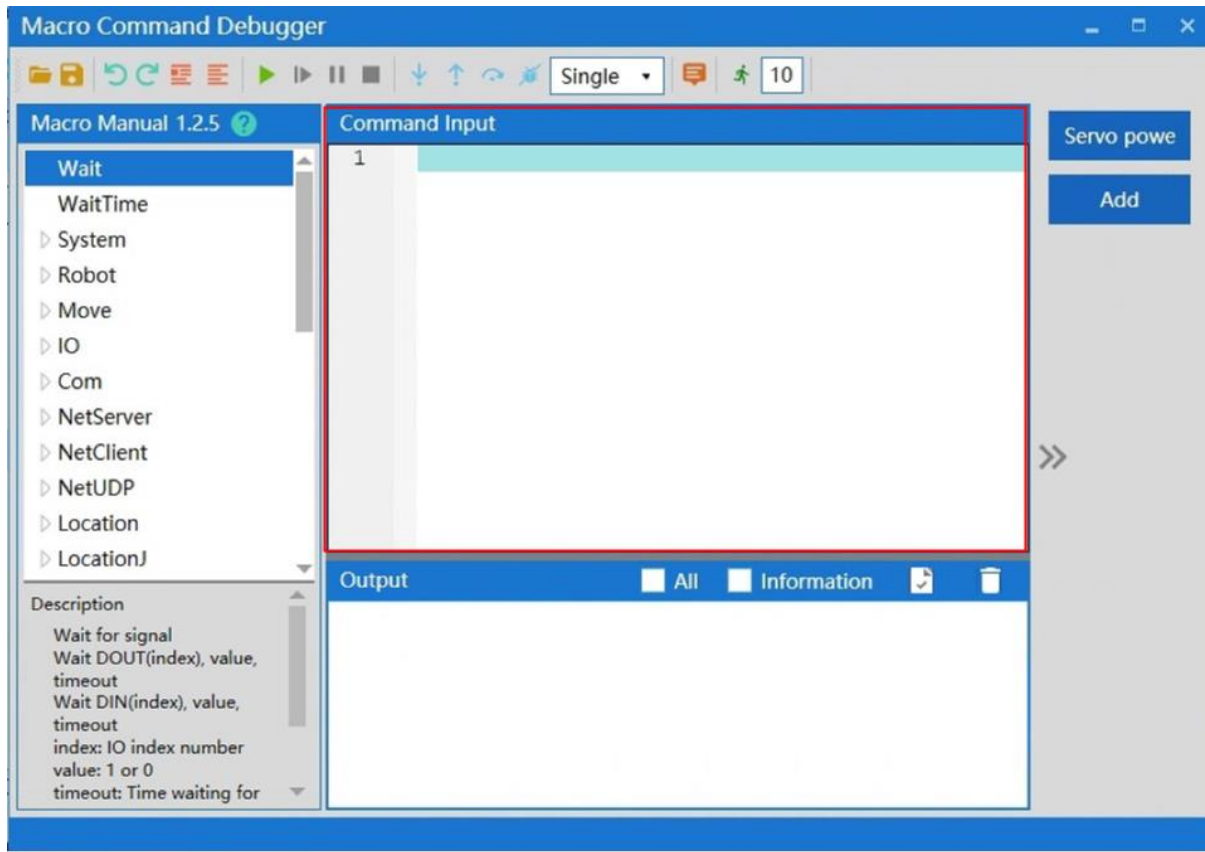


Figure 6-18 Input instructions



NOTE

The system distinguishes between case and instruction, and the default first letter of instruction is uppercase.

When inputting a single instruction, you can enter the first letter of the instruction. If you want to select an instruction, such as Location, you can enter the capital letter " L " and the initial letter is L-related instructions automatically pops up, as shown in Figure 6-19.

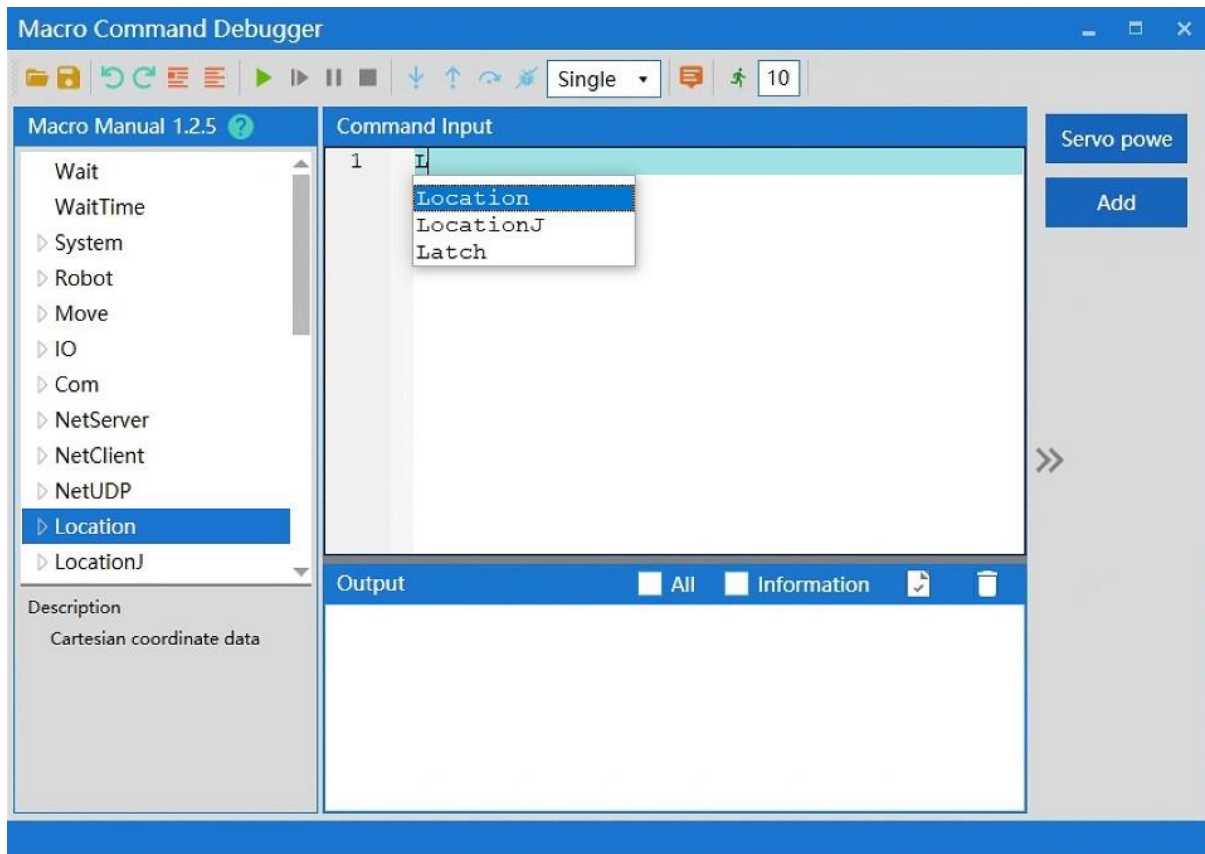


Figure 6-19 Input instructions

All instructions contained under the instruction set can be prompted automatically when you enter ".", as shown in Figure 6-20.

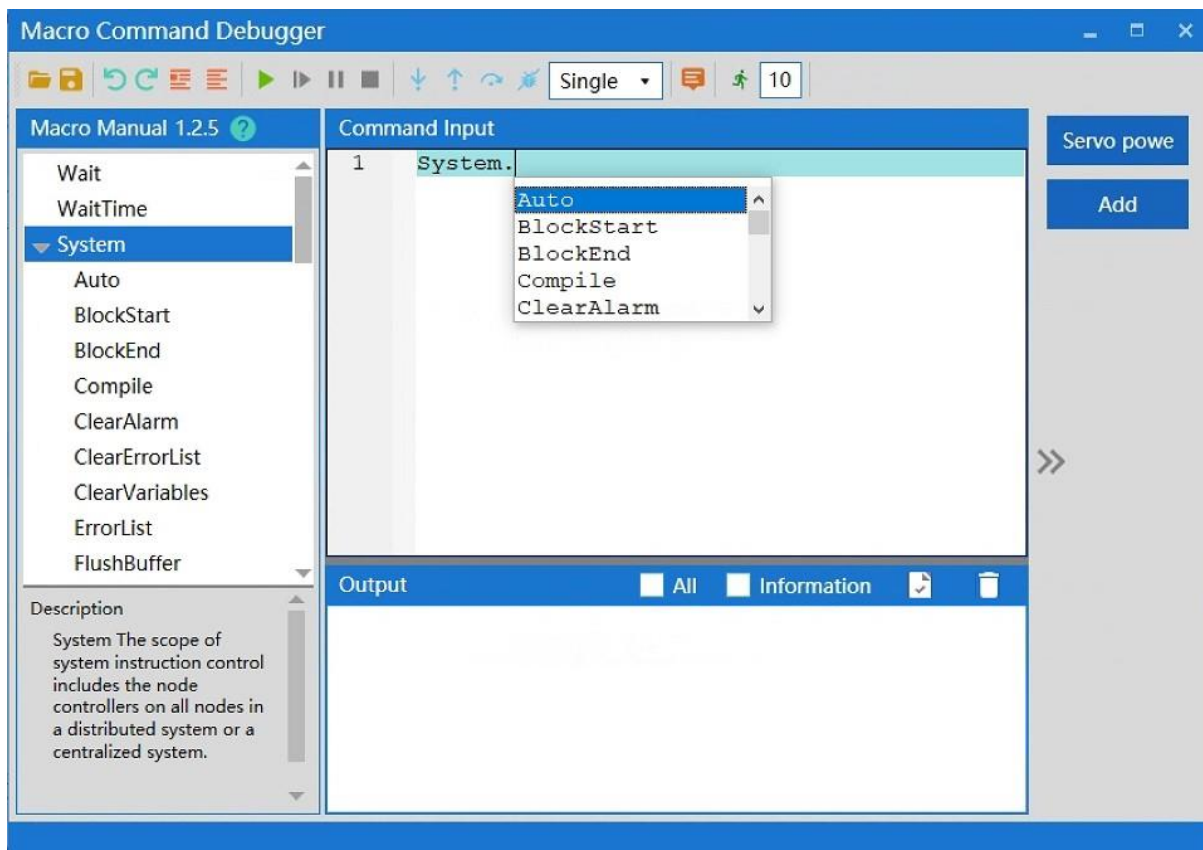


Figure 6-20 Input instructions

6.4.7 Run instructions

After editing the instructions, click on the <Run> button in the menu bar to run all the instructions in the "instruction editing area" one by one in sequence. The results are displayed in the "instruction output area", as shown in Figure 6-21.

If you select the <All > key on the upper right of the output area, the Macro instruction currently sent and received will be displayed in the "Instruction Output area"; if you select the < Information > key, the Hidden message received will be displayed in the "Instruction Output area".

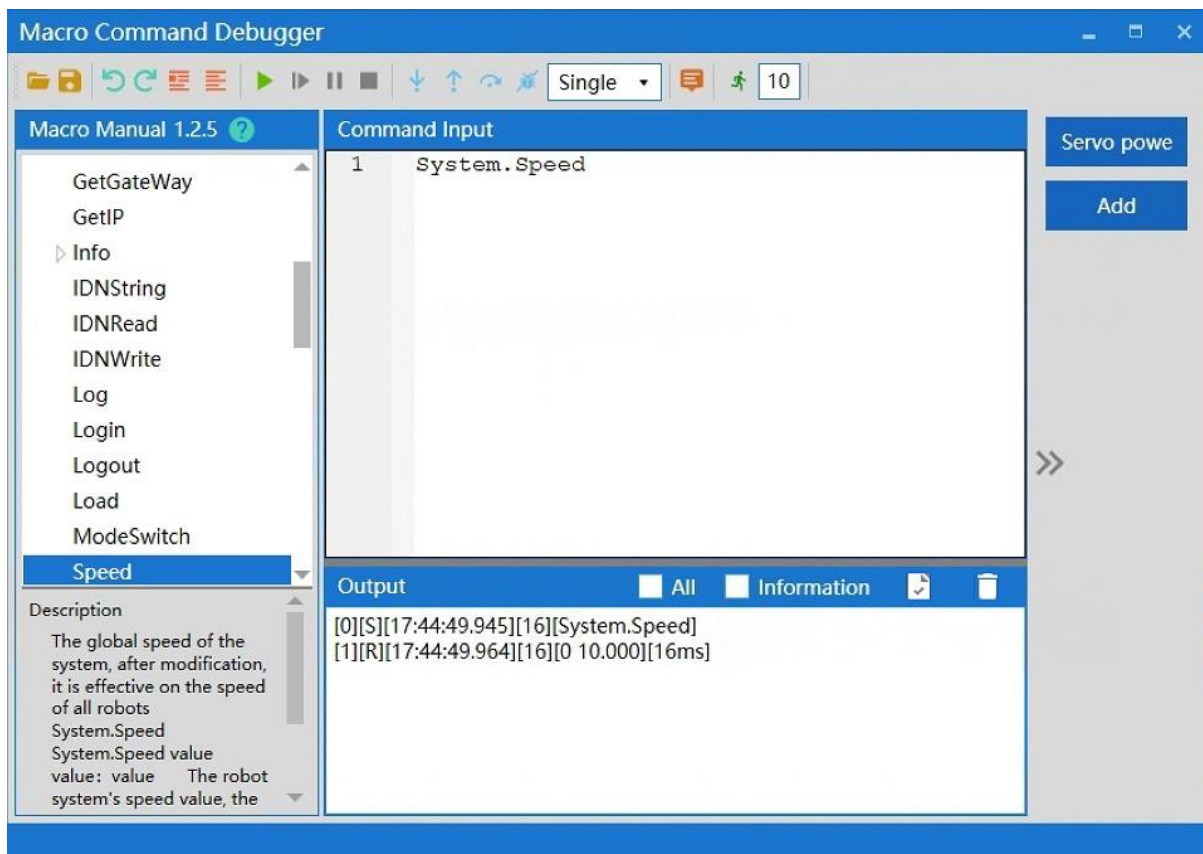


Figure 6-21 Run instructions

6.4.8 Breakpoint debugging

If you need to debug or run an instruction separately, you can locate it by adding a breakpoint before the instruction. Method of adding a breakpoint: Click the left mouse button at the position of instruction number before the instruction to add a breakpoint identifier, as shown in Figure 6-22.

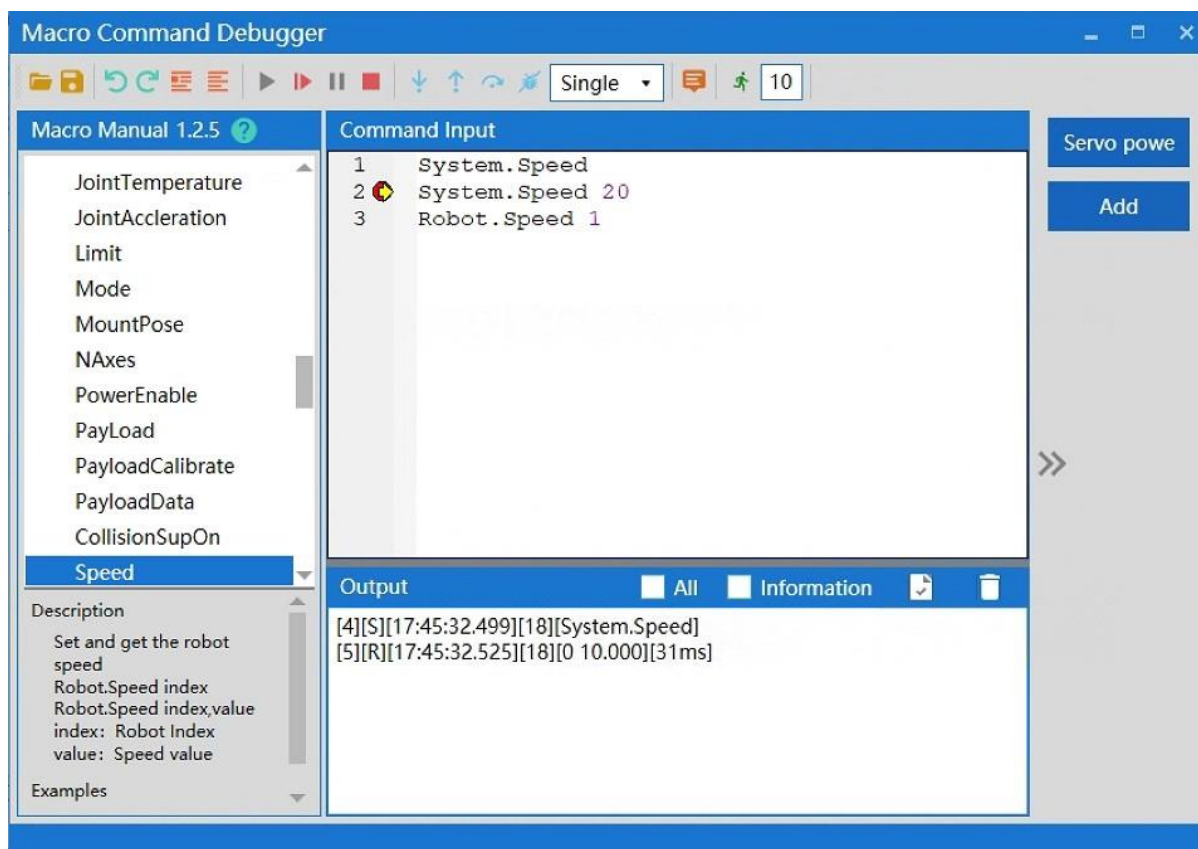


Figure 6-22 Add a breakpoint

6.4.9 Output

The output after running is displayed as shown in Figure 6-23.



NOTE

The output interface contains the feedback information of each command. If the command is successfully executed, the feedback result will be displayed in black font. If the command fails to be executed, the system will pop up the "Execution Failure" dialog box to prompt you.

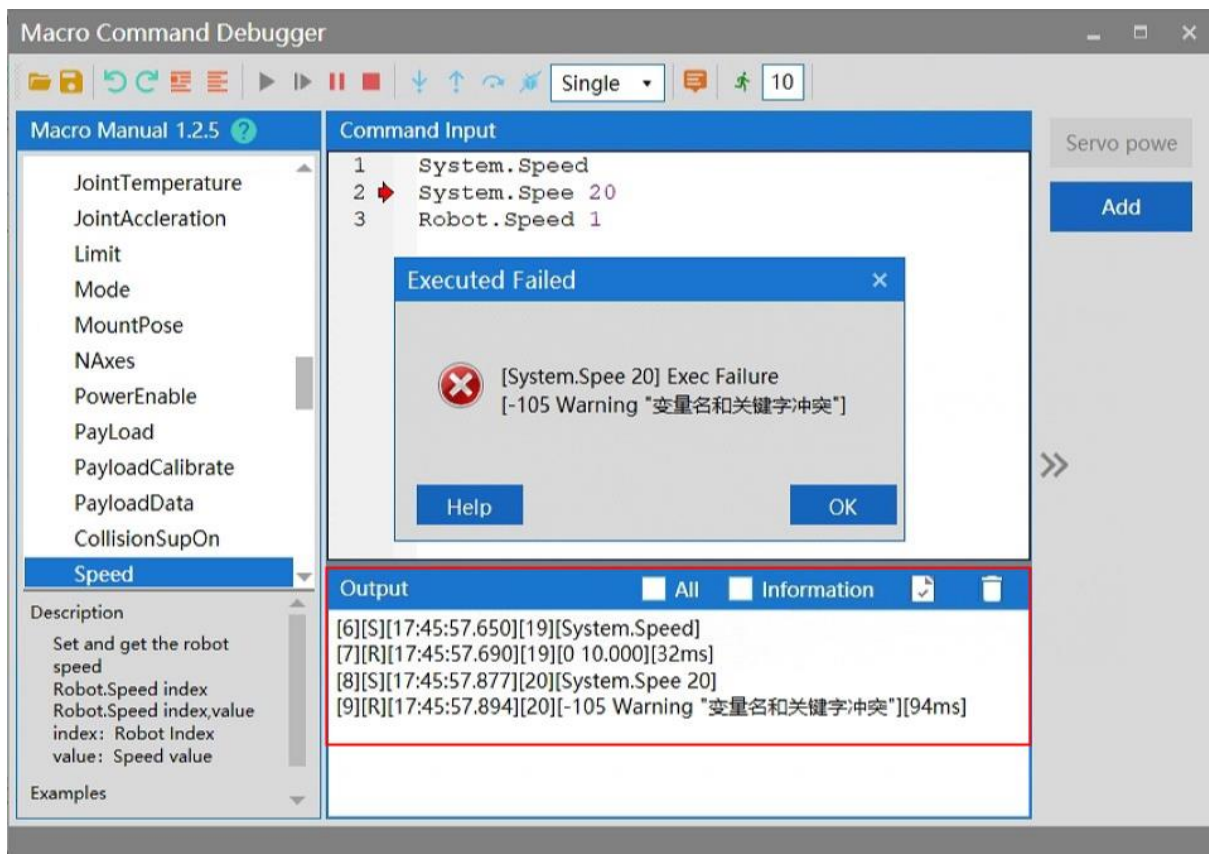


Figure 6-23 Output

6.4.10 Clear output

Click the <Clear> button in the upper right corner of the output area to complete the clear, as shown in Figure 6-24.

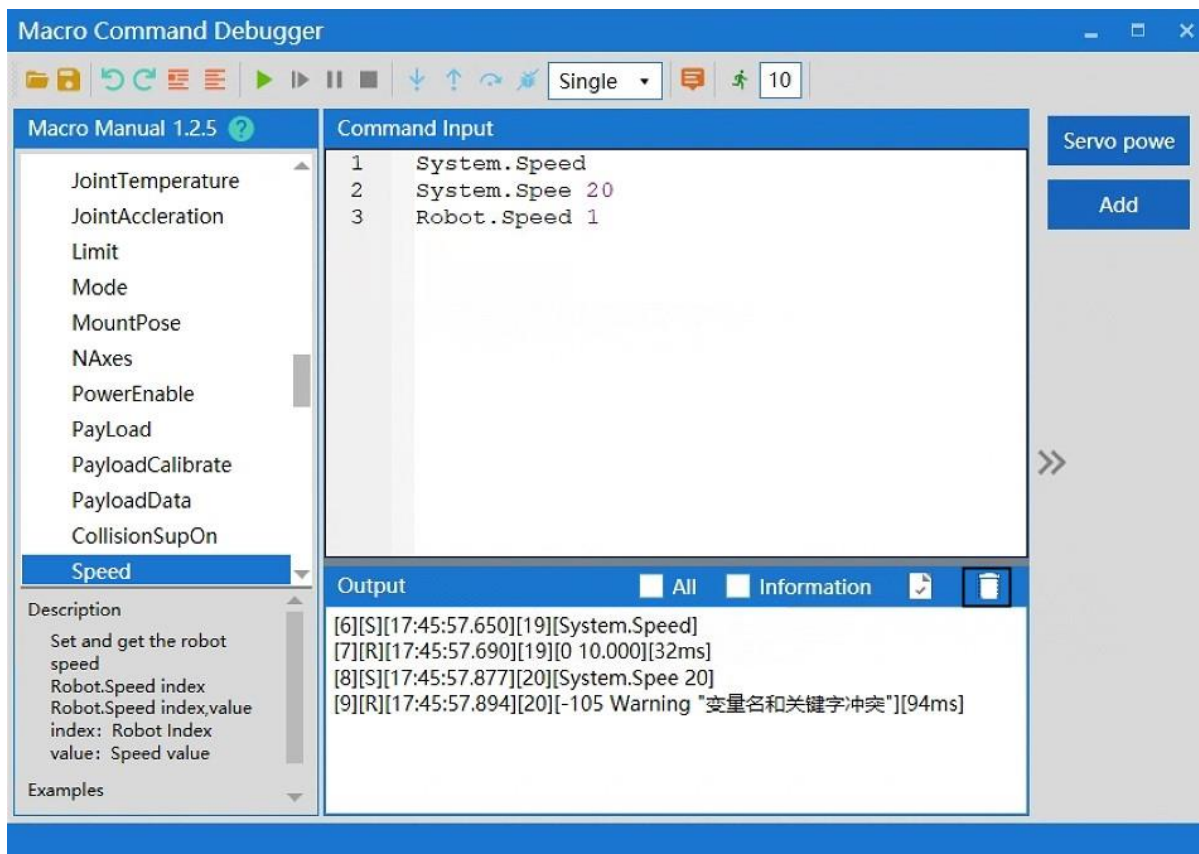


Figure 6-24 Clear output

6.4.11 Save output

If you need to save the output, you can click the <Save> button in the upper right corner of the output box to save it in the *.log format, as shown in Figure 6-25.

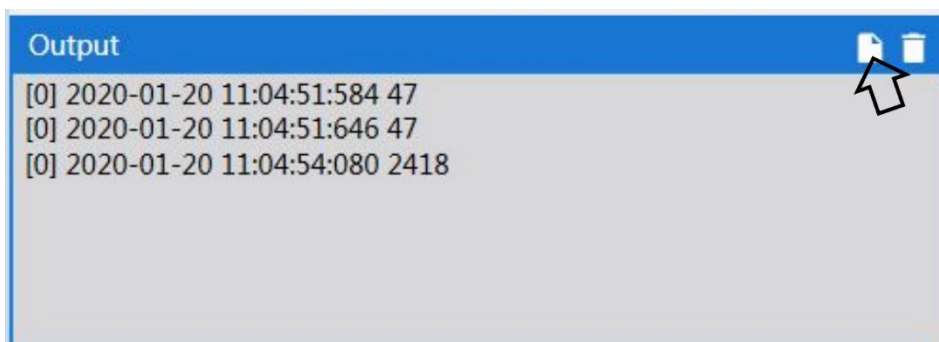


Figure 6-25 Save output





6.5 QRL mode



NOTE

QRL programs are used in ARM-installed programming environment.

6.5.1 Switch to QRL mode

In the ARM debugging interface, click the upper middle button , and then click the lit button  on the left to switch to the QRL mode . When clicking the button , a pop-up window will appear to confirm whether you would like to switch to QRL mode. Click OK to switch, as shown in Figure 6-26.

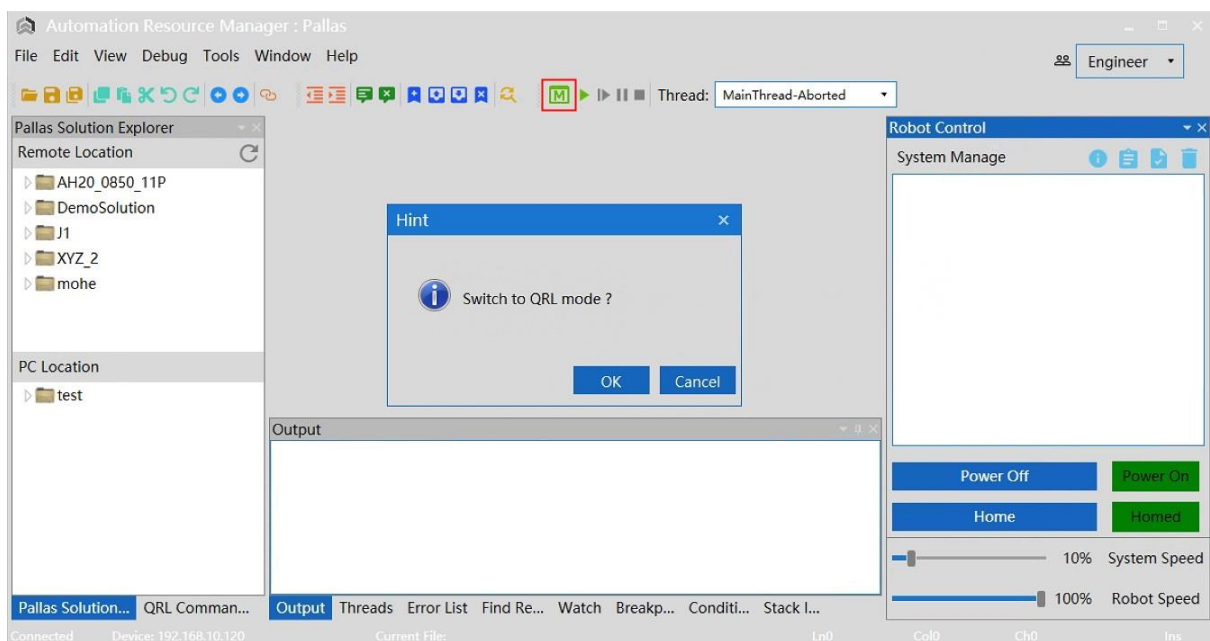


Figure 6-26 Switch to QRL mode

6.5.2 Creating QRL project files

To use QRL programs, you need to create program files. Create a new solution on the left side of the ARM debugging interface. Select "Remote

Location" under "Pallas Solution Explorer".

Step 1 Right-click in the space below "Remote Location" and click "New Solution", as shown in Figure 6-27.

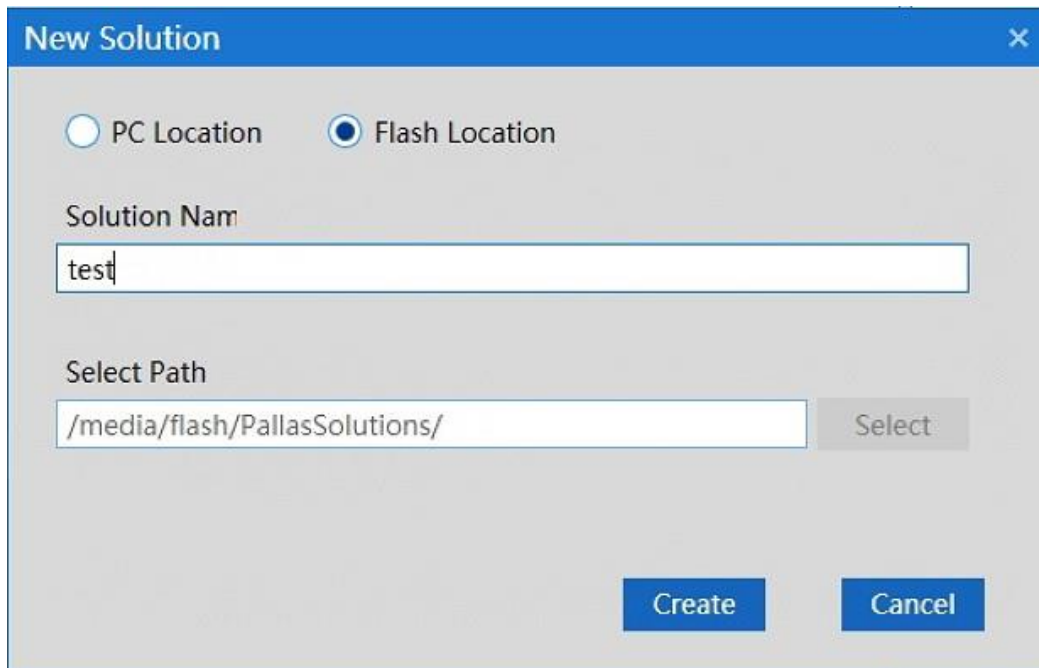


Figure 6-27 New Solution

Step 2 After the New Solution interface pops up, enter a program name, such as "test", and click "Create".

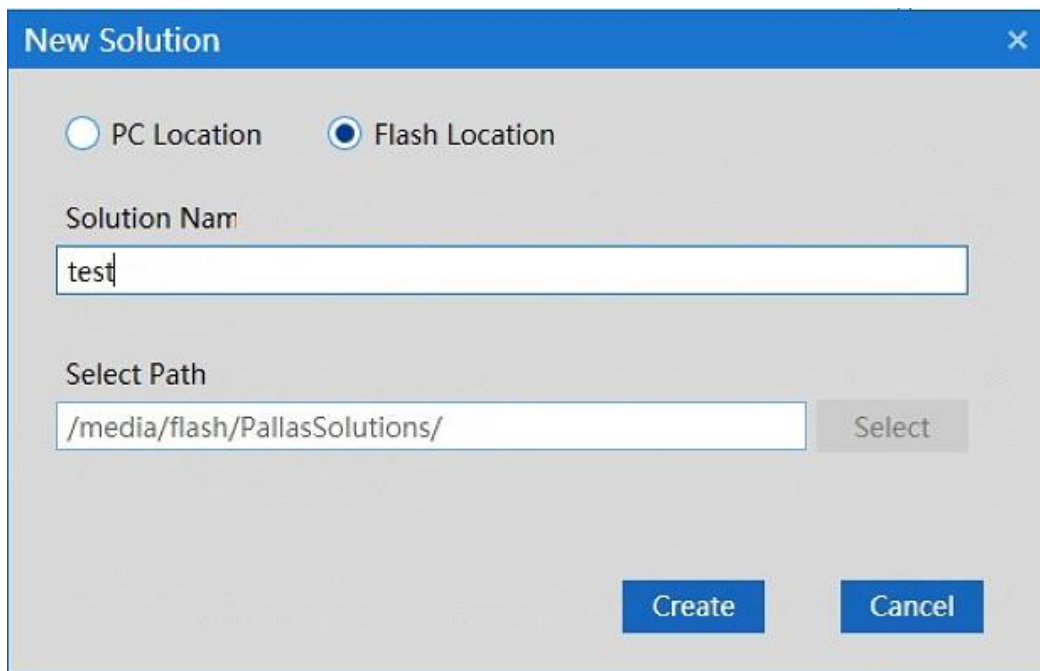


Figure 6-28 Enter a solution name

Step 3 After the creation is completed, the corresponding solution file will appear below "Remote Location". Expand the "test" file, and then the "project" file, which contains the "main.ql" and "data.qlv" program files, as shown in Figure 6-29.

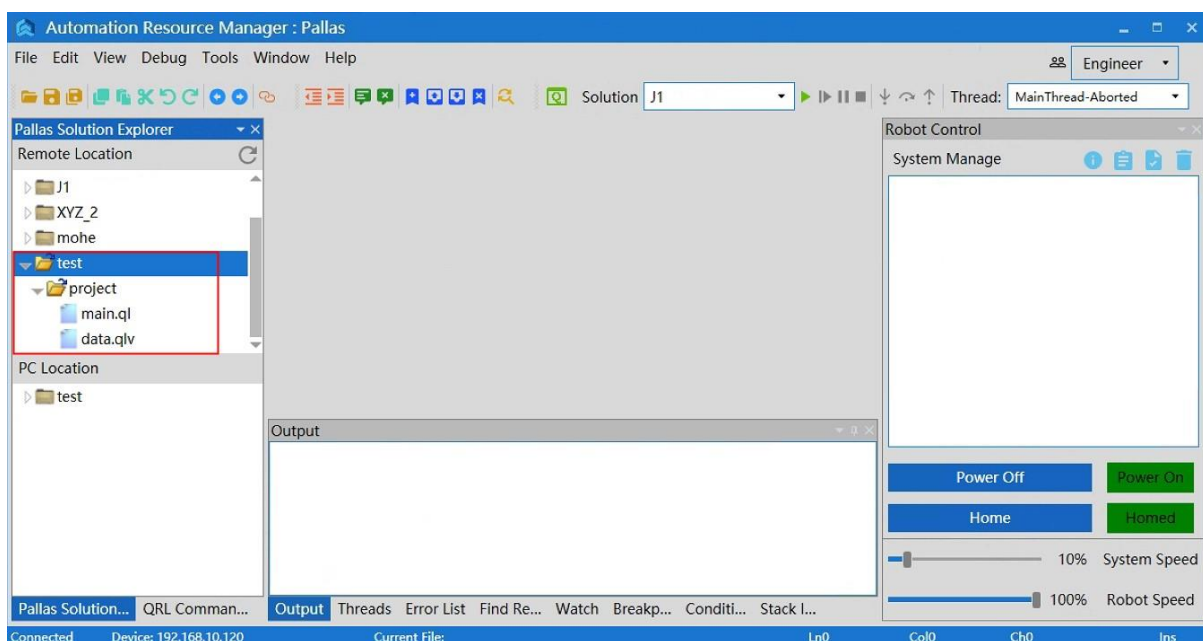


Figure 6-29 "New Solution" file interface

6.5.3 Introduction to "main.qml"

"main.qml" is the main file of the program. Robot motion, logical operation, condition control, loop statement control, thread control, etc. written in the program can be written in this file. Double click to open the "main.qml" file, the corresponding program content will appear in the middle of the ARM debugging interface, as shown in Figure 6-30. The program content in the figure is the default program in the new solution.

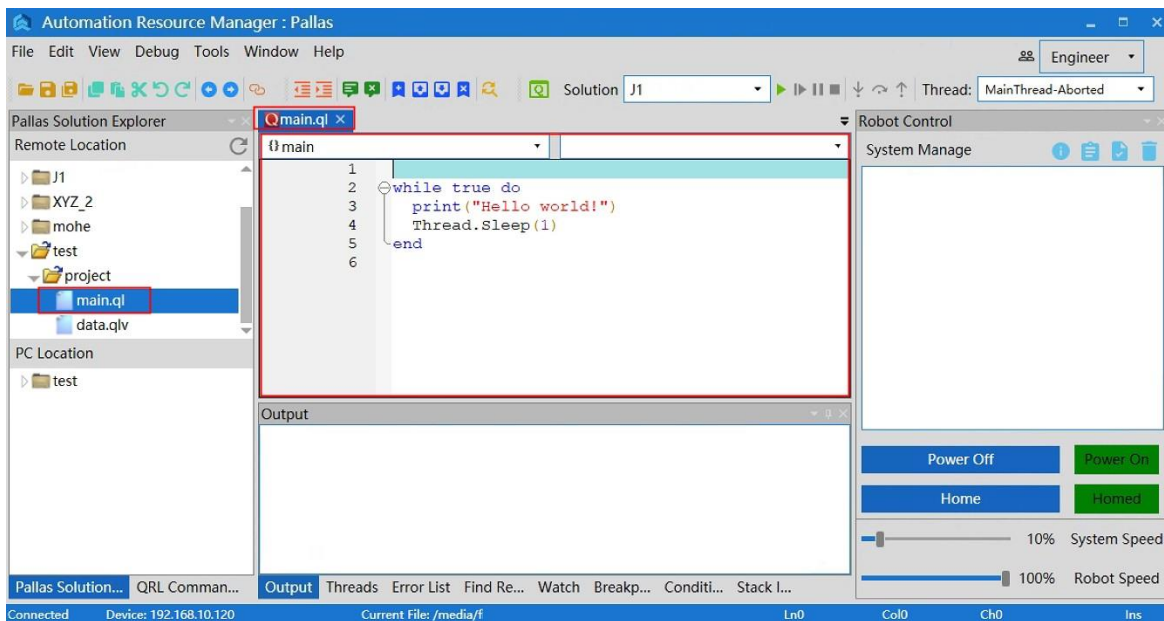
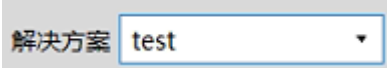



Figure 6-30 "main.qml " interface

Run the "test" solution; Select "test" in  at the top of the ARM debugging interface and click the button  to run it. At this point, the program will output "Hello world!" below in a circular way, as shown in Figure 6-31.

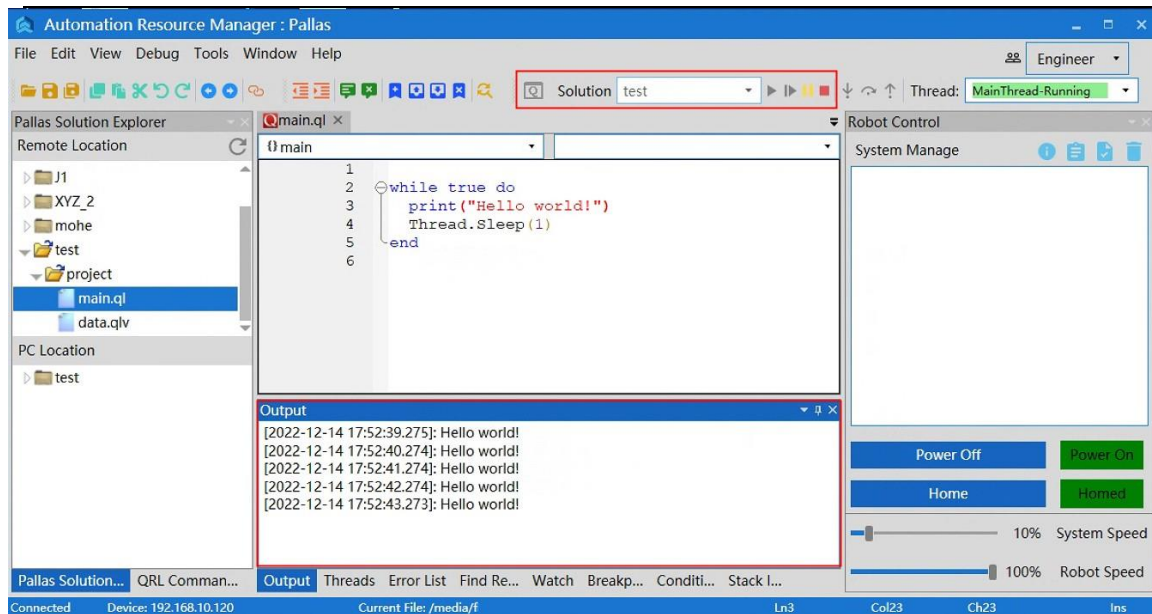


Figure 6-31 Run the solution

**NOTE**

For details of QRL program content, please refer to the "QKM Robot (QRL Language) Programming Manual".

6.5.4 Introduction to "data.qlv"

"data.qlv" is the robot motion point and motion parameter setting file. Double-click to open the "data.qlv" file, and the "data.qlv" interface will pop up, as shown in Figure 6-32. The interface contains: Location, LocationJ, Profile, Location Array, LocationJ Array, Profile Array. It is an interface of setting robot motion point information and motion parameter information.

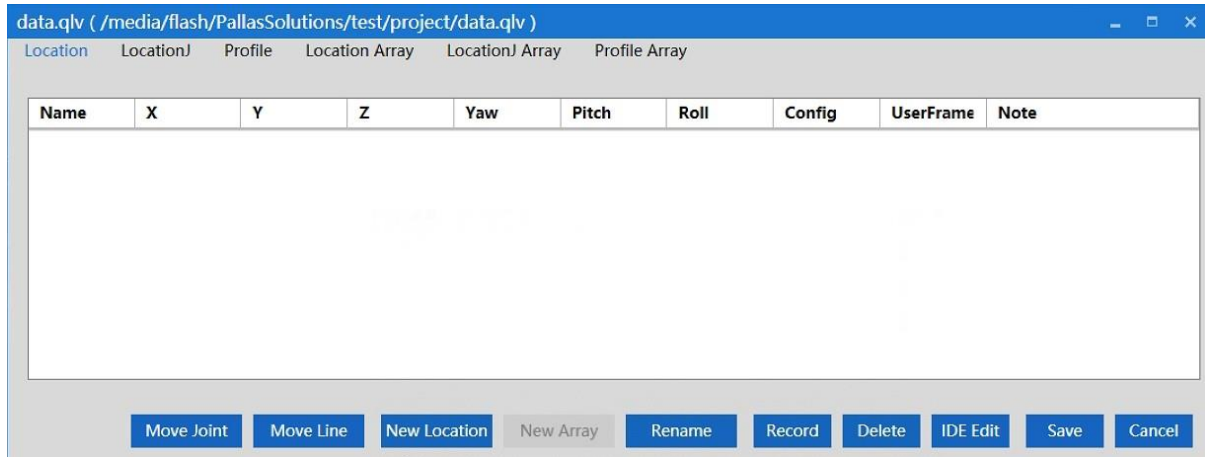




Figure 6-32 "data.qlv" interface

Introduction to Buttons	
Move Joint	Switch to the  pattern to control the joint movement of the robot to the selected point position
Move Line	Switch to the  pattern to control the linear movement of the robot to the selected point position
New Location	Add the point of the robot's current position in the current interface
New Profile	Use in the Motion Parameters interface to add motion parameters
New Array	Only use in Location Array/ LocationJ Array/Profile Array to add point/motion parameters of array type

Rename	Rename the point name
Record	Select a point to record the current robot position as that point information
Delete	Select a point and delete it; or select an array and delete it
IDE Edit	Switch to file programming and manually write coordinate points or motion parameters
Save	Save modified information in "data.qlv"
Cancel	Cancel information modification and close the "data.qlv" interface

Step 1 New Location; Click "New Location" in "Location", and the point information of the current robot's Cartesian position will appear in the interface. The point name is the default name, and you can click Rename to modify it, as shown in Figure 6-33.

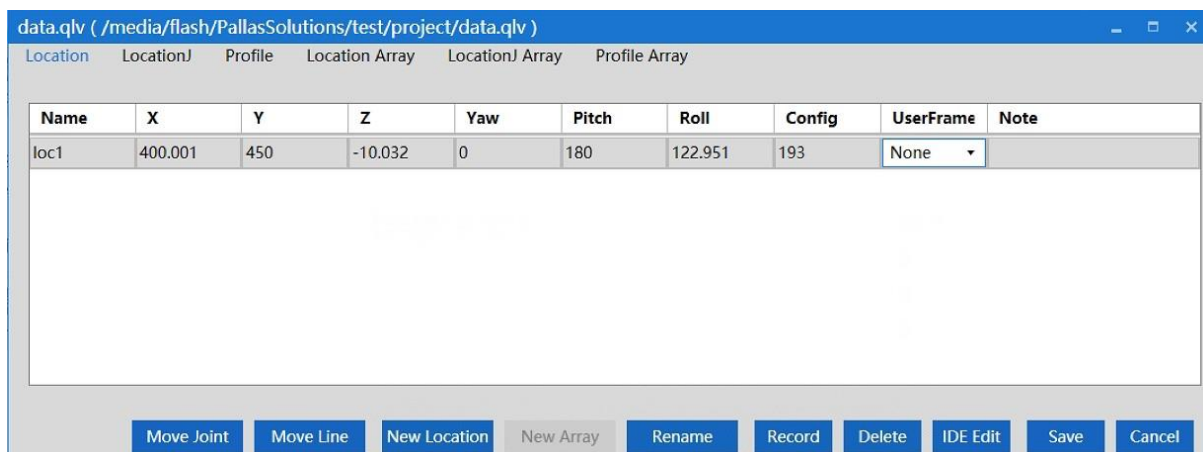


Figure 6-33 New Location

Step 2 New LocationJ; Click "New Location" in "LocationJ", and the point information of the current robot's axis coordinate position will appear in the interface. The point name is the default name, and you can click Rename to modify it, as shown in Figure 6-34.

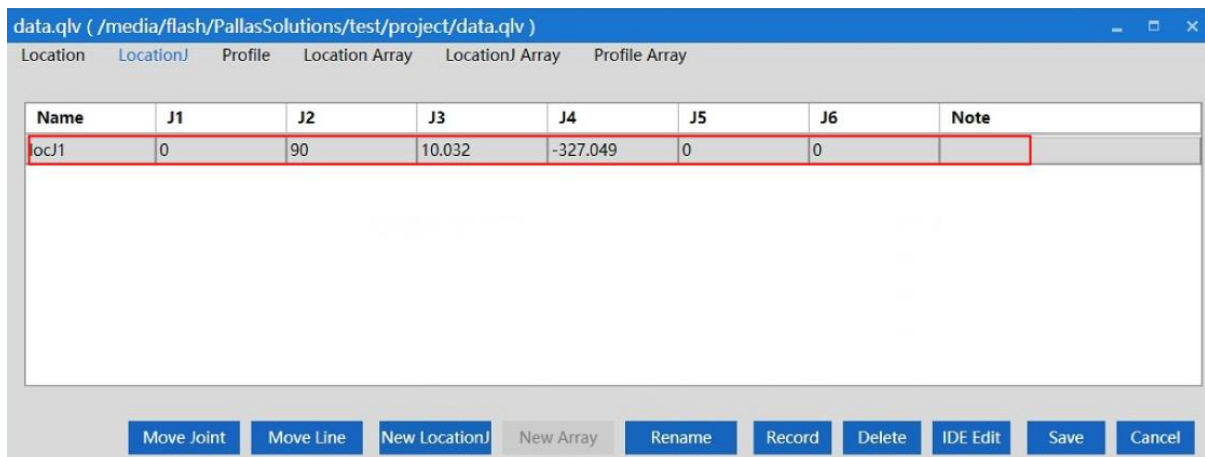


Figure 6-34 New LocationJ

Step 3 New Profile; Click "New Profile" in "Profile", and the default motion parameter information will appear in the interface. The motion parameter name is the default name, and you can click Rename to modify it, as shown in Figure 6-35.

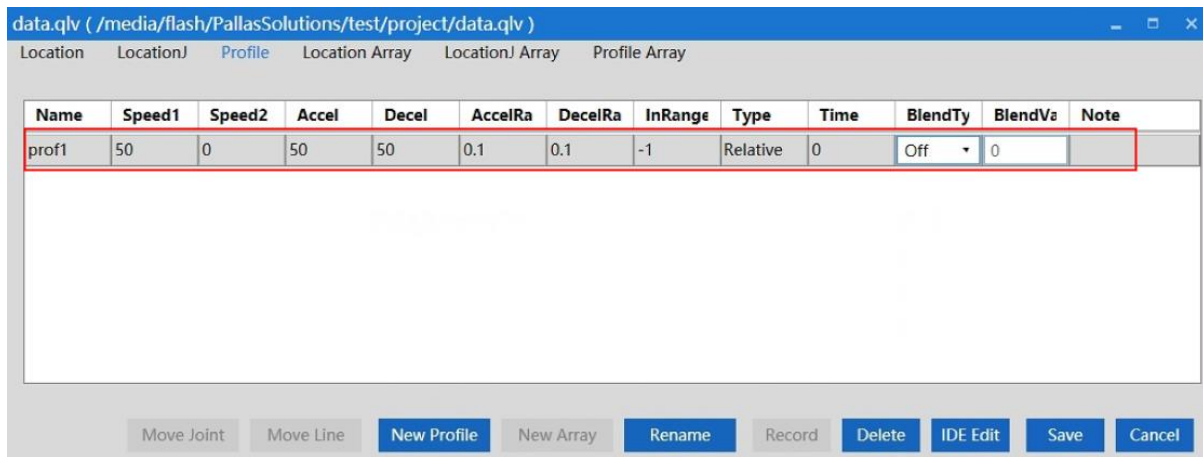


Figure 6-35 New Profile

Step 4 New Location Array; Click "New Array" in "Location Array", and the "New Array" interface will pop up. Enter the array name and array length, and click "OK", as shown in Figure 6-36.

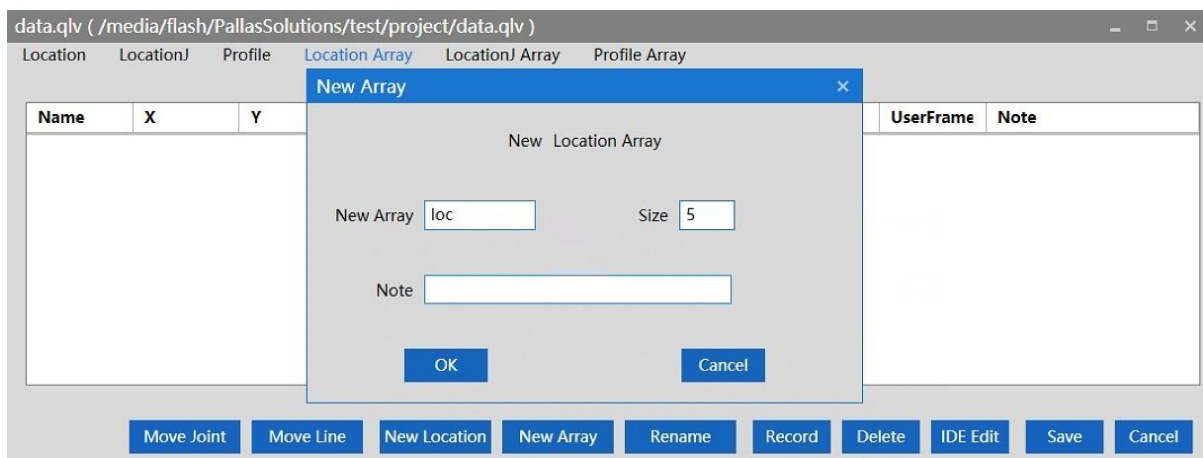


Figure 6-36 New Location Array

After completion, the "Location Array" information will appear, and the point will be recorded as the robot's current Cartesian coordinates, as shown in Figure 6-37.

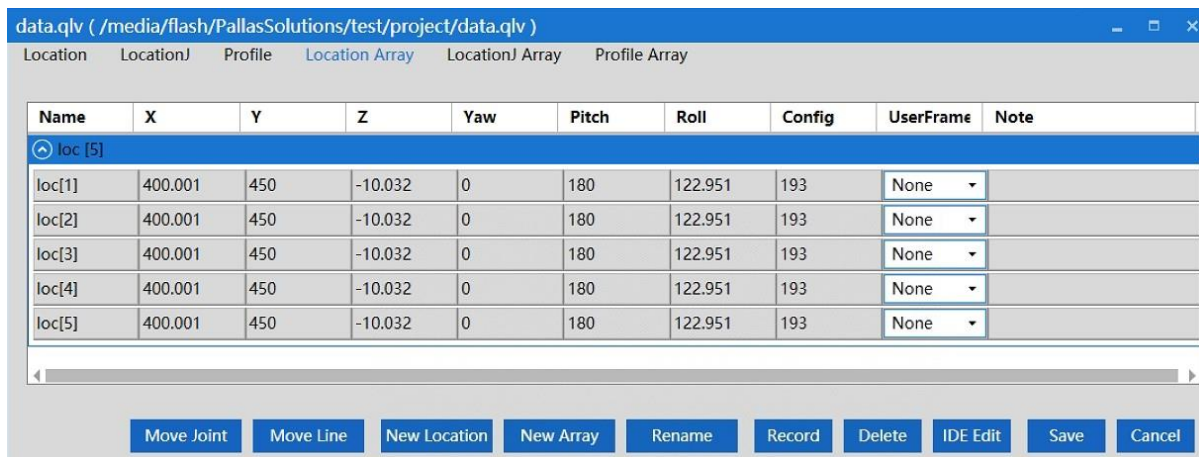


Figure 6-37 "Location Array" information interface

Step 5 New LocationJ Array; Click "New Array" in "LocationJ Array", and the "New Array" interface will pop up. Enter the array name and array length, and click "OK", as shown in Figure 6-38.

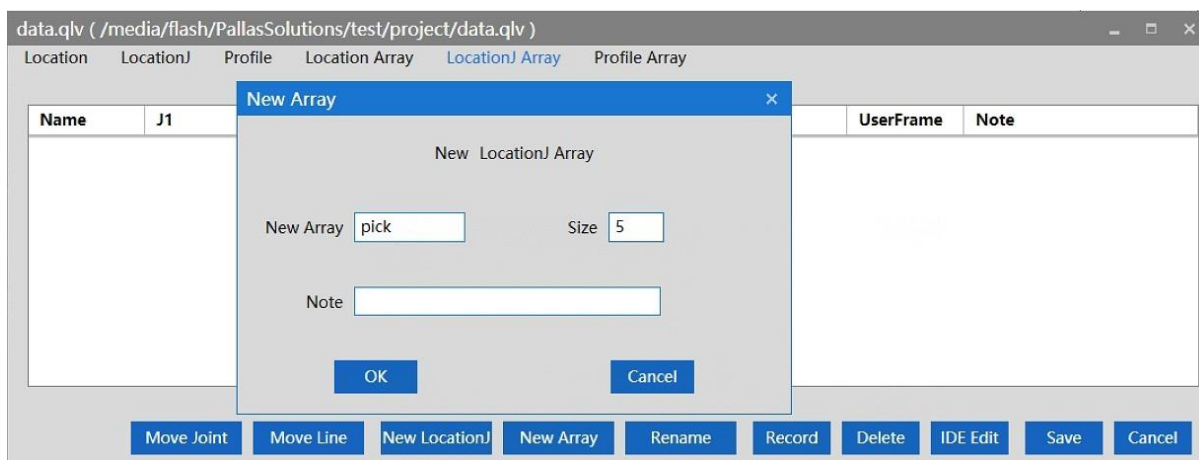


Figure 6-38 New LocationJ Array

After completion, the "LocationJ Array" information will appear, and the point will be recorded as the robot's current axis coordinates, as shown in Figure 6-39.

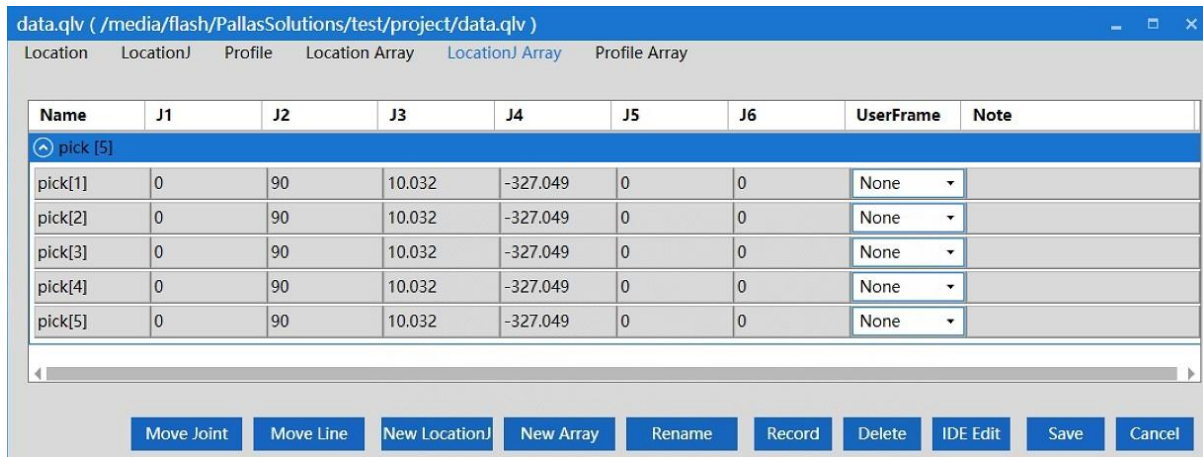


Figure 6-39 "LocationJ Array" information interface

Step 6 New Profile Array; Click "New Array" in "Profile Array", and the "New Array" interface will pop up. Enter the array name and array length, and click "OK", as shown in Figure 6-40.

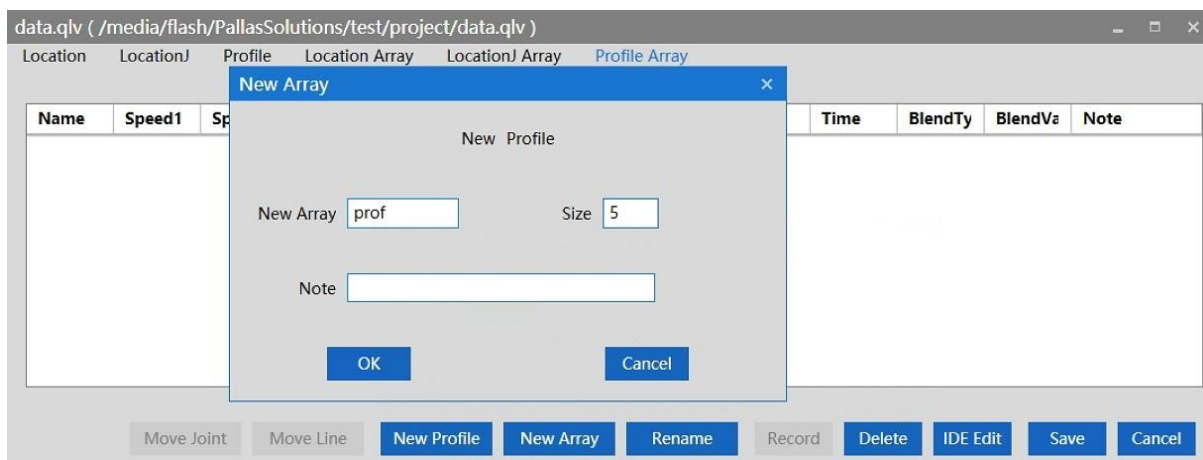


Figure 6-40 New Profile Array

After completion, the "Profile Array" information will appear, and the motion parameter information will be the default value, as shown in Figure 6-41.

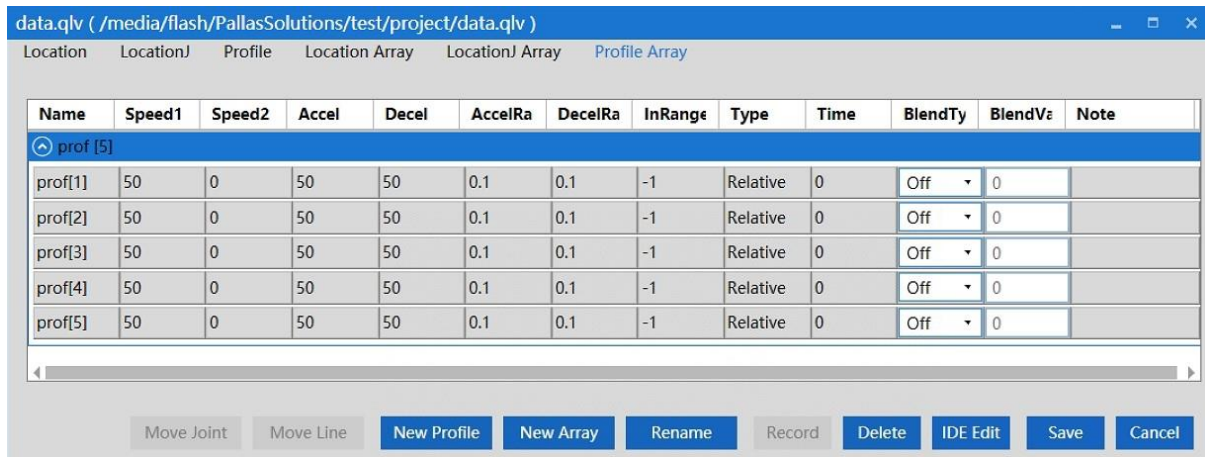


Figure 6-41 "Profile Array" information interface

Step 7 Click "IDE Edit", and the program contents of "data.qlv" will appear in the ARM debugging interface, showing the point and motion parameter information added in the above steps, as shown in Figure 6-42.

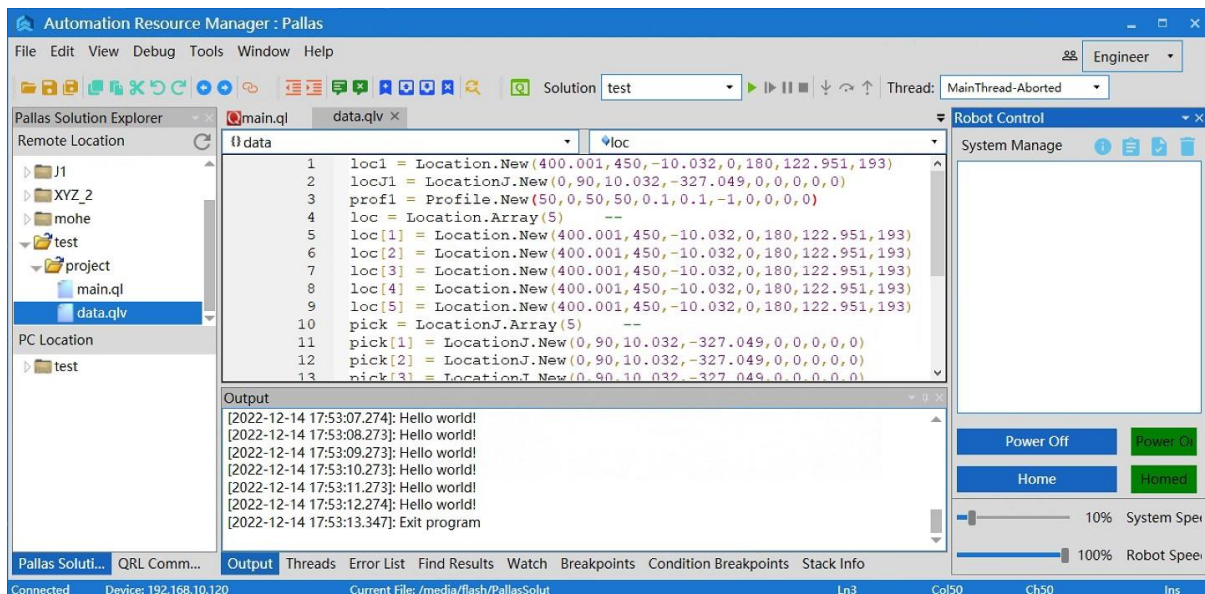


Figure 6-42 "data.qlv" program content

6.5.5 Saving and downloading program locally

Step 1 Select the solution folder to be saved, such as "test", click "test" and drag it to "PC Location", the download history path will pop up, as

shown in Figure 6-43.

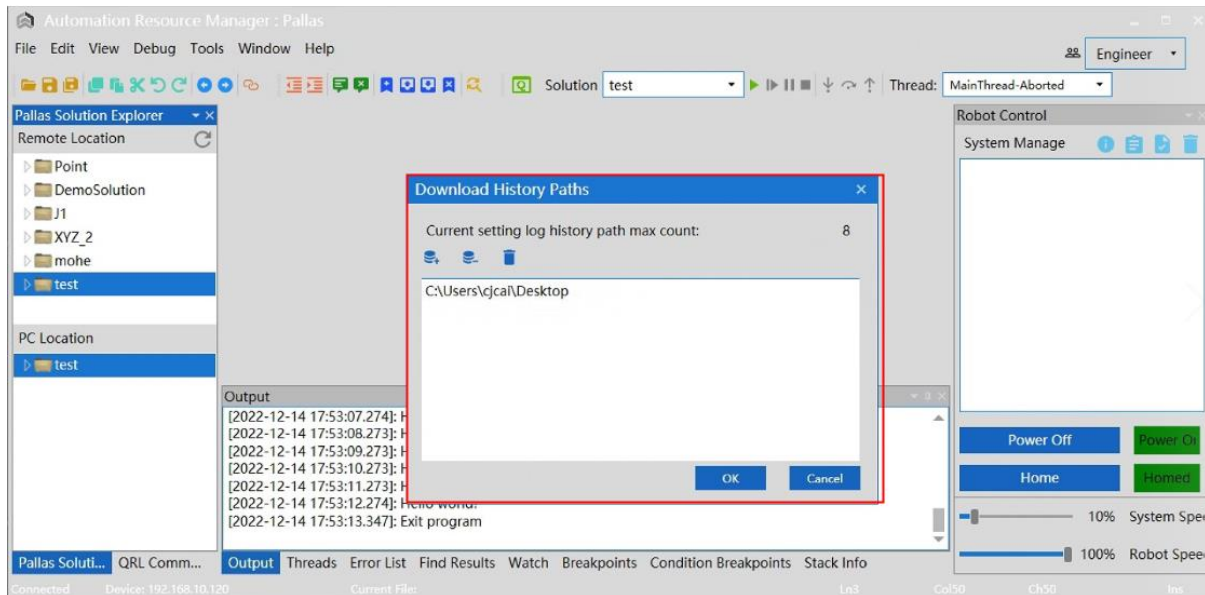



Figure 6-43 Save to "PC Location"

Step 2 Click the button  in the download history path, select the path where the file needs to be saved, and click "OK".

Step 3 A path will appear in the download history path, select this path, and click "OK" below.

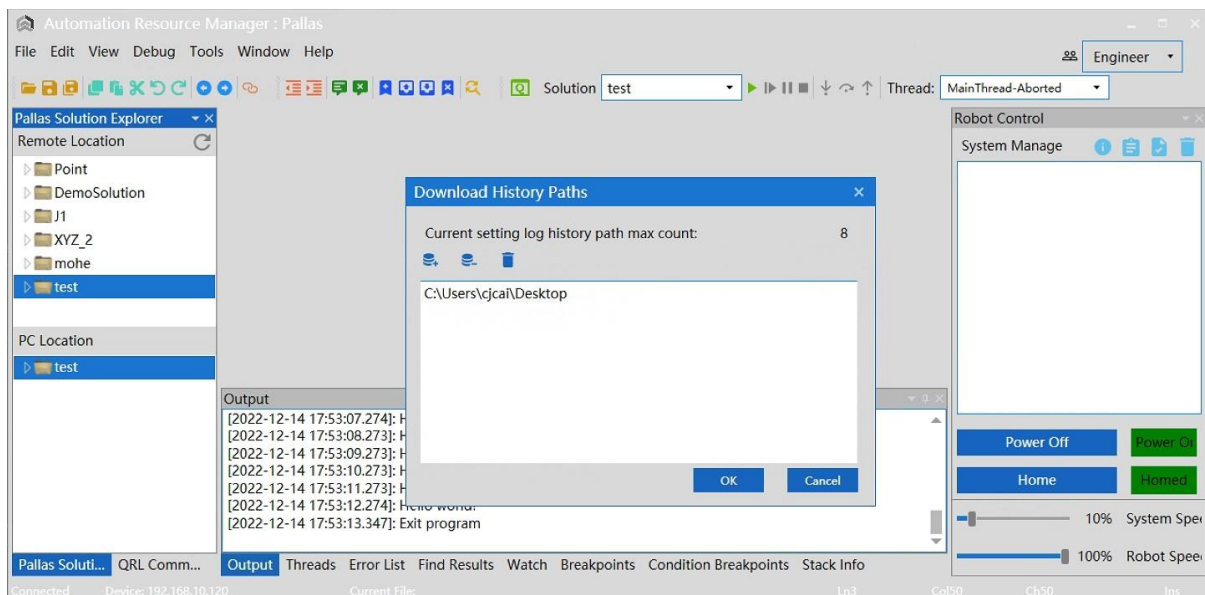


Figure 6-44 "Download History Paths" interface

Step 4 After completion, the file will appear in "PC Location", and the program file will also appear in the corresponding save path, as shown in Figure 6-45.

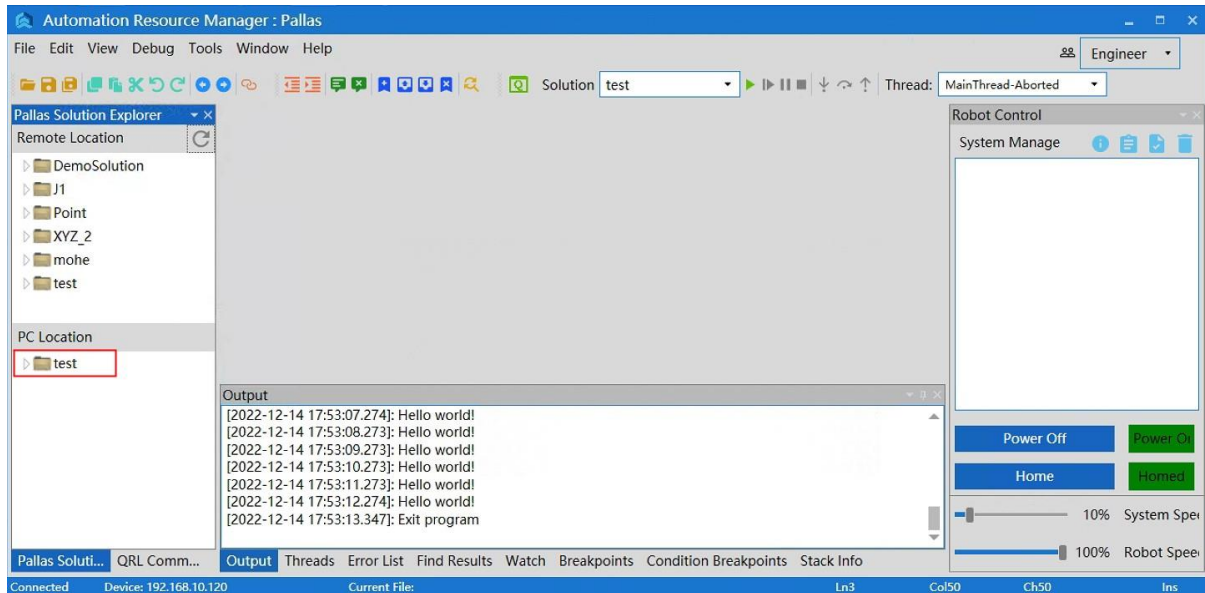


Figure 6-45 "PC Location" file interface

6.6 Manual jog teaching

On the ARM interface, click < Tools > → < Robot Controls > → < Jog Control >, and the point teaching interface pops up, as shown in Figure 6-47.



NOTE

When the click operation is enabled, the system automatically switches to manual mode.

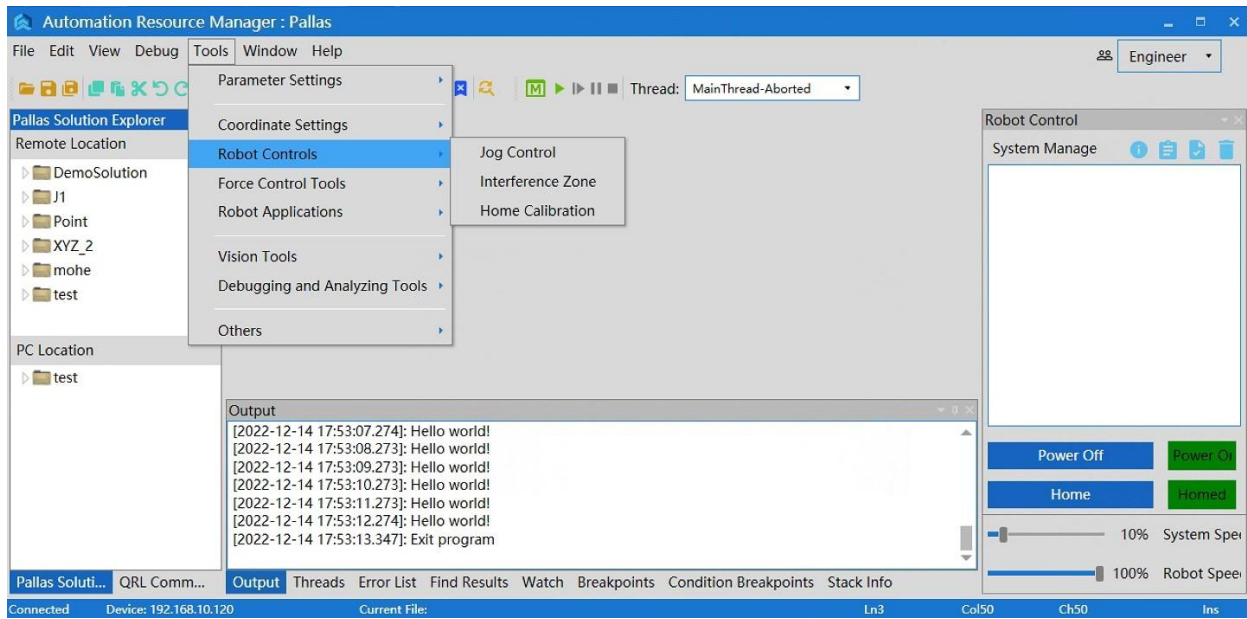


Figure 6-46 Jog teach

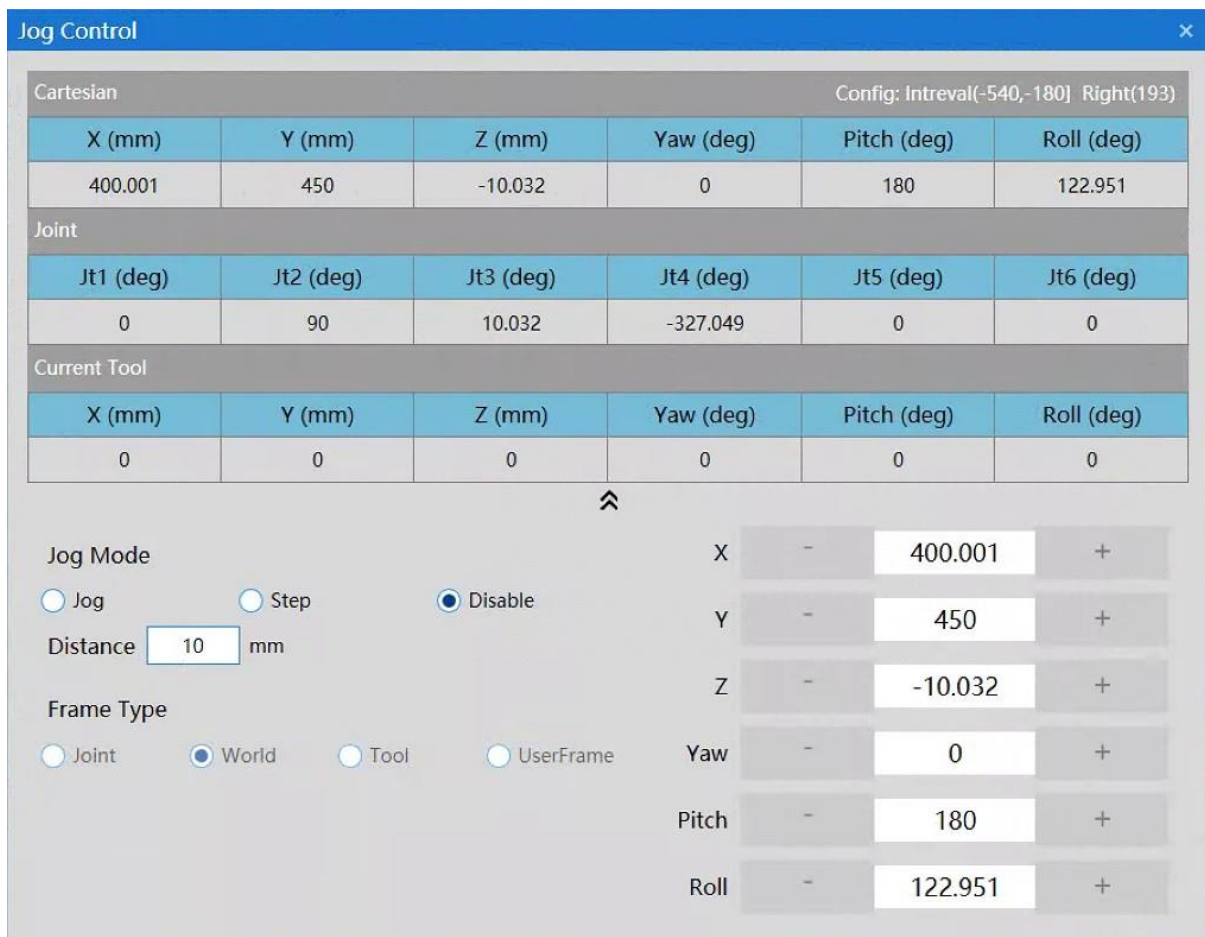



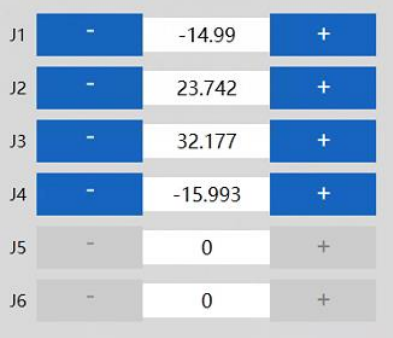
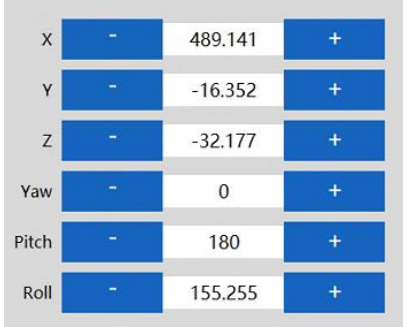
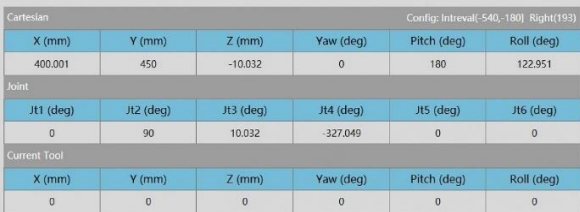


Figure 6-47 Teach interface

Table 6-2 Introduction to tools on the jog teach interface

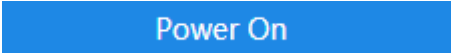
Function	Diagram	Description
Frame Type		<p>You can select [Joint],[World],[Tool] or [UseFrame].</p>
Jog Mode		<p>You can select [Jog],[Step] or [Disable] in this mode.</p>
Inching distance		<p>Manually enter the distance value for each inching.</p>
Robot coordinate	 <p>Coordinates in [Joint] mode</p> <p>Or</p>	<p>The coordinate values of ends of the current robot in different coordinate systems include X,Y,Z,Yaw,Pitch,Roll; or J1,J2,J3,J4,J5,J6. "+" and "-" light up to</p>


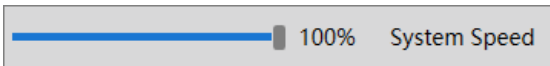
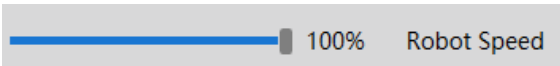
	 <p style="text-align: center;">Coordinates in [World/Tool/UseFrame] mode</p>	<p>indicate that it can be jogged.</p>
<p>Jog coordinate values</p>		<p>If you need to control the motion of the robot separately, you can click <X +>, <X->, etc. to control the motion of the robot in the direction of X, etc.</p>

6.7 Servo power-on

When controlling the motion of the robot through the ARM programming environment, you must first power on the robot via servo.

Table 6-3 Introduction to tools on the Servo power-on interface

Power on		Click < power on > to
----------	---	-----------------------

		control the robot to power on
Home		Click < Home > to control the robot to return Home
System Speed		The user adjusts the running speed of the whole system by percentage.
Robot Speed		The user adjusts the running speed of the robot by percentage.

The robot can be powered on using the two methods as follows.

After the robot is powered on for the first time or restarted after a power-off, a <Unhome> button appears on the jog teach page, so the robot needs to return to zero after it is powered on via servo.



NOTE

Method 1 (jog teach):

Click the <Home> button on the jog teach interface to enable the robot to return to zero.

Method 2 (send macro instruction):

Enter Robot.Home [robotIndex] in the instruction editing area on the macro command debugger to send a power-on instruction to the robot. (Where robotIndex is the index number of the online robot .)

For example, Robot.Home 1

```
//the current robot at the first node is powered
```

```
on
```

Method 1 (jog teach):

Click the <Power> button on the jog teach interface to power on the robot via servo, as shown in Figure 6-48.

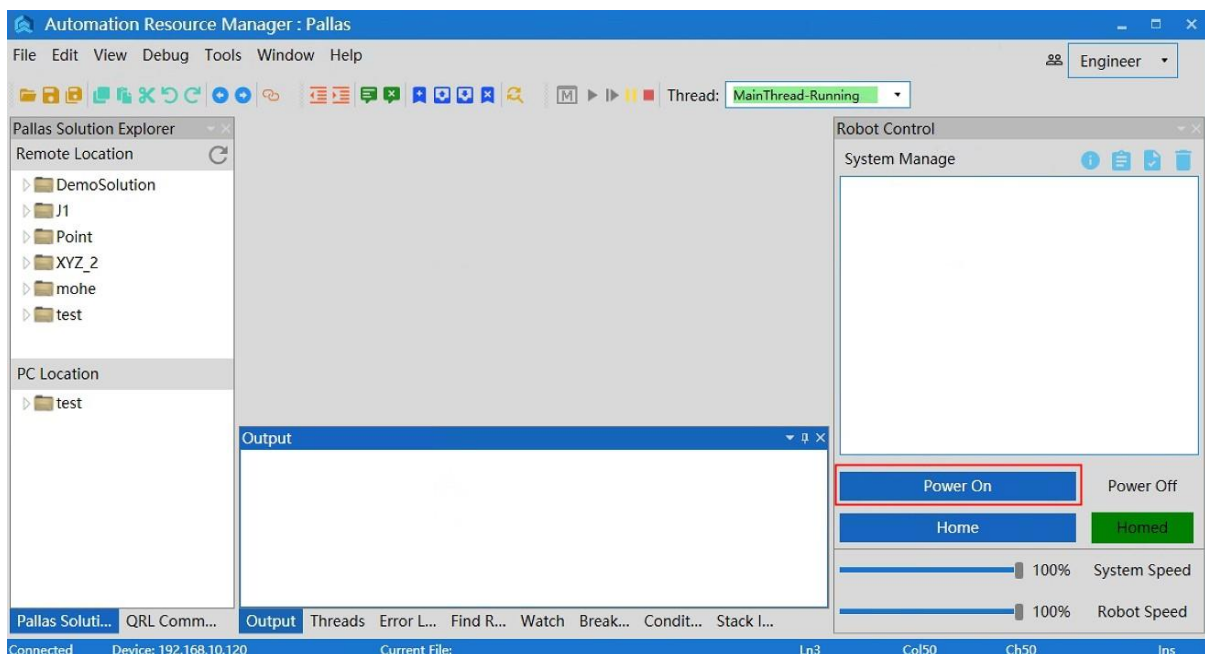


Figure 6-48 Power-on button interface

Method 2 (send macro instruction):

Prerequisites: ① Manual or auto mode; ② The control authority is 0/1 (set authority with System.LogIn).

Enter Robot.PowerEnable [robotIndex],1 in the instruction editing area on the macro language development interface to send a power-on instruction to the robot. (Where robotIndex is the index number of the online robot.)

```
For example, Robot.PowerEnable 1,1 //the robot at the first  
node is powered on
```

6.8 Speed adjustment

There are three speeds:

- System speed;
- Robot speed;
- Speed in robot motion parameters.

6.8.1 Adjustment of system speed

Under the control of the same controller, one or more robots cooperate with each other to complete one or more actions, forming a complete robot operating system including all devices participating in the motion (s). The system operates at a certain speed which is called system speed. The system speed can be adjusted using two methods:

Method 1 (jog teach):

Click the <System speed> slider on the bottom right of the ARM debugging interface and slide it to adjust the motion speed of the robot, as shown in Figure 6-49.

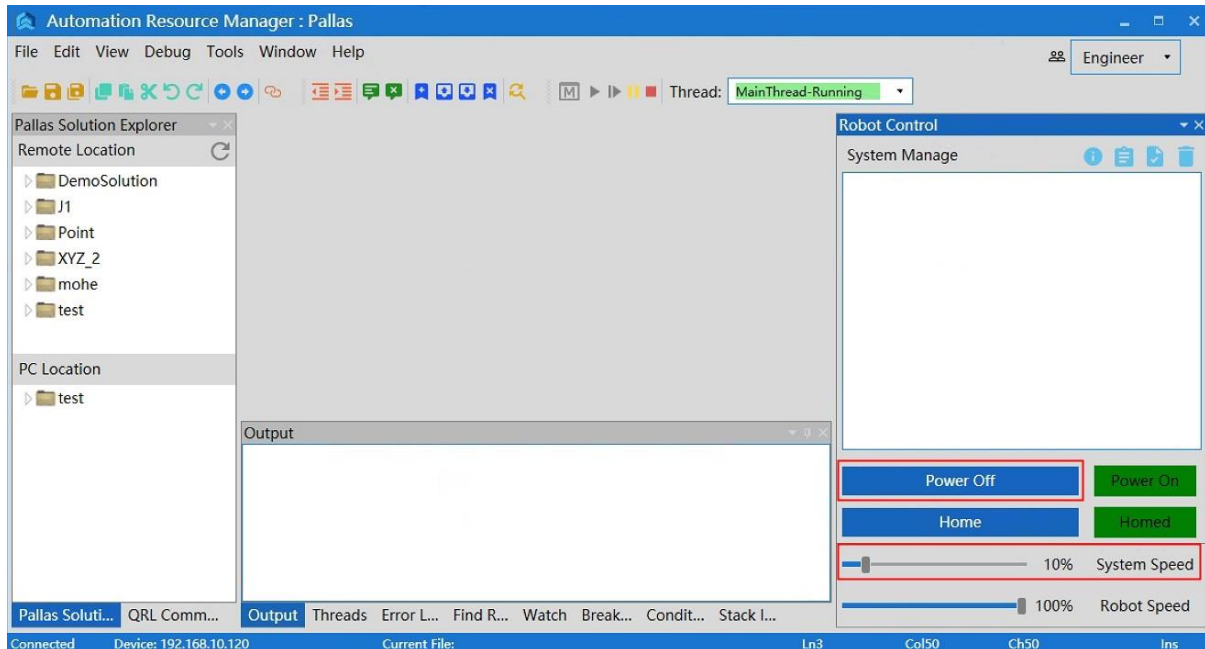


Figure 6-49 Adjustment of system speed

Method 2 (send macro instruction):

Enter `System.Speed [value]` in the instruction editing area on the macro language interface to send instructions to the robot. (Where value indicates the value of system speed of the robot and its type is double)

For example, `System.Speed 50` // The speed of all robots in the node is set to 50.

6.8.2 Adjustment of robot speed

The speed of a single robot with regard to a complete motion trajectory can

be adjusted with the two methods:

Method 1 (jog teach):

Click the < Robot speed> slider on the bottom right of the ARM debugging interface and slide it to adjust the motion speed of the robot, as shown in Figure 6-50.

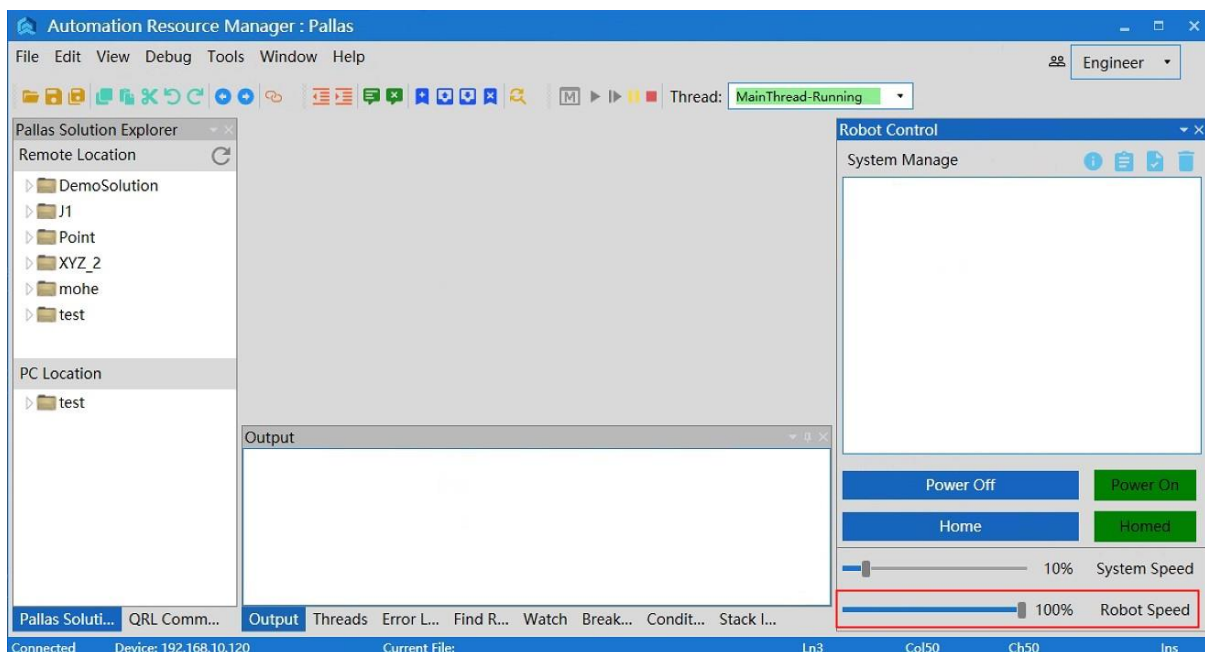


Figure 6-50 Speed adjustment

Method 2 (send macro instruction):

Prerequisites: (1) The robot is stopped; (2) The control authority is 0/1 (set authority with System.LogIn)

Enter `Robot.Speed [robotIndex], [value]` or `Robot.Speed [robotIndex]` in the instruction editing area on the macro language interface. (Where `robotIndex` is the index number of the robot and its type is Integer; `value` is the speed value of the robot system, it is a global variable ranged from 0 to 100, and its type is

double.)

```
Example 1: Robot.Speed 1,10 // Set the speed of the first robot to  
10
```

```
Example 2: Robot.Speed 1 // Return to [ 0 10] Note: Set the  
speed of the first robot to 10
```

1. The life of each part of the robot can only be guaranteed if the robot's running speed does not exceed the rated speed and rated load. Using the robot under the condition of exceeding the rated load or rated speed for a long time will cause the speed reducer and other parts to accelerate wear and lead to reduced service life.



2. The reference joint speed in the robot configuration file is calculated according to the rated speed of the motor (3000 rpm). When joint motion is used in the actual movement, the multiplication of Speed, System Speed and Robot Speed in the Profile parameter is equal to 100%, the fastest speed of the robot joint movement is 3000 rpm. An example is as follows:

(1) profile speed = 100%, system speed = 100%, robot speed = 100%, then $100\% * 100\% * 100\% = 100\%$; at this time, the fastest speed of the robot joint movement is 3000 rpm.

(2) profile speed = 200%, system speed = 50%, robot speed = 100%, then $200\% * 50\% * 100\% = 100\%$; at this time, the fastest speed of the robot joint movement is 3000 rpm.

6.8.3 Speed adjustment during motion

Method of adjusting the speed of a certain point in the process of robot motion (send a macro instruction):

Step 1 Enter Profile [profileName] = [Speed, Speed2, Accel, Decel, AccelRamp, DecelRamp, InRange, Type, Time, BlendType, BlendValue] in the instruction editing area on the macro language interface to create a new name of robot speed and assign values to its parameters.

profileName is the name of objects for motion parameters.

Speed/Speed2/Accel/Decel/AccelRamp



/DecelRamp/InRange/Type/Time/BlendType/BlendValue

respectively represents the information on speed. For

details about parameters, please refer to the "QKM Robot

Instruction Manual". (If one of the parameters is not

assigned a value, it is represented by "0" or a space.)

For example, Profile prof2 = 80,0,80,80,0.1,0.1 // Create an object named prof2 and assign a value to the parameter.

Profile prof3 = 80,80,80,0.1,0.1 // Create an object named prof3 and assign a value to the parameter.

Prerequisite: The control authority is 0/1 (set authority with System.LogIn).

Step 2 Enter Profile.Set [robotIndex], [ProfileName] and send an instruction to the robot. (Where robotIndex is the index of the robot and its type is Integer; ProfileName is the name of the speed (variable) and its type is Profile)

For example, Profile.Set 1, prof2 // The instruction for assigning value to prof2 has been executed before, then set the Profile used during the motion of robot 1 to be prof2.

6.9 Emergency stop and recovery

6.9.1 Emergency stop

During the process of manual operation, an emergency stop needs to be

performed when a collision or other unexpected conditions occur due to nonproficiency of the operator. Operation: Press the emergency stop button.

6.9.2 Recovery

After the emergency stop, some manual operations need to be performed to push the robot to a safe position, and then release the emergency stop button to restore the robot to its normal working state for safety.

The manual operations should be adjusted according to different scenarios. The robot may be stopped in an open area or stuck between obstacles. The handling methods are shown in Table 6-4. Ensure that the robot is in a safe position before releasing the emergency stop button to complete the recovery on it after the emergency stop.

Table 6-4 Handling methods

Robot position	Handling
In an open area	Manually operate the robot and move it to a safe position.
In the case where it is blocked between obstacles but the obstacles are easy to be	Directly move away the obstacles around it, and then manually operate the robot to move it to a safe position.

moved away	
In the case the obstacles around it are not easy to be moved away and it is difficult to manually operate the robot and move it to a safe position	Release the brake button and manually operate the robot to move it to a safe position.

6.10 Robot power-off

When it is necessary to stop or maintain the robot, it needs to be powered off with the two methods as follows:

Method 1 (jog teach):

Step 1 Stop the program that the robot is running.

Step 2 Click the <Power Off> at the bottom right of the ARM debugging interface, as shown in Figure 6-51.

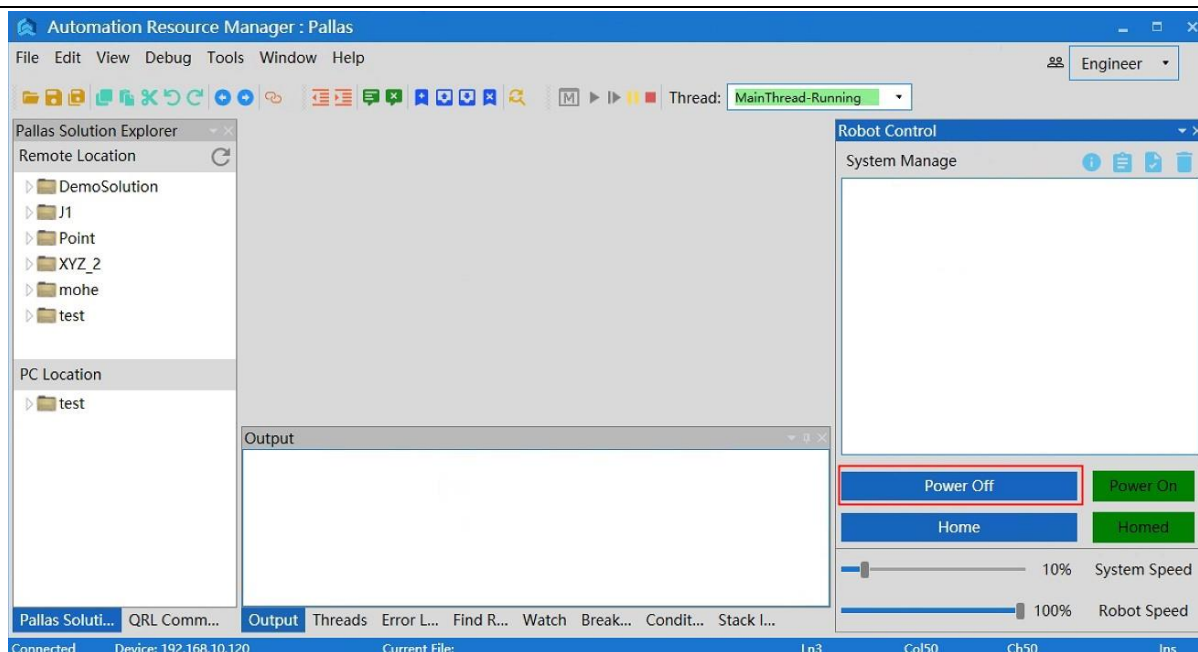


Figure 6-51 Teach interface in power-on state

Step 3 Unplug the power cable plug from the robot (turn off the power switch before unplugging the power cable plug if there is a power switch on the robot).

Method 2 (send macro instruction):

Prerequisites: ① Manual or auto mode; ② The control authority is 0/1 (set authority with System.LogIn).

Step 1 Stop the program that the robot is running.

Step 2 Enter Robot.PowerEnable [robotIndex], 0 in the instruction editing area on the macro language development interface. (Where robotIndex is the index number of the online robot.)

For example, Robot.PowerEnable 1,0 // the robot at the first

node is powered off

Step 3 Unplug the power cable from the robot (turn off the power switch before unplugging the power cable if there is a power switch on the robot).

Method 3 (press the emergency stop button):

Step 1 Stop the program that the robot is running.

Step 2 Press the emergency stop button and the robot is power off.

Unplug the power cable plug from the robot (turn off the power switch before unplugging the power cable plug if there is a power switch on the robot).

Chapter 7 Technical service

QKM Technology Co., Ltd. is committed to providing you with technical information on machine motion and operation to help you remove faults and reply to your inquiry in detail. If your robot or equipment fails during use, you can contact our service department and provide information below as much as possible:

- Model and serial number of robot or equipment
- Model and serial number of control system
- Control system version number
- Existing applications
- Description of the problem, duration and frequency of the fault, etc.



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QKM Technology(Dongguan)Co.,Ltd

Tower A, Building 17, Headquarters 1, No.4 Xinzhu Road, Songshan Lake
High-tech Industrial Development Zone, Dongguan , Guangdong,China

Tel: +86 0769-27231381

Fax: +86 0769-27231381-8053

Zip code: 523808

Email: service@qkmtech.com

Website: www.qkmtech.com



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