Applied Robotics™
Solutions in reach

EPSILON ES200
TOOL CHANGE SYSTEM

95627, Rev 03

September 5, 2022

648 Saratoga Road
Glenville, NY 12302 USA
Phone: +1 518 384 1000
Fax: +1 518 384 1200
www.appliedrobotics.com

REVISION

Revision	Date	Author	Description
00	03/31/2016	TM	Initial Release
01	08/19/2016	SC	- Updated Table 7.2-1 "Tool Changer Couples, But…" - Updated references in Table 8-1. - Updated Moment Rating - Added Information for Noise Emissions
02	09/05/2022	DS	Sections 1, 3, 5.1, 5.2, 9, 10.2, and 11.
03	08/04/2023	TM	ADDED ISO 11 ,12 patterns & A3 hardware kit

CONTENTS

1 LIFETIME GUARANTEE 5
2 PRECAUTIONS 6
3 SYSTEM DESCRIPTION 7
3.1 ROBOT SIDE 8
4 TECHNICAL SPECIFICATIONS 10
5 INSTALLATION 11
5.1 ROBOT SIDE INSTALLATION 11
5.1.1 M16 Hardware (NON-ISO PATTERN) 12
5.1.2 M12 Hardware (ISO 11 PATTERN) 13
5.1.3 M12 Hardware (ISO 12 PATTERN) 14
5.2 TOOL SIDE INSTALLATION 15
5.3 CONNECTING THE AIR SUPPLY 17
5.4 COUPLE AND UNCOUPLE SIGNALS 18
5.5 TOOL PRESENT SIGNAL (OPTIONAL) 21
5.6 GROUNDING CONNECTION 22
6 GUIDE TO OPERATION 23
6.1 INITIAL TEST 23
6.2 PROGRAMMING THE COUPLE AND UNCOUPLE POINTS 24
6.3 TOOL DROP PREVENTION 26
6.3.1 Mechanical Lock Design Feature 26
6.4 RECOMMENDED SEQUENCE OF OPERATION 28
7 TROUBLESHOOTING 31
7.1 TROUBLESHOOTING GUIDE 31
7.2 TECHNICAL SUPPORT 31
7.3 TROUBLESHOOTING FAULT TREE 32
7.4 MANUAL UNCOUPLE 33
8 MAINTENANCE 34
8.1 PREVENTIVE MAINTENANCE 36
8.1.1 Lubrication 36
8.1.1.1 Tool Side 36
8.1.2 Visual Checks 37
8.1.2.1 Robot Side 37
8.1.2.2 Tool Side 38
8.1.3 Checking Wear of the Cam Locking Mechanism 39

9 SPARE PARTS 41
10 SPARE PARTS REPLACEMENT 42
10.1 ROBOT SIDE 42
10.1.1 Locating/Alignment Pins 42
10.1.2 Couple/Uncouple Sensing Module 43
10.2 TOOL SIDE 44
10.2.1 Locating Bushing 44
11 INFORMATIONAL DOCUMENTS 45

1 LIFETIME GUARANTEE

APPLIED ROBOTICS extends a lifetime guarantee to the components that make up the operating cam locking mechanism of the Epsilon Tool Changer. The following components are covered under APPLIED ROBOTICS Lifetime Guarantee.

PART NUMBER	DESCRIPTION
0201-P17N	RING, RETAINING EXTERNAL
85943-P1021	O-RING, .801 ID X .070 75 VITON (P)
1502-C13A	SUBASSY, PISTON ROD ERS200
1502-C09N	CAM, ERS200
49986	DOWEL, M12 X 55 DIN 6325-m6
49382	DOWEL, M10 X 40 (HARD STL) M6

APPLIED ROBOTICS warrants the Epsilon Tool Changer cam locking mechanism for the lifetime of the product against manufacturer's defects in materials and workmanship. Additionally, APPLIED ROBOTICS warrants the cam locking mechanism against wear that results in the Epsilon Tool Changer to lose repeatability and precision during the docking sequence of operation (Section 8.1.3). For the purposes of this warranty, APPLIED ROBOTICS defines the lifetime as 8 years or 8,000,000 total cycles completed with regularly scheduled maintenance as per Section 8 of this manual.

CONDITIONS OF THE WARRANTY:
Products shall have been subject to only normal use and service as instructed in this manual and shall not have been misused, neglected, altered, improperly set up or otherwise damaged; and there shall be no evidence of tampering or deliberate misuse or destruction.

Defects to APPLIED ROBOTICS products will be determined solely by APPLIED ROBOTICS and not by any representative or distributor of or for APPLIED ROBOTICS. Upon determination of a defect, APPLIED ROBOTICS sole obligation will be to provide replacement material for the defective part(s). APPLIED ROBOTICS is not liable or responsible for costs borne from lost production or labor related costs for repairing the defective part(s).

Any claim against APPLIED ROBOTICS for defects in material or workmanship must be in writing. APPLIED ROBOTICS must authorize the return of any allegedly defective part before it is returned. The party making the claim must prepay all shipping and transportation costs. APPLIED ROBOTICS will not accept charges for parts purchased unless the conditions of the warranty have been satisfied.

No APPLIED ROBOTICS representative or distributor is authorized to assume for APPLIED ROBOTICS any other obligations or liabilities in connection with the product or alter the terms of this warranty in any way.

APPLIED ROBOTICS shall not be liable for damages, including special, incidental or consequential damages arising out of or in connection with the performance of an APPLIED ROBOTICS product or its use by the owner.

2 PRECAUTIONS

READ MANUAL
Do not start, operate or service machine until you read and understand operator's manual. Failure to do so could result in serious injury.

HAND CRUSH NOTICE
Indicates the possibility for a crush force between components during coupling of the Robot and Tool Side.

⚠ DANGER — Indicates a hazardous situation which, if not avoided, will result in death or serious injury.

⚠ WARNING — Indicates a hazardous situation which, if not avoided, could result in death or serious injury.

⚠ CAUTION — Indicates a hazardous situation which, if not avoided, could result in minor or moderate injury.

NOTICE — Indicates a situation which, if not avoided, could result in equipment damage and voiding the manufacturer's equipment warranty.

IGNORING INFORMATION ABOUT POTENTIAL HAZARDS CAN LEAD TO SERIOUS HARM TO PERSONNEL AND/OR DAMAGE TO THE EQUIPMENT, AND MAY RESULT IN THE NULLIFICATION OF THE MANUFACTURER'S EQUIPMENT WARRANTY.

HEED ALL PRECAUTION NOTICES

3 SYSTEM DESCRIPTION

The Epsilon ES200 Tool Changer provides a strong and reliable method for a manipulator to quickly change between different tools/end-effectors. With Applied Robotics, Inc. patented six-sided design, the ES200 Tool Changer offers the maximum flexibility for any application.

The ES200 Tool Changer contains two major components:

Robot Side (ERS200) – Mounts directly to a robot flange utilizing a 200mm pattern (See Section 11).

Tool Side (ETS200) – Mounts directly to a tooling plate utilizing a 200mm pattern (See Section 11).

The Robot Side and Tool Side lock together by means of a double-acting, pneumatically driven cam locking mechanism. The six (6) cam self-centering locking mechanism allows for reliable and repeatable operation throughout the life of the tool changer with a unique wear compensating design. Each cam also contains a mechanical locking feature which prevents the Robot Side and Tool Side from separating/disconnecting in the event of power and/or air pressure loss. As the locking mechanism actuates, the Tool Side is physically connected and disconnected along with any utilities contained in the attached modules. Couple and uncouple position indication is provided by unidirectional differential pressure switches requiring no setting or calibration and are fully immune to EMI.

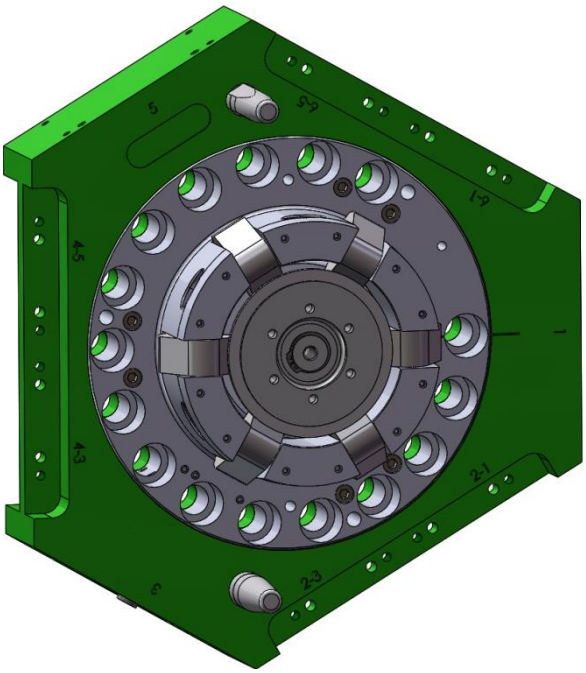


Figure 3-1. ERS200 Robot Side

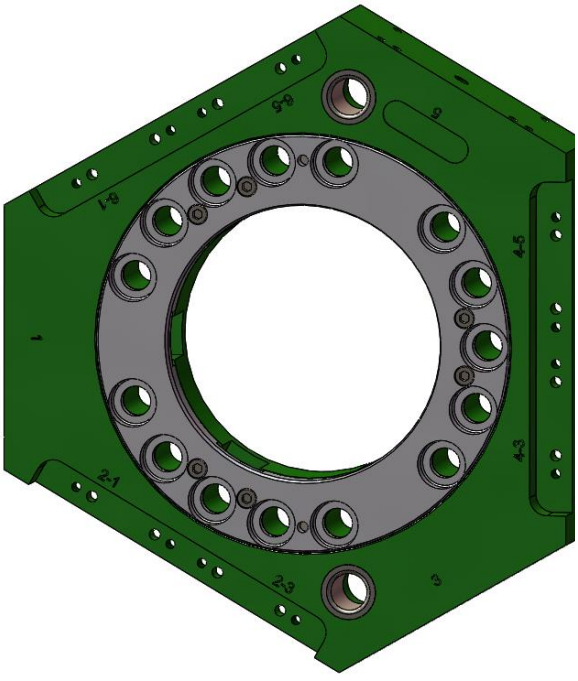
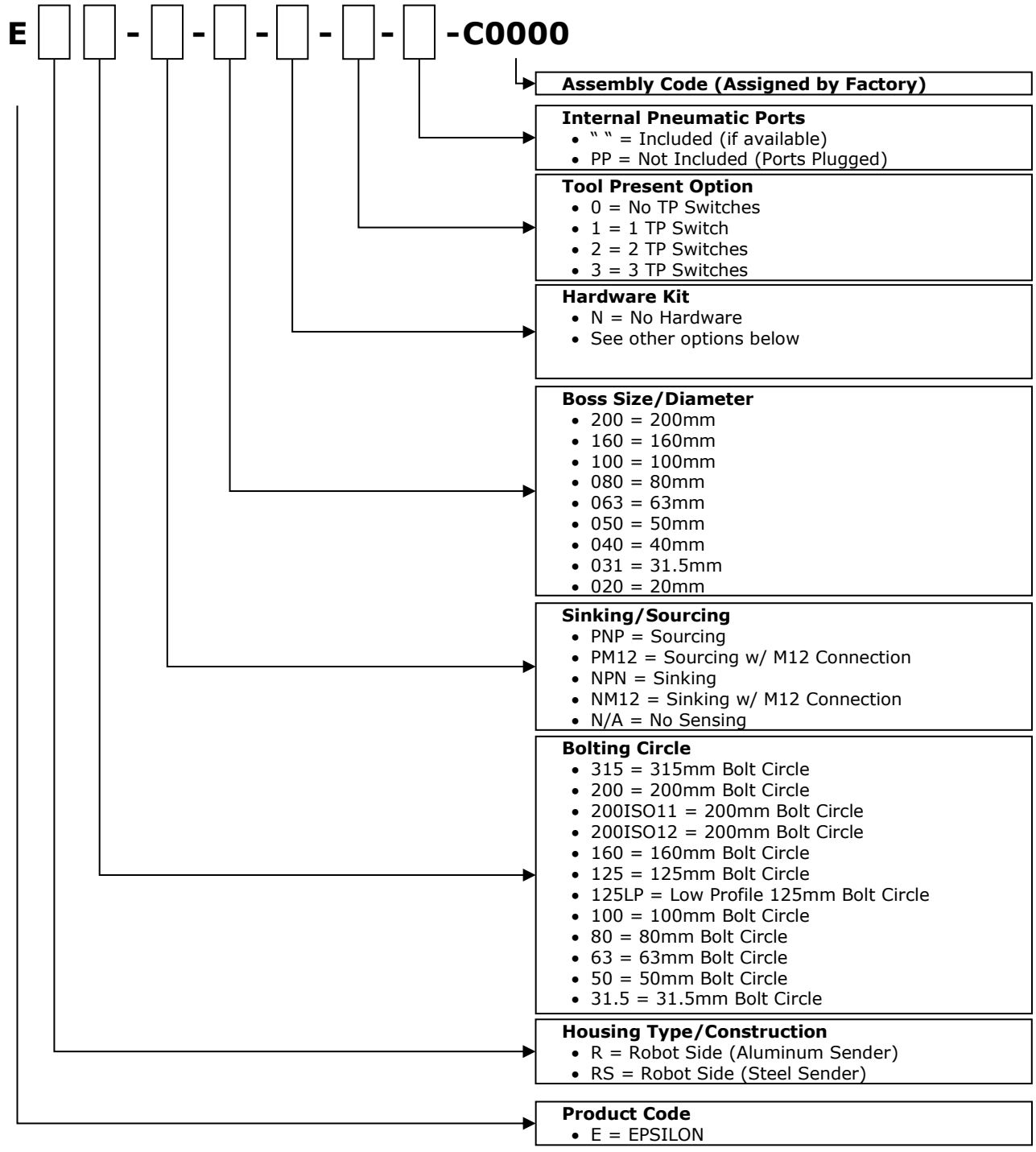


Figure 3-2. ETS200 Tool Side

3.1 ROBOT SIDE



Hardware Kits

N = No Hardware
A = 16xM16 SHCS w/ 1x12mm Dowel (ES200)
A2 = 6xM12 SHCS w/ 1x12mm Dowel (ES200)
A3 = 12xM16 SHCS w/ 1x12mm Dowel (ERS200)
A4 = 6xM12 SHCS w/ 1x12mm Dowel & QTY. 6 BUSHINGS (ES200)
B = 11xM12 SHCS w/ 1x12mm Dowel (E160)
B2 = 10xM12 SHCS w/ 2x12mm Dowels (E160)
C = 6xM12 SHCS w/ 1x12mm Dowel (E160)
D = 11xM10 SHCS w/ 1x10mm Dowel (E125)
D2 = 10xM10 SHCS w/ 2x10mm Dowels (E125)
E = 11xM10 SHCS w/ 1x10mm Dowel and 11x10.5mm ID washers (E160)
E2 = 12xM10 SHCS w/ 2x10mm Dowels and 10x10.5mm ID washers (E160)
F = 6xM10 SHCS w/ 1x10mm Dowel (E125)
G = 6xM10 SHCS w/ 1x10mm Dowel and 6x10.5mm ID washers (E160)
H = 6xM8 SHCS w/ 1x8mm Dowel (E80 & E100)
I = 4xM6 SHCS w/ 1x6mm Dowel (E50 & E63)
J = 4xM5 SLHCS w/ 1x5mm Dowel (E31.5)
R = 6xM10 SHCS w/ 1x10mm Dowel (E125LP)
Z = 15xM16 SHCS w/ 1x12mm Dowel (ES315)

Tool Side

E □ □ - □ - □ - □ - C0000

Assembly Code (Assigned by Factory)

Internal Pneumatic Ports
- " " = Included (if available)
- PP = Not Included (Ports Plugged)

Hardware Kit
- N = No Hardware
- K = 15xM16 SLHCS w/ 2x12mm Dowels (ES200)
- L = 9xM12 SHCS w/ 2x12mm Dowels (E160)
- M = 6xM10 SHCS w/ 2x10mm Dowels (E125)
- O = 6xM8 SHCS w/ 2x8mm Dowels (E100)
- P = 4xM6 SHCS w/ 2x6mm Dowels (E63)
- Q = 4xM5 SLHCS w/ 2x5mm Dowels (E31.5)
- S = 6xM10 SHCS w/ 2x10mm Dowels (E125LP)
- AA = 15xM16 SHCS w/ 2x12mm Dowels (ES315)

Hub Size/Diameter
- 250 = 250mm
- 160 = 160mm
- 100 = 100mm
- 063 = 63mm
- 040 = 40mm
- 022 = 22.5mm
- 000 = No Locating Hub, need 2 Dowels

Bolting Circle
- 315 = 315mm Bolt Circle
- 200 = 200mm Bolt Circle
- 160 = 160mm Bolt Circle
- 125 = 125mm Bolt Circle
- 125LP = Low Profile 125mm Bolt Circle
- 100 = 100mm Bolt Circle
- 63 = 63mm Bolt Circle
- 31.5 = 31.5mm Bolt Circle

Housing Type/Construction
- T = Tool Side (Aluminum)
- TS = Tool Side (Steel)

Product Code
- E = EPSILON

4 TECHNICAL SPECIFICATIONS

Table 4-1. ES200 Technical Specifications

Specification		Metric	English
Payload		1,500 kg	3,300 lb
Maximum Operating Moment (Mx, My)		15,097 Nm	133,620 in-lb
Maximum E-Stop Moment (Mx, My)		17,998 Nm	159,300 in-lb
Maximum Operating Torque (Mz)		11,660 Nm	103,200 in-lb
Maximum E-Stop Torque (Mz)		14,590 Nm	129,130 in-lb
Maximum Tensile Force (F_T)		96,393 N	21,670 lb
Maximum Compressive Force (F_C)		246,031 N	55,310 lb
Width x Length		310 mm x 358 mm	12.20 in x 14.09 in
Height (Robot and Tool Coupled)		120 mm	4.72 in
Mass / Weight *	Robot	19.09 kg	42.00 lb
	Tool	9.44 kg	20.77 lb
Rotational Repeatability		± .01°	
Operating Temperature		5 °C to 60 °C	40 °F to 140 °F
Supply Pressure		5 bar to 7 bar	72 psi to 101 psi
Couple/Uncouple Voltage		22 VDC to 28 VDC	
Noise Emission		≤ 70 dB(A) in any direction	
Transportation and Storage Humidity		Up to 50%, Maximum Temperature 40 °C (104 °F)	
Transportation and Storage Temperature		-20 °C to 40 °C	-4 °F to 104 °F

* Weight may vary depending on specific configuration.

5 INSTALLATION

5.1 ROBOT SIDE INSTALLATION

The ES200 Robot Side is designed to mount directly to interfaces utilizing a 200mm bolt pattern. There are two different ES200 Robot Sides ISO 11 & ISO 12.
The ES200ISO11 can mount to manipulator interfaces M16 hardware (Hardware kit A, 1600-P75A, not ISO) or M12 Hardware (Hardware Kit A2, 2000188X).
The ES200ISO12 can mount to manipulator interface M16 hardware (Hardware kit A3, 2100737X).
For size, locations, and tolerance information on the ES200 Robot Side, see Informational Documents (Section 11).

NOTICE

TOOL CHANGER PAYLOAD & MOMENT RATINGS BASED ON USING A MINIMUM OF 16xM16 SCREWS TO MOUNT THE ROBOT SIDE TO THE MANIPULATOR INTERFACE.

5.1.1 M16 Hardware (NON-ISO PATTERN)

NOTICE

ENSURE THAT THE MATING SURFACES OF THE ROBOT SIDE AND ROBOT FLANGE ARE FLUSH (PLANAR) WHEN FASTENING THE SCREWS.

1. Locate the Robot Side to the manipulator mounting flange utilizing the locating boss and one (1) M12 locating dowel.
2. Insert and tighten the M16 socket head cap screws (minimum Property Class 10.9) provided with the Robot Side Assembly. Torque the screws to the robot manufacturer's specification.

NOTICE

TIGHTEN FACEPLATE MOUNTING SCREWS TO ROBOT MANUFACTURER'S SPECIFICATIONS. IF USING LOCTITE, USE LOCTITE 242 OR EQUIVALENT.

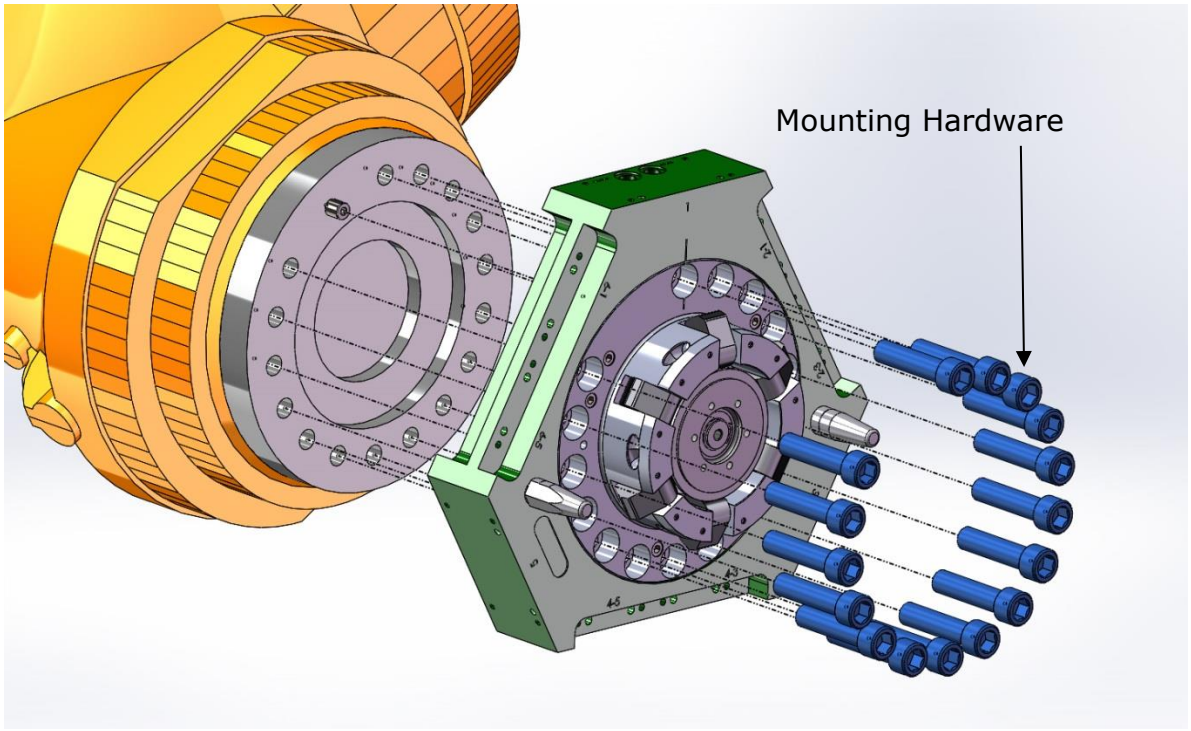


Figure 5.1.1-1. ES200 Robot Side Installation w/ M16 Hardware

⚠ WARNING

DO NOT EXCEED THE MAXIMUM OPERATING OR E-STOP MOMENT OF THE TOOL CHANGER WHEN USING A ROBOT SIDE PLATE TO ADAPT TO OTHER BOLTING PATTERNS.

5.1.2 M12 Hardware (ISO 11 PATTERN)

NOTICE

ENSURE THAT THE MATING SURFACES OF THE ROBOT SIDE AND ROBOT FLANGE ARE FLUSH (PLANAR) WHEN FASTENING THE SCREWS.

1. Locate the Robot Side to the manipulator mounting flange utilizing the locating boss and one (1) M12 locating dowel.
2. Insert and tighten the M12 socket head cap screws (minimum Property Class 10.9) with bushings provided with the Robot Side Assembly. Torque the screws to the robot manufacturer's specification.

NOTICE

TIGHTEN FACEPLATE MOUNTING SCREWS TO ROBOT MANUFACTURER'S SPECIFICATIONS. IF USING LOCTITE, USE LOCTITE 242 OR EQUIVALENT.

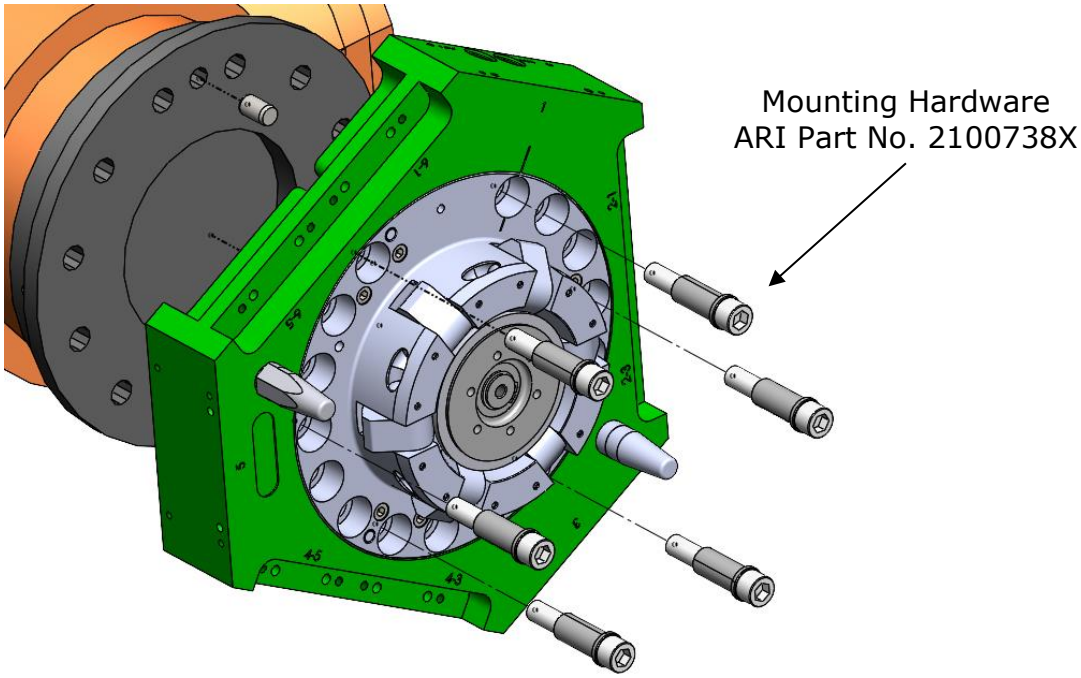


Figure 5.1.2-2 ES200 Robot Side Installation w/ ISO 11 M12 Hardware

⚠ WARNING

DO NOT EXCEED THE MAXIMUM OPERATING OR E-STOP MOMENT OF THE TOOL CHANGER WHEN USING A ROBOT SIDE PLATE TO ADAPT TO OTHER BOLTING PATTERNS.

5.1.3 M16 Hardware (ISO 12 PATTERN)

NOTICE

ENSURE THAT THE MATING SURFACES OF THE ROBOT SIDE AND ROBOT FLANGE ARE FLUSH (PLANAR) WHEN FASTENING THE SCREWS.

1. Locate the Robot Side to the manipulator mounting flange utilizing the locating boss and one (1) M12 locating dowel.
2. Insert and tighten the M16 socket head cap screws (minimum Property Class 10.9) with bushings provided with the Robot Side Assembly. Torque the screws to the robot manufacturer's specification.

NOTICE

TIGHTEN FACEPLATE MOUNTING SCREWS TO ROBOT MANUFACTURER'S SPECIFICATIONS. IF USING LOCTITE, USE LOCTITE 242 OR EQUIVALENT.

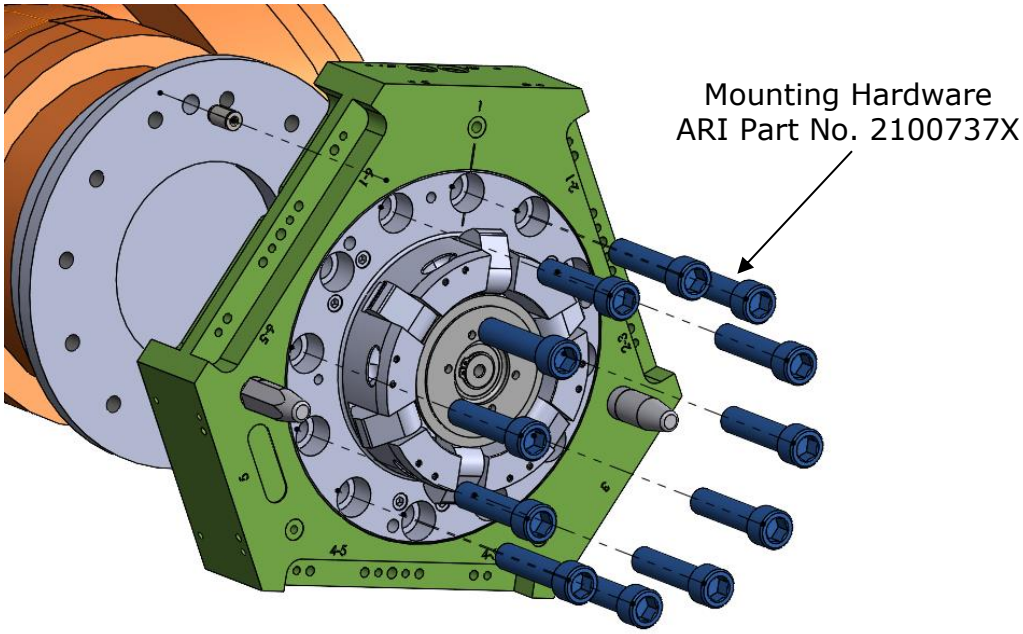


Figure 5.1.3-3 ES200 Robot Side Installation w/ ISO 12 M16 Hardware

⚠ WARNING

DO NOT EXCEED THE MAXIMUM OPERATING OR E-STOP MOMENT OF THE TOOL CHANGER WHEN USING A ROBOT SIDE PLATE TO ADAPT TO OTHER BOLTING PATTERNS.

5.2 TOOL SIDE INSTALLATION

The ES200 Tool Side is designed to mount directly to customer tooling utilizing a 200mm bolt pattern. The ES200 Tool Side can be mounted from the top down using M16 socket low head hardware on the 200mm bolt circle (Hardware Kit K, 1600-P85A). For size, locations, and tolerance information on the ES200 Tool Side mounting patterns, see Informational Documents (Section 11).

NOTICE

TOOL CHANGER PAYLOAD & MOMENT RATINGS BASED ON USING 15xM16 SCREWS TO MOUNT THE TOOL SIDE TO THE TOOLING INTERFACE.

If a locating boss/pilot is used on the tool plate to locate the tool to the Tool Side, then the boss cannot protrude into the tool changer greater than 4mm to allow for clearance of the latching mechanism (Figure 5.2-1).

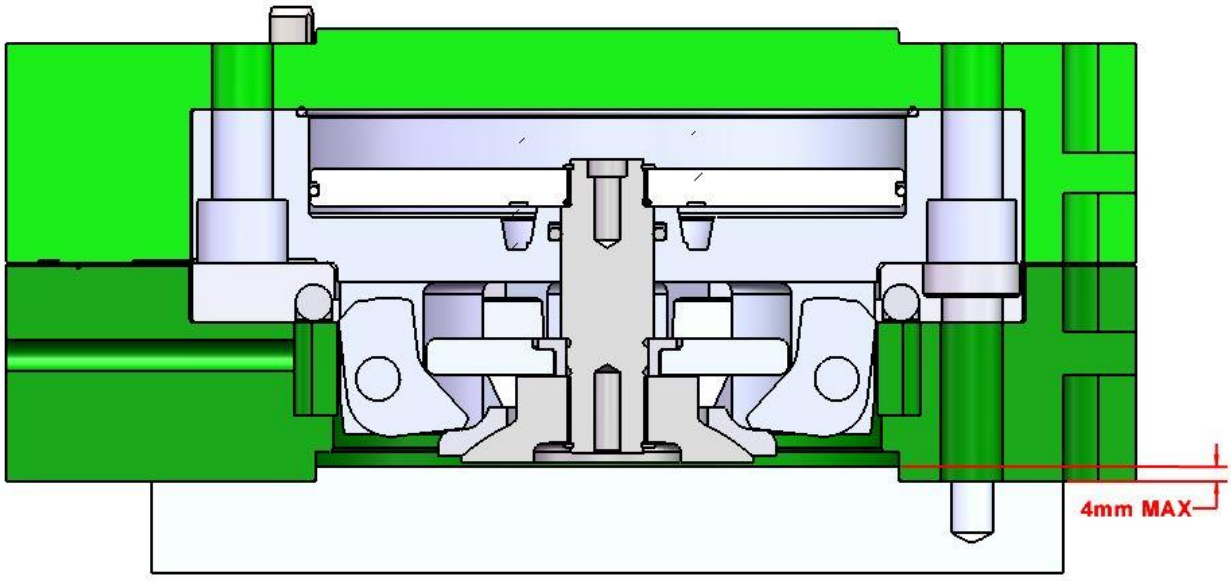


Figure 5.2-1. ES200 Tool Side and Tool Plate Installation

Installing the ES200 Tool Side from the Top Down:

NOTICE

ENSURE THAT THE MATING SURFACES OF THE TOOL SIDE AND TOOL PLATE ARE FLUSH (PLANAR) WHEN FASTENING THE SCREWS.

1. Locate the Tool Side to the tool plate utilizing either the locating hub and one (1) M12 locating dowel, or two (2) M12 locating dowels (Figure 5.2-2).
2. Insert and tighten M16 socket low head cap screws (minimum Property Class 10.9) through the Tool Side 200mm bolt circle. APPLIED ROBOTICS recommends the use of steel threads in the tool plate and appropriate thread engagement and torque values.

NOTICE

TIGHTEN MOUNTING SCREWS TO THE APPROPRIATE SPECIFICATION DEPENDING ON THE END EFFECTOR USED. IF USING LOCTITE, USE LOCTITE 242 OR EQUIVALENT.

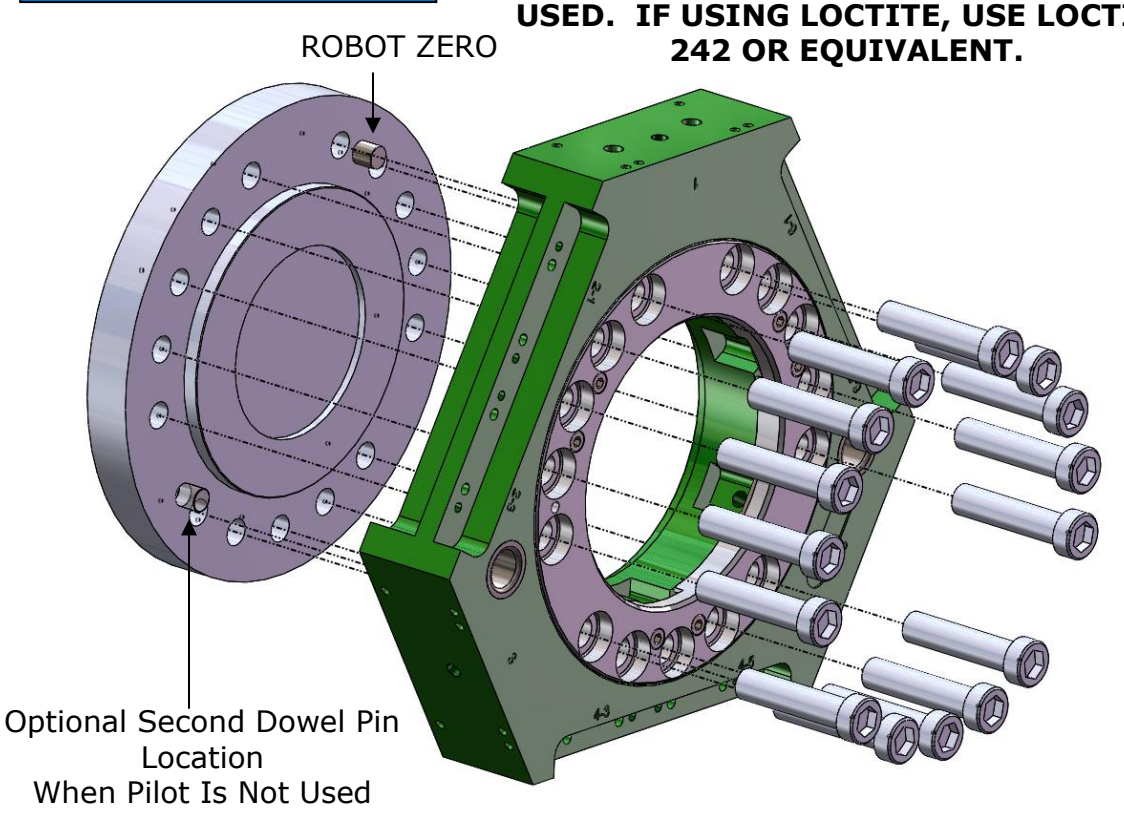


Figure 5.2-2. ES200 Tool Side Installation (Bolt Top Down)

⚠ WARNING

DO NOT EXCEED THE MAXIMUM OPERATING OR E-STOP MOMENT OF THE TOOL CHANGER WHEN USING A ROBOT SIDE PLATE TO ADAPT TO OTHER BOLTING PATTERNS.

5.3 CONNECTING THE AIR SUPPLY

The pneumatic supply for the Epsilon Tool Changer can be supplied via an APPLIED ROBOTICS supplied valve module (S.1-EM-R-V-PB), an APPLIED ROBOTICS supplied Safety Control Module (S-EM-R/T-E-SCM-*), or directly ported via air fittings supplied by the customer (Figure 5.3-1).

⚠ WARNING

PNEUMATIC PRESSURE SHOULD NEVER BE SUPPLIED TO THE EPSILON TOOL CHANGE SYSTEM UNLESS THE POSITION OF THE VALVE SUPPLYING THE AIR IS KNOWN AND HAS BEEN CONFIRMED. FAILURE TO DO SO CAN RESULT IN SERIOUS INJURY OR DEATH FROM A DROPPED TOOL.

⚠ WARNING

THE ROBOT SHOULD NEVER BE RUN WITHOUT AIR PRESSURE BEING SUPPLIED TO THE TOOL CHANGER. PRESSURE TO THE TOOL CHANGER MUST BE AT LEAST 5 BAR (72 PSIG) FOR PROPER OPERATION.

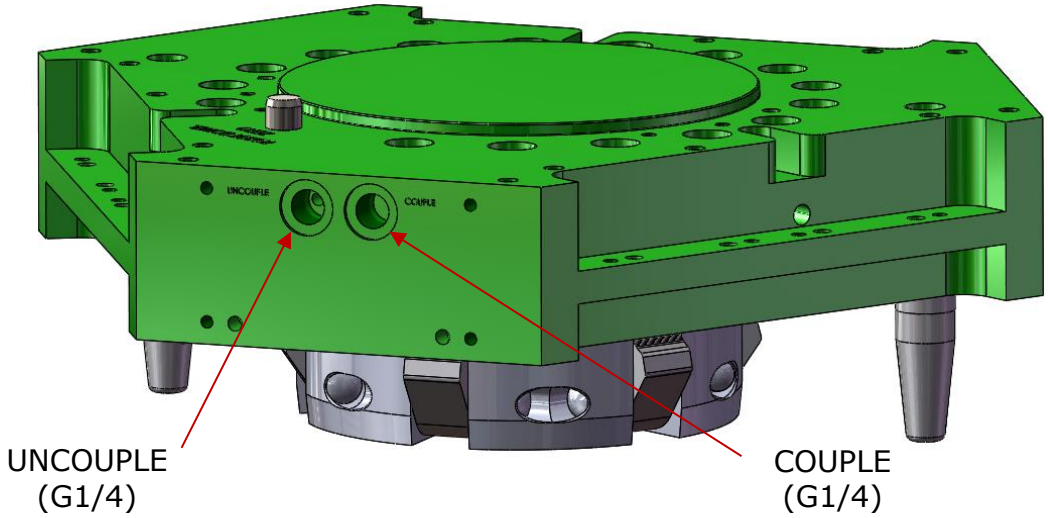


Figure 5.3-1. ES200 Robot Side Air Supply Ports

Both the couple and uncouple actuation port lines must be installed in order for the Epsilon Tool Change System to function properly. To control air to the different ports, a single solenoid, spring-return, 4-way valve or a double solenoid, 4-way valve can be used.

⚠ WARNING

IF A SINGLE SOLENOID, SPRING-RETURN, 4-WAY PNEUMATIC VALVE IS USED, THE FOLLOWING MUST BE UNDERSTOOD AND ADHERED TO:

- IN THE DE-ENERGIZED STATE, THE VALVE MUST PROVIDE AIR TO THE COUPLE PORT ONLY.

⚠ WARNING

IF A DOUBLE SOLENOID, 4-WAY PNEUMATIC VALVE IS USED, THE FOLLOWING MUST BE UNDERSTOOD AND ADHERED TO:

- THE VALVE WILL REMAIN IN ITS PRESENT POSITION UNTIL EITHER THE ALTERNATE SOLENOID IS ENERGIZED OR BY MANUALLY PRESSING THE ALTERNATE SOLENOID OVERRIDE BUTTON (IF APPLICABLE).
- TO CHANGE THE STATE OF THE VALVE, ONE SIDE OF THE SOLENOID MUST BE ENERGIZED AND THE OTHER SIDE DE-ENERGIZED. IF BOTH SIDES ARE ENERGIZED (OR DE-ENERGIZED), THE VALVE WILL NOT CHANGE STATES.
- THE VALVE MUST BE PILOT ACTUATED SO THAT THE POSITION OF THE VALVE WILL NOT CHANGE UNLESS THERE IS AIR SUPPLIED TO THE VALVE.

5.4 COUPLE AND UNCOUPLE SIGNALS

Couple and uncouple signals are provided via an electrical interface at Position 3 of the ES200 Robot Side (Figure 5.4-1 or Figure 5.4-2). APPLIED ROBOTICS utilizes unidirectional differential pressure switches to provide indication of piston limit positions (couple and uncouple). Switches are preset at the factory and do not require any adjustment for the lifetime of the tool changer.

⚠ CAUTION

COUPLE AND UNCOUPLE SENSOR SIGNALS SHOULD BE CONTINUALLY MONITORED TO VERIFY THAT THE TOOL CHANGER IS IN THE PROPER STATE BEFORE COMMANDING THE ROBOT TO MOVE.

Should the switches need to be replaced, see Section 10.1.2.

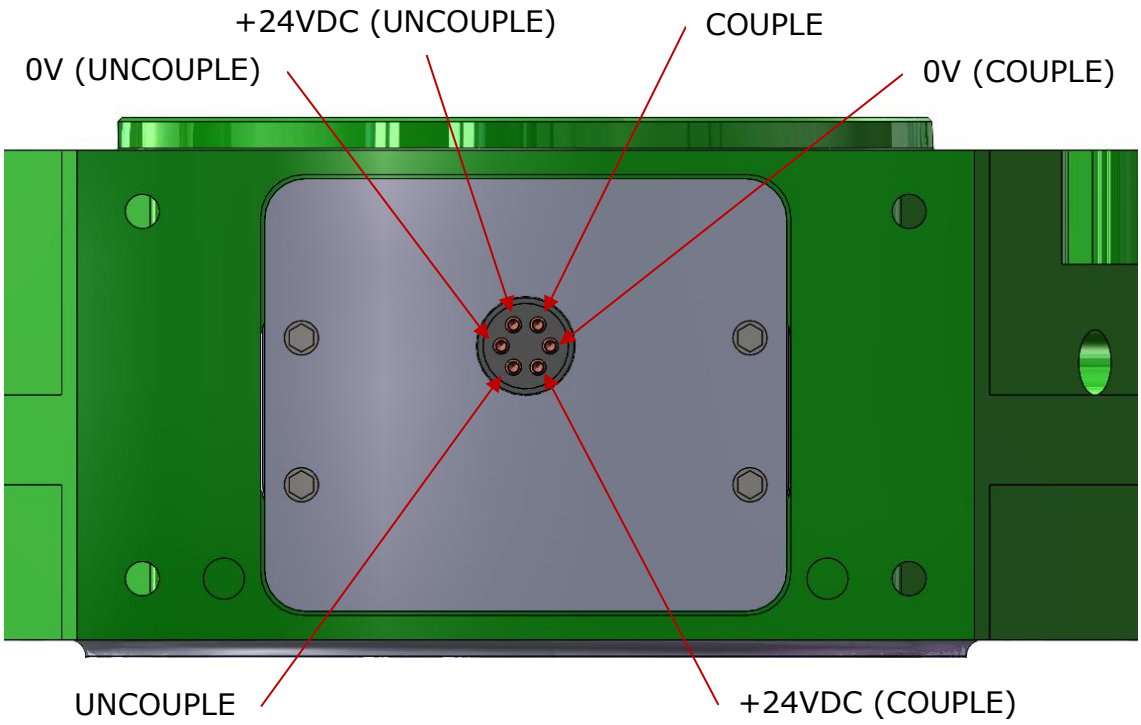


Figure 5.4-1. Couple/Uncouple Signal Interface

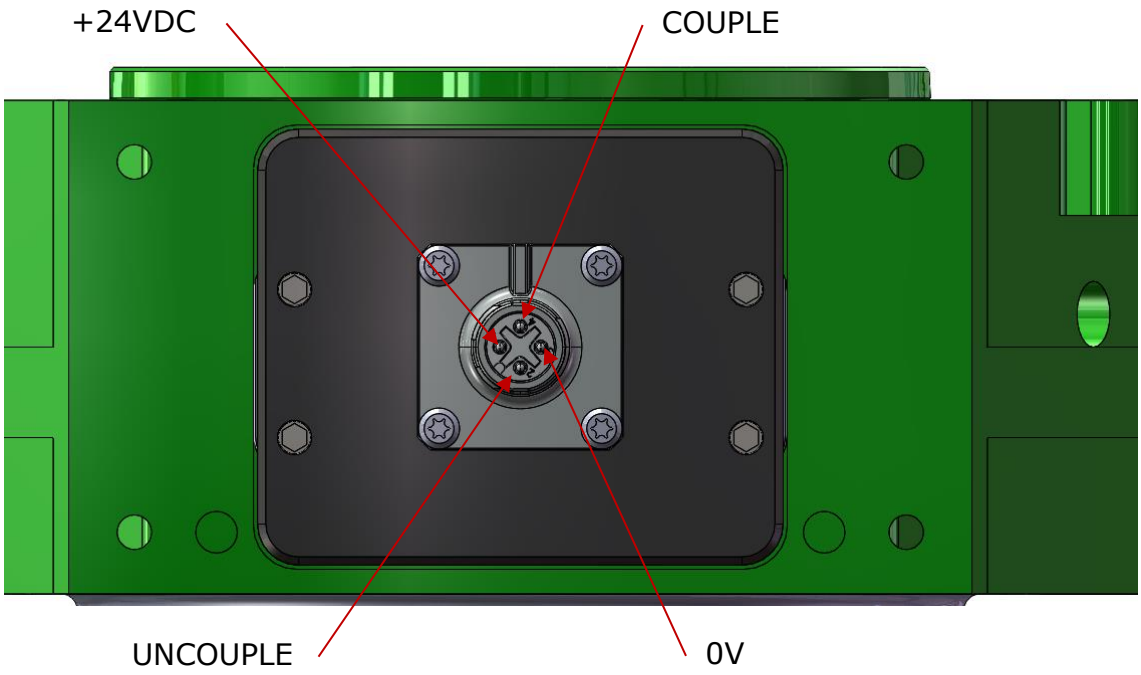


Figure 5.4-2. Couple/Uncouple M12 Signal Interface

NOTICE

COUPLE AND UNCOUPLE SENSORS REQUIRE A MINIMUM AIR PRESSURE OF 5 BAR (72 PSIG) TO FUNCTION. ANY LOSS OF AIR SUPPLY WILL RESULT IN THE LOSS OF THE COUPLE AND UNCOUPLE SIGNALS. WITH THIS FEATURE, THE COUPLE AND UNCOUPLE SIGNALS CAN BE USED FOR INDICATION OF AIR SUPPLY TO THE TOOL CHANGER.

NOTICE

MAKING CONNECTIONS WHILE UNDER POWER COULD RESULT IN DAMAGE TO THE EQUIPMENT. TO AVOID DAMAGING EQUIPMENT, ENSURE THAT ALL CABLES ARE CONNECTED BEFORE SUPPLYING POWER TO THE EQUIPMENT.

5.5 TOOL PRESENT SIGNAL (OPTIONAL)

The ES200 Tool Changer contains built-in features for Tool Present detection via proximity sensors (Figure 5.5-1). This option allows for up to three (3) Tool Present sensors to be installed and the signals to be monitored either individually or in series providing a single output signal to ensure parallelism between the Robot Side and Tool Side during docking.

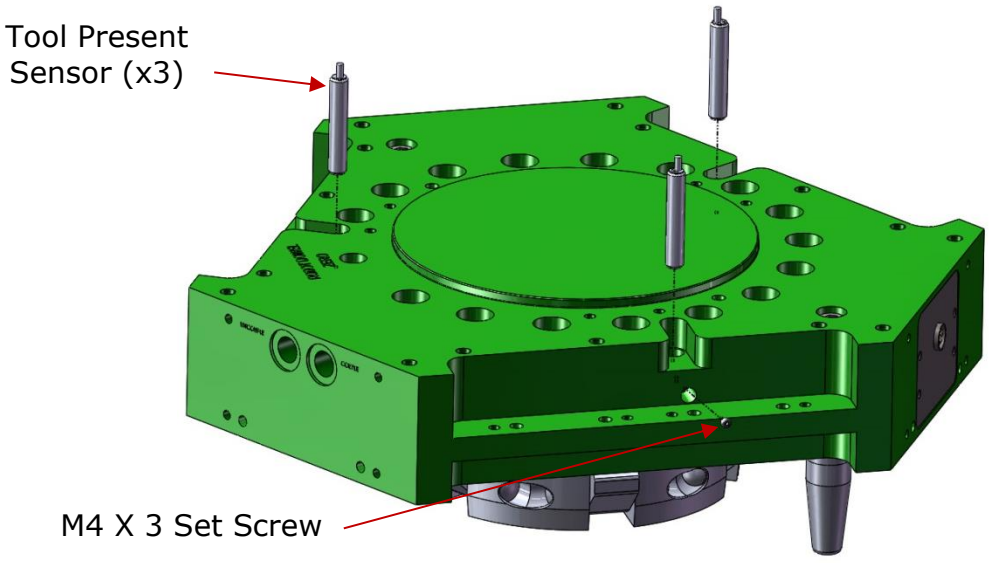


Figure 5.5-1. Tool Present Option

When the Tool Present sensors are installed, ensure that the tip of the sensor (highlighted blue) is installed flush with the Robot Side interface (Figure 5.5-2) and the sensor is secured using a M4 set screw.

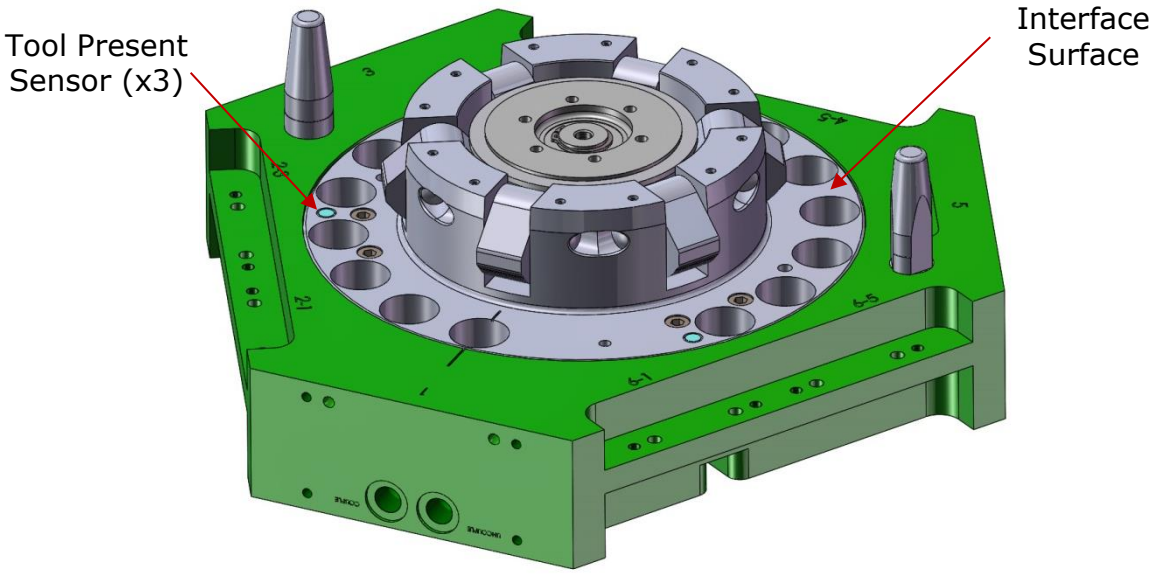


Figure 5.5-2. Tool Present Sensor Installation

5.6 GROUNDING CONNECTION

The ES200 Tool Changer has three (3) masked holes on opposite sides to attach an M8 lug as a grounding line (Figure 5.6-1 and Figure 5.6-2).

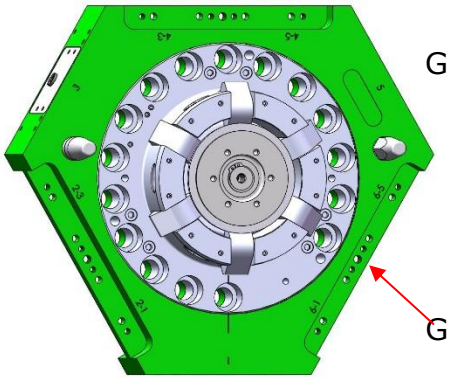


Figure 5.6-1 ERS200 Masked Grounding Holes

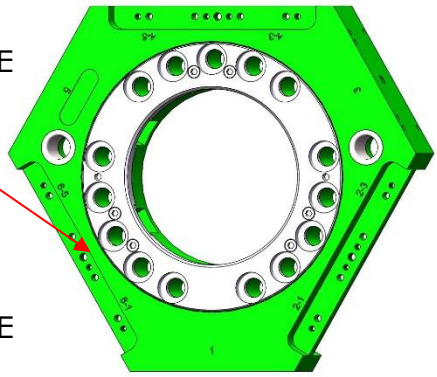


Figure 5.6-2 ETS200 Masked Grounding Holes

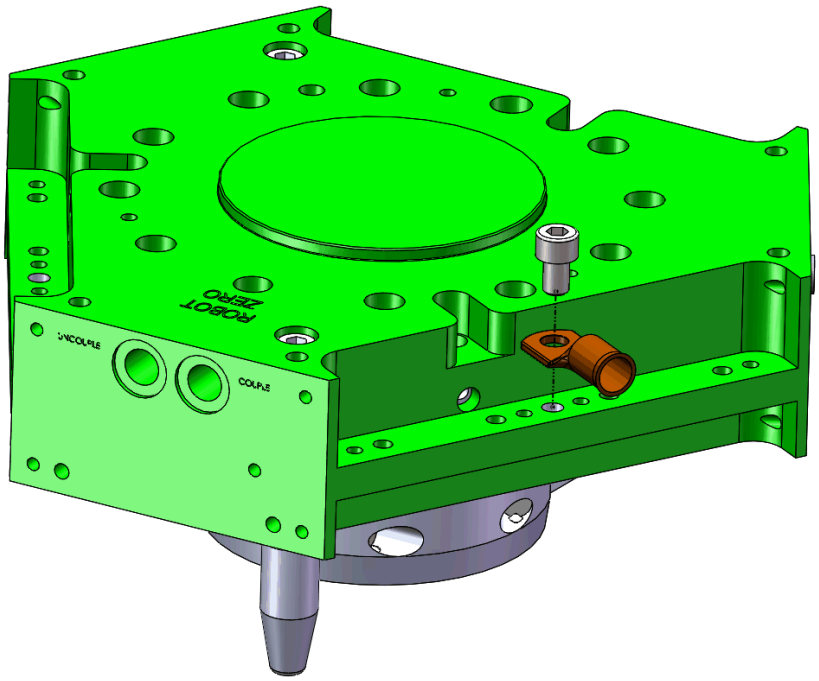


Figure 5.6-3. M8 Lug Mounting

6 GUIDE TO OPERATION

6.1 INITIAL TEST

Once the air supply has been plumbed to the couple and uncouple ports, control power is connected to the air supply valve, and the couple and uncouple position sensors are in communication with the robot controller/PLC and/or APPLIED ROBOTICS' Safety Control Module, perform the following steps to verify the proper operation of the Epsilon Tool Changer.

⚠ CAUTION

DURING TESTING, KEEP YOUR FINGERS CLEAR OF THE MECHANICAL COUPLING MECHANISM AND THE COUPLING INTERFACE SURFACES. KEEP OUT OF THE ROBOT WORK ENVELOPE WHEN DRIVE POWER IS ON.

1. Verify that the Robot Side is clear of any obstruction and not coupled to the Tool Side.
2. Turn on supply air to the control valve and verify that the cams move to the extended position (Figure 6.1-1). If using a single solenoid, spring return, 4-way valve, this will verify that it is plumbed correctly.
3. Supply control power to the solenoid valve and supply the signal from the controller/PLC to move the valve to the uncoupled (solenoid energized) position. The cams should retract to the uncoupled position (Figure 6.1-2) and the input from the uncoupled sensor should be received by the robot controller/PLC.
4. Change the state of the solenoid valve by turning off the uncouple signal (solenoid de-energized). The cams should extend back to the couple position and the uncouple sensor signal should turn OFF (LOW) and the couple sensor signal should turn ON (HIGH) at the robot controller/PLC.
5. Repeat Steps 3 and 4 several times. The cam action should be smooth and quick.

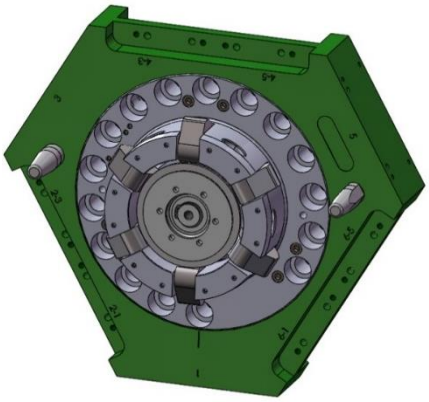


Figure 6.1-1. Robot Side Coupled (Cams Extended)

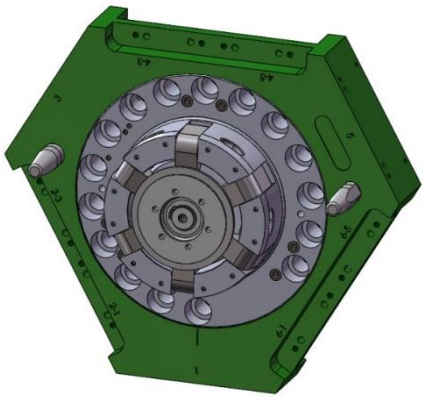


Figure 6.1-2. Robot Side Uncoupled (Cams Retracted)

6.2 PROGRAMMING THE COUPLE AND UNCOUPLE POINTS

⚠ WARNING

THE ROBOT SHOULD NEVER BE RUN WITHOUT A MINIMUM AIR PRESSURE OF 5 BAR (72 PSIG) BEING SUPPLIED TO THE ROBOT SIDE.

It is best to utilize APPLIED ROBOTICS Teaching Aid (1800903A) for simple and accurate alignment programming of the Robot Side and Tool Side. For complete instructions on the installation and use of the Teaching Aid, refer to APPLIED ROBOTICS manual 95650 or contact APPLIED ROBOTICS Applications Engineering. When programming the "dock" and "undock" points of each tooling, the following steps should be taken:

1. Orient the Robot Side and Tool Side so that the centerline axes are aligned, and the interface surfaces are parallel. Maintain approximately 55mm minimum separation between the Robot Side and Tool Side interface surfaces (Figure 6.2-1). Note that the interface surfaces lie inboard of the outer perimeter of the Robot and Tool Side.

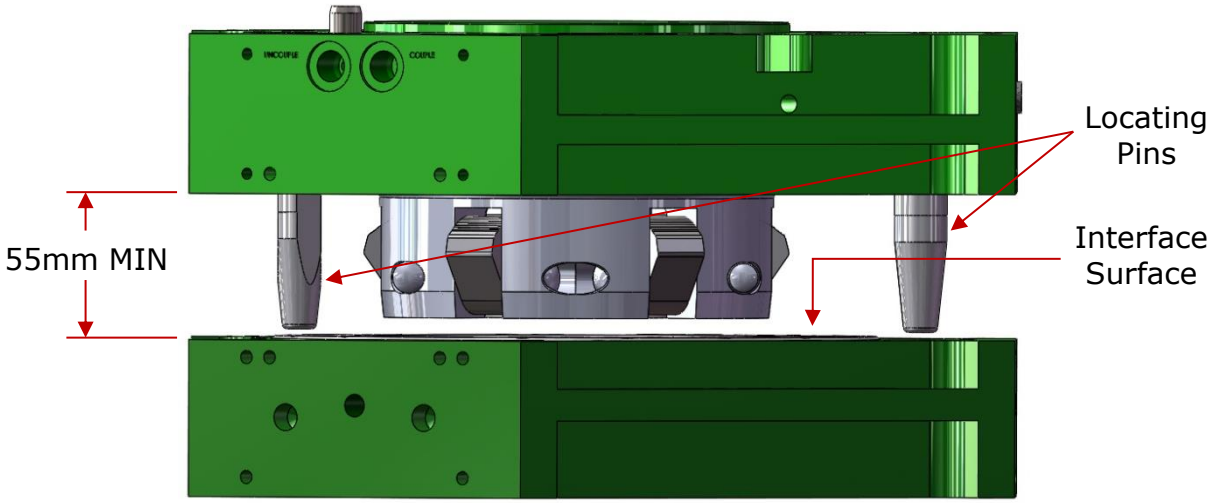


Figure 6.2-1. ES200 Tool Changer – Docking Orientation

2. Energize the solenoid, resulting in an uncoupled (cams retracted) state.
3. Rotate the Robot Side so that the locating pins are centered on the bushings in the Tool Side.
4. Start to bring the Robot and Tool Sides together while visually checking the alignment of the locating pins and bushings. Make lateral adjustments as necessary to center the locating pins to the bushings. Exact alignment is not required; however, limit the amount of interference between the locating pins and bushings while docking. Interference between the locating pins and bushings while docking increases wear and decreases the life of the locating pins.
5. Stop the motion when the distance between the Robot Side interface surface and Tool Side interface surface are touching or as close as can

reasonably be achieved. At this time, any electrical or fluid connections will be made through the use of available side modules. Note that when the interface surfaces of the Robot Side and Tool Side are in contact, there is a small gap along the outer edge of the Sides (Figure 6.2-2)

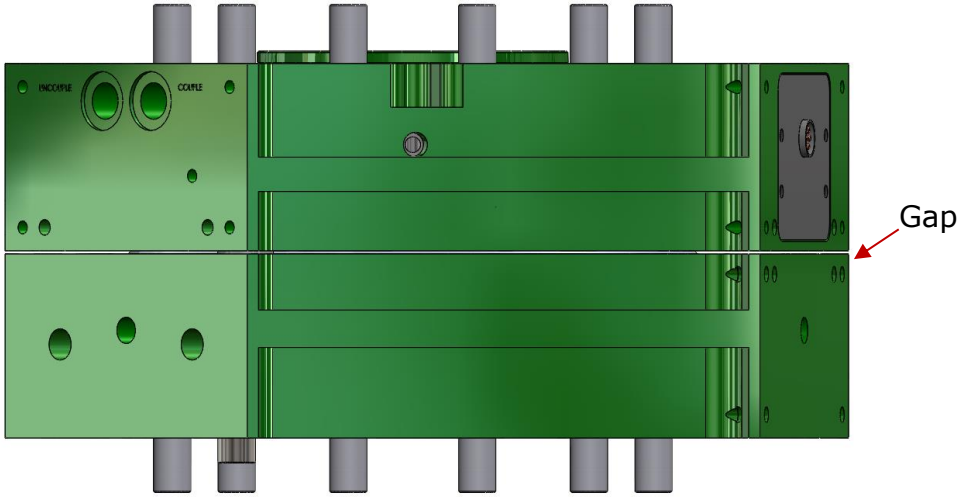


Figure 6.2-2. ES200 Tool Changer – Docked Position

NOTICE

MINIMIZING THE DISTANCE BETWEEN THE ROBOT SIDE AND TOOL SIDE INTERFACE SURFACES WHEN PROGRAMMING THE DOCK AND UNDOCK POINTS WILL ENSURE OPTIMUM PERFORMANCE OF THE TOOL CHANGER OVER ITS OPERATIONAL LIFE SPAN.

SEPARATION BETWEEN THE ROBOT SIDE AND TOOL SIDE INTERFACE SURFACES, GREATER THAN 1mm DURING DOCKING OR UNDOCKING WILL RESULT IN ADDITIONAL WEAR TO THE TOOL CHANGER AND REDUCE THE OVERALL LIFE EXPECTANCY.

6. De-energize the solenoid that controls the air pressure to the couple port. This will couple the Robot Side with the Tool Side.
7. Cycle the cams by energizing and de-energizing the solenoid several times to verify that the Tool Side is properly connected and released from the Robot Side. If properly programmed, the Robot Side and Tool Side should not move when the cams are coupled (extended) and uncoupled (retracted).
8. Record the position from Step 5 as the "dock" and "undock" coordinates for the Tool Side. Depending on the docking station used, separate dock and undock positions may be required.
9. Repeat procedure for each Tool Side used in conjunction with the corresponding Robot Side.

6.3 TOOL DROP PREVENTION

Preventing accidental uncoupling of the Tool Changer is of utmost importance when setting up your Epsilon Tool Changer for operation. Various system options are available to ensure that the Tool Changer cams can only be moved into the Uncouple position when it is safe to do so (i.e., when the Tool Side is not coupled to the Robot Side OR when the tool is safely positioned in a docking station).

Unintentional tool drops can be prevented by using a programmable safety controller, APPLIED ROBOTICS Tool Stand Monitoring (TSM) circuit, or APPLIED ROBOTICS Safety Control Module (S-EM-R/T-E-SCM-*) that mounts to the Robot and Tool Sides. For further information, consult the manual for your particular system or contact APPLIED ROBOTICS Applications Engineering.

6.3.1 Mechanical Lock Design Feature

The ES200 Tool Changer is equipped with a redundant mechanical locking feature (Figure 6.3.1-1) that prevents the cams from retracting when supply air pressure is lost. The mechanical locking feature is a machined surface cut into the profile of the cam and when air pressure is lost, the Tool Side will separate from the Robot Side slightly (~0.75mm) until the pickup dowel on the Tool Side locks into this feature (Figure 6.3.1-2). When the pickup dowel is locked into this feature, the Tool Changer is unable to separate. The spring in the ES200 Robot Side piston chamber returns the cams to the extended position (coupled) when air supply to the Tool Changer is lost, engaging the locking feature.

The ES200 cam also contains a unique wear compensating profile with a progressive design, allowing for the mechanism to remain effective for the life of the Tool Changer.

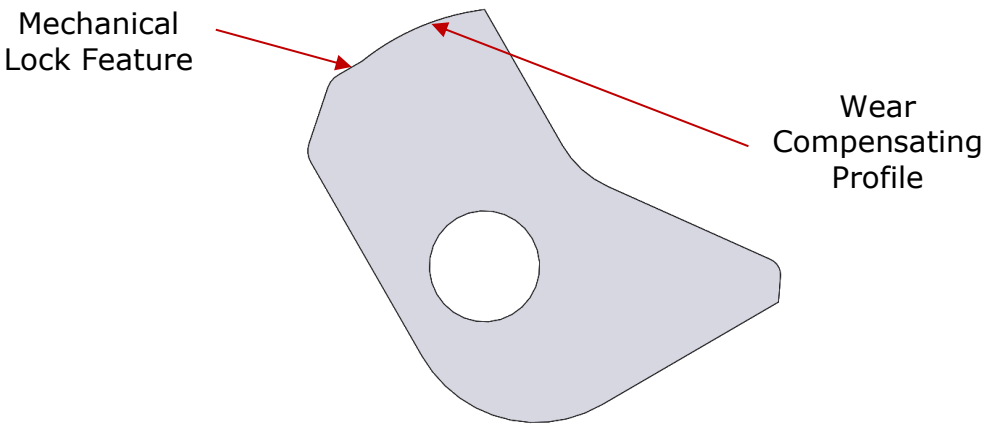


Figure 6.3.1-1. ES200 Cam Mechanical Lock Feature

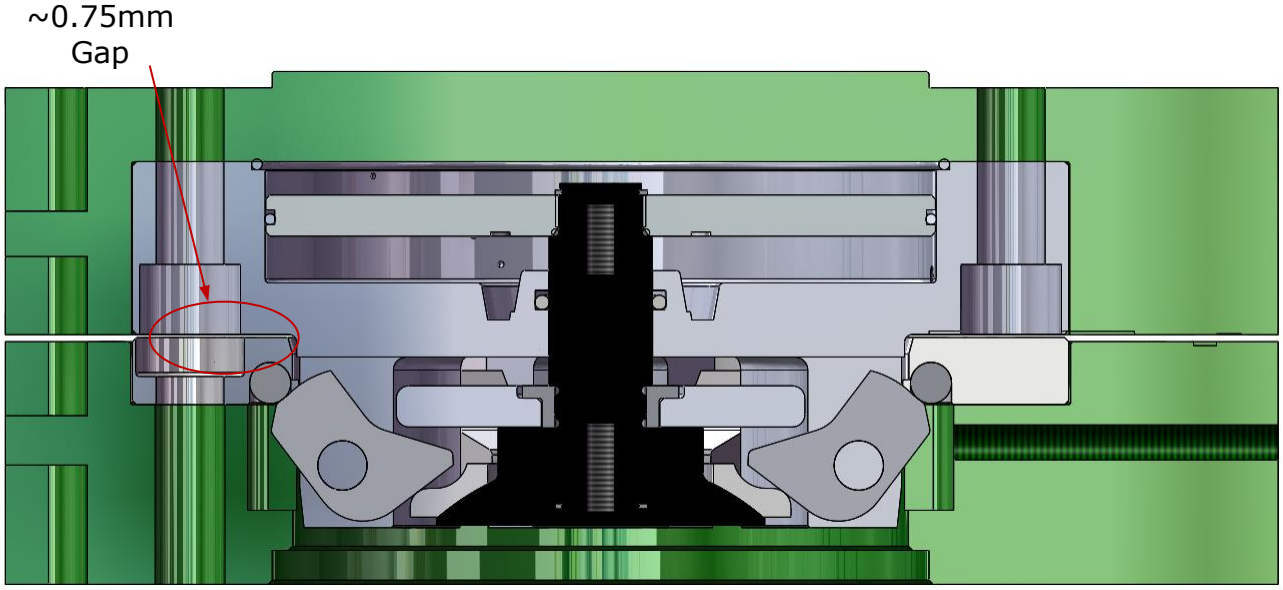


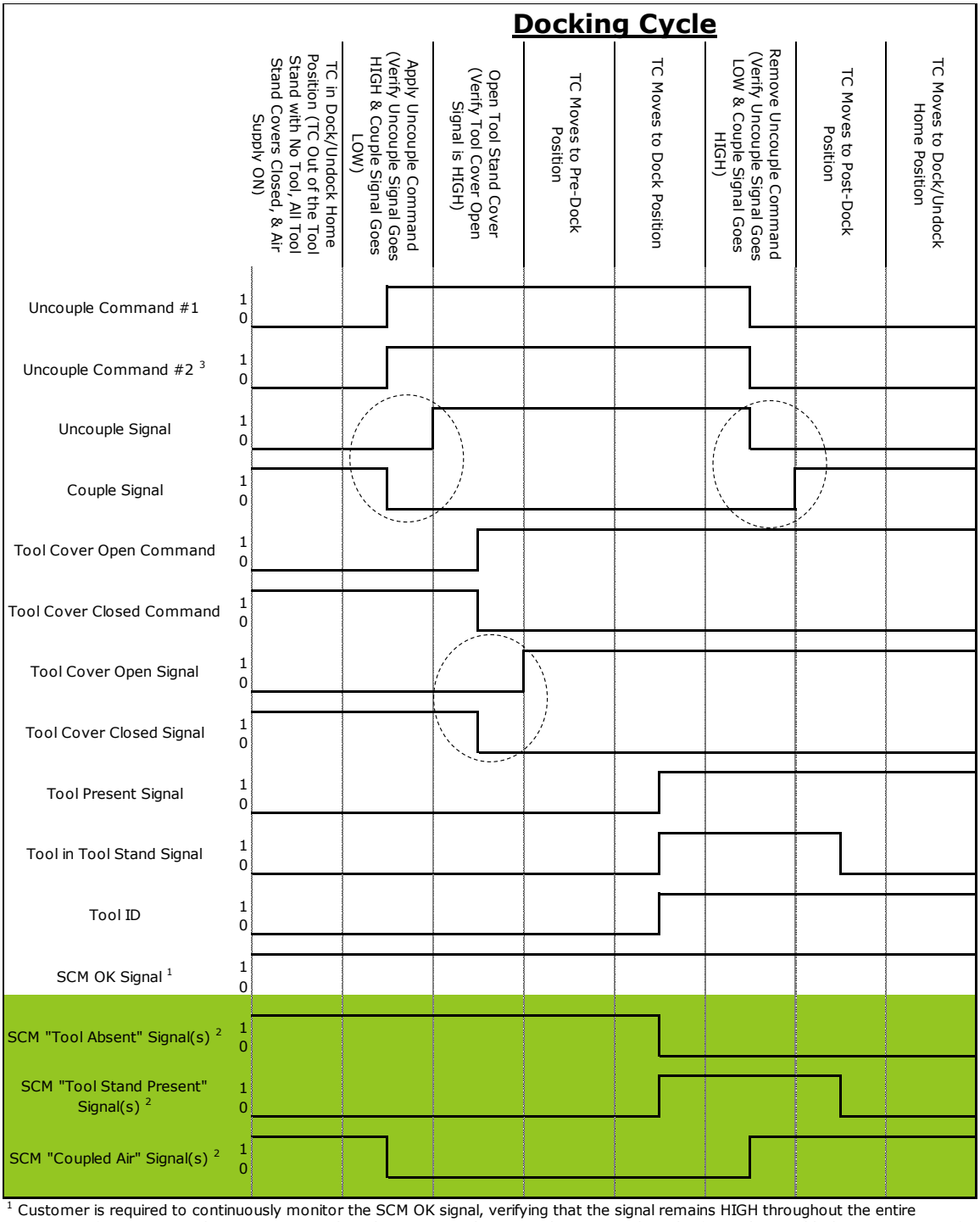
Figure 6.3.1-2. ES200 Robot & Tool Side – Loss of Air Mechanical Lock

6.4 RECOMMENDED SEQUENCE OF OPERATION

NOTICE

THE EPSILON TOOL CHANGER SYSTEM SHOULD NEVER BE UNCOUPLED UNLESS THE ATTACHED TOOL IS FULLY SUPPORTED IN A DOCKING STATION/TOOL STAND.

The following is a standard sequence of operation for a Robot, Tool Changer, and Tool combination. See Figure 6.4-1 and Figure 6.4-2 for a graphical representation of this sequence. Two (2) Uncouple Commands are required if using APPLIED ROBOTICS' Safety Control Module.



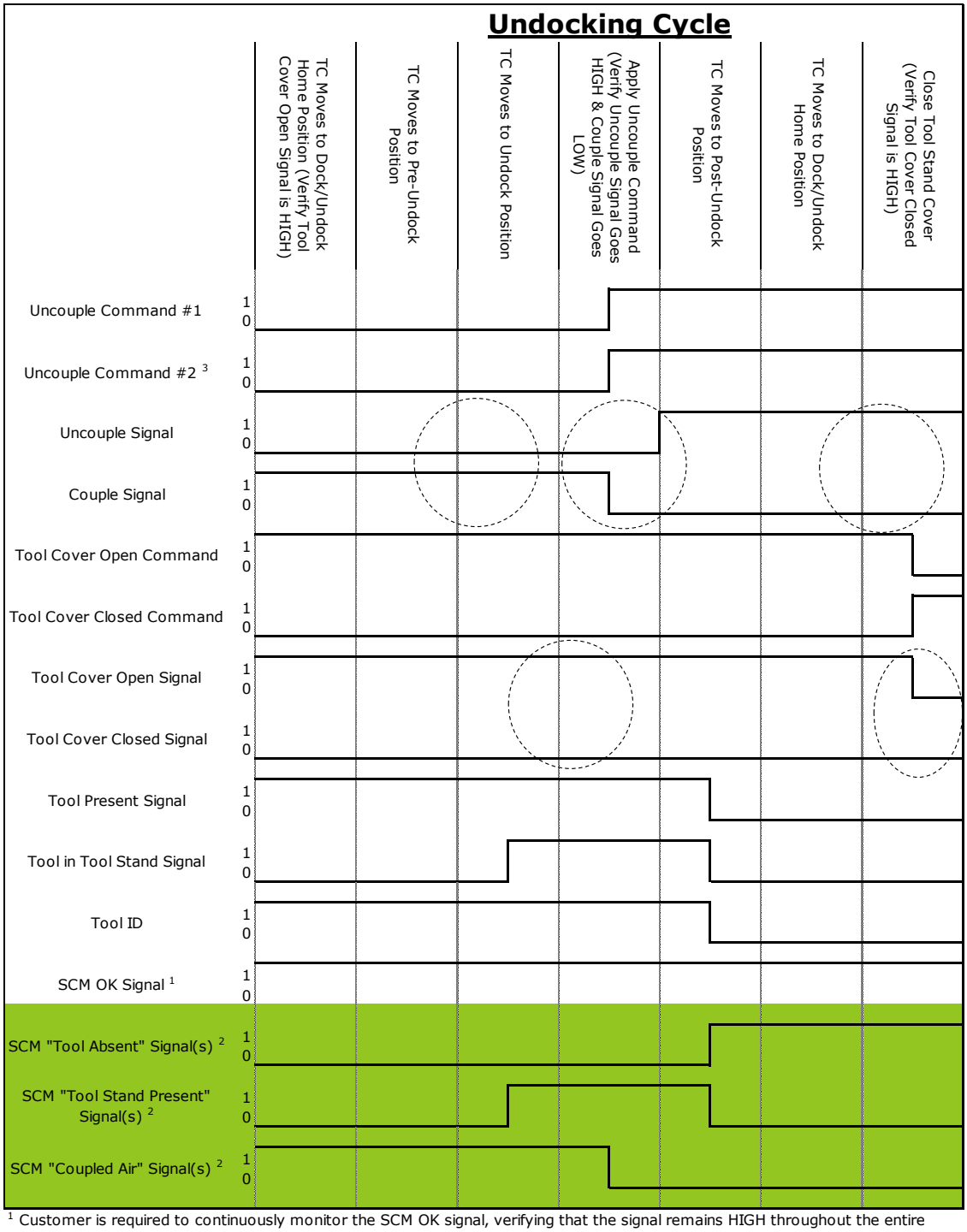
[1] Customer is required to continuously monitor the SCM OK signal, verifying that the signal remains HIGH throughout the entire operation. If SCM OK signal goes LOW, stop the robot, remove the Uncouple Commands and refer to the Troubleshooting section of the SCM User Guide.

[2] Signals (dual channel) are only available via LED's on ARI's Safety Control Module (SCM). Not available for monitoring by the robot controller.

[3] Second Uncouple Command is required when using ARI's Safety Control Module (SCM) and should be applied simultaneously with the first Uncouple Command.

- Verify the status of all signals before proceeding to the next step.
- Input/Output HIGH = 1, LOW = 0
- Dotted circles indicate a intermediate state of an actuating cyclinder when neither "Open" or "Close" signal is present.

Figure 6.4-1. Sequence of Operations Diagram – Docking Cycle



[1] Customer is required to continuously monitor the SCM OK signal, verifying that the signal remains HIGH throughout the entire operation. If SCM OK signal goes LOW, stop the robot, remove the Uncouple Commands and refer to the Troubleshooting section of the SCM User Guide.

[2] Signals (dual channel) are only available via LED's on ARI's Safety Control Module (SCM). Not available for monitoring by the robot controller.

[3] Second Uncouple Command is required when using ARI's Safety Control Module (SCM) and should be applied simultaneously with the first Uncouple Command.

- Verify the status of all signals before proceeding to the next step.
- Input/Output HIGH = 1, LOW = 0
- Dotted circles indicate a intermediate state of an actuating cyclinder when neither "Open" or "Close" signal is present.

Figure 6.4-2. Sequence of Operations Diagram – Undocking Cycle

7 TROUBLESHOOTING

7.1 TROUBLESHOOTING GUIDE

Table 7.1-1. Troubleshooting Guide

Symptom	Possible Cause	Resolution
Tool Changer Will Not Couple	Tool Changer not within required distance for coupling (<1mm)	Adjust Robot program to move within the required distance (<1mm)
	Electrical connection to the actuation valve has been lost (only if using double-acting solenoid)	Verify all connections are in place and that valve is not damaged and operating correctly
Tool Changer Will Not Uncouple	Air supply to the Tool Changer has been lost	Verify all air connections are in place and air is being supplied to the Robot cell
	Electrical connection to the actuation valve has been lost	Verify all connections are in place and that valve is not damaged and operating correctly
	Tool is not in Tool Stand	Verify the tool is supported in the tool stand and that the Tool Stand Present signal is activated
	Spring Failure	Replace sender spring
Tool Changer Couples, But No Coupled Signal is Being Received	Coupled sensing has failed	Replace sensor puck (See Section 10.1.2)
	Cable/Connections supplying signal failed	Inspect cables/connections and replace if necessary
	Air supply to the Tool Changer has been lost (Coupled via the sender spring)	Verify all air connections are in place and air is being supplied to the Robot cell
	Piston actuates, but does not reach the end/Coupled position	Verify that the distance between the mating interfaces of the Robot and Tool Side are <1mm and that the surfaces are parallel.
Tool Changer Uncouples, But No Uncoupled Signal is Being Received	Uncoupled sensing has failed	Replace sensor puck (See Section 10.1.2)
	Cable/Connections supplying signal failed	Inspect cables/connections and replace if necessary

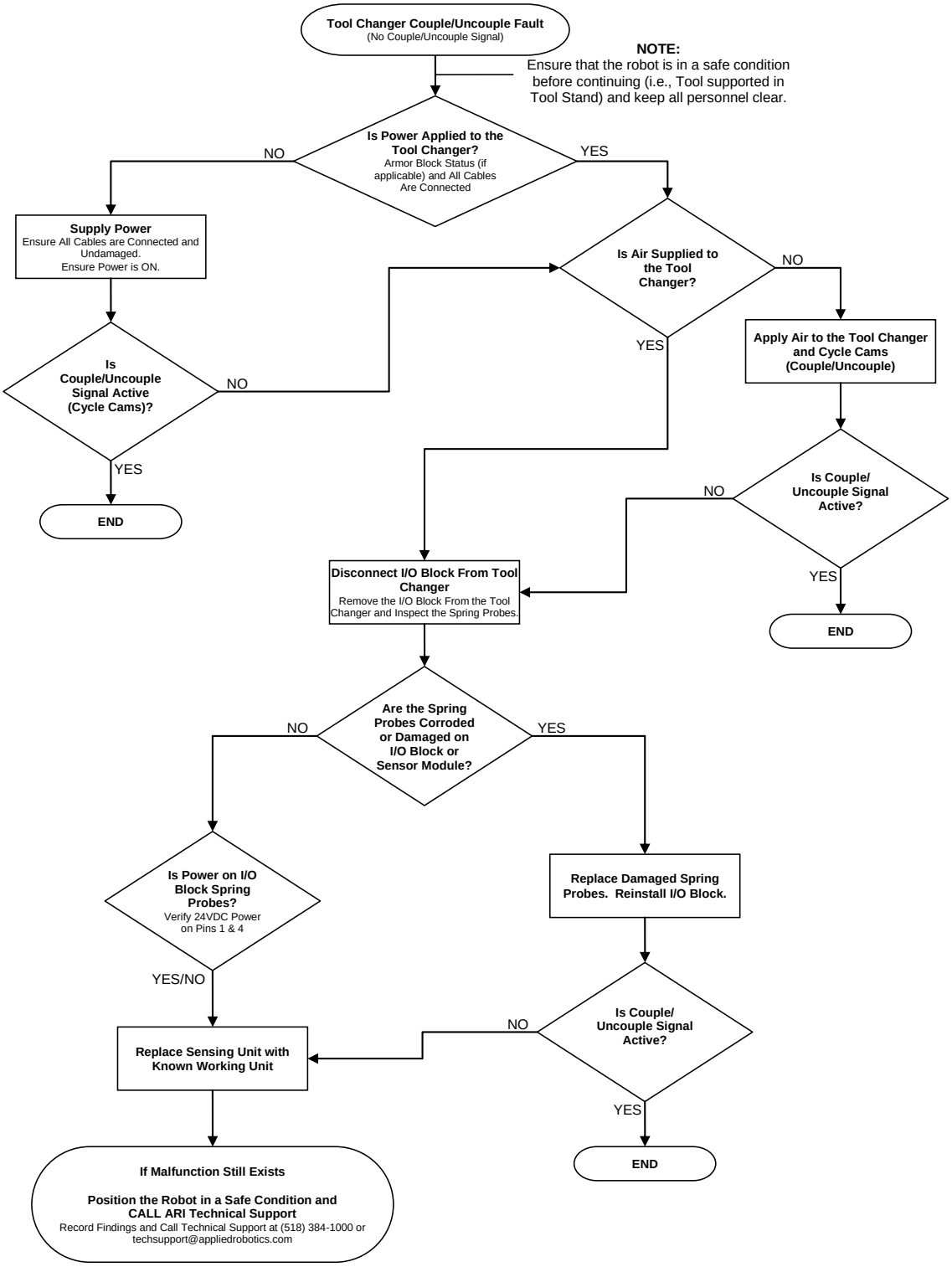
7.2 TECHNICAL SUPPORT

If you require assistance, contact APPLIED ROBOTICS Technical Support Department at:

Phone: +1 518 384 1000
E-mail: techsupport@appliedrobotics.com

7.3 TROUBLESHOOTING FAULT TREE

The fault tree provides guidance for troubleshooting a Tool Changer Couple/Uncouple fault.



7.4 MANUAL UNCOUPLE

A feature has been designed in the ES200 Tool Changer that allows the system to be manually uncoupled, if damage occurs that prevents the system from uncoupling under normal means.

⚠ WARNING

ENSURE THAT THE ATTACHED TOOLING IS SAFELY SUPPORTED, PREFERABLY IN ITS TOOL STAND.

The following steps must be followed to ensure that the ES200 Tool Changer is manually uncoupled in a safe manner:

1. Ensure that the attached tooling is safely supported, preferably in its tool stand, so that no damage or personal injury occurs when the tool is released.
2. Ensure that all unnecessary personnel are clear of the tooling before going further in this procedure.
3. Shut off the air supply to the actuating cylinder. The cylinder must not be pressurized for this operation to be performed successfully.
4. Insert an 8mm OD x 60mm long shaft followed by a M10x40mm long socket head cap screw in the hole located in the middle of side 1 of the Tool Side Housing as shown in Figure 7.4-1. This requires any tool side module on Position 1 to be removed.
5. Drive the M10 screws in until the cams are fully retracted. This action will allow the tool changer to uncouple.

NOTICE

WHEN AIR SUPPLY IS OFF, THE COUPLE/UNCOUPLE SIGNALS WILL BE LOST DUE TO THE LACK OF AIR. ONLY MOVE THE ROBOT AFTER THE CAMS HAVE BEEN FULLY RETRACTED.

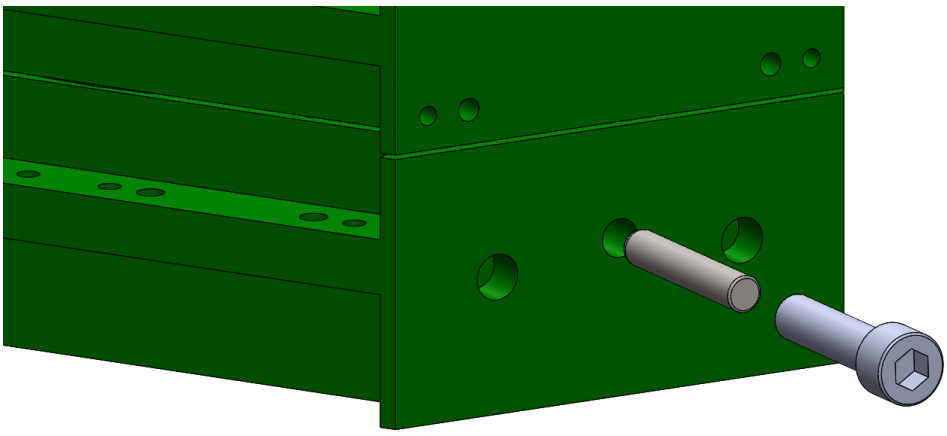


Figure 7.4-1. Manual Uncouple Feature

8 MAINTENANCE

NOTICE

FAILURE TO FOLLOW THE MAINTENANCE SCHEDULE DESCRIBED IN THIS SECTION COULD ALTER OR VOID THE WARRANTY PROVIDED BY APPLIED ROBOTICS, INC.

The following table provides a schedule for preventive maintenance to be performed for the Epsilon Tool Changer.

Table 8-1. Preventive Maintenance Schedule

	Frequency of Maintenance				
	Every 1 Month	250,000 Cycles	500,000 Cycles	750,000 Cycles	1,000,000 Cycles
Robot Side	Visual Checks (Section 8.1.2.1)	Visual Checks (Section 8.1.2.1)			Visual Checks (Section 8.1.2.1) & Replace Locating Pins if Worn or Damaged & Inspect Piston Spring Functionality and Replace if Necessary[1]
Tool Side	Visual Checks (Section 8.1.2.2)	Lubrication (Section 8.1.1.1) & Visual Checks (Section 8.1.2.2)			Lubrication (Section 8.1.1.1) & Visual Checks (Section 8.1.2.2) & Replace Locating Bushings if Worn or Damaged

	Frequency of Maintenance				
	Every 1 Month	1,250,000 Cycles	1,500,000 Cycles	1,750,000 Cycles	2,000,000 Cycles[2]
Robot Side	Visual Checks (Section 8.1.2.1)	Visual Checks (Section 8.1.2.1)			Visual Checks (Section 8.1.2.1) Replace Locating Pins if Worn or Damaged & Inspect Piston Spring Functionality and Replace if necessary & Inspect Dock and Undock Positions to Ensure Proper Alignment with Each Tool Side (Utilize APPLIED ROBOTICS Teaching Aid, See Manual 95650)
Tool Side	Visual Checks (Section 8.1.2.2)	Lubrication (Section 8.1.1.1) & Visual Checks (Section 8.1.2.2)			Lubrication (Section 8.1.1.1) & Visual Checks (Section 8.1.2.2) & Replace Locating Bushings if Worn or Damaged

[1] To test Piston Spring functionality, retract the cams (Figure 6.1-2) using air pressure, then completely vent off all air and ensure that the cams return to the extended position (Figure 6.1-1).
[2] Continue Lubrication and Visual Checks every 250,000 Cycles. Continue inspecting for wear or damaged components every 500,000 cycles.

8.1 PREVENTIVE MAINTENANCE

8.1.1 Lubrication

Proper lubrication of wear components is essential to maintaining the performance and prolonging the operational life of the ES200 Tool Changer. Failure to apply proper lubrication could result in increased wear and shorten the life expectancy of the Tool Changer. The following lubricants are approved for use on the ES200 Tool Changer.

Table 8.1.1-1. Approved Lubricants

Lubricant	ARI Part #	Manufacturer	Manufacturer's Part #
Lube-A-Cyl	51120	Parker	0766130000
White Lithium Grease	91504-P1037	Century Lubricants	ST-80
Staburags NBU 30 Grease	0903-P11N	Klüber	NBU 30
White EP Bearing Grease	96503-P1018	Dow Corning	White EP Bearing Grease

8.1.1.1 Tool Side

1. Clean the inner surface of the tool ring, the locating/alignment bushings, and the latching surfaces to ensure all existing grease, dirt, and debris is removed.
2. Apply a liberal coating of white lithium grease to the latching surfaces and to the inner surface of the locating/alignment bushings, as shown in Figure 8.1.1.1-1 with the surfaces highlighted blue.

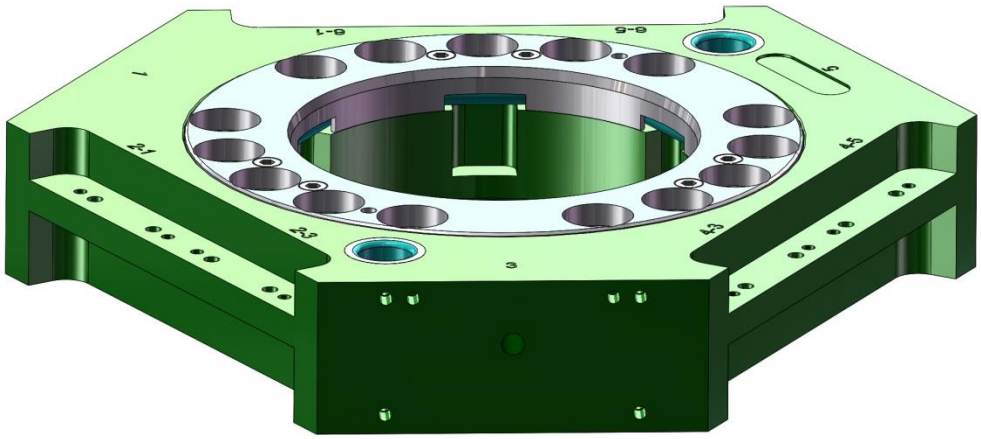


Figure 8.1.1.1-1. ES200 Tool Side Lubrication

8.1.2 Visual Checks

Periodic visual checks of the ES200 Tool Changer will provides early detection of breakage or wearing components.

8.1.2.1 Robot Side

1. Inspect the latching cams and locating/alignment pins for rust, breakage, or wear[3].
2. Inspect the Robot Side mating surface for raised material[4] or dings that could prevent proper mating to the Tool Side.
3. Uncouple the Robot Side from the Tool Side and cycle the coupling mechanism several times to verify the latching cams are operating smoothly. The cycling of the coupling mechanism will also ensure that the operating cylinder remains properly lubricated.

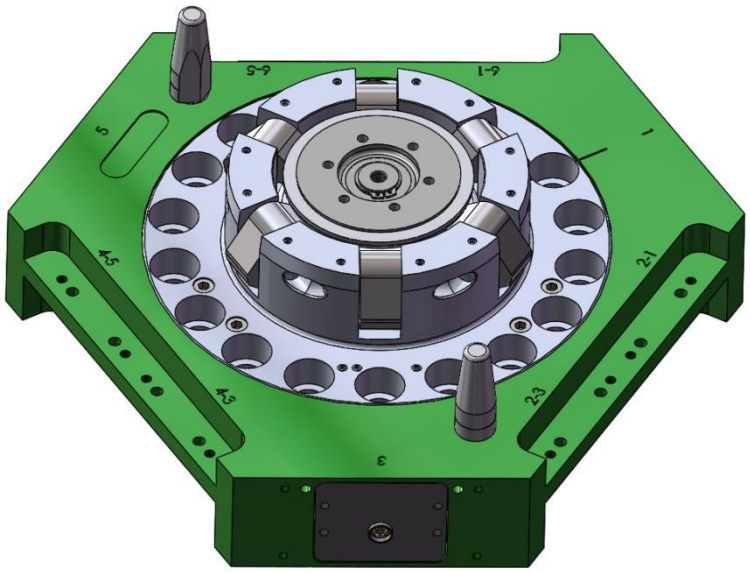


Figure 8.1.2.1-1. ES200 Robot Side Visual Inspection

[3] If excessive wear is found on the locating/alignment pins, latching cams, or Robot Adaptor mating surface, review the docking and undocking sequence of the robot program and adjust if necessary.
[4] All raised material should be filed smooth.

8.1.2.2 Tool Side

1. The locating/alignment bushings and the latching surfaces should be inspected for proper lubrication as defined in Section 8.1.1.1.
2. Inspect the latching surfaces and locating/alignment bushings for rust, breakage, or wear[5].
3. Inspect the Tool Side mating surface for raised material[6] or dings that could prevent proper mating to the Robot Side.

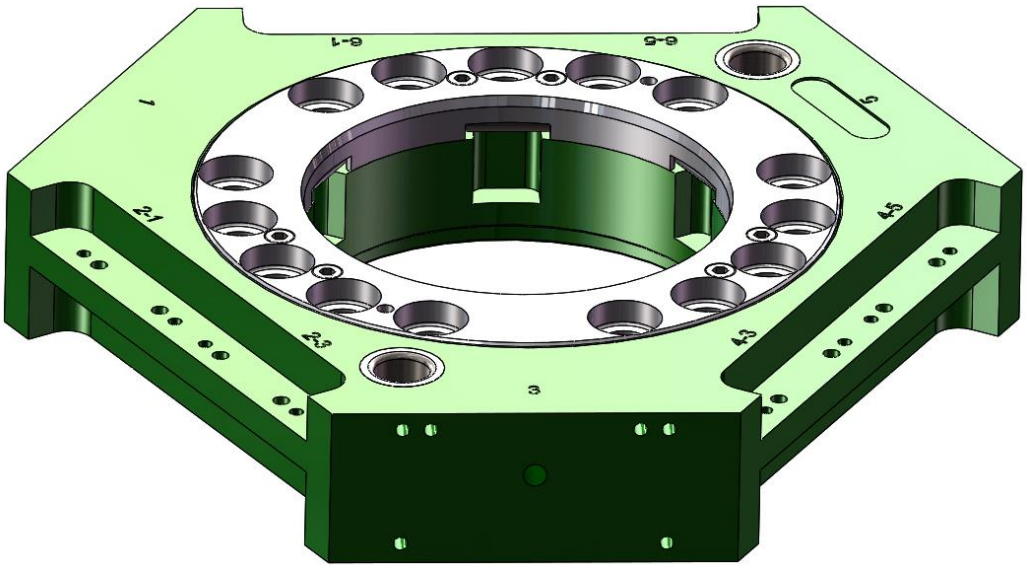


Figure 8.1.2.2-1. ES200 Tool Side Visual Inspection

[5] If excessive wear is found on the locating/alignment bushings, latching surfaces, or Tool Adaptor mating surface, review the docking and undocking sequence of the robot program and adjust if necessary.
[6] All raised material should be filed smooth.

8.1.3 Checking Wear of the Cam Locking Mechanism

Poor maintenance and/or poor programming can cause unnecessary wear on the Tool Changer. In the unlikely event that the Epsilon Tool Changer begins to demonstrate signs of wear in the cam locking mechanism, causing the connection between the Robot Side and Tool Side to lose repeatability and precision, the following can be used to check the wear of the locking mechanism.

1. Remove the Robot Side from the Robot/Manipulator.
1. Remove the Tool Side from the Tool.
2. With the Sides positioned on a workbench, inspect the mating surfaces of the Robot (Figure 8.1.3-1) and Tool (Figure 8.1.3-2) Sides for any raised material. If any raised material is found, file smooth before proceeding.

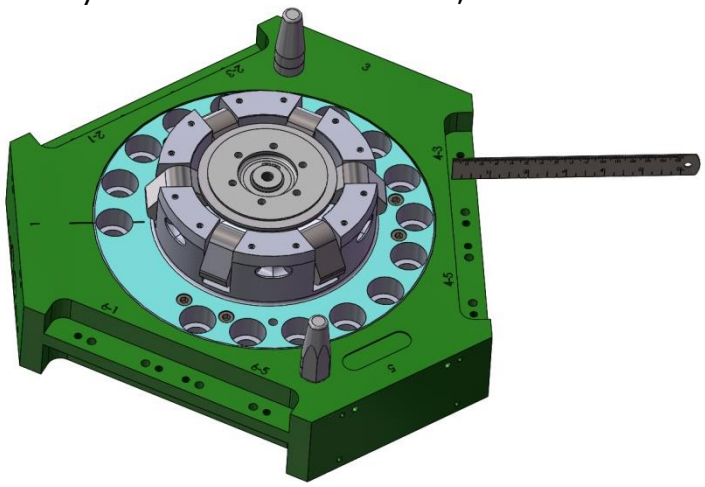


Figure 8.1.3-1. Robot Side – Raised Material Inspection

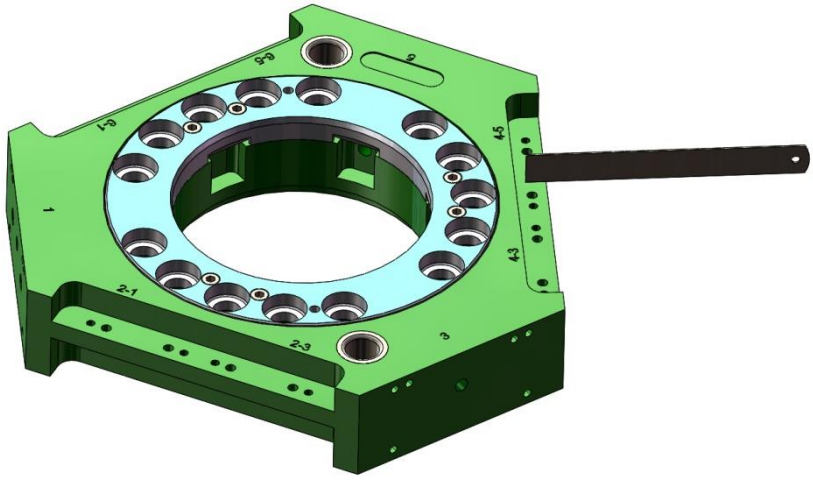


Figure 8.1.3-2. Tool Side – Raised Material Inspection

3. Connect the couple and uncouple actuation port lines (Figure 5.3-1) so that the locking mechanism can be manually actuated.

4. With the cams retracted (Figure 6.1-2), position the Robot Side and Tool Side so that they can be coupled together.
5. Place a 0.05mm piece of shim stock at the locations shown in Figure 8.1.3-3, one location at a time.
6. Actuate the cams to couple the Robot Side to the Tool Side (Figure 6.1-1).
7. With a slight tug, check if the piece of shim stock is securely clamped between the Robot Side and Tool Side interface surfaces.
8. Uncouple the Robot Side from the Tool Side.
9. Repeat Steps 6 through 9 for each location shown in Figure 8.1.3-3.

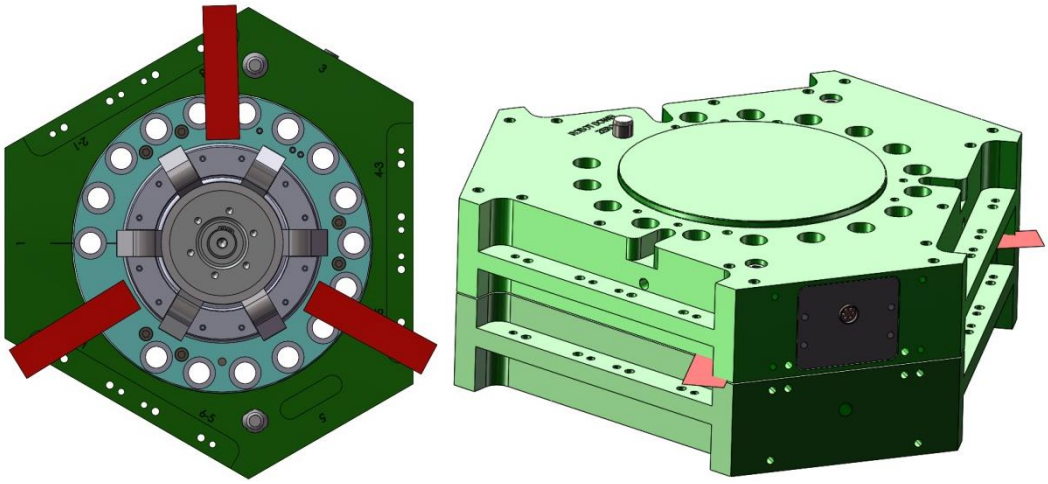


Figure 8.1.3-3. Shim Test of the Cam Locking Mechanism

If the piece of shim stock is able to be pulled free from the coupling interface while the cams are actuated (Figure 6.1-1), record the serial number of the Robot Side and Tool Side and contact APPLIED ROBOTICS Technical Support Department at +1 518 384 1000 or techsupport@appliedrobotics.com.

9 SPARE PARTS

The spare parts listed below are recommended to be maintained in stock for the life of the Tool Changer. These quantities are based on a single unit. If higher quantities are purchased, please contact the Technical Support Department at +1 518 384 1000 or techsupport@appliedrobotics.com to determine the quantity of spares recommended for the size of your installation.

Table 9-1. Robot Side Spare Parts

ROBOT SIDE		
Description	**Part Number**	**Quantity**
PIN, ROUND LOCATING S5 (Round Locating Pin)	0108-B05N	1
PIN, DIAMOND LOCATING S5 (Diamond Locating Pin)	0108-B06N	1
SUBASSY, PS MODULE S5.3R	1501-D59A	1 *
SUBASSY, PS MOD., ER200 W/M12	1800404A	1 *

* Verify which spare part is needed depending upon tool changer configuration.

Table 9-2. Tool Side Spare Parts

TOOL SIDE		
Description	**Part Number**	**Quantity**
BUSHING, LOCATING	0105-P85N	2

10 SPARE PARTS REPLACEMENT

The following procedures explain the correct method for removing and replacing the recommended spare parts listed in Section 8.1.3 of this manual. For any replacement or repair not covered in this section, please contact the Technical Support Department at +1 518 384 1000 or techsupport@appliedrobotics.com for the appropriate replacement instructions.

10.1 ROBOT SIDE

10.1.1 Locating/Alignment Pins

1. Remove the Robot Side from the Robot/Manipulator.
2. Remove the M8 socket head cap screw (49045) using a 6mm Allen wrench.
3. Remove round Locating Pin (0108-B05N) or Diamond Locating Pin (0108-B06N). Locating/Alignment Pins may need to be punched out.
4. Place new Locating Pin into the appropriate mounting hole. Check the orientation of the Diamond Locating Pin as shown in Figure 10.1.1-1.
5. Apply Loctite 242, or equivalent, to M8 socket head cap screw removed in Step 2 (Clean threads before applying thread locker) and thread it into the Locating Pin from the top side of the Robot Side Housing.

NOTICE

M8X30 SET SCREWS HAVE A RECOMMENDED TORQUE OF 15 Nm (120 in-lb).

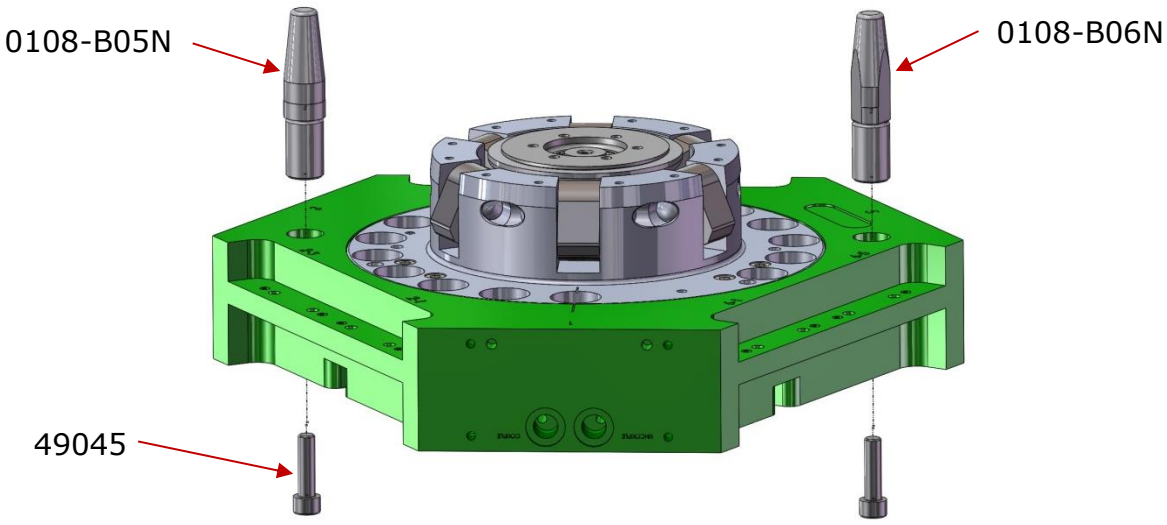


Figure 10.1.1-1. Locating/Alignment Pin Replacement

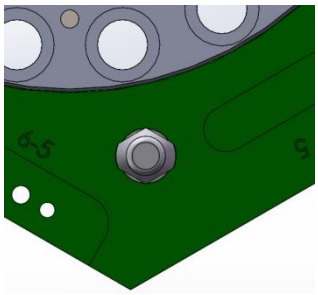


Figure 10.1.1-2. Locating/Alignment Pin Replacement

10.1.2 Couple/Uncouple Sensing Module

1. Remove the module on Side 3.
2. Loosen the captivated socket head cap screws holding the Sensing Module using a 3mm Allen wrench.
3. Remove the Sensing Module (1500-D59A or 1800404A) and either discard or send to APPLIED ROBOTICS for repair.
4. Replace unit with another Sensing Module.
5. Clean the socket head cap screw threads and apply Loctite 242, or equivalent, to the threads and tighten.
6. Ensure that the cavity in the Robot Side Housing holding the Sensing Module is free of all foreign objects.
7. Ensure that the four (4) O-rings (0601-P65N) for the air ports, supplied with the Sensing Module, are properly positioned.
8. Install the new Sensing Module using the captivated socket head cap screws.
9. Reinstall module removed from Side 3 in Step 1.
10. Prior to coupling the Tool Changer, cycle the actuating cylinder for the Robot Side several times to ensure that the sensors are working properly, and the correct inputs are being received by the robot controller.

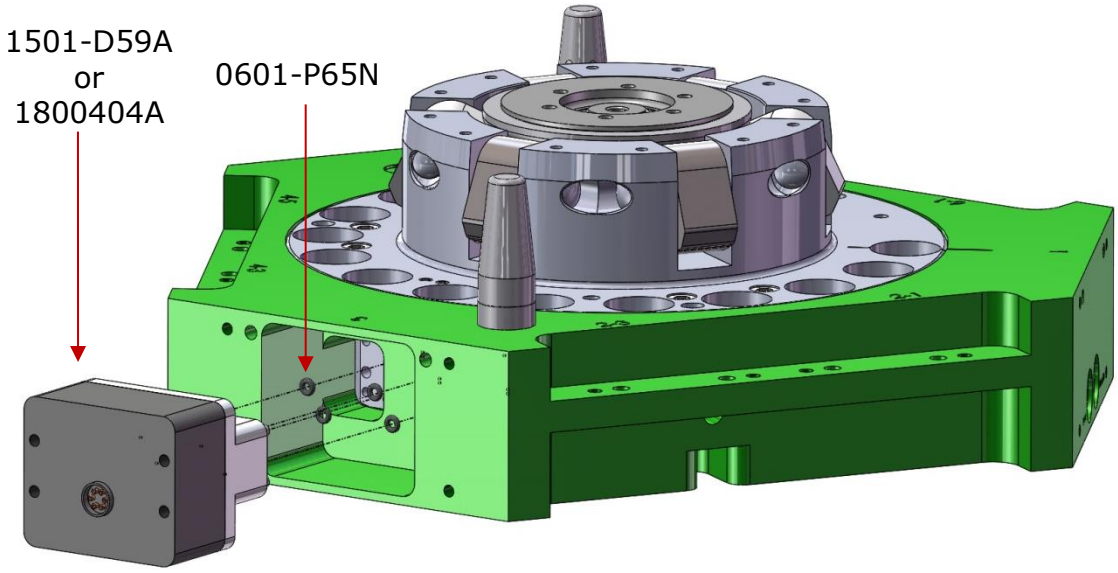


Figure 10.1.2-1. Couple/Uncouple Sensing Module Replacement

NOTICE

MAKING CONNECTIONS WHILE UNDER POWER COULD RESULT IN DAMAGE TO THE EQUIPMENT. TO AVOID DAMAGING EQUIPMENT, ENSURE THAT ALL CABLES ARE CONNECTED BEFORE SUPPLYING POWER TO THE EQUIPMENT.

10.2 TOOL SIDE

10.2.1 Locating Bushing

1. Remove the Tool Side from the Tool.
2. Press out the Locating Bushings (0105-P85N) from the bottom of the Tool Side Housing.
3. Press in new Locating Bushings from the top of the Tool Side Housing until it is flush with the Tool Side Housing surface. Ensure that the rounded edge of the Locating Bushing faces the top surface of the Tool Side Housing.
4. Lubricate the Locating Bushing per Section 8.1.1.1.

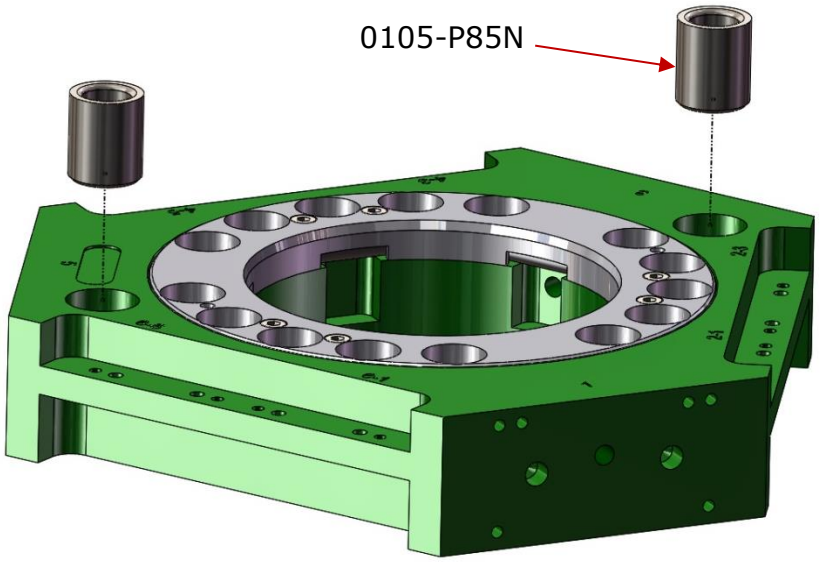


Figure 10.2.1-1. Locating Bushing Replacement

11 INFORMATIONAL DOCUMENTS

The drawings in this section can assist with installation, use, and identification of replacement parts for the Epsilon Tool Changer. Please contact **APPLIED ROBOTICS Technical Support** if you have any questions.

DECLARATIONS
• Declaration of Incorporation for Partly Completed Machinery

DRAWINGS	
DRAWING NUMBER	**DESCRIPTION**
1501-E99A	ERS200ISO11-PNP-160-N-0-C0000
1900474A	ERS200ISO11-PM12-160-N-0-C0000
2000189A	ERS200ISO11-PNP-125-N-0-C0000
2000190A	ERS200ISO11-PM12-125-N-0-C0000
2100728A	ERS200ISO12-PNP-125-N-0-C0000
2100810A	ERS200ISO12-PM12-125-N-0-C0000
1501-E98A	ETS200-160-N-C0000

Declaration of Incorporation of Partly Completed Machinery (Annex II 1 B of EC Machinery Directive 2006/42/EC)

Description and identification of the partly completed machinery:

XChange – EPSILON Series Tool Changers & Utility Modules

Fulfills the following function:

Allows industrial robots (and other automated equipment) to automatically change their end of arm tooling under programmed control without the need of human intervention. These products are intended to be incorporated into machinery supplied by others.

The following essential requirements of EC Machinery Directive 2006/42/EC (Annex I) have been applied and fulfilled:

Section 1.1.2.	Principles of safety integration
Section 1.1.3.	Materials and products
Section 1.1.5.	Design of machinery to facilitate its handling
Section 1.2.1.	Safety and reliability of control systems
Section 1.2.6.	Failure of the power supply
Section 1.3.2	Risk of break-up during operation
Section 1.3.3.	Risks due to falling or ejected objects
Section 1.3.4.	Risks due to surfaces, edges or angles
Section 1.3.7.	Risks related to moving parts
Section 1.3.9.	Risks of uncontrolled movements
Section 1.5.1.	Risks due to electricity supply
Section 1.5.3.	Risks due to energy supply other than electricity (air pressure)
Section 1.5.8.	Risks due to noise
Section 1.5.10.	Risks due to non-ionizing radiation
Section 1.6.4.	Operator intervention
Section 1.7.1.	Information and warnings on the machinery
Section 1.7.2.	Warning of residual risks
Section 1.7.3.	Marking of machinery
Section 1.7.4.	Instructions.

The partly completed machinery has been designed and manufactured according to the following harmonized standards:

EN ISO 12100-1	Safety of machinery - Basic concepts, general principles for design Part 1: Basic terminology, methodology
EN ISO 12100-2	Safety of machinery - Basic concepts, general principles for design Part 2: technical principles

648 Saratoga Road
Glenville, NY 12302 USA
Tel: 518 384 1000
Fax: 518 384 1200

Via Roma 141/143
8017 San Maurizio
d'Opaglio (NO) - Italy
Tel: +39 (0) 32 29 65 93
Fax: +39 (0) 32 29 50 686

www.appliedrobotics.com

EN ISO 10218-2	Robots and robotic devices — Safety requirements for industrial robots — Part 2: Robot systems and integration
EN ISO 60204-1	Safety of machinery. Electrical equipment of machines. General requirements
EN 61000-6-2	Electromagnetic compatibility (EMC) - Generic standards. Immunity for industrial environments
EN 61000-6-4	Electromagnetic compatibility (EMC) - Generic standards. Emission standard for industrial environments
EN 61000-4-2	Electromagnetic compatibility (EMC). Testing and measurement techniques. Electrostatic discharge immunity test
EN 61010-1	Safety requirements for electrical equipment for measurement, control, and laboratory use -- Part 1: General requirements

The relevant technical documentation has been compiled in accordance with Annex VII, Part B of EC Machinery Directive 2006/42/EC. We undertake, in response to a reasoned request, to supply it in electronic form to the market surveillance authorities within a reasonable period.

The party authorized to compile the technical documentation is:

Giovanni Patrini, at Effecto Group SpA

The partly completed machinery must not be put into service until the final machinery into which it is to be incorporated has been declared in conformity with the provisions of the Machinery Directive.

Stefan Casey
Vice President, Engineering

APRIL 20, 2018
Date

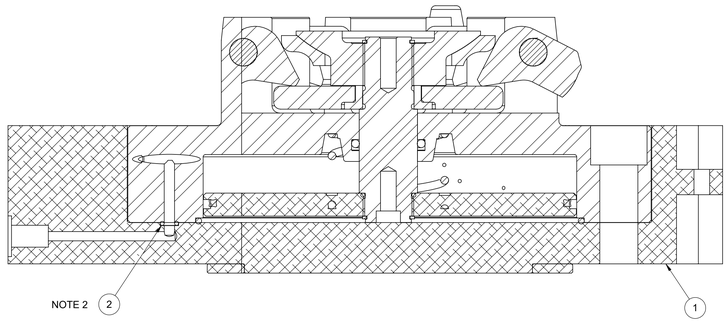
648 Saratoga Road
Glenville, NY 12302 USA
Tel: 518 384 1000
Fax: 518 384 1200

Via Roma 141/143
8017 San Maurizio
d'Opaglio (NO) - Italy
Tel: +39 (0) 32 29 65 93
Fax: +39 (0) 32 29 50 686

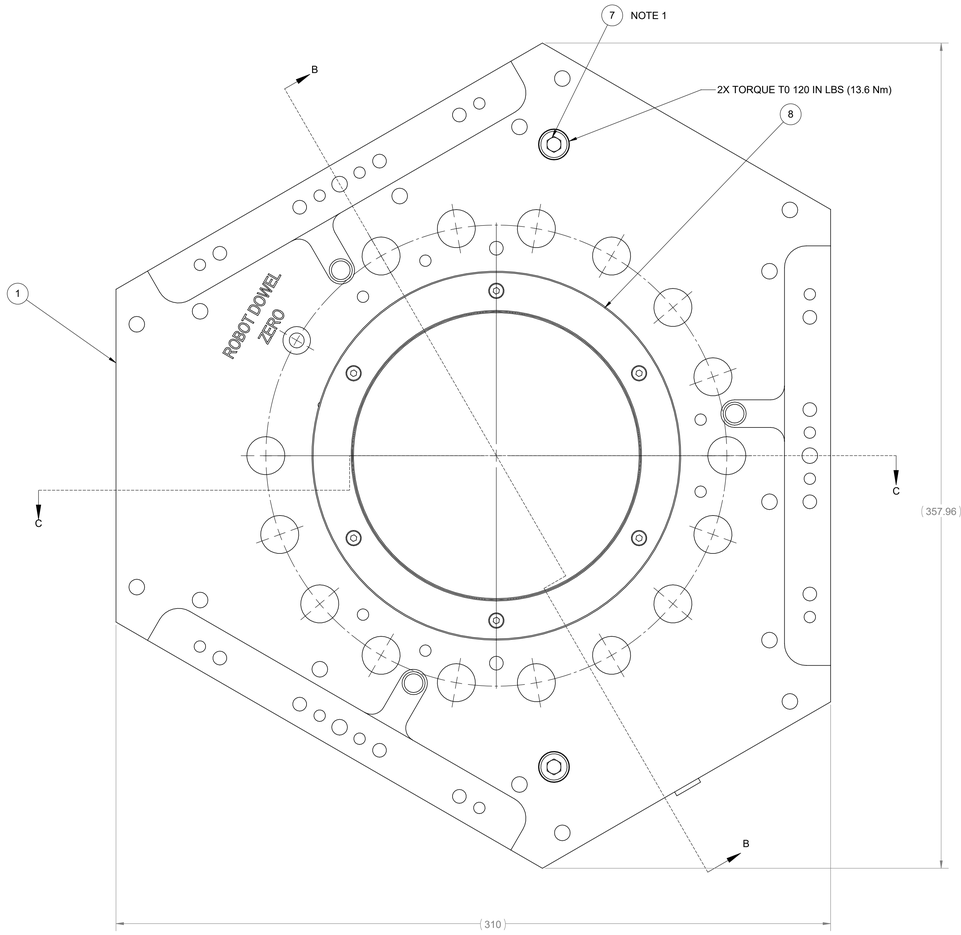
www.appliedrobotics.com

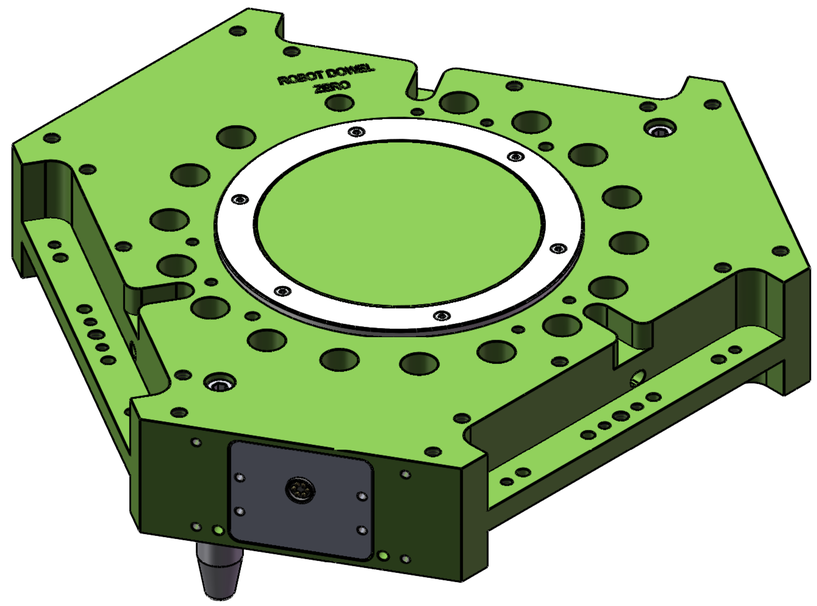
SIZE	DRAWING NUMBER	REV
E	1501-E99A	04

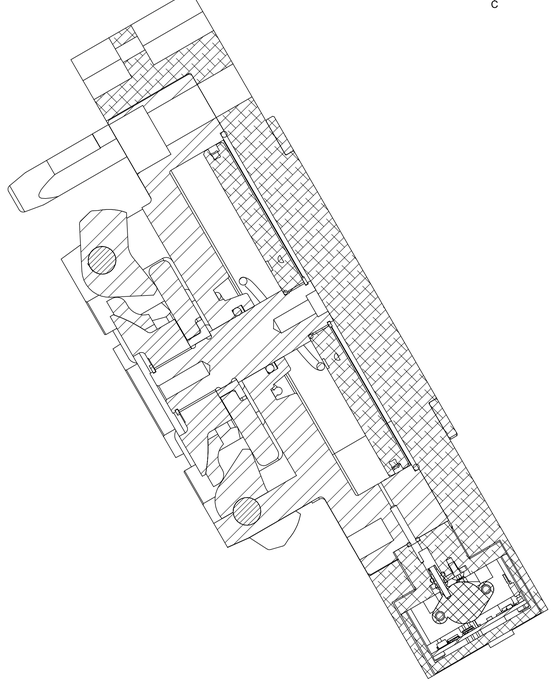
REVISIONS						
ZONE	REV	DESCRIPTION	DR	CHK	DATE	ECR/ESR NO.
	00	RELEASED FOR MANUFACTURE	TM	JV	4-10-15	JVAA-9TLLJN
	01	ADDED TEACHING	TM	TM	06/10/19	TMAA-BA6GET
	02	REPLACED PISTON SEA WITH QUAD RING	TM	TM	3-4-20	TMAA-BL3MT9
	03	ADDED 2000192A	TM	PS	3-27-20	DSCZ-BMUG9K
	04	DESCRIPTION WAS ERS200-PNP-160-N-0-C0000	PS	TM	12/15/2021	PSLI-C7YRYE



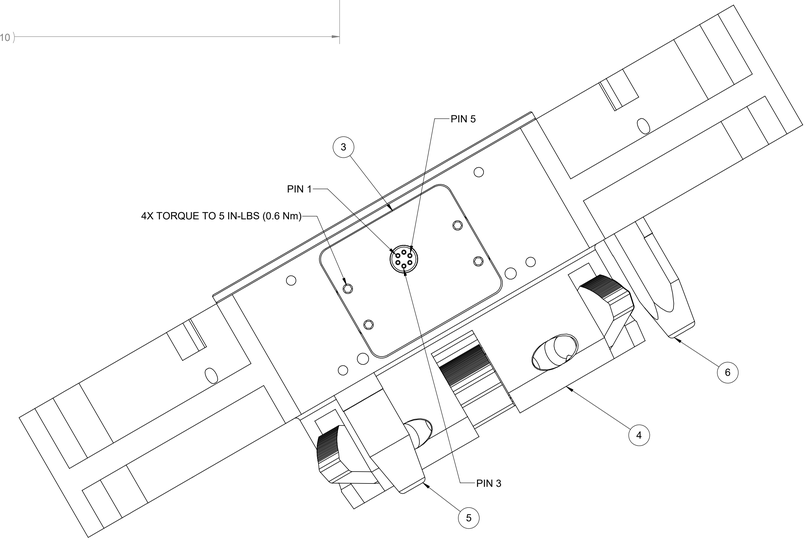
SECTION C-C
SCALE 1 : 1







SECTION B-B
SCALE 1 : 1



VIEW A-A
SCALE 1 : 1

NOTES:

1. APPLY LOCTITE 242, ARI #50106.
2. APPLY LUBE-A-CYL, ARI #51120.

ITEM NO.	QTY	PART NO.	DESCRIPTION
8	1	2000192A	SUBASSY, RING 125 TO 160 HUB
7	2	49045	SCR, SOC HD CAP M8 X 30 (STL)
6	1	0108-B06N	PIN, DIAMOND LOCATING S5R & S8R
5	1	0108-B05N	PIN, ROUND LOCATING S5R & S8R
4	1	1502-D01A	SUBASSY, SENDER ERS200
3	1	1501-D59A	SUBASSY, PS MODULE, S5.3R
2	1	85551-P1008	O-RING, .176 ID X .07 75 VITON
1	1	1501-E83N	HOUSING, ROBOT ERS200

THIRD ANGLE PROJECTION

METRIC

UNLESS OTHERWISE SPECIFIED:

UNTOLERANCED DIMS ARE BASIC

⌓ .25 A B C

⌖ Ø .25M A B C

ALL HOLE DIAMETERS +/-.0.25

INTERNAL RADIS & BROKEN EDGES TO BE .13-.38

ALL SURFACE FINISHES 1.6Ra

MAT'L: Material <not specified>

DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994

SURFACE TREATMENT: NONE

DR:	T. MARCELLA
CHK:	J. VALLELUNGA
ENG:	T. MARCELLA
MFG:	C. BEST
QC:	M. DUONATH

3D MODEL NUMBER: 1501-E99A

SCALE: 1:2

DO NOT SCALE DRAWING

ISO 9001 REGISTERED

Applied Robotics™ Solutions in reach

648 Saratoga Rd. Glenville, NY. 12302
www.appliedrobotics.com

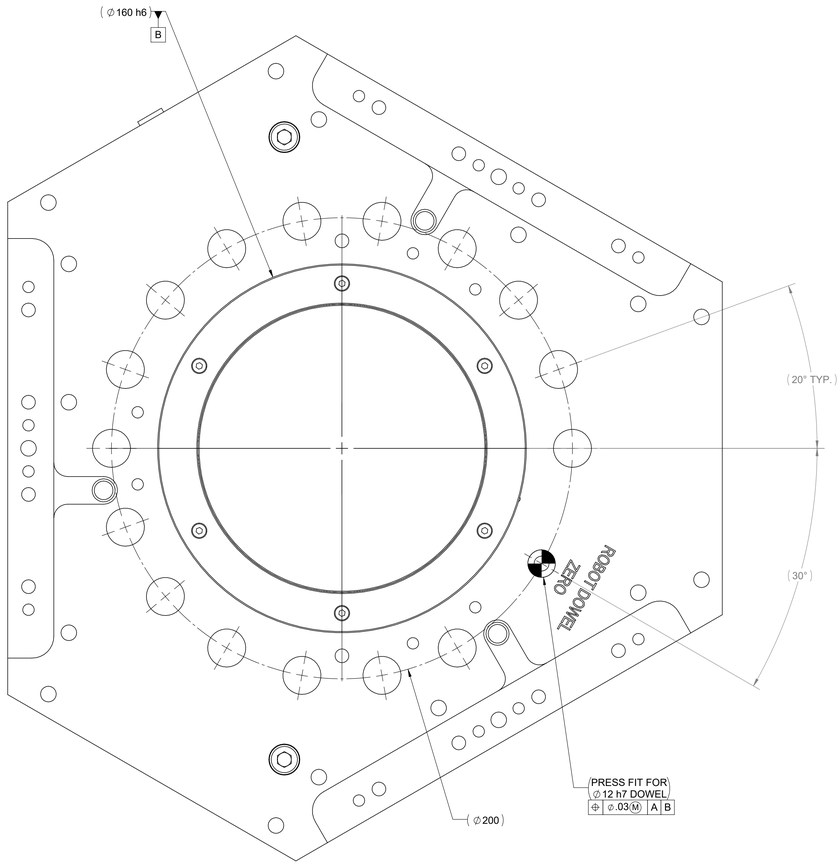
TITLE:
ERS200ISO11-PNP-160-N-0-C0000
(PRESSURE SENSING)

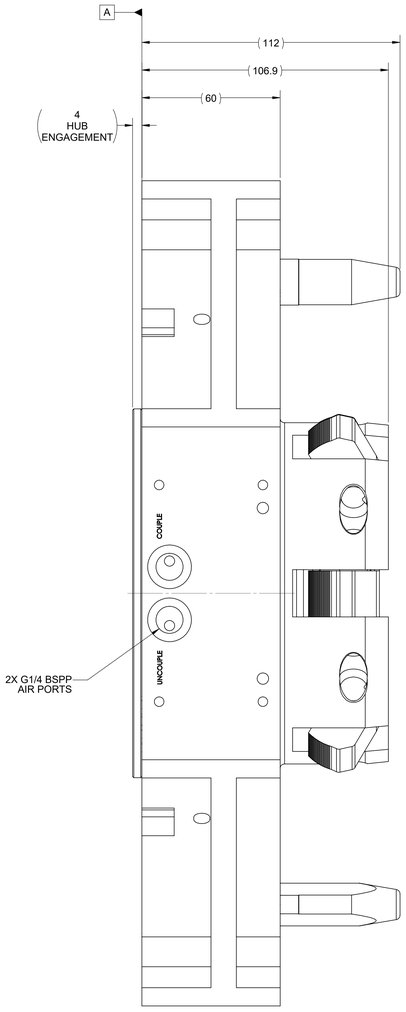
SIZE	DRAWING NUMBER	REV
E	1501-E99A	04

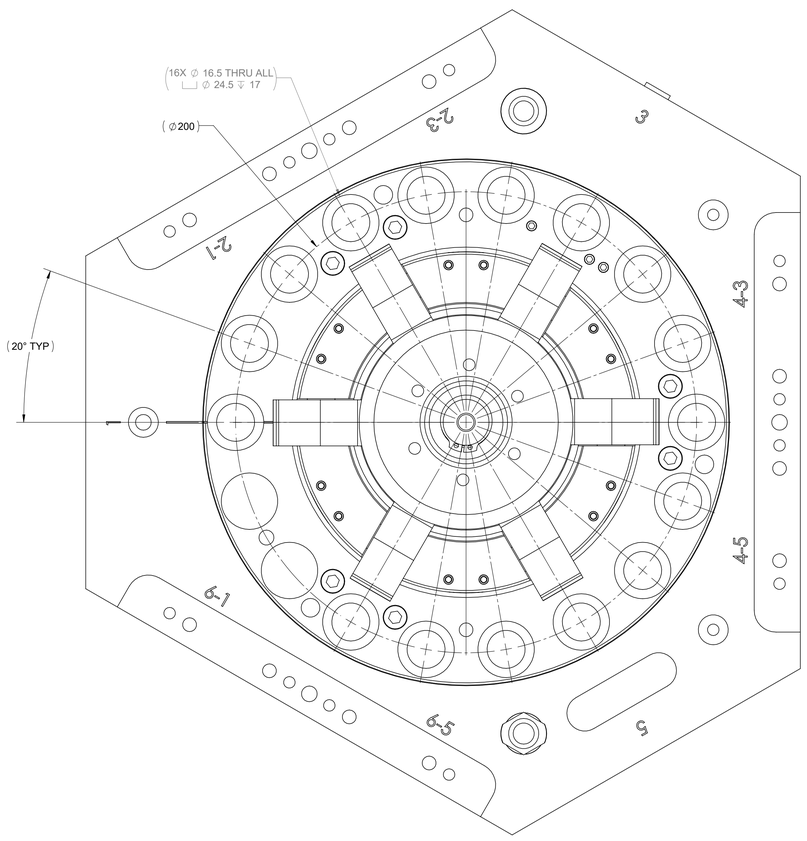
WEIGHT: 19.09 kg | RoHs COMPLIANT: - | SHT. 1 OF 2

PRINT DATE 12/22/2021

SIZE	DRAWING NUMBER	REV
E	1501-E99A	04







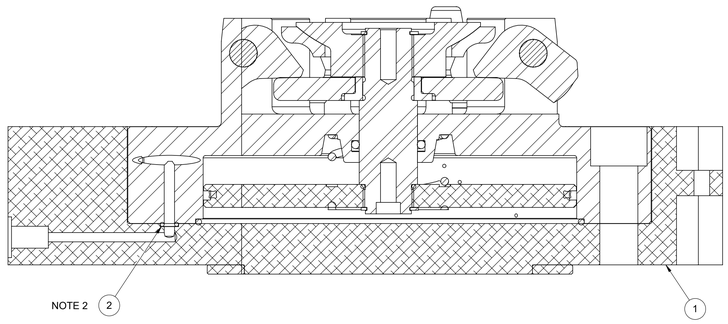
THIRD ANGLE PROJECTION	METRIC	DR: T. MARCELLA	Applied Robotics™ Solutions in reach
THE INFORMATION CONTAINED HERE IN IS THE SOLE PROPERTY OF APPLIED ROBOTICS INC. THE INFORMATION IN THIS DOCUMENT/FILE IS SUBJECT TO CHANGE WITHOUT NOTICE. APPLIED ROBOTICS MAKES NO WARRANTY OF ANY KIND WITH REGARD TO THIS DOCUMENT/FILE, INCLUDING, BUT NOT LIMITED TO IMPLIED WARRANTIES OR FITNESS FOR A PARTICULAR PURPOSE. APPLIED ROBOTICS INC. SHALL NOT BE LIABLE FOR ERRORS CONTAINED HERE IN OR FOR INCIDENTAL OR CONSEQUENTIAL DAMAGES IN CONNECTION WITH THE PERFORMANCE OR USE OF THIS DOCUMENT/FILE.	UNLESS OTHERWISE SPECIFIED: UNTOLERANCED DIMS ARE BASIC ⌓ .25 A B C ⌖ ⌀ .25Ⓜ A B C ALL HOLE DIAMETERS +/-0.25 INTERNAL RADIS & BROKEN EDGES TO BE .13-.38 ALL SURFACE FINISHES 1.6Ra	CHK: J. VALLELUNGA ENG: T. MARCELLA MFG: C. BEST QC: M. DUDNATH 3D MODEL NUMBER: 1501-E99A	648 Saratoga Rd. Glenville, NY. 12302 www.appliedrobotics.com TITLE: ERS200ISO11-PNP-160-N-0-C0000 (PRESSURE SENSING) -
PRINT DATE 12/22/2021	MATL: Material <not specified> DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994	SCALE: 1:2 DO NOT SCALE DRAWING SURFACE TREATMENT: NONE	ISO 9001 REGISTERED

SIZE	DRAWING NUMBER	REV
E	1501-E99A	04

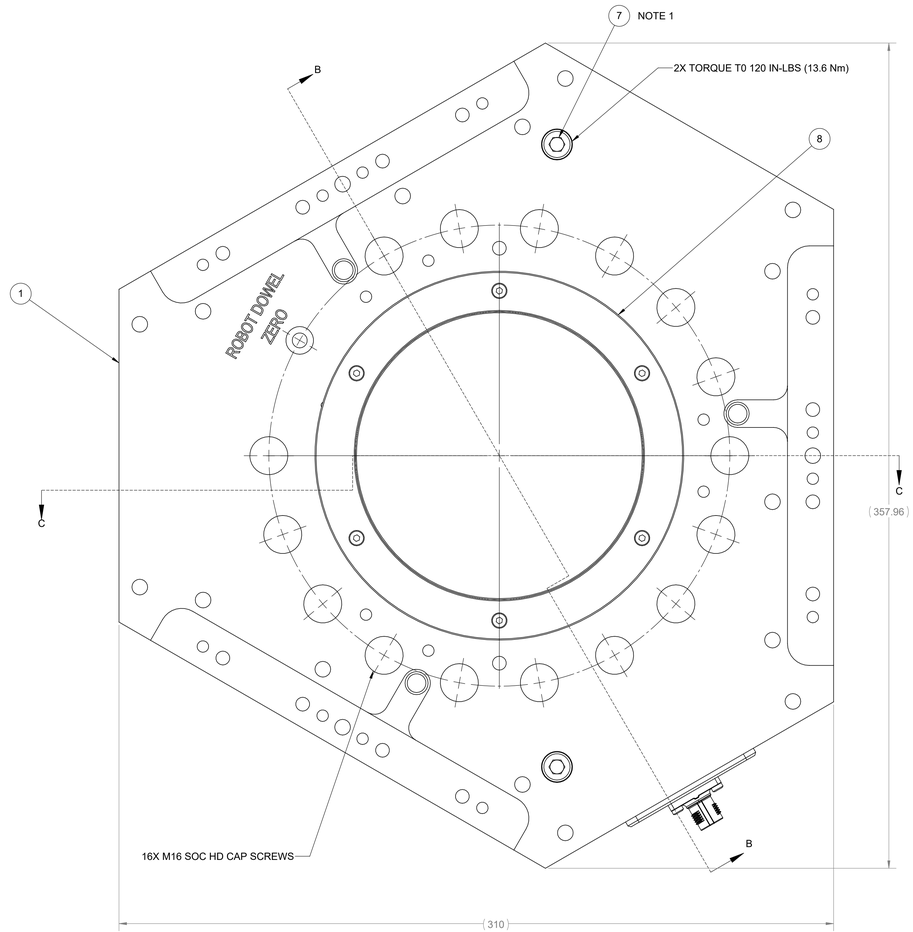
WEIGHT: 19.09 kg | RoHs COMPLIANT: - | SHT. 2 OF 2

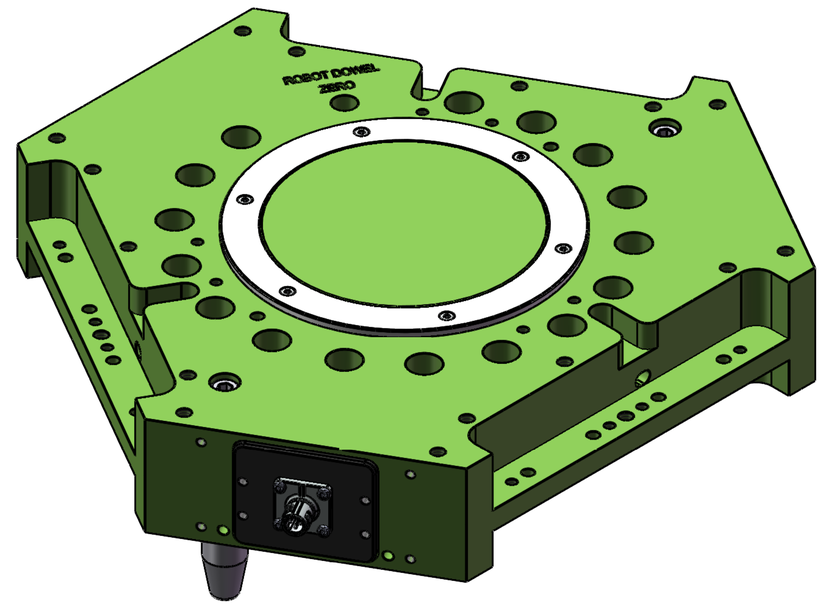
SIZE	DRAWING NUMBER	REV
E	1900474A	03

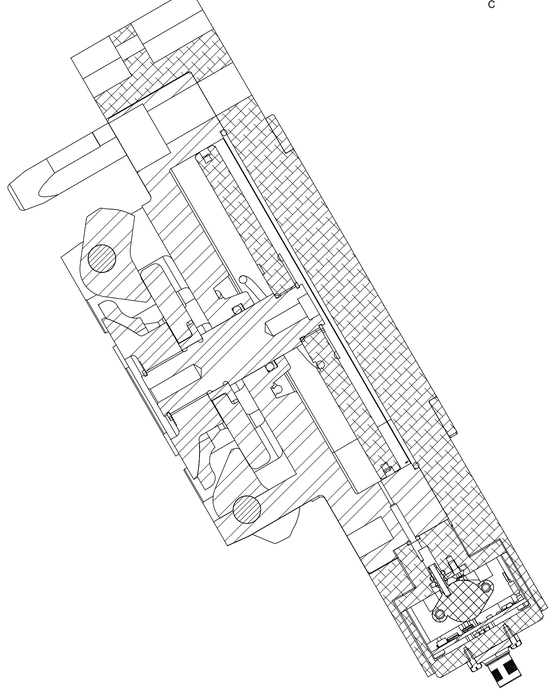
REVISIONS						
ZONE	REV	DESCRIPTION	DR	CHK	DATE	ECR/ESR NO.
	00	RELEASED FOR MANUFACTURE	JV	PS	6/26/2019	WZEH-BD9LAQ
	01	REPLACED O-RING WITH QUAD RING	TM	PS	3-4-20	TMAA-BL3MT9
	02	ADDED 2000192A	TM	PS	3-27-20	DSCZ-BMUG9K
	03	DESCRIPTION WAS ERS200-PM12-160-N-0-C0000	PS	TM	12/15/2021	PSLI-C7YRYE



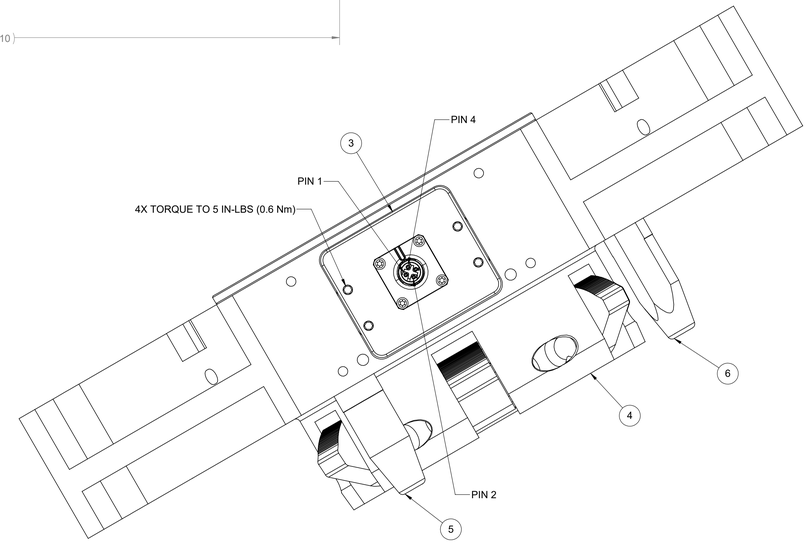
SECTION C-C
SCALE 1 : 1







SECTION B-B
SCALE 1 : 1



VIEW A-A
SCALE 1 : 1

NOTES:

1. APPLY LOCTITE 242, ARI #50106.
2. APPLY LUBE-A-CYL, ARI #51120.

ITEM NO.	QTY	PART NO.	DESCRIPTION
8	1	2000192A	SUBASSY, RING 125 TO 160 HUB
7	2	49045	SCR, SOC HD CAP M8 X 30 (STL)
6	1	0108-B06N	PIN, DIAMOND LOCATING S5R & S8R
5	1	0108-B05N	PIN, ROUND LOCATING S5R & S8R
4	1	1502-D01A	SUBASSY, SENDER ERS200
3	1	1800404A	SUBASSY, PS MOD., ER200
2	1	85551-P1008	O-RING, .176 ID X .07 75 VITON
1	1	1501-E83N	HOUSING, ROBOT ERS200

THIRD ANGLE PROJECTION

METRIC

UNLESS OTHERWISE SPECIFIED:

UNTOLERANCED DIMS ARE BASIC

.25 A B C

Ø .25M A B C

ALL HOLE DIAMETERS +/- 0.25

INTERNAL RADIS & BROKEN EDGES TO BE .13-.38

ALL SURFACE FINISHES 1.6Ra

MAT'L:
Material <not specified>

DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994

SURFACE TREATMENT:
NONE

DR:	J. VALLELUNGA
CHK:	P. SLAVINSKI
ENG:	J. VALLELUNGA
MFG:	M. DUDNATH
QC:	M. DUDNATH

3D MODEL NUMBER:
1900474A

SCALE: 1:2

DO NOT SCALE DRAWING

ISO 9001 REGISTERED

Applied Robotics™
Solutions in reach
648 Saratoga Rd. Glenville, NY 12302
www.appliedrobotics.com

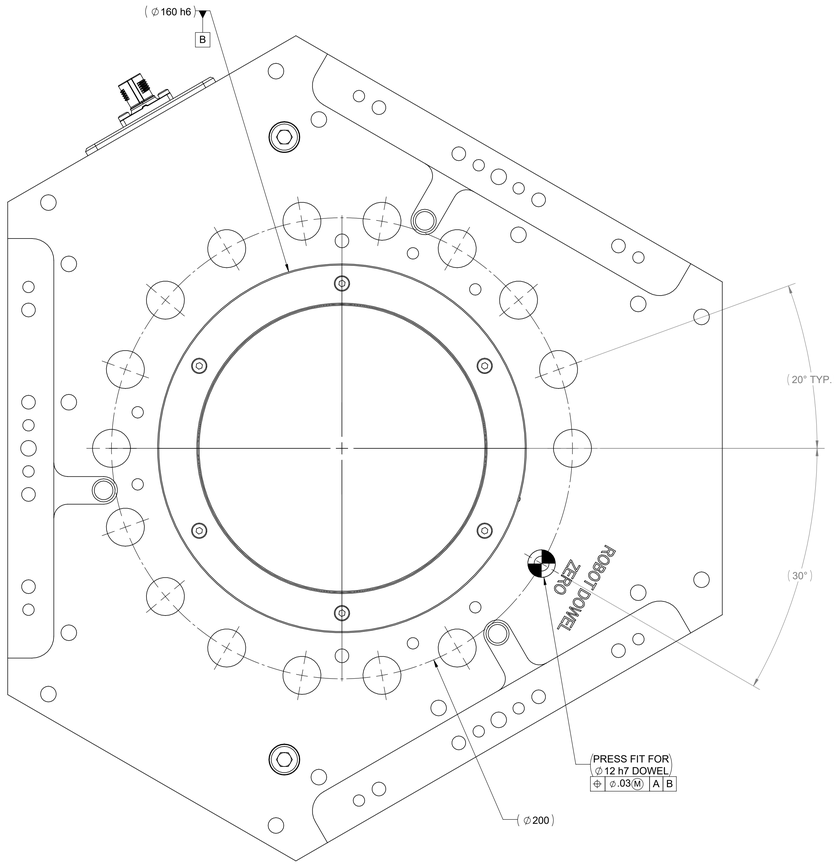
TITLE:
ERS200ISO11-PM12-160-N-0-C0000
(PRESSURE SENSING)
-

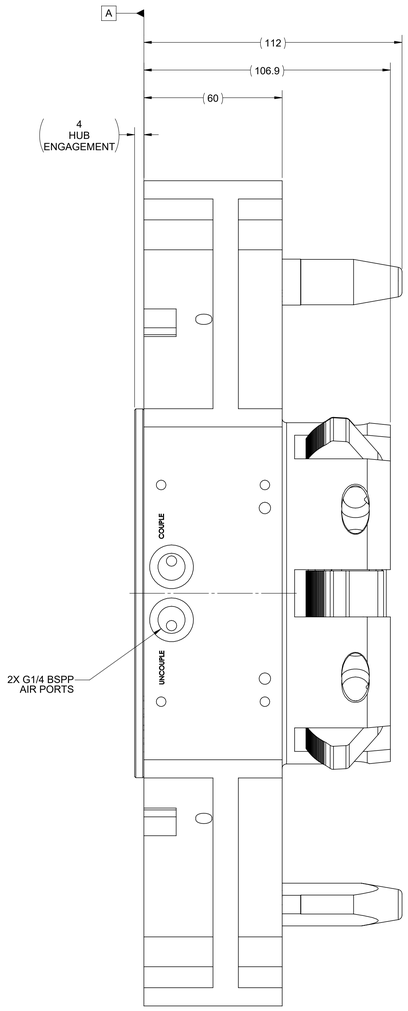
SIZE	DRAWING NUMBER	REV
E	1900474A	03

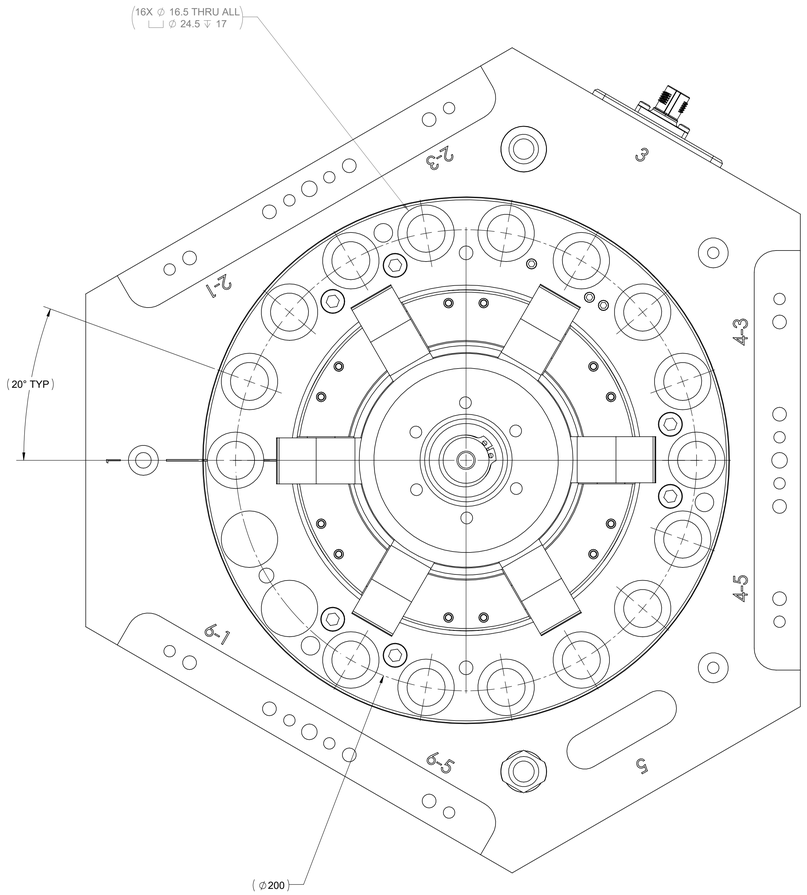
WEIGHT: 19.10 kg | RoHs COMPLIANT: - | SHT. 1 OF 2

PRINT DATE
12/22/2021

SIZE	DRAWING NUMBER	REV
E	1900474A	03







THIRD ANGLE PROJECTION

DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994

METRIC

UNLESS OTHERWISE SPECIFIED:

UNTOLERANCED DIMS ARE BASIC

⌓ .25 A B C

⌖ ⌀ .25Ⓜ A B C

ALL HOLE DIAMETERS +/- 0.25

INTERNAL RADIIS & BROKEN EDGES TO BE .13-.38

ALL SURFACE FINISHES 1.6Ra

MAT'L: Material <not specified>

SURFACE TREATMENT: NONE

DR:	J. VALLELUNGA
CHK:	P. SLAVINSKI
ENG:	J. VALLELUNGA
MFG:	M. DUDNATH
QC:	M. DUDNATH

3D MODEL NUMBER: 1900474A

SCALE: 1:2

DO NOT SCALE DRAWING

ISO 9001 REGISTERED

PRINT DATE 12/22/2021

Applied Robotics™ Solutions in reach
648 Saratoga Rd. Glenville, NY. 12302
www.appliedrobotics.com

TITLE:

ERS200ISO11-PM12-160-N-0-C0000 (PRESSURE SENSING)

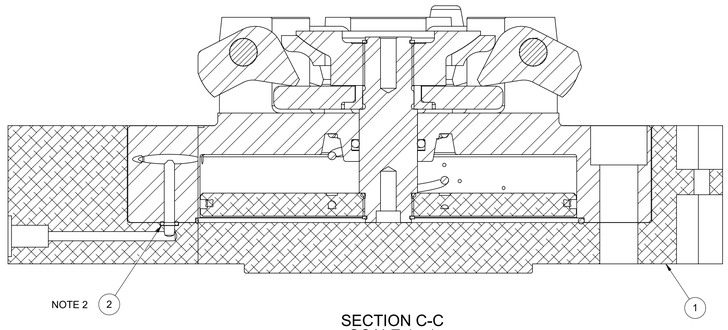
-

SIZE	DRAWING NUMBER	REV
E	1900474A	03

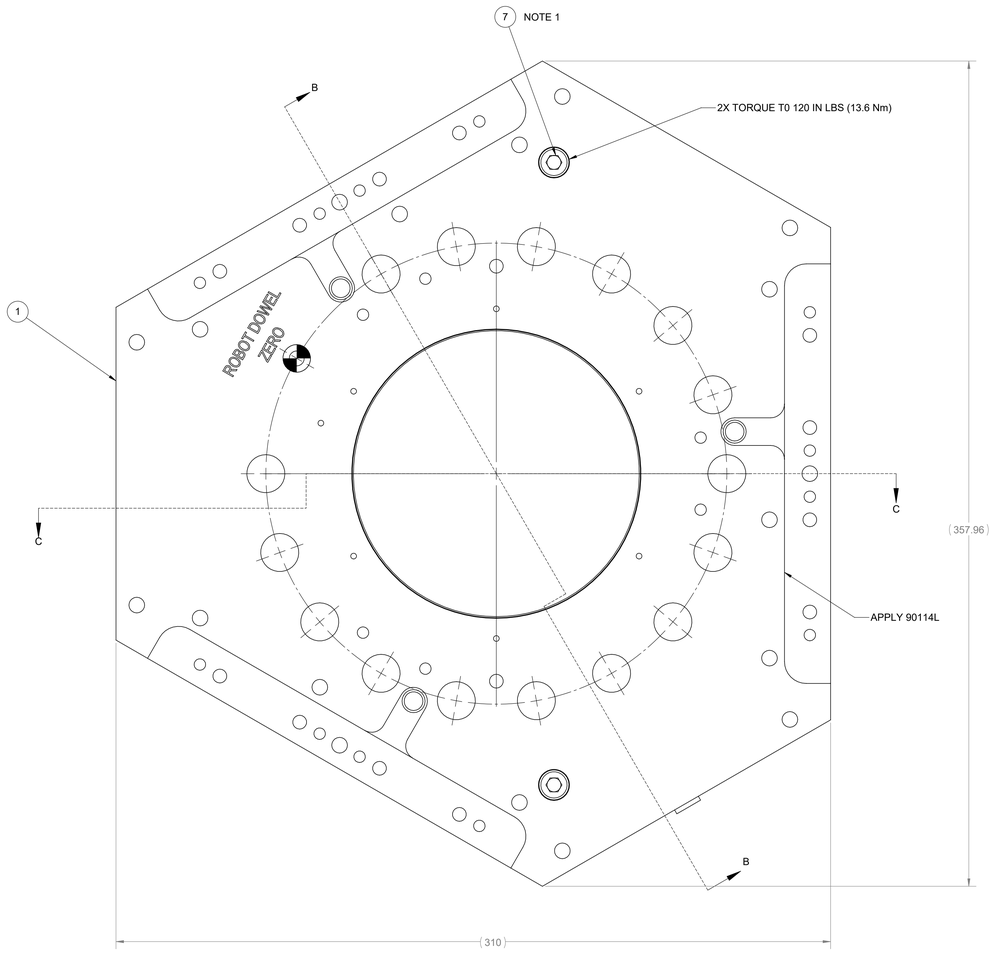
WEIGHT: 19.10 kg | RoHs COMPLIANT: - | SHT. 2 OF 2

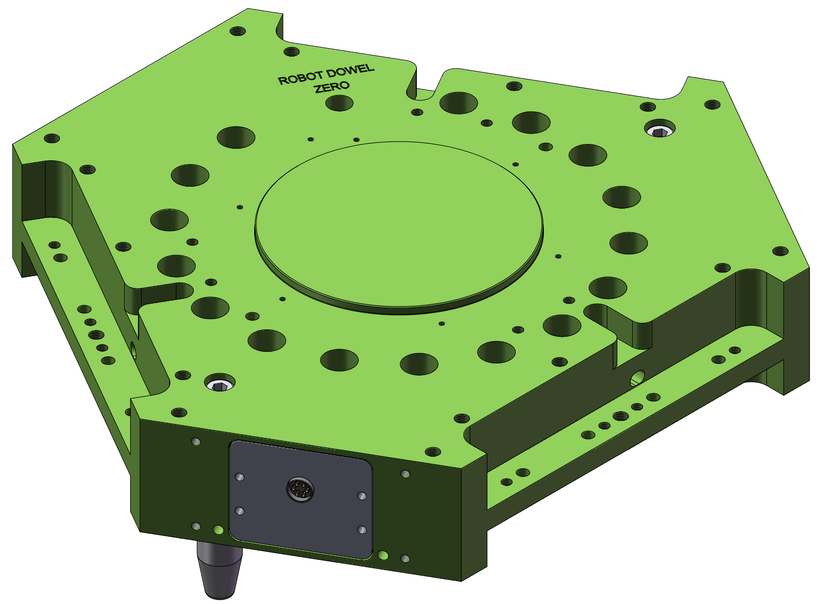
SIZE	DRAWING NUMBER	REV
E	2000189A	01

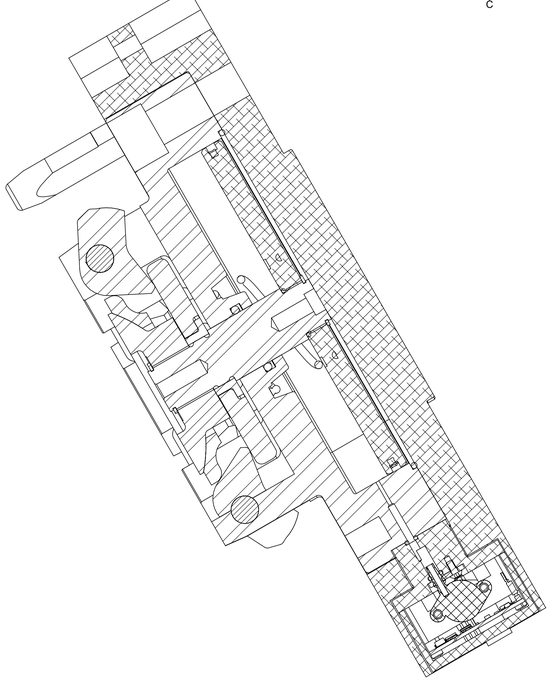
REVISIONS						
ZONE	REV	DESCRIPTION	DR	CHK	DATE	ECR/ESR NO.
	00	RELEASED FOR MANUFACTURE	TM	PS	3-27-20	DSCZ-BMUG4R
	01	DESCRIPTION WAS ERS200-PNP-125-N-0-C0000	PS	TM	12/15/2021	PSLI-C7YRYE



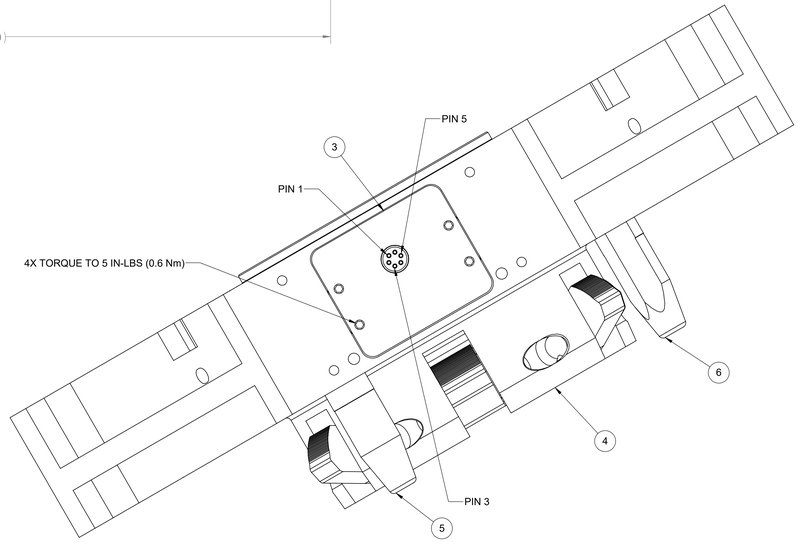
SECTION C-C
SCALE 1 : 1







SECTION B-B
SCALE 1 : 1



VIEW A-A
SCALE 1 : 1

NOTES:

1. APPLY LOCTITE 242, ARI #50106.
2. APPLY LUBE-A-CYL, ARI #51120.

ITEM NO.	QTY	PART NO.	DESCRIPTION
7	2	49045	SCR, SOC HD CAP M8 X 30 (STL)
6	1	0108-B06N	PIN, DIAMOND LOCATING S5R & S8R
5	1	0108-B05N	PIN, ROUND LOCATING S5R & S8R
4	1	1502-D01A	SUBASSY, SENDER ERS200
3	1	1501-D59A	SUBASSY, PS MODULE, S5.3R
2	1	85551-P1008	O-RING, .176 ID X .07 75 VITON
1	1	1501-E83N	HOUSING, ROBOT ERS200

THIRD ANGLE PROJECTION

METRIC

UNLESS OTHERWISE SPECIFIED:

UNTOLERANCED DIMS ARE BASIC

⌓ .25 A B C

⌖ Ø .25M A B C

ALL HOLE DIAMETERS +/-0.25

INTERNAL RADIS & BROKEN EDGES TO BE .13-.38

ALL SURFACE FINISHES 1.6Ra

MAT'L: Material <not specified>

SURFACE TREATMENT: NONE

DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994

DR:	T. MARCELLA
CHK:	SEE REV BLOCK
ENG:	T. MARCELLA
MFG:	M. DUDNATH
QC:	D. DITONNO

3D MODEL NUMBER: 2000189A

SCALE: 1:2

DO NOT SCALE DRAWING

ISO 9001 REGISTERED

Applied Robotics™ Solutions in reach
648 Saratoga Rd. Glenville, NY. 12302
www.appliedrobotics.com

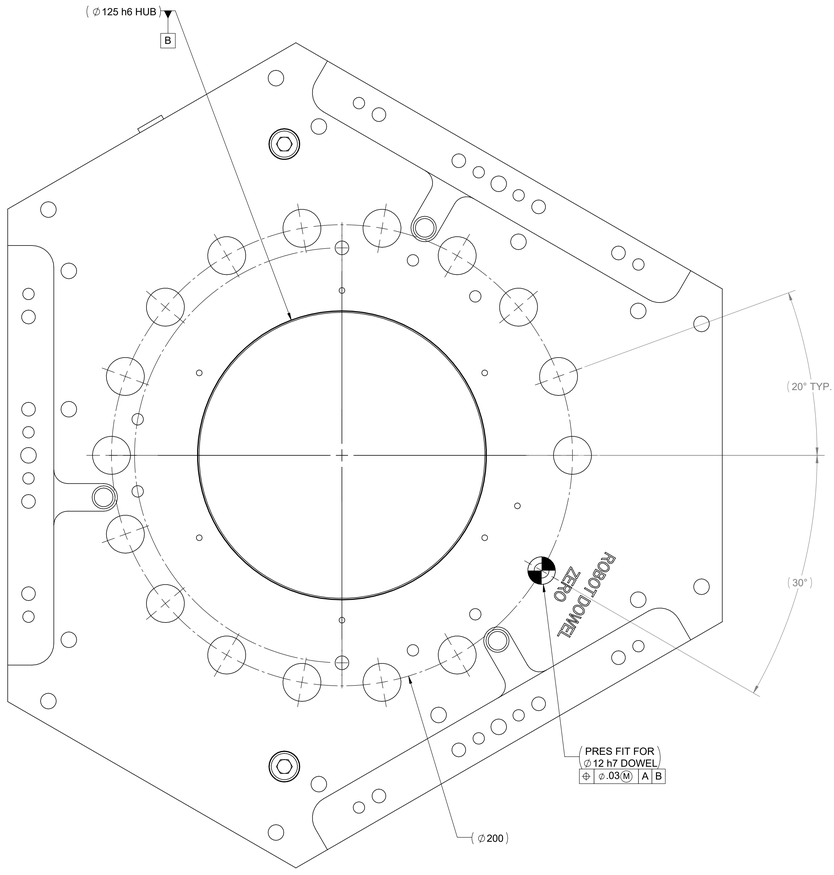
TITLE:
ERS200ISO11-PNP-125-N-0-C0000
(PRESSURE SENSING)

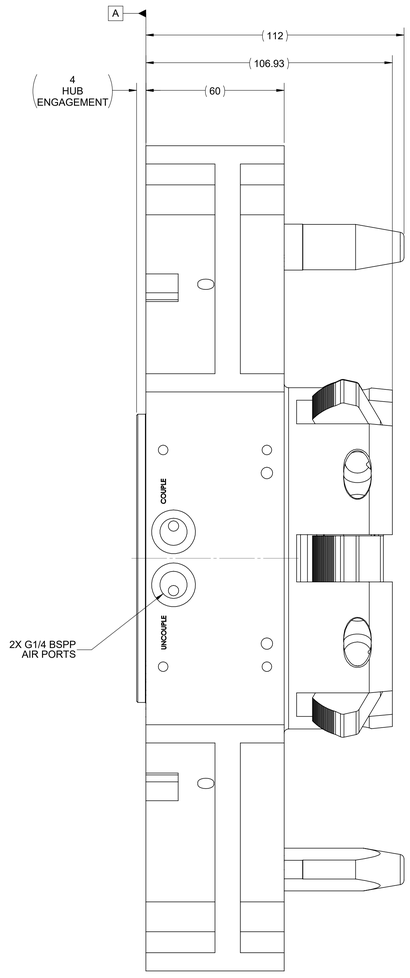
SIZE	DRAWING NUMBER	REV
E	2000189A	01

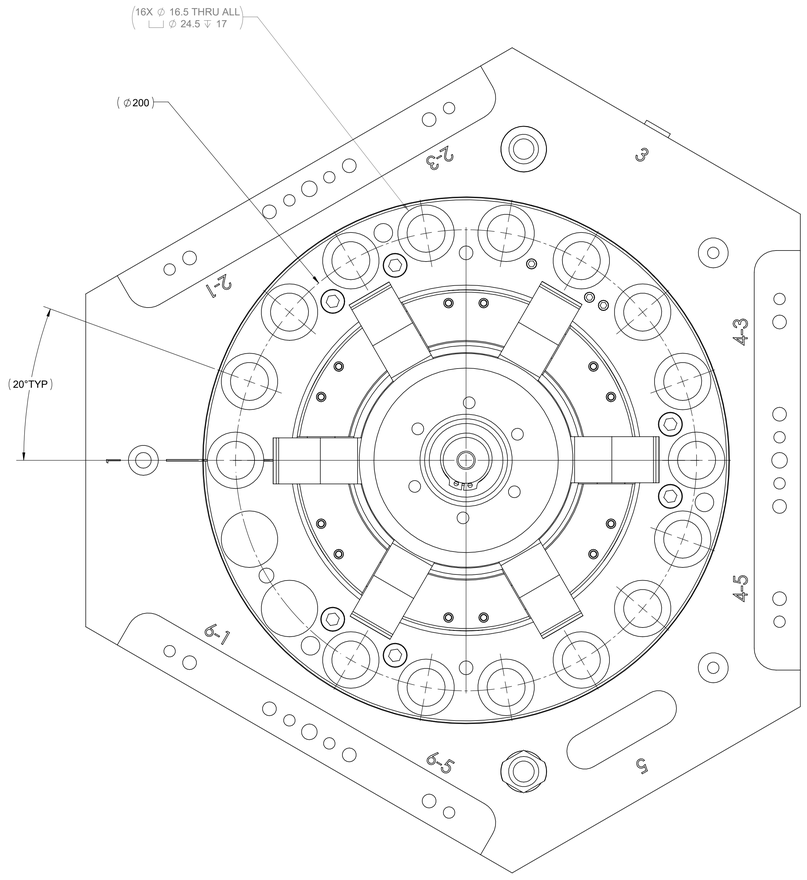
WEIGHT: 19.00 kg | RoHs COMPLIANT: - | SHT. 1 OF 2

PRINT DATE 12/22/2021

SIZE	DRAWING NUMBER	REV
E	2000189A	01







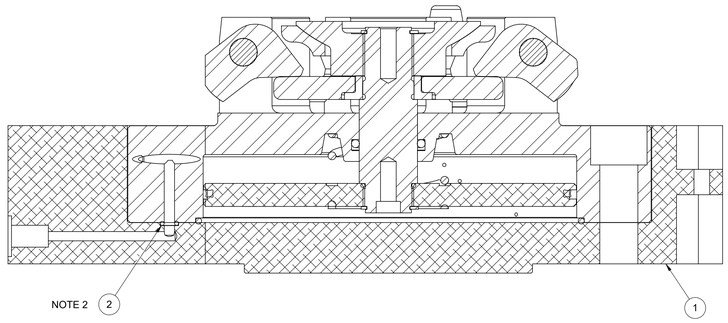
THIRD ANGLE PROJECTION	METRIC	DR: T. MARCELLA	Applied Robotics™ Solutions in reach
THE INFORMATION CONTAINED HERE IN IS THE SOLE PROPERTY OF APPLIED ROBOTICS INC. THE DOCUMENT FILE IS SUBJECT TO CHANGE WITHOUT NOTICE. APPLIED ROBOTICS MAKES NO WARRANTY OF ANY KIND WITH REGARD TO THIS DOCUMENT FILE, INCLUDING, BUT NOT LIMITED TO, THE WARRANTIES OR FITNESS FOR A PARTICULAR PURPOSE. APPLIED ROBOTICS INC. SHALL NOT BE LIABLE FOR ANY ERRORS CONTAINED HEREIN OR FOR INCIDENTAL OR CONSEQUENTIAL DAMAGES IN CONNECTION WITH THE PERFORMANCE OR USE OF THIS DOCUMENT FILE.	**UNLESS OTHERWISE SPECIFIED:** UNTOLERANCED DIMS ARE BASIC .25 A B C ⌖ ⌀ .25Ⓜ A B C ALL HOLE DIAMETERS +/- 0.25 INTERNAL RADIIS & BROKEN EDGES TO BE .13-.38 ALL SURFACE FINISHES 1.6Ra	CHK: SEE REV BLOCK ENG: T. MARCELLA MFG: M. DUDNATH QC: D. DITONNO 3D MODEL NUMBER: 2000189A	648 Saratoga Rd. Glenville, NY 12302 www.appliedrobotics.com
	MAT'L: Material <not specified>	SCALE: 1:2 DO NOT SCALE DRAWING	TITLE: ERS200ISO11-PNP-125-N-0-C0000 (PRESSURE SENSING) -
PRINT DATE 12/22/2021	DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994	SURFACE TREATMENT: NONE	ISO 9001 REGISTERED

SIZE	DRAWING NUMBER	REV
E	2000189A	01

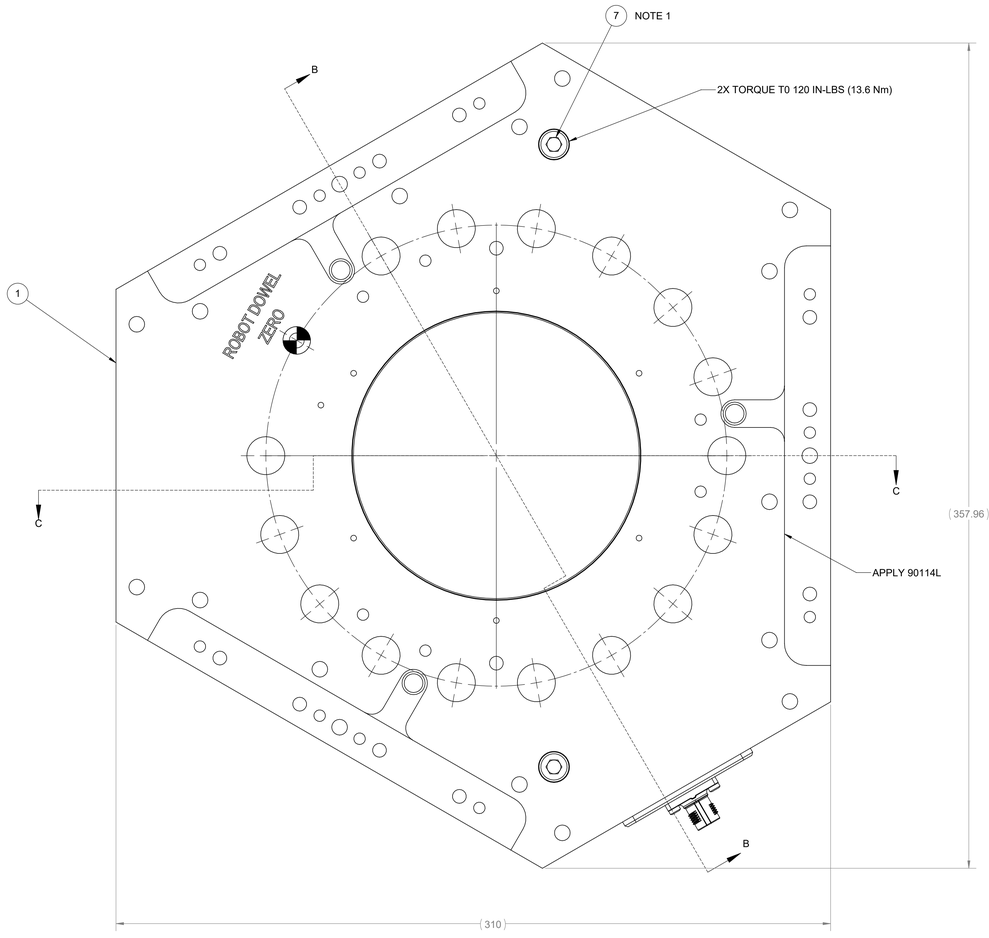
WEIGHT: 19.00 kg	RoHs COMPLIANT: -	SHT. 2 OF 2

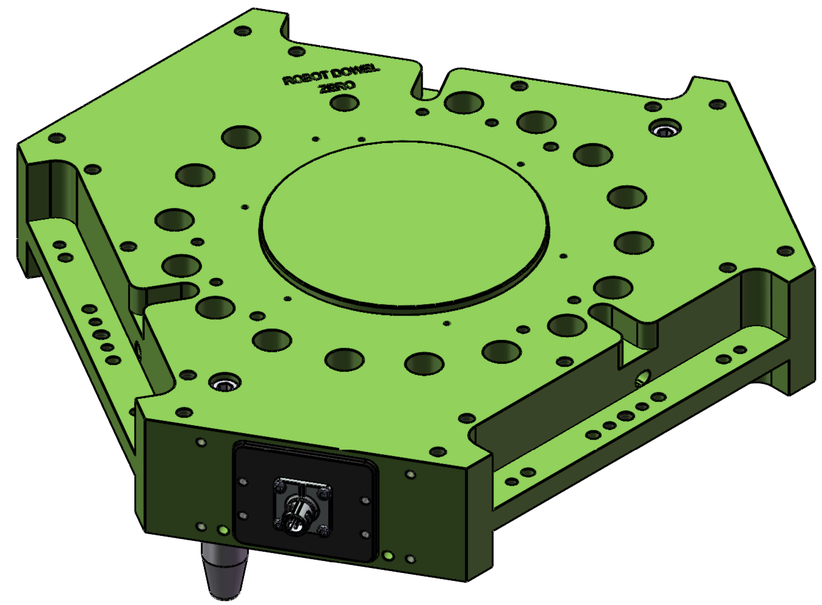
SIZE	DRAWING NUMBER	REV
E	2000190A	01

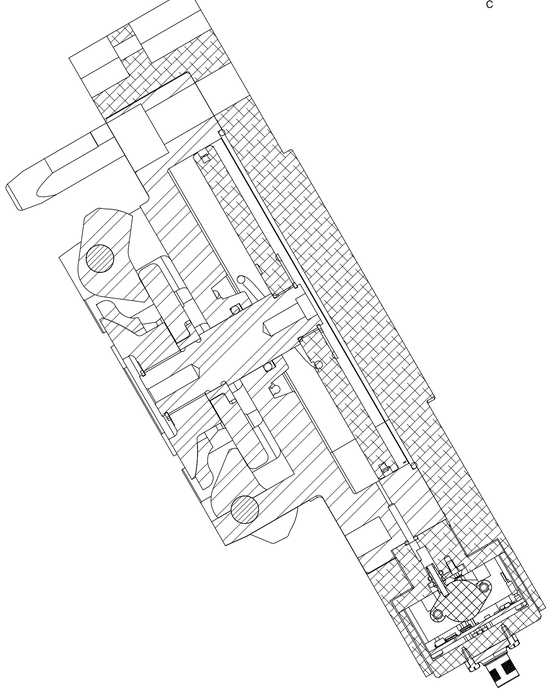
REVISIONS						
ZONE	REV	DESCRIPTION	DR	CHK	DATE	ECR/ESR NO.
	00	RELEASED FOR MANUFACTURE	TM	PS	3-27-20	DSCZ-BMUG4R
	01	DESCRIPTION WAS ERS200-PM12-125-N-0-C0000	PS	TM	12/15/2021	PSLI-C7YRYE



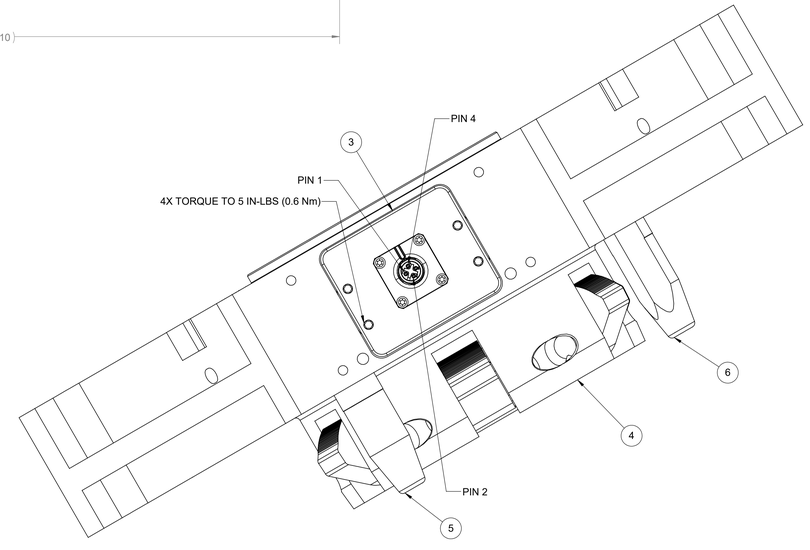
SECTION C-C
SCALE 1 : 1







SECTION B-B
SCALE 1 : 1



VIEW A-A
SCALE 1 : 1

NOTES:

1. APPLY LOCTITE 242, ARI #50106.
2. APPLY LUBE-A-CYL, ARI #51120.

ITEM NO.	QTY	PART NO.	DESCRIPTION
7	2	49045	SCR, SOC HD CAP M8 X 30 (STL)
6	1	0108-B06N	PIN, DIAMOND LOCATING S5R & S8R
5	1	0108-B05N	PIN, ROUND LOCATING S5R & S8R
4	1	1502-D01A	SUBASSY, SENDER ERS200
3	1	1800404A	SUBASSY, PS MOD., ER200
2	1	85551-P1008	O-RING, .176 ID X .07 75 VITON
1	1	1501-E83N	HOUSING, ROBOT ERS200

THIRD ANGLE PROJECTION

METRIC

UNLESS OTHERWISE SPECIFIED:

UNTOLERANCED DIMS ARE BASIC

.25 A B C

Ø .25M A B C

ALL HOLE DIAMETERS +/- 0.25

INTERNAL RADIS & BROKEN EDGES TO BE .13-.38

ALL SURFACE FINISHES 1.6Ra

MAT'L: Material <not specified>

SURFACE TREATMENT: NONE

DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994

DR:	T. MARCELLA
CHK:	SEE REV BLOCK
ENG:	T. MARCELLA
MFG:	M. DUDNATH
QC:	D. DITONNO

3D MODEL NUMBER: 2000190A

SCALE: 1:2

DO NOT SCALE DRAWING

ISO 9001 REGISTERED

Applied Robotics™ Solutions in reach
648 Saratoga Rd. Glenville, NY. 12302
www.appliedrobotics.com

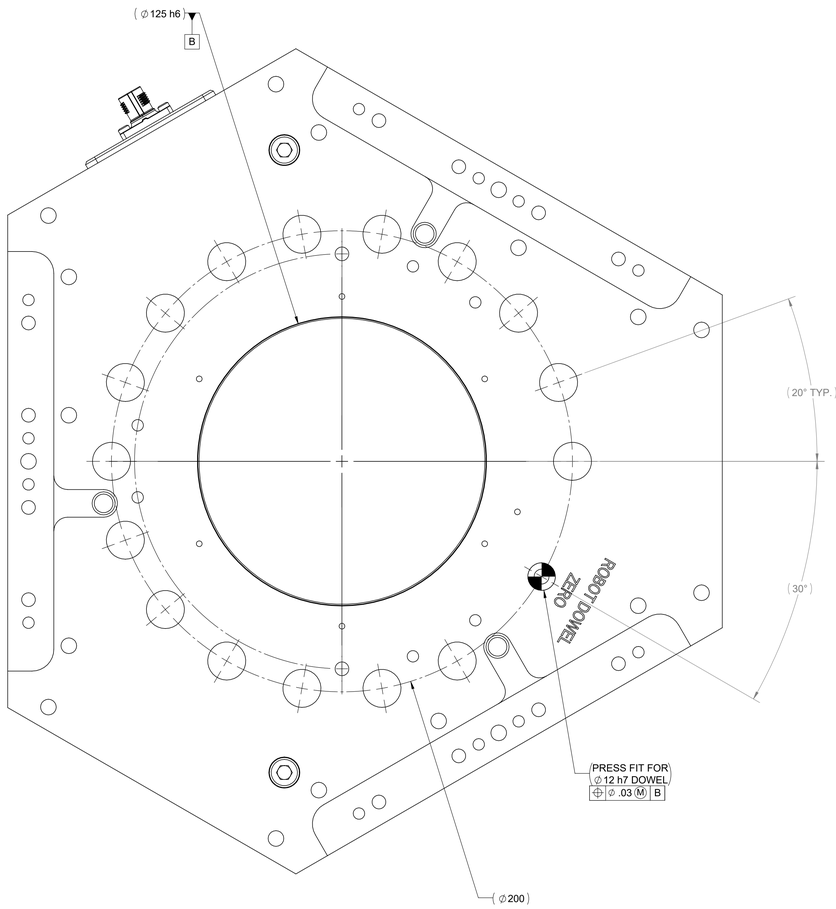
TITLE:
ERS200ISO11-PM12-125-N-0-C0000
(PRESSURE SENSING)

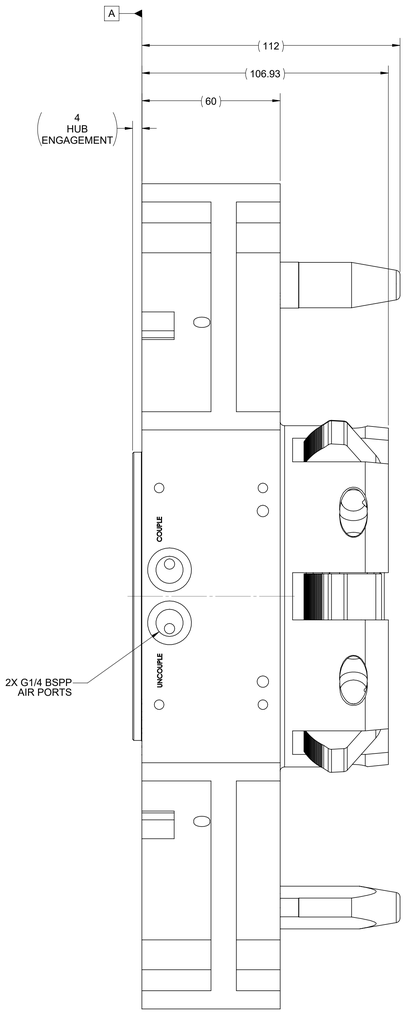
SIZE	DRAWING NUMBER	REV
E	2000190A	01

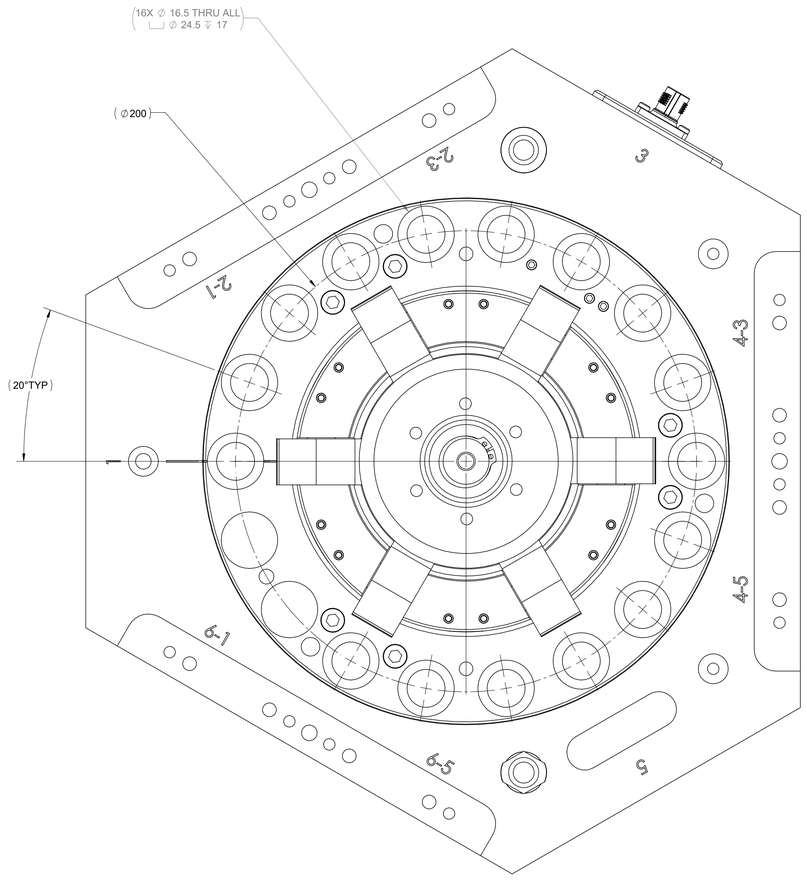
WEIGHT: 19.01 kg | RoHs COMPLIANT: - | SHT. 1 OF 2

PRINT DATE 12/22/2021

SIZE	DRAWING NUMBER	REV
E	2000190A	01







THIRD ANGLE PROJECTION

PRINT DATE
12/22/2021

METRIC

UNLESS OTHERWISE SPECIFIED:

UNTOLERANCED DIMS ARE BASIC

⌓ .25 A B C

⌖ ⌀ .25 M A B C

ALL HOLE DIAMETERS +/-0.25

INTERNAL RADIS & BROKEN EDGES TO BE .13-.38

ALL SURFACE FINISHES 1.6Ra

MAT'L:
Material <not specified>

SURFACE TREATMENT:
NONE

DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994

DR:	T. MARCELLA
CHK:	SEE REV BLOCK
ENG:	T. MARCELLA
MFG:	M. DUDNATH
QC:	D. DITONNO

3D MODEL NUMBER:
2000190A

SCALE: 1:2

DO NOT SCALE DRAWING

ISO 9001
REGISTERED

Applied Robotics™
Solutions in reach
648 Saratoga Rd. Glenville, NY. 12302
www.appliedrobotics.com

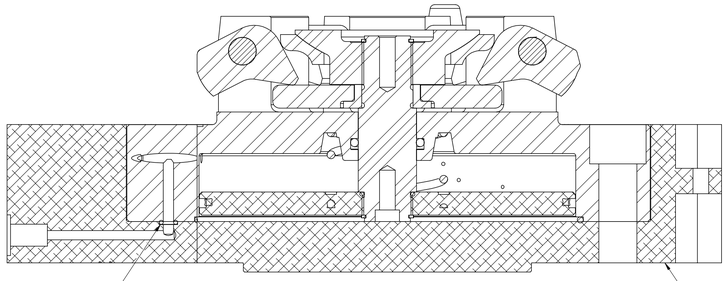
TITLE:
ERS200ISO11-PM12-125-N-0-C0000
(PRESSURE SENSING)
-

SIZE	DRAWING NUMBER	REV
E	2000190A	01

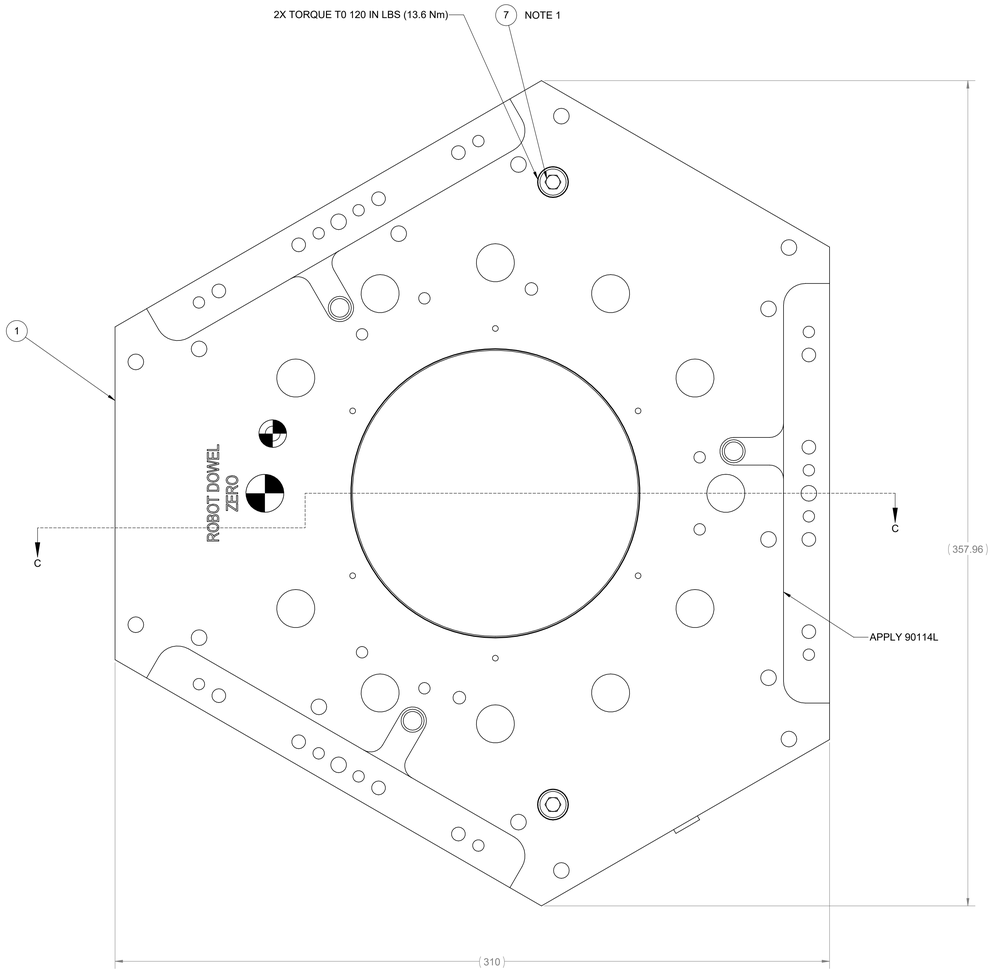
WEIGHT: 19.01 kg | RoHs COMPLIANT: - | SHT. 2 OF 2

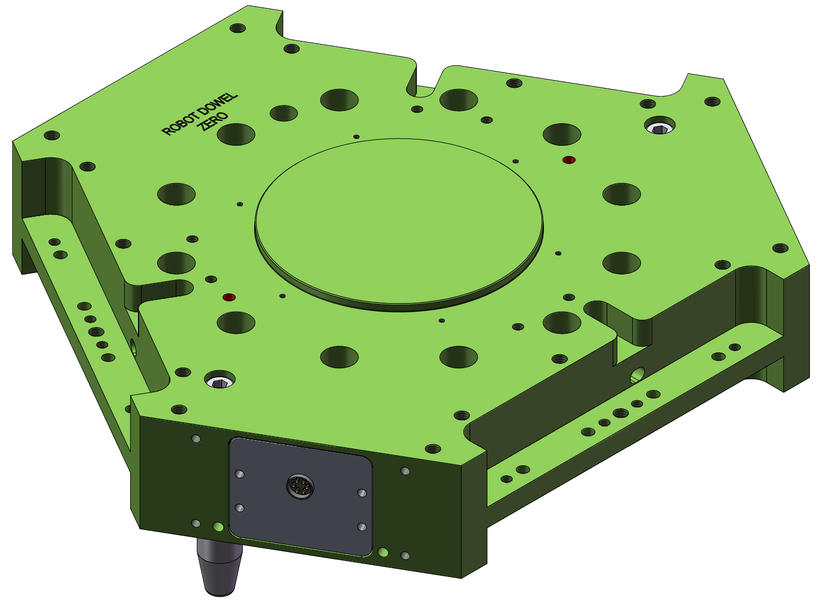
SIZE	DRAWING NUMBER	REV
E	2100728A	00

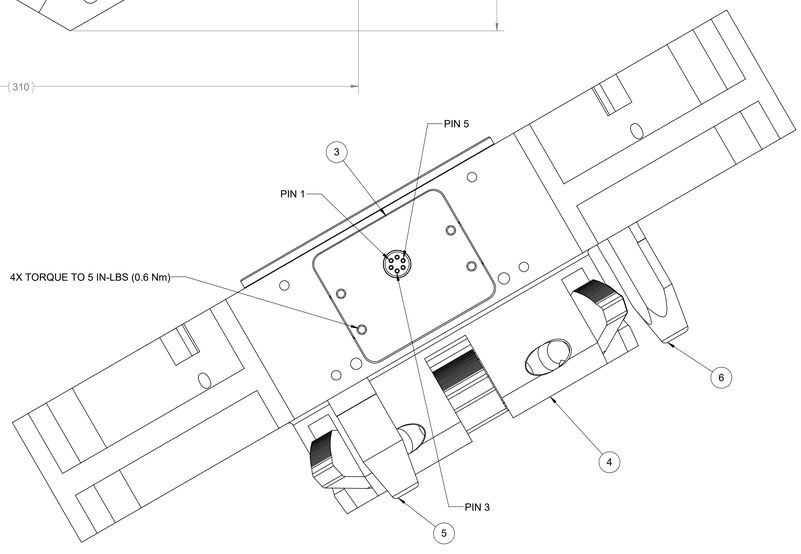
REVISIONS						
ZONE	REV	DESCRIPTION	DR	CHK	DATE	ECR/ESR NO.
	00	RELEASED FOR MANUFACTURE	PS	JV	10/29/2021	GPAI-C4VH2B



SECTION C-C
SCALE 1 : 1







VIEW A-A
SCALE 1 : 1

NOTES:

1. APPLY LOCTITE 242, ARI #50106.
2. APPLY LUBE-A-CYL, ARI #51120.

ITEM NO.	QTY	PART NO.	DESCRIPTION
7	2	49045	SCR, SOC HD CAP M8 X 30 (STL)
6	1	0108-B06N	PIN, DIAMOND LOCATING S5R & S8R
5	1	0108-B05N	PIN, ROUND LOCATING S5R & S8R
4	1	2100731A	SUBASSY, SENDER ERS200ISO12-PNP-125-N-0-C0000
3	1	1501-D59A	SUBASSY, PS MODULE, S5.3R
2	1	85551-P1008	O-RING, .176 ID X .07 75 VITON
1	1	2100729M	HOUSING, ERS200ISO12-PNP-125-N-0-C0000

THIRD ANGLE PROJECTION

METRIC

UNLESS OTHERWISE SPECIFIED:

UNTOLERANCED DIMS ARE BASIC

.25 A B C

⌀ .25M A B C

ALL HOLE DIAMETERS +/- 0.25

INTERNAL RADIUS & BROKEN EDGES TO BE .13-.38

ALL SURFACE FINISHES 1.6Ra

MAT'L:
Material <not specified>

SURFACE TREATMENT:

DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994

DR:	P. SLAVINSKI
CHK:	J. VALLELUNGA
ENG:	P. SLAVINSKI
MFG:	M. DUDNATH
QC:	M. DUDNATH

3D MODEL NUMBER:
2100728A

SCALE: 1:2
DO NOT SCALE DRAWING

ISO 9001 REGISTERED

PRINT DATE
12/22/2021

Applied Robotics™
Solutions in reach
648 Saratoga Rd. Glenville, NY 12302
www.appliedrobotics.com

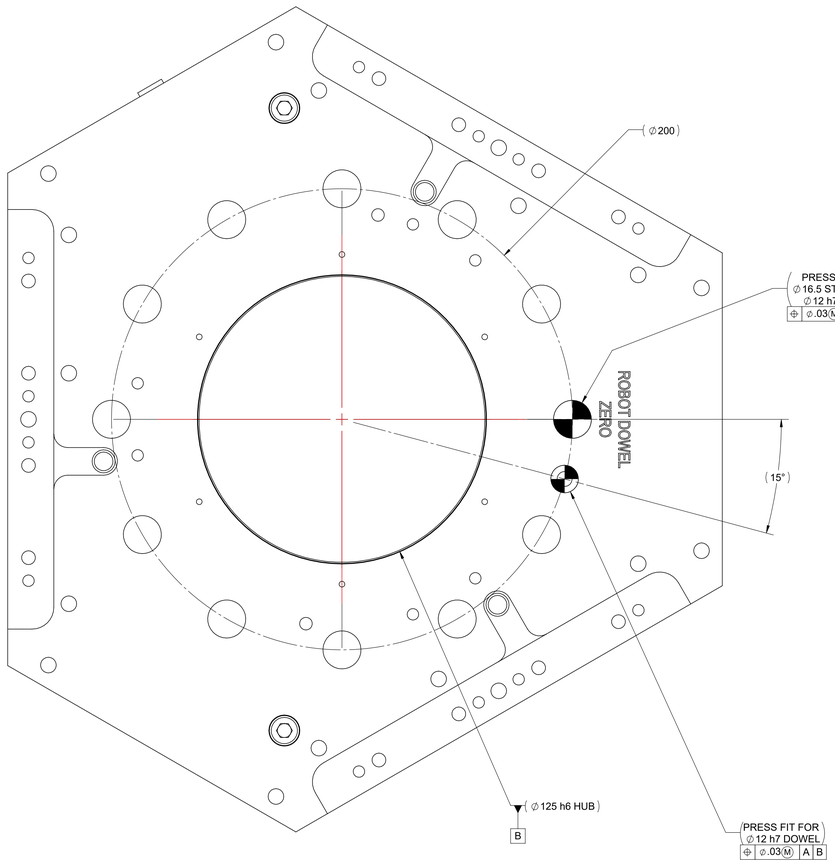
TITLE:

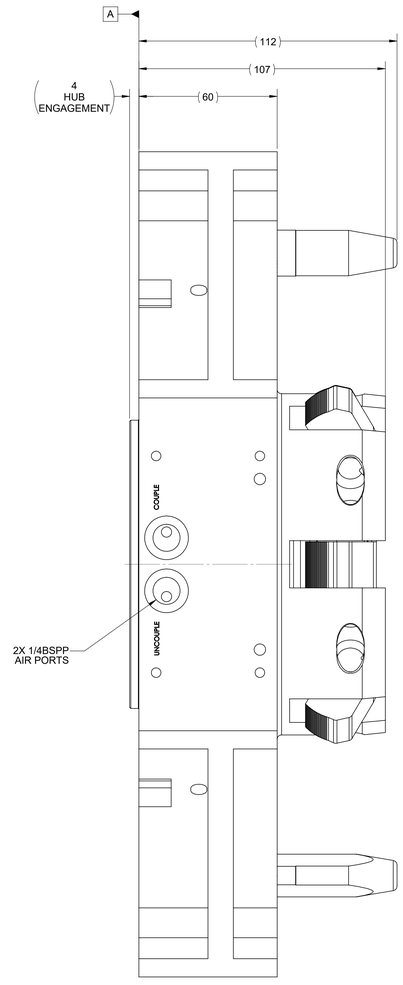
ERS200ISO12-PNP-125-N-0-C0000
(PRESSURE SENSING)
-

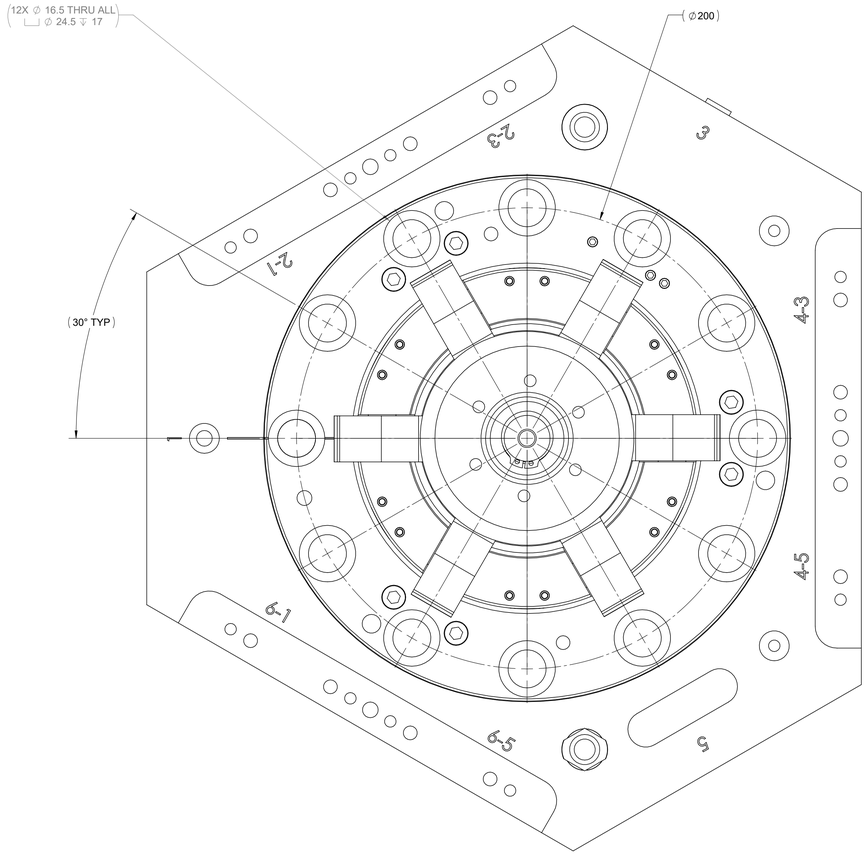
SIZE	DRAWING NUMBER	REV
E	2100728A	00

WEIGHT: 19.47 kg | RoHs COMPLIANT: - | SHT. 1 OF 2

SIZE	DRAWING NUMBER	REV
E	2100728A	00







THIRD ANGLE PROJECTION

PRINT DATE
12/22/2021

METRIC

UNLESS OTHERWISE SPECIFIED:

UNTOLERANCED DIMS ARE BASIC

⌓ .25 A B C

⌖ ⌀ .25Ⓜ A B C

ALL HOLE DIAMETERS +/- 0.25

INTERNAL RADIIS & BROKEN EDGES TO BE .13-.38

ALL SURFACE FINISHES 1.6Ra

MAT'L:
Material <not specified>

SURFACE TREATMENT:

DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994

DR:	P. SLAVINSKI
CHK:	J. VALLELUNGA
ENG:	P. SLAVINSKI
MFG:	M. DUDNATH
QC:	M. DUDNATH

3D MODEL NUMBER:
2100728A

SCALE: 1:2

DO NOT SCALE DRAWING

ISO 9001
REGISTERED

Applied Robotics™
Solutions in reach
648 Saratoga Rd. Glenville, NY. 12302
www.appliedrobotics.com

TITLE:

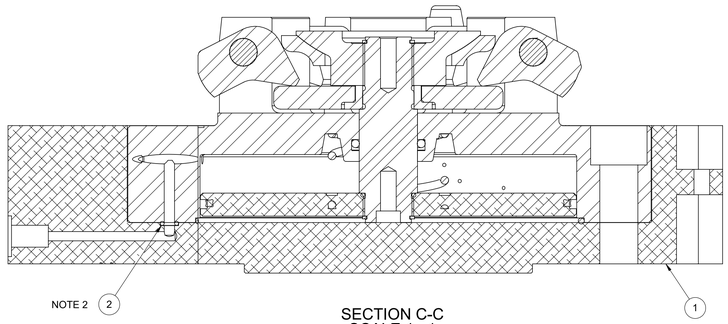
ERS200ISO12-PNP-125-N-0-C0000
(PRESSURE SENSING)
-

SIZE	DRAWING NUMBER	REV
E	2100728A	00

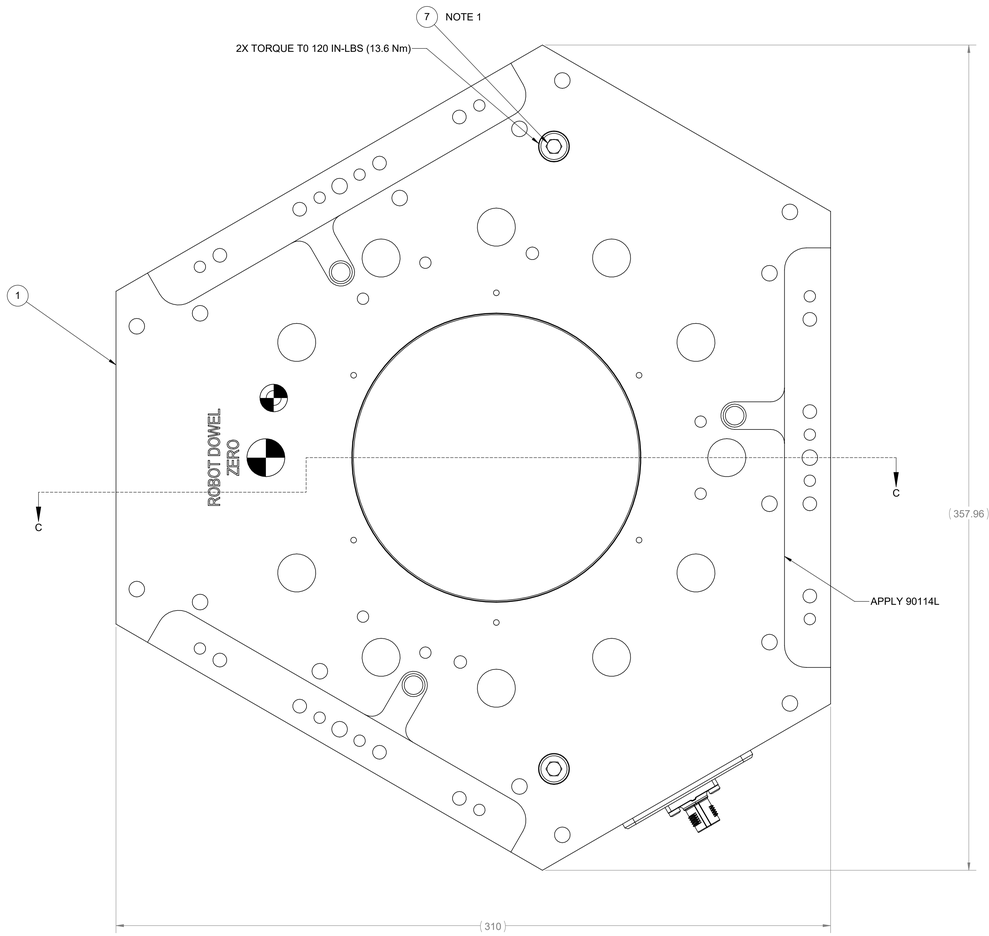
WEIGHT: 19.47 kg | RoHs COMPLIANT: - | SHT. 2 OF 2

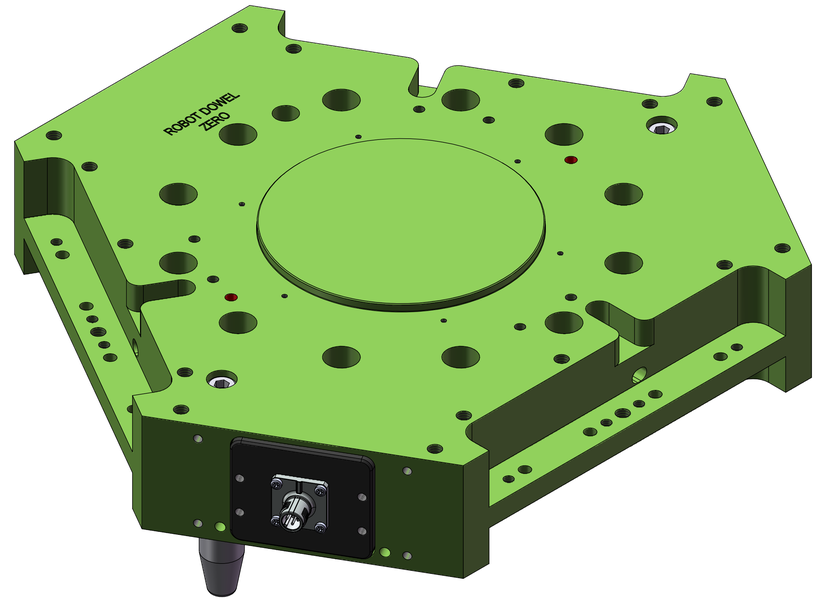
SIZE	DRAWING NUMBER	REV
E	2100810A	00

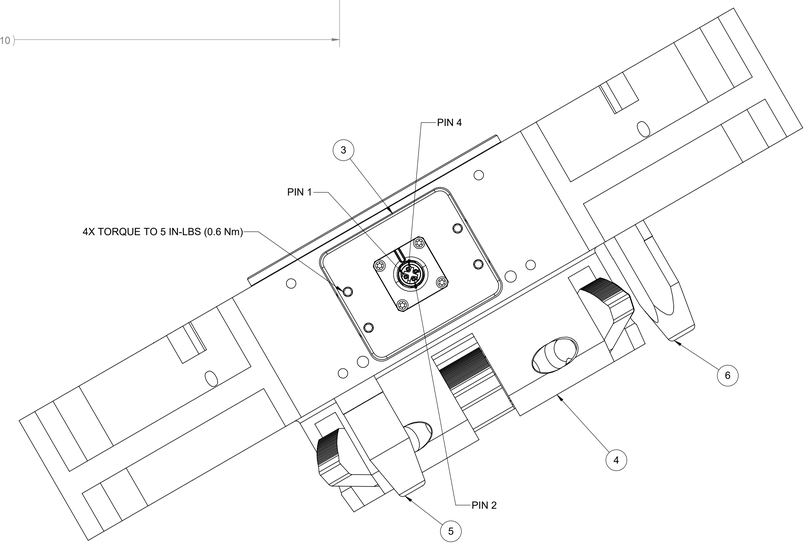
REVISIONS						
ZONE	REV	DESCRIPTION	DR	CHK	DATE	ECR/ESR NO.
	00	RELEASED FOR MANUFACTURE	PS	TM	12/08/2021	GPAI-C4VH2B



SECTION C-C
SCALE 1 : 1







VIEW A-A
SCALE 1 : 1

NOTES:

1. APPLY LOCTITE 242, ARI #50106.
2. APPLY LUBE-A-CYL, ARI #51120.

ITEM NO.	QTY	PART NO.	DESCRIPTION
7	2	49045	SCR, SOC HD CAP M8 X 30 (STL)
6	1	0108-B06N	PIN, DIAMOND LOCATING S5R & S8R
5	1	0108-B05N	PIN, ROUND LOCATING S5R & S8R
4	1	2100731A	SUBASSY, SENDER ERS200ISO12-PNP-125-N-0-C0000
3	1	1800404A	SUBASSY, PS MOD., ER200
2	1	85551-P1008	O-RING, .176 ID X .07 75 VITON
1	1	2100729M	HOUSING, ERS200ISO12-PNP-125-N-0-C0000

THIRD ANGLE PROJECTION

METRIC

UNLESS OTHERWISE SPECIFIED:

UNTOLERANCED DIMS ARE BASIC

.25 A B C

⌀ .25Ⓜ A B C

ALL HOLE DIAMETERS +/- 0.25

INTERNAL RADIUS & BROKEN EDGES TO BE .13-.38

ALL SURFACE FINISHES 1.6Ra

MAT'L:
Material <not specified>

SURFACE TREATMENT:

DR:	P. SLAVINSKI
CHK:	T. MARCELLA
ENG:	P. SLAVINSKI
MFG:	M. DUDNATH
QC:	M. DUDNATH

3D MODEL NUMBER:
2100810A

SCALE: 1:2

DO NOT SCALE DRAWING

ISO 9001 REGISTERED

Applied Robotics™ Solutions in reach
648 Saratoga Rd. Glenville, NY 12302
www.appliedrobotics.com

TITLE:

ERS200ISO12-PM12-125-N-0-C0000
(PRESSURE SENSING)
-

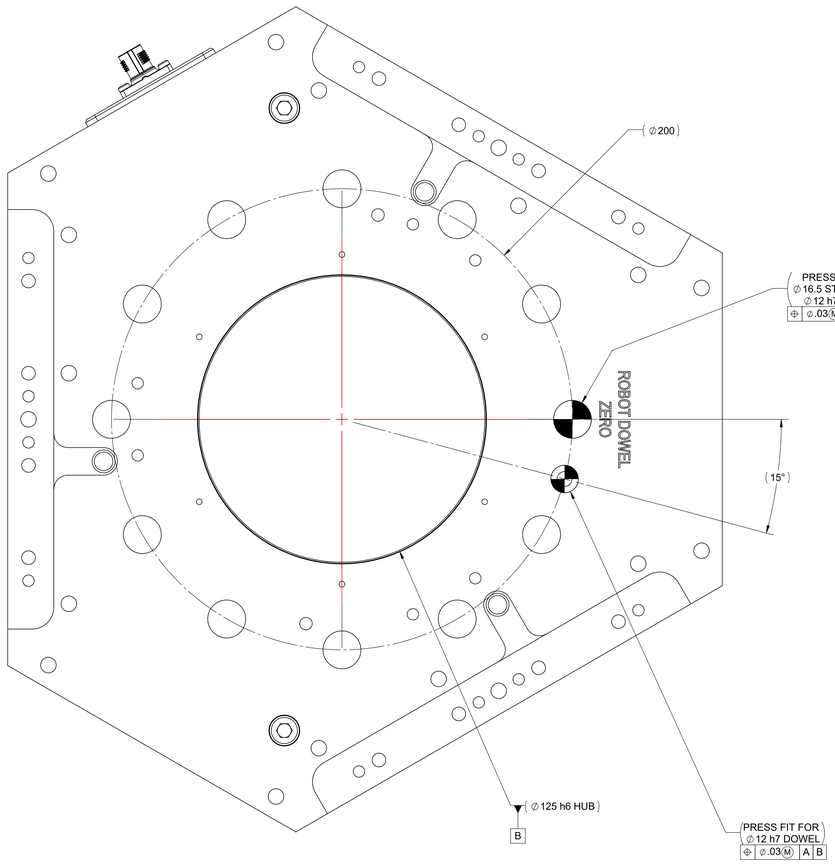
SIZE	DRAWING NUMBER	REV
E	2100810A	00

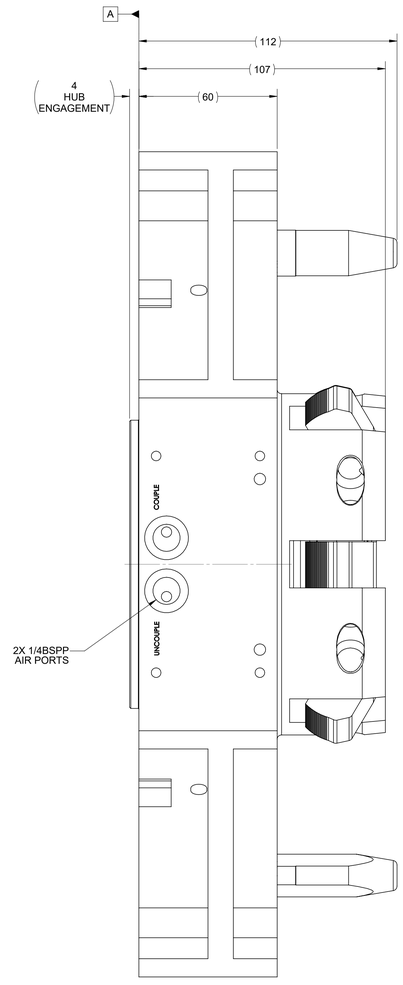
WEIGHT: 19.48 kg | RoHs COMPLIANT: - | SHT. 1 OF 2

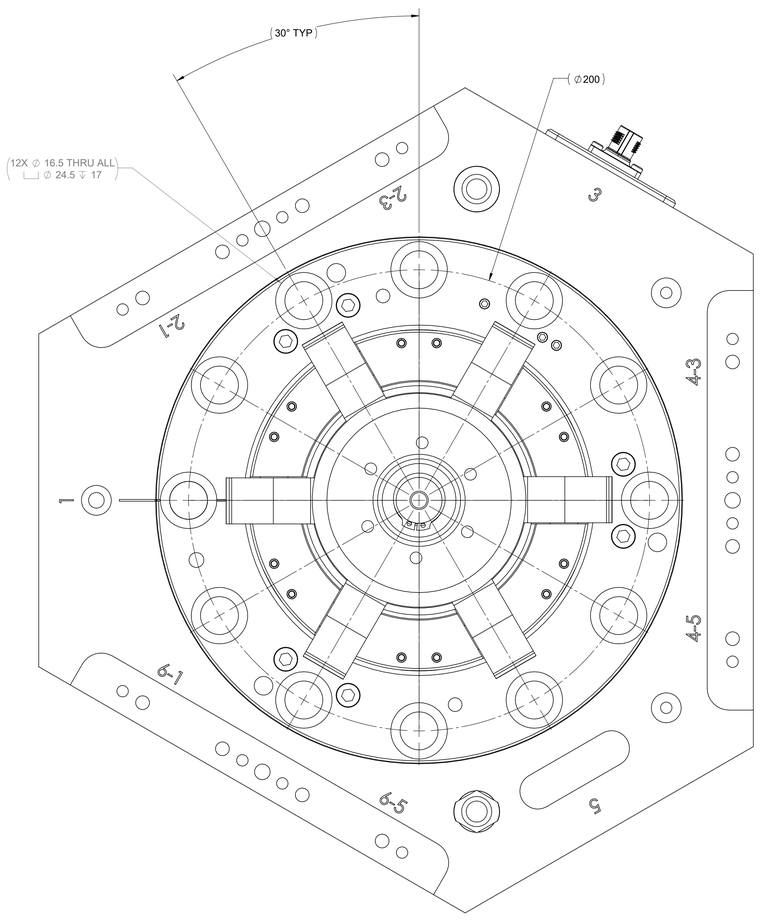
PRINT DATE
12/22/2021

DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994

SIZE	DRAWING NUMBER	REV
E	2100810A	00







THIRD ANGLE PROJECTION

PRINT DATE
12/22/2021

METRIC

UNLESS OTHERWISE SPECIFIED:

UNTOLERANCED DIMS ARE BASIC

⌓ .25 A B C

⌖ ⌀ .25Ⓜ A B C

ALL HOLE DIAMETERS +/- 0.25

INTERNAL RADIIS & BROKEN EDGES TO BE .13-.38

ALL SURFACE FINISHES 1.6Ra

MAT'L:
Material <not specified>

SURFACE TREATMENT:

DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994

DR:	P. SLAVINSKI
CHK:	T. MARCELLA
ENG:	P. SLAVINSKI
MFG:	M. DUDNATH
QC:	M. DUDNATH

3D MODEL NUMBER:
2100810A

SCALE: 1:2

DO NOT SCALE DRAWING

ISO 9001
REGISTERED

Applied Robotics™
Solutions in reach
648 Saratoga Rd. Glenville, NY. 12302
www.appliedrobotics.com

TITLE:

ERS200ISO12-PM12-125-N-0-C0000 (PRESSURE SENSING)

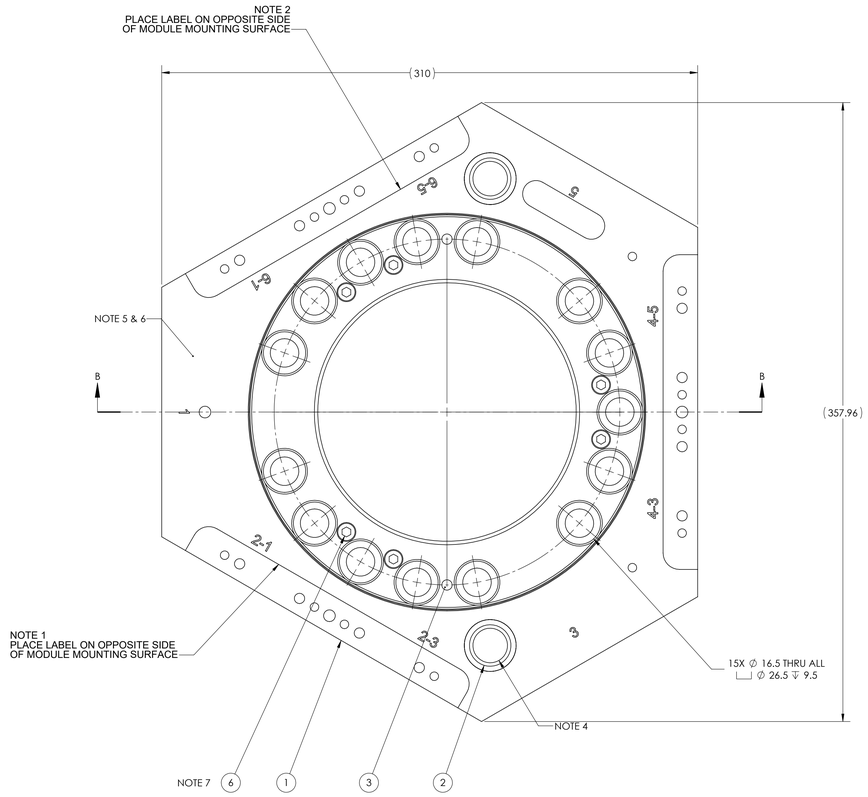
-

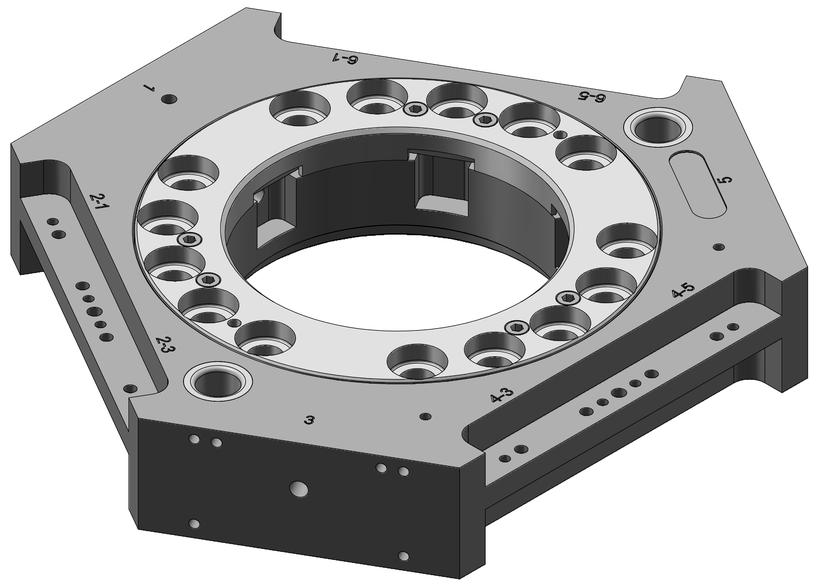
SIZE	DRAWING NUMBER	REV
E	2100810A	00

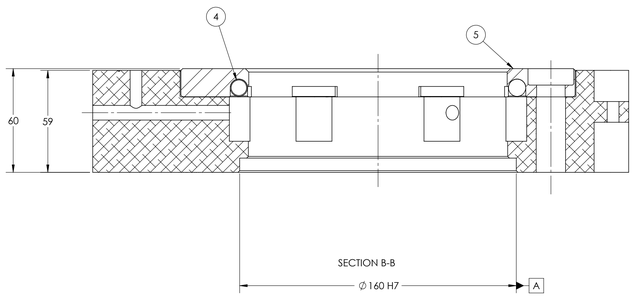
WEIGHT: 19.48 kg | RoHs COMPLIANT: - | SHT. 2 OF 2

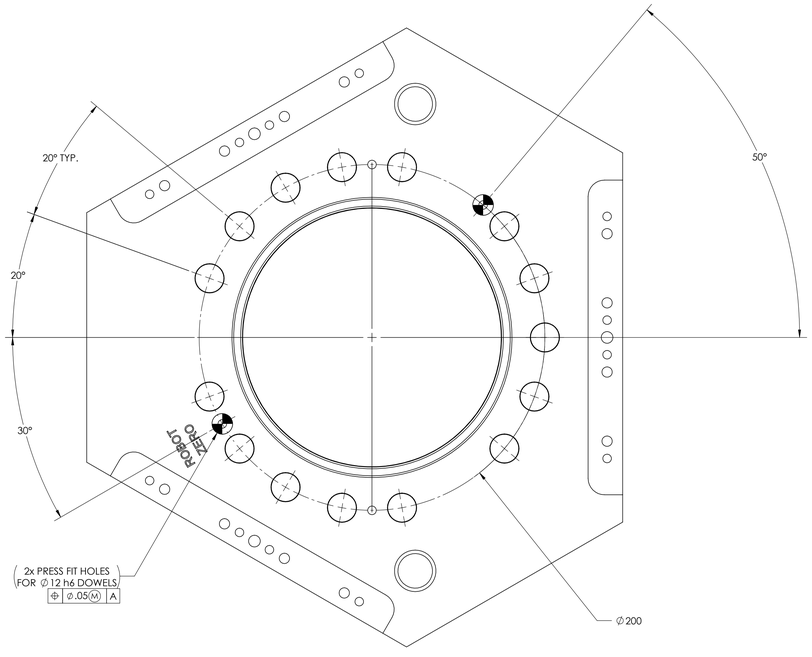
SIZE	DRAWING NUMBER	REV
E	1501-E98A	01

REVISIONS						
ZONE	REV	DESCRIPTION	DR	CHK	DATE	ECR/ESR NO.
	00	RELEASE TO MANUFACTURE	TM	JV	4/3/2015	JVAA-9TLLJN
	01	ADDED TEACHING	TM	PS	06/10/19	TMAA-BA6GET









NOTES:
1. APPLY LABEL (ARI P/N 90114L).
2. APPLY 90994 ADDRESS LABEL.
3. CUSTOMER TO INSTALL BOLTS AND DOWEL(S) USING SUPPLIED BOLT KIT.
4. APPLY GREASE (ARI P/N 91504-P1037) TO BEARING SURFACES ON ITEM 2.
5. APPLY LABEL (ARI P/N 0708-P74N).
6. APPLY LABEL (ARI P/N 0708-P75N).
7. APPLY LOCTITE 242 (ARI P/N 50106).

SCREW TORQUE CHART	
SIZE	TORQUE
M5	4.5 ft-lbs (6.1 N-m)
M6	7.7 ft-lbs (10.4 N-m)
M8	19.0 ft-lbs (25.7 N-m)
M10	37.0 ft-lbs (50.1 N-m)
M12	65.0 ft-lbs (88.1 N-m)

ITEM NO.	QTY	PART NO.	DESCRIPTION
6	6	48038	SCR, SOC HD CAP M6 X 20 (SS)
5	1	1502-D12N	RING, TOOL ETS200
4	6	49382	DOWEL, M10 X 40 (HARD STL) M6
3	2	91500-P1038	DOWEL, M8 X 14 (HD STL), M6
2	2	0105-P85N	BUSHING, LOCATING S5.1
1	1	1502-D10N	HOUSING, TOOL ETS200

THIRD ANGLE PROJECTION

METRIC

UNLESS OTHERWISE SPECIFIED:

UNTOLERANCED DIMS ARE BASIC

.25 A B C

⌖ ∅.25Ⓜ A B C

ALL HOLE DIAMETERS +/-.0.25

INTERNAL RADIUS & BROKEN EDGES TO BE .13-.38

ALL SURFACE FINISHES 1.6Ra

MAT'L: Material <not specified>

SURFACE TREATMENT: -

DIM. AND TOLERANCING IN ACCORDANCE WITH ANSI Y14.5M-1994

DR:	T. MARCELLA
CHK:	J. VALLELUNGA
ENG:	T. MARCELLA
MFG:	C. BEST
QC:	M. DUDNATH

3D MODEL NUMBER: 1501-E98A

SCALE: 3:4

DO NOT SCALE DRAWING

ISO 9001 REGISTERED

PRINT DATE 3/8/2023

Applied Robotics™ Solutions in reach
648 Saratoga Rd. Glenville, NY 12302
www.appliedrobotics.com

TITLE:

ETS200-160-N-C0000 TOOL ADAPTER ASSEMBLY -

SIZE	DRAWING NUMBER	REV
E	1501-E98A	01

WEIGHT: 9.42 kg | RoHs COMPLIANT: - | SHT. 1 OF 1