

CR30 Series Hardware User Guide

SHENZHEN DOBOT CORP
Original Instructions

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Before using our product, please thoroughly read and understand the contents of this document and related technical documents that are published online, to ensure that the robot is used on the premise of fully understanding the robot and related knowledge. Please use this document with technical guidance from professionals. Even if follow this document or any other related instructions, damages or losses may happen in the using process. Dobot shall not be considered as a guarantee regarding all security information contained in this document.

The user has the responsibility to make sure following the relevant practical laws and regulations of the country, in order that there is no significant danger in the use of the robot.

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Preface

This document describes the installation instructions of Dobot CR30 series robot, making it easy for users to fully understand and use it.

Important safety notice

The robot is a **semi-finished machinery**, so a risk assessment must be conducted after each installation. Please strictly adhere to all safety regulations outlined in Chapter 1.

Intended audience

This document is intended for:

- Customer
- Sales Engineer
- Installation and Commissioning Engineer
- Technical Support Engineer

Related documents

Document	Description	Download link
DobotStudio Pro User Guide	Explains how to use the robot control software, DobotStudio Pro.	Visit Dobot official website, click “Support > Download Center”, and search by document name or filter by product series.
Dobot TCP_IP Remote Control Interface Guide	Describes how to use the secondary development interface based on TCP/IP protocol. In addition to the document, you can also access multi-language development DEMOs from Github .	
Dobot Bus Communication Protocol Guide (EtherNetIP_Profinet)	Introduces the usage of the robot's bus communication functions (EtherNetIP/Profinet).	
Dobot Cobot Teach Pendant User Guide	Explains how to use the Teach Pendant that accompanies the collaborative robot.	
Dobot VX500 Smart Camera User Guide	Explains how to use the VX500 Smart Camera that accompanies the CRA series robot.	

Revision history

Date	Version	Revision history
2025/06/26	V1.0	The first release

Symbol conventions

The symbols that may be found in this document are defined as follows.

Symbol	Description
 DANGER	Indicates a hazard with a high level of risk which, if not avoided, could result in death or serious injury.
 WARNING	Indicates a hazard with a medium level or low level of risk which, if not avoided, could result in minor or moderate injury, robot arm damage.
 NOTICE	Indicates a potentially hazardous situation which, if not avoided, could result in robot arm damage, data loss, or unanticipated result.
 NOTE	Provides additional information to emphasize or supplement important points in the main text

Contents

Preface	ii
Important safety notice	ii
Intended audience	ii
Related documents	ii
Revision history	ii
Symbol conventions	iii
1. Safety	1
1.1 Responsibility	1
1.1.1 Responsibility and norms	1
1.1.2 Limitation of liability	1
1.2 Intended use	1
1.3 Risk assessment	1
1.4 Pre-use assessment	2
1.5 Safety warning sign	4
1.6 General safety	4
1.7 Personal safety	8
1.8 Residual risks	9
1.9 Emergencies	10
1.9.1 Emergency stop device	10
1.9.2 Emergency recovery	10
1.9.3 Personnel rescue in emergency situations	10
2. Transportation	12
2.1 Transportation precautions	12
2.2 Unpackaged handling	12
3. Installation and Use	13
3.1 Installation environment	13
3.2 Unpacking	13
3.3 Robot installation	13
3.3.1 Installation platform requirements	13
3.3.2 Robot arm installation	14
3.3.3 Controller installation	17
3.3.4 Tool installation	18
3.4 Cable connection	18
3.5 Power-on and debugging	19

1. Safety

1.1 Responsibility

1.1.1 Responsibility and norms

The information in this document does not cover designing, installing and operating a complete robot system, nor does it cover all peripheral equipment that may affect the safety of the complete system. The complete system must be designed and installed in accordance with the safety requirements set forth in the standards and regulations of the country where the robot is installed.

The integrators of Dobot are responsible for ensuring that the applicable safety laws and regulations in the country concerned are observed and that any significant hazards in the complete robot application are eliminated. This includes, but is not limited to:

- Performing a risk assessment for the complete robot system.
- Adding safety machines and mechanisms based on the risk assessment, including but not limited to building a proper safety circuit to achieve safe stop.
- Setting up the appropriate safety settings in the software.
- Ensuring that the user will not modify any safety measures.
- Validating that the total robot system is designed and installed correctly.
- Specifying instructions for use.
- Marking relevant signs and contact information of the integrators on the robot.
- Archiving relevant technical files.

1.1.2 Limitation of liability

Any safety information provided in this document should not be considered as a warranty from Dobot. The robot may cause injury or damage even if all safety instructions are observed.

1.2 Intended use

Dobot CR30 series robots are collaborative robots only for general industrial use, such as processing or delivering products or parts through end tools.

Dobot CR30 series robots are equipped with special safety mechanisms including collision detection. These mechanisms are purposely designed for human-robot collaboration, but only intended for non-hazardous applications after risk assessment, where tools, products, environment and other machines have been demonstrated to be incapable of significant risk through application-specific risk assessments.

Any use or application deviating from intended use is deemed to be impermissible misuse, including, but is not limited to:

- Use in potentially explosive environments.
- Use in vacuum environments.
- Use for transporting people or animals.
- Use in life-critical applications.
- Use before performing a risk assessment.
- Use over-stated specifications.
- Use as a climbing aid.

1.3 Risk assessment

As the robot is a **semi-finished machinery**, the integrator is responsible for conducting a risk assessment of the overall system after integration. It is recommended that integrators perform a risk assessment based on ISO 12100 and ISO 10218-2 and refer

to the Technical Specification ISO/TS 15066 for integration guidance.

The risk assessment should consider all workflows during the robot's entire lifecycle, including but not limited to:

- Teaching the robot during the setup and development process.
- Maintenance and repairs.
- Robot installation.

The risk assessment must be completed **before the robot is powered on for the first time**, including but not limited to confirming the safety function settings and evaluating whether additional emergency stop buttons or other protective measures are required.

When performing the risk assessment, the integrator should focus on the following safety functions:

- Collision detection sensitivity settings: Limiting the force applied during a collision between the robot and the operator.
- Robot and tool pose limitations: Reducing the risk of the robot and tools colliding with the operator, especially in specific body areas such as the head and neck.
- Speed limit: Limiting the robot's operating speed to reduce safety risks.

The integrator must set permissions and passwords to prevent unauthorized personnel from modifying the safety function configurations.

When conducting a risk assessment for collaborative robot applications, the integrator must consider potential collision risks caused by human error, including:

- The severity of potential collisions.
- The probability of potential collisions.
- The likelihood of avoiding potential collisions.

If the robot is installed in a non-collaborative application where its built-in safety functions cannot effectively eliminate safety risks (e.g., using hazardous tools), the integrator must consider adding additional protective measures (e.g., safety barriers or safety lasers) during the risk assessment.

The integrator must consider potential risks including but not limited to:

1. Cuts from sharp edges and points on the end tools or end effector connectors.
2. Cuts from sharp edges and points on obstacles in or near the robot's workspace.
3. Scrapes caused by contact with the robot.
4. Sprains or fractures resulting from collisions between heavy payloads on the robot's end and hard surfaces.
5. Consequences of loose bolts securing the robot or end tool.
6. Consequences of items falling off the end tool.
7. Consequences of incorrectly pressing the emergency stop button of other equipment.
8. Consequences of unauthorized changes to the safety function configurations.

1.4 Pre-use assessment

Before using the robot for the first time or after any modifications are made, testing must be conducted to ensure that all safety inputs and outputs are correctly connected and functioning properly:

1. Test whether the emergency stop button on the teach pendant and user emergency stop input can trigger an emergency stop.
2. Test whether the protective stop input can halt the robot's motion. If a protective stop reset input is configured, test whether this input must be activated before the robot can resume operation.
3. If a reduced mode input is configured, test whether this input can switch the robot to reduced mode (reduced-speed operation).

4. If the teach pendant is equipped with three-position enabling switch, test whether the robot can only be enabled when the three-position switch is in the center position in manual mode.
5. Test whether the system connected to the emergency stop status output can detect the output change and respond accordingly.
6. If other safety outputs are configured, test whether the system connected to the corresponding output can detect the output change and respond accordingly.

1.5 Safety warning sign

The following safety warning signs may appear on the product, and their meanings are as follows:

Sign	Description
 DANGER	Indicates a high potential hazard that, if not avoided, could result in death or serious injury.
 ELECTRICITY	Indicates a potentially dangerous electrical situation that, if not avoided, could result in injury, death, or serious damage to the equipment.
 HOT 	Indicates a potentially dangerous hot surface that, if touched, could result in personnel injury.
 WARNING	Indicates a moderate or low potential hazard that, if not avoided, could result in minor personal injury and damage to the equipment.
 NOTICE	Indicates a potential risk that, if ignored, could result in robot arm damage, data loss, or unpredictable result.
 NOTICE	Indicates a situation that, if not avoided, could result in personnel injury or damage to the equipment. For items marked with such signs, depending on the specific situation, there is sometimes a possibility of significant consequences

1.6 General safety

Follow the safety instructions below when starting and using the robot for the first time.



DANGER

- The robot control system is an electrically powered device. Non-professionals should not modify the circuit, otherwise, it may result in robot damage or personal injury.
- Strictly comply with local laws and regulations when operating the robot. The safety precautions described in this document serve only as a supplement to local safety standards.
- Use the robot within the specified environmental conditions. Operating beyond the rated specifications and load conditions may shorten the robot's lifespan or even damage it.
- Ensure that the robot is operated under safe conditions and there is no harmful object around the robot.
- Avoid frequently powering the robot on and off, as this may degrade the performance of the main circuit components inside. If repeated power cycling is necessary, limit it to no more than once per minute.

 HOT

- The robot and controller generate heat during operation. Do not operate or touch the robot while it is running or immediately after it stops.
- Turn off the power and wait one hour for the robot to cool down.
- Do not place your fingers on the heat generating area of the controller.

 WARNING

- Wear anti-static clothing and anti-static gloves before operating the equipment.
- It is prohibited to modify or remove the nameplate, instructions, icons, or labels on the equipment.
- Before operating the equipment, locate and be familiar with the emergency stop function to ensure that the robot can be stopped urgently in case of an emergency. The emergency stop function is classified as a Stop Category 1.
- Be careful when handling or installing the robot. Follow the instructions on the packaging box, place the robot gently, and position it according to the arrow markings to prevent damage.
- To ensure device and personal safety, use supplied cables.
- Make sure that both the robot and the tools are correctly and securely installed.
- Make sure that the robot has sufficient space to move freely.
- Do not continue using the robot if it is damaged.
- Any impact will release a large amount of kinetic energy, which can be much higher than during high-speed or high-load operations.

 NOTICE

- Personnel responsible for installing, operating, and maintaining the equipment must undergo rigorous training, fully understand all safety precautions, and master proper operation and maintenance procedures before handling the equipment.
- Unauthorized personnel without professional training must not disassemble or repair the equipment. In case of a malfunction, contact Dobot's technical support engineer in time.
- Perform daily inspections and periodic maintenance, replacing faulty components promptly to ensure the safe operation of the equipment.
- If the equipment is scrapped, please comply with the relevant laws for the proper disposal of industrial waste to protect the environment.
- Establish safety measures (e.g., fences, ropes, or warning lines) near the robot's operating area to ensure that personnel stay out of the robot's reach while it is in operation or about to start.
- Do not enter the robot's safety zone defined by the risk assessment or touch the robot while the system is running.
- Do not expose the robot to a permanent magnetic field, as strong magnetic fields can cause damage.

 NOTICE

- Handling operations using lifting rings, cranes, or similar equipment must be conducted using appropriate and reliable lifting devices, and must be carried out by qualified personnel or those authorized by the company in accordance with local regulations.
- Make sure that there are no obstacles within 2 meters of the robot during the transportation, and personnel should stay away from the suspended robot.
- Dobot is not responsible for any damage caused during the transportation and handling of the equipment.
- Make sure that the robot is in the packing posture before packaging, and the brakes on each axis are normal.
- Make sure that the packing area is free of obstacles to allow staff to evacuate quickly in case of emergencies.
- Secure the packaging firmly during transport to keep the robot stable.
- After removing the outer packaging, make sure that the robot maintains its original packing posture and the brakes on each axis are normal.
- Make sure that the unpacking area is free of obstacles to allow staff to evacuate quickly in case of emergencies.
- During debugging, make sure that no personnel or other equipment (including computer used for debugging) is present in the hazardous area of the machine.
- Wear appropriate personal protective equipment when necessary, such as safety helmets, safety shoes (with non-slip soles), face shields, safety goggles, and gloves. Inappropriate clothing may cause personal injury.
- Do not enter the robot's workspace while the robot is operating, as this may result in injury to the robot or operator.
- If an abnormality occurs with the robot, ensure that the system is stopped before conducting an inspection.
- After debugging, operators must first test the system in manual mode. Once this is confirmed to be correct, switch to automatic operation.
- All suspended safety configurations should be restored to their full functionality before selecting the automatic operation mode.
- If the controller needs to be restarted due to a power failure, the robot must be manually returned to the initial position of the automatic operation program before restarting automatic operation.
- Before performing maintenance, inspection, or wiring work, the power supply must be completely cut off, and a "No power supply" sign must be posted. Failure to do so may result in electric shock or personal injury.
- Observe ESD (Electrostatic Discharge) regulations when disassembling the robot or controller.
- Avoid disassembling the power supply system inside the controller. Even after the controller is turned off, high voltage may remain for several hours.
- For disassembly and repair of the robot, contact Dobot's technical support engineer.
- Maintenance and repair work must be carried out by designated personnel, otherwise electric shock or personal injury may result.
- If the brake is manually released, the robot may move due to gravity. Therefore, when manually releasing the brake, ensure proper support for the robot and any attached tools or workpieces.

 NOTICE

- If the power supply must be turned on while the controller door is open for maintenance or inspection, avoid direct exposure of the controller interior to strong light sources such as sunlight or spotlights, as this may cause malfunctions or errors.
- To prevent electric shock, turn off the circuit breaker and disconnect the main power before replacing any components.
- Wait at least five minutes after disconnecting the main power before replacing components.
- Component replacement must be performed by authorized personnel.
- The robot is designed and tested according to industrial, scientific, and medical (ISM) equipment standards. In household and light industrial environments, the robot may cause radio interference, requiring protective measures.
- Do not operate the robot near strong radiation sources (e.g., unshielded RF sources), as this may interfere with normal operation.
- The maximum operating speed of the robot is set to an optimal value at the factory. If an increase in speed is required, contact Dobot's technical support engineer for consultation. Unauthorized modification of the maximum speed limit may result in excessive joint torque and other operational issues.

1.7 Personal safety

When operating the robot system, please strictly follow the general precautions listed below to ensure the personal safety.

 WARNING

- Comply with local laws or regulations with regard to the maximum weight one person is permitted to carry.
- Do not touch the wiring terminals or disassemble the equipment while it is powered on, as this may result in electric shock.
- Make sure that the equipment is properly grounded, otherwise, it may endanger personal safety.
- Do not touch the power terminals or disassemble internal components within 10 minutes of disconnecting the robot from the power supply, as residual voltage in the internal capacitors may cause electric shock.
- Even when the robot's power switch is turned off, do not touch or disassemble internal components, as residual voltage in the internal capacitors may cause electric shock.
- Do not wear loose clothing or jewelry when working with the robot. Tie your long hair back behind your head.
- If the robot appears to be stationary while the equipment is running, it may be in a standby state, waiting for a start signal. In such cases, the robot should still be considered active. Do not approach the robot.

1.8 Residual risks

Dobot robots have undergone rigorous safety design and testing, and a series of safety measures have been implemented to minimize risks during installation, commissioning, operation, and maintenance. However, certain **residual risks** may remain and should be handled with caution during operation:

- **Mechanical collision or pinching:**
Unexpected collisions of mechanical components or abnormal gripping may occur during the robot's operation.
- **Electrical hazards:**
Risks such as accidental electrical leakage may arise due to cable aging or improper installation environments.
- **Programming errors or loss of control:**
Communication interference, incorrect parameter settings, or improper integration with other equipment could result in deviations from the intended robot actions.
- **Human operational errors:**
Risks caused by failure to strictly adhere to operational requirements, unauthorized parameter adjustments, or untrained personnel entering the robot's motion area.

To reduce residual risks, follow these recommended practices during use:

- **Wear protective equipment:**
Always wear safety gear such as hard hats, safety glasses, and insulated gloves, especially when entering the robot's motion area.
- **Isolate the workspace:**
Use barriers or warning signs to prevent unauthorized personnel from entering the robot's operating range.
- **Familiarize yourself with the emergency stop button:**
Ensure the emergency stop button is always easily accessible and press it immediately in case of emergencies.
- **Perform regular maintenance:**
Conduct routine inspections of all robot components as specified in the manual to ensure proper functioning.
- **Authorized use only:**
Robots should only be operated by trained and qualified personnel. Unauthorized modification of parameters or disassembly of components is strictly prohibited.

When using the robot, always operate it in strict accordance with the operational instructions and safety guidelines. Dobot assumes no responsibility for any losses incurred due to failure to comply with these regulations.

1.9 Emergencies

1.9.1 Emergency stop device

In an emergency, pressing the emergency stop button on the teach pendant will immediately halt all robot motions. According to IEC 60204-1 and ISO 13850, emergency stop devices are not safeguards. They serve as supplementary protective measures and are not intended to prevent injuries.

Based on the results of the risk assessment for the robot system, additional emergency stop buttons may be connected. The emergency stop button must comply with the IEC 60947-5-5 standard.

1.9.2 Emergency recovery

The emergency stop button locks when pressed and must be rotated as indicated on the button to unlock it. After unlocking, the alarm can be cleared and the robot can be re-enabled via DobotStudio Pro to recover from the emergency status.



WARNING

Operate the robot arm to recover from emergency status only after the danger to the robot system has been completely eliminated.

1.9.3 Personnel rescue in emergency situations

In rare emergency cases, you may need to move the robot arm while in an emergency stop status to rescue a trapped person. In such cases, you can:

Manually releasing the brakes

Open DobotStudio Pro and navigate to **"Settings > Safety > Joint brake"** page, click **"Edit"**, hold the joint with your hand and turn on the switch of the joint you want to move, then click **"Save"**.

Once the brake is ON, you can drag the joint to rescue the trapped person.



WARNING

When switching on the "Joint brake" function, be sure to hold the joint with your hand to prevent it from falling.

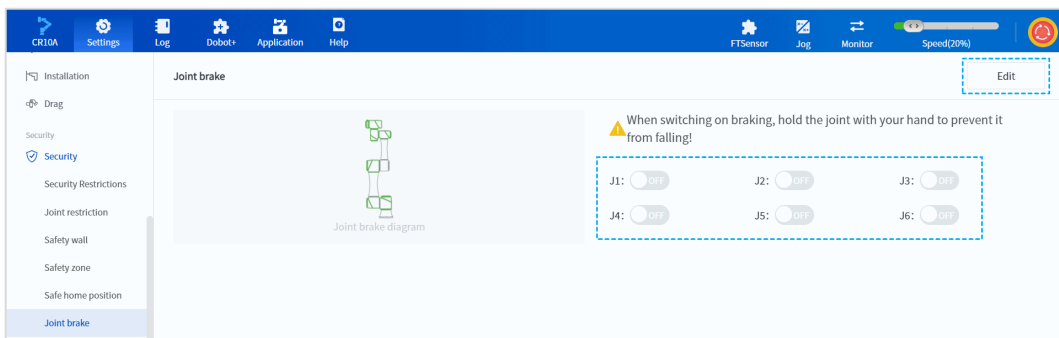


Figure 1.1 Manually release the brakes

Removing the fixing screws from robot base

Refer to [Robot arm installation](#). After removing the fixing screws from the robot base, you can move the robot arm to free the trapped person.



WARNING

- Disconnect the robot arm from the power before removing the screws.
- Hold the robot throughout the process of removing the screws and moving the robot arm.

2. Transportation

2.1 Transportation precautions

- The robot arm should be restored to its packing posture before transportation. This can be set in DobotStudio Pro (refer to *DobotStudio Pro User Guide* for details). Use the original packaging for transportation.
- During transportation, ensure that the robot arm remains stable and is securely fastened.
- During transportation and long-term storage, maintain an ambient temperature range of -20°C to +55°C, with humidity ≤95% and no condensation.
- After transportation, store the original packaging in a dry place for future repacking and transportation.



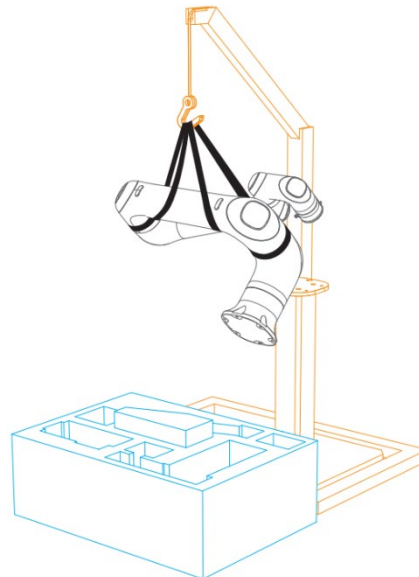
WARNING

- Dobot assumes no responsibility for any damage incurred during transportation.
- Strictly follow the installation instructions when installing the robot.

2.2 Unpackaged handling

When moving the robot arm from its packaging to the installation position or relocating it, follow these handling guidelines:

- If the robot arm is not in the packing posture, restore it to the packing posture first.
- When handling and installing the robot, hold the robot arm with your hand until all base mounting bolts are fully tightened.
- Please use the factory-supplied slings for lifting. Detailed lifting procedures can be found in the [Robot arm installation](#) section. **Do not attach the slings to joints J3 – J6 or the forearm to lift the robot, as this may damage the internal structure.**



3. Installation and Use

3.1 Installation environment

To maintain the performance of the controller and robot arm and ensure safe use, please place the controller and robot arm in an environment that meets the following conditions.



NOTICE

Please make sure that the installation environment meets the following conditions to avoid potential damage.

- Install indoors with good ventilation.
- Keep away from excessive vibration and shock.
- Keep away from direct sunlight and radiant heat.
- Keep away from dust, oil mist, smoke, salinity, metal powder, corrosive gases, and other contaminants.
- Do not use in a closed environment. A closed environment may cause the controller to overheat and shorten its service life.
- Keep away from flammable.
- Keep away from cutting and grinding fluids.
- Do not use in high electromagnetic interference environments.

3.2 Unpacking

Upon unpacking, check the attached shipping list to ensure that all items are included. If anything is missing, please contact your supplier.

3.3 Robot installation

3.3.1 Installation platform requirements

- When installing the robot, it must be securely fixed to a stable base. The base should be able to withstand at least 10 times the maximum torque of the J1 joint and at least 5 times the weight of the robot arm.
- If the robot arm is installed on a linear axis or a movable platform, the acceleration of the platform should be low, as high acceleration may trigger the robot's collision detection mechanism, causing it to stop.
- The robot arm is connected to the controller via a heavy-duty cable. If the heavy-duty cable needs to pass through a cable routing hole on the installation platform, the diameter of hole for cable passing through should not be less than 40mm.
- The heavy-duty cables of CR30 robot arm only support side cable routing. The recommended distance between the hole for cable passing through and the robot base should be no less than $L+8D$ (L: the length after connecting the heavy-duty connector; D: the diameter of the heavy-duty cable):
 - For CR30, $L \approx 150\text{mm}$, $D = 15.6\text{mm}$, so the recommended distance between the cable routing hole and the robot base should be at least 280mm.

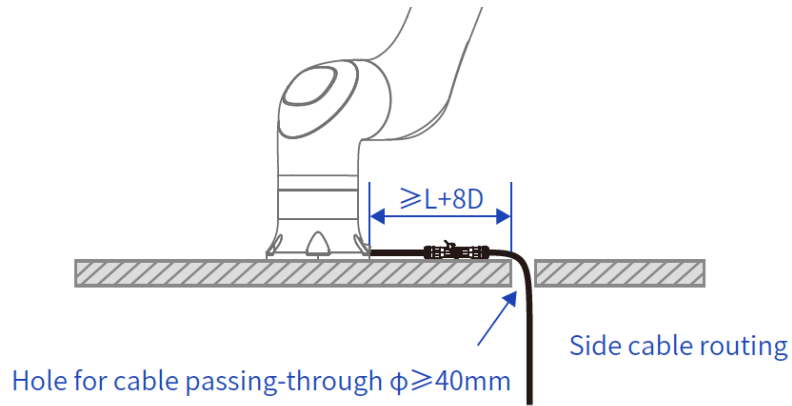


Figure 3.1 Heavy-duty cable routing

3.3.2 Robot arm installation

The CR30 series robot arms support 360° mounting at any angle. The figure below shows several typical installation postures for robot arm.

NOTE

The installation posture at the bottom of the figure is the standard mounting angle. When installing the robot in a non-standard mounting angle, you need to calibrate the mounting angle through DobotStudio Pro after power-on. For details, refer to *DobotStudio Pro User Guide*.

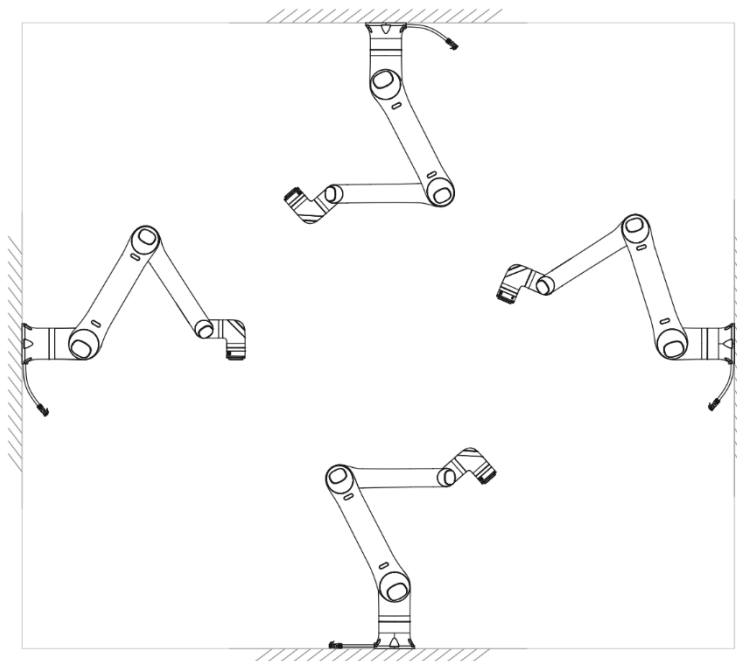


Figure 3.2 Robot arm installation postures

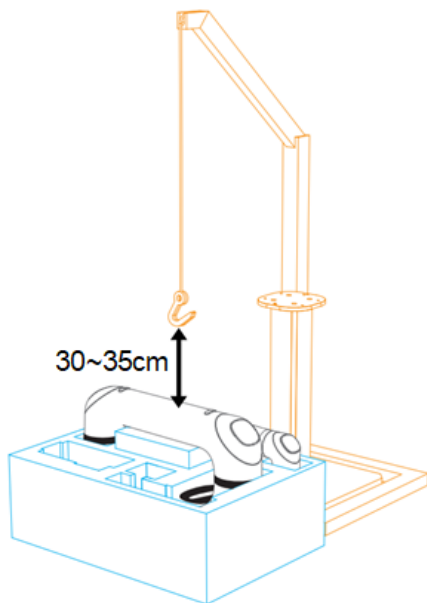
When installing the robot arm, position the mounting holes on the installation platform according to the base dimension. After lifting the robot arm onto the platform, secure its base to the platform using bolts. Be sure to observe the following during installation:



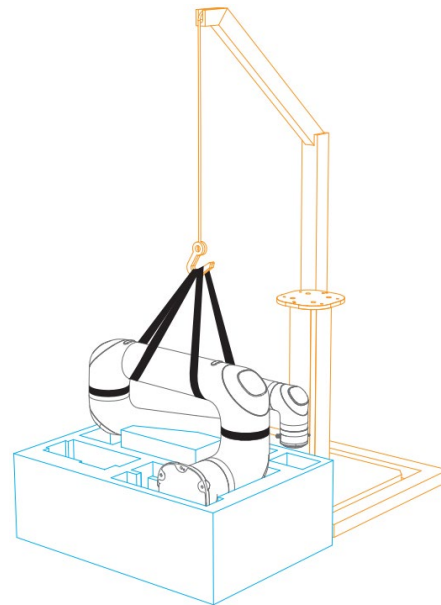
NOTICE

- During transportation, ensure that the robot is stable and properly secured in its position.
- When the robot is hoisted, be sure to take appropriate measures to locate the moving parts so as not to cause accidental movement and harm during hoisting and transportation.
- When lifting the robot arm from its packaging to the installation position, hold the robot with your hand at all times until all bolts on the base are tightened.
- The robot base must be secured to the platform using hex bolts (ISO898-1: 2013, property class: 12.9).
- For wall-mounted or upside-down installations, safety measures must be taken to prevent the robot base from falling.

- ① Move the hoist so that the hook aligns with the central axis of the robot arm and is positioned approximately 30–35 cm away from the arm.

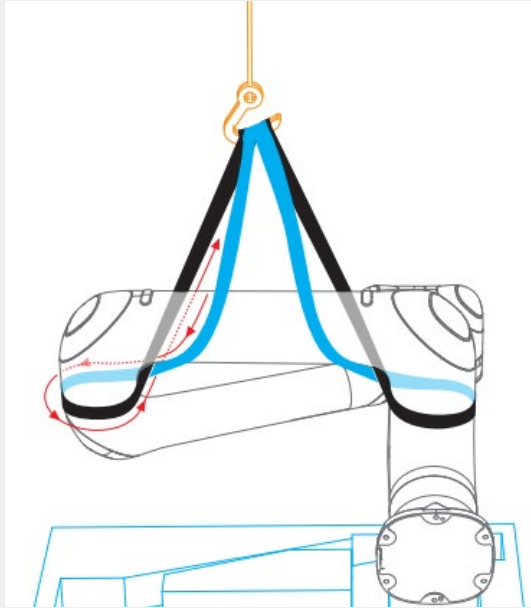


- ② Attach the factory-supplied slings of the robot arm onto the hook.

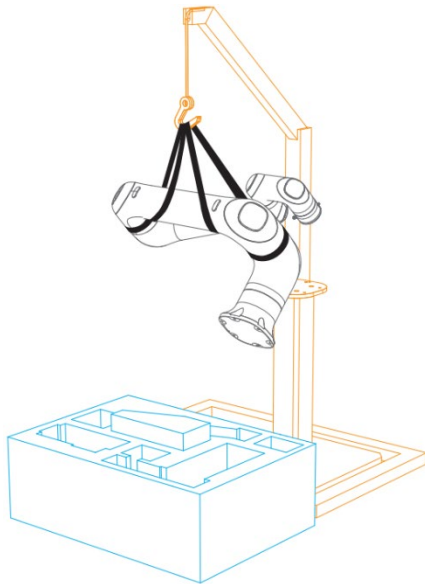


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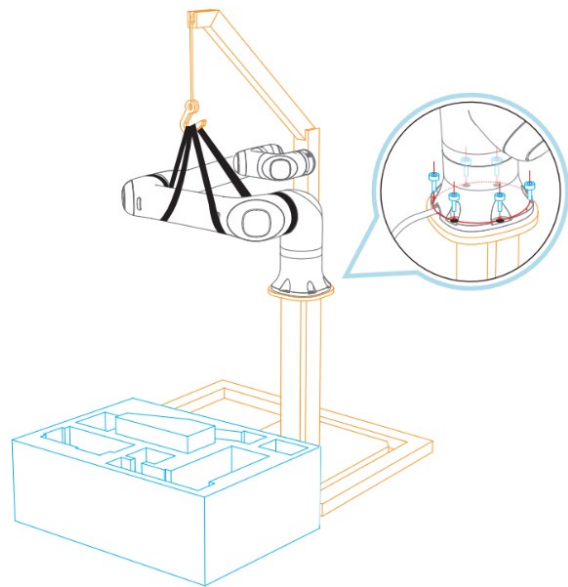
If the lifting sling shifts or detaches during transportation, it can be rewound using the "figure-8 winding method" as described below.



- ③ Control the hoist to slowly lift the robot arm (ensure personnel support the arm throughout the entire process).



- ④ Lift the robot arm to its installation platform, align it with the holes, and securely fasten the arm in place using six M10 hex bolts.



3.3.3 Controller installation

Place the controller on a stable platform outside the robot's workspace, and reserve enough space for cable connections and operation. The controller supports both vertical and horizontal installation. Keep the air inlet and outlet unobstructed and leave at least 200mm space on the corresponding sides for proper heat dissipation. Leave 200mm space at the front of the controller for cable wiring.

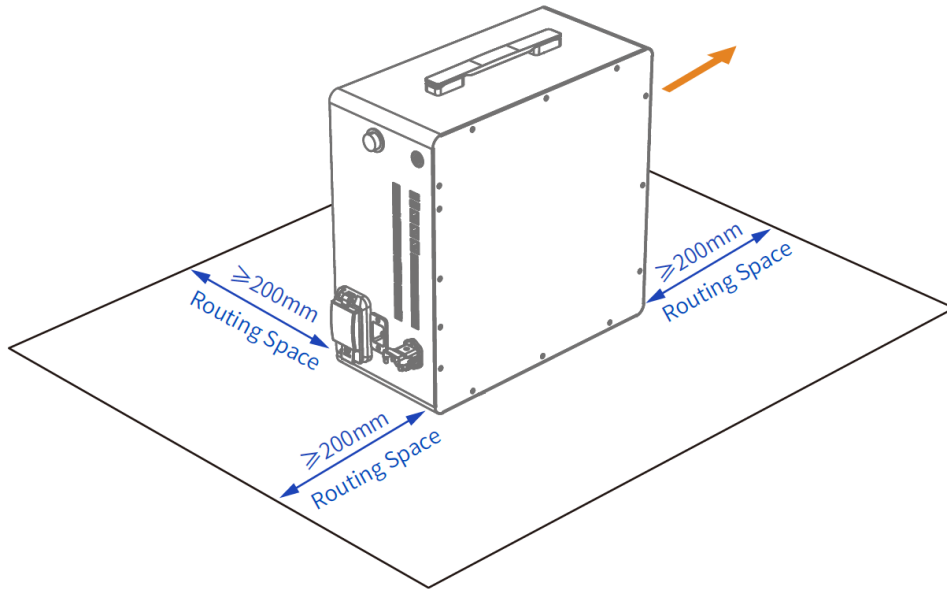


Figure 3.3 Vertical installation

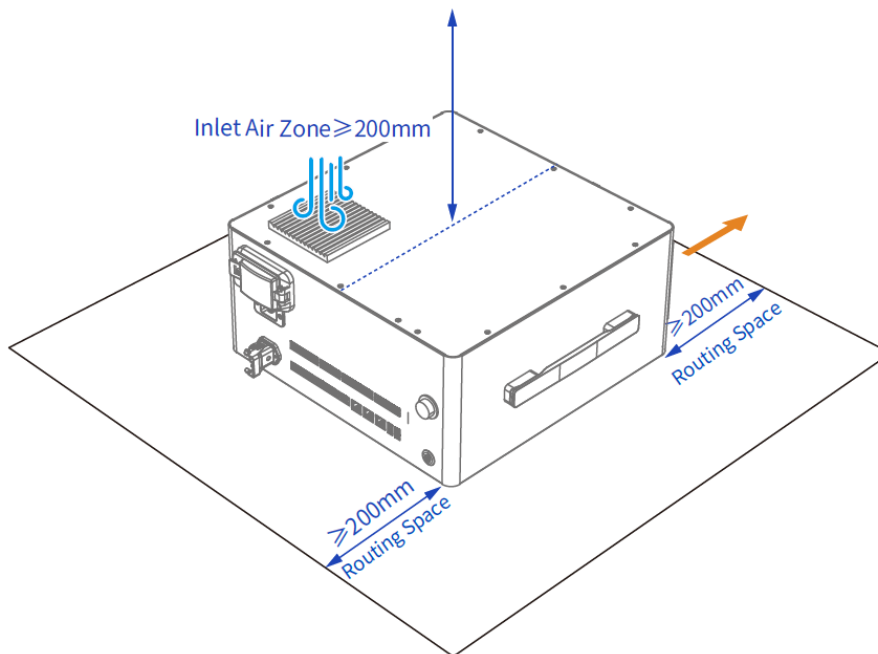


Figure 3.4 Horizontal installation

3.3.4 Tool installation

The robot's end flange of CR30 is equipped with 6 M8 threaded holes, which can fix the tool to the end of the robot arm. To ensure precise alignment of the tool, the reserved positioning holes can be used with pins for accurate positioning.

3.4 Cable connection

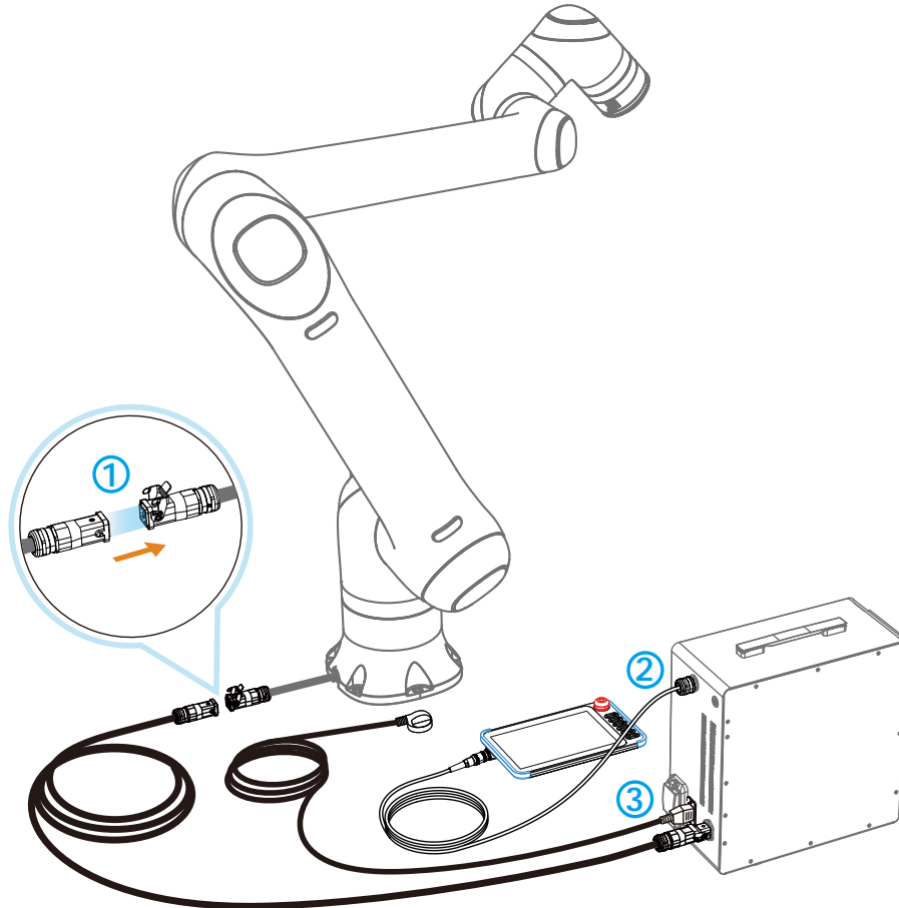


Figure 3.5 Cable connection

- ① Connect the controller to the robot arm using the heavy-duty cable: insert one end of the heavy-duty cable into the interface for heavy-duty cable on the controller, and connect the other end to the robot arm's built-in heavy-duty cable connector.



NOTICE

For NSF models, ensure the heavy-duty cable's aviation plug connector is placed in an enclosed space and never directly exposed to food production environments.

- ② Plug the teach pendant cable into the emergency stop switch interface on the controller.
- ③ Insert one end of the power cable into the controller's power interface, and the other end into a mains power socket.



NOTICE

- The specifications and installation method of the external cables should comply with local laws and regulations.
- Do not disassemble the robot by yourself, as this may result in electrical leakage.
- Make sure that the device is properly grounded.
- Do not bend the cable excessively, otherwise it may cause poor connections or cable breakage.
- Before connecting external devices, make sure the power outlet of the control system is disconnected. If not disconnected, may result in electric shock or device failure.
- To ensure device and personal safety, use supplied cables.
- After wiring, make sure that there are no loose screws or exposed cables inside the device.
- During normal operation, do not plug or remove the power cables and communication cables.
- The device must be fully wired before powering it on.
- Make sure that the cables are connected correctly to avoid damage to internal modules or external devices.
- Before connecting, check that the insulation and shielding of external cables are not damaged.

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

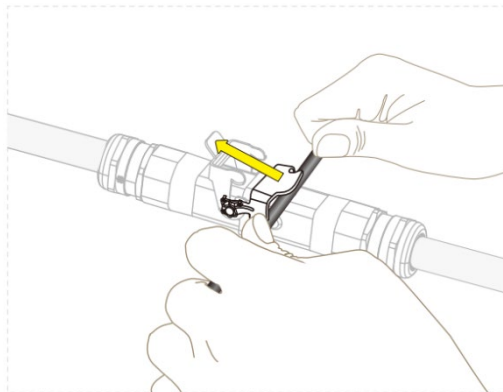


Figure 3.6 Unlock the heavy-duty plug

3.5 Power-on and debugging

After turning on the external power supply, press and release the round button located on top of the controller.

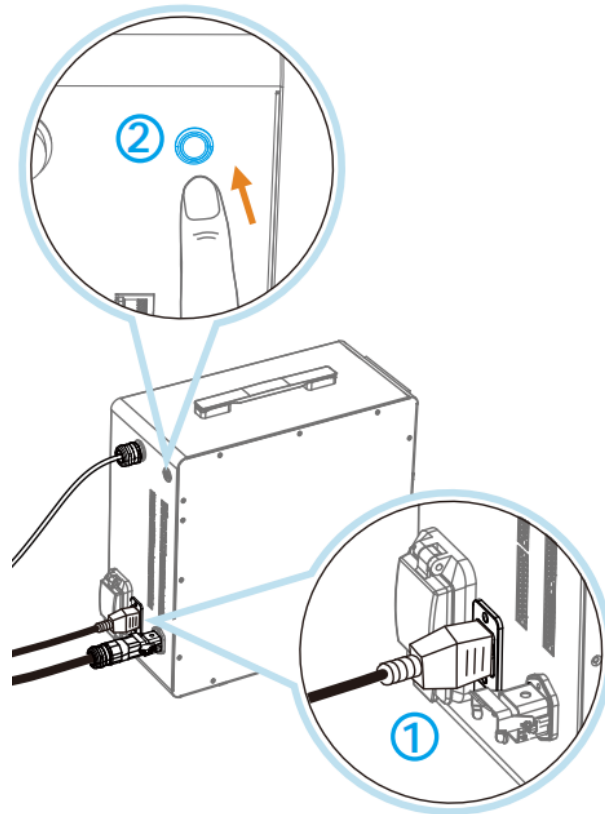


Figure 3.7 Power-on

Once the indicator lights on both the robot arm's end-effector and the controller's round button turn solid blue, you can connect to the robot using the operation terminal, enable it, and jog it for debugging.

For detailed operation instructions, refer to *DobotStudio Pro User Guide*.

When the robot is not in use, press the round button on the top of the controller for to power it off. Wait until the indicator lights on both the robot arm's end-effector and the controller's round button turn off. Then, disconnect the external power supply.



NOTICE

If the robot is being used for the first time or has been left idle for a long period of time, performing high-speed, high-load movements immediately after power-on may trigger false alarms. It is recommended to perform a few minutes of low-speed movements to warm up the robot before normal operation.