

User Guide (en)

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MiR 1350

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Original instructions (English)

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1. About this document

This user guide explains how to set up and start operating your MiR1350 robot and provides examples of simple missions you can expand to your purposes. This guide also contains information regarding the external and internal components of MiR1350 along with instructions for proper maintenance of the robot. You will also find information regarding safety and specifications needed to commission a safe MiR1350 robot application.



NOTICE

Save this manual. It contains important safety and operating instructions.

1.1 Where to find more information

On the Support Portal at [the MiR website](#), you can find the following resources under **Documentation**:

- **Quick starts** describe how you start operating MiR robots quickly. It comes in print in the box with the robots. Quick starts are available in multiple languages.
- **User guides** provide all the information you need to operate and maintain MiR robots and how to set up and use top modules and accessories, such as charging stations, hooks, shelf lifts, and pallet lifts. User guides are available in multiple languages.
- **Operating guides** describe how to set up and use MiR accessories or supported functions that are mainly hardware-based, such as charging stations and shelf functions.
- **Getting started guides** describe how to set up MiR accessories that are mainly software-based, such as MiR Fleet.

- **Reference guides** contain descriptions of all the elements of the robot interface and MiR Fleet interface. Reference guides are available in multiple languages.
- **Best practice guides** provide helpful information you can use when commissioning or operating your robot.
- **REST API references** for MiR robots, MiR Hooks, and MiR Fleet. HTTP requests can be used to control robots, hooks, and MiR Fleet.
- **MiR network and WiFi guide** specifies the performance requirements of your network and how you must configure it for MiR robots and MiR Fleet to operate successfully.
- **Cybersecurity guide** provides important information and instructions to increase the cybersecurity of your MiR product.
- **How to guides** are short guides providing instruction for maintenance, replacement, commissioning, and other tasks related to MiR products.
- **Troubleshooting guides** can help you determine the cause of an issue you are experiencing with your MiR product and how to resolve it.

1.2 Version history

This table shows current and previous versions of this document.

MiR1350	
	
Revision	Description
1.2	Date: 2022-05-31 Robot HW: 1.0 Top module HW: 1.0

Revision	Description
	<ul style="list-style-type: none"> • Improved description of Power save, Deep sleep, and storing the battery. Affects section: Battery storage. • Added that localization is disabled while brakes are released manually. Affects section: Manual brake release, • Added lower boundary in camera FoV. Affects section: Obstacle detection. • Added warning not to use two chargers to charge the robot simultaneously. Affects section: Charging the robot. • Corrected payload specifications. Affects sections: Product presentation and Shelf specifications. • Added notice that cable chargers only charge the robot's battery to 80–90%. Affects sections: Charging the robot
1.1	<p>Date: 2021-10-07</p> <p>Robot HW: 1.0</p> <p>Top module HW: 1.0</p> <ul style="list-style-type: none"> • Applied general corrections. Affects sections: Payload distribution, Footprints, and Nameplate. • Updated manual to ensure compliancy with radio equipment directives. Affects sections: Safety, Connecting to the robot interface, and Connecting the robot to a WiFi network
1.0	<p>Date: 2021-08-12</p> <p>Robot HW: 1.0</p>

Revision	Description
	Top module HW: 1.0 First edition.

2. Product presentation

MiR1350 is an autonomous mobile robot that can transport loads up to 1350 kg indoors within production facilities, warehouses, and other industrial locations where access to the public is restricted.



Users operate MiR1350 via a web-based user interface, which is accessed through a browser on a PC, smartphone, or tablet—see [Connecting to the robot interface on page 60](#). The robot can be set up to run a fixed route, be called on demand, or perform more complex missions.

The robot interface of MiR1350 can be accessed via Google Chrome, Google Chromium, Apple Safari, Mozilla Firefox, and Microsoft Edge browsers.

The robot uses a map of its work area to navigate and can move to any position on the map—see [Navigation and guidance system on page 85](#). The map can be created or imported the first time the robot is used. While operating, the robot avoids obstacles that are not mapped, like people and furniture.



Specifications for MiR1350 are available on the [MiR website](#).

2.1 Main features of MiR1350

The main features of MiR1350 are:

- **Driving in a populated workspace**
 The robot is designed to operate among people and maneuvers safely and efficiently in highly dynamic environments.
- **Overall route planning and local adjustments**
 The robot navigates autonomously to find the most efficient paths to its destinations. The robot adjusts the path when it encounters obstacles that are not on the map, like personnel and vehicles.
- **Efficient transportation of heavy loads**
 The robot is designed to automate transportation of loads up to 1350 kg.
- **Sound and light signals**
 The robot continuously signals with light and sounds, indicating where it will drive and its current status, for example, waiting for a mission, driving to a destination, or destination reached.
- **User-friendly and flexible**
 The web-based user interface, accessed from a PC, tablet, or smartphone, gives easy access to operation and monitoring of the robot and can be programmed without any prior experience. Different user group levels and tailored dashboards can be set up to suit different users.
- **Alert for 'lost'**
 If the robot enters a situation where it is unable to find a path to its destination, it stops, turns on the yellow-purple running error light, and a custom defined Try/Catch action may be used to alert personnel or take other actions—see [Creating the mission Try/Catch on page 206](#).
- **Automatic deceleration for objects**
 The built-in sensors ensure that the robot is slowed down when obstacles are detected in front of it.

- **Internal map**

The robot can either use a floor plan from a CAD drawing, or a map can be created by manually driving the robot around the entire site in which the robot is going to operate. When the robot is mapping, the robot's sensors detect walls, doors, furniture, and other obstacles, and the robot then creates a map based on these input. After you've finished mapping, you can add positions and other features in the map editor—see [Creating and configuring maps on page 143](#).

Top modules

The following top modules are available for MiR1350:

- **MiR Shelf Lift**

A lift platform can be mounted on MiR1350 enabling it to automate the internal transport of shelves that meet specifications outlines by MiR—see *MiR1350 Shelf Lift User Guide* for the shelf requirements.

- **MiR Pallet Lift 1350**

A lift platform can be mounted on MiR1350 enabling it to automate the internal transport of US standard 40×48 pallets.

- **MiR EU Pallet Lift 1350**

A pallet lift for EU pallets can be mounted on MiR1350 enabling it to automate the internal transport of EU pallets.



To learn more about the top modules and accessories, go to [the MiR website](#).

Accessories

The following accessories are available for MiR1350:

- **MiR Pallet Rack**

Use a MiR Pallet Rack with MiR Pallet Lift 1350. The lift places and picks up US standard 40×48 in (1016×1219 mm) pallets from the rack autonomously.

- **MiR EU Pallet Rack**
Use a MiR EU Pallet Rack with MiR EU Pallet Lift 1350. The lift places and picks up EU pallets from the rack autonomously.
- **MiR Fleet**
MiR Fleet offers centralized control of robots throughout all your facility. MiR Fleet is available as an installation file you can install on a server of your choice or as a computer server where MiR Fleet comes pre-installed.
- **MiR AI Camera**
An intelligent camera that detects and recognizes different moving objects, which can trigger certain actions in MiR Fleet.
- **MiR Charge 48V**
These fully automatic chargers enable MiR robots to recharge their batteries. Together with MiR Fleet, charging of robots can be fully automated, ensuring that robots never run out of power during missions.

2.2 External parts

This section presents the parts of MiR1350 that are visible on the outside.



Figure 2.1. MiR1350 external parts.

Table 2.1. Identification of the external parts in <i>Figure 2.1</i>			
Pos.	Description	Pos.	Description
1	Left top compartment— see Internal parts on page 23	2	Right top compartment— see Internal parts on page 23

Pos.	Description	Pos.	Description
3	Antenna: two pcs, in opposite corners	4	Emergency stop button: four pcs, two on each side—see Emergency stop circuit on page 121
5	Status light: on all four sides of the robot—see Obstacle detection on page 90	6	Left side maintenance hatch: opens to the left side compartment—see Internal parts on page 23
7	Front safety laser scanner—see Obstacle detection on page 90	8	Front maintenance hatch: opens to the front compartment—see Internal parts on page 23
9	3D depth cameras: two pcs, detect objects in front of the robot— see Obstacle detection on page 90	10	Proximity sensors: eight pcs, two in each corner behind the corner covers—see Obstacle detection on page 90.
11	Right side maintenance hatch: opens to the right side compartment—see Internal parts on page 23	12	Rear safety laser scanner—see Obstacle detection on page 90

Pos.	Description	Pos.	Description
13	Rear maintenance hatch: opens to the rear compartment—see Internal parts on page 23	14	Signal light: eight pcs, two on each corner—see Light indicators and speakers on page 135
15	Control panel and antenna—see Control panel on the next page		

Identification label

MiR1350 is delivered with an identification label mounted to the product. The identification label identifies the product, the product serial number, and the hardware version of the product.

The identification label of MiR1350 is located in the left compartment next to the battery.

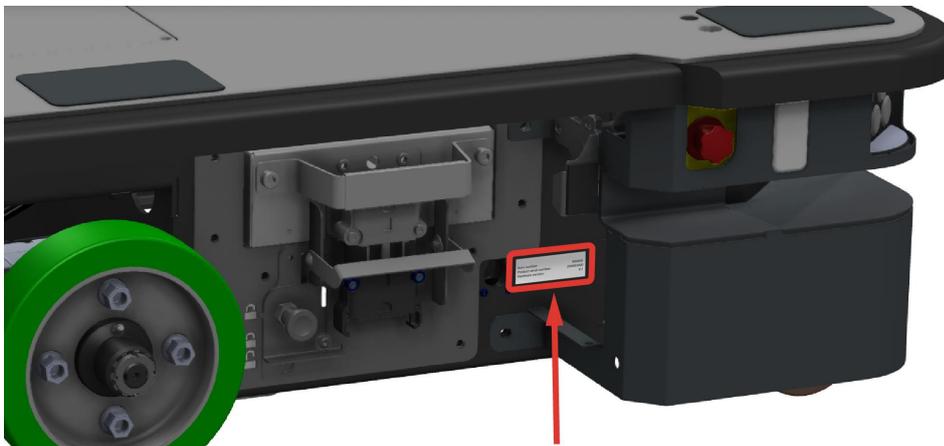


Figure 2.2. Placement of the identification label.

Item number:	801350
Product serial number:	205003000
Hardware version:	V.1

Figure 2.3. Example of a MiR1350 identification label.

Nameplate

Every MiR application is delivered with a nameplate that must be mounted on the robot. The nameplate of MiR1350 identifies the application model and serial number and includes the CE mark, technical specifications, and the address of Mobile Industrial Robots. The nameplate identifies the complete MiR application, for example, a robot with a top module.

It is the responsibility of the commissioner to mount the nameplate on the application—see [Mounting the nameplate on page 72](#).

Weight without payload:	233 kg	Nominal power:	2 × 400 W	Contains FCC ID:	RYK-261ACNBT
Maximum speed:	1.2 m/s	Type:	Driverless truck		
Maximum incline/decline:	1%	Model:	MiR1350		
Maximum payload:	1350 kg	S/N:	102100000	This device complies with part 15 of the FCC rules. Operation is subject to the following two conditions: (1) This device may not cause harmful interference, and (2) this device must accept any interference received, including interference that may cause undesired operation.	
Footprint of payload:	Equal to robot footprint	Year of construction:	2021		
Lithium-ion battery		Made in Denmark			
Nominal voltage:	48 V	Mobile Industrial Robots A/S			
Maximum capacity:	34.2 Ah	Emil Neckelmanns Vej 15F			
Battery weight:	14 kg	DK-5220 Odense SØ			
Dimensions	546 × 75 × 204 mm				

Figure 2.4. Example of a MiR1350 nameplate.

Control panel

MiR1350 has a control panel in the rear-left corner of the robot.

The control panel buttons

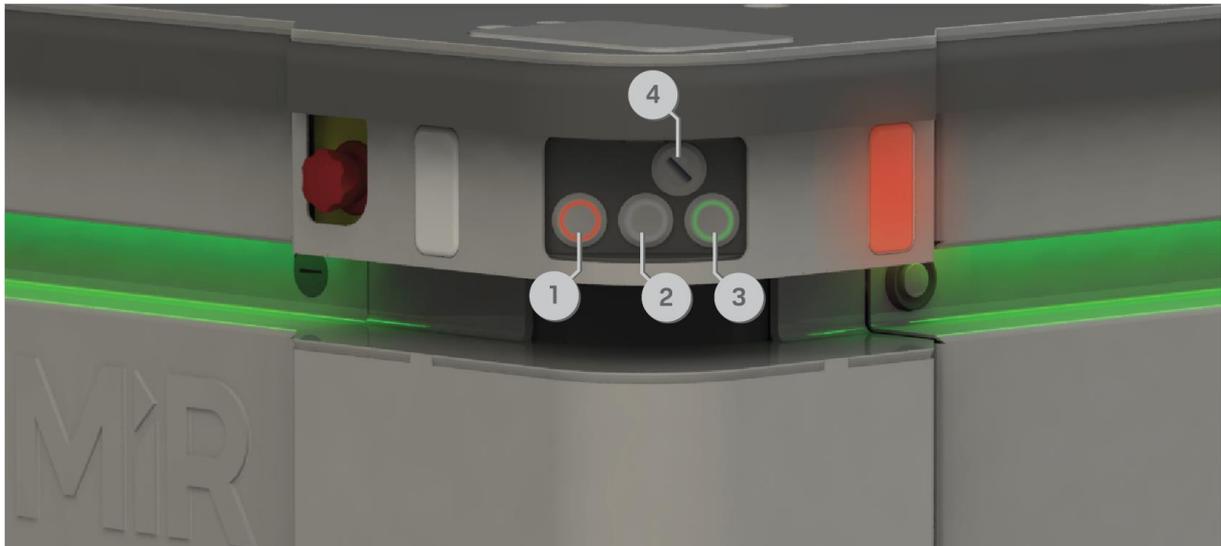


Figure 2.5. The MiR1350 control panel.

Table 2.2. Identification of items on the control panel in <i>Figure 2.5</i>			
Pos.	Description	Pos.	Description
1	Manual stop button	2	Resume button
3	Power button	4	Operating mode key

Manual stop button

Pressing this button stops the robot. After pressing this button, you must press the Resume button to let the robot continue operating.

Color indication:

- Red: It is possible to engage the Manual stop.

Resume button

Pressing this button:

- Clears the Emergency or Protective stop state.
- Lets the robot continue operating after the Manual stop button was pressed or after the operating mode changes.
- Lets the robot start operating after powering up.

Color indication:

- Blinking blue: The robot is waiting for a user action. For example, press the button to clear a Protective stop or acknowledge the change of operating mode.

Power button

Pressing this button for three seconds turns the robot on or shuts it off.

Color indication:

- Blinking green: The robot is starting up.
- Green: Normal operation.
- Blinking blue: The robot is checking that the battery level is high enough to start up.
- Blinking red: The battery level is too low to start without additional charging, or the robot is shutting down.

The Operating mode key

The Operating mode key lets you switch between operating modes.

- **Left position: Autonomous mode**
Puts the robot in Autonomous mode.
- **Middle position: Locked**
Locks the robot. The robot blocks the wheels; you cannot start a mission or drive the robot manually.
- **Right position: Manual mode**
Puts the robot in Manual mode.

For more information on operating modes, see [Operating modes below](#).



Remove the Operating mode key during normal operation. The vibrations from the robot's driving may shake the key and plug, and can cause an unwanted Protective stop.

Operating modes

MiR1350 has two operating modes: Manual mode and Autonomous mode.

Manual mode

In this mode, you can drive the robot manually using the joystick in the robot interface. Only one person can control the robot manually at a time. To ensure that nobody else takes control of the robot, the robot issues a token to the device on which you activate the Manual mode.

For information about activating this mode, see [Driving the robot in Manual mode on page 68](#).



To control the robot manually, you need to connect to the robot interface—see [Connecting to the robot interface on page 60](#).

Autonomous mode

In this mode, the robot executes the programmed missions. After switching the key to this mode, you can remove the key, and the robot will continue driving autonomously. In Autonomous mode, the joystick is disabled in the robot interface.

2.3 Internal parts

Most internal parts of MiR1350 are accessed through maintenance hatches that open to different compartments:

- Front compartment
- Rear compartment
- Side compartments
- Top compartments

To access the compartments correctly, see [Accessing the internal parts on page 43](#).



CAUTION

Opening or removing hatches from the robot exposes parts connected to the power supply, risking damage to the robot from a short circuit and personnel getting burnt.

- Before removing any covers, turn off the robot, and disconnect the battery—see [Disconnecting the battery on page 80](#).

Front compartment

The front compartment holds several electronic components, such as the robot computer and the safety PLC.

To open the front compartment, see [Accessing the internal parts on page 43](#).

Front compartment components

The front compartment components are listed in **Table 2.3**

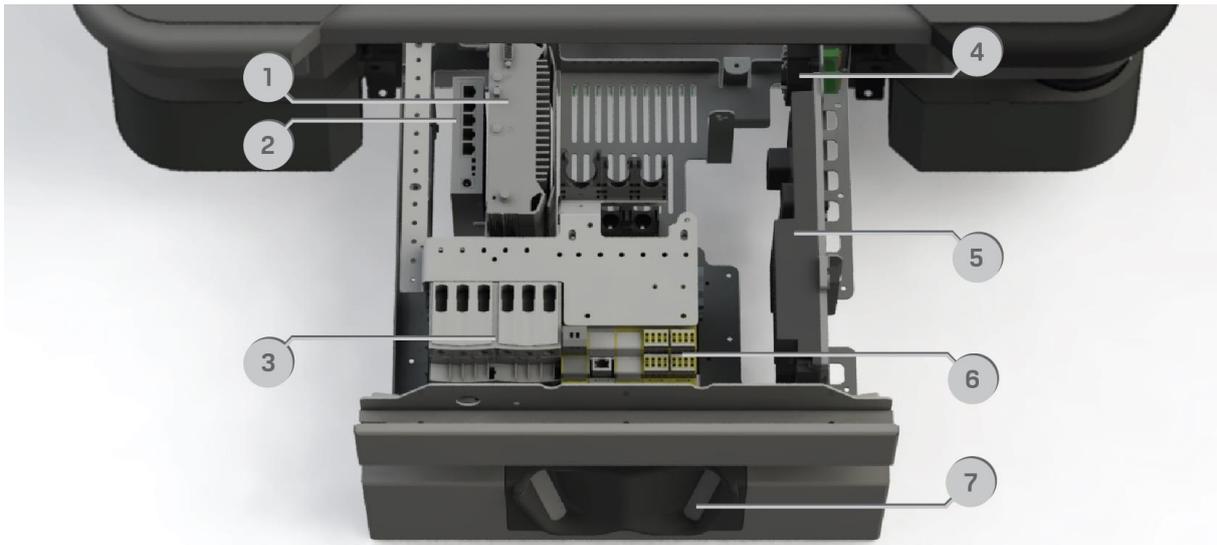


Figure 2.6. Internal parts of the front compartment.

Table 2.3.
Identification of internal parts in *Figure 2.6*

Pos.	Description	Pos.	Description
1	Robot computer: processes data from the sensors and controls the robot's navigation	2	Switch: enables communication between the robot computer, safety PLC, top interface, and power board
3	Safe Torque Off contactors: cut power to the robot's motors when the robot enters Protective or Emergency stop	4	GPIO module: manages signals from the GPIO top module interface
5	Power board: controls the power distribution for the motor controller, robot computer, and safety PLC	6	Safety PLC: controls the safety system—see Safety-related functions and interfaces on page 104

Pos.	Description	Pos.	Description
7	3D cameras: detect obstacles in front of the robot—see Obstacle detection on page 90		

Rear compartment

The rear compartment holds the Manual brake release switch and an inner compartment with the motor controller carrier board and dynamic brake contactors.

To open the rear compartment, see [Accessing the internal parts on page 43](#).

The rear compartment components are listed in **Table 2.4**.



Figure 2.7. Internal parts of the outer rear compartment.

Table 2.4. Identification of internal parts in <i>Figure 2.7</i>			
Pos.	Description	Pos.	Description
1	Connector for the status light band	2	Motor controller carrier board: contains the motor controllers and the controller for proximity sensors and light indicators
3	Connection interface for MiR Controller: connect a MiR Controller to drive the robot with a joystick	4	Manual brake release switch: releases the brakes so the robot can be pushed manually. Shown in the Off position, where the robot engages and releases the brakes automatically—see Manual brake release switch on page 29
5	Dynamic brake contactors: used by the safety system to stop the robot when a safety function is triggered		

Side compartments

The side compartments contain the bogies and drive wheels.

To access a side compartment, see [Accessing the internal parts on page 43](#).



NOTICE

The unique nameplate of your robot is to be mounted on the right side compartment hatch—see [Mounting the nameplate on page 72](#). Make sure you do not swap the hatch with hatches from other robots.

Side compartment components

The left and right side compartment components are listed in **Table 2.5**.

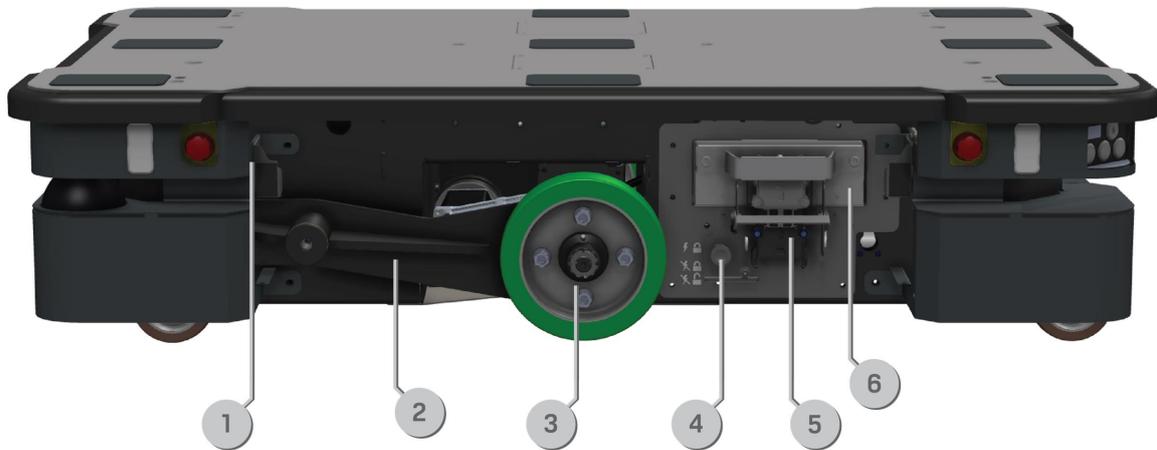


Figure 2.8. Internal parts of the MiR1350 left and right side compartments.

Table 2.5. Identification of internal parts in <i>Figure 2.8</i>			
Pos.	Description	Pos.	Description
1	Connector for the status light band	2	Bogie
3	Drive wheel	4	Battery lock pin (only in left side compartment)

Pos.	Description	Pos.	Description
5	Fast-swap battery assembly (only in left side compartment)	6	Battery (only in left side compartment)

Top compartments

The two top compartments contain electrical interfaces that can be connected to top modules.

To open a top compartment, see [Accessing the internal parts on page 43](#).

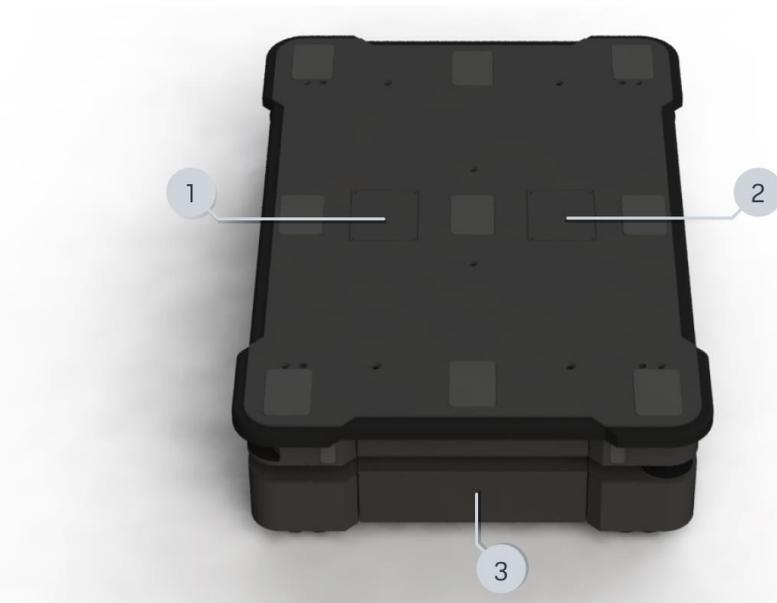


Figure 2.9. The top compartments on the robot.

Table 2.6. Identification of top compartments in <i>Figure 2.9</i>			
Pos.	Description	Pos.	Description
1	Left top compartment	2	Right top compartment
3	Rear compartment		

Top compartment components

The top compartments interfaces are listed in **Table 2.7**. For detailed information on electrical interfaces, see [Interface specifications on page 243](#).

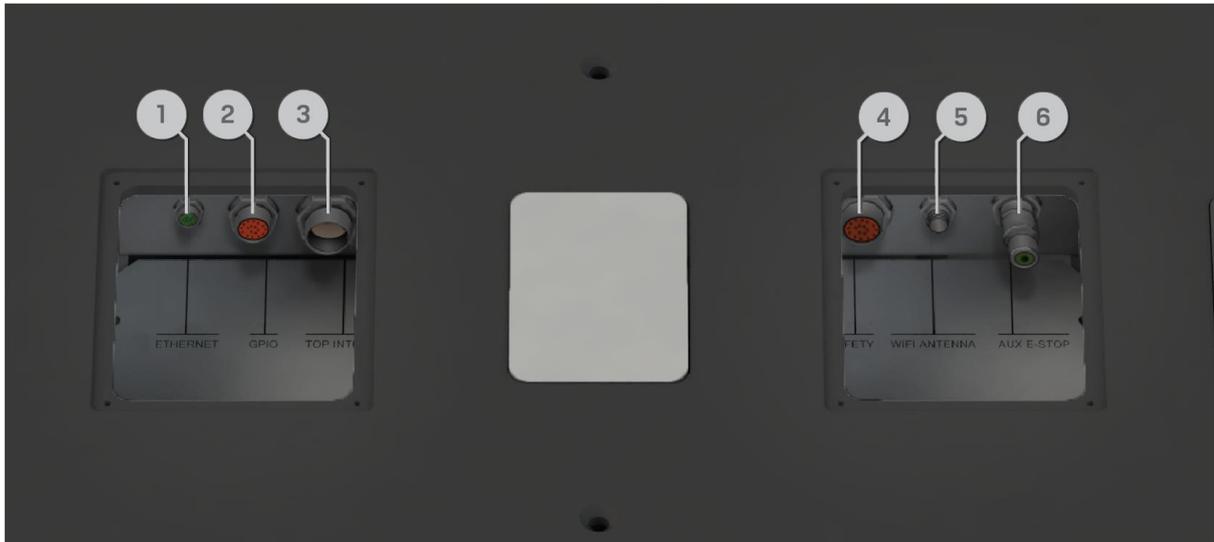


Figure 2.10. Interfaces in the top compartments.

Table 2.7. Identification of interfaces in 2.3			
Pos.	Description	Pos.	Description
1	Ethernet	2	GPIO: General purpose I/O
3	Power	4	Auxiliary safety functions
5	WiFi antenna	6	Auxiliary emergency stop with dummy plug

2.4 Manual brake release switch

The Manual brake release switch is located in the rear compartment. You release the robot's mechanical brakes by turning the Manual brake release switch clockwise.

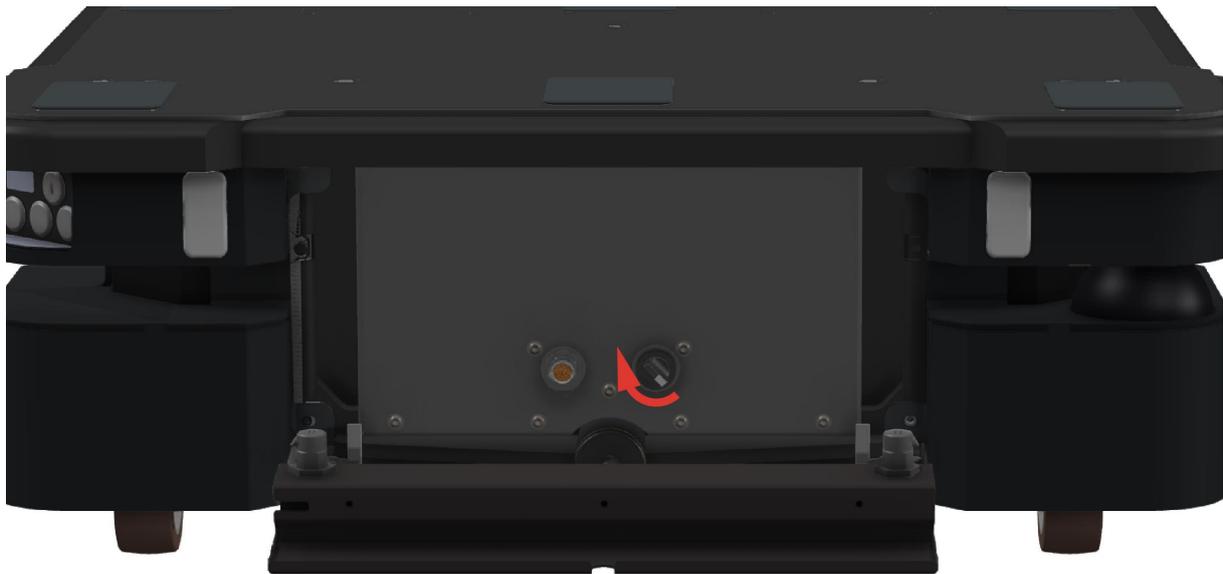


Figure 2.11. Turn the Manual brake release switch clockwise to release the brakes.

The mechanical brakes require electrical power to be released, so if the robot is without power, the mechanical brakes cannot be released. You can see if the robot is powered by checking if the Power button on the control panel lights up.

When the robot is driving the robot engages and releases the mechanical brakes automatically. You should only release the brakes manually when you want to move the robot by hand.

When you release the brakes manually, all power to the motors is cut. This means the robot loses connection to some of the CAN bus nodes and the robot does not receive data that it needs to localize itself. After moving the robot manually, you must correct the robot's location on the map. Once you engage the automatic brake system, the connection to the CAN bus nodes is reestablished, and the robot can update its location on the map automatically.



The robot cannot operate while the mechanical brakes are released manually.

3. Warranty

Mobile Industrial Robots offers a standard warranty on all products.

Contact your distributor to see the terms and extent of product coverage.



NOTICE

Mobile Industrial Robots disclaims any and all liability if MiR1350 or its accessories are damaged, changed, or modified in any way.

Mobile Industrial Robots cannot be held responsible for any damages caused to MiR1350, accessories, or any other equipment due to programming errors or malfunctioning of MiR1350.

4. Safety

Read the information in this section before powering up and operating MiR1350.

Pay particular attention to the safety instructions and warnings.



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4.1 Safety message types

This document uses the following safety message types.



WARNING

Indicates a potentially hazardous situation that could result in death or serious injury. Carefully read the message that follows to prevent death or serious injury.



CAUTION

Indicates a potentially hazardous situation that could result in minor or moderate injury. Alerts against unsafe practices. Carefully read the message that follows to prevent minor or moderate injury.



NOTICE

Indicates important information, including situations that can result in damage to equipment or property.

4.2 General safety precautions

This section contains general safety precautions.



WARNING

Harmful electromagnetic interference might be the result of having two radio modules transmitting at the same time.

- Do not attach an access point or additional radio modules to the robot while it is connected to a wireless network.



WARNING

If the robot is not running the correct software and is therefore not functioning properly, the robot may collide with personnel or equipment causing injury or damage.

- Ensure that the robot is always running the correct software.



WARNING

When the robot is in an operating hazard zone, there is a risk of injury to any personnel within the zone.

- Ensure that all personnel are instructed to stay clear of operating hazard zones when the robot is in the zone—see [Using operating hazard zones on page 173](#).



WARNING

The robot may drive over the feet of personnel, causing injury.

- All personnel must be informed of the side Protective fields of the robot and be instructed to wear safety shoes near an operating robot—see [Personnel detection on page 111](#).



WARNING

The robot may drive into a ladder, scaffold, or similar equipment that has a person standing on it. Personnel risk fall injuries, and equipment may be damaged.

- Don't place ladders, scaffolds, or similar equipment in the robot's work environment.



WARNING

The robot may drive down staircases or holes in the floor and cause serious injury to personnel and damage to the robot and to equipment.

- Mark all descending staircases and holes as Forbidden zones on maps.
- Install physical barriers around descending staircases and holes that are in the robot's operating area. If the hazard is not close to the robot's operating area, it may be sufficient to use a Forbidden zone on its own.
- Keep the maps up to date.
- Inform personnel that the robot cannot detect descending staircases and holes in the floor in time to stop.



WARNING

Contact with live electrical parts can cause electric shock.

- Do not touch any internal components of the robot while it is powered.



WARNING

Using a charging device different from the one supplied by the manufacturer can cause a fire and thereby burn injuries to nearby personnel and damage to the robot and equipment.

- Only use an original MiR charger.



WARNING

Lithium battery packs may get hot, explode, or ignite and cause serious injury if they are misused electrically or mechanically.

Observe the following precautions when handling and using lithium-ion batteries:

- Do not short-circuit, recharge, or connect with false polarity.
- Do not expose to temperatures beyond the specified temperature range or incinerate the battery.
- Do not crush, puncture, or disassemble the battery. The battery contains safety and protection devices, which, if damaged, may cause the battery to generate heat, explode, or ignite.
- Do not allow the battery to get wet.
- In the event the battery leaks and the fluid gets into one's eye, do not rub the eye. Rinse well with water, and immediately seek medical care. If left untreated, the battery fluid could cause damage to the eye.
- In case of fire, use water to put out the fire. There is no need for special extinguishing media. An ambient fire can be fought with class D extinguishing media.
- Do not touch damaged batteries with bare hands. Only personnel using suitable Personal Protection Equipment (PPE) and tools should handle damaged batteries.



- Isolate the battery and keep clear if the following conditions are observed:
 - The battery exhibits abnormally high temperatures.
 - The battery emits abnormal odors.
 - The battery changes color.
 - The battery case is deformed or otherwise differs from the normal electrical or mechanical condition.
- Modifications or manipulations of the battery may lead to considerable safety risks and are therefore prohibited.
- Never smoke or allow an open spark or flame in the vicinity of the robot's battery.
- Do not use the battery for anything other than MiR1350.



WARNING

Load falling or robot overturning if the load on the robot is not positioned or fastened correctly can cause fall injuries to nearby personnel or damage to equipment.

- Ensure that the load is positioned according to the specifications and is fastened correctly.



CAUTION

Robot malfunctions can cause an electrical fire, causing damage and injury to equipment and personnel.

- Personnel operating near the robot must be informed on how to use an ABC fire extinguisher to put out an electrical fire should the robot malfunction and catch on fire.

**CAUTION**

Risk of trapping or injury to personnel if robots malfunction or if personnel enter operating hazard zones.

- Personnel operating near the robot must be informed on how to engage the robot's Emergency stop function in emergency situations.

4.3 Intended use

MiR1350 is intended to be commissioned and used in indoor industrial environments where access for the public is restricted. For details about the environmental conditions in which MiR1350 should operate, see specifications for MiR1350 on the MiR website.

MiR1350 is intended to be commissioned according to the guidelines in [Commissioning on page 139](#). This is a prerequisite for safe usage of MiR1350.

MiR1350 is equipped with safety-related features that are purposely designed for collaborative operation where the robot operates without a safety enclosure or together with people—see [Safety-related functions and interfaces on page 104](#).

MiR1350 is intended to be used with top modules supported by Mobile Industrial Robots or custom modules that:

- Do not have any moving parts.
- Do not extend the physical dimensions of the robot.
- Operate within the environmental conditions required for MiR1350.
- Are within the weight distribution requirements—see [Payload distribution on page 239](#).

If used with custom modules, all obligations of a manufacturer apply to the individual who performs the modifications. All modifications must be in accordance with the machinery directive.

MiR1350 is designed for and all risks are considered when used with one of the following types of top modules:

- MiR Pallet Lift 1350 used with MiR Pallet Rack
- MiR EU Pallet Lift 1350 used with MiR EU Pallet Rack
- MiR Shelf Lift to transport MiR supported shelves

MiR1350 can be used as a partly complete machine as defined in the EU machinery directive with top modules that do not meet the above limitations. Those who design, manufacture, or commission a system that does not meet the limitations of use of MiR1350 carry the obligations of a manufacturer and shall ensure a safe design according to EN ISO 12100. Guidelines outlined in this manual are not sufficient.



NOTICE

A safe machine does not guarantee a safe system. Follow the guidelines in [Commissioning on page 139](#) to ensure a safe system.

4.4 Users

MiR1350 is only intended to be used by personnel that have received training in their required tasks.

There are three types of intended users for MiR1350: commissioners, operators, and direct users.

Commissioners

Commissioners have thorough knowledge of all aspects of commissioning, safety, use, and maintenance of MiR1350 and have the following main tasks:

- Commissioning of the product. This includes creating maps and restricting the user interface for other users and making brake tests with a full payload.
- Conducting the risk assessment.

- Determining the payload limit, weight distribution, safe fastening methods, safe loading and unloading of loads on MiR1350, and ergonomic loading and unloading methods if relevant.
- Ensuring the safety of nearby personnel when the robot is accelerating, braking, and maneuvering.
- Marking operating hazard zones.

Operators

Operators have thorough knowledge of MiR1350 and of the safety precautions presented in this user guide. Operators have the following main tasks:

- Servicing and maintaining MiR1350.
- Creating and changing missions and map features in the robot interface.

Direct users

Direct users are familiar with the safety precautions in this user guide and have the following main tasks:

- Assigning missions to MiR1350.
- Fastening loads to MiR1350 securely.
- Loading and unloading from a paused robot.

All other persons in the vicinity of MiR1350 are considered indirect users and must know how to act when they are close to the robot. For example, they must be aware that visibly marked operating hazard zones must be respected.

4.5 Foreseeable misuse

Any use of MiR1350 deviating from the intended use is deemed as misuse. This includes, but is not limited to:

- Using the robot to transport people
- Using the robot on inclines outside the robot's specifications
- Making changes to the SICK configuration

- Driving the robot on cross slopes
- Exceeding the maximum payload
- Positioning or fastening loads incorrectly according to the specifications—see [Payload distribution on page 239](#)
- Using Emergency stop buttons for anything other than emergency stops
- Using the robot in medical and life critical applications
- Operating the robot outside the permissible operating parameters and environmental specifications
- Using the robot in potentially explosive ATEX environments
- Using the robot outdoors
- Using the robot in hygiene zones
- Using the robot together with an external radio module that in any way results in simultaneously active radio transmitters

The following list gives examples of custom modules that are foreseeable misuse of MiR1350:

- Top modules (including the payload) that increase the physical dimensions of MiR1350
- Conveyers (powered and non-powered)
- Industrial robot arms
- Devices that tow carts
- Customized load transfer stations
- Top modules or modifications that use additional antennas or result in transmitting radio signals simultaneously with the existing radio module.

4.6 Warning label

MiR1350 is supplied with a warning label that specifies that it is strictly prohibited to ride on the robot.

The label must be placed on the robot or top module so that it is clearly visible.



Figure 4.1. The warning label must be placed on the robot or top module.

4.7 Residual risks

Mobile Industrial Robots has identified the following potential hazards that commissioners must inform personnel about and take all precautions to avoid when working with MiR1350:

- You risk being run over, drawn in, trapped, or struck if you stand in the path of the robot or walk towards the robot or its intended path while it is in motion.
- You risk being run over, drawn in, trapped, or struck if you stand in the path of the robot or walk towards it while it is driving in reverse. The robot only drives in reverse when undocking from a marker, such as a charging station or load transfer station.
- You risk being crushed or trapped if you touch the robot while it is in motion.
- You risk being crushed or trapped if the robot places a load outside a designated drop-off area due to faulty localization.
- You risk losing control of the robot if it is accessed by unauthorized users. Consider increasing the IT security of your product—see [Cybersecurity on page 84](#).



NOTICE

Other significant hazards may be present in a specific robot installation and must be identified during commissioning.

5. Accessing the internal parts

Most internal parts of MiR1350 are accessed through maintenance hatches that open to different compartments.



CAUTION

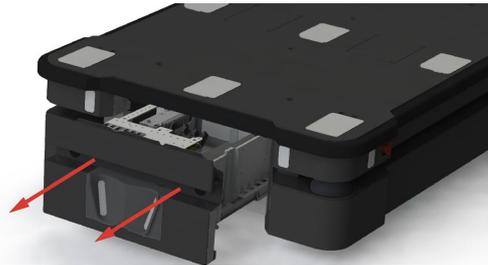
Opening or removing hatches from the robot exposes parts connected to the power supply, risking damage to the robot from a short circuit and personnel getting burnt.

- Before removing any covers, turn off the robot, and disconnect the battery—see [Disconnecting the battery on page 80](#).

5.1 Front compartment



To open the front compartment, turn the two screws 90° with a flat-head screwdriver, and pull out the compartment.

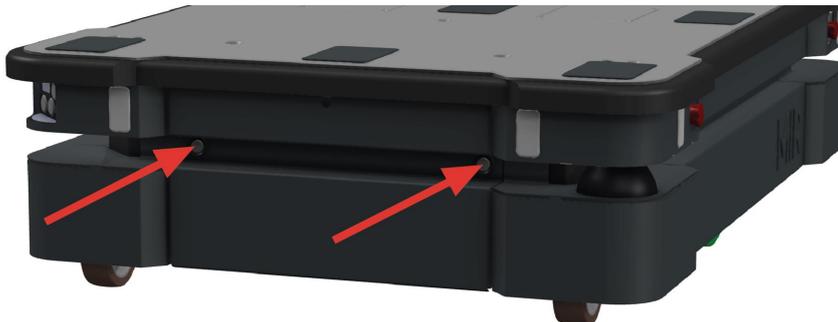


5.2 Rear compartment

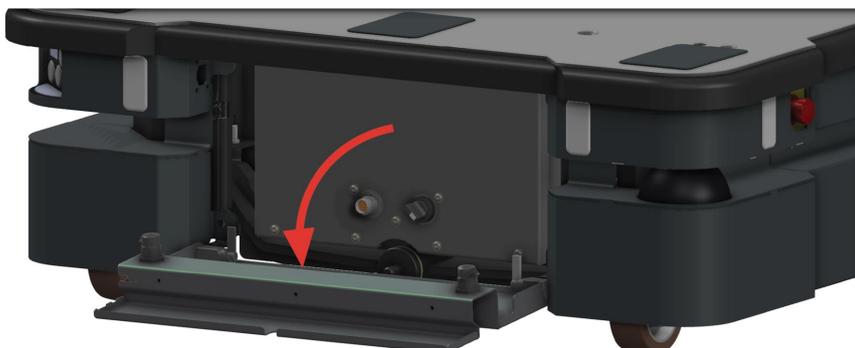


To open the rear compartment, follow these steps:

1. Push the two white buttons to unlock the hatch.



2. Pull open the hatch.

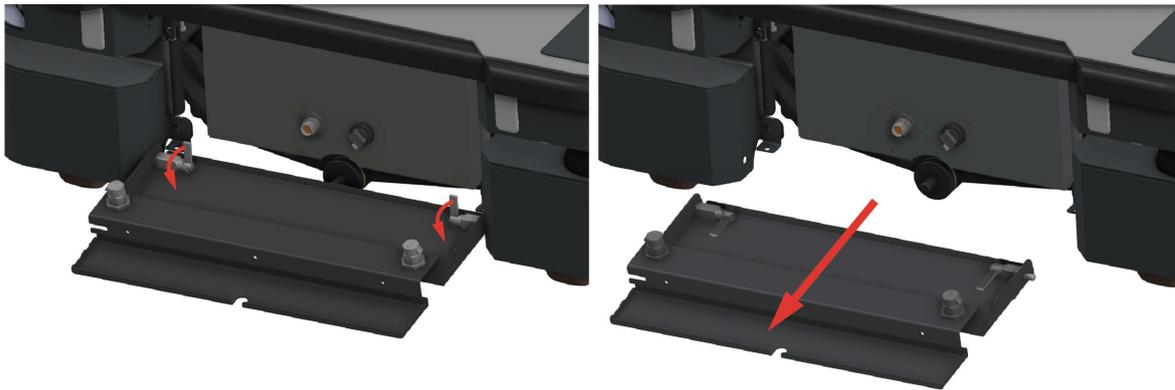


You can now access the Manual brake release switch and MiR Controller interface. To access the motor controller carrier board and dynamic brake contactors, follow these steps:

3. Disconnect the status light connector.



4. Remove the hatch by twisting the two hinges.



5. Remove the seven screws on the rear panel.



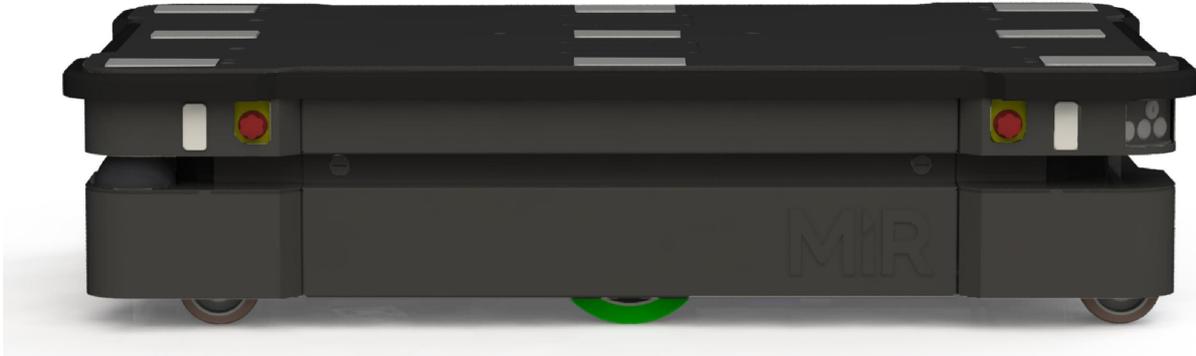
6. Loosen the top three screws while holding the bottom of the panel.



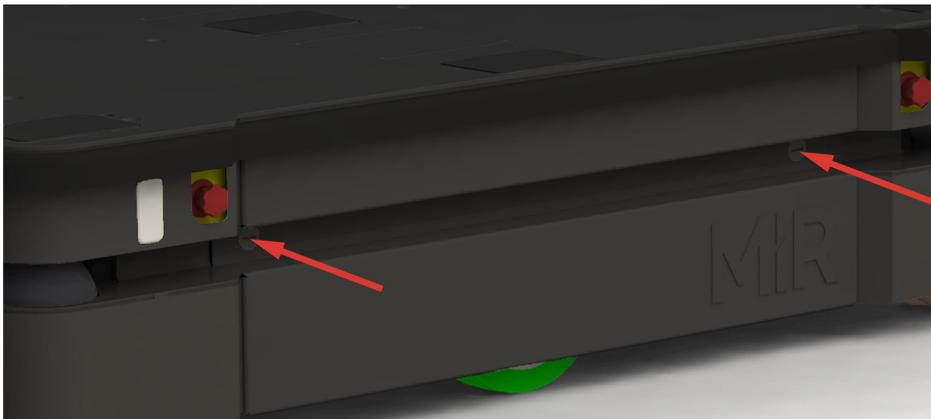
7. Remove the panel by sliding it downwards and out to access the rear maintenance compartment.



5.3 Side compartments



To open a side compartment, push the two white buttons to unlock the hatch, and pull it open.



5.4 Top compartments

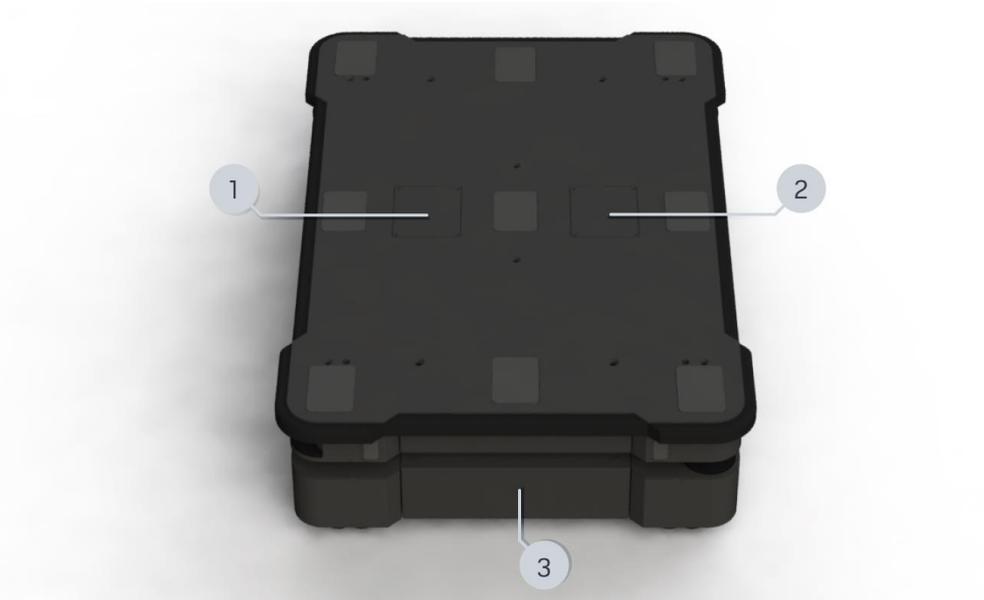
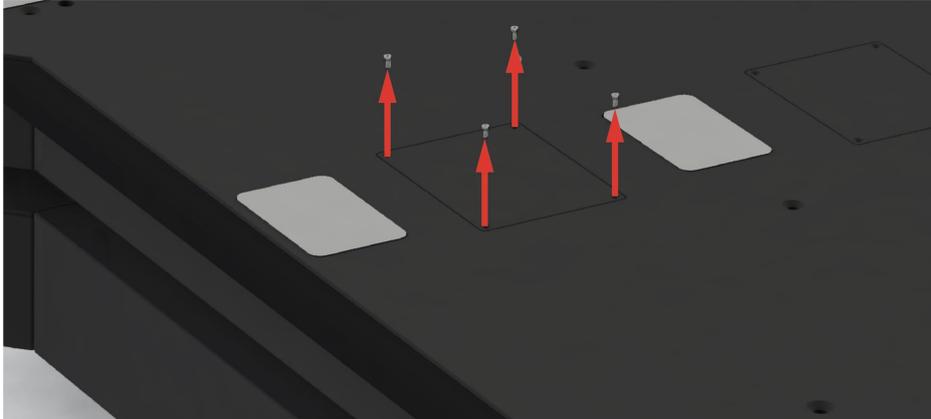


Figure 5.1. The top compartments on the robot.

Table 5.1. Identification of top compartments in <i>Figure 5.1</i>			
Pos.	Description	Pos.	Description
1	Left top compartment	2	Right top compartment
3	Rear compartment		

To open a top compartment, remove the four screws and lift off the top cover.



6. Getting started

This section describes how to get started with MiR1350.



NOTICE

To be able to use MiR1350, your robot must be running software version 2.12.0 or higher.



NOTICE

Read [Safety on page 32](#) before powering up MiR1350.



In some images in this section, the robot is shown with a MiR EU Pallet Lift 1350 top module.

6.1 In the box

This section describes the contents of the MiR1350 box.



Figure 6.1. The box containing the robot and accessories.

The box contains:

- The MiR1350 robot
- Adapter cable to connect a cable charger directly to the battery—see the *MiR 48V Battery Technical Guide* for intended use and instructions
- High visibility stickers

- A MiR1350 document folder containing a USB flash drive and the following printed documents:
 - *MiR1350 Quick Start*
 - *The CE Declaration of Conformity* for your robot
 - *Getting the robot online*
 - *Passwords*
 - *Unpacking note*
 - The unique nameplate for your robot
- The USB flash drive in the document folder has the following content:
 - *MiR1350 User Guide*
 - *MiR1350 Quick Start*
 - *MiR Network and WiFi Guide*
 - *MiR Cybersecurity Guide*
 - *MiR Robot Reference Guide*
 - *Getting the robot online*
 - *CE Declaration of Conformity*

6.2 Unpacking MiR1350

This section describes how to unpack the robot.



Keep the original packaging for future transportation of MiR1350.

To unpack the robot, follow these steps:

1. Place the box with the robot so that there is at least three meters of free space at the front or the back of the box. This is necessary as the robot drives out of the box on a ramp.

2. Remove the screws that attach the walls of the box to the box lid and the base of the box.



3. Remove the lid from the box, and remove the wooden lath beneath the lid.



4. Place the lid of the box so that you can use it as a ramp. Align the lid so that it is flush with the base of the box.



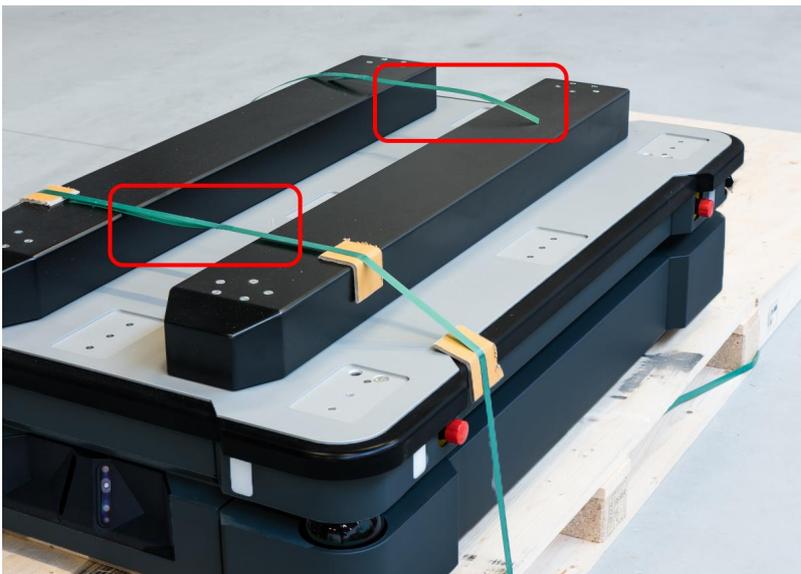
5. Take the folder with the printed documents and the USB flash drive out of the box.



6. Remove the pallet collars and the protective foam blocks.



7. Cut the protective straps.



For increased visibility, you can add the supplied high visibility stickers to the four corners of the robot.



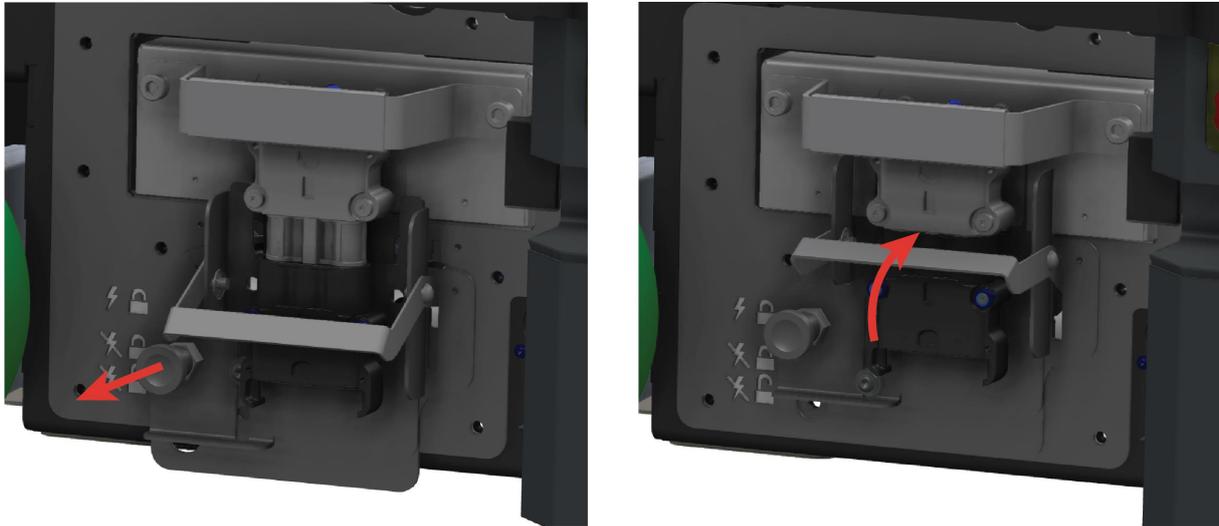
8. Remove the wheel stop board from the pallet to let the robot drive on the ramp.



6.3 Connecting the battery

To connect the battery to the robot, you need to open the left side compartment—see [Accessing the internal parts on page 43](#).

Once you have accessed the left side compartment, pull the Battery lock pin out, and pull the Battery lever to the top position. The battery is now connected, and you can close the side maintenance hatch.



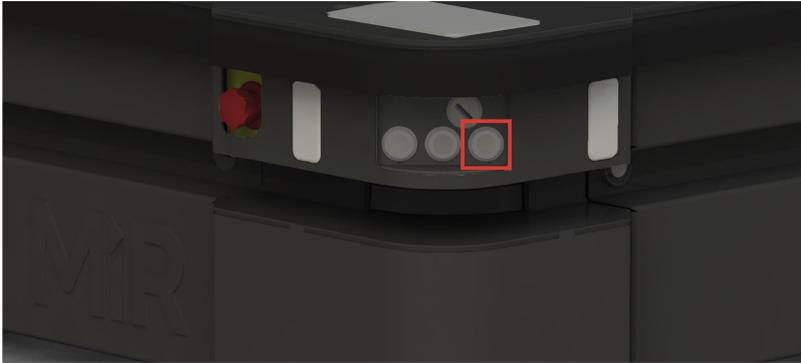
6.4 Powering up the robot

To power up the robot, follow these steps:

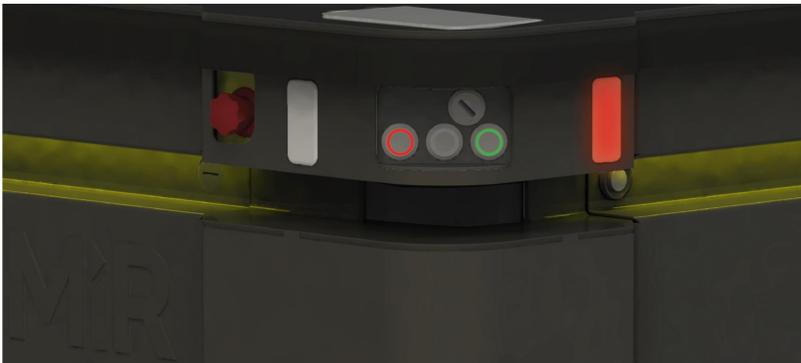
1. Ensure that all four Emergency stop buttons are in the released state. Turn an Emergency stop button counter-clockwise to release it.



2. Press the Power button for five seconds.



The robot turns on the red signal lights and the yellow wavering status lights and starts the software initialization process.



When the initialization process ends, the robot goes into Protective stop.

3. Press the Resume button to clear the Protective stop.



The robot is now ready for operation.



If you are not able to power up the robot upon delivery, see [MiR 48V Battery Technical Guide](#) to troubleshoot the issue.

6.5 Connecting to the robot interface

When the robot is turned on, you can connect a PC, tablet, or phone to the robot's internal network via the RJ45 Ethernet port under the bumper on the front-right corner shield of the robot. Once connected, you can configure the robot's settings and connect it to a wireless network.

You can connect to the robot using an Ethernet cable or an access point. If you are located in North America, EU, or a part of EAC, you can purchase a MiR Access Point from MiR. Outside these areas, you need to use your own

access point that is approved for use in your region. If you choose to use an access point, you must ensure that the robot is disconnected from the wireless network before attaching the access point to remain compliant—see [Connecting the robot to a WiFi network on page 64](#).



The robot is certified to have only one radio module active at any given time.



Whether you connect via Ethernet cable or an access point dongle, it is recommended that the client is configured to DHCP. See the documentation of your operating system.



If you require a static IP on the client, assign an address above 192.168.12.150 and set the DNS server and Gateway address to 192.168.12.1. See the documentation of your operating system.



WARNING

Harmful electromagnetic interference might be the result of having two radio modules transmitting at the same time.

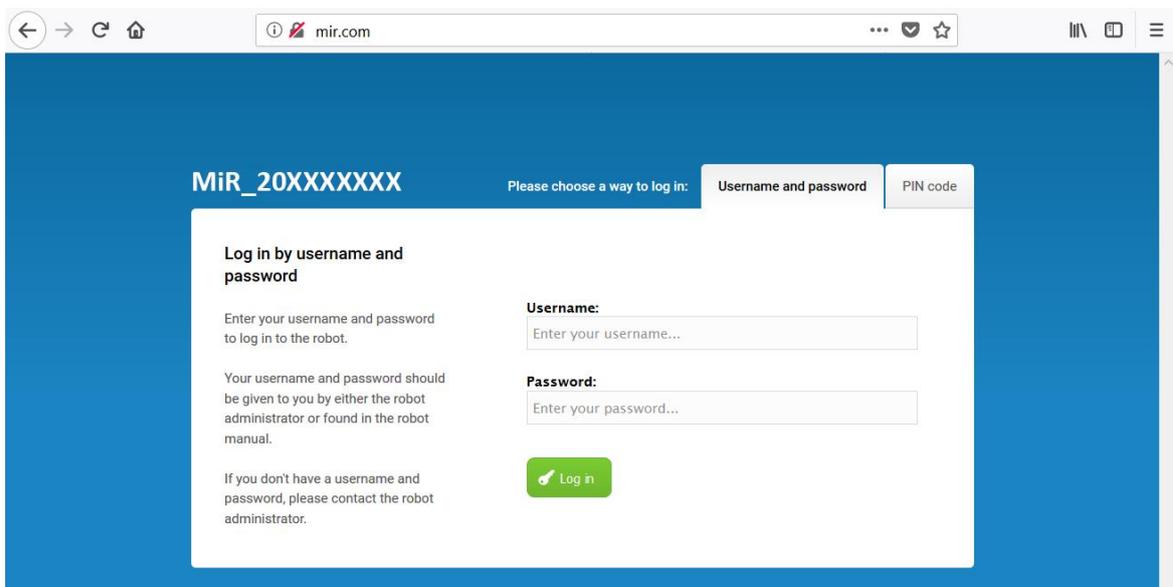
- Do not attach an access point or additional radio modules to the robot while it is connected to a wireless network.

To connect to the robot interface, follow these steps:

1. Locate the RJ45 Ethernet port under the bumper on the front-right corner shield of the robot.



2. Connect your device directly to the robot using an Ethernet cable, or connect an access point to the Ethernet port for a wireless connection.
3. If you are using an access point, connect your device to the access point. The MiR Access Point WiFi has the following format: **MiR_3042XXXXX**. Use the password shipped with the access point to connect.
4. In a browser, go to the address **mir.com** and sign in.



You are now signed in to the robot interface and can set up your robot for operation.

If you want to connect the robot to your local WiFi network, connect the robot to the network as described in [Connecting the robot to a WiFi network on the next page](#).

If you want to drive the robot off the pallet immediately, you can do so from the interface as described in [Driving the robot in Manual mode on page 68](#).



If you are going to drive the robot manually and you are using an Ethernet cable to connect to the robot, make sure that the cable you have used is long enough for the robot to move without disconnecting the cable.



Always make sure your robot is running the latest recommended software. This also applies to newly supplied robots, as there may have been important software updates during the storage time and shipment of the robot. Contact your distributor for the latest recommended update file.

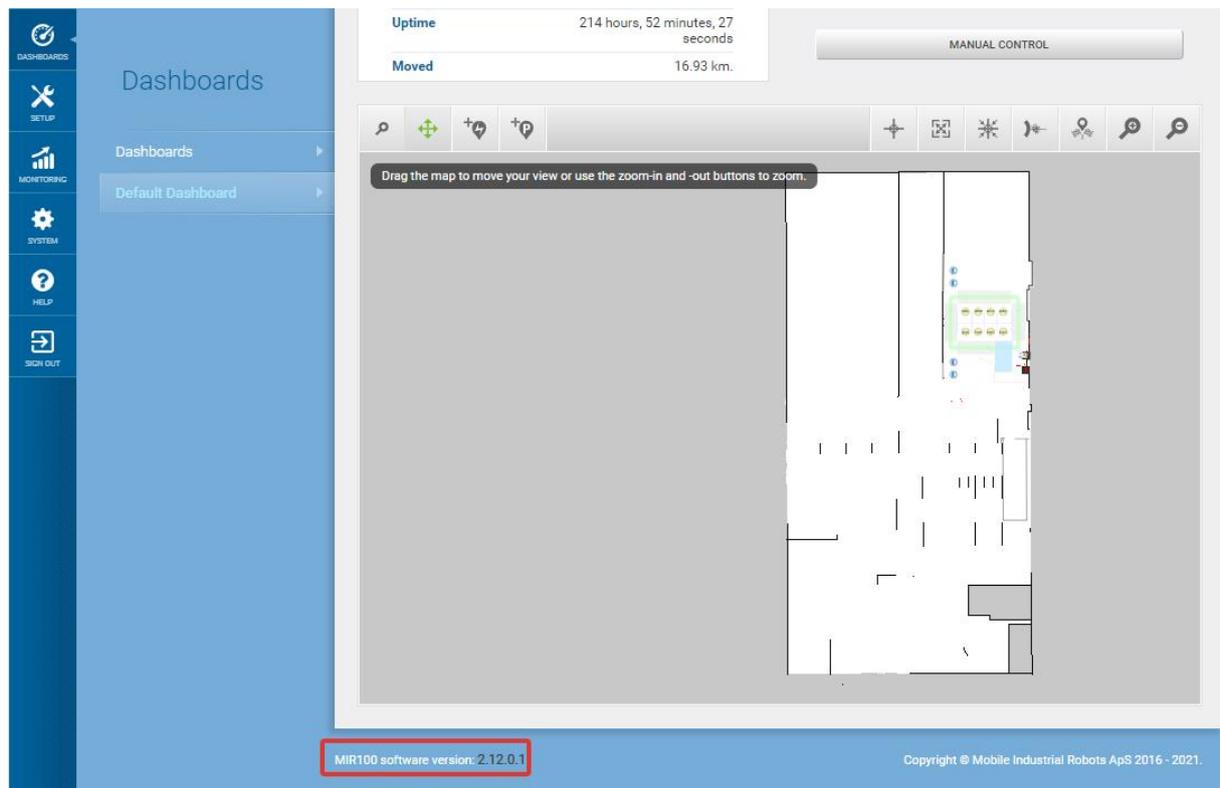


Figure 6.2. You can see the software version your robot is running in the bottom left corner of the robot interface.

6.6 Connecting the robot to a WiFi network

To communicate with the robot wirelessly without using an access point dongle, connect the robot to your local WiFi network. This enables you to access the robot interface via your WiFi network by entering the assigned IP address of your robot in a web browser.

To connect the robot to a WiFi network, follow these steps:

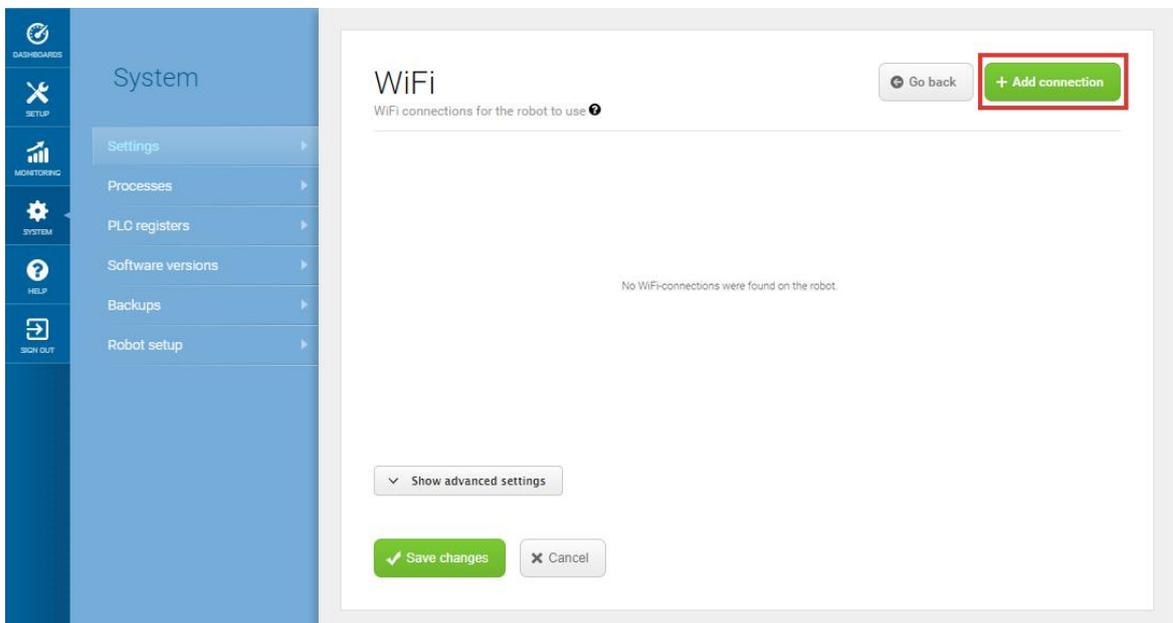
1. Connect to your robot as described in [Connecting to the robot interface on page 60](#).



NOTICE

To comply with the robot's certification, you must use an Ethernet cable to avoid simultaneously active radio transmitters while setting up connection to the local WiFi network.

2. Go to **System > Settings > WiFi**, and select **Add connection**.



3. Select the network you want the robot to be connected to, and fill out the displayed fields—see the guide *How to connect a MiR robot to a WiFi network* for more information about the WiFi settings.

Add connection

You can set up new WiFi connections by selecting from a list of available wireless networks.

Select a network:

MIR

Security type:

WPA/WPA2 Enterprise TLS

Username:

Password:

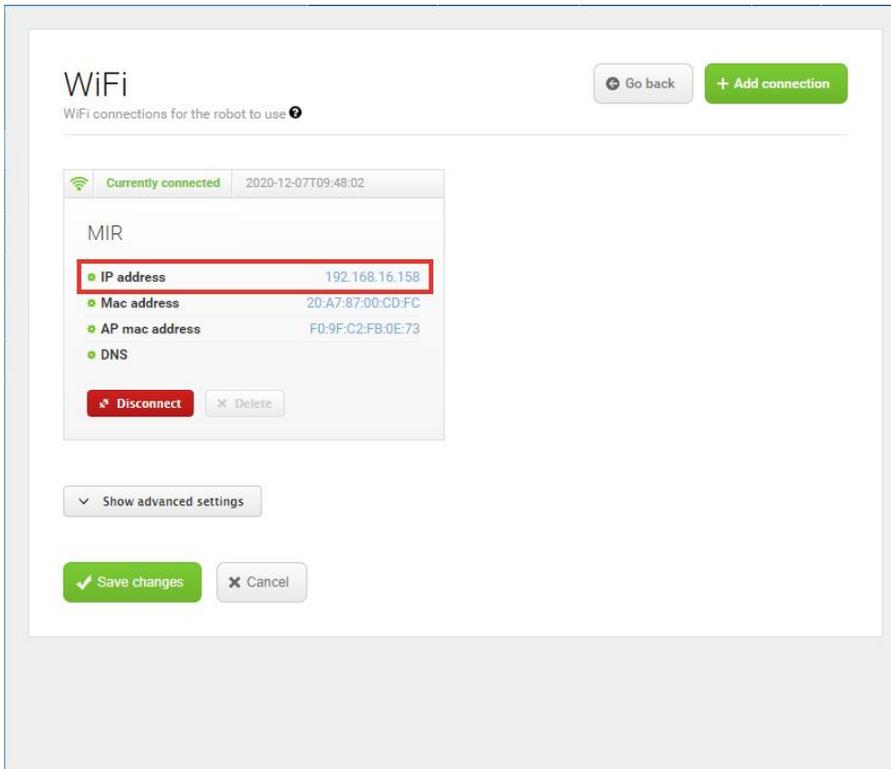
DNS servers

Certificate:

No file chosen

Use static IP

4. Select **Add connection** when you have finished. The robot is now connected to the network. When you are connected to the same network, you can access the robot's interface by entering the IP address displayed under the connection description into your internet browser.



To disconnect the robot from a WiFi network, select **Disconnect**.

6.7 Driving the robot in Manual mode



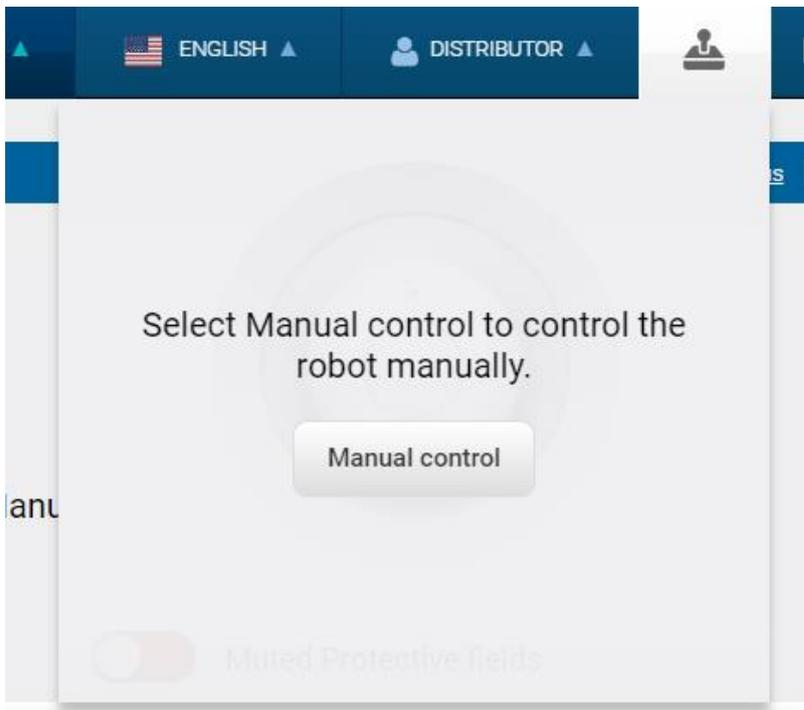
CAUTION

When driving the robot in Manual mode, it is possible to mute the Protective fields and drive the robot into Forbidden zones and Unpreferred zones on the map. This means that the robot will not stop for physical objects and will not respond to zones on the map. This can result in injury to personnel or damage to equipment if the robot is not driven carefully.

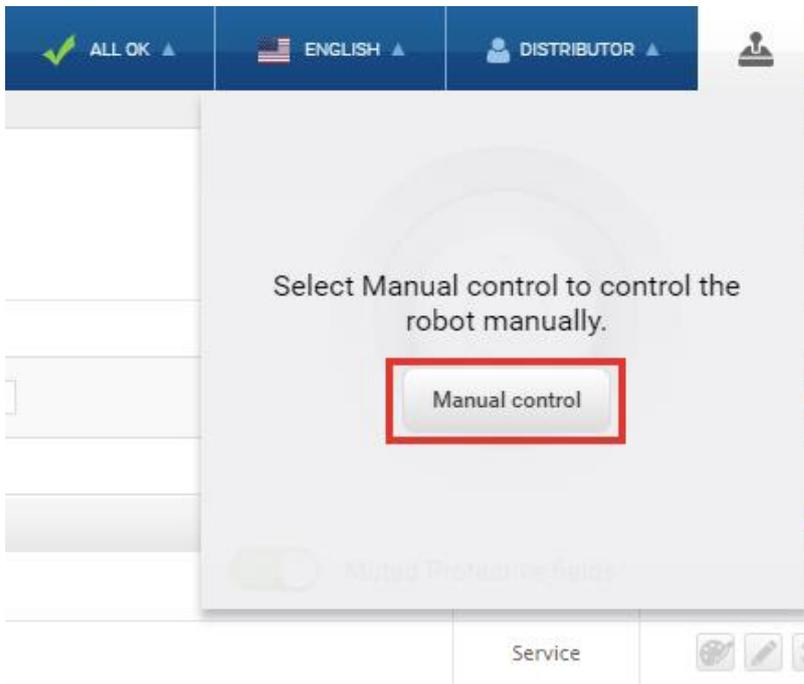
- Drive carefully to avoid collisions with any personnel or objects when driving the robot in Manual mode.
- Avoid driving the robot manually without a clear visual of the robot.

To drive the robot in Manual mode, follow these steps:

1. On the robot, turn the Operating mode key to Manual mode (turn it to the right).
2. In the robot interface, select the joystick icon.



3. Select **Manual control**. The Resume button on the robot starts blinking.



4. On the robot, press the Resume button. The status lights turn blue, indicating that the robot is in Manual mode.



The robot is shown with an EU pallet lift.



5. Drive the robot off the ramp using the joystick.



Place your foot in front of the ramp while the robot drives on it to keep the ramp from slipping.



6.8 Checking the hardware status

To check that all hardware components work as intended, follow these steps:

1. Sign in to the robot interface—see [Connecting to the robot interface on page 60](#).
2. Go to **Monitoring > Hardware health**.

3. Check that all elements on the page have the **OK** status and that they have green dots on the left.



For more information, see [Error handling on page 266](#).

6.9 Mounting the nameplate

Before using MiR1350, you must mount its unique nameplate to it. The nameplate contains information specific to your MiR application—see [Nameplate on page 19](#).



NOTICE

The nameplate must be mounted as described in the following steps. If mounted incorrectly, the CE mark is invalid.

To mount the nameplate correctly, follow these steps:

1. Locate the right side hatch—see [External parts on page 16](#).
2. Clean the area marked in the image below with a degreasing agent.



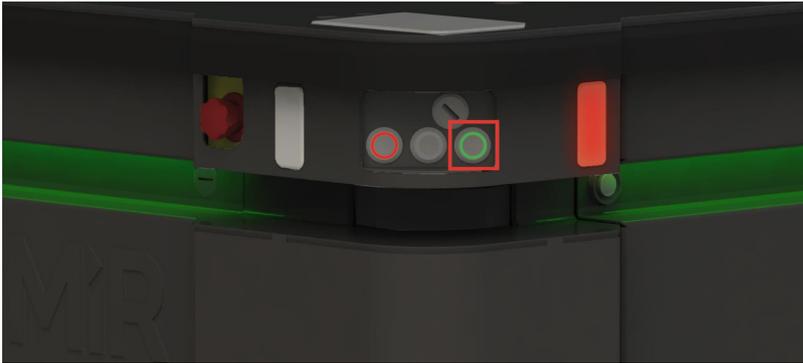
3. Mount the nameplate on the cleaned area.



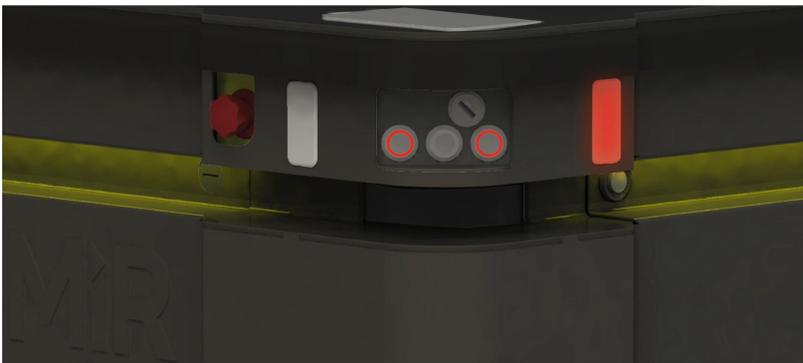
6.10 Shutting down the robot

To shut down MiR1350, follow these steps:

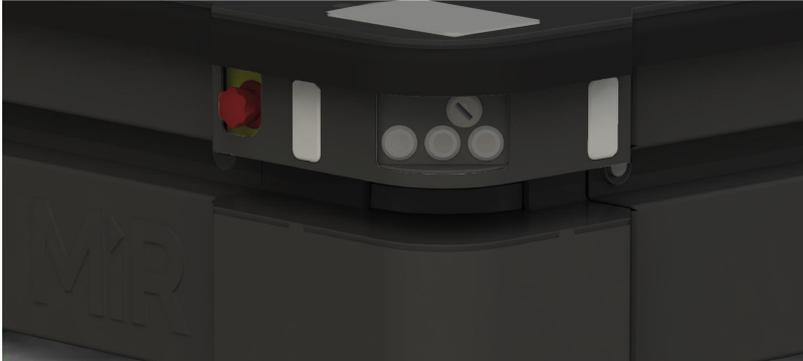
1. Ensure that the robot is not moving or executing an action.
2. Press the Power button for three seconds.



3. Wait for the robot to finish the shutdown process. The status lights waver yellow, and the Power button blinks red.



When the robot finishes the shutdown process, the status and signal lights go off.



When you shut down the robot for transportation, service, or repair, the battery must be disconnected—see [Disconnecting the battery on page 80](#).

7. Battery and charging

The robot is powered by a lithium battery that can be charged with a MiR cable charger or a MiR Charge 48V charging station.

Table 7.1 identifies the main components of the battery fast-swap assembly and describes the three different positions the assembly can be set to.

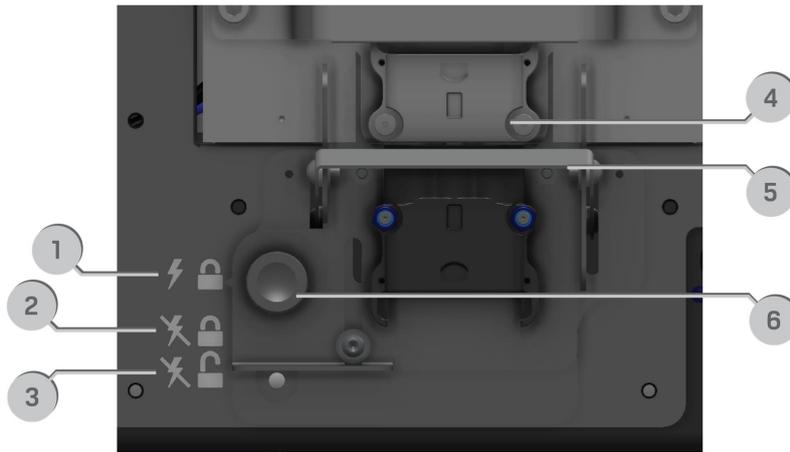


Figure 7.1. The main components of the Fast-swap battery assembly.

Table 7.1. Identification of components in <i>Figure 7.1</i>			
Pos.	Description	Pos.	Description
1	Top position: The battery is locked and connected. Use this position when you want to operate the robot.	2	Center position: The battery is locked and disconnected. Use this position when servicing or transporting the robot.
3	Bottom position: The battery is unlocked and disconnected. Use this position when removing the battery from the robot.	4	Battery connector: Connects the battery to the robot.

Pos.	Description	Pos.	Description
5	Battery lever: Used to change between top, center, and bottom positions.	6	Battery lock pin: Pull the pin out to enable you to move the Battery lever between positions.



NOTICE

Do not parallel couple the battery with more batteries. Parallel coupled batteries will result in the batteries shutting down.

7.1 Charging the robot

This section describes how to charge MiR1350 using a MiR cable charger.



NOTICE

The most efficient way to charge MiR robots is with MiR charging stations. Cable chargers are intended as a backup solution as they charge significantly slower than charging stations, and because they can only charge the robot's battery to 80–90%.



A MiR cable charger is not part of the MiR1350 standard delivery. Contact your distributor for more information.



To charge MiR1350 with a standard MiR cable charger, you will also need an adapter for the cable to fit to the battery connector. The adapter is supplied by MiR.



The robot is delivered 40-60% charged.



CAUTION

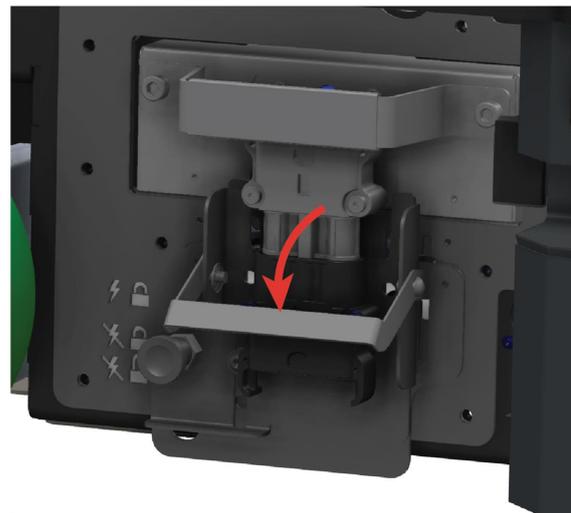
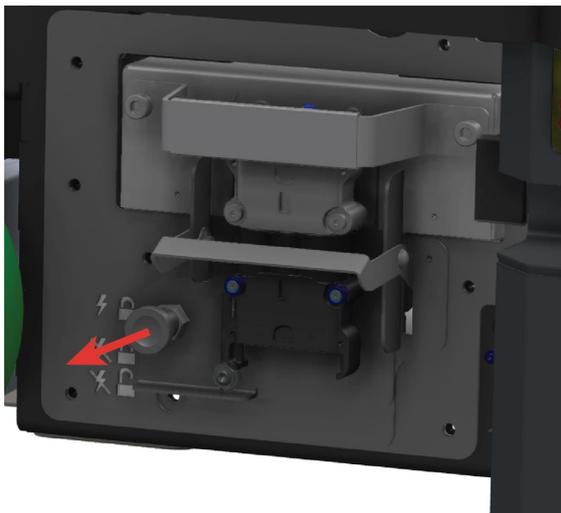
Charging the robot with a charging station and a cable charger simultaneously can damage the battery.

- Never charge with two chargers simultaneously.

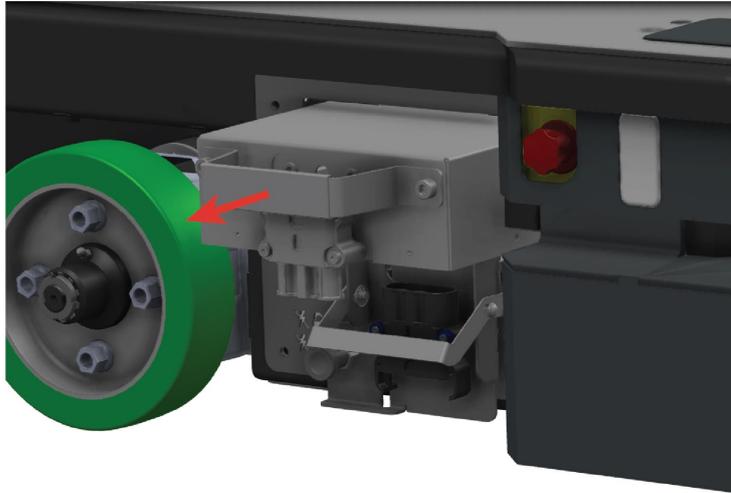
The left side compartment holds the robot's battery. To access the side compartments, see [Accessing the internal parts on page 43](#).

To charge MiR1350 using the cable charger, follow these steps:

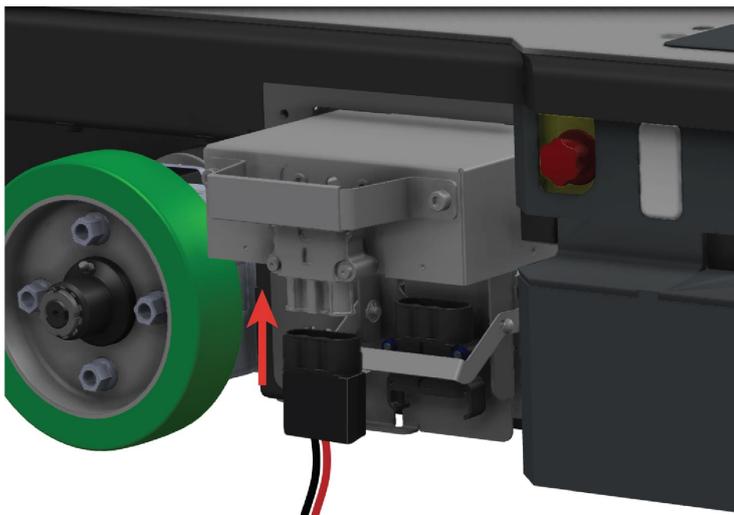
1. Plug the cable charger into an AC power supply. Always make sure to connect the cable charger to a power supply before connecting it to the battery. Over time, the battery cells may get damaged if you connect the charger to the battery before the power supply.
2. Connect a battery adapter to the other end of the cable charger.
3. On the robot, pull out the Battery lock pin, and pull the Battery lever down to the bottom position. The battery is now disconnected and unlocked.



4. Grab the handle, and pull the battery out approximately 10 cm.



5. Connect the adapter from the cable charger directly to the battery connector. The charger should begin humming once it starts charging the battery.



Use only an original MiR cable charger.

Once the battery has finished charging, reconnect the battery, and close the maintenance hatch.

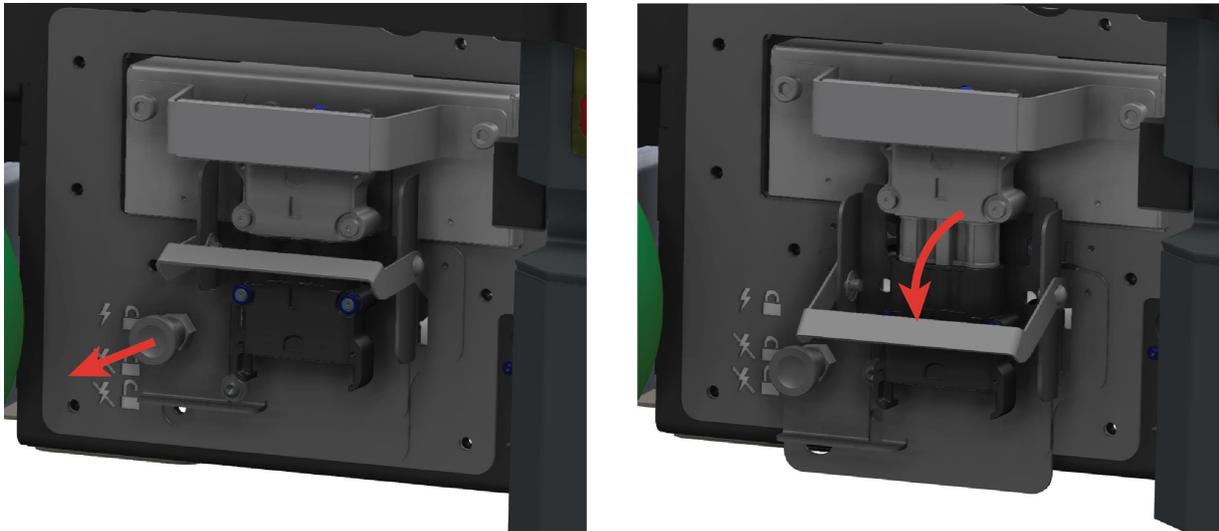
For information about the charging time, see specifications on the MiR website.

7.2 Disconnecting the battery

Whenever the robot is to be transported, undergo maintenance, or stored for over 24 hours, you should always disconnect the battery.

The left side compartment holds the robot's battery. To access the side compartments, see [Accessing the internal parts on page 43](#).

To disconnect the battery, pull out the Battery lock pin, and pull the Battery lever down to the center position. The battery is still securely locked in the robot but is no longer connected electrically.



7.3 Swapping out the lithium-ion battery

MiR1350 is supplied with a removable lithium-ion battery.

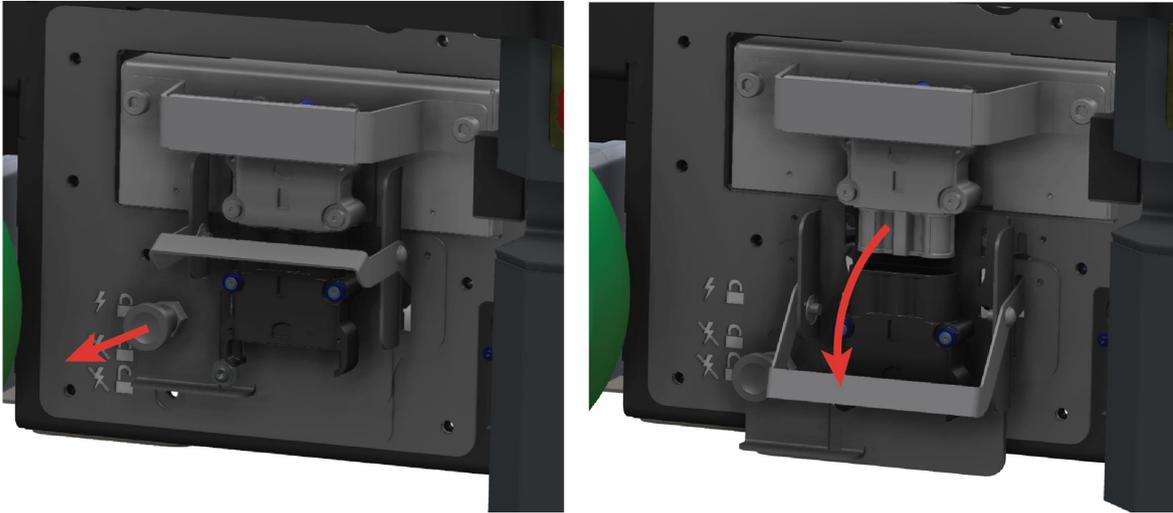


The robot is delivered with one lithium-ion battery. Contact your distributor if you need more batteries.

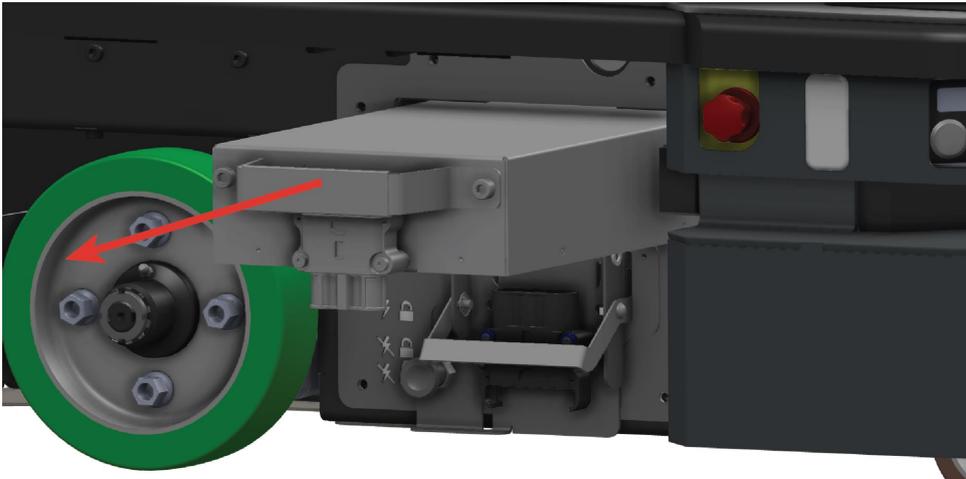
The left side compartment holds the robot's battery. To access the side compartments, see [Accessing the internal parts on page 43](#).

To swap out the battery, follow these steps:

1. Pull out the Battery lock pin, and pull the Battery lever down to the bottom level. The battery is now disconnected and unlocked from the robot.



2. Grab the handle and gently pull the battery out.



3. Insert another battery.
4. Pull out the Battery lock pin, and pull the Battery lever up to the center position to lock the battery in place or to the top position to lock and connect the battery to the robot.

7.4 Battery storage

If you are storing the robot's battery for any duration, we recommend the following:

- The battery should be stored in an area at room temperature with a non-condensing relative air humidity—see specifications on the MiR website. Temperatures and humidity below or above the specifications will shorten the service life of the battery.
- The battery should not be exposed to nor submerged in any liquid as this may damage the battery.
- Charge the battery before storage.
- Check state of charge of the battery regularly and make sure to recharge the battery if the state of charge is low.
- Disconnect the battery from the robot before storing the robot.

If the battery is not used for a period of time, it can enter one of two states where it does not power the robot:

- If the battery percentage is not low, but has been unused for a period of time, the battery enters Power save mode. You can activate the battery again in two ways depending on the battery percentage:
 - Disconnect the battery from the robot for 30 seconds, reconnect it to the robot, wait 30 seconds, and then turn on the robot.
 - If the battery percentage is very low, you must either connect a 48V cable charger directly to the battery or connect MiR Cable Charger Lite 48V 3A to the robot's charging interface while the battery is connected to the robot.
- If the battery percentage is very low and the battery cells may soon take damage, the battery enters Deep sleep mode. Depending on how long the battery has been in Deep sleep, you may be able to revive it using MiR Cable Charger Lite 48V 3A.



To properly troubleshoot any battery issues and for the exact time periods and battery voltages that trigger the transitions between states, see *MiR 48V Battery Technical Guide*. These guides provide more detailed information about determining exactly which state the battery is in and how to safely and securely restore the battery without damaging the robot or battery.

7.5 Battery disposal

Legal obligations apply to used batteries. Used batteries must be recycled.

Disposing used batteries in the household waste is prohibited.

A recycling label indicates that the battery needs to be recycled and not disposed as municipal waste—see **Figure 7.2**

Contact your distributor to get specific information about their take back service.



Figure 7.2. Battery disposal symbols.

8. Cybersecurity

Cybersecurity in the context of MiR products means protecting IT (Information Technology) and OT (Operational Technology) assets from unauthorized access, use, disruption, modification, or destruction.

MiR1350 communicates all data over the network that it is connected to. It is the responsibility of the commissioner to ensure that it is connected to a secure network. MiR recommends conducting a cybersecurity risk assessment before commissioning MiR1350.

To ensure the cybersecurity of your MiR product, see *MiR Cybersecurity Guide* found on the USB drive shipped with MiR1350 and on the Support Portal.

9. Navigation and guidance system

The navigation and guidance system is responsible for driving the robot to a goal position while avoiding obstacles. This section describes the processes and components involved in the robot's navigation and guidance system.

9.1 System overview

The purpose of the navigation and guidance system is to guide the robot from one position on a map to another position. The user provides the map and chooses the goal position the robot must move to. The diagram in **Figure 9.1** describes the processes in the system.

The main processes involved in the navigation and guidance system are:

- **Global planner**
The navigation process starts with the global planner determining the best path for the robot to get from its current position to the goal position. It plans the route to avoid walls and structures on the map.
- **Local planner**
While the robot is following the path made by the global planner, the local planner continuously guides the robot around detected obstacles that are not included on the map.
- **Obstacle detection**
The safety laser scanners, 3D cameras, and proximity sensors are used to detect obstacles in the work environment. These are used to prevent the robot from colliding with obstacles.
- **Localization**
This process determines the robot's current position on the map based on input from the motor encoders, inertial measurement unit (IMU), and safety laser scanners.
- **Motor controller and motors**
The motor controller determines how much power each motor must receive to drive the robot along the intended path safely. Once the robot reaches the goal position, the brakes are engaged to stop the robot.

Each part of the process is described in greater detail in the following sections.

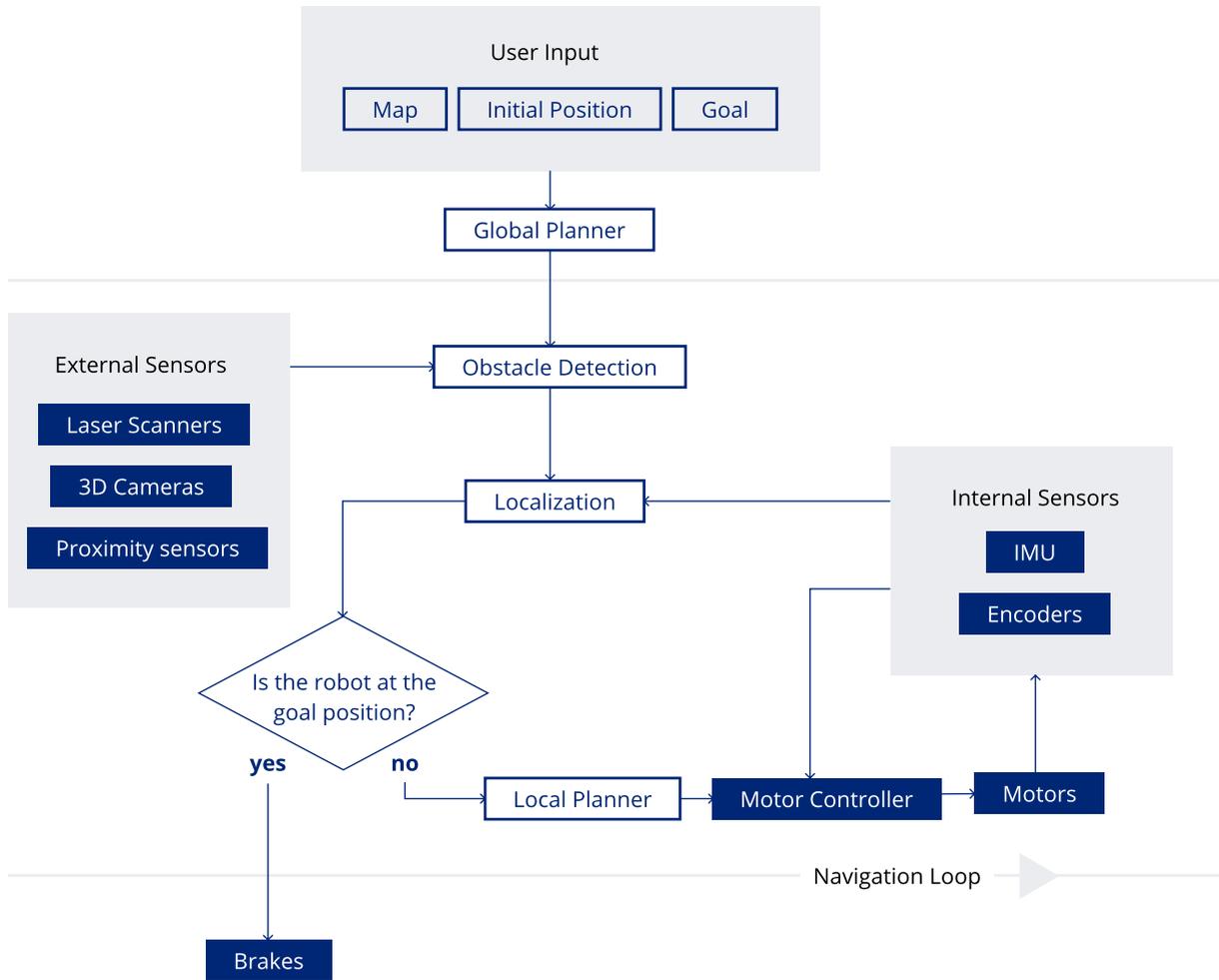


Figure 9.1. Flow chart of the navigation and control system. The user provides the necessary input for the robot to generate a path to the goal position. The robot executes the steps in the navigation loop until it reaches the goal position and stops by engaging the brakes.

9.2 User input

To enable the robot to navigate autonomously, you must provide the following:

- A map of the area, either from a .png file or created with the robot using the mapping function—see [Creating and configuring maps on page 143](#).
- A goal destination on that map—see [Markers on page 155](#).
- The current position of the robot on the map. This usually only needs to be provided when a new map is activated.

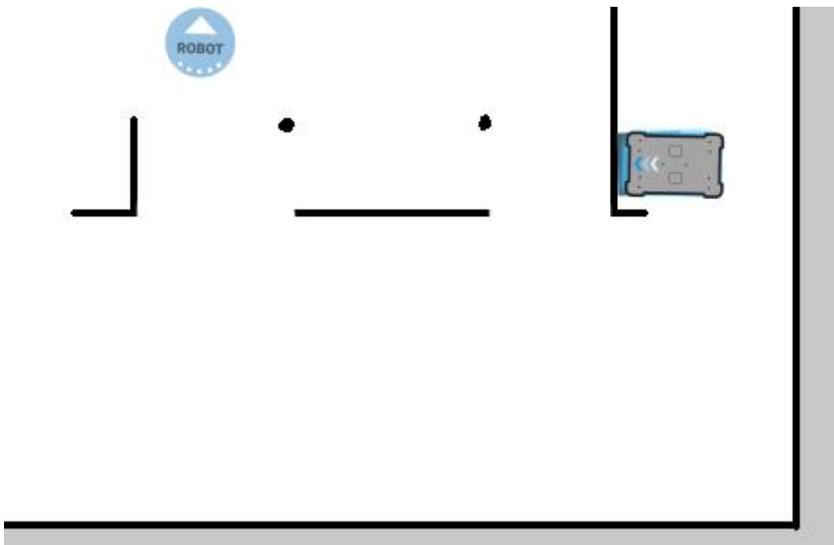


Figure 9.2. On the map, the current position of the robot is identified by the robot icon , and the goal destination in this example is the robot position . The robot computer now determines a path from the current position to the goal position.

Once the robot computer has a map with the robot's current position and a goal destination, it begins planning a route between the two positions on the map using the global planner.

9.3 Global planner

The global planner is an algorithm in the robot computer that generates a path to the goal position. This path is known as the global path.

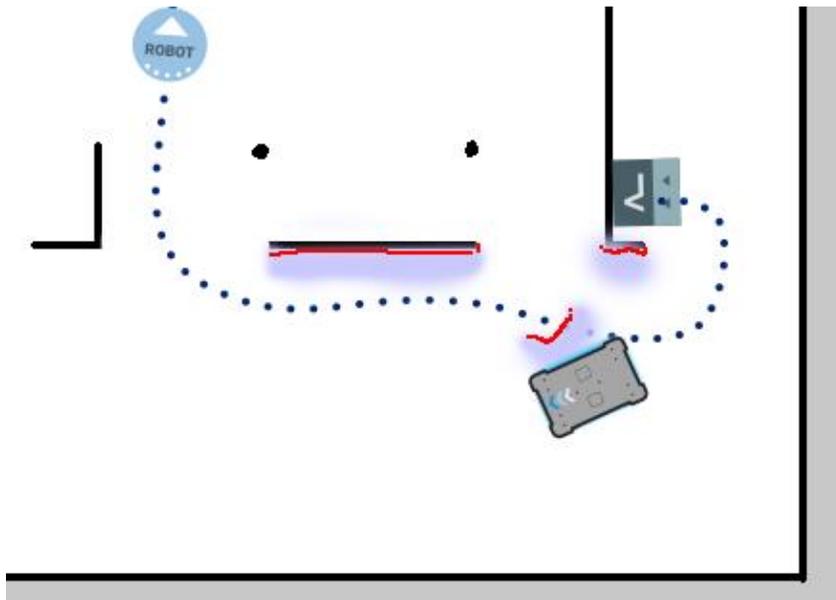


Figure 9.3. The global path is shown with the blue dotted line that leads from the start to the goal position.

The global path is created only at the start of a move action or if the robot has failed to reach the goal position and needs to create a new path. The generated path only avoids the obstacles the robot detected when the path was made and the obstacles marked on the map. The global path can be seen in the robot interface as a dotted line from the robot's start position to the goal position.

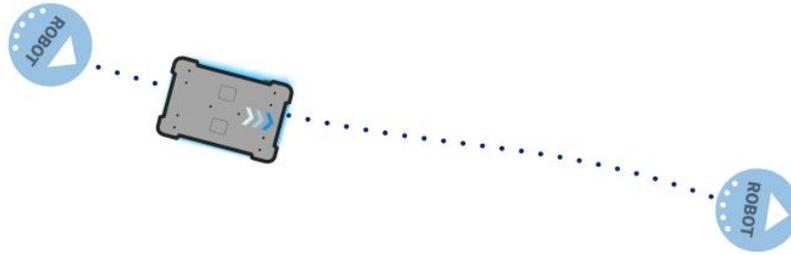


Figure 9.4. The dotted line from the start position of the robot to the goal position is the global path generated by the robot computer.

9.4 Local planner

The local planner is used continuously while the robot is driving to guide it around obstacles while still following the global path.

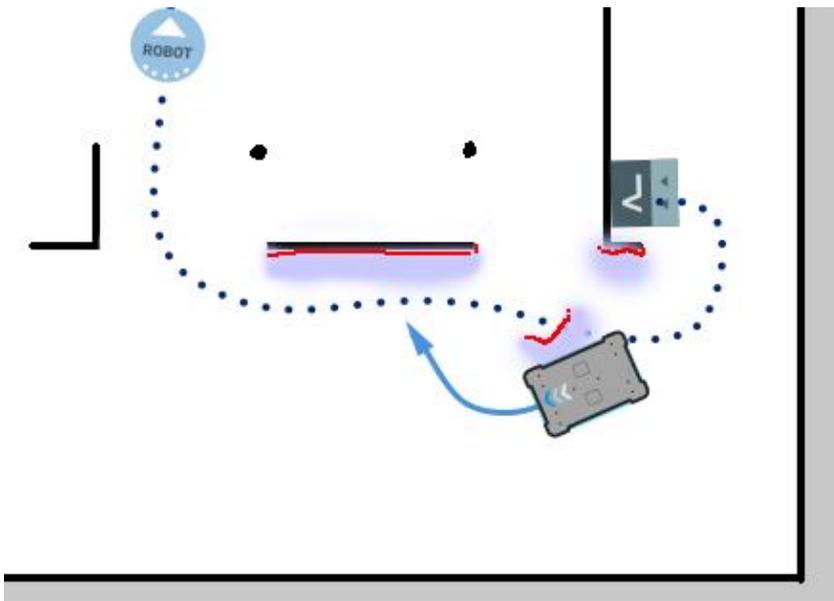


Figure 9.5. The global path is indicated with the dotted blue line and is visible on the map. The local path is indicated with the blue arrow, showing the robot driving around a dynamic obstacle.

Whereas the global planner creates a single path from start to finish, the local planner continues to create new paths that adapt to the current position of the robot and the obstacles around it. The local planner only processes the area that is immediately surrounding the robot, using input from the robot sensors to avoid obstacles.



The local path is not displayed in the robot interface. The arrows in the images here are visual aids used in this guide only.

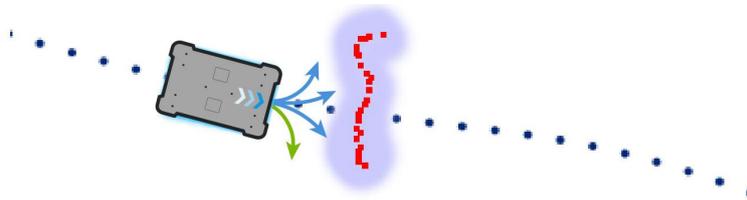


Figure 9.6. The local planner usually follows the global planner, but as soon as an obstacle gets in the way, the local planner determines which immediate path will get the robot around the obstacle. In this case, it will likely choose the path indicated with a green arrow.

Once the local path is determined, the robot computer derives the desired rotational velocity of each drive wheel to make the robot follow the local path and sends the desired velocities for each motor to the motor controllers—see [Motor controller and motors on page 102](#).

9.5 Obstacle detection

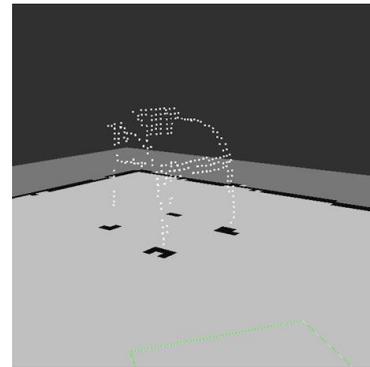
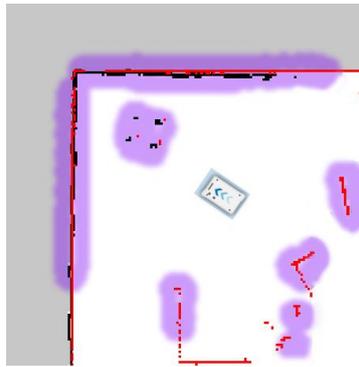
The robot detects obstacles continuously while driving. This enables the robot to use the local planner to drive around obstacles and to determine the robot's current position on the map.

Three sensor types are responsible for detecting obstacles:

- The safety laser scanners
- The 3D cameras
- The proximity sensors

Table 9.1.
Description of how the robot sees obstacles with its sensors

What a human sees	What the laser scanners see	What the 3D cameras see
-------------------	-----------------------------	-------------------------



A chair placed in the corner of a room is detectable by the robot.

In the robot interface, the red lines on a map are obstacles detected by the laser scanners, and the purple clouds are an aggregate of the 3D camera and laser scanner data. The scanners only detect the four legs of the chair.

The 3D cameras detect more details of the chair when the robot gets close enough to it. This view cannot be seen in the robot interface.

Safety laser scanners

Two safety laser scanners, diagonally placed on one front and one rear corner of the robot, scan their surroundings. Each safety laser scanner has a 270° field of view, overlapping and thus providing a full 360° visual protection around the robot—see **Figure 9.7**.

When in motion, the safety laser scanners continuously scan the surroundings to detect objects.

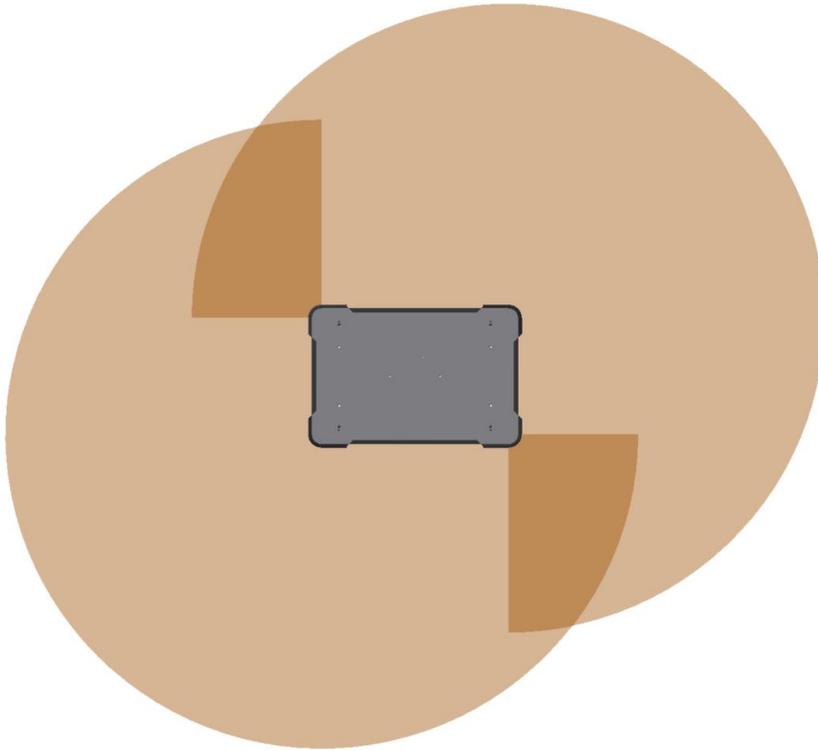


Figure 9.7. The two safety laser scanners together provide a full 360° view around the robot.



When mapping, the safety laser scanners' view is reduced to 20 m to ensure that maps get the highest possible quality.

The laser scanners have the following limitations:

- They can only detect objects that intersect a plane at 200 mm height from the floor.
- They do not detect transparent obstacles well.
- The scanner data can be inaccurate when detecting reflective obstacles.
- The laser scanners may detect phantom obstacles if they are exposed to strong direct light.



If you are using the robot in an area with walls made of glass or reflective material, mark the walls as Forbidden zones on the map, not as walls—see [Creating and configuring maps on page 143](#). Walls on the map that the robot cannot detect will confuse the robot's navigation system.

3D cameras

Two 3D cameras positioned on the front of the robot detect objects in front of the robot. The 3D cameras detect objects:

- Vertically up to 1800 mm at a distance of 1200 mm in front of the robot.
- Horizontally in an angle of 114° and 250 mm to the first view of ground.
- From the floor plane, the robot does not detect objects below 30 mm from the ground. This value increases by 10 mm per meter from the robot—see **Figure 9.9**.

The 3D cameras are only used for navigation. They are not part of the robot's safety system.



CAUTION

The 3D cameras cannot be used as a means for safety related risk reduction, for example, detecting low hanging obstacles. They cannot be used as an alternative to the Personnel detection safety function—see [Personnel detection on page 111](#). The robot may collide with and cause injury to personnel if you rely on the 3D cameras alone to detect personnel.

- Do not modify the safety laser scanner settings with the expectation that the 3D cameras will prevent collision with personnel.
- Do not include the 3D cameras as a risk reduction means in your risk assessment of the robot.



The camera readouts are used as 3D point cloud data. They are not recording recognizable objects or people.

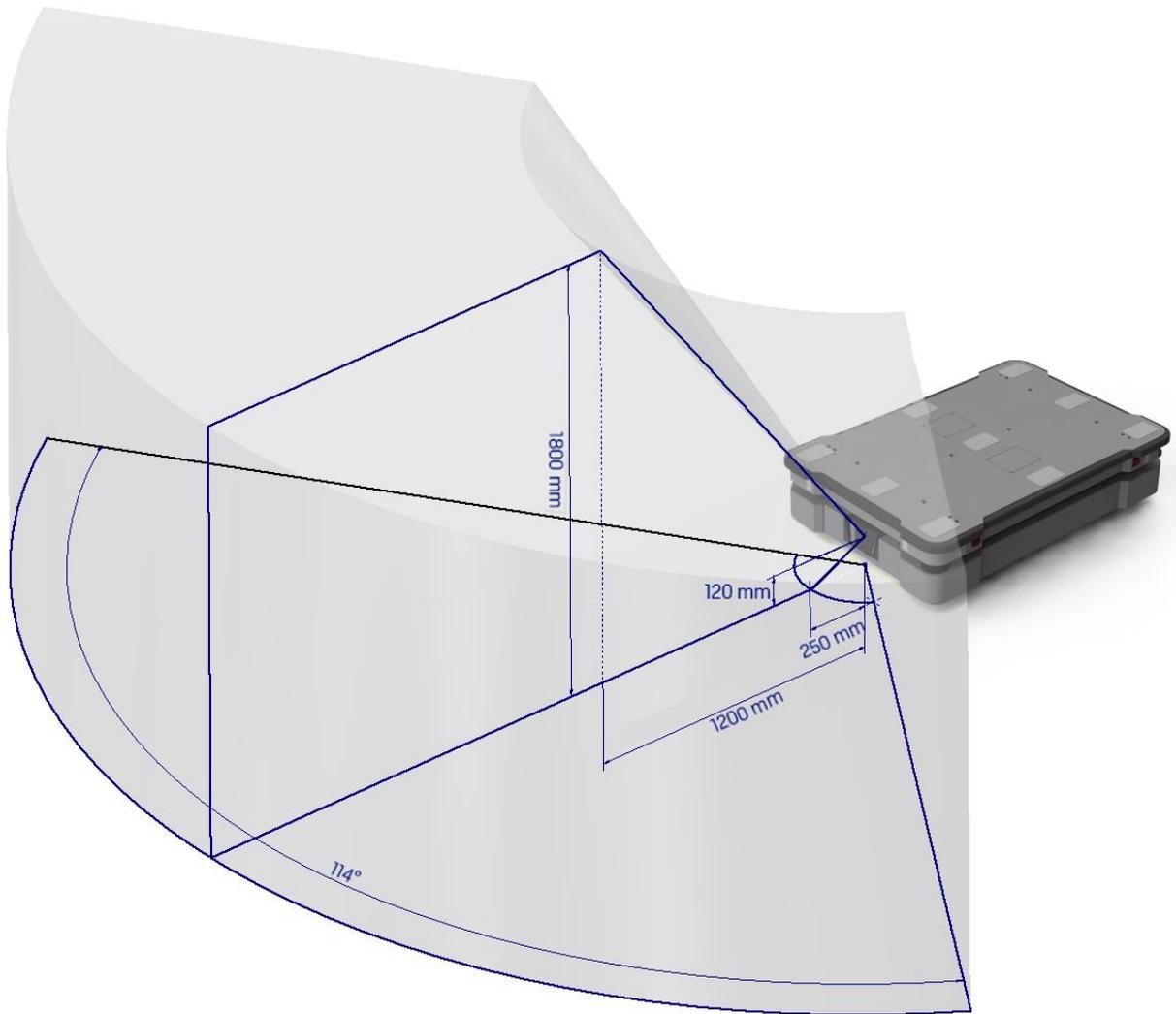


Figure 9.8. The two 3D cameras can see objects up to 1800 mm above floor height at a distance of 1200 mm in front of the robot and have a horizontal field of view of 114°.

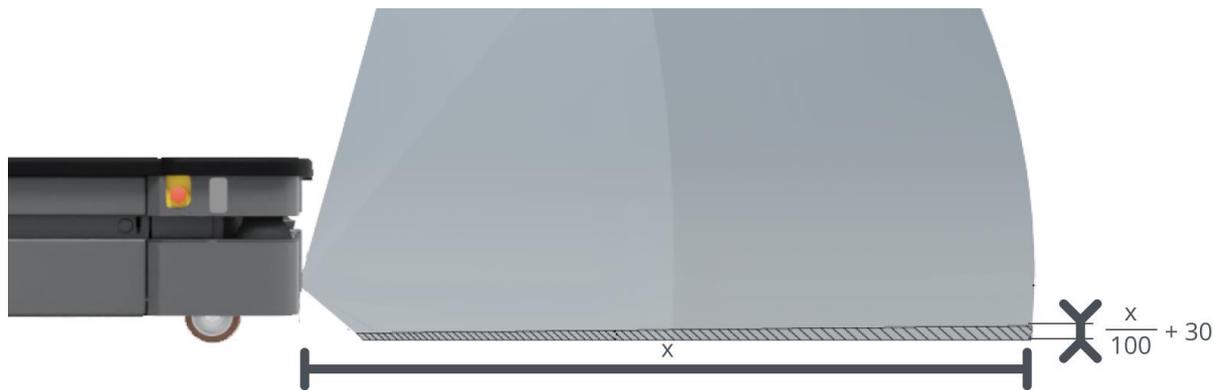


Figure 9.9. Objects below 30 mm from the ground are not detected by the camera. This value increases by 10 mm per meter from the robot.

The 3D cameras have the following limitations:

- They can only detect objects in front of the robot, unlike the full 360° view of the laser scanners.
- They do not detect transparent or reflective obstacles well.
- They do not detect holes or descending stairways.
- The cameras are not reliable at determining depth when viewing structures with repetitive patterns.
- The cameras may detect phantom obstacles if they are exposed to strong direct light.

Proximity sensors

Using infrared light, the proximity sensors point downwards and detect low objects around the corners of the robot outside the field of view of the safety scanners and 3D cameras.



Figure 9.10. The proximity sensors in the corners of the robot detect objects below the safety laser scanners' plane of view.

The main purpose of the proximity sensors is to detect low objects, such as pallets and forklift forks, placed close to the robot while it is standing still. When the robot begins to drive, it plans a path around the nearby detected obstacles.



The proximity sensors are disabled by default. To make the robot use the proximity sensor data, you must enable the sensors and calibrate them. For more information, contact your distributor for the guide *How to calibrate the proximity sensors*.

The following points describe the main features of the proximity sensors once they are enabled:

- The proximity sensors are constantly active.
- Because of the sensors' limited range, the data from them is only useful when the robot is standing still or moving at low speeds.
- The proximity sensors are most reliable at detecting objects while standing still. The faster the robot drives, the less reliable the sensor data becomes.
- The field of view of the proximity sensors does not span all the way around the robot. They are mainly focused around the robot corners.

- The proximity sensors are used for navigation, not safety. The robot does not enter Protective stop if the sensors detect an object. If the robot cannot navigate around an obstacle detected by the sensors, the robot reports an error that it cannot find a free path.
- The proximity sensors mitigate the risk of collision but cannot fully prevent it in all scenarios.



CAUTION

Proximity sensors cannot be used as a means for safety related risk reduction, for example, detecting feet. They cannot be used as an alternative to the Personnel detection safety function—see [Personnel detection on page 111](#). The robot may collide with and cause injury to personnel if you rely on the proximity sensors alone to detect personnel.

- Do not modify the safety laser scanner settings with the expectation that the proximity sensors will prevent collision with personnel.
- Do not include the proximity sensors as a risk reduction means in your risk assessment of the robot.

Besides preventing collision with low objects placed close to the robot upon movement after standstill, the proximity sensors can also improve driving performance in the following situations:

- When the robot is docking, reversing, turning sharply, or pivoting at reduced speeds, the robot is more likely to detect and avoid low objects. The slower the robot drives, the more likely the proximity sensors will detect objects outside the scanners' and cameras' fields of view.
- If the robot is dragging an obstacle below the scanner's plane of view, the proximity sensors will detect it, and the robot will stop and report that the path is blocked.



NOTICE

Because proximity sensor data is not intended to be used while the robot is driving, there is a risk that the robot may still collide with low objects when reversing, turning, or pivoting. Collision with objects may damage the robot or other assets or lead to interruption of operation.

- Inform relevant personnel that the robot cannot detect lowered forklift forks while operating, and that personnel must not park forklifts in the robot's operating area.
- Keep the operating area of the robot clear of unnecessary objects.

The proximity sensors have the following limitations:

- They do not have a long range and are mainly used to detect obstacles placed near the robot while it is standing still and begins driving.
- They only detect low obstacles around the corners of the robot.
- When the robot is driving, obstacles detected by the proximity sensors are too close for the robot to stop or avoid. The robot relies on the laser scanners and 3D cameras to detect obstacles while it is driving.
- The effectiveness of the proximity sensors may be influenced by the shape, material, reflectivity, and color of obstacles.

9.6 Localization

The goal of the localization process is for the robot to determine where it is currently located on its map. The robot has three inputs for determining where it is:

- The initial position of the robot. This is used as a reference point for the methods used to determine the robot position.
- The IMU and encoder data. This is used to determine how far and fast the robot has traveled from the initial position.

- The laser scanner data. This is used to determine the likely positions of the robot by comparing the data with nearby walls on the map.

This data is used by a particle filter to determine the most likely position of the robot on the map.

IMU and motor encoders

Both the data from the IMU (Inertial Measurement Unit) and motor encoders is used to derive where and how fast the robot has traveled over time from its initial position. The combination of both sets of data makes the derived position more accurate.



If the drive wheels are worn down significantly—see [Maintenance on page 226](#)—or the robot is running with an incorrect gear ratio, the robot will miscalculate how far it has traveled based on the encoder data.

Laser scanners and particle filtering

The robot computer compares the input from the laser scanners with the walls on the map to try and find the best match. This is done using a particle filter algorithm. The robot computer only compares input from the area where it expects the robot to be based on the encoder and IMU data. Therefore, it is important that the initial position of the robot is correct.

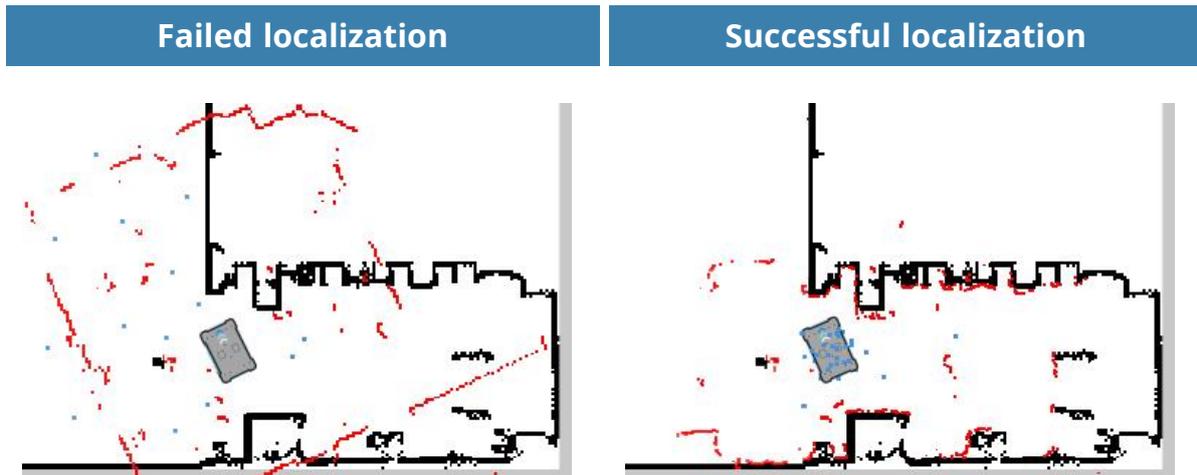
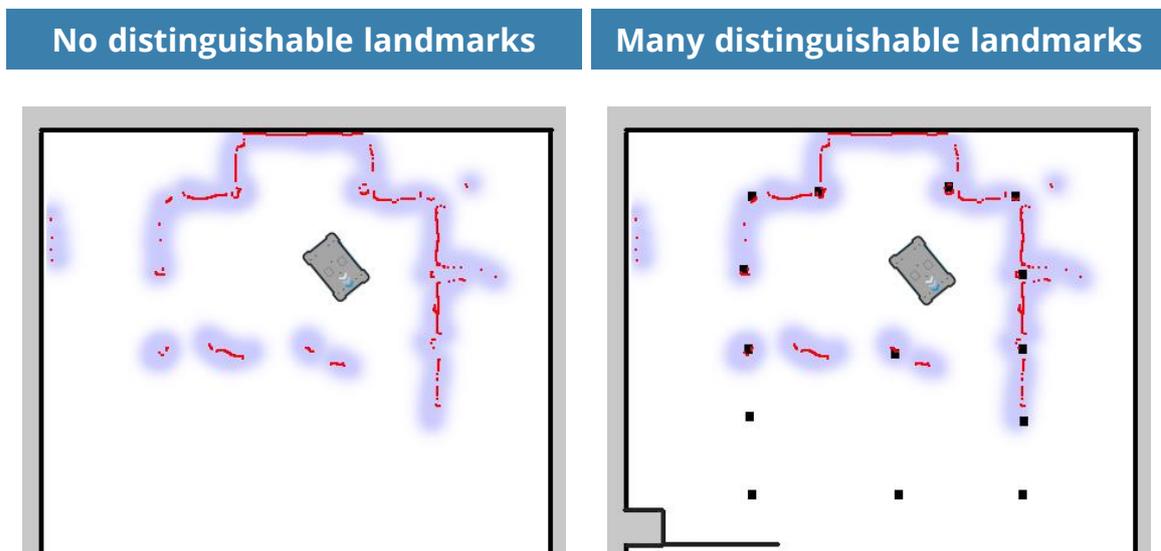


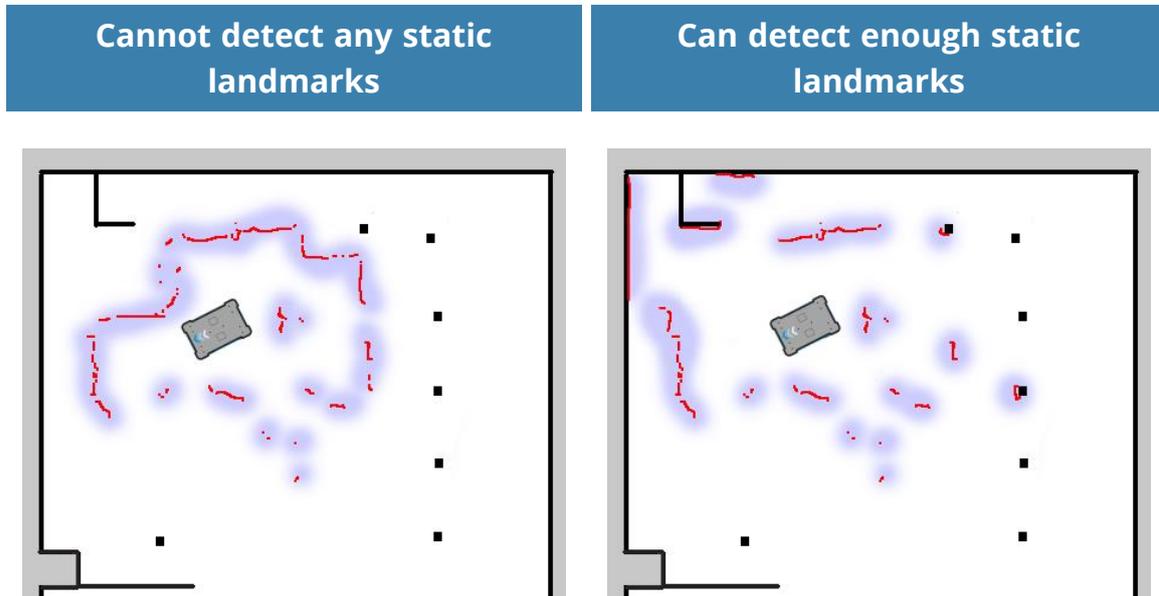
Figure 9.11. In a failed localization, the robot cannot determine a position where the red lines (laser scanner data) align with the black lines on the map. When the robot can localize itself, it determines a cluster of likely positions, indicated in the images above as blue dots.

To make sure the robot can localize itself well using particle filtering, consider the following when creating a map:

- There must be unique and distinguishable static landmarks on the map that are easily recognizable. A landmark is a permanent structure that the robot can use to orient itself, such as corners, doorways, columns, and shelves.



- The robot must be able to detect the static landmarks that are marked on the map to be able to approximate its current position. Make sure there are not too many dynamic obstacles around the robot so that it cannot detect any static landmarks.



- The robot does not compare the laser scanner data with the entire map, but only around the area that it expects to be close to based on the IMU and encoder data and its initial position. This is why it is important that the initial position you place the robot at on the map is accurate.
- The robot can drive for a short distance without being correctly localized. As it drives, the estimated positions should converge to a small area, indicating the robot has determined an accurate estimate. If this does not occur within a set time limit, the robot reports a localization error.

9.7 Motor controller and motors

The robot keeps adjusting how much power is sent to each motor based on sensory input. This means that the robot can correct its speed when going up slopes or when carrying a heavier payload, and it can change its driving direction to avoid moving obstacles.

9.8 Brakes

Once the approximated position of the robot determined from localization is the same as the goal position calculated by the global planner, the robot stops by using regenerative braking in the motors.

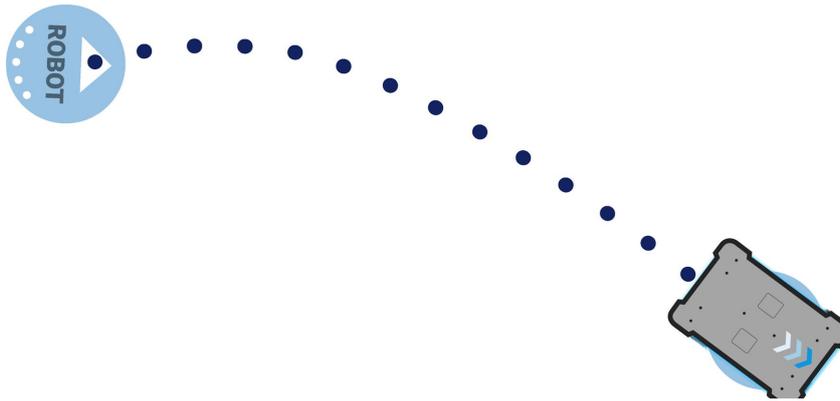


Figure 9.12. The robot has reached the goal position and stops by engaging the dynamic brake function.

Once the robot has stopped, the mechanical brakes are enabled. These brakes are used to keep the robot in place once it has stopped. You can compare the mechanical brakes with the parking brake or hand brake in a car.



The mechanical brakes are only used to stop the robot when it is in motion in emergency situations triggered by the safety system. They will wear down if they are used repeatedly to stop the robot—see [Safety stop on page 134](#).

The mechanical brakes are automatically released again when the robot receives a new order requiring it to move.

10. Safety-related functions and interfaces

The robot's safety system is designed to mitigate significant hazards which could lead to injury, for example, stopping the robot if a person is in its path.

MiR1350 is equipped with a range of built-in safety-related functions as well as safety-related electrical interfaces designed for integration with a top module. Each safety function and interface is designed according to the standard ISO 13849-1. The safety-related functions and interfaces are selected to support compliance with EN 1525 and ISO 3691-4.

For the PFHd, PL, and Architecture as defined by ISO 13849-1:2015 of the main safety functions, see [Safety functions performance overview on page 129](#).

10.1 System overview

The safety system is controlled mainly by the safety PLC. The PLC regulates inputs and outputs from safety-related functions or interfaces involved with ensuring the safety of personnel working nearby the robot.

If a safety function is triggered, the robot uses its STO (Safe Torque Off) contactors to bring the robot to a category 0 stop (stopping by "immediate removal of power to the machine actuators" according to IEC 60204-1) followed by a controlled brake which brings MiR1350 to a stop. This is known as bringing the robot into Emergency stop or Protective stop, depending on the function—see [Types of stop on the next page](#).

Some interfaces are also used to signal safety-related states between the top module and robot, for example whether the robot is in motion or if the top module is in a state where the robot must stop or slow down. Each of these are connected through the safety-related electrical interfaces through two identical circuits to ensure redundancy.

Types of stop

There are four different stopped states:

- Operational stop
- Protective stop
- Emergency stop
- Manual stop

The last three types of stop are monitored by the safety PLC.



When the robot is in Protective stop or Emergency stop, the robot loses connection to CAN bus nodes 3, 4, and 20, and may report an error regarding missing data. The connection is reestablished once the robot is brought out of Protective or Emergency stop.

Operational stop

The robot is in Operational stop when it is stopped through the robot interface either through a mission action or by pausing the mission. The top module and all moving parts are still connected to a power supply.

Protective stop

The robot enters Protective stop automatically to ensure the safety of nearby personnel. When the robot enters Protective stop, internal safety contactors are switched so the robot's top module and all moving parts of the robot do not receive power. You can hear the safety contactors emit audible clicks when they are switched.

When the robot is in Protective stop, the status lights of the robot turn red, and you are not able to move the robot or send it on missions until you bring the robot out of the Protective stop. The following cases describe the various Protective stops and how to bring the robot out of them:

- **A safety laser scanner detects an object in its active Protective field**
Remove the object from the active Protective field—see [Personnel detection on page 111](#). The robot will resume its operating state after two seconds.
- **The robot finishes the startup process**
The Resume button will flash after startup. Press the flashing Resume button to bring the robot out of Protective stop.
- **Switching between Manual mode and Autonomous mode**
After turning the Operating mode key to switch operating modes, the robot enters Protective stop, and the Resume button flashes. Press the Resume button to bring the robot out of Protective stop.
- **The safety system detects a fault, or the motor control system detects a discrepancy**
To bring the robot out of Protective stop, resolve the fault causing the error. Use information regarding the error from the robot interface to determine the fault. Go to [Monitoring > Hardware health](#) to find specific information on what caused the issue. For further guidance, contact your distributor for help troubleshooting the issue.

Emergency stop

The robot enters Emergency stop when an Emergency stop button has been pressed physically. When you press the Emergency stop button, internal safety contactors are switched so the robot's top application and all moving parts of the robot do not receive power. You can hear the safety contactors emit audible clicks when they are switched.

When the robot is in Emergency stop, the status lights of the robot turn red, and you are not able to move the robot or send it on missions until you bring the robot out of the Emergency stop. To do this, you must release the Emergency stop button and then press the Resume button. The Resume button begins flashing blue after you have released the Emergency stop button. If the robot is in Emergency stop, it will immediately resume an operating state after you press the flashing Resume button.



Figure 10.1. MiR1350 has four Emergency stop buttons and the option to connect additional Emergency stop buttons through the electrical interface.



CAUTION

Emergency stop buttons are not designed for frequent use. If a button has been used too many times, it may fail to stop the robot in an emergency situation, and nearby personnel may be injured by electrical hazards or collision with moving parts.

- Only press Emergency stop buttons in emergencies.
- Check that all Emergency stop buttons are fully functional—see [Maintenance on page 226](#).
- Use the robot interface to stop the robot in non-emergency situations.

Manual stop

The robot enters Manual stop when the red Stop button in the control panel is pressed. Manual stop brings the robot into the same state as a Protective stop where it can only be brought to an operational state by pressing the Resume button.

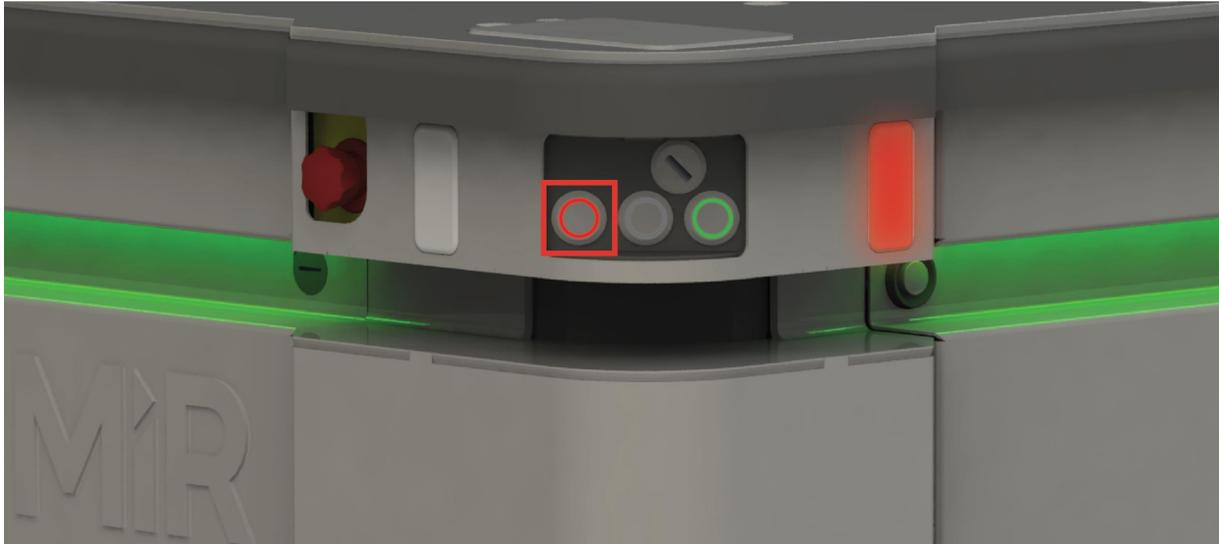


Figure 10.2. The Stop button is the left-most button on the control panel.

Safety-related functions

The following functions are integrated within the robot itself and cannot be modified or used with other applications. The following list introduces the main safety-related functions integrated in MiR1350:

- **Personnel detection**

This function ensures that the robot stops before it collides with personnel or an object. If the laser scanners detect an object or person within a defined Protective field, the robot is brought to a stop. The function determines what the current speed of the robot is based on data from the motor encoders, and the function switches between predefined Protective fields accordingly. The faster the speed, the larger the Protective field is.

- **Overspeed avoidance**

The safety system monitors if the motor encoder data indicates that the speed of either motor is above the limits for maximum speed, or if the speed difference between the motors exceeds the predefined limits. If a limit is exceeded, the robot enters Protective stop.

- **Emergency stop buttons**

MiR1350 has four Emergency stop buttons. When one of the buttons is pressed, the robot goes into Emergency stop.

Safety-related electrical interfaces

The following interfaces are parts of the Auxiliary emergency stop and Auxiliary safety function interfaces that can be used to connect the safety PLC to a top module—see [Internal parts on page 23](#). Most of the electrical interfaces are redundant, meaning they use two identical circuits. If one of the circuits fail, the robot enters Protective stop until both circuits are working correctly again and the robot is restarted, ensuring safe communication between the top module and robot—see [Interface specifications on page 243](#).

The following list introduces the main safety-related electrical interfaces between MiR1350 and its top module:

- **Emergency stop circuit**

The Emergency stop circuit goes through all Emergency stop buttons and the Auxiliary emergency stop interface. The circuit is broken whenever an Emergency stop button is pressed which brings the robot into Emergency stop.

- **Safeguarded stop**

This function consists of a circuit that goes through the Auxiliary safety function interface that connects to the top module. This circuit can be used to bring the robot into Protective stop until otherwise signaled.

- **Locomotion**

The locomotion function signals when the robot is driving. A top module can be connected to this interface if the top module should operate differently when the robot is driving, such as activating brakes or disconnecting the power to actuators.

- **System emergency stop**

This function consists of a shared circuit between the robot and top module, enabling them to trigger each other into an Emergency stop.

- **Reduced speed**

The reduced speed function can be connected to a top module, enabling it to make the robot reduce its speed to 0.3 m/s. This is for example used by MiR lifts to ensure that the robot does not drive fast when the lift is raised.

- **Shelf mode**

This function is intended to be used together with MiR Shelf Lift indicating when the robot should check that it is carrying a shelf. If you do not have a shelf lifting top module, this function should not be used.

These functions are described in further detail in the following sections.

The diagram in **Figure 10.3** shows the inputs to these functions and interfaces and how they are all connected and monitored by the safety PLC. The safety PLC is able to switch the safety contactors to cut off power to the robot motors and the top module whenever a Protective or Emergency stop is triggered. Also, the safety PLC sends information to the robot computer to be displayed in the robot interface (go to **Monitoring > Hardware health**) and to indicate the robot's status through the status lights and the speaker.

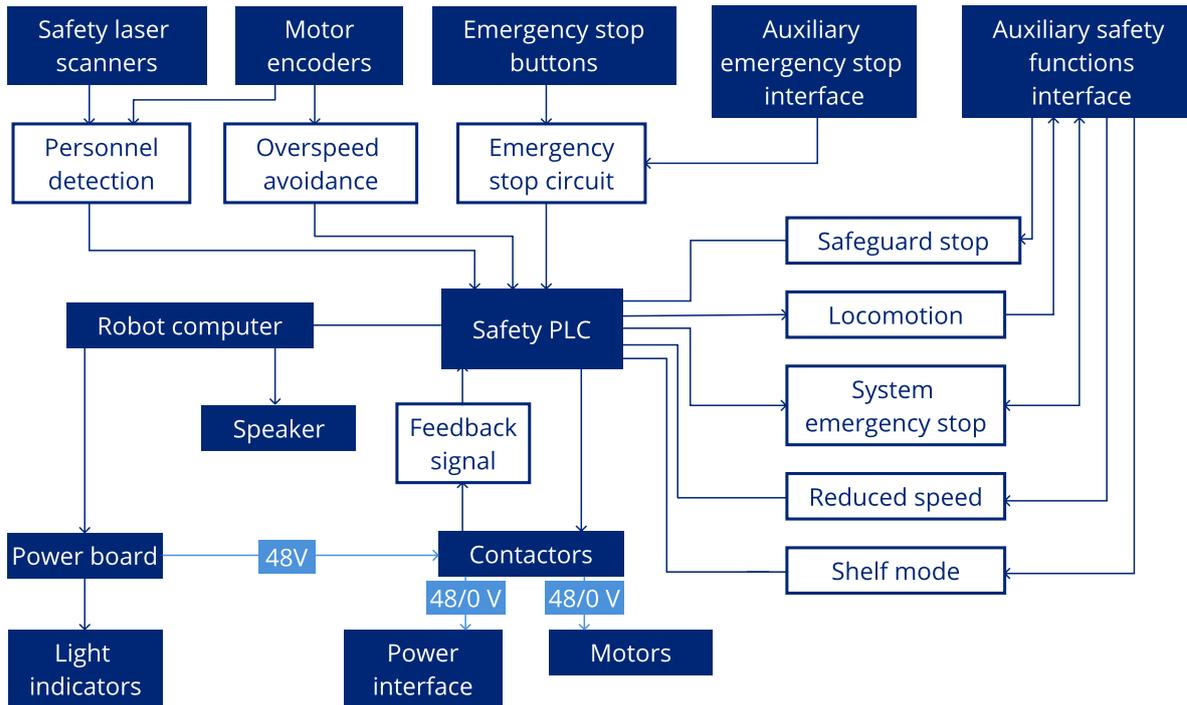


Figure 10.3. Overview of components involved in each safety function and interface. When a safety function is triggered, the safety PLC switches the STO contactors so the motors and power supply to the top module no longer receive power.

10.2 Personnel detection

The Personnel detection safety function prevents the robot from colliding with personnel or obstacles by stopping it before it collides with any detected obstacles. It does this using the safety laser scanners.

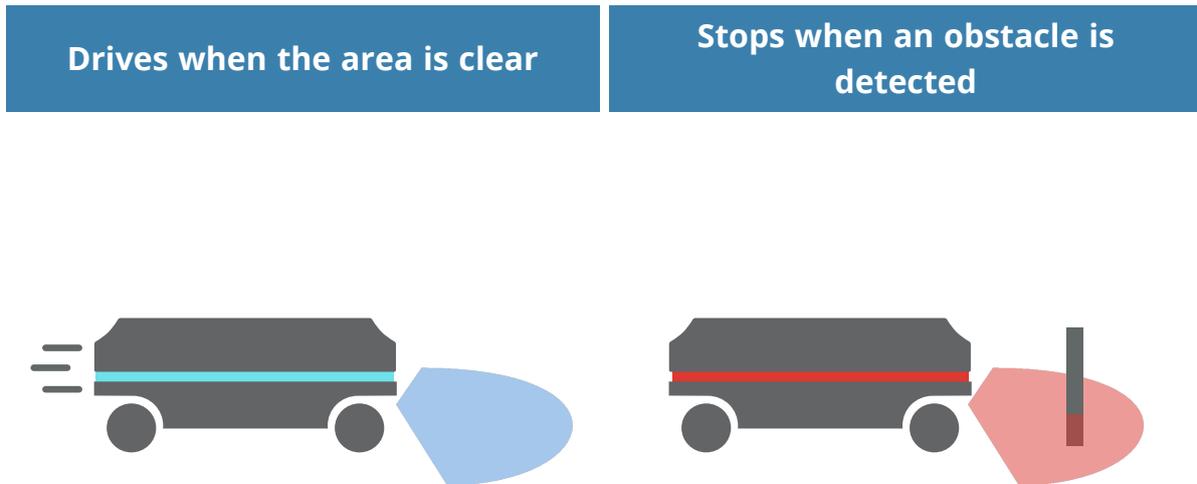


Figure 10.4. Personnel detection ensures that the robot drives when its path is clear and stops if an obstacle is detected within its Protective field.

The safety laser scanners are programmed with two sets of Protective fields. One field set is used when the robot is driving forward and the other when it is driving backward. The Protective field sets are part of the robot's Personnel detection safety function. Each Protective field in the sets is an individually configured contour around the robot. The robot activates the correct field based on the speed. If a person or object is detected within the active Protective field, the robot enters Protective stop until the Protective field is cleared of obstacles for at least two seconds.

The tables in the following sections show the sizes of the Protective fields at given speeds. The faster the robot moves, the larger the scanners' field is. The speed of the robot is determined based on the encoder data.



The Protective fields on the left and right sides of MiR1350 are 350 mm when the robot is driving, and the field on the side opposite of the driving direction is always 25 mm.
The Protective fields on all sides of the robot are all 250 mm when the robot is at standstill (between 0–0.05 m/s).

Field set when driving forward

The following table shows speeds and the field ranges when driving forward. The table describes the length of the Protective field in front of the robot in different cases. Each case is defined by a speed interval that the robot may operate at. The colors and cases in **Table 10.1** correspond to the field set shown in **Figure 10.5**.

Table 10.1. Range of the robot's Protective fields within its forward speed interval cases.			
Case	Speed	Protective field range	Comments
1	0.0 to 0.10 m/s	0-250 mm	When pivoting
2	0.10 to 0.30m/s	0-381 mm	
3	0.30 to 0.40 m/s	0-453 mm	
4	0.40 to 0.60 m/s	0-634 mm	
5	0.60 to 0.90 m/s	0-982 mm	
6	0.90 to 1.10 m/s	0-1242 mm	
7	1.10 to 1.25 m/s	0-1481 mm	Forward at max. speed

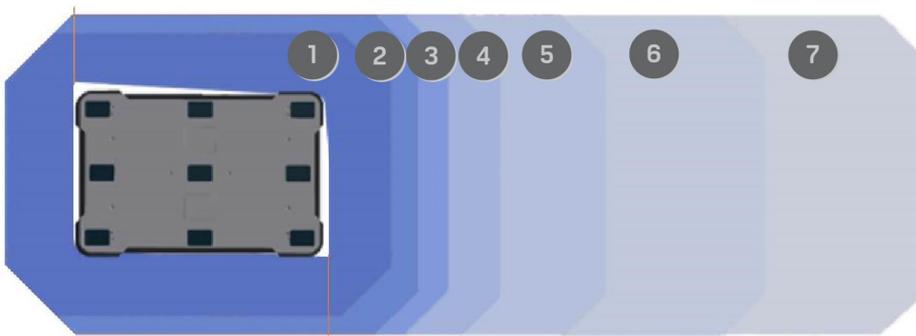


Figure 10.5. The illustration shows the field set contours when the robot drives forward. The range of the active field changes with the robot's speed.

Field set when driving backward

The field set for driving backward is the same as the field set for driving forward. The colors and cases in **Table 10.2** correspond to the field set shown in **Figure 10.6**.

Table 10.2. Range of the robot's Protective fields within its backward speed interval cases.			
Case	Speed	Protective field range	Comments
1	0.0 to -0.10 m/s	0-250 mm	When pivoting
2	-0.10 to -0.30 m/s	0-381 mm	
3	-0.30 to -0.40 m/s	0-453 mm	
4	-0.40 to -0.60 m/s	0-634 mm	
5	-0.60 to -0.90 m/s	0-982 mm	
6	-0.90 to -1.10 m/s	0-1242 mm	
7	-1.10 to -1.25 m/s	0-1481 mm	Backward at max. speed

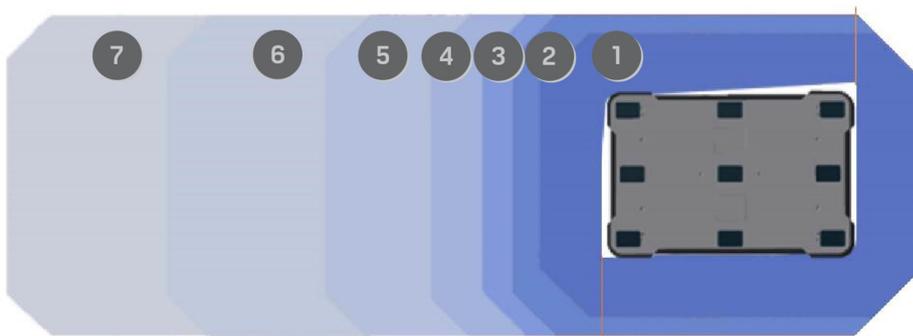


Figure 10.6. The illustration shows the field set contours when driving backward. The range of the active field changes with the robot's speed. The illustration also shows how the front scanner reduces its Protective field to a minimum when the robot moves backward.



NOTICE

Scanners measure distances to diffuse reflections, which means that a tolerance is added to the Protective field sets to secure a safe detection of persons crossing the Protective field sets. The tolerance distance is 65 mm.

Muted Protective fields

When it is required that the robot moves close to surrounding objects, the robot can be configured to mute the Protective fields. This muting is by default enabled in the template missions for docking to known markers such as charging stations or pallet racks, or it can manually be configured for any customized mission.



CAUTION

Other risk reduction means shall be implemented as muted Protective fields introduce a risk for collision with personnel in its path.

- Areas where Protective fields are muted must be marked as Operating hazard zones, and personnel must be informed not to enter the zone while the robot is operating in it—see [Using operating hazard zones on page 173](#).

When the Protective fields are muted, the robot does the following:

- Disables the Protective fields
- Decreases and ensures that the maximum speed is set to 0.3 m/s
- Flashes the yellow signal lights
- Emits audible warning sounds if configured to do so in the safety system settings—see [Light indicators and speakers on page 135](#).

User-configured muting of the Protective fields

There are two ways you can mute the Protective fields using the robot interface:

- Adding the Mute protective fields action to a mission:
 1. Enable **Mute protective fields** under **System > Settings > Features**—see [System settings on page 183](#).
 2. Under **Setup > Missions**, create or edit a mission—see [Creating missions on page 164](#).
 3. Add the action **Mute protective fields** from the Safety system menu.
 4. Edit the action parameters so the Protective field sets are muted.



MiR1350 cannot mute specific Protective fields; you can either mute all or none of the fields. Otherwise, the robot reports an error.

5. Add and drag all the actions you want the robot to execute with muted protective fields inside the Mute protective fields action.

- When driving the robot in Manual mode:
 1. Put the robot into Manual mode—see [Driving the robot in Manual mode on page 68](#).
 2. In the robot interface, select **Muted Protective fields** in the joystick control.
 3. In the dialog box, select **Yes** to acknowledge the muting of the Protective fields.



If you are using Manual mode, you can mute the Protective fields without marking the area as an operating hazard zone. It is the responsibility of the user driving the robot to ensure that it does not damage equipment or injure personnel. The robot will not stop automatically for detected obstacles.

Pre-configured muting of the Protective fields

The Protective fields are automatically muted when the robot docks to most types of markers, including shelves. This ensures that the robot can drive closely to the marker without entering Protective stop.



The only marker that does not mute the Protective fields is the L-marker.

The Protective fields are muted from when the docking starts and until the robot has undocked and has started a new action that requires the robot to plan a path.

The Protective fields will remain muted during any Relative move action that comes right after the docking action. The Protective fields will also remain muted if you engage the Manual brake release—see [Manual brake release switch on page 29](#).

For more information about markers, docking, and undocking—see [Markers on page 155](#).

10.3 Overspeed avoidance

The overspeed function stops the robot if the motor encoders measure that the robot is driving over the predefined safety limits or that the difference between how fast each wheel turns is outside the predefined safety limits. This indicates that the robot is not driving as intended, for example, if one of the wheels loses traction or if there is a hardware error in the robot.

If the robot detects overspeed, it is immediately brought into Protective stop. This ensures that the robot cannot drive if it has lost control of the speed of the drive wheels.

10.4 Emergency stop buttons

There are four Emergency stop buttons on MiR1350. When one of the buttons is pressed, it breaks the Emergency stop circuit, triggering an Emergency stop. The Emergency stop circuit runs through all of the Emergency stop buttons and connects to the safety PLC through the Auxiliary emergency stop interface—see **Figure 10.7**.

You must connect a circuit to the Auxiliary emergency stop interface that closes the circuit before the robot can operate. If you mount a top module to the robot that has Emergency stop buttons, you can connect these buttons to the circuit so MiR1350 enters Emergency stop when the buttons on the top module are pressed.



The Auxiliary emergency stop interface-circuit needs to be closed at all times. To prevent the robot from entering Emergency stop, the robot must be fitted with a closed connection such as a dummy plug or top module. Dummy plugs are supplied by MiR. Additionally, the connection interface for the MiR controller in the rear compartment also has a dummy plug that must be connected to keep the circuit closed.

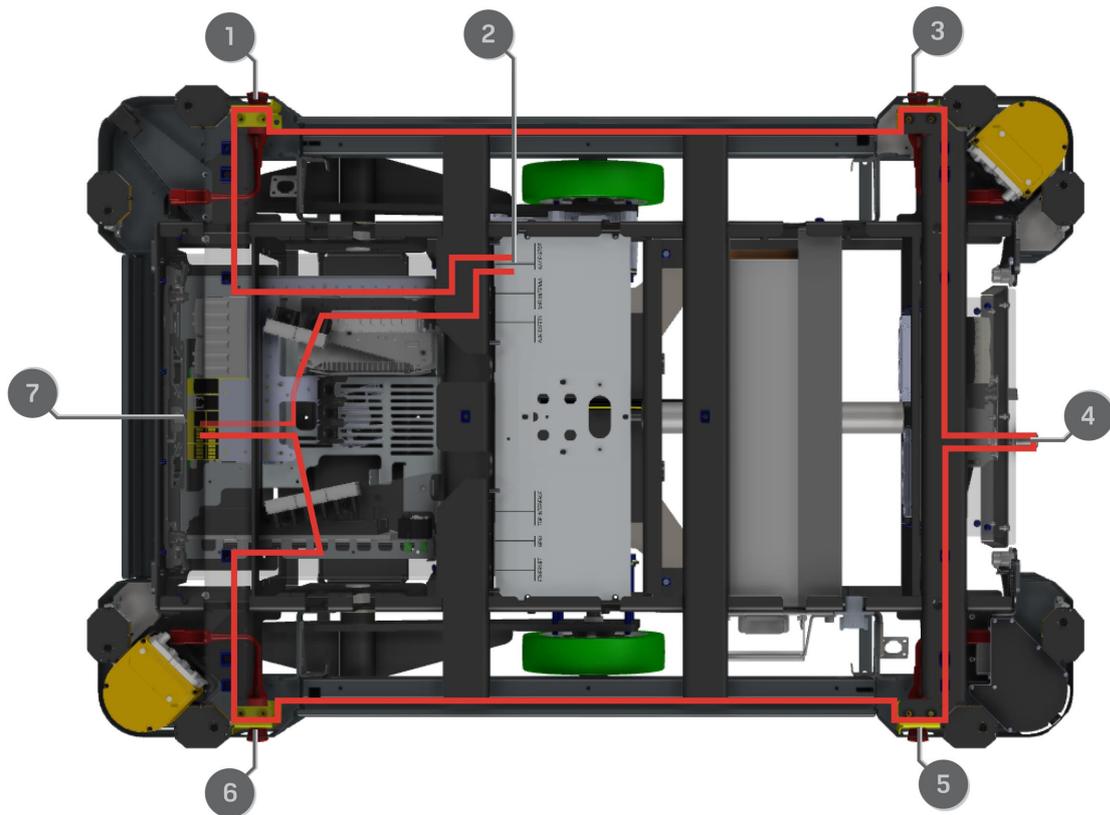


Figure 10.7. The Emergency stop circuit in MiR1350.

Table 10.3. Identification of parts in <i>Figure 10.7</i>			
Pos.	Description	Pos.	Description
1	Front-right Emergency stop button	2	Auxiliary emergency stop interface —see Emergency stop circuit on the next page
3	Rear-right Emergency stop button	4	Connection interface for MiR controller with dummy plug
5	Rear-left Emergency stop button	6	Front-left Emergency stop button

Pos.	Description	Pos.	Description
7	Safety PLC		

10.5 Emergency stop circuit

The Emergency stop circuit goes through the four Emergency stop buttons in MiR1350—see [Emergency stop buttons on page 119](#)—and then through the Auxiliary emergency stop interface where you can connect external input to bring the robot into an Emergency stop. The interface uses two output pins to provide a 24 V signal and two input pins to bring the robot into Emergency stop.

It is intended that the circuit is set up so the 24 V signal delivered from the safety PLC outputs passes through all Emergency stop buttons of the top module and then continues to the two input pins. When the input pins both receive 24 V, the robot can operate. The connected Emergency stop buttons must break the circuit when you press them so both inputs receive a 0 V signal that will bring the robot into Emergency stop.

If the circuit or an Emergency stop button is installed incorrectly so the input signals are not the same, the robot enters Protective stop until the circuit is fixed.

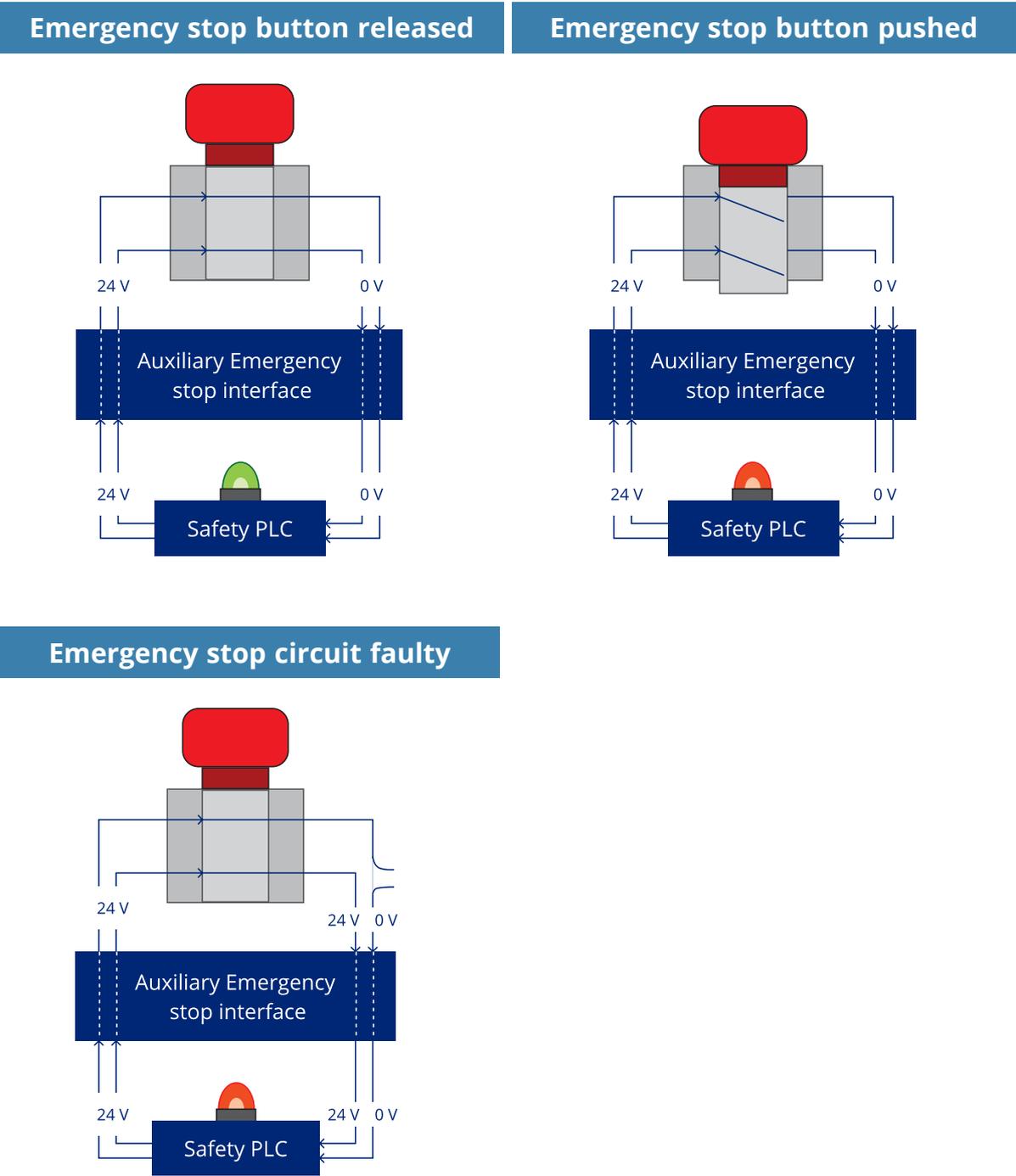


Figure 10.8. If the input pins deliver 24 V to the robot, it can operate. When you push a connected Emergency stop button, both pins deliver 0 V, and the robot enters Emergency stop. If the pins do not deliver the same input, the robot enters Protective stop until the circuits are fixed.

In the Auxiliary emergency stop interface, pins 1 and 2 deliver 24 V from the safety PLC, and pins 3 and 4 connect to the Emergency stop circuit inputs of the safety PLC. 24 V must be delivered to pins 3 and 4 for the robot to operate.

10.6 Safeguarded stop

The Safeguarded stop interface provides an input to the robot that can bring the robot into Protective stop. This interface uses two input pins where both pins must receive 24 V for the robot to be able to operate. If either or both pins receive 0 V, the robot is brought into Protective stop. The robot can be brought out of Protective stop again if both pins receive 24 V again.

If the input pins are unequally set for more than three seconds, the safety PLC registers this as an error in the system and needs to be reset before the robot can operate again. To do this, you must restart the robot.

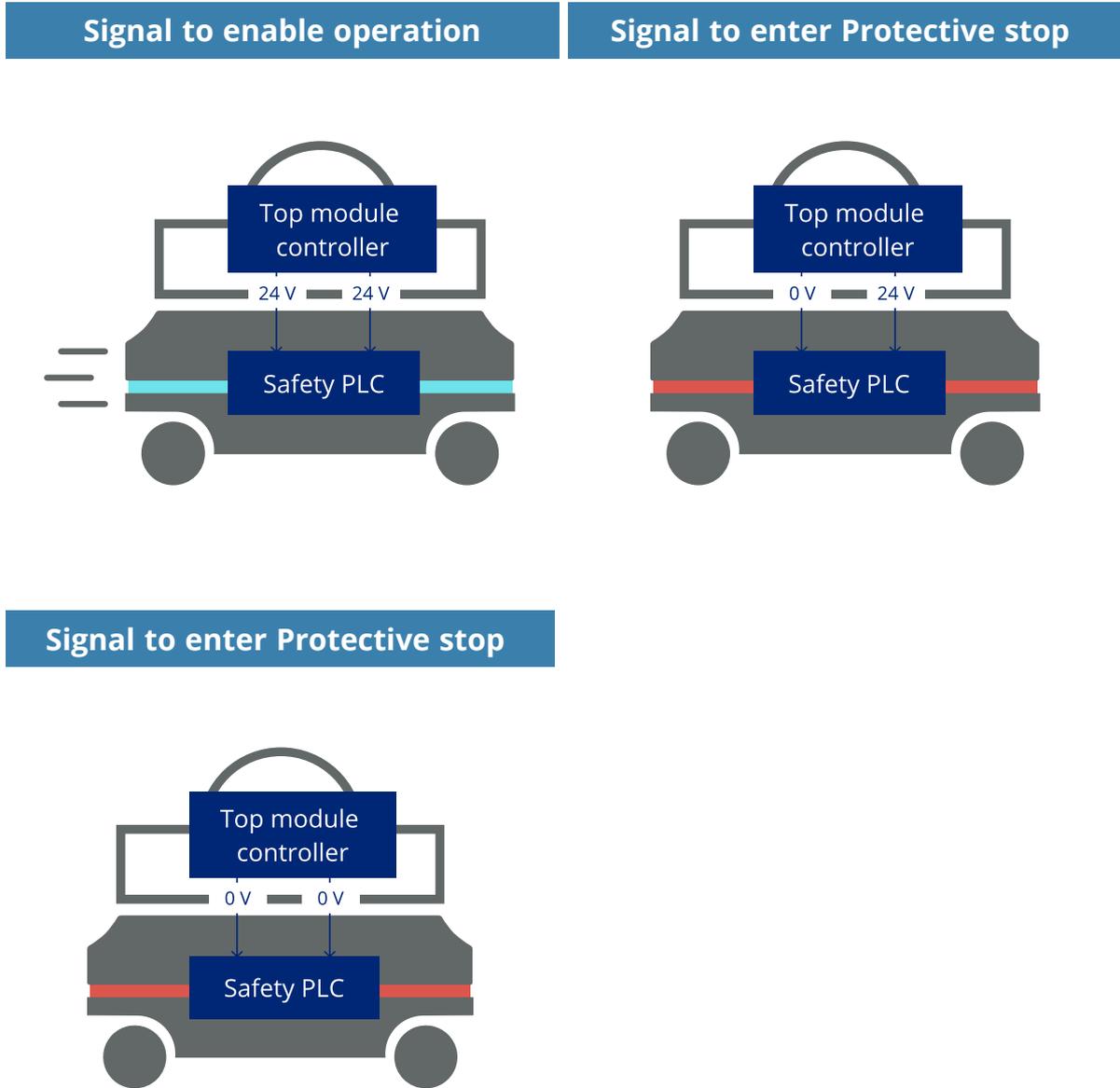


Figure 10.9. If both pins deliver 24 V to the robot, it can operate. If either or both of the pins deliver 0 V, the robot enters Protective stop.

Pins 3 and 4 in the Auxiliary safety function interface are used for the Safeguarded stop function.

10.7 Locomotion

The Locomotion interface is used to signal to a top module that the robot is driving. This function uses two output pins, where both pins deliver 0 V when the robot is driving and 24 V when the robot is stopped. You can use this interface to make your top module behave differently depending on whether the robot is driving or not.

The interface is intended to be used to ensure that the top module is programmed to go into a safe state when the robot is driving. For example by engaging the brakes in any actuators that may result in injury to personnel.

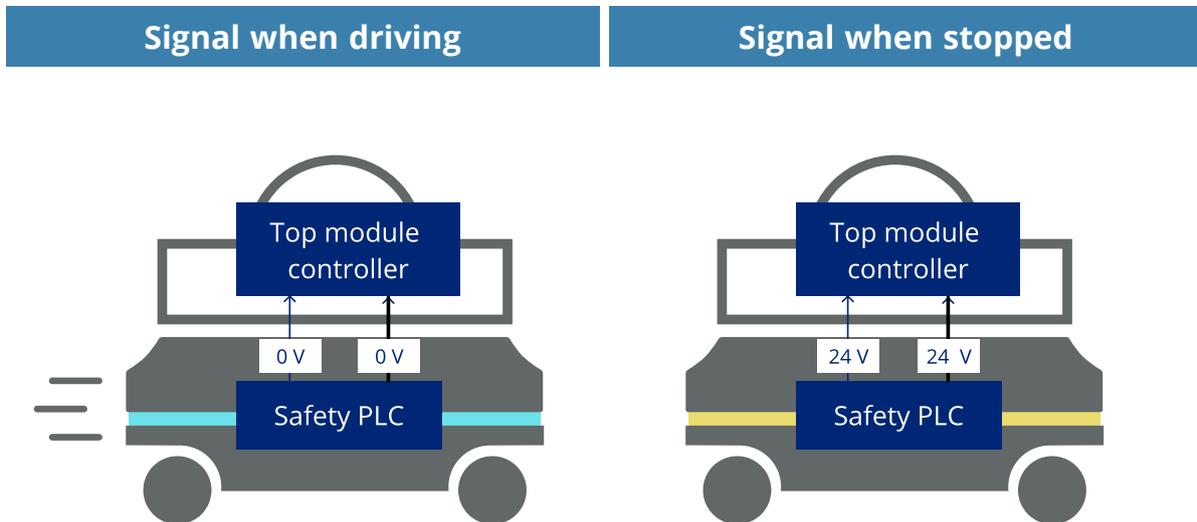


Figure 10.10. When the robot is driving, the safety PLC sends a 0 V signal to the top module through the Auxiliary safety function interface. When the robot is stopped, the signal becomes 24 V.

Pins 5 and 6 in the Auxiliary safety function interface are used for the Locomotion function.

10.8 System emergency stop

The System emergency stop interface is used to control the Emergency stop state between the robot and a top module. The interface has two inputs for bringing the robot into Emergency stop and two outputs for signaling when the robot is in Emergency stop.

The outputs are used to signal to the top module that the robot is in Emergency stop. When the robot is in an operational state, the outputs deliver 24 V. As soon as the robot enters Emergency stop, they deliver 0 V.

The inputs are intended to enable the top module to bring the robot into Emergency stop. When both inputs deliver 24 V, the robot can operate, but as soon as either or both of the inputs deliver 0 V, the robot enters Emergency stop.

These signals can be used if the top module has its own Emergency stop system and you want both the robot and the top module to enter Emergency stop when either system is triggered.

If the input pins are unequally set for more than three seconds, the safety PLC registers this as an error in the system and needs to be reset before the robot can operate again. To do this, you must restart the robot.



The robot only delivers 24 V from the System emergency stop output when one of the robot's Emergency stop buttons are pressed. The robot can be in Emergency stop but delivers 0 V from the System emergency stop outputs if the Emergency stop signal is received from the connected top module.

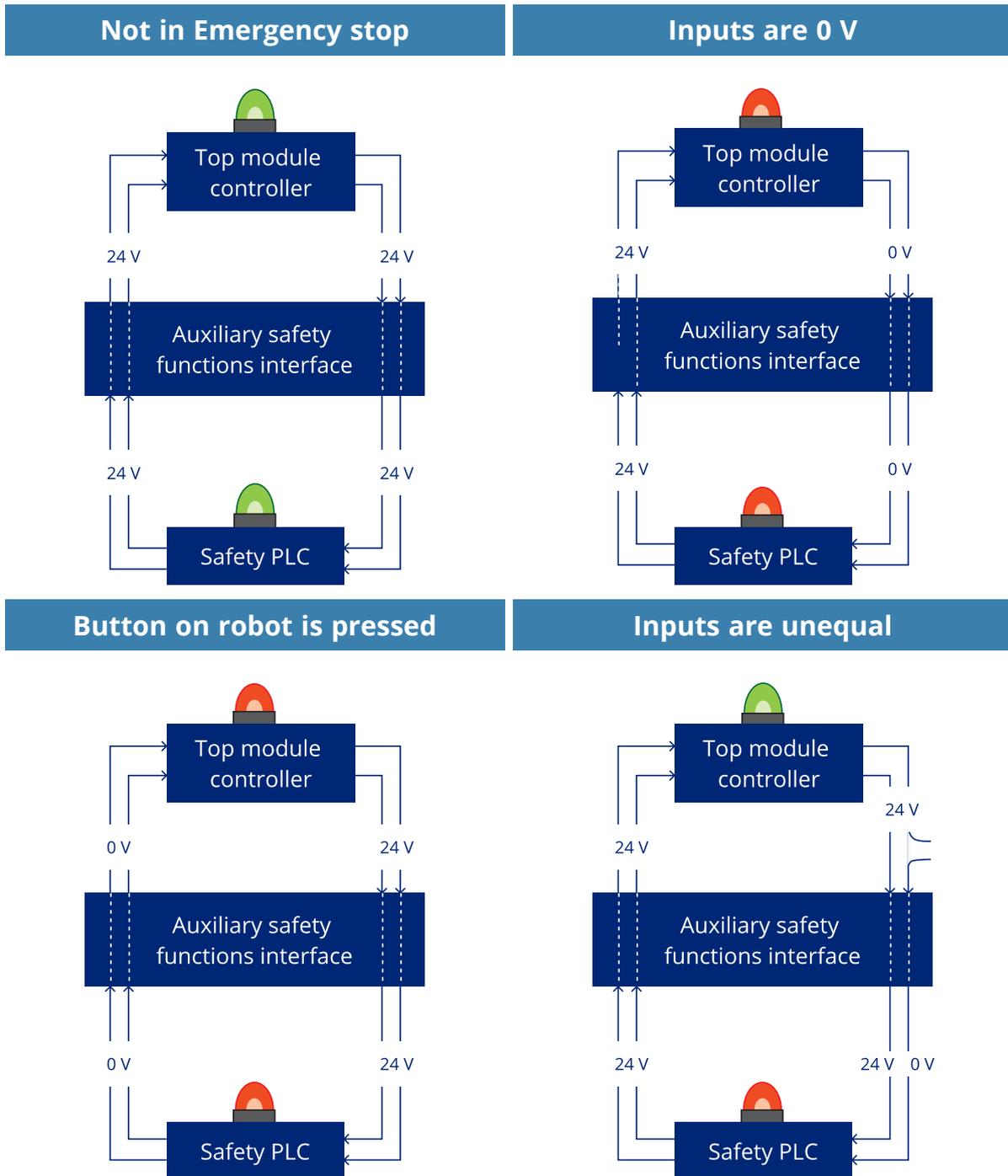


Figure 10.11. There are four cases described above. They illustrate respectively: 1. the robot is not in Emergency stop so the output is 24 V, 2. the robot is in Emergency stop because it receives 0 V

input from the System emergency stop interface, 3. the robot is in Emergency stop because an Emergency stop button has been pressed, 4. the robot is in Emergency stop because the inputs are unequal.

In the Auxiliary safety function interface, pins 7 and 8 are used for the output and pins 9 and 10 are used for the input of the System emergency stop function.

10.9 Reduced speed

The Reduced speed interface is used to signal to the robot that it must drive at a reduced speed of 0.3 m/s. This is the same speed used when the robot mutes its Protective fields. The interface uses one input pin where the robot drives at a reduced speed when it is 0 V.

This can, for example, be used in cases where the top module can register whether the load it is carrying is not securely placed or the module is currently under operation.

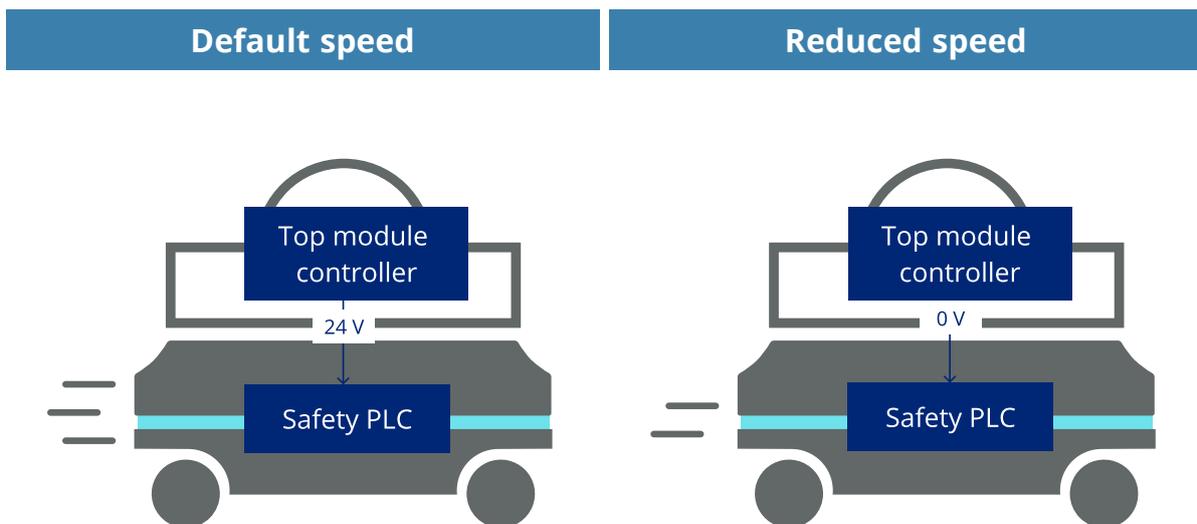


Figure 10.12. The robot drives at its default speed only when the input is 24 V. If the pin delivers 0 V, the robot drives at 0.3 m/s.

Pin 11 in the Auxiliary safety function interface is used for the Reduced speed function.

10.10 Shelf mode



If you do not have a shelf lifting top module mounted on top of the robot, this interface should remain inactive at all times.

The Shelf mode interface is a signal specifically used when MiR Shelf Lift is mounted to the robot. The signal activates when the robot is carrying a shelf, triggering the robot to change to the shelf specific Protective field sets and use the laser scanners to check that the four shelf legs are detected around the robot, ensuring that the robot has successfully picked up the shelf.

Pin 12 in the Auxiliary safety function interface is used for the Shelf mode function.

10.11 Safety functions performance overview

Table 10.4 lists each safety function with its associated triggering event, reaction, reliability, and how it is realized.

The following terms are used in the table:

- **PFHd:** The Probability of Failure on Demand per Hour
- **PL:** Performance Level as defined in EN ISO 13849-1:2015
- **Architecture:** as defined in EN ISO 13849-1:2015



The text for the footnotes in the table can be found after the table.

Table 10.4. Overview of integrated safety functions in MiR1350		
Function name	Description	PFHd, PL, and architecture
Emergency stop ¹	<p>Triggering event: Pressing any Emergency stop button on the robot, connected top module, or connected MiR Controller joystick—see Emergency stop buttons on page 119.</p> <p>Reaction: Category 0 stop (IEC 60204) and mechanical spring-applied brakes engage. System emergency stop pins deliver 0 V—see System emergency stop on page 126.</p> <p>Reset function: Release all Emergency stop buttons, and press the Resume button on the robot.</p>	<p>PFHd: 4.0 × 10⁻⁸</p> <p>PL: e</p> <p>Architecture: Category 3</p>
Overspeed	<p>Triggering event: The speed of the robot exceeding 2.10 m/s or the difference in speed between the drive wheels exceeding 0.37 m/s—see Overspeed avoidance on page 119.</p> <p>Reaction: Category 0 stop (IEC 60204) and mechanical spring-applied brakes engage.</p> <p>Reset function: Press the Resume button on the robot.</p>	<p>PFHd: 5.2 × 10⁻⁸</p> <p>PL: e</p> <p>Architecture: Category 3</p>

Function name	Description	PFHd, PL, and architecture
Field switching	<p>Triggering event: Changing the robot speed to another case interval—see Personnel detection on page 111.</p> <p>Reaction: Activate Protective field that is suitable for the speed of the robot.</p> <p>Reset function: Continuous function. No action required.</p>	<p>PFHd: 2.0×10^{-7}</p> <p>PL: d</p> <p>Architecture: Category 3</p>
Personnel detection	<p>Triggering event: Safety laser scanners detecting an object in the active Protective field—see Personnel detection on page 111.</p> <p>Reaction: Category 0 stop (IEC 60204) and mechanical spring-applied brakes engage.²</p> <p>Reset function: Resumes automatically after 2 s of cleared Protective field.</p>	<p>PFHd: 1.2×10^{-7}</p> <p>PL: d</p> <p>Architecture: Category 3</p>
Speed monitor	<p>Triggering event: The speed of the robots exceeding 0.3 m/s while the Protective fields are muted.</p> <p>Reaction: Category 0 stop (IEC 60204) and mechanical spring-applied brakes engage.</p> <p>Reset function: Press the Resume button on the robot.</p>	<p>PFHd: 5.2×10^{-8}</p> <p>PL: e</p> <p>Architecture: Category 3</p>

Function name	Description	PFHd, PL, and architecture
Safeguard stop ¹	<p>Triggering event: External device delivering 0 V to the Safeguard stop input pins—see Interface specifications on page 243.</p> <p>Reaction: Category 0 stop (IEC 60204) and mechanical spring-applied brakes engage.</p> <p>Reset function: Resumes when external signals are active (24 V).</p>	<p>PFHd: 3.7 × 10⁻⁸</p> <p>PL: e</p> <p>Architecture: Category 3</p>
Locomotion	<p>Triggering event: The speed of the robot exceeding 0.1 m/s—see Locomotion on page 125.</p> <p>Reaction: Locomotion pins deliver 0 V.</p> <p>Reset function: Unapplicable</p>	<p>PFHd: 4.5 × 10⁻⁸</p> <p>PL: e</p> <p>Architecture: Category 3</p>
Hold to run ¹	<p>Triggering event: Driving the robot using a connected joystick (not the virtual one in the robot interface) and the speed of the robot exceeding 0.1 m/s. ³</p> <p>Reaction: Category 0 stop (IEC 60204) and mechanical spring-applied brakes engage.</p> <p>Reset function: Press the Resume button on the robot.</p>	<p>PFHd: 5.7 × 10⁻⁸</p> <p>PL: e</p> <p>Architecture: Category 1</p>

Function name	Description	PFHd, PL, and architecture
Mode selection	<p>Triggering event: Changing mode or setting to Locked mode.</p> <p>Reaction: Category 0 stop (IEC 60204) and mechanical spring-applied brakes engage.</p> <p>Reset function: Press the Resume button on the robot.</p>	<p>PFHd: 1.2×10^{-6}</p> <p>PL: c</p> <p>Architecture: Category 1</p>
System emergency stop ¹	<p>Triggering event: External device delivering 0 V to the System emergency stop input pins. These are Auxiliary safety functions pins 9 and 10—see Interface specifications on page 243.</p> <p>Reaction: Category 0 stop (IEC 60204) and mechanical spring-applied brakes engage.</p> <p>Reset function: When external signals are active (24 V), press the Resume button on the robot.</p>	<p>PFHd: 3.7×10^{-8}</p> <p>PL: e</p> <p>Architecture: Category 3</p>

¹This safety function uses external input. The values in **Table 10.4** are evaluated without any external input. The resulting functional safety, including the external device or equipment, is determined by the overall architecture and the sum of all PFHds. This includes the PFHd provided in **Table 10.4**.

²The robot will stop within the active Protective field if the payload, CoM, mass inertia moment, and friction coefficient are within specifications—see [Making a brake test on page 175](#).

³This function is by default disabled by a physical dummy plug inserted in the joystick connector.

10.12 Safety stop

There are two pairs of contactors used to stop MiR1350: the STO (Safe Torque Off) contactors and the dynamic brake contactors. These are controlled by the safety PLC and are used when the robot goes into Protective or Emergency stop. The following processes occur to stop the robot safely:

1. The safety PLC first turns off the STO contactors so power is cut from the motors.



To ensure that the STO contactors switch states as expected, there is a feedback circuit that connects to the safety PLC to verify that the contactors switch to the correct state. When the robot is starting up, the feedback circuit and STO contactors are checked before allowing the robot to be operated.

2. The safety PLC turns off the dynamic brake contactors to bring the robot to a stop.
3. The safety PLC monitors data from the motor encoders to determine whether the robot has stopped within the expected amount of time.
4. Once the robot has stopped, the mechanical brakes are engaged to keep the robot in place, similar to the parking brake in a car.

The mechanical brakes are only intended to engage when the robot has stopped. Only when the dynamic brake function does not stop the robot within the expected amount of time are the mechanical brakes engaged to stop the robot while it is in motion. This is considered an emergency situation where the dynamic brakes have failed, and an error is reported in the robot interface. This can occur, for example, if the robot drives on surfaces that are not within specifications or the load on the robot does not fulfill the payload specifications—see [Payload distribution on page 239](#).

10.13 Light indicators and speakers

The robot uses two types of light indicators to let people in the environment know what the robot is currently doing or planning to do.

- **Status lights**

The LED light bands on all four sides of the robot use colors and light motion patterns to signal the current status of the robot.

- **Signal lights**

The signal lights at the front and back of the robot show if the robot is about to turn a corner or go backward. Front lights are white and rear lights are red. Right and left turns are indicated by blinking.



Figure 10.13. Indicator lights on MiR1350.

Table 10.5. Identification of indicator lights in <i>Figure 10.13</i>			
Pos.	Description	Pos.	Description
1	Signal lights	2	Status lights

Status lights

The LED light bands running all the way around the robot indicate the robot's current operational state. Colors may also be used as part of missions, but as standard, status lights indicate the statuses described in **Table 10.6**.

Table 10.6. Status light colors	
Red	Emergency stop
Green	Ready for job
Cyan	Drives to destination
Purple	Goal/Path blocked
White	Planning/Calculating
Yellow	Mission paused
Yellow wavering	Startup signal before PC is active
Yellow fade	Shutting down robot
Yellow blinking	Relative move, ignoring obstacles
Purple - yellow	General error, for example hardware, localization
Blue	Manual drive
Blue wavering	Mapping
Contracting white	Charging at charging station
White wavering	Prompt user / Waiting for user's response
Cyan wavering (robots connected to MiR Fleet only)	Waiting for MiR Fleet resource or for another MiR robot to move



When the robot's battery reaches a critically low level of power (0-1%), the ends of the status lights flash red.



When the robot is charging in a charging station, the status lights on the side of the robot indicate the robot's battery percentage.

Signal lights

Signal lights are used to indicate the robot's immediate motion plans by signaling forwards-backwards-braking and left-right turns.

The signal lights work similarly to lights used on cars; white at the front, red at the back, and indicating a left or right turn by blinking.

When the robot drives with muted Protective fields, for example, when docking to a charging station, all signal lights blink yellow.

Speakers

In **Setup > Sounds**, you can upload new sounds to the robot or edit the volume and length of the default sounds.

Sounds are used in missions and can be used as alerts or to attract attention, for example, when the robot has arrived at a position.

When the robot drives with muted Protective fields it emits a warning sound. In **System > Settings > Safety system**, you can choose which sound the robot makes and the volume of the sound.



CAUTION

Changing the safety system can cause the robot to not comply with safety standards.

- Do not disable the sound in the safety system.

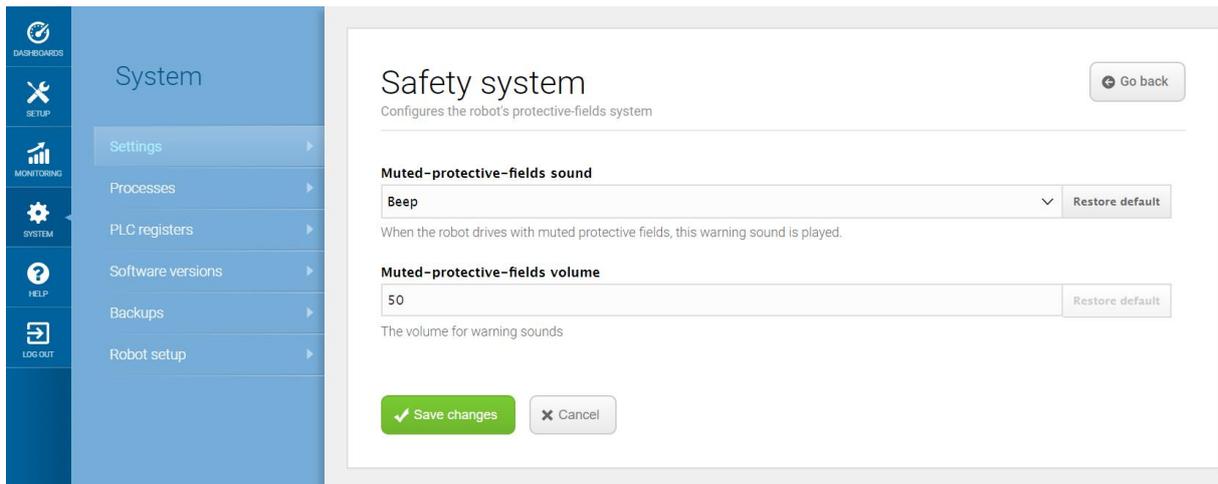


Figure 10.14. In the Safety system settings, you can modify the sounds the robot plays when the robot mutes its Protective fields.



CAUTION

Unaware personnel may not see the robot in certain situations and risk colliding with the robot. This may result in injury to personnel or damage to equipment.

- Make sure to adjust the volume of the robot's warning sounds so they are audible in the robot's work environment.
- Implement warning sounds from the robot in missions and areas where it can reduce the risk of hazardous situations.

11. Commissioning

This section describes how to commission MiR1350.

Commissioning should be done without any load on the robot, except when doing brake tests where the robot should have a load equaling the heaviest load it will be driving with.

Only persons assigned with the commissioning task should be present during commissioning.

It is the responsibility of the commissioner to:

- Analyze the work environment.
- Make a risk assessment of the full installation.
- Create and configure the site with maps.
- Create missions.
- Configure audio and light signals according to the environment.
- Change the robot's footprint or create new footprints depending on the top module or loads of the robot.
- Create operating hazard zones.
- Make a brake test.
- Create user groups and users.
- Create dashboards.
- Update robot software.
- Change the relevant system settings.

11.1 Analysis of the work environment

The work environment of the robot must fulfill a number of requirements for the robot to function properly and safely. This section describes the factors that must be considered when the robot is being commissioned to function in a work environment.

Surfaces

The floor surface of the work environment must be dry. MiR1350 functions on many different types of surfaces, but some materials can affect the performance and safety of the robot, such as very thick carpets or slippery floors.

It is the responsibility of the commissioner to test the performance and safety of the robot on the surfaces in the work environment—see [Making a brake test on page 175](#).

Light, reflections, and materials

Bright sunlight and reflective or transparent objects can affect the performance of the robot's laser scanners and cameras. This can result in the robot detecting nonexistent objects or failing to detect real objects.

Likewise, docking to markers made in very high gloss or transparent materials can reduce the effectiveness of the robot's scanners, hindering a successful docking.

It is the responsibility of the commissioner to test if sunlight, reflections from high gloss materials, and transparent objects affect the robot's performance or safety.

Temperature and humidity

Temperatures outside of the approved temperature range can affect the performance and durability of the robot—see specifications on the MiR website. This is especially relevant for the robot's battery—see [Battery storage on page 82](#).

Inclines, doorways, gaps, and steps

The robot must operate within the approved specifications for driving on inclines, through doorways, and over gaps and steps—see specifications on the MiR website. Operating in areas that do not meet the specifications may result in the robot failing to complete the missions or losing control of its load.

Space

The robot must have sufficient space to operate efficiently. Determine during commissioning if the robot has sufficient space to drive, dock, turn, and perform other tasks. Make sure to test each mission under the most likely operating conditions to determine if there is enough space for the robot to maneuver—see your robot's space requirement guide on the Support portal.



CAUTION

Driving in environments with no escape routes can lead to hazardous situations. There is a risk of damage to equipment or injury to personnel.

- At all times there must be at least 0.5 m wide and 2.1 m high pedestrian escape routes on each side of the robot, also in operating hazard zones.

Dust

Dusty environments can affect the performance and durability of the robot. Dust can get into the robot computer and mechanical parts, affecting their performance and durability, and it can obstruct the view of the robot's sensor system. Make sure the environment MiR1350 operates in is suitable for its IP rating—see specifications on the MiR website.

Static landmarks and dynamic obstacles

The robot uses static landmarks to navigate by. If it cannot detect enough distinguishing landmarks, it cannot navigate the map efficiently—see [Localization on page 99](#).

11.2 Risk assessment

To achieve a safe installation, it is necessary to conduct a risk assessment of MiR1350 in the environment it will be used in. This is the responsibility of the commissioner.

The risk assessment must cover both MiR1350 itself and also take into account carts, potential load transfer stations, work cells, and the work environment.



NOTICE

Mobile Industrial Robots takes no responsibility for the creation and performance of the risk assessment, but we provide information and guidelines that may be used in this section.

For more guidelines, see the guide .

It is recommended that the commissioner follows the method in ISO 12100 to conduct the risk assessment.

In EN 1525 clause 4 and ISO 3691-4 annex B there are lists of possible significant hazards and hazardous situations that the commissioner should consider.

A risk assessment of the application must be used to determine the adequate information for users. Special attention to at least the following Essential Health and Safety Requirements (EHSR) from Directive 2006/42/EC must be taken:

- 1.2.2 Control devices
- 1.3.7 Risk related to moving parts
- 1.7.1 Information and warning on the machinery
- 1.7.2 Warning of residual risks
- 1.7.3 Marking of the machinery
- 1.7.4 Instructions

The risk assessment will lead to new instructions that shall be written by the party who draw up the CE marking. The instructions must at least include:

- Intended use and foreseeable misuse.
- A list of residual risks.
- Training required for personnel.

11.3 Creating and configuring maps

The map is visible in the robot interface and is the basis for the robot's ability to navigate its surroundings safely and efficiently. The map illustrates the physical area in which the robot operates.

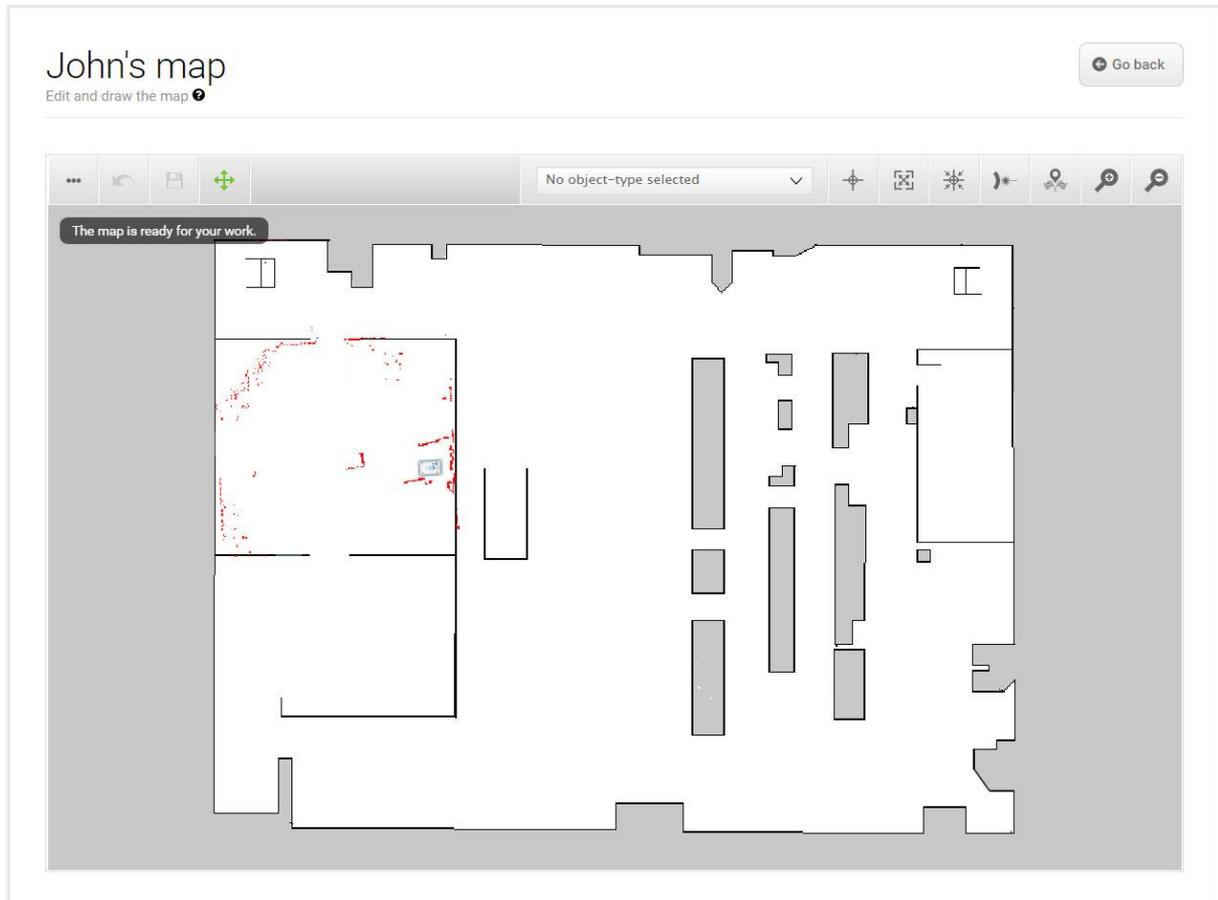


Figure 11.1. Example of a map without any added zones, positions, or markers.

The robot must have a map for every area that it operates in. It is important to create robust and reliable maps for the robot to perform effectively and safely.

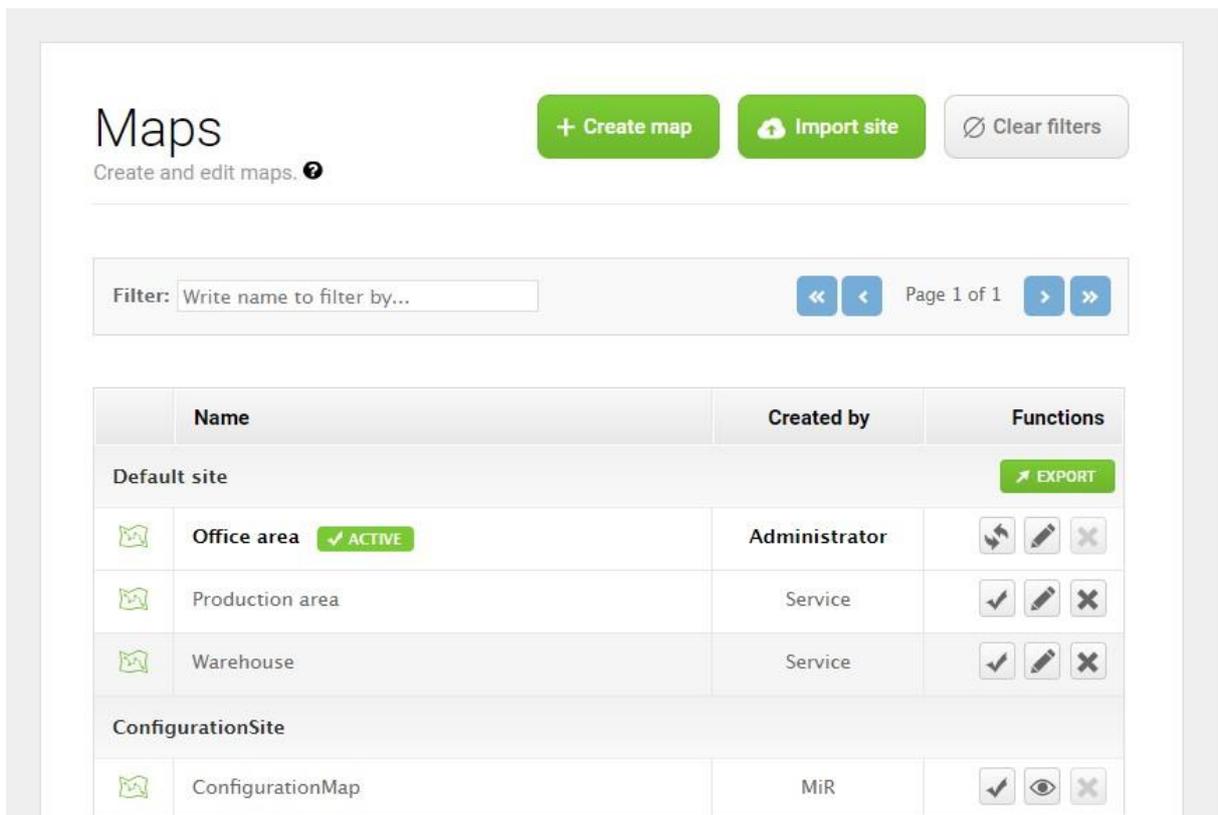


Figure 11.2. The **Default site** has three maps within it for the areas in the site: **Office area**, **Production area**, and **Warehouse**.

A site contains one or more maps that often connect to each other. The number of maps you need in a site depends on the work environment of the robot:

- If the operating area is very large, you may need to split the area into smaller maps.
 - You can tell that a map is too large if the robot takes a long time to plan its routes or often reports CPU errors.
 - In general, we recommend that maps should not exceed an area of 300 x 300 meters.
 - You can connect maps using map transitions—see *MiR Robot Reference Guide*, or ask your distributor for the guide *How to set up transitions between maps*.

- If the robot must operate on different floors connected with ramps or elevators, you must have a map for each floor.
 - If you are using an elevator, ask your distributor for the guide *How to set up elevators in MiR Fleet*.
 - If you are using ramps, connect the maps using transitions—see *MiR Robot Reference Guide*, or ask your distributor for the guide *How to set up transitions between maps*.



Each site also includes other elements in the interface, such as missions. For the full list of what is included in a site, see *MiR Robot Reference Guide* on the MiR website.

Creating a map

To create a new map, you drive the robot around its intended work environment while its sensors gather data to generate a map from. This process is known as mapping.

As the robot moves during mapping, the laser scanners detect physical obstacles, which are recorded on the map as walls. In the editing afterward, you can remove all obstacles that should not stay on the map, for example carts or boxes that were present at the time of recording but will not stay permanently.

Before you map a new location, be sure to do the following preparations:

- Clear the area of dynamic obstacles, such as pallets and carts. Dynamic obstacles can also be deleted from the map later.
- Ensure that all doors and gates that the robot should be able to go through are opened before mapping.

Avoid doing the following:

- Starting the mapping with the robot in a very open space.
- Getting the robot stuck close to walls or objects as you will have to push it away manually.

To create a new map, see *MiR Robot Reference Guide* on the MiR website. When mapping, you should apply the following best practices:

- Focus on mapping in a circular pattern around the perimeter of the working environment.
- When reaching long corridors with few obstacles, let the robot stay in position for approximately five seconds before moving down the corridor.
- Walk behind the robot as you map.
- End the mapping in the same place you started it.



For more information on creating a map, see the *Creating your first map*-course in MiR Academy on the MiR website. Contact your distributor for access to MiR Academy.

Cleaning up a map

The robot navigates best when using a clean map with as little noise as possible. **Figure 11.3** is an example of what a map can look like after the mapping process but where it still needs further editing.



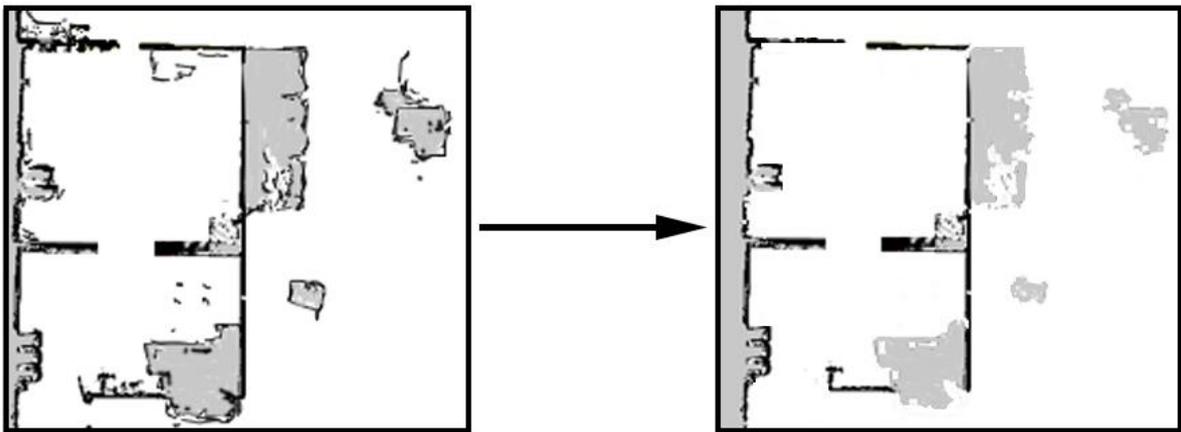
Figure 11.3. Example of a map that includes too much noise and dynamic obstacles.

There are several tools in the robot interface that you can use to improve your map:

- Use **Erase uploaded or recorded data**  when editing walls to remove walls that were created around dynamic obstacles and noise on the map.



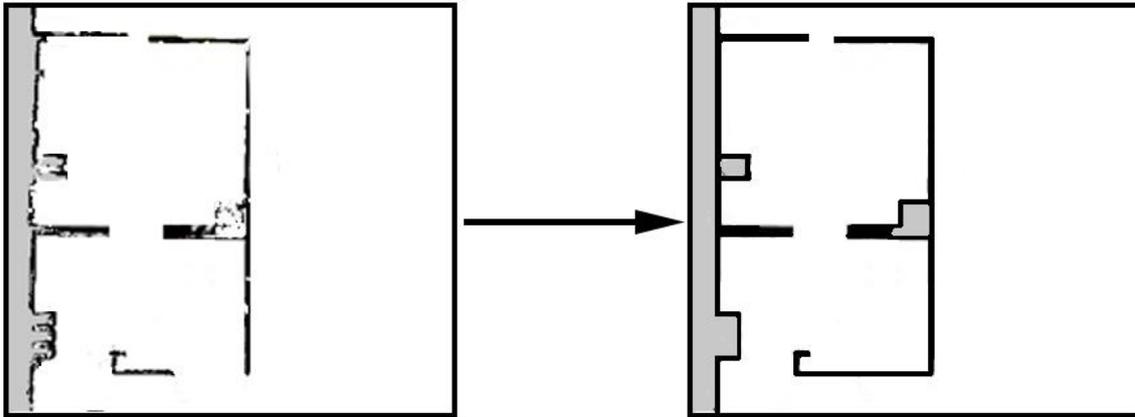
Noise refers to recorded data that originates from interfering elements. This can be physical obstacles that make the robot record walls where there are none or more subtle interferences that can make recorded walls appear pixelated.



- Use **Draw a new shape**  when editing floors to fill out the gray areas where there should be floor. When using this tool, you do not affect the walls on the map.



- Use **Draw a new line**  when editing walls to create solid and even walls.



Adding zones to the map

Adding zones to the map helps organize robot traffic. There are several different zones that can optimize the preferred paths and driving behavior of the robot.



For more information about what each zone does, see *MiR Robot Reference Guide* on the MiR website, or see the guide *How to use zones on a map*.



NOTICE

All zones are ignored when you drive the robot in Manual mode or when you use a Relative move action (except when using Relative move actions in Limit-robots zones).



NOTICE

The robot prioritizes the instructions it receives in the following order:

1. Instructions from zones.
2. Instructions from mission actions.
3. Instructions from system settings (except instructions from the setting Maximum allowed speed, which are never overruled by neither zones nor mission actions).

Examples of when and how to use zones

The following sections describe examples of cases where certain zones can be used to improve the robot's operations.



For more examples, see the guide [How to use zones on a map](#).

Descending staircases

Issue: The robot sensors cannot detect descending staircases. Marking a staircase as a wall on the map will only confuse the robot as it will try to navigate from a wall that is not there.

Solution: Mark staircases and areas surrounding staircases or holes in the floor as Forbidden zones on the map.

Low hanging fixtures

Issue: If a low hanging fixture is outside of the robot sensors' range, the robot may try to travel beneath it. This can be dangerous if the robot is carrying a tall top module or load that can collide with the fixture.

Solution: Mark the area where the low hanging fixture is located as a Forbidden zone.

Highly dynamic areas

A highly dynamic area is an area where objects are moved frequently. This could be a production area where pallets and boxes are often moved back and forth.

Issue: The robot will stop if a person steps out in front of it. In a transient work flow area, the robot will stop and reassess its paths many times a day, thereby wasting valuable time.

Solution: Mark highly dynamic areas on the map with Unpreferred zones (blue) or Forbidden zones (red) depending on the environment. Directional zones can also be used here to guide the robot in a specific direction.

If the robot has trouble with localization in a highly dynamic area, place some static objects with three meters of distance between them and mark them as walls on the map. Remove the 'walls' created from dynamic obstacles in the area. Static objects make it easier for the robot to localize and navigate the area.

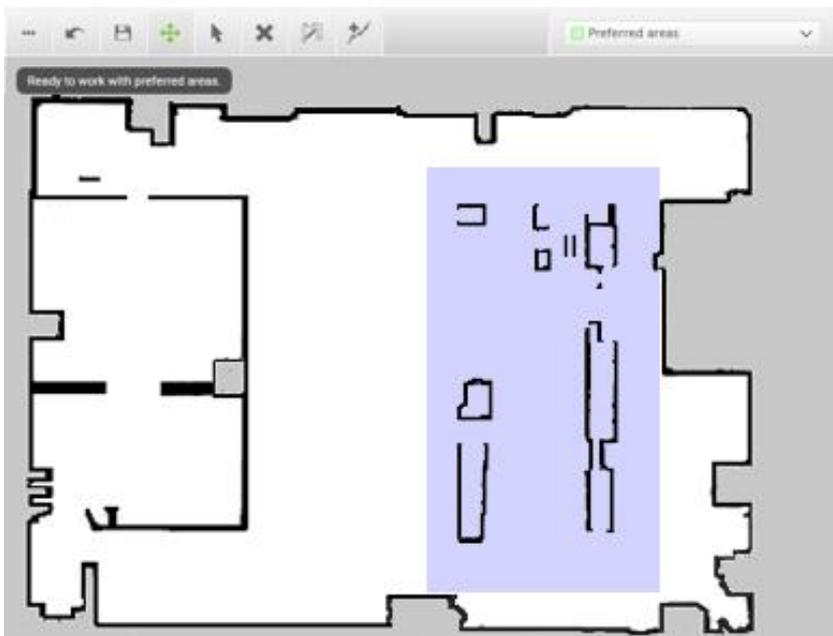


Figure 11.4. Unpreferred zones (marked with purple) can be used in highly dynamic areas to solve issues with replanning of paths.

Doorways

Going through narrow doorways can cause problems for the robot's global planner since the robot must drive closer to wall edges than it usually would. It can also be hazardous for the people working near the robot, as they might not see the robot coming.

Issue: The robot does not plan its global path through narrow doorways, since this will bring the robot too close to a known obstacle.

Solution: Add a Critical zone (orange) in the narrow doorway to enable the global planner to make a path through the corridor. You only need to place the zone down the center of the doorway so the center of the robot is in the zone. Add Sound and light zones (yellow) in narrow doorways to warn people near the doorway that the robot is coming through.

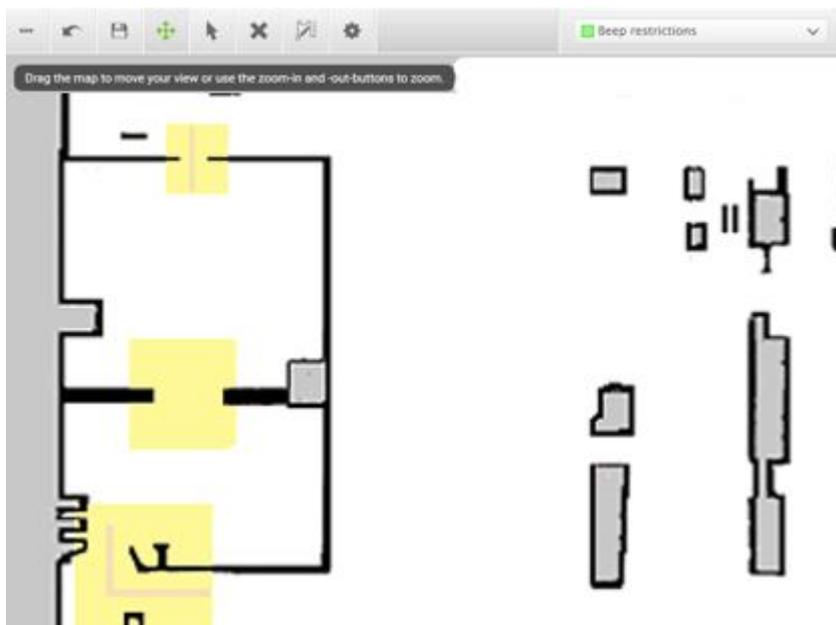


Figure 11.5. Narrow doorways can be marked with a Sound and light zone (marked with yellow) to warn people that a robot is coming through. A Critical zone (orange) can be placed in the narrow doorway to enable the global planner to make a path through the corridor.

Shelves

Shelves are often placed in a certain height above the floor on four (or more) posts and will often appear as dots on a map for the robot. This may cause the robot to believe that there is enough space (if the posts are far enough apart) below the shelves to pass through. The robot will then plan a path underneath the shelves, but when it comes closer, the camera will see the obstacle. This could result in replanning paths several times a day.

Issue: The robot will only see shelves as dots on the map and believe that it can make a global plan underneath the shelves.

Solution: Add a Forbidden zone (red) around the shelves.

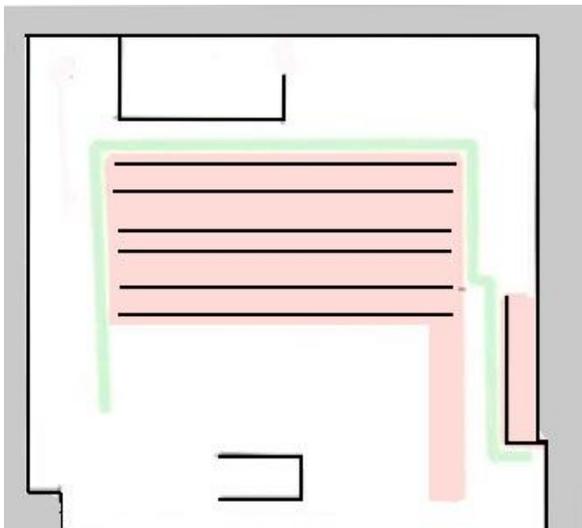


Figure 11.6. A Forbidden zone covering the shelf area.

Glass

Highly transparent glass may not be detected by the safety laser scanners.

Issue: The robot will not stop before driving into a glass window, door, or other glass objects.

Solution: Make the glass visible to the safety laser scanners by gluing non-transparent window film on the glass in the scanner height, 150 to 250 mm, or mark the wall as a Forbidden zone. Edit the map afterwards in the robot interface and mark the glass as walls to help the robot localize.

Directional lanes

Issue: In some areas, such as long corridors, robots driving towards each other may have a hard time passing each other efficiently.

Solution: If there is not enough space for the two robots to pass each other, you can create a two-way lane using Directional zones in combination with Forbidden or Unpreferred zones.

- Create a thin Forbidden zone (red) in the middle of the corridor parallel to the corridor walls. This is the lane separator.
- Create Directional zones (gray with arrows) on both sides of the Forbidden zone. Make the directions of the zones opposite.

With such a configuration, robots going in the opposite directions use different lanes and do not get in each others' way. Replacing the Forbidden zone with an Unpreferred zone gives robots more space for maneuvers, for example, if a robot needs to cross the lane separator to drive around an obstacle.



Figure 11.7. The robot drives down a two-way lane. The two Directional zone lanes are separated by a Forbidden zone.

If there isn't enough space for robots to pass each other, you can use a Limit-robots zone to specify that only one robot may drive down the corridor at a time.



To use Limit-robots zones, your robots must be connected to MiR Fleet.

11.4 Markers

Markers are defined as X-Y coordinates on a map that mark locations where you want the robot to travel to. Markers are points on the map that mark a physical entity, such as a charging station or a pallet rack, and enable the robot to position itself accurately relative to this entity.

You should always use markers when it is important that the robot is positioned accurately relative to an object in the work environment, such as load transfer stations and work stations.

Docking to markers

Markers require the robot to do a docking sequence. When the robot is docking, it uses its safety laser scanners to detect the marker and drives itself to the correct position relative to the detected marker. The robot begins docking to a marker from the marker's Entry position—see **Figure 11.8**. The Entry position is automatically created approximately one meter in front of the marker and can be moved in the map editor.

The Entry position can be manually moved, however moving the entry position does not guarantee that the robot is able to dock to the marker or dock within the claimed specifications. It is the responsibility of the person who moves the Entry position to validate and ensure that the docking can still be performed.

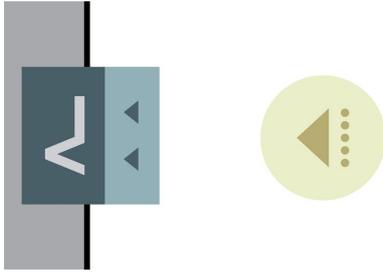


Figure 11.8. A VL-marker with its Entry position from the robot interface.



CAUTION

When a robot docks to a marker (except L-markers), it mutes its Protective fields and disables Collision avoidance, enabling it to drive closer to the marker. If an object is placed or personnel walk in front of the robot while these functions are disabled, the robot will continue docking until it collides with the obstacle.

- Mark the area around the marker as an operating hazard zone, and inform personnel not to walk in front of the robot while it is docking—see [Using operating hazard zones on page 173](#).
- Do not place objects directly in front of a robot marker.
- By default, Collision avoidance is disabled 0.2 m from the final docking point. If necessary, you can modify the distance under **System > Settings > Docking > Distance to marker for disabling collision checks**.



L-markers are the only markers where the Protective fields are not muted automatically. If you want the robot to mute the Protective fields while docking to an L-marker, you must use a Mute Protective fields action—see [Personnel detection on page 111](#).

Undocking from markers

A MiR robot can undock from markers automatically. When undocking, the robot reverses from the marker until it is outside of the undocking area—see **Figure 11.9**. The robot will keep muting its Protective fields while it undocks. Once the robot begins a new action that requires it to plan a new path, the Protective fields are activated again, and the robot continues normal operation.



The only case where the robot will not execute the undocking sequence is if you use a Relative move action right after the Dock to action. The robot will always execute the Relative move action first, and if the robot is outside of the undocking area after finishing the Relative move action, it will continue to the next action without undocking.

To enable automatic undocking from markers, go to **System > Settings > Docking** and enable the parameter **Undock from markers**.

You can also modify the size of the undocking area under **System > Settings > Docking** by using the parameters **Docked at marker reverse distance** and **Docked at marker side threshold**—see **Table 11.1**.

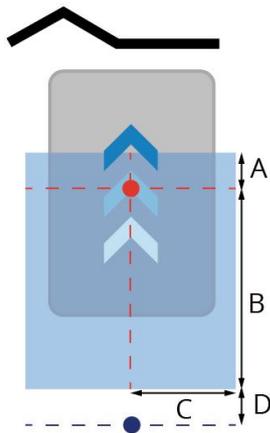


Figure 11.9. The undocking area initiates an undocking sequence for any robots with their center in the zone before beginning an action (except Relative move actions). The red dot represents the center of the robot when it is docked to the marker, the blue dot represents how far back the robot intends to move to undock from the marker, and the blue area represents the undocking area.

Table 11.1. Identification of the dimensions in <i>Figure 11.9</i>			
Pos.	Description	Pos.	Description
A	Always 100 mm. This is the distance in front of the robot's center when docked to the marker. This ensures that even if the robot is pushed forward a bit, it will still undock when leaving the marker.	B	The distance entered under Docked at marker reverse distance . This is the distance from the center of the robot when it is docked to the edge of the undocking area furthest from the marker.
C	The distance entered under Docked at marker side threshold . This is the distance to either side of the center line from the robot's docked position.	D	Always 100 mm. To make sure the robot's center has exited the undocking area, the robot aims to move back an additional 100 mm.

The undocking sequence will always occur if a robot begins an action where it plans a new route while inside the undocking area, even if the robot was not previously docked to the marker. This means the sequence is also initiated on robots that have entered the area via a Relative move action or Manual control.

The robot will reverse from the marker as long as it's orientation to the marker is below 90° . If the orientation difference is greater than 90° , the robot will move forward to exit the undocking area instead. This means that if the robot reverses into the area or is perpendicular to the marker, it will undock by moving forward.

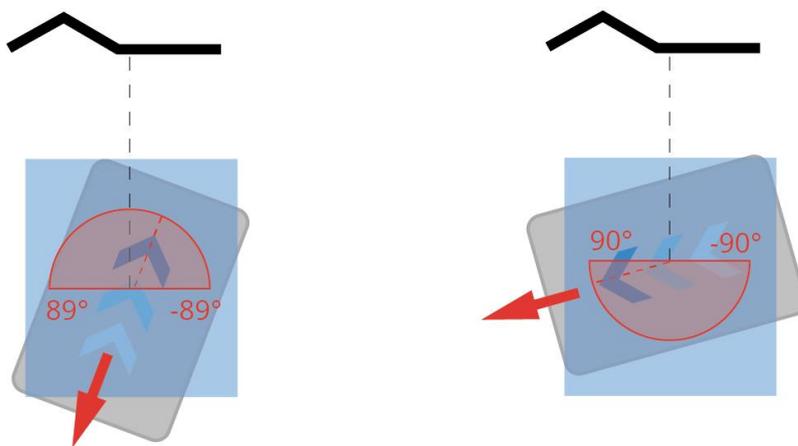


Figure 11.10. Robots that stop inside the undocking area at an angle less than 90° to the marker undock by driving backward. Robots that stop with an angle greater than 90° undock by driving forward.



L-markers are the only markers that do not support automatic undocking. If you want a robot to undock from an L-marker, you must use a Relative move action.

Types of markers

There are four standard marker types that all MiR robots can use: V, VL, L, and Bar-markers.

A **V-marker** is a small, V-shaped marker that is designed for the robot to either dock to so its front or its rear is facing the marker. The V-marker is the simplest marker available for the robot. It consists of a V shape with an interior angle of 120° and sides of 150 mm. The robot must dock straight toward the inside of the V.

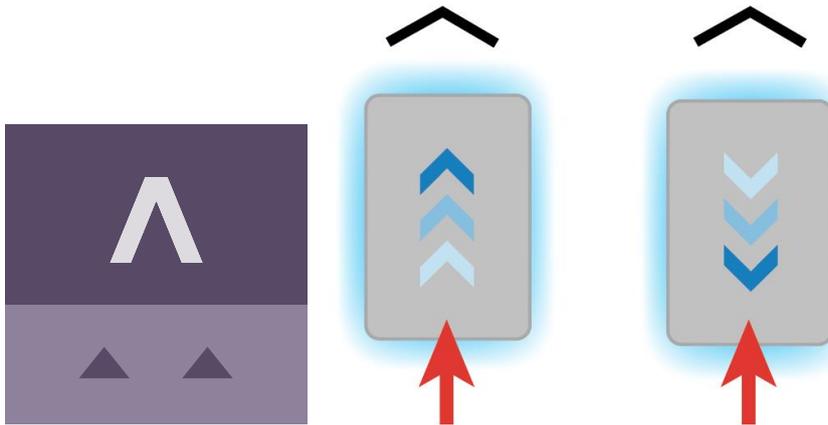


Figure 11.11. The icon used for V-markers in the interface and an illustration of how robots can dock to the marker.

A **VL-marker** is a larger marker that enables the robot to dock more accurately than V-markers. It consists of a V-marker with a 350 mm plate attached to the right of the V shape. Like V-markers, VL-markers are also designed for the robot to either dock to so its front or its rear is facing the marker. The robot must dock straight toward the inside of the V.

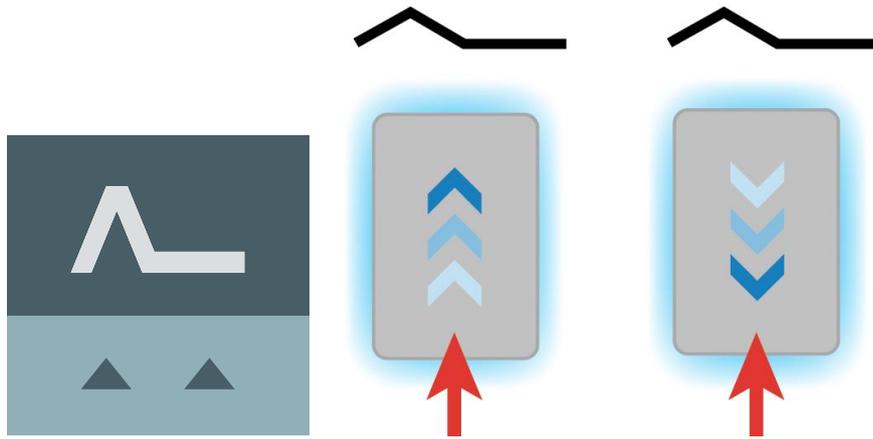


Figure 11.12. The icon used for VL-markers in the interface and an illustration of how robots can dock to the marker.

An **L-marker** makes it possible for the robot to dock in several different ways and orientations. Robots can both dock to the inside and outside of an L-marker, and the marker can be on any side of the robot. The marker is shaped liked an L with a defined angle of 90° and the dimensions 400 mm × 600 mm.

The robot must dock so the longer side of the L-marker is parallel with the right and left sides of the robot. If the robot is docking outside of the marker, it must approach from the side with the 90° corner.

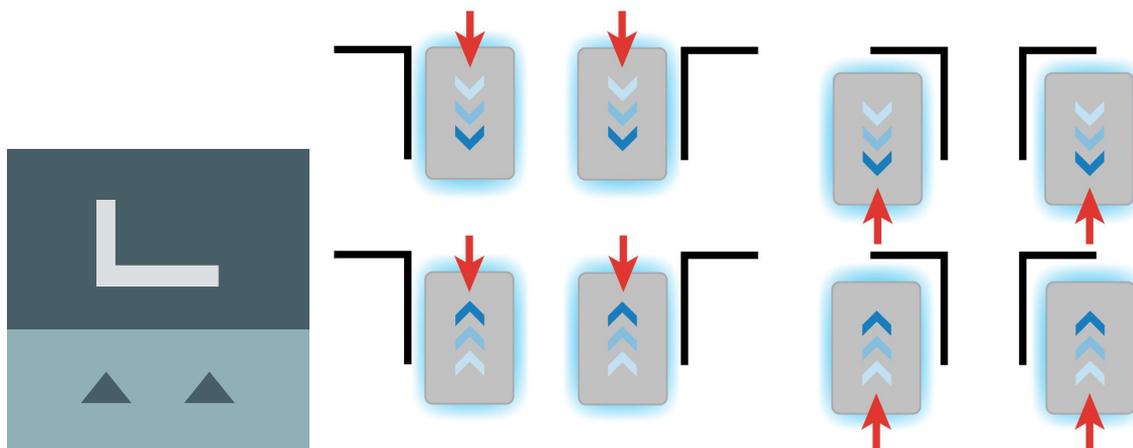


Figure 11.13. The icon used for L-markers in the interface and an illustration of how robots can dock to the marker.

A **Bar-marker** can be used for forward or reverse docking between two bars or plates, similar to pallet racks or shelves. Bar-markers must be between 400 mm and 2000 mm long, and the distance between the bars must be between 750 mm and 1500 mm. The robot can dock and undock from either end of the marker.



The distance between the bars must be larger than the physical dimensions of your robot.

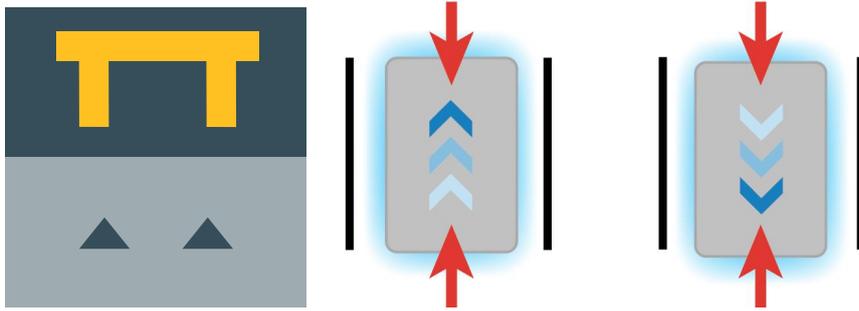


Figure 11.14. The icon used for Bar-markers in the interface and an illustration of how robots can dock to the marker.

Determine during commissioning how much space is required between marker to make docking possible.



For further information on markers, contact your distributor for the guide *How to create and dock to V-markers, VL-markers, L-markers, and Bar-markers.*



To create a marker, see [Creating markers on page 193](#).

11.5 Positions

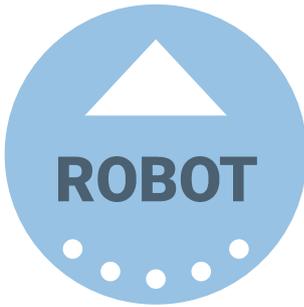
Positions are defined as X-Y coordinates on a map that mark locations where you want the robot to travel to. Positions mark a point on the map the robot travels to. To reach a position, the robot must be correctly localized on the map—see [Localization on page 99](#).

Positions are used either as destination positions or as waypoints on a route that you want to use in missions. With positions, the robot does not compare its position to a physical entity, making them less accurate than markers.

Generally, positions are used to mark where robots should wait when they are idle, which points robots must pass through along a route, or as destinations you often want to send the robots to.

The final orientation of the robot is indicated by the arrow on the position icon.

There are different types of positions depending on whether the robot is part of a fleet or drives with top modules, but the standard position that is available in all MiR applications is the Robot position. This position has no special features, it simply marks a location where you want to be able to send the robot to.



To create a position, see [Creating positions on page 200](#).

11.6 Creating missions

MiR robots function through missions that you create. A mission is made up of actions, such as: move actions, logic actions, docking actions, and sounds, which can be put together to form a mission with as many actions as needed. Missions themselves can also be nested into other missions.

Most actions have adjustable parameters, for example, which position to go to. Most actions can also use variables, enabling the user to choose the value of a parameter each time the mission is used. This can be practical in cases where the robot performs the same series of actions in different areas of the site that require different parameter settings in the mission actions.

When you create a mission, you can save it in the default **Missions group**, or you can choose to save it in any of the available actions groups. The actions groups are found in the top bar of the mission editor window, and you can distinguish missions from actions by the small icons shown next to their names: missions have a target icon , and actions have a running-man icon .

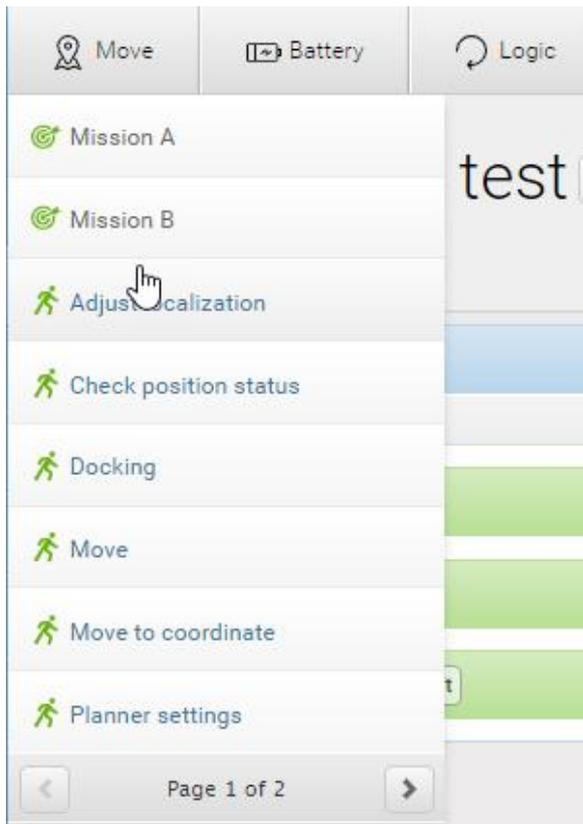


Figure 11.15. You can find the actions groups in the top bar of the mission editor window.



For more information on parameters and variables, see the guide *How to use variables in missions*.



NOTICE

The robot prioritizes the instructions it receives in the following order:

1. Instructions from zones.
2. Instructions from mission actions.
3. Instructions from system settings (except instructions from the setting Maximum allowed speed, which are never overruled by neither zones nor mission actions).

To create efficient missions, you should first familiarize yourself with the available actions in MiR Robot Interface—see the *MiR Robot Reference Guide*— and then consider:

- Which tasks do I want the robot to perform?
- Which actions are involved in this task and in which order are the actions executed?
- How much do each of these tasks differ? Are they similar enough that you can reuse the same mission but use variables for some of the parameters? If so, identify which of the parameters change in each mission—see **Figure 11.16**.

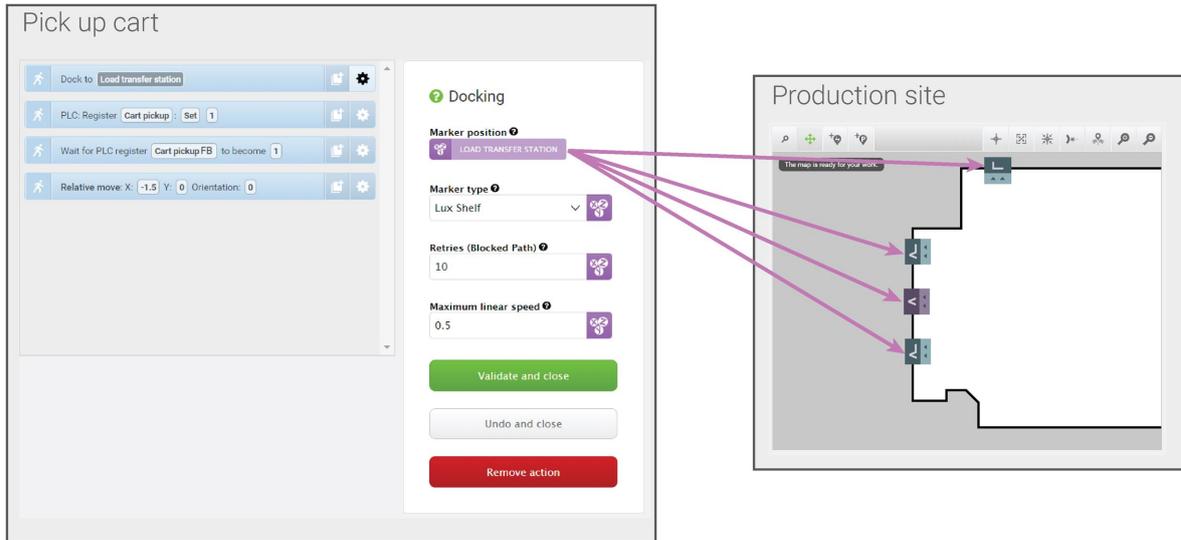


Figure 11.16. You can use variables to make a mission where you can set a parameter in one of the actions each time you use the mission (either when you add the mission to the mission queue or nest it in another mission). In this example, you can set the variable **Load transfer station** to any marker created on the map. This means that you can use the same mission for making the robot pick up a load from any of the markers on the map.

- Are there small parts of different missions that are the same each time where it would be worthwhile to make a mission for the repeated task and nest this mission into the larger missions? For an example, see **Figure 11.17**.

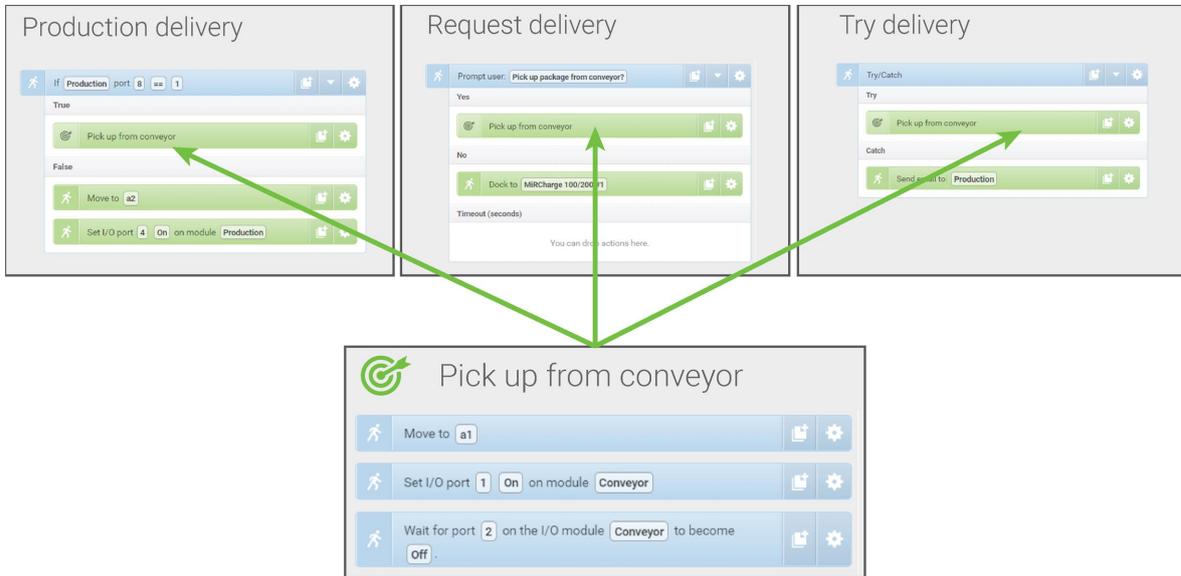


Figure 11.17. You can nest small missions into other missions. In this example, the mission *Pick up from conveyor* is used in three different missions. If you want to change how the robot picks up a package from the conveyor, you only need to change it once in the original mission instead of three times in each individual mission.



It is often a good idea to reuse the same missions if you know that any changes that may need to be applied to one of the tasks will also need to be applied to all other similar tasks.

When you make a mission, you should also consider all the possible outcomes from the mission and prepare it for the possibilities of error and what the robot should do if an error occurs—see an example of this in [Creating the mission Try/Catch on page 206](#).



For more information on building robust missions, see the *Mission robustness* videos in MiR Academy on the MiR website. Contact your distributor for access to MiR Academy.

When you have figured out which tasks you want the robot to perform and how many different missions you need to create, you should consider how you want to organize the missions in different mission groups. You can consider the following:

- Do you want to add the missions into existing action groups?
- Do you want to create new mission groups to organize your missions in? If so, consider how you want to divide your missions. For example, you can divide them based on function, location, priority, or responsible users.

The section [Usage on page 193](#) provides several examples of how to create simple missions with different types of mission actions and describes how you add a mission to the mission queue to test it. Whenever you create a mission, it is very important that you test it to ensure the robot performs as expected.



For more information on creating missions, see *MiR Robot Reference Guide* and the *Making your first missions*-course in MiR Academy on the MiR website. Contact your distributor for access to MiR Academy.

11.7 Creating a footprint

The footprint specifies how much space the robot occupies, including any loads or top modules. The footprint is defined by a number of points relative to the robot's center coordinate system and the total height of the robot application.

If your robot drives with loads or top modules that exceed the width or length of the robot, you must define new footprints for the robot to ensure that the robot plans its route correctly and avoids colliding with obstacles with its top module or load.

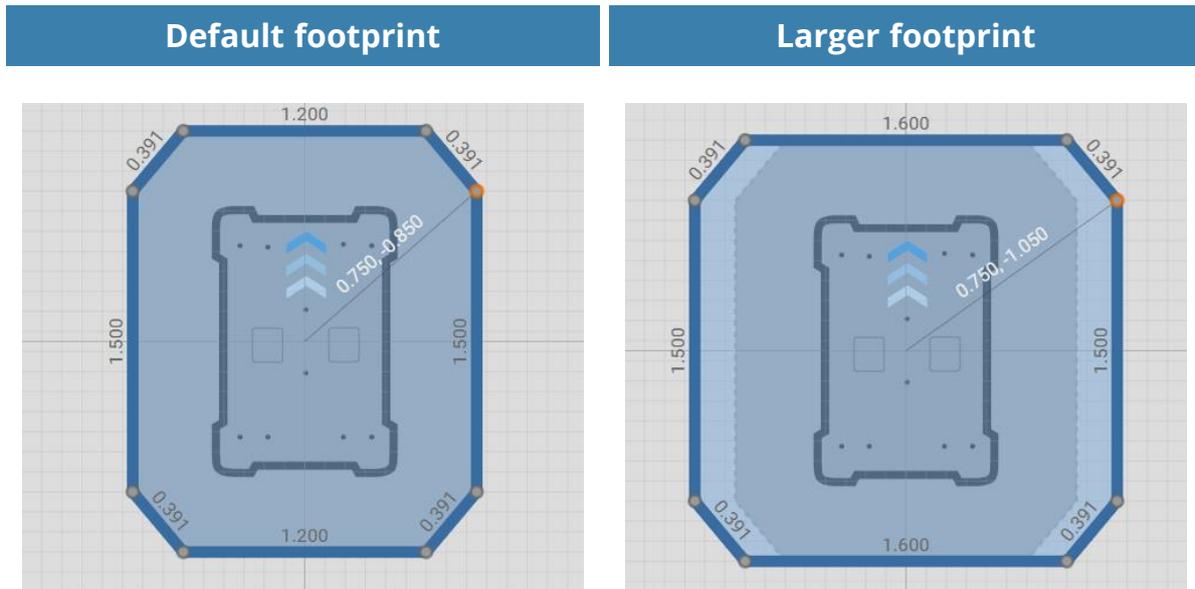


Figure 11.18. Examples of the default robot footprint and an extended footprint. The values displayed along each line is the length of the edge in meters.

The number of footprints you need to define depends on:

- The top modules you use with your robot.
 - If a robot's top module exceeds the width or length of the robot, you must define a new footprint for that top module.
 - If a top module has moving parts that can extend over the edges of the robot's footprint while the robot is moving, you must define a footprint that includes the moving parts when they are at their most extended positions.
- The loads the robot transports.
 - For each load the robot transports that exceeds the length or width of the robot, you must define a footprint for that load.
 - If you prefer to only have one footprint for the robot when it is carrying oversized loads, create a footprint that is suitable for the load that has the largest footprint.

- If there are low hanging fixtures that the robot can pass under only when it is not carrying certain loads or top modules, you must define new footprints for the various heights that the robot and its load can have to ensure that they don't collide with the low hanging fixtures.



CAUTION

The footprint is only used by the robot's global and local planner to avoid obstacles. The Personnel detection safety function—see [Personnel detection on page 111](#)—still uses the same Protective field sets. If your robot is carrying a load or top module that extends the footprint in front of or behind the robot, it may collide with personnel or equipment.

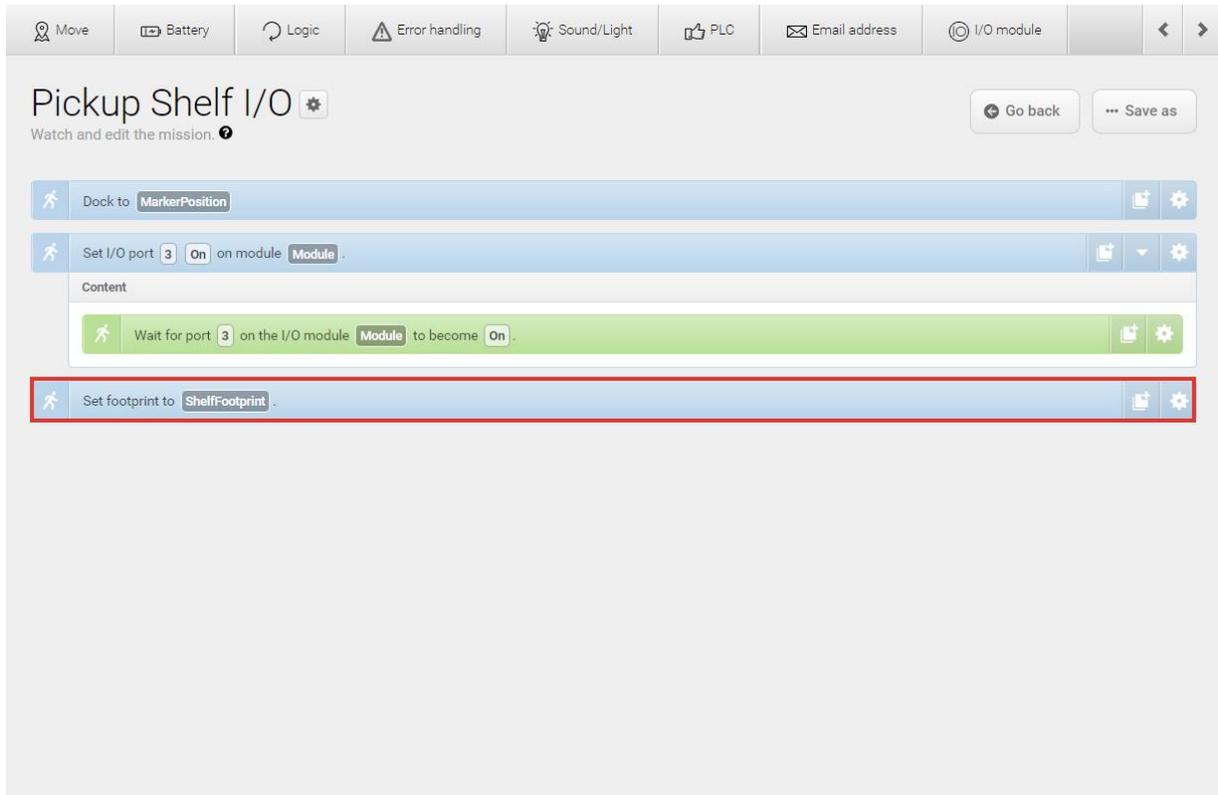
- Avoid extending the footprint in front of or behind the robot.
- Mark all areas where the robot drives with an unsafe load as operating hazard zones.
- Consider modifying the Protective field sets if necessary—see [Personnel detection on page 111](#).



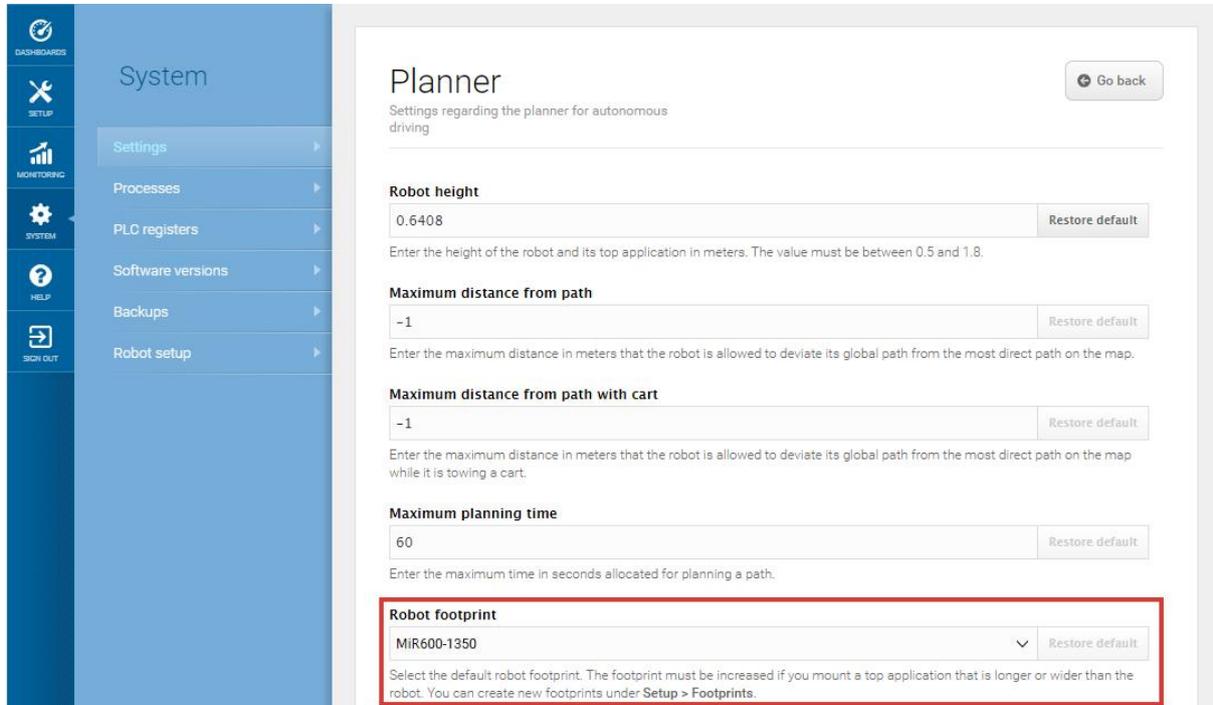
For a more thorough guide to creating footprints, see the guide *How to change the robot footprint*.

For more information about the footprint editor, see *MiR Robot Reference Guide*.

If you want to change the footprint in a mission, use the Set footprint action found under the Move action group. This is used to change the footprint when the robot picks up a load that extends the footprint or places a load and the footprint returns to the default.



If you want to edit the default footprint of the robot, for example if the mounted top module is larger than the robot, go to **System > Settings > Planner**, and select a new footprint under **Robot footprint**.



11.8 Using operating hazard zones

Operating hazard zones are areas that must be visibly marked to comply with safety standards in EN 1525 and ISO 3691-4. Personnel must be instructed to stay clear of operating hazard zones when a robot is approaching.

Areas where the robot drives with muted Protective fields and areas with inadequate clearance must be marked as operating hazard zones with signal tape or similar marking material. For more information about when the robot mutes its Protective fields, see [Personnel detection on page 111](#).

To create a sufficiently large operating hazard zone, the marking must be at least one meter away from the potentially hazardous area in all directions.



Robots may need more space to operate than the required operating hazard zone. Consider expanding operating hazard zones to include the required free space for operation to ensure that the robot can operate smoothly. For the robot's space requirements, see the space requirements guide for your robot on the Support portal or see the specifications for your robot on the MiR website.

It is not allowed to have work stations in operating hazard zones.

You can add zones to the map in the robot interface to mitigate the risks to personnel in operating hazard zones. We recommend considering whether adding the following zones can reduce the risks in an operating hazard zone:

- Speed zones can be used to reduce the speed of the robot to the minimum robot speed.
- Sound and light zones can be used to add acoustic and visual warnings when the robot drives into the zones.

For more information about zones, see the *MiR Robot Reference Guide*.

Docking to a marker

When docking to a marker, the robot mutes its Protective fields temporarily—see [Markers on page 155](#). This prevents the robot from entering Protective stop when it drives very close to the marker. Because the robot mutes its Protective fields, the area must be marked as an operating hazard zone.

The muting starts when the robot reaches the Entry position approximately one meter from the marker. To indicate this to people nearby, MiR1350 slows down and starts blinking yellow, using the eight signal lights on the corners of the robot.

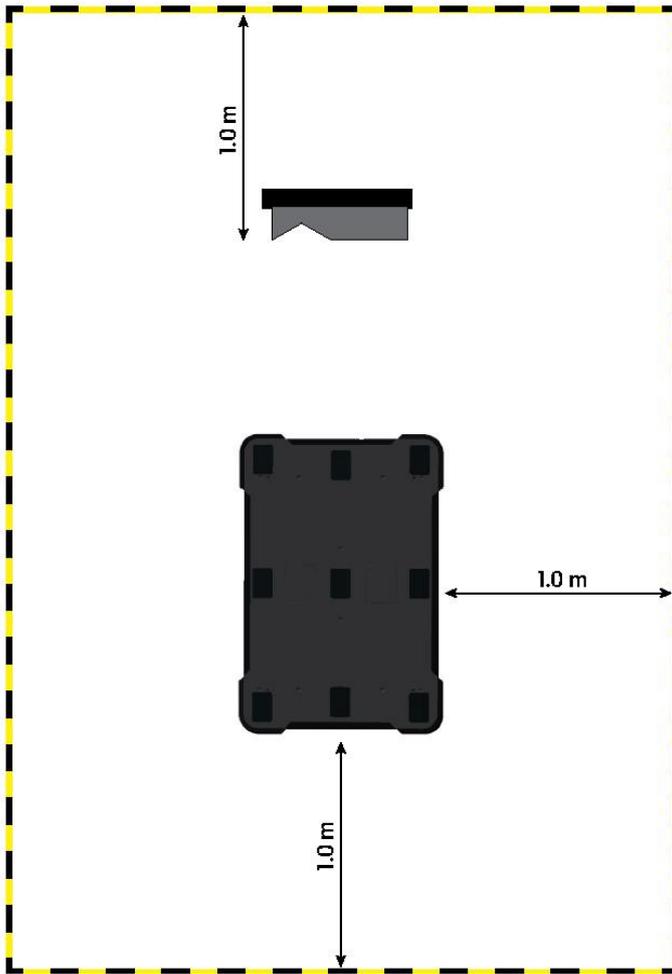


Figure 11.19. The striped black and yellow line identifies the required operating hazard zone around the marker. The robot is placed on the Entry position to the marker.

You must mark the floor area one meter around the docking marker and the robot when it is at the Entry position. This is illustrated in **Figure 11.19** where the robot is docking to a VL-marker.

11.9 Making a brake test

It is the responsibility of the commissioner to perform an adequate test of the robot's braking capability.

The braking distance of MiR1350 is particularly dependent upon four factors:

1. The speed of the robot
2. The payload of the robot
3. The surface the robot drives on
4. The decline of the surface the robot drives on

Because of this, it is not possible to predetermine the exact braking distance of MiR robots. The distance has to be determined in the environment and under the driving conditions the robot will be operating in.

The goal of the brake test is to ensure that the robot will brake in time to avoid a collision with a person or object when driving with maximum payload, with different field sets for different speeds, and at the steepest supported decline.

If the measured braking distance is too long, the Protective field sets of the robot should be made larger to ensure a safe installation. This can happen if the floor has low friction, for example, high gloss floors and similar. The Protective fields should always be at least somewhat larger than the braking distance at all speeds. To modify the field sets, see the guide *How to adjust the Protective field sets on MiR500, MiR600, MiR1000, and MiR1350*.

11.10 Creating user groups and users

All users of the robot must have a user profile in the system. Users are administered in the Users section where you set up, edit, and delete system users.

The user profiles are created during commissioning. By default, the robot has three user groups: User, Administrator, and Distributor. Parts of the user interface can be locked by the commissioner. The locked parts are typically related to the safety of the robot system, and changing these settings can violate the CE marking of the robot.

It is important to analyze and consider who is:

- Working directly with MiR1350 as direct users or operators?
- Responsible for MiR1350 as commissioner?

Furthermore, the following questions should be answered:

- How many different users are there?
- What tasks does each user have with MiR1350?
- What permissions should the different users have?
- What functions or widgets should be available for the different users?



For more details on users and dashboards, see [MiR Robot Reference Guide](#) on the MiR website.

Create user groups

In **Setup > User groups**, you can create specific user groups with specific access to different parts of the robot interface.

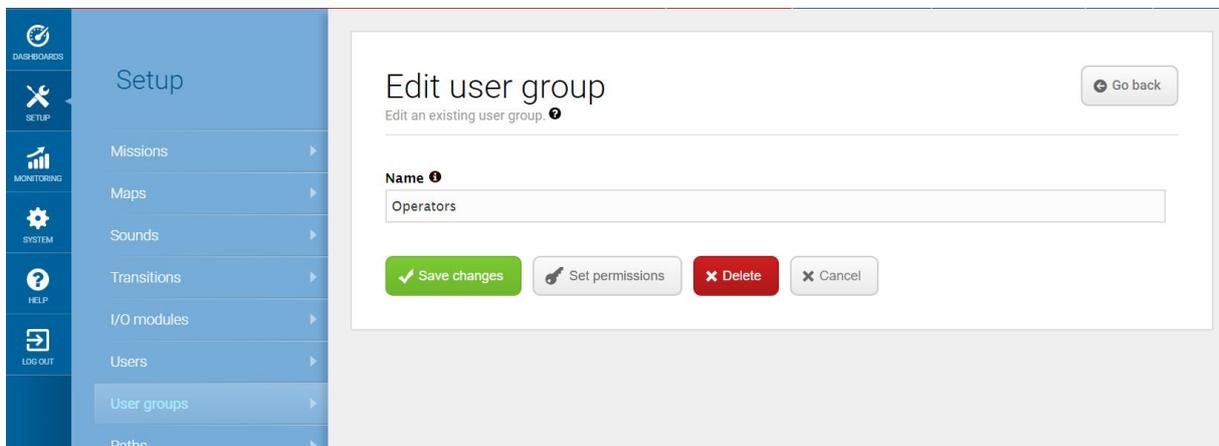


Figure 11.20. You can create specific user groups.

Under **Set permissions**, you can select the specific parts of the robot interface that the user group has access to.

Maps & positions		
	Section	<input type="checkbox"/> Write
	Sites	<input type="checkbox"/> Write
	Maps	<input type="checkbox"/> Write
	Zones	<input type="checkbox"/> Write
	Positions	<input checked="" type="checkbox"/> Write
	Paths	<input type="checkbox"/> Write
	Path guides	<input type="checkbox"/> Write
	Marker types	<input checked="" type="checkbox"/> Write

Figure 11.21. You can select the specific parts of the robot interface that the user group has access to.

Create users

In **Setup > Users**, you can create new users and select:

- Which user group they belong in.
- If they are Single-dashboard users with no access to other parts of the interface than to control the robot from a dashboard.
- If they should be allowed quick access to the interface via a four digit PIN code. We only recommend PIN codes for users with no access to settings and safety system.

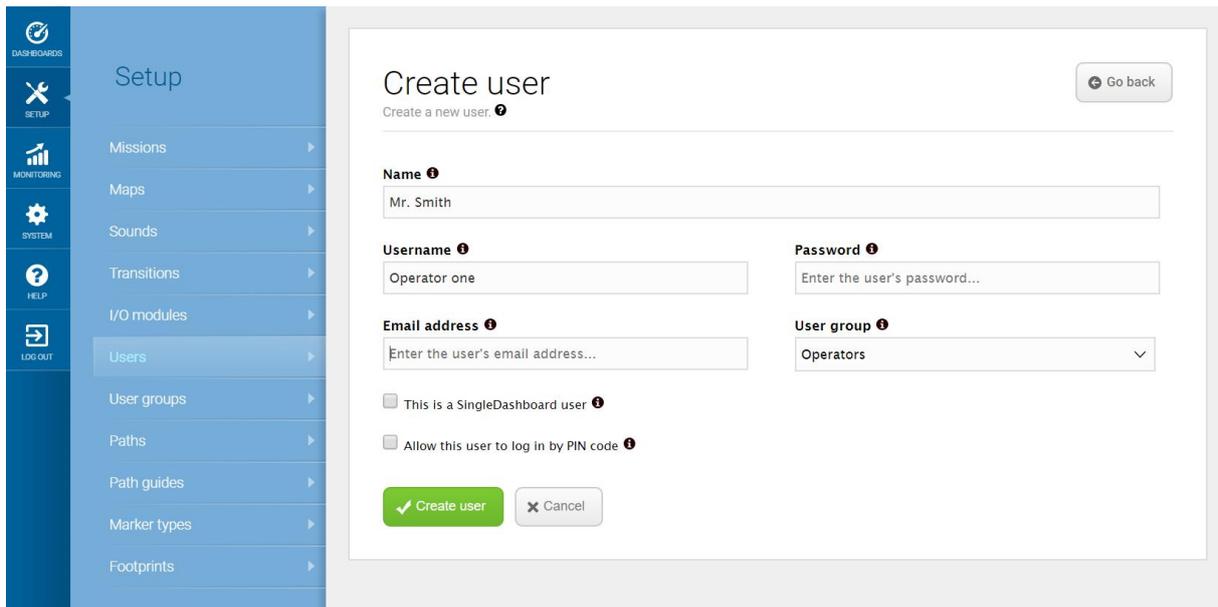


Figure 11.22. When you create a user, you must fill out the fields shown in this image.

Table 11.2.
Examples of which users MiR recommends should be able to edit which features

Feature	User group
Controlling the robot manually	Operator
Creating maps and positions	Commissioner
Creating and editing missions	Operator
Adjusting warning sounds	Commissioner
Creating new user groups	Commissioner
Assigning missions	Direct user
Changing system settings	Commissioner

11.11 Creating dashboards

To make the user experience as easy and simple as possible, you can build a unique dashboard for each user. Dashboards are an easy way for different user groups to control the robot, giving direct access to the individual groups' key functions.



For more details on how to use and create dashboards, see *MiR Robot Reference Guide*.

A dashboard is made up of a number of widgets, each representing a feature in the system, for example a particular mission, the map the robot is operating on, or the current mission queue.

The system comes with a default dashboard—see **Figure 11.23**—, and users with access rights to create dashboards can create an unlimited number of additional customized dashboards.

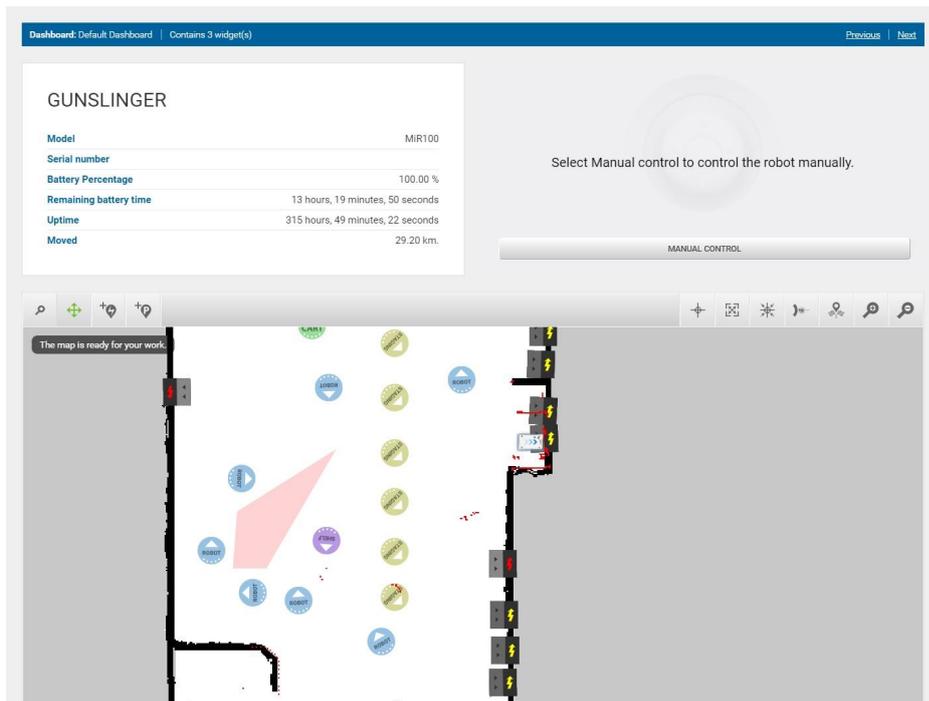


Figure 11.23. The default dashboard includes the robot information, a joystick for manual control, and the active map.

When creating new dashboards, you should consider the following:

- Who will be using the dashboards?
- Which functionalities will they need to use the most?
 - For example, if your robot uses many I/O modules, you may want to monitor them from the dashboard, or if there is a mission that the robot often has to execute on demand, you may want to add it to the dashboard.
- Will each user or user group need a different dashboard? If so, what should be included in each?
- Will some users need more than one dashboard?
 - Users that are responsible for both maintaining and operating the robot could have separate dashboards for the maintenance routine and another dashboard for operating the robot.

- If you have any Single-dashboard users, which functionalities will they need and which would be useful to include?
 - Often it is not a good idea to include too many widgets in the dashboard as this can slow down the interfacing to the robot. Try to include only the necessary widgets.

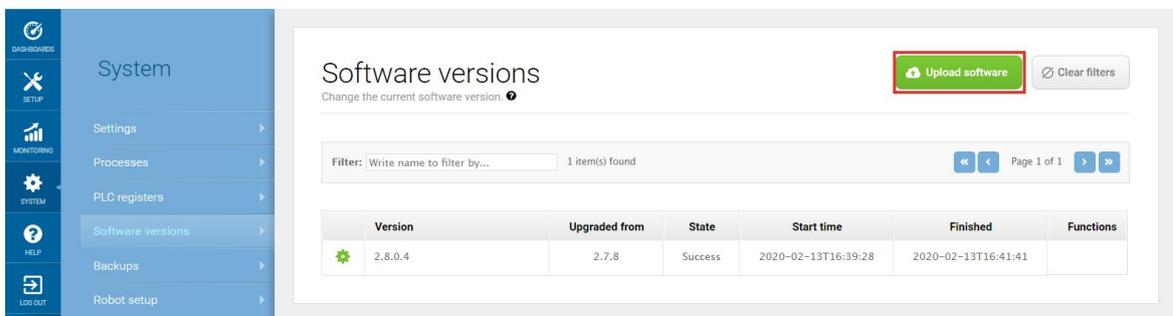
11.12 Updating software

MiR continuously updates the software the robots use, either to fix issues, to improve existing features, or to introduce new features. Each software release is issued with a release note explaining the content of the update and its target audience.

Contact your distributor for the latest recommended update file and see *How to update a MiR product's software* on the Support Portal.

Follow the steps below to update MiR1350 software:

1. Connect your computer to the robot you want to update, and sign in to the robot interface.
2. Go to **System > Software versions** and select **Upload software**.



3. Locate and select the downloaded software package. It may take 10-20 minutes for the package to successfully upload depending on whether or not the software introduces new security patches.
4. Once the software is uploaded, turn the robot off and then on again.

11.13 Creating backups

It can be useful to create a backup if you at a later stage want to be able to revert to the exact state of the current software, including data such as settings, missions, and reports.

We recommend to create a backup in the following cases:

- Before you update the robot software.
- Before making any large changes to your site.



Backups take up some of your robot's memory space. It is a good idea to remove any old backups you are certain you will not need in the future.

For more information on how to create, roll back, and delete backups, see *MiR Robot Reference Guide*.

11.14 System settings

This section describes some of the commonly used system settings of MiR1350 that the commissioner must be aware of.



Only the basic system settings are explained in this section—see *MiR Robot Reference Guide* for more information.



NOTICE

The robot prioritizes the instructions it receives in the following order:

1. Instructions from zones.
2. Instructions from mission actions.
3. Instructions from system settings (except instructions from the setting Maximum allowed speed, which are never overruled by neither zones nor mission actions).

In **System > Settings**, you can access the settings of the robot. Access to the settings must be restricted by the commissioner—see [Creating user groups and users on page 176](#).

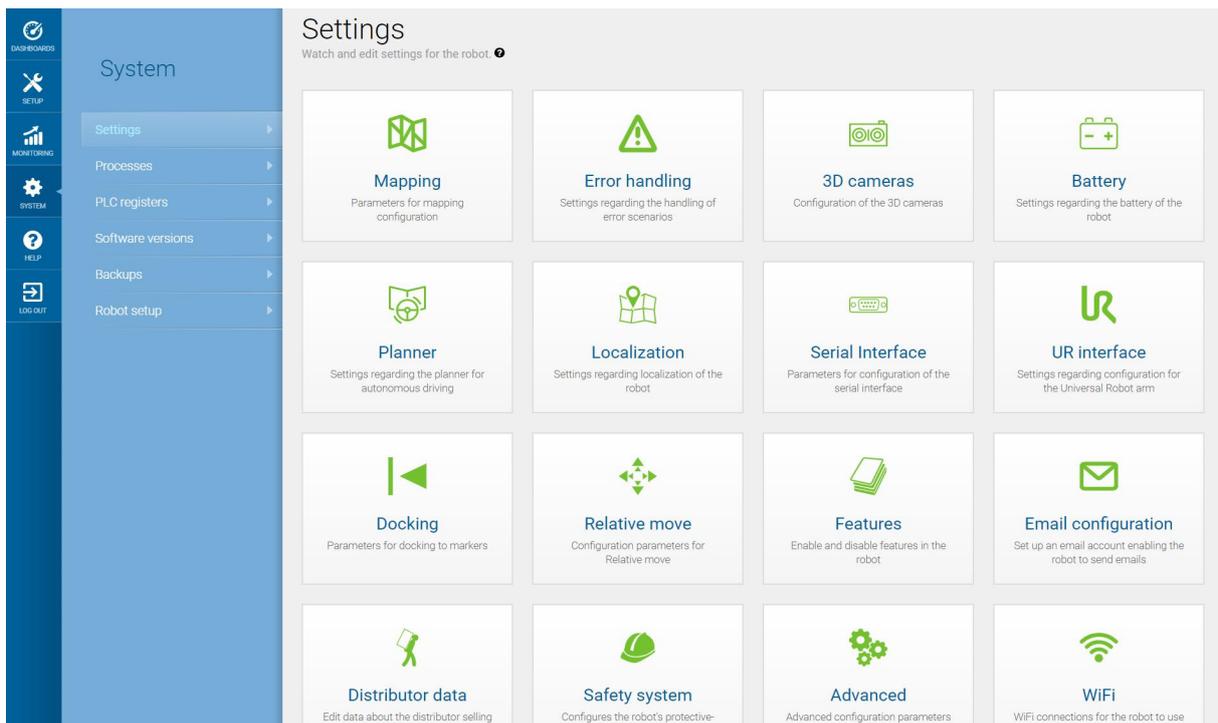


Figure 11.24. Under **System > Settings**, there are several menus where you can edit your robot's settings.



Remember to restart the robot if you have made any changes to the system settings.

Planner

In the Planner section, you set the basic parameters for driving the robot.



This section refers to the local and global planner functions. For more information on the robot's path planners, see [Global planner on page 88](#) and [Local planner on page 89](#).

Planner

Settings regarding the planner for autonomous driving

Go back

Robot height

1.4

Restore default

Defines the robot height (Default: 1.4, minimum: 0.5, maximum 1.8).

Max distance from path

-1

Restore default

Maximum distance in meters that the robot is allowed to deviate from the optimal path in the map.

Max distance from path with cart

-1

Restore default

Maximum distance in meters that the robot with a cart is allowed to deviate from the optimal path in the map.

Maximum planning time

60

Restore default

The maximum time allocated for planning a path. The value is specified in seconds.

Path timeout

0

Restore default

Timeout before asking for a new global plan [in seconds]. Note! Negative value means infinite waiting time.

Path deviation

-1

Restore default

Maximum distance in meters that the robot is allowed to deviate from the path planner in the map. Note! Negative value disables the feature.

Indicator light

False



Restore default

Set to True to enable indicator lights while driving autonomously.

Figure 11.25. You set basic parameters for driving the robot in the Planner section.

Robot height defines the height of the robot including top modules. Use this setting if your robot operates permanently with a top module that makes the combined robot application higher than the robot itself. This prevents the robot from colliding with obstacles from above.

Max distance from path defines the maximum allowed distance in meters that the generated global path is allowed to deviate from the most direct path on the map. By default, this parameter is disabled, meaning the robot will always make a global path and follow it to the goal position no matter how far the path is. If you want to avoid the robot traveling paths of a specific length and report an error instead, enter the maximum length that the global path may exceed the most direct path.

Maximum planning time defines the maximum time allowed for planning a path. By default, this parameter is disabled, meaning the robot will always try to finish planning a global path no matter how long it takes. If you want the robot to report an error after a set time period instead, enter the maximum amount of time in seconds that the robot can spend planning a path before it reports an error.

Path timeout defines the maximum time the robot's path can be blocked before the robot generates a new global path. By default, this value is 0, meaning the robot will not wait if its current global path is blocked by an obstacle it cannot navigate around using the local planner. If you want the robot to wait and see if the obstacle moves before planning a new path, enter the maximum waiting time.

Maximum path deviation defines the maximum distance in meters that the local path is allowed to deviate from the global path before the robot makes a new global path. By default, this parameter is disabled, meaning the robot can deviate from the global path using the local planner to go around an obstacle as far as possible in the map.

Optimizing the timeout and deviation of paths is useful in situations where you want to configure how strictly the robot should follow the path it has planned. Making the robot follow the exact path it has planned with little or no deviation is known as Line-following mode.



This can be useful, for example, in narrow corridors where there isn't enough space for the robot to go around dynamic obstacles—see **Figure 11.26**.

For more information on Line-following, see the guide *How to set up Line-following mode*.

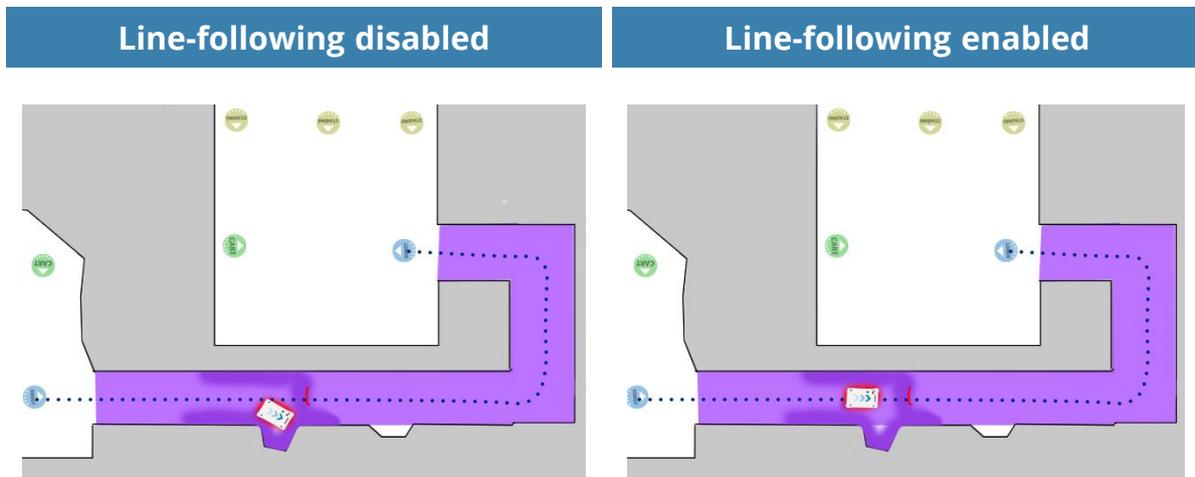


Figure 11.26. Example of where the robot might benefit from using a Line-following configuration. When there isn't enough space for the robot to go around an obstacle, it will often spend more time trying to maneuver around the obstacle and correct its trajectory afterward than it would have just waiting for the obstacle to move out of the way.

Maximum allowed speed defines the overall speed limit of the robot. The maximum allowed speed will never be exceeded no matter what is stated in a mission or Speed zone. This setting can be useful if, for example, the robot transports motion sensitive objects or if the work environment in other ways requires the robot to always stay below a certain speed threshold.

Desired speed sets the desired speed of the robot. This setting can be useful in the same way as maximum allowed speed, but with this setting, the robot will drive faster than the set desired speed in a Speed zone that requires it.

Docking

In the Docking section, you can change the parameters regarding docking to and from markers.

Docking

Parameters for docking to markers

Go back

Undock from markers

True Restore default

Select True to make the robot undock before starting move from docked position.

^ Hide advanced settings

Distance to marker for disabling collision checks.

0.2 Restore default

Distance to marker where collision detection is disabled.

Docked at marker side threshold

0.4 Restore default

Side threshold for being docked to a marker

Docked at marker angle threshold

20 Restore default

Angular threshold for being docked to a marker

Parameter for driving more straight during docking

1.0 Restore default

Setting of maximum allowed change to marker estimate when the robot moves towards a marker (in meters per meter). Reducing the value of this parameter makes the robot move more straight during docking. However, it also reduces the precision of the docking.

Relative move target when docking to markers.

0.5 Restore default

Relative move target offset when docking to markers. The value is specified in meters.

Figure 11.27. Change the parameters regarding docking to and from markers in the Docking section.

In **Undock from markers**, you can select if the robot should undock from a marker before it starts moving from a docked position. It is usually best to set this setting to **True** to prevent the robot from going into Protective stop when moving away from markers.



The robot cannot undock from L-markers automatically—see [Markers on page 155](#). You must use a Relative move action.

In the advanced settings, you can adjust the parameters for docking to markers. This can be useful in case of docking issues. To see the advanced docking settings, select **Show advanced settings**.

Safety system

In the Safety system section, you can change which warning sound the robot should emit when it mutes its Protective fields and how loud the sound should play.

Safety system
Configures the robot's protective-fields system

Go back

Muted-protective-fields sound

Beep Restore default

When the robot drives with muted protective fields, this warning sound is played.

Muted-protective-fields volume

50 Restore default

The volume for warning sounds

Save changes Cancel

Figure 11.28. In the Safety system section, you can change the robot's warning sound.

Select **Muted protective fields sound** to change the warning sound that is played when the robot drives with muted Protective fields.

Select **Muted protective fields volume** to set the volume in decibels for the warning sound that is played when the robot drives with muted Protective fields.



CAUTION

- Always have the robot play an audible warning sound when driving with muted Protective fields.



CAUTION

Unaware personnel may not see the robot in certain situations and risk colliding with the robot. This may result in injury to personnel or damage to equipment.

- Make sure to adjust the volume of the robot's warning sounds so they are audible in the robot's work environment.
- Implement warning sounds from the robot in missions and areas where it can reduce the risk of hazardous situations.

Features

In the Features section, you can disable and enable robot features.

Features

Enable and disable features in the robot

Go back

Shelf

False Restore default

Select **True** if the robot is used to pick up and place shelves.

Email address

True Restore default

Select **True** to add an action for sending emails from missions.

PLC registers

True Restore default

Select **True** to add actions for setting PLC registers from missions and monitoring PLC register in the robot interface.

Universal Robots Interface

False Restore default

Select **True** to add an action for running UR-programs from missions.

Fleet

False Restore default

Select **True** if the robot is part of a fleet

Modbus

False Restore default

Select **True** if the robot uses Modbus

I/O modules

True Restore default

Add actions for communicating with IO modules

Figure 11.29. Disable and enable robot features in the Features section.

Shelf enables the shelf feature. Enable this feature if the robot is used to pick up and place shelves. This modifies how some of the pins in the electrical interfaces are used.

Email address enables an action for sending emails from missions. You can configure the email account that the robot sends the emails from under **System > Settings > Email Configuration**.

PLC registers enables actions for setting PLC registers from missions and monitoring PLC registers in the robot interface. When enabled, you can access the page **System > PLC registers** to set up the registers.

Universal Robots Interface enables an action for running Universal Robots programs from missions. Enable this feature if the robot drives with an application from Universal Robots.

Fleet makes the robot visible for MiR Fleet. Enable this feature if the robot is part of a fleet.

Modbus enables Modbus communications. When enabled, you can access the page **System > Triggers** to set up the Modbus triggers.

Pallet lift enables the lift feature. Enable this feature if the robot has a pallet lift or shelf lift top module mounted to it. This modifies how some of the pins in the electrical interfaces are used.

I/O modules adds actions for communicating with I/O modules. This can be used for setting PLC registers and trigger missions. Enable this feature if the robot uses I/O modules, for example, when any MiR top module is mounted to the robot.

Mute protective fields enables an action to mute the robot's Protective fields in missions.

12. Usage

The main way to use MiR1350 is through missions that you create.

In the following sections you will find practical examples of how missions can be tailored to different tasks. The examples include:

- Setting markers and positions on the map.
- Creating a mission that uses a Prompt user action. The example mission is titled *Prompt user*.
- Creating a mission that uses a Try/Catch action. The example mission is titled *Try/Catch*.
- Creating a mission that uses variables. The example mission is titled *Variable docking*.

12.1 Creating markers

Before creating a marker, you must ensure that the robot is localized correctly on an active map. If in doubt, you can check if the red lines representing the laser scanner view match the black lines on the map, as shown in **Figure 12.1**.

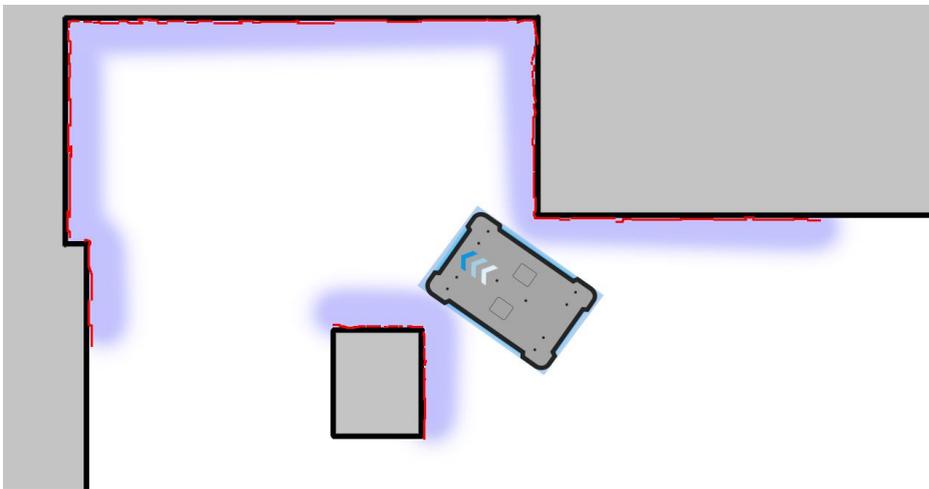
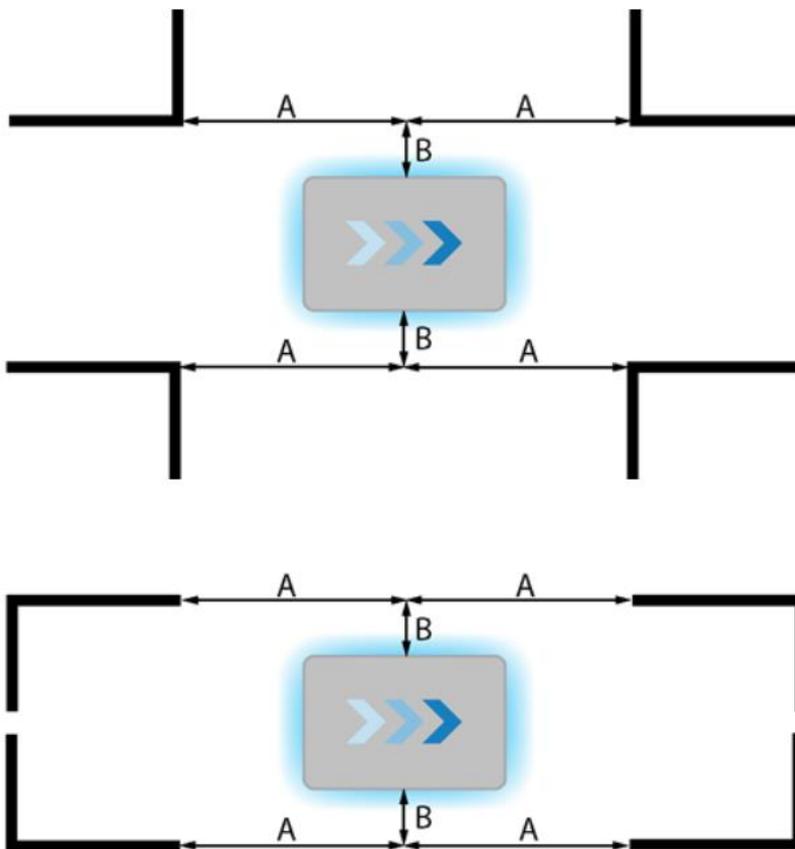


Figure 12.1. The red lines represent the obstacles the laser scanners detect. The robot is localized correctly when the red lines align with the black lines that represent walls.

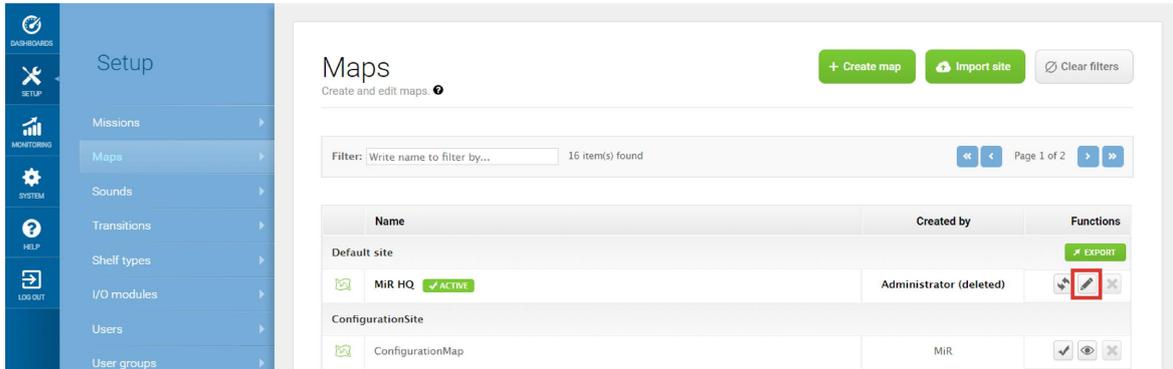
Once the robot is localized, you can insert a marker on the map. In this example, we are using a VL-marker . To create a marker, follow these steps:

1. Place your physical marker where you want the robot to dock.
2. Manually drive the robot to the marker so the robot is facing the marker. The correct distance from the marker differs depending on the marker type:
 - For L-markers, the following values apply:
 - A: 1 000 mm \pm 50 mm
 - B: 200 mm \pm 50 mm

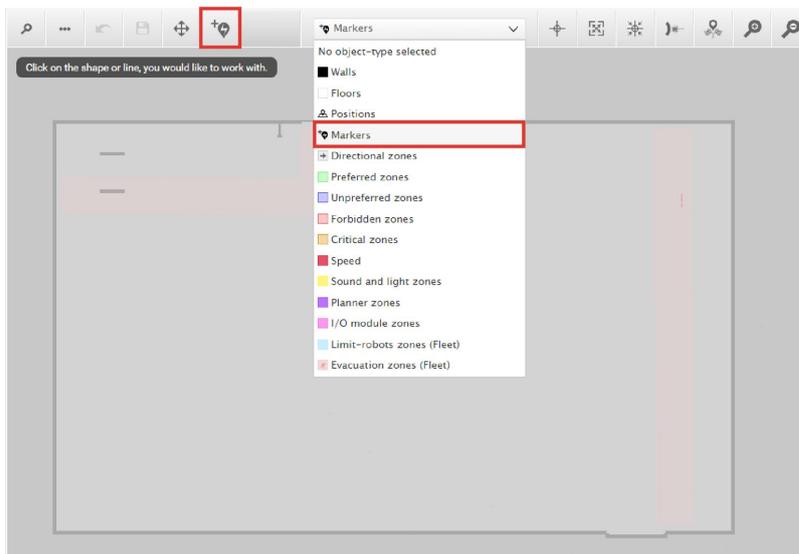


- For all other markers, the robot must be positioned approximately one meter directly in front of the marker.

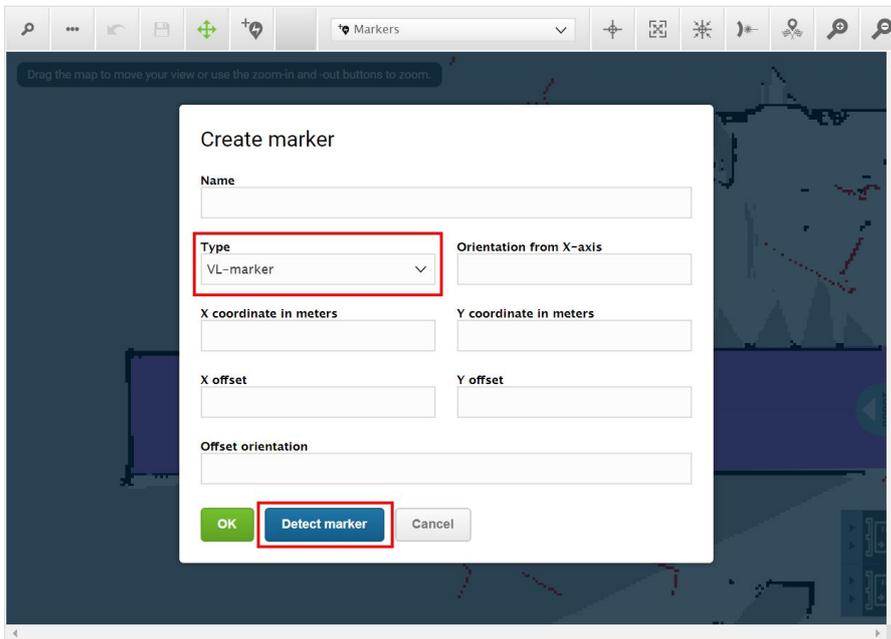
3. Go to **Setup > Maps**, and select **Edit**  for the active map.



4. Within the editor, select **Markers** in the Object-type drop-down menu, and then select **Draw new marker**  in the editor tools.



- In the **Create marker** dialog box, name the marker. Under **Type**, select your marker type. In this case, a **VL-marker** is used. Then select **Detect marker**.



The X, Y, and orientation values will automatically be filled out with the current position of the robot.

- If the robot cannot detect the marker, verify that the robot is correctly positioned and that the laser scanners can detect the marker in the active map by checking that red lines are displayed on the map where the marker is.
- If you are trying to make the robot detect an L-marker but it keeps detecting other objects with a 90° angle instead, shield the objects that the robot is not supposed to detect with a flat plate.
- If you want the robot to dock straight to the marker, set the **Offset orientation** to 0°. If you want the robot to reverse into the marker, set the **Offset orientation** to 180°.



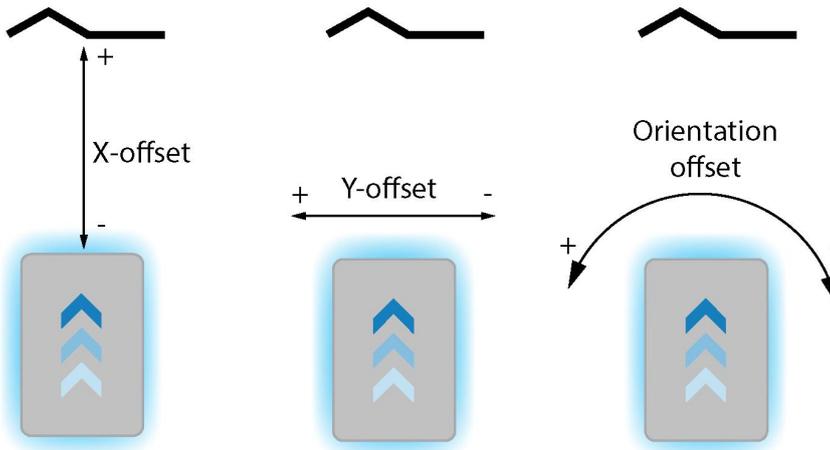
Detecting the marker with the rear scanner will automatically set the orientation offset to approximately 180° for a reverse docking.

- To change where the robot stops relative to the marker, you can adjust the offsets.

Edit marker

Name	
ROEQ_Docking yoyo cart	
Type	Orientation from X-axis
VL-marker	-91.612
X coordinate in meters	Y coordinate in meters
26.152	18.196
X offset	Y offset
-0.51	0.04
Offset orientation	
0	

- The X-offset moves the robot closer to or further from the marker in meters.
- The Y-offset moves the robot further to the left or right of the marker in meters.
- The orientation offset changes the final orientation of the robot in degrees.



For more information about the marker offsets, see *How to create and dock to V-markers, VL-markers, L-markers, and Bar-markers.*

6. Select **Save** to create the marker. The marker is now visible on the map.



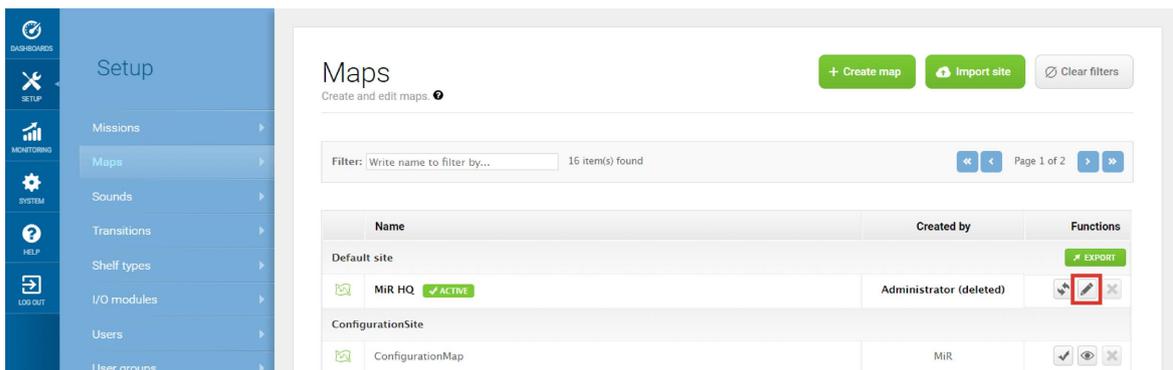
You can make the robot dock to the marker by selecting it on the map and selecting **Go to**. The marker can also be used in missions.



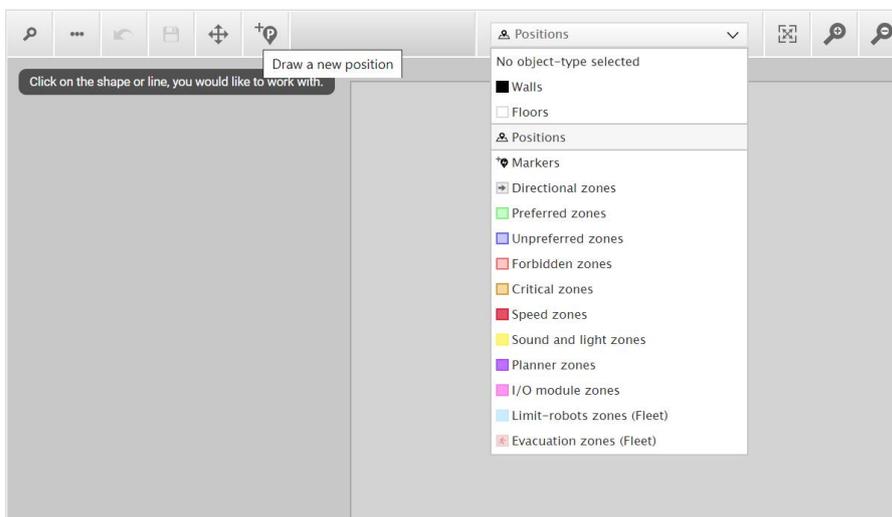
12.2 Creating positions

The following steps describe how to create a position on a map. In this example, we are creating a Robot position .

1. In the robot interface, go to the map editor of the map where you want to create a position. This is done by going to **Setup > Maps** and selecting **Edit**  next to the map you would like to work on.



2. In the Object-type drop-down menu, select **Positions**, and then select **Draw a new position** .



3. Select where on the map you want the position to be, and choose in which direction you want it to face.

- Name the position. Under **Type**, select which type of position you want to make. In this example we are making a Robot position.

Create position

Name
Test

Type
Robot position

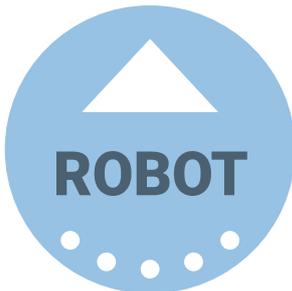
Orientation from X-axis
-74.604

X coordinate in meters
6.950

Y coordinate in meters
11.250

OK Cancel

- Select **OK** to create the position. The position is now visible on the map.



You can send the robot to the position by selecting it on the map and selecting **Go to**. The position can also be used in missions.

GO TO	Send robot to this position
EDIT	Edit this position's name and parameters.
DELETE	Delete this position from the map.
SHOW ENTRY POSITION(S)	Show entry position(s) for this position.
CANCEL	Close this dialogue.

12.3 Creating the mission *Prompt user*

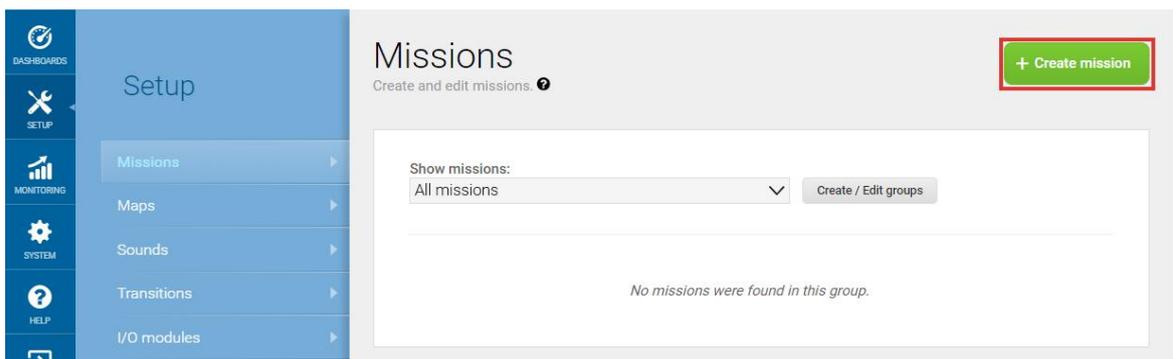
Prompt user actions are used for prompting the user with a question on how the robot should proceed. *Prompt user* is an example mission that uses a Prompt user action that lets you choose whether to send the robot to one position or another.

Before you create the mission *Prompt user*, it is assumed that you have completed the following:

- Created two robot positions named *No. position 1* and *No. position 2* as described in [Creating positions on page 200](#).
- Defined a user group named *Users*.

To create the mission, follow the steps below:

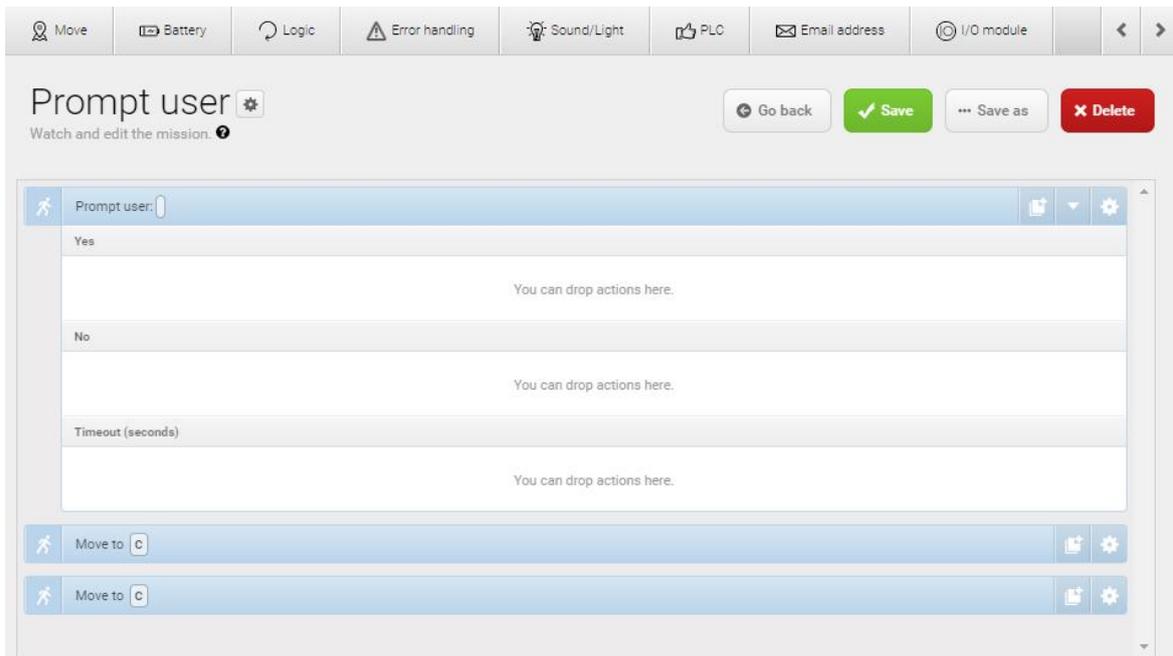
1. Go to **Setup > Missions**. Select **Create Mission**.



2. Name the mission *Prompt user*. Select the group and site you want it to belong to. Select **Create mission**.

3. Select the following actions:

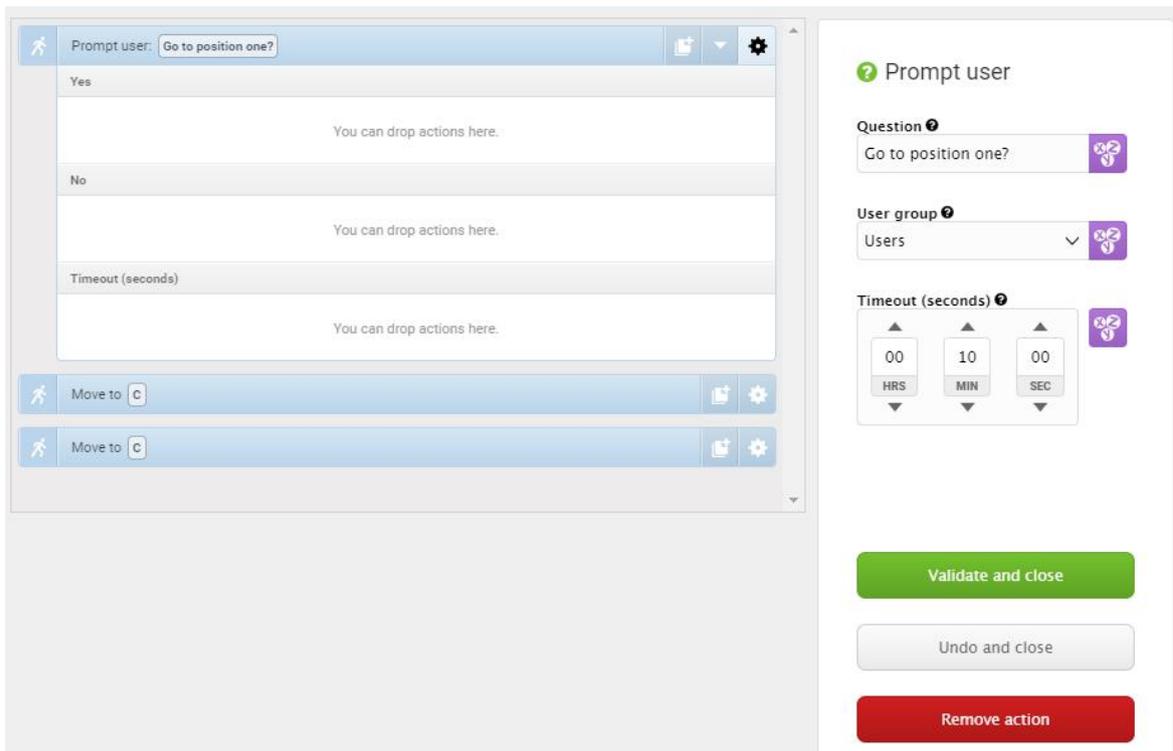
- In the Logic menu, select **Prompt user**.
- In the Move menu, select **Move**.
- In the Move menu, select **Move**.



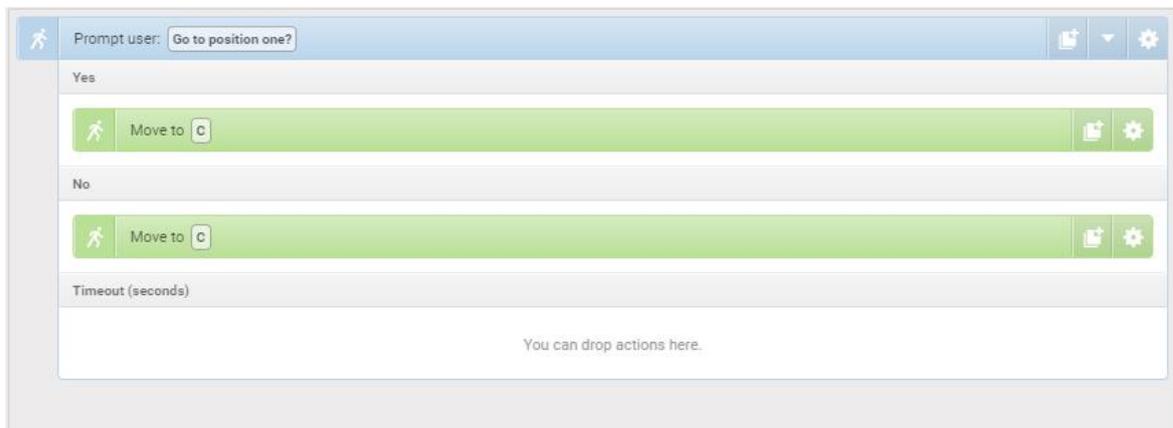
The following steps describe which parameters each action should be set to. To modify the parameters, select the gearwheel  at the right end of the action line to open the action dialog box. When you have set the parameters, select **Validate and close**.

4. In the Prompt user action, set the parameters as follows:

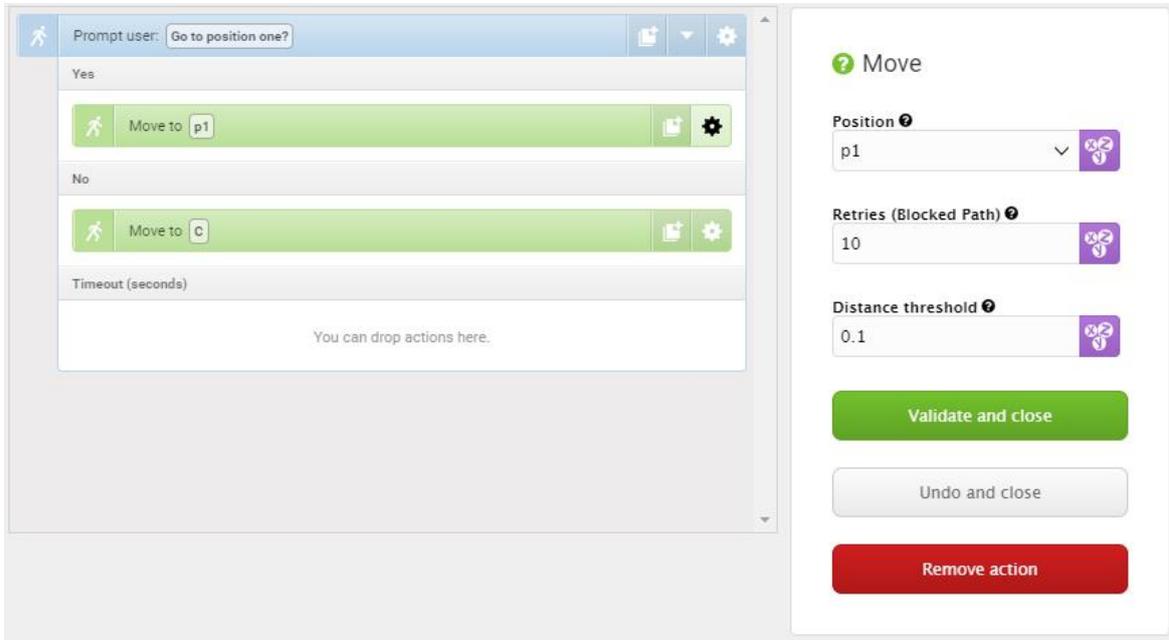
- **Question:** Enter the question **Go to position one?**
- **User group:** Select **Users**.
- **Timeout:** Set the timeout to 10 minutes.



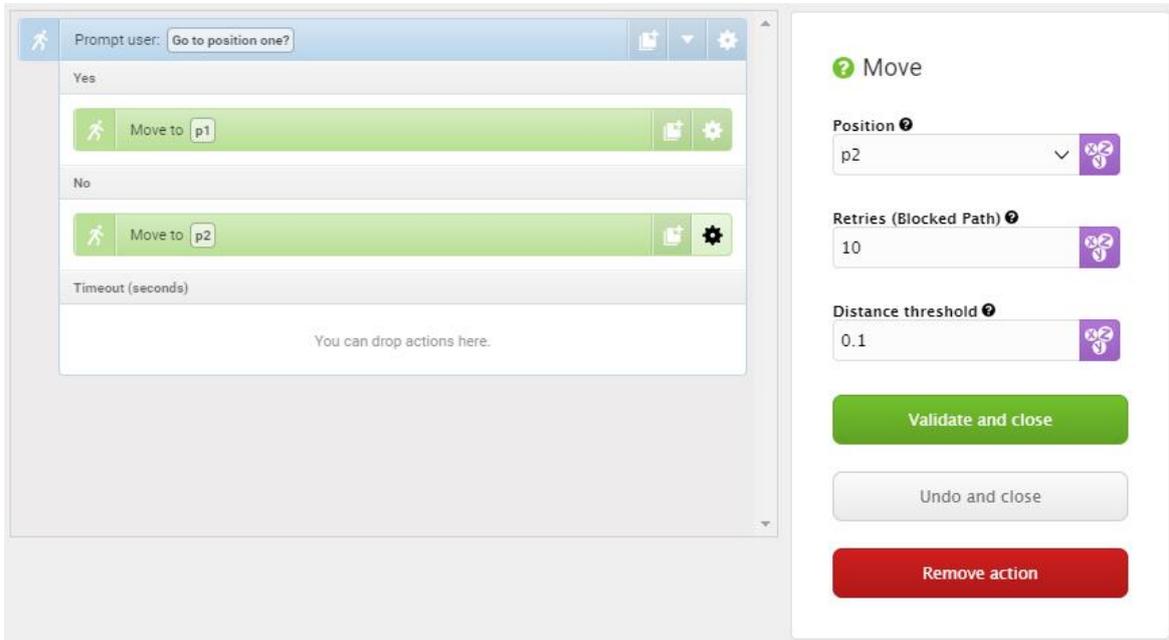
5. In the Prompt user action, drag a Move to action under the **Yes** box and a Move to action under the **No** box.



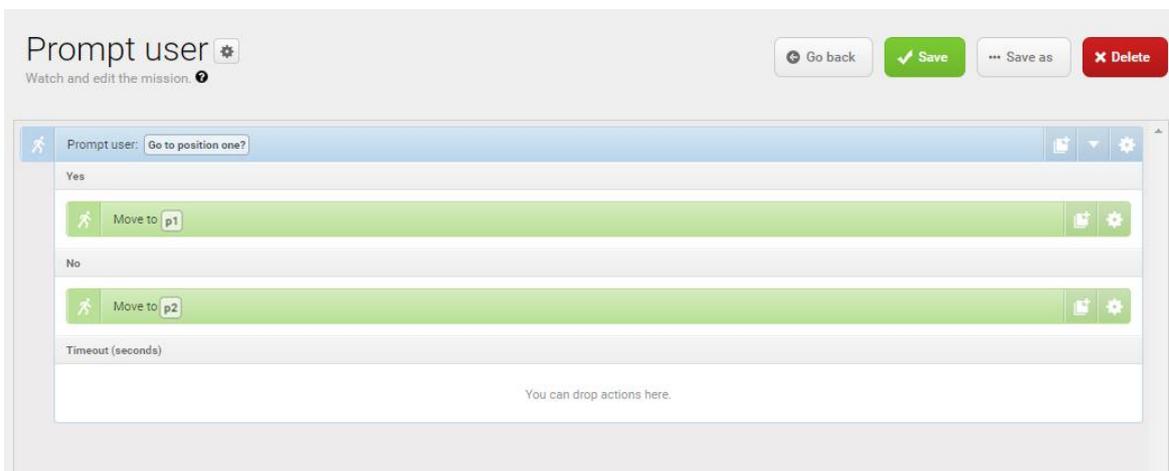
6. In the first Move to action, under **Position**, select **No. position 1**.



- In the second Move to action, under **Position**, select **p2**.



The mission should look like this:



- Select **Save** ✓ to save the mission.

12.4 Creating the mission *Try/Catch*

Try/Catch actions are used to handle mission errors. When you use a Try/Catch action, you can define what the robot should do if, at any point, it fails to execute its main mission. This prevents the robot from going into an error state and

stopping in the middle of a mission by providing an alternative course of action if the main mission fails.

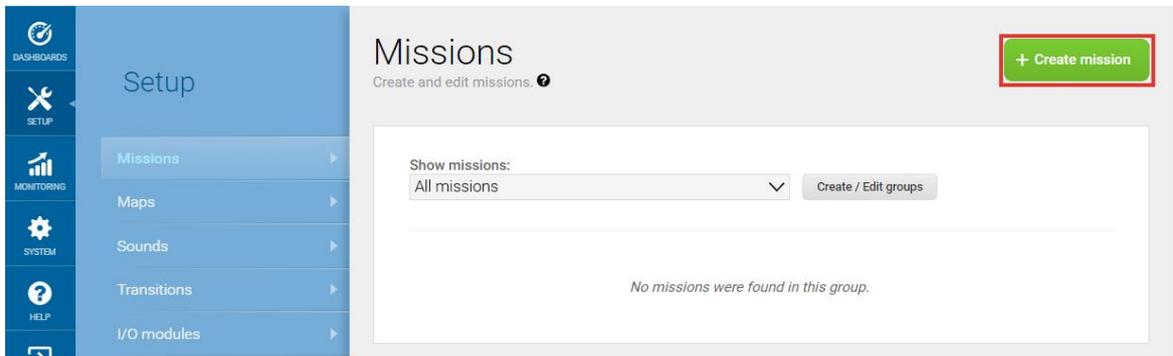
Try/Catch is a mission example where the robot runs the mission *Prompt user* created in [Creating the mission Prompt user on page 202](#), and if the robot for some reason fails to complete the mission, the robot plays a sound.

To create the mission *Try/Catch*, it is assumed you have completed the following:

- Created the mission *Prompt user* as described in [Creating the mission Prompt user on page 202](#).

To create the *Try/Catch* mission, follow the steps below:

1. Go to **Setup > Missions**. Select **Create Mission**.



2. Name the mission *Try/Catch*. Select the group and site you want it to belong to. Select **Create mission**.

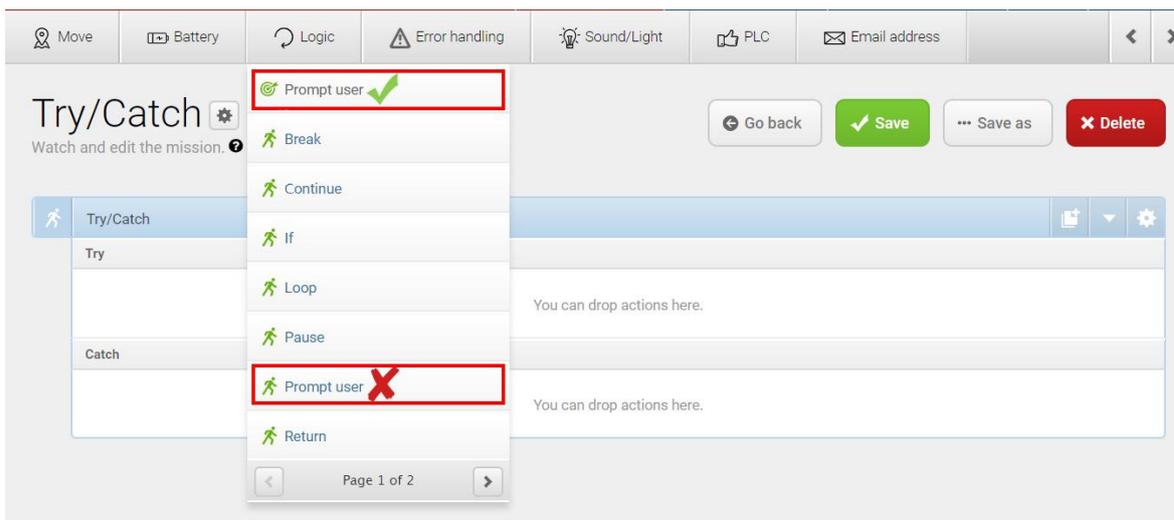
3. Select the following actions:

- In the Error handling menu, select **Try/Catch**.
- Select the Prompt user mission you have made.

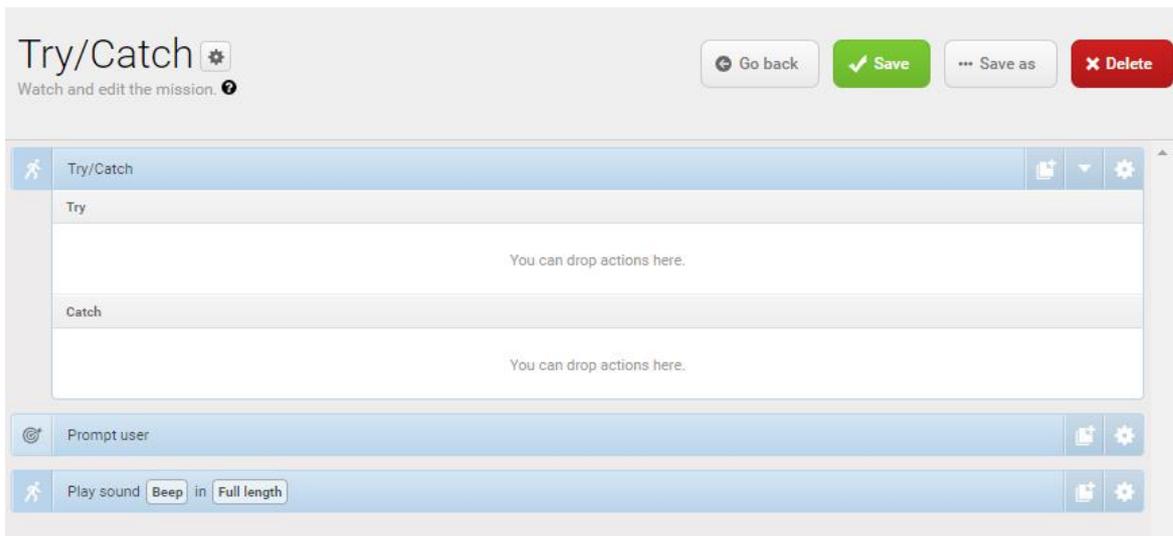
The mission menu you have saved the mission under will figure as a menu in the mission editor. The menus contain both missions and actions.



Missions have this icon  and actions have this icon . In this example, the mission is saved under the Logic menu that also includes the Prompt user action . Be sure to select the Prompt user mission .

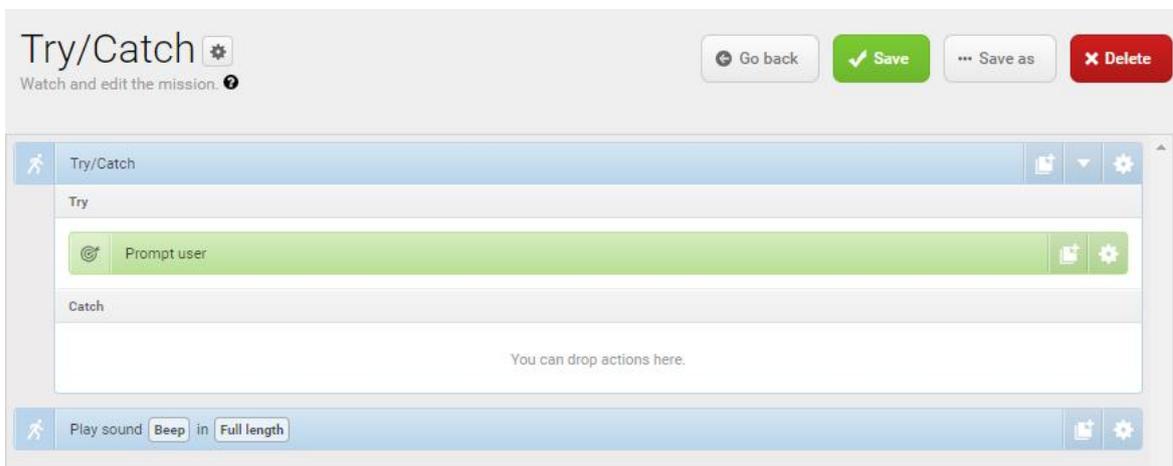


- In the Sound/Light menu, select **Play sound**.



The following steps describe which parameters each action should be set to. To modify the parameters, select the gearwheel  at the right end of the action line to open the action dialog box. When you have set the parameters, select **Validate and close**.

4. Drag the Prompt user mission into the **Try** box under **Try/Catch**.

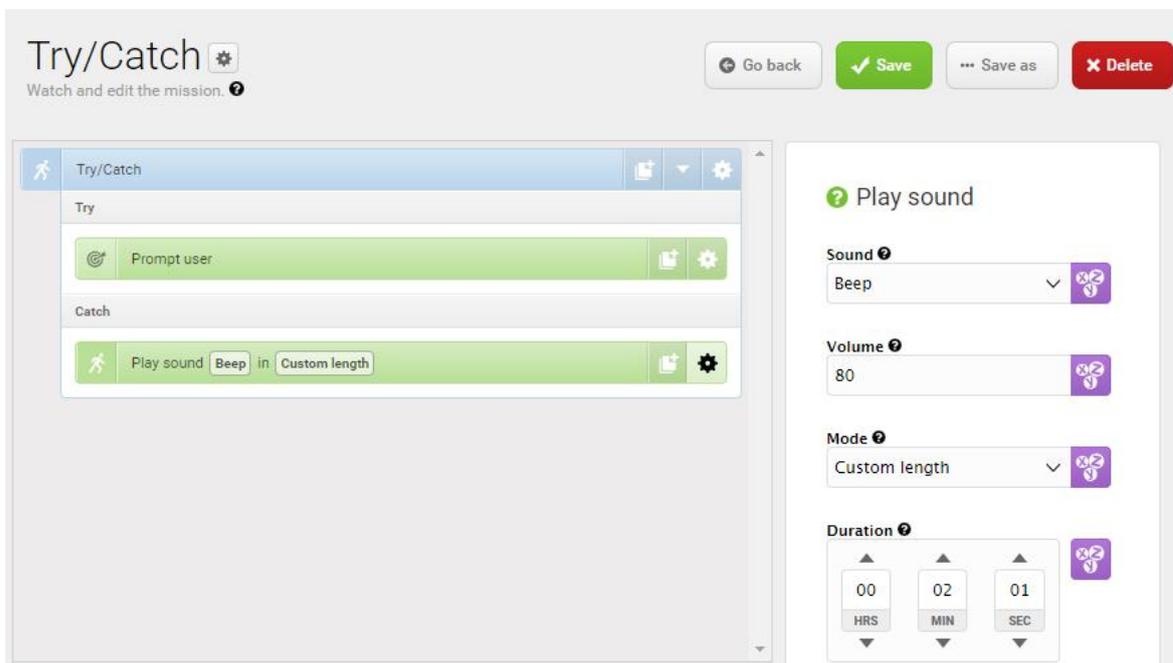


5. Drag the Play sound action under the **Catch** box under **Try/Catch**.



6. In the Play sound action, set the parameters as follows:

- **Sound:** Select **Beep**.
- **Volume:** Enter the value **80**. This is approximately 64 dB.
- **Mode:** Select **Custom length** so you can enter the duration of time the sound is played.
- **Duration:** Set the duration to two minutes.



The mission should look like this:



7. Select **Save** ✓ to save the mission.

12.5 Creating the mission *Variable docking*

All mission actions that require the user to specify the value of a parameter when they choose to use the mission have the option of defining a variable. If you use a variable in a mission, when you add the mission to the mission queue or nest it inside another mission, you must select a value for the parameter where the variable is used. This allows you to reuse the same mission for different but still similar tasks.

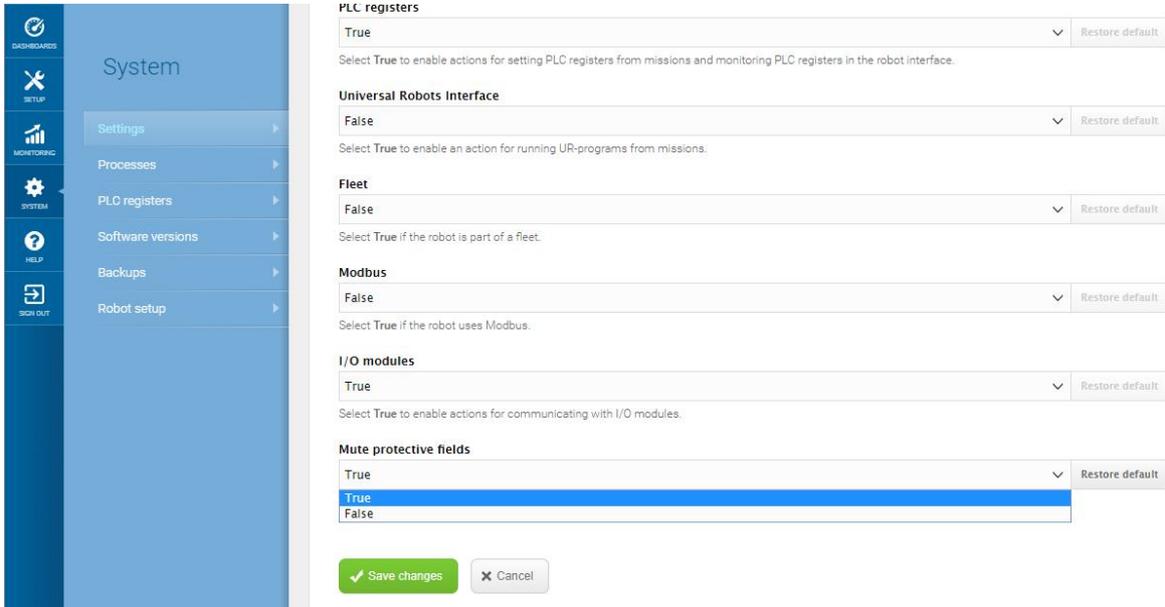
Variable docking is a mission example that enables you to select which marker the robot should dock to, which Protective fields it should mute when docking, and how long the robot should wait before undocking each time you use the mission.



When a robot docks to known markers except L-markers, the robot automatically mutes its Protective fields to prevent itself from triggering a Protective stop when it drives close to the marker. But, for L-markers, you must manually mute the Protective fields if you need the robot to drive close to an obstacle. This mission is especially useful for this.

To create the mission *Variable docking*, it is assumed you have completed the following:

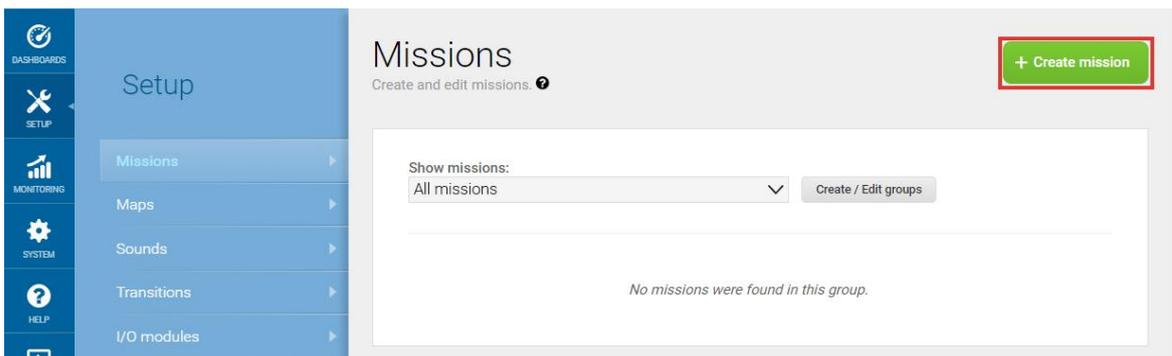
- Enabled the muting of the Protective fields. Go to **System > Settings > Features**, and set **Mute protective fields** to **True**.



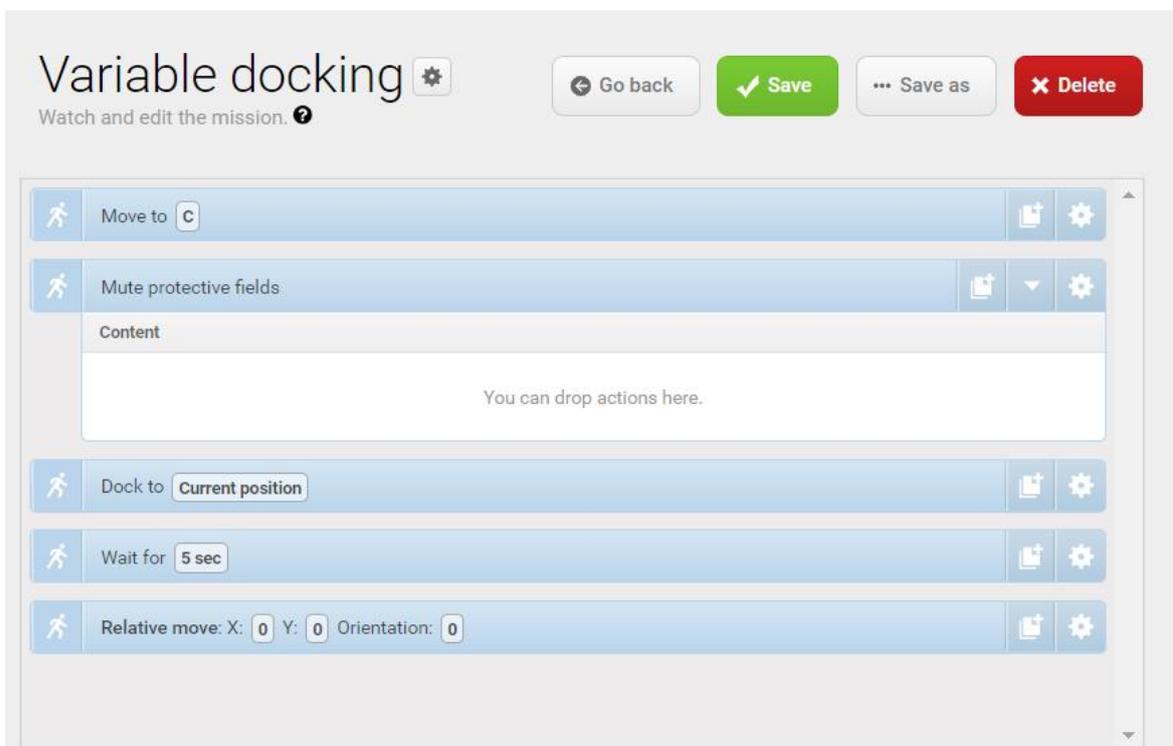
- Created several markers that the robot can dock to—see [Creating markers on page 193](#).

To create the mission, follow these steps:

1. Go to **Setup > Missions**. Select **Create Mission**.

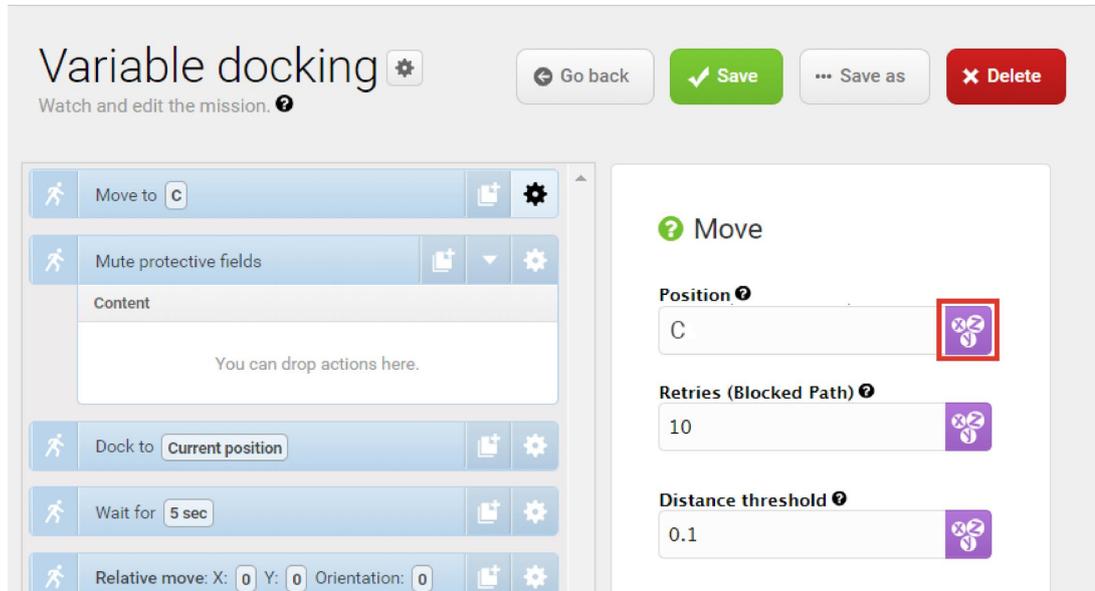


2. Name the mission *Variable docking*. Select the group and site you want it to belong to. Select **Create mission**.
3. Select the following actions:
 - In the Move menu, select **Move**.
 - In the Safety system menu, select **Mute protective fields**.
 - In the Move menu, select **Docking**.
 - In the Logic menu, select **Wait**.
 - In the Move menu, select **Relative move**.



The following steps describe which parameters each action should be set to. To modify the parameters, select the gearwheel  at the right end of the action line to open the action dialog box. When you have set the parameters, select **Validate and close**.

4. In the Move action, make the parameter **Position** a variable that can be set each time you use the mission. The following steps describe how to create a variable:
 - a. Under **Position**, select **Variables** .



- b. Select **Create variable** in the upper-right corner.
- c. Name the variable *Marker*. Select **OK**.

Create variable

In the **Name** field, enter a question that describes what the variable is used for, for example, "How far should the robot move?" In the **Default value** field, enter a default distance.

Variable name

Marker

Default value

A1

OK **Cancel**

- d. Under **Position type**, select **Entry**. This will make the robot move to the entry position of the marker.



If the parameter **Position type** does not show up at first, select **Validate and close**, and then open the action dialog box again.

The screenshot displays the 'Variable docking' mission editor. At the top, there are buttons for 'Go back', 'Save', 'Save as', and 'Delete'. Below the title, a subtitle reads 'Watch and edit the mission.' The main workspace is divided into two sections. On the left, a list of actions is shown, including 'Move to C', 'Mute protective fields', 'Dock to Current position', 'Wait for 5 sec', and 'Relative move: X: 0 Y: 0 Orientation: 0'. On the right, the configuration panel for the selected 'Move' action is visible. It includes a 'Position' dropdown set to 'MARKER', a 'Cart position' dropdown set to 'Main', two 'Position type' dropdowns both set to 'Entry', a 'Retries (Blocked Path)' input field set to '10', and a 'Distance threshold' input field set to '0.1'.

5. In the Mute protective fields action, set the parameters as follows:

- **Sound:** Select **Default**
- **Front:** Create a variable titled **Mute fields**.
- **Rear:** Create a variable titled **Mute fields**.
- **Sides:** Create a variable titled **Mute fields**.



MiR1350 cannot mute specific Protective fields; you must either mute all or none of the fields. Otherwise, the robot reports an error. If you use a variable with the same name in all parameters, you ensure that you apply the same parameter setting to all.

The screenshot shows the 'Variable docking' interface. At the top, there is a title 'Variable docking' with a gear icon, and buttons for 'Go back', 'Save', 'Save as', and 'Delete'. Below the title, it says 'Watch and edit the mission.' with a question mark icon. The main area is divided into two panels. The left panel shows a list of actions: 'Move to Marker', 'Mute protective fields', 'Dock to Marker', 'Wait for 5 sec', and 'Relative move: X: 0 Y: 0 Orientation: 0'. The 'Mute protective fields' action is selected, and its configuration panel is shown on the right. The configuration panel has a title 'Mute protective fields' and a gear icon. It contains the following settings: 'Sound' set to 'Default', 'Volume' set to 'Default', and three sections: 'Front', 'Rear', and 'Sides', each with a 'MUTE FIELDS' button.

- Drag the Docking action into the Mute protective fields action, and under **Marker position**, create another variable titled *Marker*.



If two variables share the same name, the value you select for that variable will be applied both places. In this case, by using the variable *Marker* in two places, you ensure that the robot docks to the same marker that it moved to in the first action.

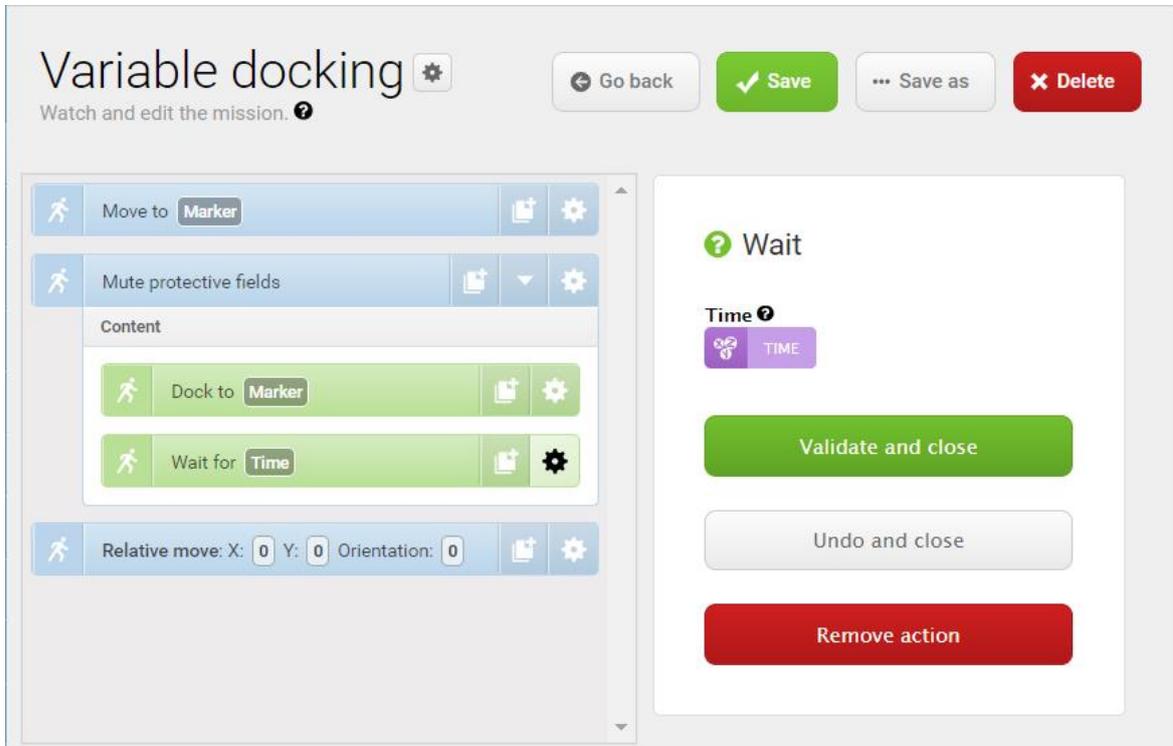
The screenshot shows the 'Variable docking' configuration screen. At the top, there are buttons for 'Go back', 'Save', 'Save as', and 'Delete'. Below this, the mission steps are listed in a scrollable area:

- Move to **Marker**
- Mute protective fields
 - Content: Dock to **Marker**
- Wait for **5 sec**
- Relative move: X: **0** Y: **0** Orientation: **0**

On the right, the 'Docking' configuration panel is visible, showing the following settings:

- Marker position**: MARKER
- Marker type**: Narrow asymmetric MiR500y1
- Retries (Blocked Path)**: 10
- Maximum linear speed**: 0.5

7. Drag the Wait action into the Mute protective fields action, and under **Time**, create another variable titled *Time*.



- Drag the Relative move action into the Mute protective fields action, and under **X**, enter **-2**. This will make the robot move two meters back to undock from the marker.

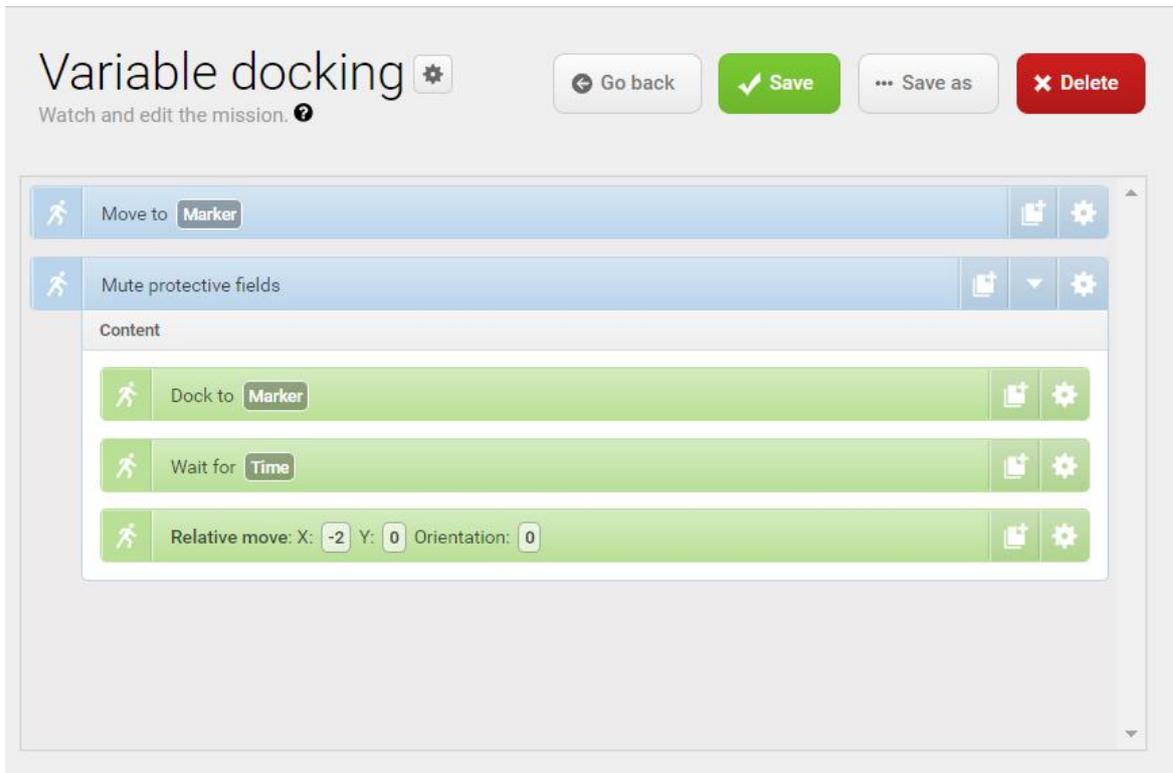
The screenshot displays the 'Variable docking' mission editor. At the top, there are navigation buttons: 'Go back', 'Save', 'Save as', and 'Delete'. The mission sequence is as follows:

- Move to **Marker**
- Mute protective fields
 - Content:
 - Dock to **Marker**
 - Wait for **Time**
 - Relative move: X: **-2** Y: **0** Orientation: **0**

The configuration panel for the 'Relative move' action is shown on the right with the following settings:

- X**: -2
- Y**: 0
- Orientation**: 0
- Maximum linear speed**: 0.5
- Maximum angular speed**: 0.5
- Collision detection

9. Select ✓ **Save** to save the mission.



12.6 Testing a mission

After you create a mission, always run the mission to test that the robot executes it correctly.



NOTICE

Always test missions without load to minimize potential hazards.

To run a mission, follow these steps:

1. Go to **Setup > Missions**.
2. Select **Queue mission** next to the mission you want to run. The mission is now added to the mission queue.

3. Select **Continue** ► to start the mission.
4. Watch the robot execute the mission, and verify that it performs as expected.



We recommend running the mission 5-10 times to ensure that it runs smoothly. If something interrupts the mission, use a Try/Catch action in that step of the mission and decide what the robot has to do if a mission action fails.

13. Applications

You can install top modules on top of MiR1350 for specific applications.

For more information about top modules from MiR, see [MiR Top Modules](#) on the MiR website.

For more information about top modules from third parties, see [MiRGo](#) on the MiR website.

Top modules from MiR are delivered with instructions on how to mount and operate them with MiR1350.

For instructions on how to mount third party top modules and accessories, contact your distributor.

13.1 Mounting a top module

MiR1350 has four M10 holes for mounting top modules as shown in **Figure 13.1**. The tightening torque is 47 Nm.

MiR1350 also has four M12 holes used for fixation of transportation eye bolts.



M12 lifting holes can also be used to mount top modules. If a top module is mounted using these holes, it is necessary to drill M12 lifting holes in the top application in order to lift the robot—see [Maintenance on page 226](#). Alternatively, the top module must be easily removed to access the M12 holes.

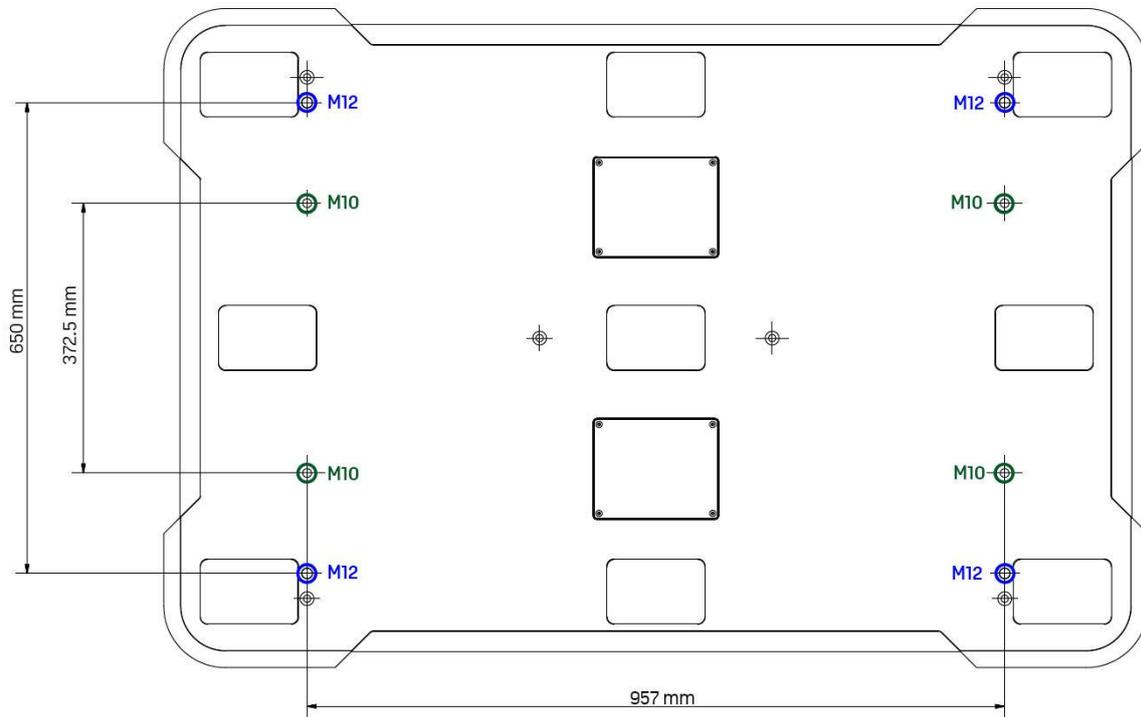


Figure 13.1. Mounting holes on the top of MiR1350.

Certain top modules may require the installation of an extra Emergency stop button. Perform a risk assessment according to standard ISO 12100—see [Risk assessment on page 141](#).



CAUTION

Certain top modules may lead to new hazards and increased risks that cannot be eliminated or reduced by the risk reduction measures applied by Mobile Industrial Robots.

- Perform a risk assessment according to standard ISO 12100 when mounting a top module—see [Risk assessment on page 141](#).



CAUTION

MiR1350 may tip over if weight and payload specifications are not met, risking damage to equipment or injury to nearby personnel.

- Stay within the specifications for weight and the total payload's center of gravity—see [Payload distribution on page 239](#).

14. Maintenance

The following maintenance schedules give an overview of regular cleaning and parts replacement procedures.

It is the responsibility of the operator to perform all maintenance tasks on the robot.



The stated intervals are meant as guidelines and depend on the operating environment and frequency of usage of the robot.



It is recommended to make a maintenance plan to make sure that all maintenance tasks are done and that the responsible(s) are aware of their tasks.



See the sections [External parts on page 16](#), [Internal parts on page 23](#), and [Accessing the internal parts on page 43](#) to see where the parts mentioned in the maintenance schedules are located and how to access them.



NOTICE

Always disconnect the battery before performing maintenance tasks to prevent unexpected start-up—see [Disconnecting the battery on page 80](#).

**NOTICE**

Only use approved spare parts. Contact your distributor for the list of spare parts and the appropriate how-to guides.

Mobile Industrial Robots disclaims any and all liability if unapproved spare parts are used. Mobile Industrial Robots cannot be held responsible for any damages caused to the robot, accessories, or any other equipment due to use of unapproved spare parts.

14.1 Regular weekly checks and maintenance tasks

Once a week, carry out the maintenance tasks in **Table 14.1**.

Table 14.1.
Regular weekly checks and maintenance tasks

Parts	Maintenance tasks
Robot top cover and maintenance hatches	<p>Clean the robot on the outside with a damp cloth.</p> <p>i Do not use compressed air to clean the robot.</p>

Laser scanners	<p>Clean the optics covers of the scanners for optimum performance. Use anti-static cleaning products, and avoid aggressive or abrasive cleaning agents.</p> <p>i Make sure to also clean the top part of the optics cover. The contamination sensors scan the entire optics cover glass piece.</p>
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In the robot interface under **Monitoring > Hardware health > Emergency stop**, see if **Front scanner cover** and **Back scanner cover** is **Clean**.

i NOTICE

Static charges cause dust particles to be attracted to the optics cover. You can diminish this effect by using the anti-static plastic cleaner (SICK part no. 5600006) and the SICK lens cloth (part no. 4003353). See the manufacturer's own documentation.

Parts	Maintenance tasks
Caster wheels (the four corner wheels)	Remove dirt with a damp cloth, and make sure nothing is entangled in the wheels.
Drive wheels (the two middle wheels)	Remove dirt with a damp cloth, and make sure nothing is entangled in the wheels. Wipe away an grease that may have leaked from the roller bearings.
Status lights	Check if the LED light band is intact. Ensure the light shows all the way around the robot. Clean with a soft cloth to ensure even lighting around the robot.
Signal lights	Check if the signal lights on the four corners blink and show light correctly.

14.2 Regular checks and replacements

Before starting replacement tasks that involve removal of the top cover or side hatches:

- Shut down the robot—see [Shutting down the robot on page 74](#).
- Disconnect the battery—see [Disconnecting the battery on page 80](#).

Table 14.2 contains the parts that you should check and how often you should do that.

Table 14.2. Regular checks and replacements		
Part	Maintenance	Interval
Robot top cover	Check mounting. Ensure it sits evenly on top of the robot with connections accessible.	Check monthly, and replace as needed.
Safety PLC	In the robot interface under Monitoring > Hardware health > Communication , see if the robot is running with the correct SICK configuration or if the warning The SICK Safety PLC is running a non-standard configuration is shown.	Check monthly and after commissioning or if you make any changes to the robot setup.
Robot hardware	In the robot interface under Monitoring > Hardware health , check if there are any warnings (marked with yellow).	Check monthly and after commissioning or if you make any changes to the robot setup.
Front, rear, and side compartment covers	Check mounting. Ensure the covers are even and are not in contact with the wheels.	Check monthly, and replace as needed. ❗ If you replace the cover with the robot's nameplate, make sure to mount a new copy of the nameplate to the replacement cover.

Part	Maintenance	Interval
Loudspeaker and signal lights	Check that all visual and auditory warnings function.	Check monthly, and adjust or replace as needed.
Caster wheels (the four corner wheels)	Check bearings and tighten, and check the wheels for wear and tear.	Check weekly, and replace if the diameter is less than 93 mm.
	Measure the diameter of the wheels to assess how worn down they are.	Replace all four caster wheels together.
Drive wheels (the two middle wheels)	Check wheel surfaces for wear.	Check every six months, and replace if the diameter is less than 185 mm.
	Measure the diameter of the wheels to assess how worn down they are.	Replace in pairs.

ⓘ NOTICE

The robot's IMU must be calibrated after replacement of the wheels—see *How to calibrate the IMU*.

Part	Maintenance	Interval
Drive wheels (the two middle wheels)	Lubricate the roller bearings. To lubricate the bearings, attach a grease pump to the grease fitting on one of the drive wheels, and apply 2 g of Rocol Foodlube Hi-Temp 2. Clean away any excess grease.	Lubricate the roller bearings yearly.
Safety laser scanners	Check for visual defects, for example cracks and scratches.	Replace as needed.
Control panel	Check that all buttons on the control panel function.	Every three to four months.
Emergency stop	Check that the Emergency stop buttons work, push down the red button, and check that the Emergency reset button lights up.	Every three to four months according to <i>EN/ISO 13850 Safety of machinery - Emergency stop function</i> .
ESD tail	Check the ESD tail, open the left-hand side maintenance hatch, and make sure that the tail has contact with the ground.	Check every six months and replace as needed.

Part	Maintenance	Interval
Charging pads/broom	<p>Disconnect the battery on the robot. Using your hands, ensure that each pad moves up and down freely.</p> <p>Clean the charging pads using sandpaper. Also clean the pads on the charging stations.</p> <p>Clean the broom and check that it is intact.</p>	Check monthly, and replace as needed. See the guide <i>How to clean the charging pads under MiR robots</i>
Heat sink	See the guide <i>How to clean the heat sink on MiR600 and MiR1350</i> for instructions.	<p>Check every two months or after the robot has driven 1000 km.</p> <p>Can be increased to three months or 1500 km if very little dust is accumulated in the heat sink.</p>
3D cameras	<p>Check for visual defects, for example cracks and scratches.</p> <p>To test the cameras, see the guide <i>How to test if the 3D cameras are working on MiR robots</i></p>	Check monthly, and calibrate or replace as needed— see the guide <i>How to calibrate a D435 3D camera</i> .
Proximity sensors	Check for dust or dirt, and clean with a swab.	Check weekly.

Part	Maintenance	Interval
Manual brake release switch	Check if the Manual brake release switch functions by releasing the brakes and pushing the robot gently forward. Remember to enable the brakes again when done.	Check monthly, and replace as needed.
Safety marking on the floor	Check if the safety markings around operating hazard zones are intact and visible.	Check every six months, and replace as needed.
Safety stickers and nameplate	Check if the safety stickers, identification label, and nameplate on the robot are still intact and visible.	Check every six months, and replace as needed.



CAUTION

If the robot has been impacted, it may be structurally damaged, causing a risk of malfunction and injury to personnel.

- If you suspect the robot has suffered any damage, you need to conduct a thorough inspection to ensure that the robot's strength and structure is not compromised.

14.3 Battery maintenance

The battery is generally maintenance-free but should be cleaned if it gets very dirty. Before cleaning, the battery must be removed from any power source. Only use a dry and soft cloth to clean the housing of the battery, and do not use abrasives or solvents.

For storage of the battery, see [Battery storage on page 82](#).

For disposal of the battery, see [Battery disposal on page 83](#).

14.4 Lifting MiR1350

It may be necessary to lift the robot while servicing it. To lift the robot, use the four M12 mounting holes in the corners of the top cover of the robot—see **Figure 14.1**.

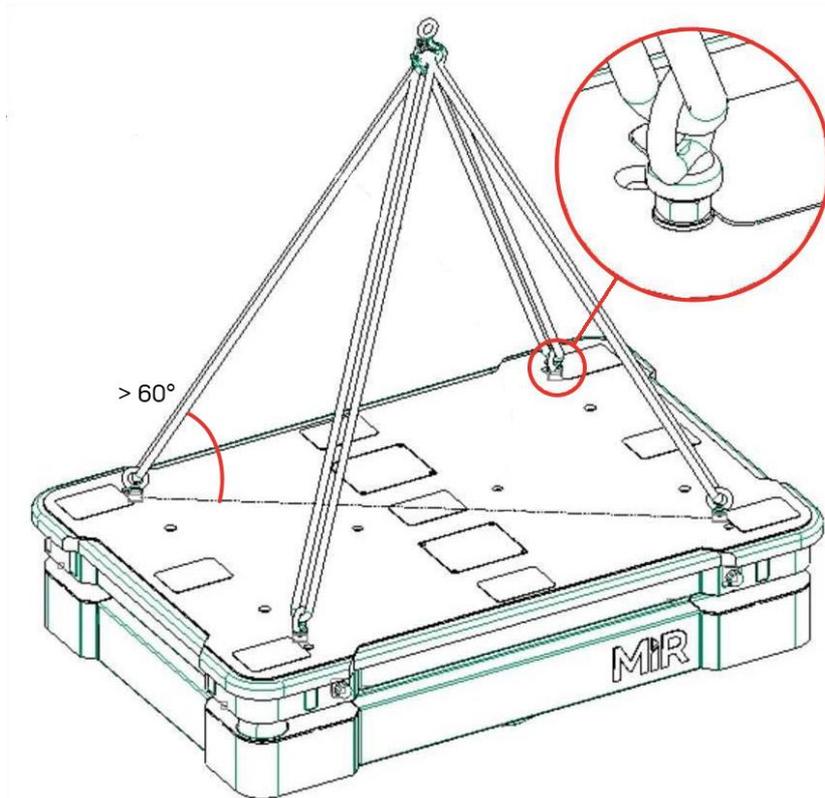


Figure 14.1. Illustration of how to lift MiR1350.

To lift the robot safely without damaging it, ensure that the following criteria are met:

- Use four M12 eye-bolts with counternuts and washers in each corner of the robot.
- Make sure the thread engagement is greater than 12 mm.
- Tighten the counternuts to at least 25 Nm.
- All slings must be of equal length and have a lift rating of at least 1 000 kg.

- The angle between the top cover and sling must be greater than 60°—see **Figure 14.1**.
- The bolts must be parallel with the diagonal between opposite corners.

15. Packing for transportation

This section describes how to pack the robot for transportation.

15.1 Original packaging

Use the original packaging materials when transporting the robot.



Figure 15.1. The packing materials.

The packaging materials are:

- The bottom of the box (the pallet)
- The lid of the box (the ramp)
- The walls of the box
- The wheel stop board
- Protective foam blocks: Side blocks and the top layer
- Protective corner braces. The braces prevent the robot from being damaged by the transport straps

15.2 Packing the robot for transportation

Before packing the robot for transportation:

- Shut down the robot—see [Shutting down the robot on page 74](#).
- Disconnect the battery—see [Disconnecting the battery on page 80](#).

To pack the robot, repeat the steps in [Unpacking MiR1350 on page 53](#) in the reverse order.



NOTICE

Pack and transport the robot in an upright position. Packing and transporting the robot in any other position voids the warranty.

15.3 Battery

The lithium-ion battery is subject to transport regulations. Make sure that you follow the safety precautions in this section and the instructions in [Packing for transportation on the previous page](#). Different regulations apply depending on the mode of transportation: land, sea, or air.

Contact your distributor for more information.



CAUTION

Lithium-ion batteries are subject to special transportation regulations according to United Nations Regulation of Dangerous Goods, UN 3171. Special transport documentation is required to comply with these regulations. This may influence both transport time and costs.

16. Payload distribution

The following drawings illustrate where the center of mass (CoM) of payloads must be located for safe operation with different payloads.



WARNING

Load falling or robot overturning if the load on MiR1350 is not positioned or fastened correctly can cause damage to equipment and injury to personnel.

- Ensure that the load is positioned according to the specifications and is fastened correctly.



CAUTION

Bumps and holes can cause loads to fall off of the robot, causing damage to equipment and injury to personnel.

- The floor the robot drives on must be even without bumps and holes for the payload specifications to be valid. If bumps and holes are present, the commissioner must take additional measures to ensure a safe operation.



CAUTION

A slippery surface can cause instability when driving with payloads, causing damage to equipment and injury to personnel.

- The friction coefficient between the floor and the drive wheels on the robot must be in the range of 0.60 to 0.80 for the payload specifications to be valid. If the friction coefficient is not in this range, the commissioner must take additional measures to ensure a safe operation.

The specifications apply to total payloads of up to 1350 kg.

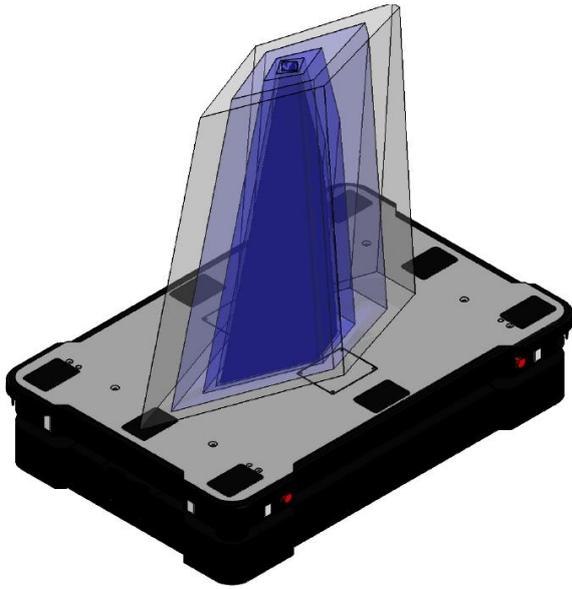


Figure 16.1. Overview of the permitted center of mass (CoM) of payloads.

16.1 Side view

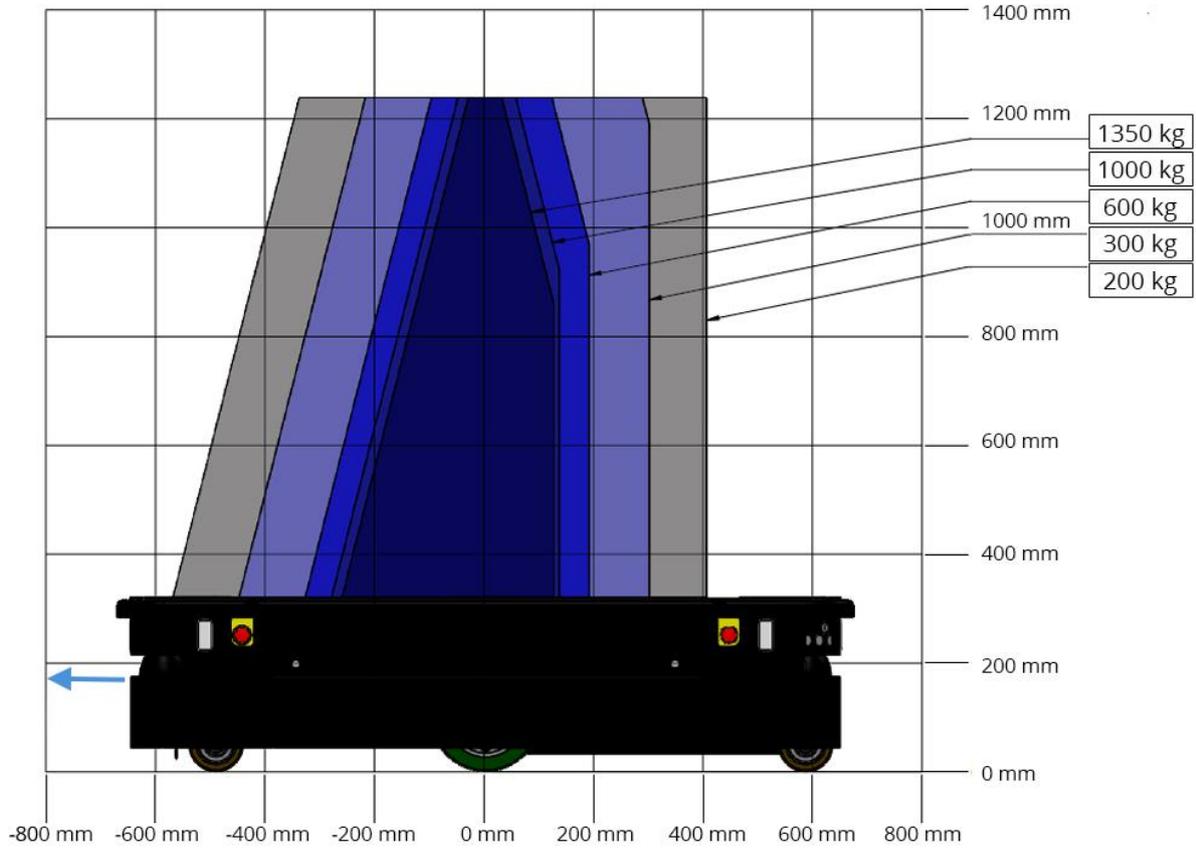


Figure 16.2. The center of mass (CoM) of payloads seen from the side at maximum speed.

16.2 Front view

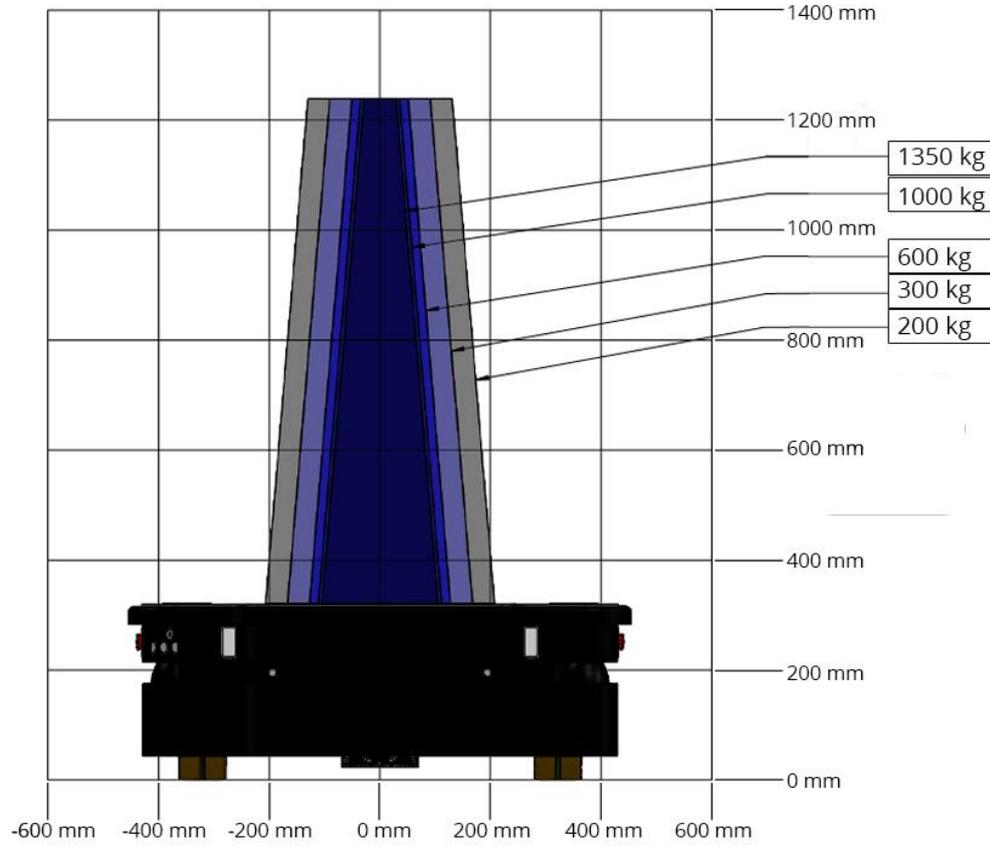


Figure 16.3. The center of mass (CoM) of payloads seen from the front at maximum speed.

17. Interface specifications

This section describes the specifications of the top application interfaces.



NOTICE

Read [Safety on page 32](#) before using the electrical interface.

MiR1350 has six electrical interfaces divided into two groups:

- Left top compartment
 - Power
 - Ethernet
 - GPIO
- Right top compartment
 - Auxiliary safety functions
 - Auxiliary emergency stop
 - Antenna

To see the locations of the electrical interfaces on the robot, see [Internal parts on page 23](#).

17.1 Left compartment interfaces

This section describes the general purpose interfaces located in the left top compartment of MiR1350.

Power

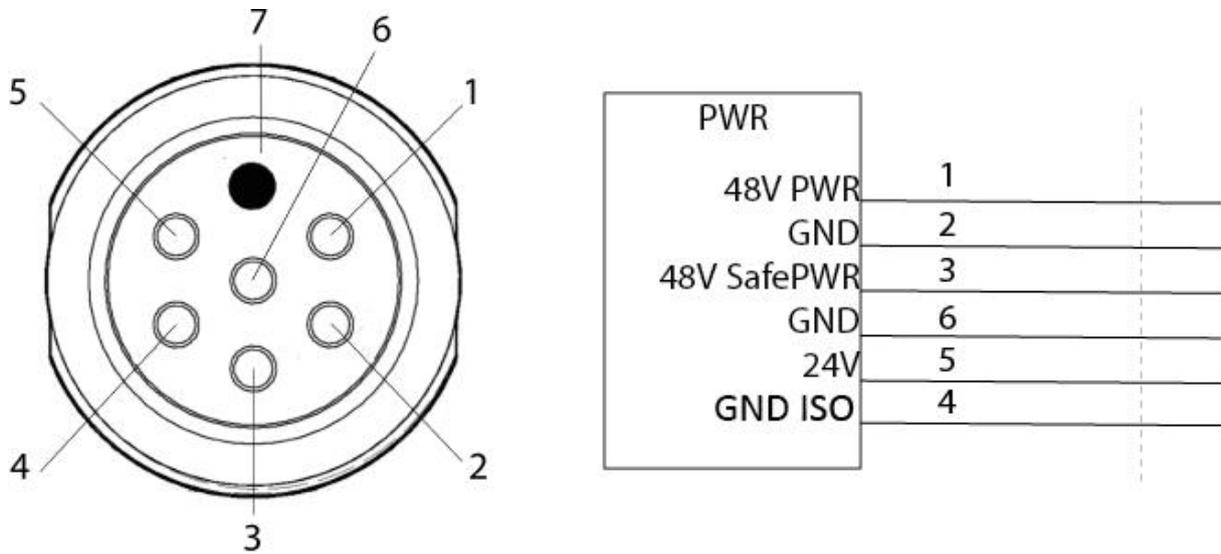


Figure 17.1. Pin numbers: female connector viewed from the front (left) and wiring diagram (right).

Table 17.1 contains the description of the pins of the Power interface.



The maximum current across pins 1 and 3 combined is 20 A when the robot is at standstill. When the robot is driving, the maximum combined current is 2 A.



The maximum capacitance of devices connected to pins 1 and 3 is 2 000 μF combined. If your device has a higher capacitance, you must integrate your own softstarter that keeps the current under 2 A for the first 100 ms, and thereafter under 20 A with a maximum peak current of 100 A.



CAUTION

Connecting power and ground signals to the chassis while stacking the 24 V and 48 V power supplies can lead to severe damage to the robot.

- Never connect power and ground signals to the chassis, and never stack the 24 V and 48 V power supplies.



CAUTION

Connecting 48 V power supplies to 24 V pins or vice versa can lead to severe damage to the robot.

- Never connect 48 V power supplies to 24 V pins or vice versa.



CAUTION

The robots are not designed to absorb inverse current from top modules. This can damage the electrical components inside the robot, and the top module will likely not work as intended.

- Never connect a top module that can deliver an inverse current to the robot interfaces.

Table 17.1.
Description of the pins in the Power interface

Pin no.	Description
1	<p>Signal name: 48V PWR</p> <p>Max. current: 20 A</p> <p>Voltage range: 41.8 - 53.8 V.</p> <p>Standard function: Turns off during Protective and Emergency stops by default, but can be changed to continuously supply power when the robot is on. This can be done in the robot interface under System > Settings > Features > Turn off TOP FUSE—see Turn off TOP FUSE feature on the next page. The power supply is cut via a transistor in the power board. There are no additional safety precautions taken with this power output. For this reason, it is recommended to use the power output from pin 3 instead.</p> <p>Intended use: Intended for high power loads like motors or actuators.</p>
2	<p>Signal name: GND</p> <p>Standard function: Ground. Intended to be connected to pin 1.</p>

Pin no.	Description
3	<p>Signal name: 48V SafePWR</p> <p>Max. current: 20 A</p> <p>Voltage range: 41.8 - 53.8 V.</p> <p>Standard function: Turns off in case of a Protective or Emergency stop. This output is controlled by the internal safety PLC and the STO contactor, to ensure that power is always disconnected from this pin in case of a protective or emergency stop. For this reason, it is always recommended to use this power output instead of the output from pin 1.</p> <p>Intended use: Intended for high power loads like motors or actuators.</p>
4	<p>Signal name: GND</p> <p>Standard function: Ground. Intended to be connected to pin 3.</p>
5	<p>Signal name: 24V</p> <p>Max. current: 2 A</p> <p>Standard function: Always on when robot is on. Intended for low power use, like powering an external PLC.</p>
6	<p>Signal name: GND_ISO</p> <p>Standard function: Ground. Intended to be connected to pin 5.</p>
7	<p>Unassigned</p>

Turn off TOP FUSE feature

You can use the **Turn off TOP FUSE** feature to disable the TOP FUSE to the Power top interface during a Protective or Emergency stop. This is the fuse that cuts power to the TOP 48V pin and the TOP-Safe 48V.

By default, the feature is set to **True** meaning that:

- Neither the TOP 48V pin nor the TOP-Safe 48V pin can draw power during an Emergency or Protective stop.
- The power from both pins are softstarted by gradually raising the voltage from 0 to 48 V in 100 ms. During this period, the current should be less than 2 A.

If you set the feature to **False**, the TOP FUSE does not turn off when the robot enters Protective or Emergency stop. This means that:

- The TOP 48V pin can still draw power from the robot during an Emergency or Protective stop.
- The TOP-Safe 48V pin cannot draw power until the robot exits the stopped state, but the inrush current is not reduced by the softstarter. If the inrush current is too high, the fuse will trip and start again with the inbuilt softstarter.

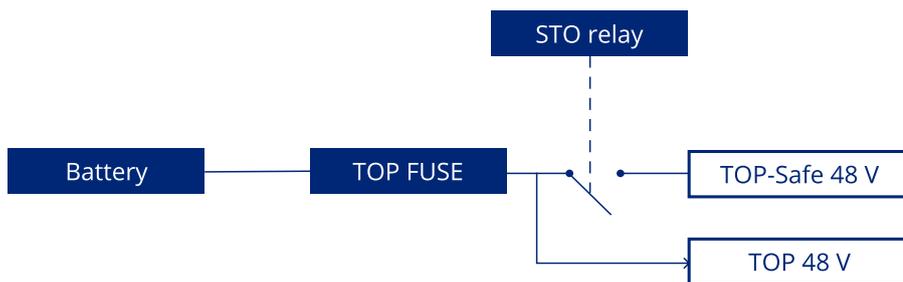


Figure 17.2. Diagram of how the TOP FUSE and STO contactors control the power connection to the Power top interface.

If you disable the feature and connect a load that has a capacity above 100 μ F or draws large currents in the first 100 ms to the TOP-Safe 48 V pin, and you don't integrate your own softstarter to the device, the TOP FUSE will trip when the robot exits Emergency or Protective stop. The fuse will reconnect again shortly after using the inbuilt softstarter.



NOTICE

There is a risk that the fuse will break when it is tripped. For this reason, we recommend that you ensure your top module does not trip the fuse as described above, even though in most cases it will reconnect.

GPIO

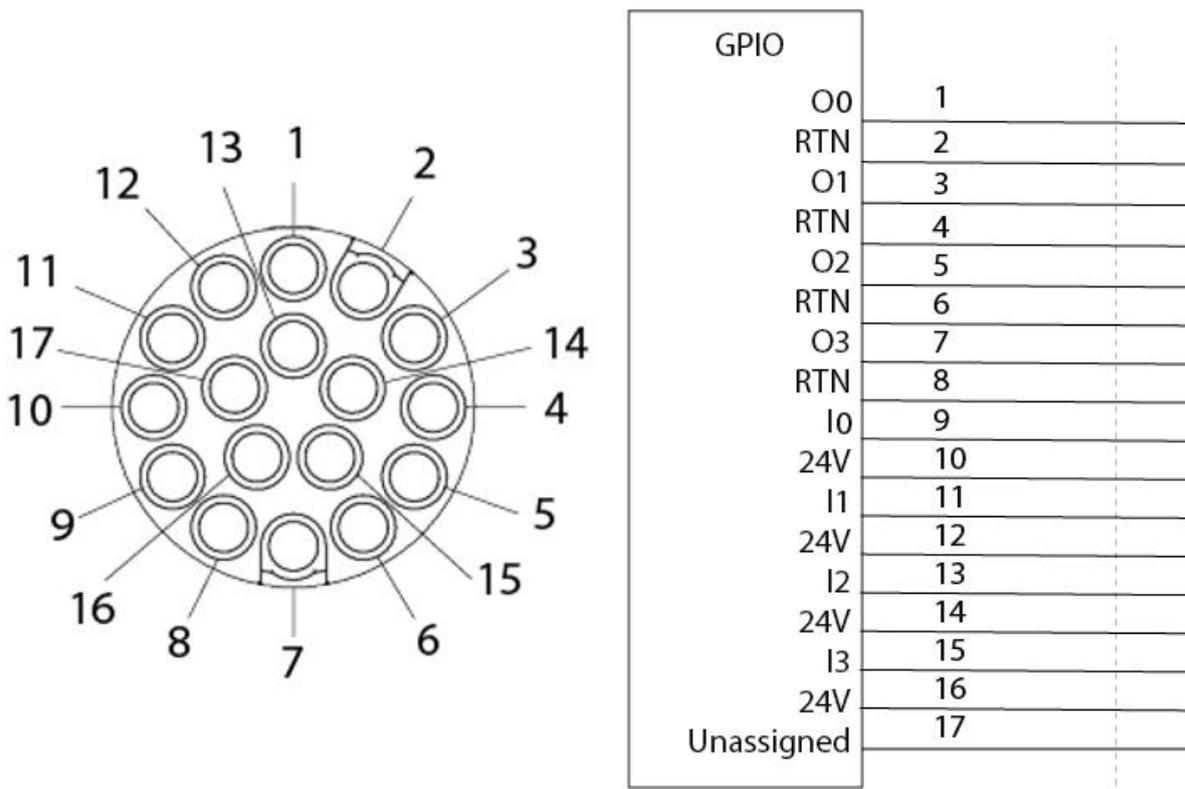


Figure 17.3. Pin numbers: male connector viewed from the front (left) and wiring diagram (right).

The GPIO has the following pins:

- Four inputs, for use with 24 V, but robust against 48 V.
- Four outputs, for use with 24 V.

The GPIO supports low current/power devices like relays, contactors, lamps, and separate PLC units.

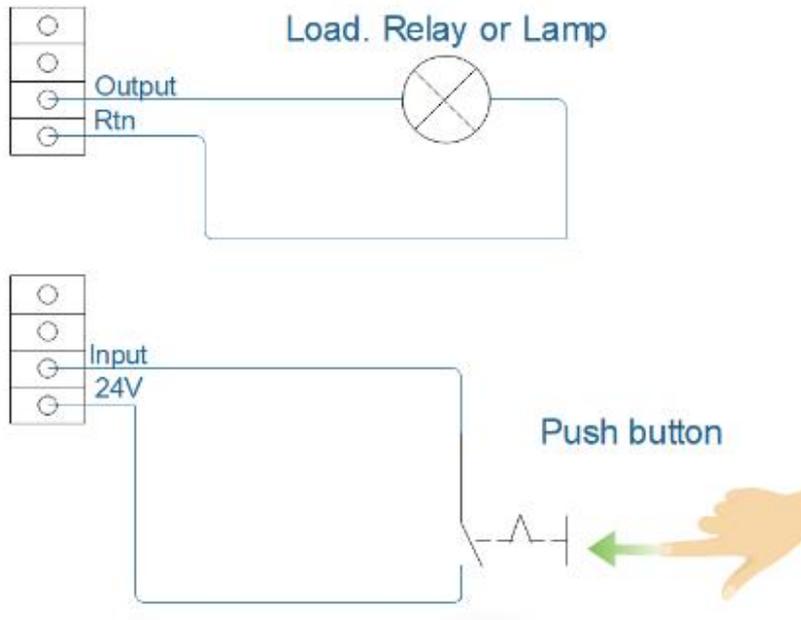


Figure 17.4. Outputs and RTNs are used to send signals to the top module, and inputs and 24 V pins are used to receive signals from the top module.



To use the GPIO for a top module of your own design, ensure that the **Pallet lift** and **Shelf** features are disabled under **System > Settings > Features**. This enables the GPIO interface to work as input and output to top modules that can be controlled in missions. The pallet lift and shelf features use a different kind of communication that is specific to the MiR top modules.

Outputs (O0, O1, O2, O3) can be toggled on and off by the robot in a Set I/O module mission action or manually in **Setup > I/O modules**.

A top module can be connected to the output pins and monitor when they are active at 24 V. RTN is used as ground.

Inputs (I0, I1, I2, I3) can be used by the top application to send inputs to the robot. When 24 V is connected to the input pin, the robot registers the input as active.

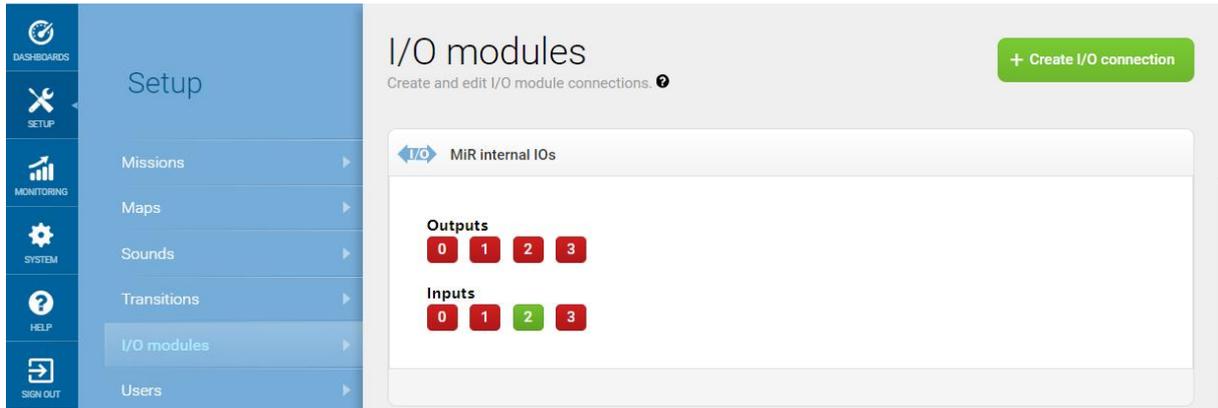


Figure 17.5. Example of I2 registered as high by the robot.

Output pins must be connected to RTN pins, and input pins must be connected to 24 V pins.

Table 17.2 contains the description of the pins of the GPIO interface.

Table 17.2. Description of the pins in the GPIO interface	
Pin no.	Description
1	<p>Name: O0</p> <p>Maximum current: 1 A at 24 V</p> <p>Standard function: Output 0</p>
2	<p>Name: RTN</p> <p>Standard function: Protected return</p>

Pin no.	Description
3	Name: O1 Maximum current: 1 A at 24 V Standard function: Output 1
4	Name: RTN Standard function: Protected return
5	Name: O2 Maximum current: 1 A at 24 V Standard function: Output 2
6	Name: RTN Standard function: Protected return
7	Name: O3 Maximum current: 1 A at 24 V Standard function: Output 3
8	Name: RTN Standard function: Protected return
9	Name: I0 Maximum current: 1 A at 24 V Standard function: PNP input 0
10	Name: 24V Maximum current: 1 A at 24 V Standard function: Protected output

Pin no.	Description
11	Name: I1 Maximum current: 1 A at 24 V Standard function: PNP input 1
12	Name: 24V Maximum current: 1 A at 24 V Standard function: Protected output
13	Name: I2 Maximum current: 1 A at 24 V Standard function: PNP input 2
14	Name: 24V Maximum current: 1 A at 24 V Standard function: Protected output
15	Name: I3 Maximum current: 1 A at 24 V Standard function: PNP input 3
16	Name: 24V Maximum current: 1 A at 24 V Standard function: Protected output
17	Unassigned

Ethernet

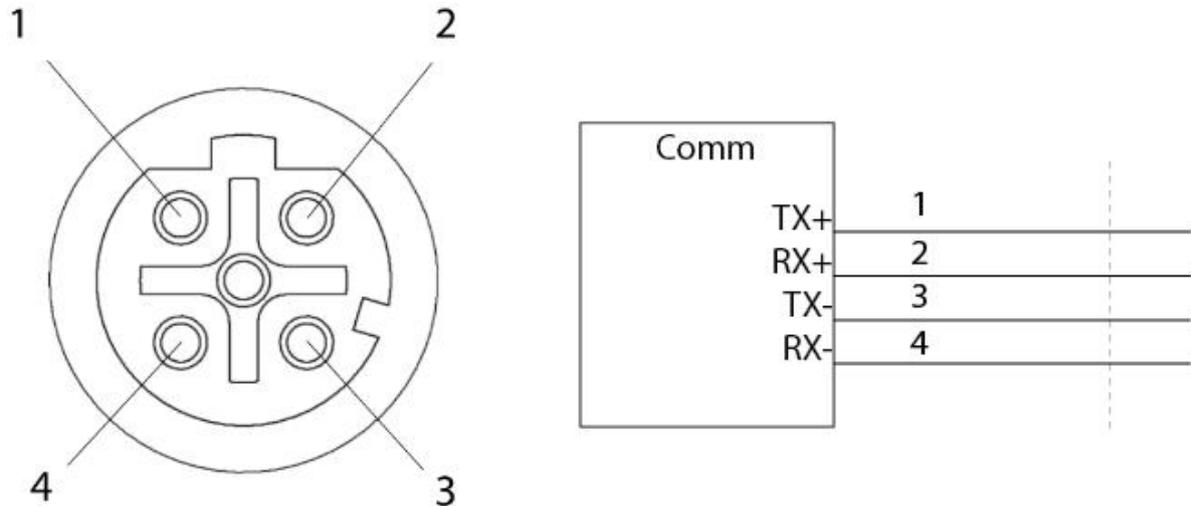


Figure 17.6. Ethernet connection. Pin numbers (left) and wiring diagram (right).

The communication interface is 10/100 Mbit Ethernet using a M12 connector—see [Connector list on page 263](#).

The Ethernet connection supports power over Ethernet.

Various protocols are supported, such as Modbus. For more information on how to use Modbus, ask your distributor for the guide *How to use Modbus with MiR robots*.

Table 17.3 contains the description of the pins of the Ethernet interface.

Table 17.3. Description of the pins in the Ethernet interface	
Pin no.	Signal name
1	TX+
2	RX+
3	TX-
4	RX-

17.2 Right compartment interfaces

This section describes the safety interfaces and antenna interface located in the right side top compartment of MiR1350.

Auxiliary emergency stop

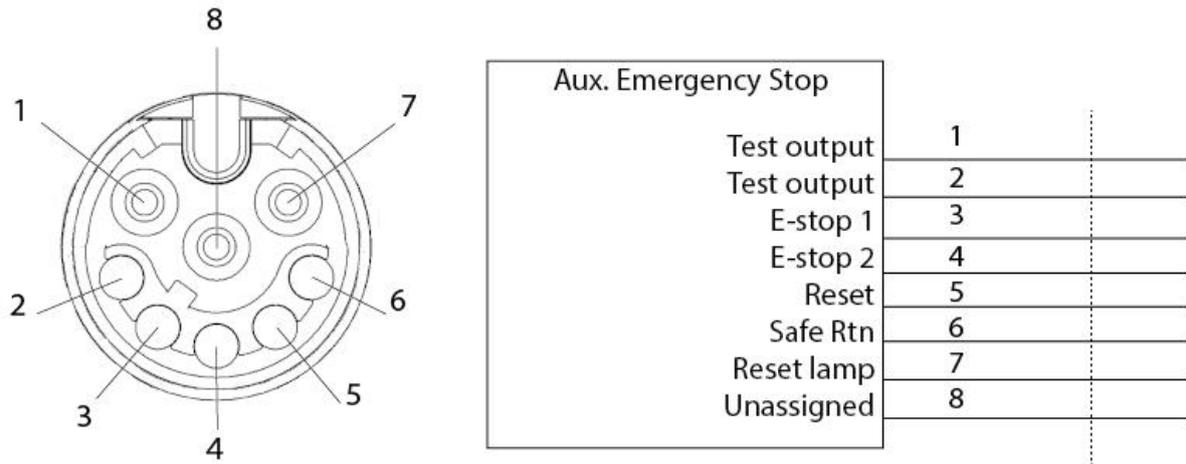


Figure 17.7. Pin numbers: female connector viewed from the front (left) and wiring diagram (right).

The Auxiliary emergency stop interface is designed to support Emergency stop and other safety functions—see [Emergency stop circuit on page 121](#).

Table 17.4 contains the description of the pins of the Auxiliary emergency stop interface.

Table 17.4. Description of the pins in the Auxiliary emergency stop interface	
Pin no.	Description
1	<p>Signal name: Test output</p> <p>Type: Output</p> <p>Standard function: 24 V output signal from the safety PLC for the Emergency stop circuit. Should connect to pin 3.</p>
2	<p>Signal name: Test output</p> <p>Type: Output</p> <p>Standard function: 24 V output signal from the safety PLC for the Emergency stop circuit. Should connect to pin 4.</p>
3	<p>Signal name: E-stop 1</p> <p>Type: Input</p> <p>Standard function: Input signal to the safety PLC for the Emergency stop circuit. Must receive 24 V to prevent the robot from entering Emergency stop. Should connect to pin 1.</p>
4	<p>Signal name: E-stop 2</p> <p>Type: Input</p> <p>Standard function: Input signal to the safety PLC for the Emergency stop circuit. Must receive 24 V to prevent the robot from entering Emergency stop. Should connect to pin 2.</p>

Pin no.	Description
5	<p>Signal name: Reset</p> <p>Type: Input</p> <p>Standard function: When active, the robot resets.</p>
6	<p>Signal name: Safe RTN</p> <p>Type: Ground</p> <p>Standard function: Safe return.</p>
7	<p>Signal name: Reset lamp</p> <p>Type: Output</p> <p>Standard function: Active when robot needs to be reset.</p>
8	<p>Unassigned.</p>

Auxiliary safety functions

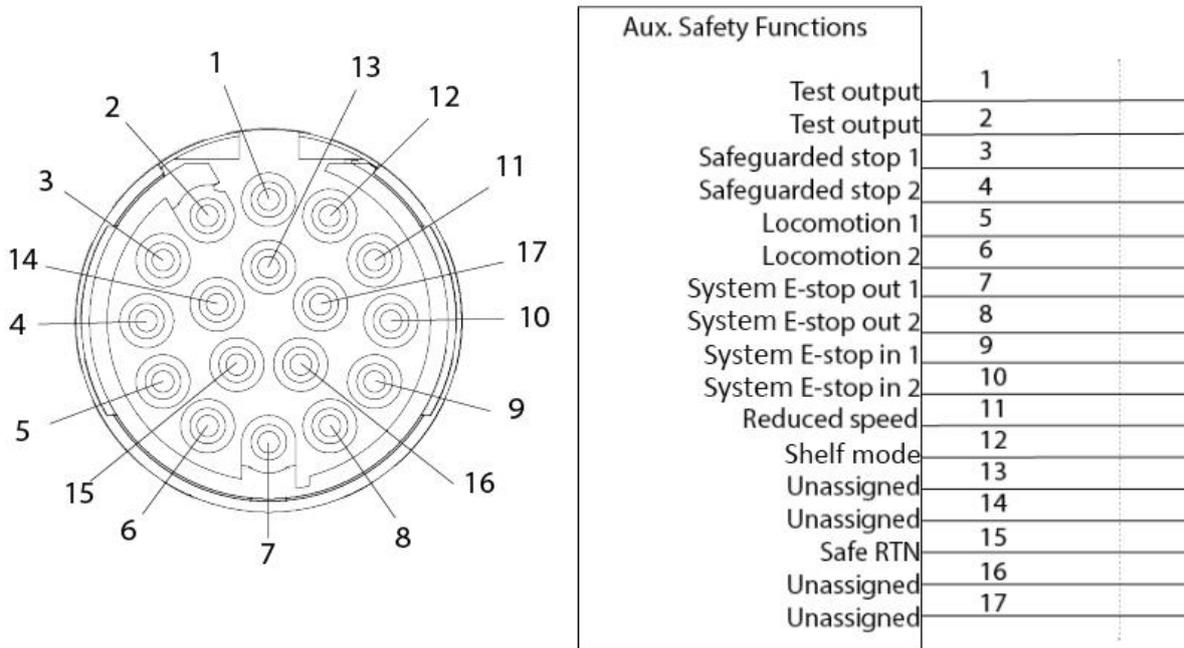


Figure 17.8. Pin numbers: female connector viewed from the front (left) and wiring diagram (right).

The Auxiliary safety functions interface is designed to support safety functions that can trigger a Protective stop—see [Safety-related functions and interfaces on page 104](#).

Table 17.5 contains the description of the pins of the Auxiliary safety functions interface.

Table 17.5. Description of the pins in the Auxiliary safety functions interface	
Pin no.	Description
1	<p>Signal name: Test output</p> <p>Type: Output</p> <p>Standard function: 24 V output.</p>

Pin no.	Description
2	<p>Signal name: Test output</p> <p>Type: Output</p> <p>Standard function: 24 V output.</p>
3	<p>Signal name: Safeguarded stop 1</p> <p>Type: Input</p> <p>Standard function: When inactive, the robot enters Protective stop. If pins 3 and 4 are unequally set for more than three seconds, the robot must be restarted.</p>
4	<p>Signal name: Safeguarded stop 2</p> <p>Type: Input</p> <p>Standard function: When inactive, the robot enters Protective stop. If pins 3 and 4 are unequally set for more than three seconds, the robot must be restarted.</p>
5	<p>Signal name: Locomotion 1</p> <p>Type: Output</p> <p>Standard function: Active when the robot is standing still.</p>
6	<p>Signal name: Locomotion 2</p> <p>Type: Output</p> <p>Standard function: Active when the robot is standing still.</p>
7	<p>Signal name: System E-stop out 1</p> <p>Type: Output</p> <p>Standard function: Inactive when the robot is in Emergency stop.</p>

Pin no.	Description
8	<p>Signal name: System E-stop out 2</p> <p>Type: Output</p> <p>Standard function: Inactive when the robot is in Emergency stop.</p>
9	<p>Signal name: System E-stop in 1</p> <p>Type: Input</p> <p>Standard function: When inactive, the robot enters Emergency stop.</p>
10	<p>Signal name: System E-stop in 2</p> <p>Type: Input</p> <p>Standard function: When inactive, the robot enters Emergency stop.</p>
11	<p>Signal name: Reduced speed</p> <p>Type: Input</p> <p>Standard function: When inactive, the robot cannot drive faster than 0.3 m/s .</p>
12	<p>Signal name: Shelf mode</p> <p>Type: Input</p> <p>Standard function: When active, the robot checks for shelf legs if pin 11 is also active. Is only intended to be used with MiR Shelf Lift</p>
13	Unassigned.
14	Unassigned.

Pin no.	Description
15	<p>Signal name: Safe RTN</p> <p>Type: Ground</p> <p>Standard function: Safe return.</p>
16	Unassigned.
17	Unassigned.

WiFi antenna

The antenna interface is an RP-SMA connector that goes to the front compartment. It is not connected to the robot computer by default.

Adding antennas is considered a modification to the robot, and it is the modifier's responsibility to ensure applicable compliance.

Connecting the WiFi antenna interface

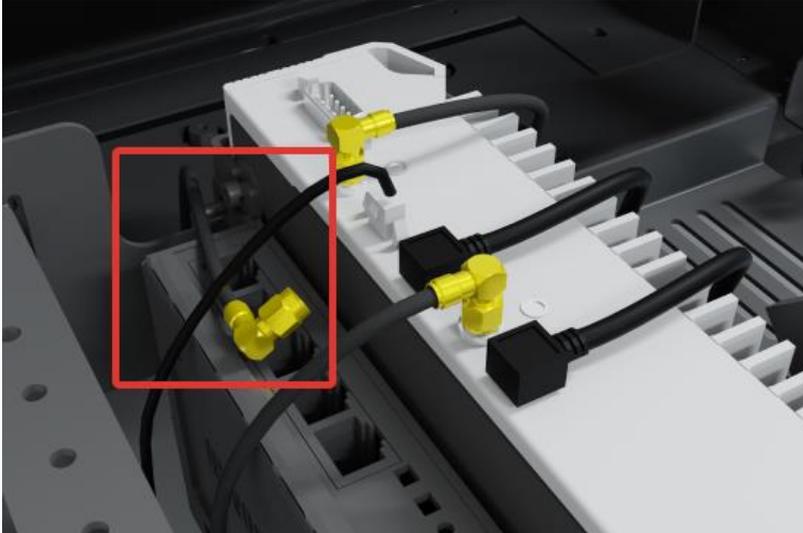
By default, the top interface WiFi antenna connector is not enabled. It is connected to an antenna cable inside the robot that leads to the front compartment, but the cable is not connected to the robot computer.

If you choose to use the WiFi antenna interface, you must disconnect one of the two antennas already installed in the robot, and connect the antenna cable from the top interface WiFi antenna to the robot computer instead.

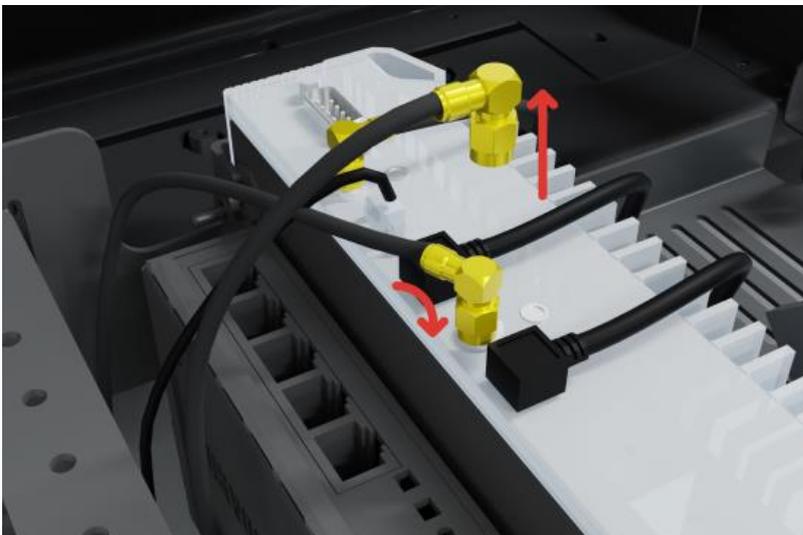
To swap which antenna is connected to the robot computer, follow these steps:

1. Open the front compartment—see [Accessing the internal parts on page 43](#).
2. Locate the robot computer—see [Front compartment on page 23](#).

3. Locate the loose RP-SMA antenna cable that is not yet connected. The cable will be nearby the robot computer.



4. Disconnect one of the connected antenna cables from the robot computer and connect the other antenna cable in its place. Use an 8 mm wrench to loosen and tighten the connectors.



5. Close the front compartment.

17.3 Connector list

Table 17.6 describes the connectors for the different interfaces that we recommend using.

Table 17.6. Description of the connectors used for the interfaces			
Connector name	Connector type	Phoenix Contact	Dimensions
Power	M23 6p	CA-06P1N8A8008S	See Figure 17.9 .
GPIO	M17 17p	ST-17S1N8A8K03S	See Figure 17.10 .
Ethernet	M12 4p	SACC-MSD-4PCT-SH PN SCO	
Auxiliary emergency stop	M17 8p	ST-08P1N8A8K03S	See Figure 17.10 .
Auxiliary safety functions	M17 17p	ST-17P1N8A8K03S	See Figure 17.10 .
WiFi antenna	RP-SMA	N/A	N/A

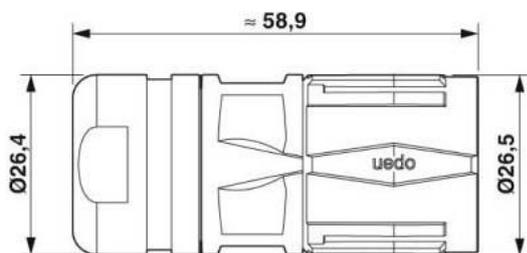


Figure 17.9. Connector dimensions for Power connector.

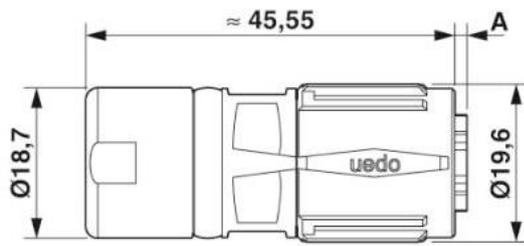


Figure 17.10. Connector dimensions for GPIO, Auxiliary emergency stop, and Auxiliary safety functions connectors.

18. Disposal of the robot

According to the European directive 2012/19/EU, Article 2, paragraph 4) d) and 4) e) (WEEE directive), MiR's robots are not in scope of the directive.

The robot is therefore not classified as WEEE and can be disposed of in accordance with the applicable local regulations.



NOTICE

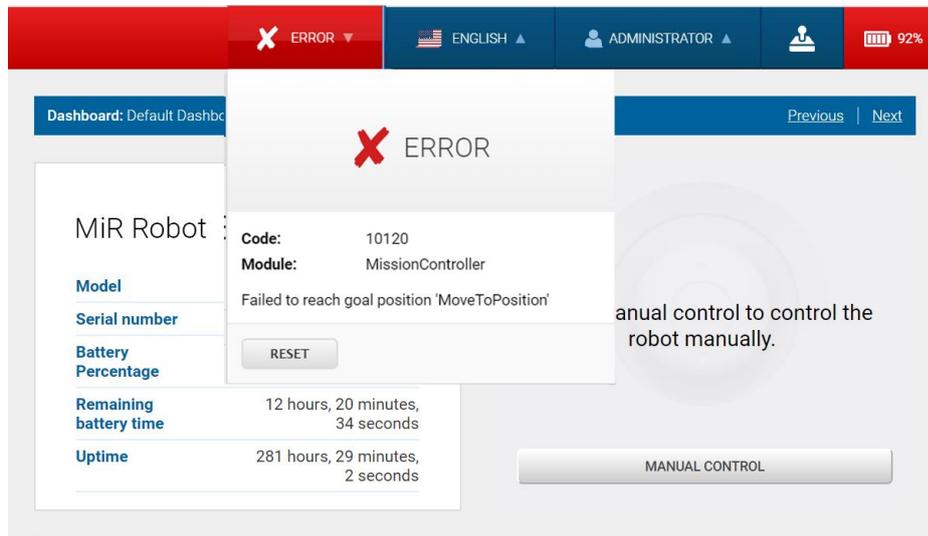
It is important to disconnect and remove the battery before disposal of the robot.

For information on how to disconnect the battery, see [Disconnecting the battery on page 80](#).

For battery disposal, see [Battery disposal on page 83](#).

19. Error handling

The robot enters an error state when it can't solve a problem on its own.



Errors include:

- Hardware faults
- Failed localization
- Failure to reach destination
- Unexpected events in the system

An error triggers a Protective stop. The robot is paused until a user acknowledges the error and clears it.

19.1 Software errors

Software errors such as localization and failure to reach the goal destination can be prevented with the proper setup of maps and missions:

- Always test your missions under full observation and normal work environment conditions before leaving the robot to execute the missions autonomously—see [Testing a mission on page 221](#).

- Use Try/Catch actions to make the robot react in a specific way if it fails to execute certain actions—see [Creating the mission Try/Catch on page 206](#).
- Use Prompt user actions in missions that require intervention from users—see [Creating the mission Prompt user on page 202](#).
- Define forbidden areas with Forbidden or Unpreferred zones on the map—see [Creating and configuring maps on page 143](#).
- Remove noise from maps—see [Creating and configuring maps on page 143](#).
- Create Directional or Preferred zones to guide the robot around areas that are difficult for the robot to travel through—see [Creating and configuring maps on page 143](#).

To clear an error, select the red warning indicator in the interface, and select **Reset**.

For more details on setting up missions and error handling, see *MiR Robot Reference Guide* on the MiR website.

19.2 Hardware errors

If the error is a fault in the hardware, either you will not be able to clear it, or the error will return until the fault is fixed. If this occurs, you can try to fix the issue with these actions:

- Turn your robot off and then on again. This resets the robot components and may resolve the issue.
- Check that all Emergency stop buttons are released.
- Check your robot for any physical damage such as cracks, dents, or severe scratches or contamination such as dust, dirt, and grease. Pay special attention to the 3D cameras, safety laser scanners, and drive wheels.

- Sign in to the robot interface and go to **Monitoring > Hardware health**. The interface displays which component is failing and often for what reason. This can help identify the source of the error. If an internal component is failing, turn off the robot, disconnect the battery, and have the commissioner or operator visually check the internal component for obvious faults.





- For further troubleshooting, contact your distributor for the MiR troubleshooting guides and the document *Error codes and solutions*.

20. Glossary

A

Autonomous mode

Mode in which the robot drives autonomously based on the missions you assign to it.

C

Commissioner

Commissioners have thorough knowledge of all aspects of commissioning, safety, use, and maintenance of MiR1350 and have the following main tasks: commissioning the product, including creating maps and restricting the user interface for other users; making the risk assessment; determining the payload limit, weight distribution, and safe methods of fastening of loads to MiR1350; and ensuring the safety of nearby personnel when a MiR robot is accelerating, braking, and maneuvering.

D

Direct user

Direct users are familiar with the safety precautions in the user guide and have the following main tasks: assigning missions to MiR1350, fastening loads to MiR1350 securely, and loading and unloading from a paused robot.

Dynamic obstacle

Dynamic obstacles are obstacles that are moved around, such as pallets, crates, and carts. These should not be included when creating a map.

E

Emergency stop

Emergency stop is a state the robot enters when an Emergency stop button has physically been pressed. When the robot is in Emergency stop, the status light of the robot turns red, and you are not able to move the robot or send it on missions until you bring the robot out of Emergency stop. To do this, you must release the Emergency stop button and then press the Resume button.

F

Footprint

A footprint set in the robot interface defines the size of the robot and its top module or load. It consists of a horizontal shape around the robot that should be slightly bigger than the robot itself to ensure that there is enough space along the calculated path, and a maximum height that ensures the robot does not try to drive under low obstacles. The horizontal shape is defined as coordinates relative to the robot's center.

G

Global path

The global path is the route the robot calculates that leads it to its goal position.

I

Identification label

The identification label is the label that is mounted to the product in production. The label is used to identify the components in your MiR application. It identifies the product model, the hardware version, and the product serial number.

L

Light indicators

Signal light and/or audial warnings. The signal lights are by default blinking yellow when the protective fields are muted. Audial warnings can be added in System settings.

Local path

The local path is the route the robot creates within its immediate vicinity that guides it around obstacles while still following the global path.

Localization

The method used by the robot to determine its position on the map relative to where it is in the work environment.

M

Manual mode

The mode in which you can drive the robot manually using the joystick in the robot interface.

Mapping

Mapping is the process of manually driving the robot around to create a new map. The robot uses its sensors to detect walls and obstacles and generates a map of the area based on this input.

Marker

A marker of a physical entity that the robot can dock to. This enables the robot to position itself accurately relative to the marker.

MiR application

A MiR application is either a single MiR product or a combination of MiR products that is able to execute certain tasks. A MiR application is often a MiR base robot combined with a MiR top module. If a custom top module is used, the CE mark on the nameplate of the base robot does not extend to the top module.

MiR robot interface

The MiR robot interface is the web-based interface that enables you to control your MiR robot. It is accessed by connecting to the same network as the robot and entering the robot's IP address in a browser.

N

Noise

With MiR robots, noise in maps refers to recorded data that originates from interfering elements. This can be physical obstacles that make the robot record walls where there are none or more subtle interferences that can make recorded walls appear pixelated.

O

Operator

Operators have thorough knowledge of MiR1350 and of the safety precautions presented in the User guide of MiR1350. Operators have the following main tasks: servicing, maintaining, and creating and changing missions and map positions in the robot interface.

P

Payload

The payload is the weight the robot carries. The maximum payload is the maximum weight the robot can carry, including the weight of any top modules, shelves, carts, or other devices.

Position

A position is a set of X-Y coordinates on the map that you can send the robot to.

Protective fields

The Protective fields are a part of the Personnel detection safety function. They are contours surrounding the robot that change size depending on the speed of the robot. When a safety laser scanner detects a person or

object within the active field, the robot enters Protective stop until the field is clear.

R

REST API

REST API is used by MiR Fleet and MiR robots to communicate status data and orders.

S

Site

A site is the overall container of any number of maps and all data relevant to the map, such as missions, features, robot groups, and transitions.

Static landmark

Static landmarks are obstacles that cannot be moved, such as walls, columns, and fixed structures. These must be included on the map and are used by the robot to localize itself.