

# MELFA Robots

Industrial Robot

Instruction Manual

## SD Series DeviceNet Slave Interface (2D-TZ571)



## Safety Instructions

**Before attempting to use the robot, carefully read the following safety instructions and those given in the "Safety Manual" that accompanies and take necessary actions.**

A. Safety instructions based on the requirements of the Labor Safety and Health Regulations (Articles 36, 104, 150, and 151) are listed below in abbreviated form.



### CAUTION

The robot teaching operation should be performed only by workers trained specifically in safety practices.  
(This applies to maintenance service done without shutting down the power source as well.)  
→ Implementation of safety training



### CAUTION

The robot teaching operation should be performed in accordance with established work rules which cover method or procedure used when operating the robot or actions taken to deal with all operating conditions including abnormal situations and subsequent restarting of the equipment.  
(This applies to maintenance service done without shutting down the power source as well.)  
→ Establishment of work rules



### WARNING

The robot teaching operation must be performed with a means being provided which permits an immediate shutdown of the robot.  
(This applies to maintenance service done without shutting down the power source as well.)  
→ Provision of an emergency shutdown switch



### CAUTION

During the performance of the robot teaching operation, an indication to that effect should be given in the immediate vicinity of the start switch or the like.  
(This applies to maintenance service done without shutting down the power source as well.)  
→ Indication of an ongoing robot teaching operation



### DANGER

During the operation of the robot, a fence or enclosure must be put around the robot so that workers are protected from inadvertent contact with the robot.  
→ Setting-up of a safety fence



### CAUTION

Robot operation should be started on a specific signal given to every worker concerned according to an established rule.  
→ A signal for starting an equipment operation



### CAUTION

Maintenance service should in principle be carried out with power being shut off. Ensure that an indication showing maintenance service being in progress is given in the immediate vicinity of the start switch or the like.  
→ Indication of an ongoing maintenance service

















### CAUTION

Before starting the operation of the robot, check the robot, emergency stop switch, and other associated devices for good condition.  
→ Checkup before starting robot operation

B. Safety instructions contained in the accompanying "Safety Manual" are listed below in abbreviated form.

For more details, read the main text of the "Safety Manual."

-  **CAUTION** Use the robot in an environment where operational parameters (temperature, humidity, atmosphere, noise, etc.) are kept within the specified limits. Otherwise, the robot may diminish in reliability or suffer a breakdown.
-  **CAUTION** When moving the robot, keep it in an attitude specified in the handling instructions that apply. Otherwise, the robot may turn over or drop and result in personal injury or equipment breakdown.
-  **CAUTION** Install the robot securely onto a rigid mount. Insecure installation may cause the robot to become mispositioned or develop undue vibration.
-  **CAUTION** Route cables as far away from a noise source as possible. If allowed to run too close to a noise source, the cable may be a cause for robot misposition or malfunction.
-  **CAUTION** Avoid placing excessive strain on the connector or bending the cable too abruptly. A poor connection or a break in the wiring may result.
-  **CAUTION** Ensure that the mass of work including that of the robot hand does not exceed the rated load and permissible torque. Excessive work mass may give rise to an alarm condition or mechanical failure.
-  **WARNING** The robot hand and tools must be installed securely and the work must be gripped firmly in place. Otherwise, objects may become dangerous projectiles during operation, causing personal injury or property damage.
-  **WARNING** The robot and controller must be well-grounded. Otherwise, noise may give rise to malfunction or, in some cases, an electric shock may be received.
-  **CAUTION** During the operation of the robot, an indication to that effect is put out. Without such an indication, worker may inadvertently get near the robot or make an operational mistake.
-  **WARNING** Before attempting to perform a robot teaching operation within its working radius, worker must make certain that he has acquired a precedence in the control of the robot. Otherwise, the robot may be activated by a command from any external source with a danger of personal injury or property damage.
-  **CAUTION** When applying jog control to the robot, use as low a speed as possible and keep an eye on the robot. Otherwise, interference between the robot and the peripheral equipment or structure may take place.
-  **CAUTION** Before placing the robot in auto operation following a program editing, be sure to check the robot for proper trajectories by manipulating it in stepwise fashion. Otherwise, an error in the programming or other glitch may lead to interference between the robot and the peripheral equipment or structure.
-  **CAUTION** Provision should be such that during the automatic operation of the robot, the entrance/exit door of the safety fence put around the robot is locked to forestall an attempt to open it or the robot is automatically placed in a stopped state to permit the opening of the door. Otherwise, personal injury may result.
-  **CAUTION** Do not make any modification to the product concerned on your own judgment or use maintenance/repair parts other than those that are recommended by the manufacturer. Otherwise, mechanical failure or malfunction may be experienced.



## WARNING

When moving the robot arm manually from outside, do not put your hands or fingers into any opening provided on the robot.  
You may, depending on your posture, get your hands or fingers caught between the structural members.



## CAUTION

Do not attempt to stop the robot, whether in normal operation or in emergency, by turning off the main power supply on the robot controller.

If the main power supply on the robot controller is turned off while the robot is in automatic operation, adverse effect may be caused on the precision with which the robot operates. Also, interference with the peripheral equipment or structure may result if the robot arm should drop or as it coasts to stop.



## CAUTION

Do not turn off the main power supply on the robot controller when internal information stored on the controller (programs or parameters) is being rewritten.  
If the main power supply on the robot controller is turned off during automatic operation or the loading of programs/parameters, internal information stored on the controller may be corrupted.

■ Revision History

Printing date	Manual No.	Description
2009-07-23	BFP-A8753*	Initial edition

■ Introduction

Thank you for purchasing Mitsubishi Electric SD Series Industrial Robot.

The DeviceNet Slave Interface (2D-TZ571) is an optional device which, installed into the SD Series Robot Controller, permits you to connect the Robot Controller to a DeviceNet network.

Before using the Interface, read this manual and familiarize yourself with all pages to ensure safe operation and obtain maximum satisfactory service from the DeviceNet Slave Interface (2D-TZ571).

Note: All descriptions in this manual assume that the user has an adequate understanding about basic operating procedures and functions which pertain to the Mitsubishi Industrial Robot SD Series. For detailed information about the basic operating procedures, refer to the "Instruction Manual - Detailed Explanations of Functions and Operations" which is separately issued.

■ Safety notation used in this manual:



**DANGER**

Indicates an immediately hazardous situation which, if not properly dealt with, will result in death or serious injury.



**WARNING**

Indicates a hazardous situation which, if not properly dealt with, could result in death or serious injury.



**CAUTION**

Indicates a hazardous situation which, if not properly dealt with, could result in injury, or property damage alone.

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# 1. Before Using DeviceNet Slave Interface

This section explains checks or precautions that you should perform or take before using the DeviceNet Slave Interface (2D-TZ571).

## 1.1 About Terms Used in This Manual

Table 1-1 Terms Used in This Manual

Generic name/abbreviation	Description
DeviceNet	A field network developed for FA applications by Allen-Bradley of the United States. At present, DeviceNet is a registered trademark of Open DeviceNet Vendor Association, Inc. (ODVA).
2D-TZ571	DeviceNet Slave Interface for SD Series (a complete set of products)
2D-TZ571 Card	DeviceNet Slave Interface Card for SD Series (TZ571)
Master station	A station that controls a data link system. At least one Master Station must be present in any one data link system.
Slave station	A station that is allowed to communicate with the Master Station.
Station number	A number assigned to Master Station or Slave Station. Numbering is in the range of 0 to 63.
Trunk line	A line that serves as a main in a networked system.
Drop line	A branch line that connects via a branch tap to a trunk line. Connection topologies usable for equipment on a branch line include "T-branch," "star connection," "daisy chain connection," and "branching."
Mutidrop	A topology in which equipment is connected directly to a trunk line.
Terminator resistor	Resistor connected to the DeviceNet network at each end.
Polling	One of connection types used during I/O communication. A mode in which a master station communicates with one slave station after another in sequence.

## 1.2 How to Use This Manual

This manual describes the functions of the 2D-TZ571 Card with its constituent sections organized as shown in the table below. For information about the functions available from the standard Robot Controller and the operating method thereof, refer to the "Instruction Manual" that is supplied with the Robot Controller.

Table 1-2 Organization of This Instruction Manual

Section	Title	Contents
1	Before Using 2D-TZ571	This section describes how to use this document (DeviceNet Slave Interface Instruction Manual). Read and familiarize yourself with the information contained before using the 2D-TZ571.
2	Features and specification of 2D-TZ571 Card	This section describes the features and specification of the Robot DevinceNet Interface.
3	Out of the Package	Upon receipt of the 2D-TZ571, check to see that all component parts are in the package and that the version of the Robot Controller is as specified.
4	Connections and Wiring	This section describes the method used to connect the 2D-TZ571 Card to the Master Station via cable.
5	Communication Test	This section describes the procedure followed to carry out a communication test before incorporating the 2D-TZ571 into the existing system.
6	Startup Procedure	This section describes the procedure followed to start the system.
7	Troubleshooting	This section presents information that helps find solutions when operational anomalies or errors are encountered during the use of the 2D-TZ571. Make reference to this section as occasion arises.
8	Appendix	The appendix explains the method for displaying information about the 2D-TZ571 Card on the screen by using RT ToolBox2.

## 2. Features and Specification of 2D-TZ571 Card

### 2.1 Features

The 2D-TZ571 Card has the following features:

- (1) A DeviceNet Slave interface variant for CRnD-700 series.
- (2) Compliant with the DeviceNet Specification, Release 2.0.
- (3) An interface specifically designed for robotics applications, which operates as a slave station alone.
- (4) Communication parameters for the DeviceNet can be established by using any of parameter setting functions listed following : R32TB, R56TB, or RT ToolBax2
- (5) I/O communication with a master station can be performed with input of up to 128 bytes (1,024 points) and output of up to 128 bytes (1,024 points).
- (6) Polling can be used for I/O communication with a master station.



### Caution

#### **Connectivity with DeviceNet products from other suppliers:**

The 2D-TZ571 may be expected to have connectivity with most of commercially available DeviceNet products. But Melco disclaims all warranties which pertain to such connectivity.

## 2.2 System Configuration

### 2.2.1 Overall Configuration

The DeviceNet permits you to connect a total of up to 64 stations, including master, slave and master/slave stations. Each station is connected either via a tap or directly to a trunk line. The following diagram shows an example of system configuration.

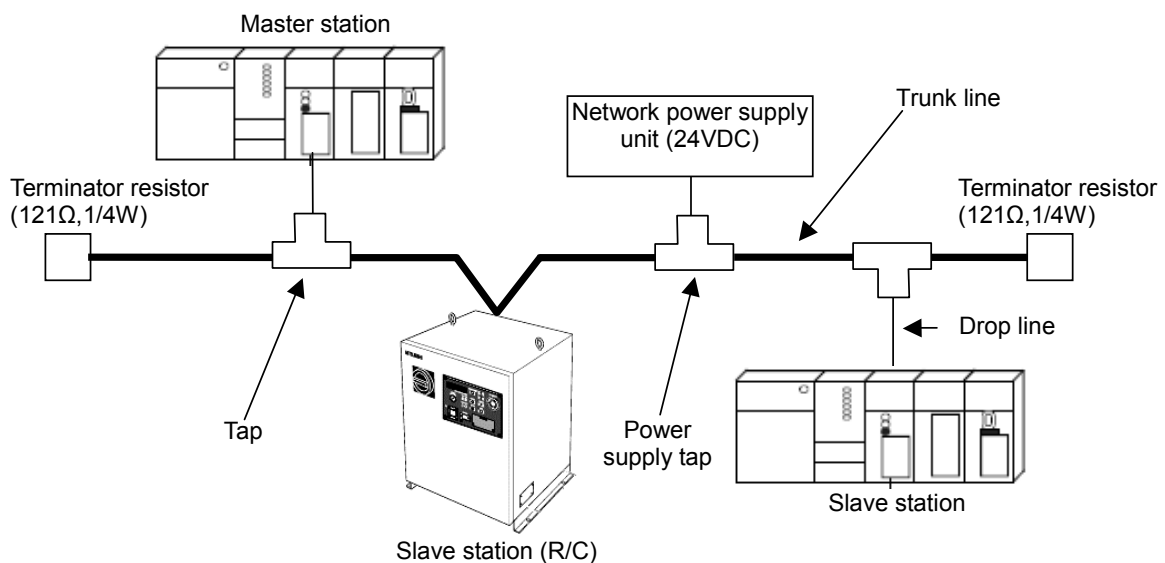


Figure 2-1 DeviceNet - Overall System Configuration

- (1) Robot controller is connected via a 2D-TZ571 Card to a DeviceNet network.
- (2) 2D-TZ571 Card can be used only as a slave station, not as a master station or a master/slave station.
- (3) A total of up to 64 stations, including master and slave stations, can be connected.
- (4) Master stations or slave stations need not be arranged in sequence based on station number.
- (5) Network cabling consists of a trunk line and drop line(s), and the trunk line must be provided with a terminator resistor at each end.
- (6) A network power supply is required in addition to the power supply which feeds individual stations.
- (7) The terminator resistors to be used may be ones that are supplied with the 2D-TZ571 or ones that are furnished by the user.

### **2.2.2 Network Specification**

The following is a description of a DeviceNet network specification incorporating the 2D-TZ571 Card.

(a) Communication speed

Communication speed of 125, 250 or 500 kbaud is user-selectable. Selection of a communication speed is accomplished by choosing a setting of the mode selector switch on the 2D-TZ571 Card. For switch setting details, see "Table 2-10 A Listing of Mode Switch (SW3) Settings." It should be noted that maximum usable cable length varies with communication speed. For more information, see "Table 2-2 Transmission Specification" and "Table 2-3 Transmission Speed in Mixed Thick/Thin-Cable Configuration".

(b) Network Power Supply

Network power is supplied to individual stations in the following manner:

- [1] A dedicated power supply tap is installed on the trunk line cable and a network power supply unit is connected to the tap.
- [2] Power from the network power supply unit is fed to individual stations over the network cable.

## 2.3 Specification

Table 2-1 General Specification (2D-TZ571 Card Specification)

Item		Specification	Remark
Type name of DeviceNet Slave Interface Card		TZ571	-
Communication capability		Both <b>bit</b> data and <b>word</b> data can be handled.	-
Option slots which accept an interface card		Slot 1/ Slot 2/Slot 3	Only one slot is usable at any time. <b>(CR1D is provided with Slot 1 only.)</b>
Number of cards accepted in slot		One	No more than one card is accepted.
Concurrent use with other fieldbus (*1)		Not permitted	-
DeviceNet specification supported		Release 2.0	-
Type of station * Type of station: master or slave		<b>Intended to serve as a slave station alone</b>	<b>Not intended to serve as a master station</b>
Type of node		DeviceNet slave (Group2 server)	-
Transmission speed		125, 250, or 500 kbaud	Rotary switch-selectable
Station number		0~63	Rotary switch-selectable (Default setting: 0)
Number of connections that can be generated (I/O connections)		One (polling)	-
Number of I/O communication points per robot controller	Transmission	<b>1,024</b> maximum	128 bytes
	Reception	<b>1,024</b> maximum	128 bytes
Head number of input/output to/from robot controller		<b>2000~</b>	For more information about signal assignment, see "Table 2-7 A Listing of DeviceNet Signals."
Terminator resistor		Uninstalled	-
Input/output signal access		2D-TZ571 Card send/receive data is assigned to input/output signal No. 2000 and up. In a MELFA-BASIC V network, these signals are treated as input/output signals like parallel I/O signals are.	-

(\*1)CC-Link Interface Card and Device Net Interface Card (both under development).

Table 2-2 Transmission Specification

Item	Specification						
Medium	Thick cable and thin cable						
Network configuration	Bus type (trunk line/drop line)						
Data link method	Polling						
Maximum length of cable (*1)	Transmission speed	Trunk line			Drop line		
		Thick cable	Thin cable	Mixed Thick/Thin-Cable	Maximum	Total	
		125kbps	500m	100m	see"Table2-3"	6m	156m
		250kbps	250m				78m
500kbps	100m	39m					

(\*1)The maximum length of cable applies to DeviceNet specifications Release2.0 Volume1 and Volume2.

Table 2-3 Transmission Speed in Mixed Thick/Thin-Cable Configuration

Transmission Speed	Maximum transmission speed in mixed thick/thin cable configuration
125kbps	Length of thick cable + 5 x thin cable ≤ 500m
250kbps	Length of thick cable + 2.5 x thin cable ≤ 250m
500kbps	Length of thick cable + thin cable ≤ 100m

Table 2-4 A Listing of Robot Parameters Used in DeviceNet

Item	Initial value	Setting range	Description
STOP2	-1, -1	-1 ~ 19999	A dedicated input parameter used to specify a dedicated input signal which causes robot program to be suspended. Please set 2000-3023 when setting it to the Input/Output signals of 2D-TZ571 Card. [Element 1] Stop input [Element 2] Pausing output (Because the parameter "STOP" is fixed at "0," DeviceNet uses "STOP 2" to define a suspend signal from outside.)
ORST2000 ORST2032 . ORST2992	00000000, 00000000, 00000000, 00000000	0/1/*	Value of data sent over DeviceNet at signal output reset is specified. For more information, see "2.6 General-purpose Output Resetting Function."
DNSDLN	8	0 ~ 128	Number of transmission bytes in I/O communication over DeviceNet (0~128)
DNRDLN	8	0 ~ 128	Number of reception bytes in I/O communication over DeviceNet (0~128)
DNERR	0	0/1	A parameter specified for a temporary reset to clear error condition at the occurrence of error about DeviceNet. (1: reset enabled (but communication not to be performed) / 0: error at all times while anomaly exists in the link) <b>* This parameter returns to initial value "0" when the operator resets power supply to the robot controller.</b>
DNFIL	5000, 200	0 ~ 32767	The communication abnormality detection filter is specified. This error occurs if each error continues during specified time. [Element 1] Error 8410, 8440, 8441, 8442, 8460 [Element 2] Error 8430 [Unit]ms

## 2.4 Compatible Versions

The table below shows the versions of the Controller and PC support software which are accommodated by the 2D-TZ571 Card.

Table 2-5 Compatible Versions

Name	Version
Robot Controller	P7a or later
PC support software	RT ToolBox2: Not dependent on version

## 2.5 Robot Controller Input/Output Signals

Input/output signals handled in the Robot Controller are in the range of 2000~3023 maximum irrespective of station numbers.

Table 2-6 DeviceNet Input/Output Number

	Input (received from master station)	Output (sent to master station)
Number	2000 ~ 3023	2000 ~ 3023

The data size of input/output signal is determined by specifying associated parameter (DNSDLN for transmission or DNRDLN for reception) with a number of bytes.

The range of parameter settings is 0 to 128 bytes and an initial value is 8 bytes.

Table 2-7 A Listing of DeviceNet Signals

Number of bytes	Usable number of points	Start	End
0	0	-	-
1	8	2000	2007
2	16	2000	2015
3	24	2000	2023
4	32	2000	2031
5	40	2000	2039
6	48	2000	2047
7	56	2000	2055
8	64	2000	2063
9	72	2000	2071
10	80	2000	2079
11	88	2000	2087
12	96	2000	2095
13	104	2000	2103
14	112	2000	2111
15	120	2000	2119
16	128	2000	2127
17	136	2000	2135
18	144	2000	2143
19	152	2000	2151
20	160	2000	2159
21	168	2000	2167
22	176	2000	2175
23	184	2000	2183
24	192	2000	2191
25	200	2000	2199
26	208	2000	2207
27	216	2000	2215
28	224	2000	2223
29	232	2000	2231
30	240	2000	2239
31	248	2000	2247
32	256	2000	2255
33	264	2000	2263
34	272	2000	2271
35	280	2000	2279
36	288	2000	2287
37	296	2000	2295
38	304	2000	2303
39	312	2000	2311
40	320	2000	2319
41	328	2000	2327
42	336	2000	2335
43	344	2000	2343
44	352	2000	2351
45	360	2000	2359
46	368	2000	2367
47	376	2000	2375
48	384	2000	2383
49	392	2000	2391
50	400	2000	2399
51	408	2000	2407
52	416	2000	2415
53	424	2000	2423
54	432	2000	2431
55	440	2000	2439
56	448	2000	2447
57	456	2000	2455
58	464	2000	2463
59	472	2000	2471
60	480	2000	2479
61	488	2000	2487
62	496	2000	2495
63	504	2000	2503
64	512	2000	2511
65	520	2000	2519
66	528	2000	2527
67	536	2000	2535
68	544	2000	2543
69	552	2000	2551
70	560	2000	2559
71	568	2000	2567
72	576	2000	2575
73	584	2000	2583
74	592	2000	2591
75	600	2000	2599
76	608	2000	2607
77	616	2000	2615
78	624	2000	2623
79	632	2000	2631
80	640	2000	2639
81	648	2000	2647
82	656	2000	2655
83	664	2000	2663
84	672	2000	2671
85	680	2000	2679
86	688	2000	2687
87	696	2000	2695
88	704	2000	2703
89	712	2000	2711
90	720	2000	2719
91	728	2000	2727
92	736	2000	2735
93	744	2000	2743
94	752	2000	2751
95	760	2000	2759
96	768	2000	2767
97	776	2000	2775
98	784	2000	2783
99	792	2000	2791
100	800	2000	2799
101	808	2000	2807
102	816	2000	2815
103	824	2000	2823
104	832	2000	2831
105	840	2000	2839
106	848	2000	2847
107	856	2000	2855
108	864	2000	2863
109	872	2000	2871
110	880	2000	2879
111	888	2000	2887
112	896	2000	2895
113	904	2000	2903
114	912	2000	2911
115	920	2000	2919
116	928	2000	2927
117	936	2000	2935
118	944	2000	2943
119	952	2000	2951
120	960	2000	2959
121	968	2000	2967
122	976	2000	2975
123	984	2000	2983
124	992	2000	2991
125	1000	2000	2999
126	1008	2000	3007
127	1016	2000	3015
128	1024	2000	3023

## 2.6 General-purpose Output Resetting Function

The factory default setting sets all general-purpose output signals to OFF (0) at power up. The status of general-purpose output signals after power up can be changed by changing the following parameter. Note that this parameter also affects the general-purpose output signal reset operation (called by dedicated I/O signals) and the reset pattern after executing the Clr instruction.

The following table lists parameters for 2D-TZ571 Card which pertain to general-purpose output resetting.

Table 2-8 A Listing of General-purpose Output Reset Pattern Parameters

Parameter name	Head number	Last number
ORST2000	2000	2031
ORST2032	2032	2063
ORST2064	2064	2095
ORST2096	2096	2127
ORST2128	2128	2159
ORST2160	2160	2191
ORST2192	2192	2223
ORST2224	2224	2255
ORST2256	2256	2287
ORST2288	2288	2319
ORST2320	2320	2351
ORST2352	2352	2383
ORST2384	2384	2415
ORST2416	2416	2447
ORST2448	2448	2479
ORST2480	2480	2511
ORST2512	2512	2543
ORST2544	2544	2575
ORST2576	2576	2607
ORST2608	2608	2639
ORST2640	2640	2671
ORST2672	2672	2703
ORST2704	2704	2735
ORST2736	2736	2767
ORST2768	2768	2799
ORST2800	2800	2831
ORST2832	2832	2863
ORST2864	2864	2895
ORST2896	2896	2927
ORST2928	2928	2959
ORST2960	2960	2991
ORST2992	2992	3023

Parameter ORSTOOOO has the initial values of "0000000, 00000000, 00000000, and 00000000". The value corresponds to bits from the left. Setting is "0", "1", or "\*\*\*".

"0" = Set to off    "1" = Set to on    "\*\*\*" = Maintain status with no change. (Set to off at power up.)

For example, if ORST2000 is set to "\*\*\*0000001, 00000000, 11110000, and 00000000," the following will result when power is turned back on to the Robot Controller:

Output No. 2000: Holds a state which existed before reset the Robot Controller

Output No. 2007: ON

Output Nos. 2016 ~ 2019: ON

Others: OFF

## 2.7 Hardware of 2D-TZ571 Card

The following subsections explain the steps followed to choose the rotary switch settings and LED indications on the 2D-TZ571 Card.

### 2.7.1 Overall View

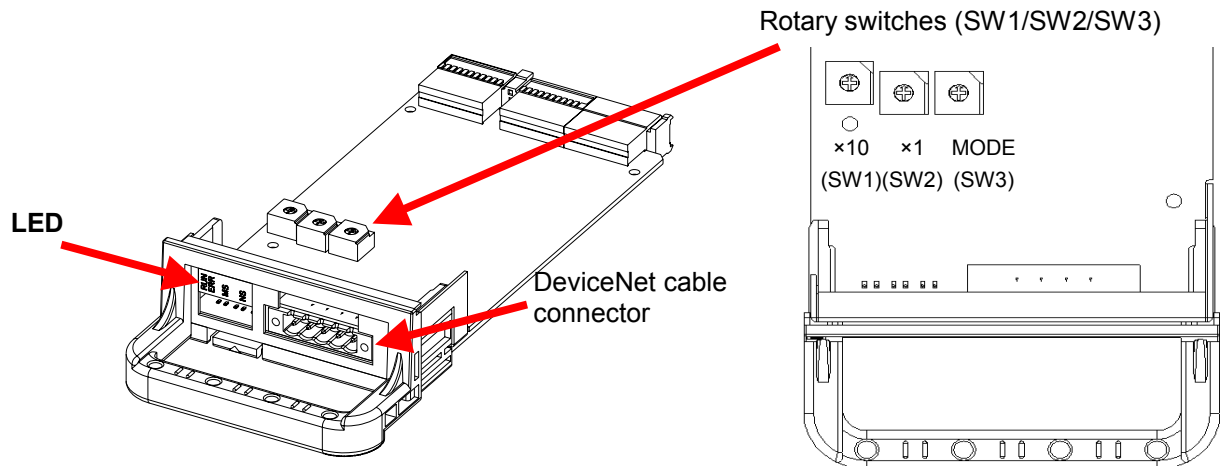


Figure 2-2 Overall View of 2D-TZ571 Card

### 2.7.2 Rotary Switch

There are three rotary switches (SW1/SW2/SW3) provided on the 2D-TZ571 Card. The table below shows settings which can be chosen from the rotary switches.

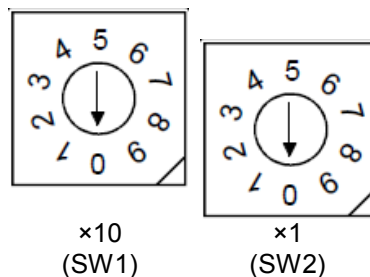
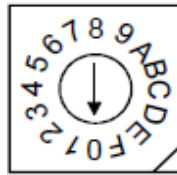


Table 2-9 A Listing of Station Number Selector Switch (SW1/SW2) Settings

Name	Item	Default setting	Description	Remark
Station number selector switch	x10	0	Specifies the tens digit of station number	Setting range: 0~63 (If any setting outside the range of 0 to 63 is chosen, Error 8421 (DEVICENET Unit number switch is outside) will result with the "ERR." LED lighting up.) * Be careful to avoid selecting station numbers which overlap one another.
	x1	0	Specifies the units digit of station number	

◇◆◇ "Assign as small a number to the Master Station as possible" ◇◆◇  
Station number can be chosen from a range of 0 to 63, but the characteristic of a DeviceNet network is such that a smaller station number carries a higher transmission priority. Therefore, it is advisable that as small a number as possible be assigned to Master Station.



MODE  
(SW3)

Table 2-10 A Listing of Mode Switch (SW3) Settings

Name	Setting	Function	Description	Remark
Mode switch	0	<b>Prohibited from use</b>		Use of these settings will result in Error 8420 (DEVICENET Mode switch is outside).
	1			
	2			
	3	Slave function	Card acts as a slave station. Communication speed: 125 Kbaud	
	4		Card acts as a slave station. Communication speed: 250 Kbaud	
	5		Card acts as a slave station. Communication speed: 500 Kbaud	
	6	<b>Prohibited from use</b>		Use of these settings will result in Error 8420 (DEVICENET Mode switch is outside).
	7			
	8			
	9	<b>Prohibited from use</b>		Use of these settings will result in Error 8420 (DEVICENET Mode switch is outside).
	A	Communication test	Transmission/reception test is carried out. Communication speed: 125 Kbaud	
	B		Transmission/reception test is carried out. Communication speed: 250 Kbaud	
	C		Transmission/reception test is carried out. Communication speed: 500 Kbaud	
	D-F	<b>Prohibited from use</b>		Use of these settings will result in Error 8420 (DEVICENET Mode switch is outside).

### 2.7.3 LEDs

There are five LEDs provided on the 2D-TZ571 Card, each of which lets you know the operating state of the Interface Card by going on, flickering, or going off.

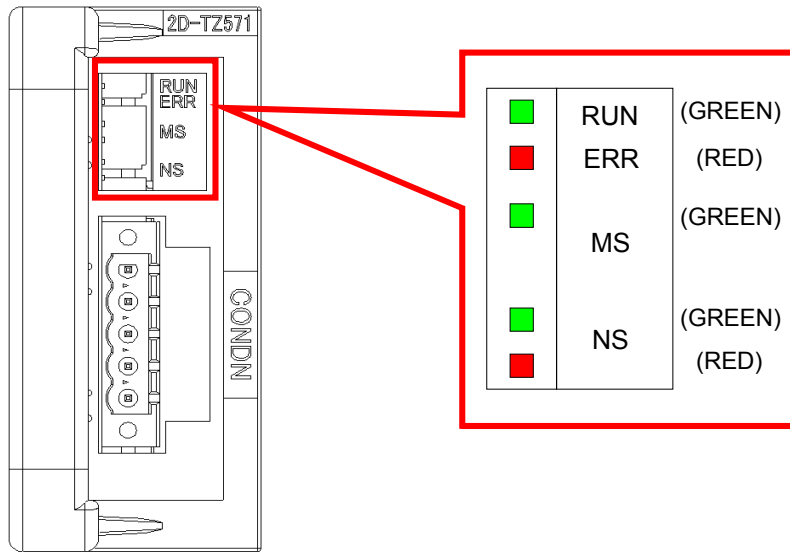


Figure 2-3 Placement of LEDs

Table 2-11 A Listing of LEDs (in Mode 3~5)

LED name	Color	Indications
RUN	Green	On: Operating normally
		Off: Watchdog timer error
ERR	Red	On: Station number setting error
		Flickering: Change has been made to Station Number Selector Switch and/or Mode Selector Switch settings during the operation of the unit.
MS	Green	On: Communication enabled
		Flickering: Parameter error
NS	Green	On: Communication going on
		Flickering: Waiting for communication (robot being in initialization process or waiting for other equipment to get ready to start communication)
	Red	On: There are overlapping station numbers.
		Bus off error (anomaly in communication line)
Green/red	Off: Network power supply is not lost.	

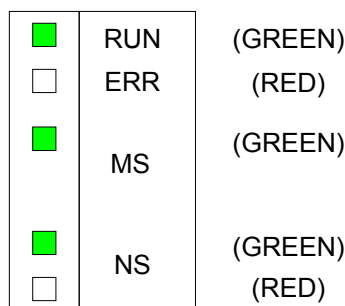


Figure 2-4 On-Off State of LEDs under Normal Operation

Table 2-12 A Listing of LEDs (in Mode A~C: Communication Test)

RUN	MS	ERR State	
On	Flickering	Off	Communication test going on
On	On	Off	Normal completion
On	Off	On	Abnormal completion

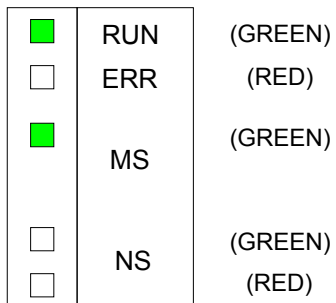


Figure 2-5 On-Off State of LEDs at Normal Completion

## 3. Out of the Package

### 3.1 Checking Component Parts

The product you purchased comes standard with the components listed in the table below. Check the product to ensure that it is complete with these components.

Table 3-1 Standard Components of Product

No.	Item name	Type name	Quantity
[1]	Instruction manual (this document)	BFP-A8735	1
[2]	DeviceNet Slave Interface Card (2D-TZ571 Card)	TZ571	1
[3]	Ferrite core	E04SR301334	1
[4]	Online connector for communication	MSTB2.5/5-STF-5.08AU M	1

Note: Numbers in the table corresponds to those in the figure below.

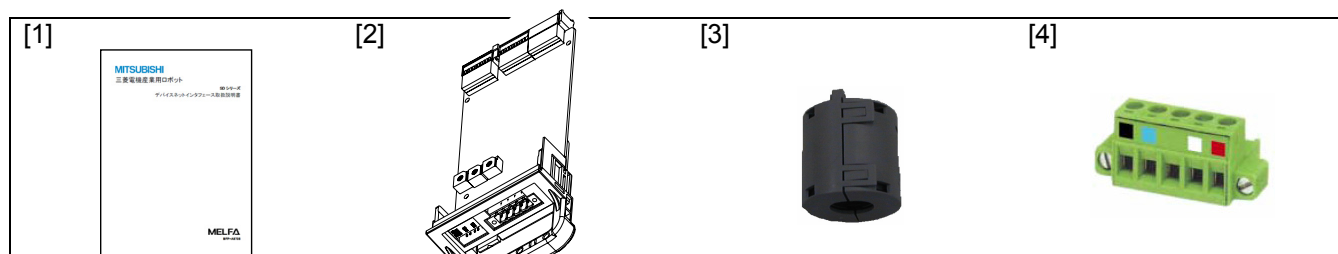


Figure 3-1 A Listing of Components Supplied with the Product

### 3.2 Compatible Versions

Please confirm the Compatible version of the Robot controller and the PC support software. (Refer to 2.4 Compatible Versions)

### 3.3 Items To Be Furnished by User

The following table shows the items that the user is required to have ready before using the 2D-TZ571 Card.

Table 3-2 Items To Be Furnished by User

Item	Requirements
Master station	DeviceNet-compliant master station
Communication cable (*1)	Cable specifically designed for use with DeviceNet Melco disclaims all guarantees of DeviceNet system performance if any cable other than those described herein is used. There are limits to maximum total cable length and inter-station cable length.

(\*1) For more information, visit "ODVA" website at <http://www.odva.org/>.

## 4. Connection and Wiring

### 4.1 Installing 2D-TZ571 Card

For instructions on how to install an optional card onto the Robot Controller, see the section under the heading "Installing Optional Devices" which is included in the controller's instruction manual "Controller Setup - From Basic Operating Procedure to Maintenance."

Only one 2D-TZ571 Card is permitted to be installed into either of the option slots (1 ~ 3) of the Robot Controller. If more than one card is installed into the slots, Error 8450 (DEVICENET Install more than one) will occur.

#### 4.1.1 For CR1D Controller

Remove the option slot interface cover on the rear of the Controller and install a 2D-TZ571 Card into the slot. During installation, use the handle fitted to the Interface Card.

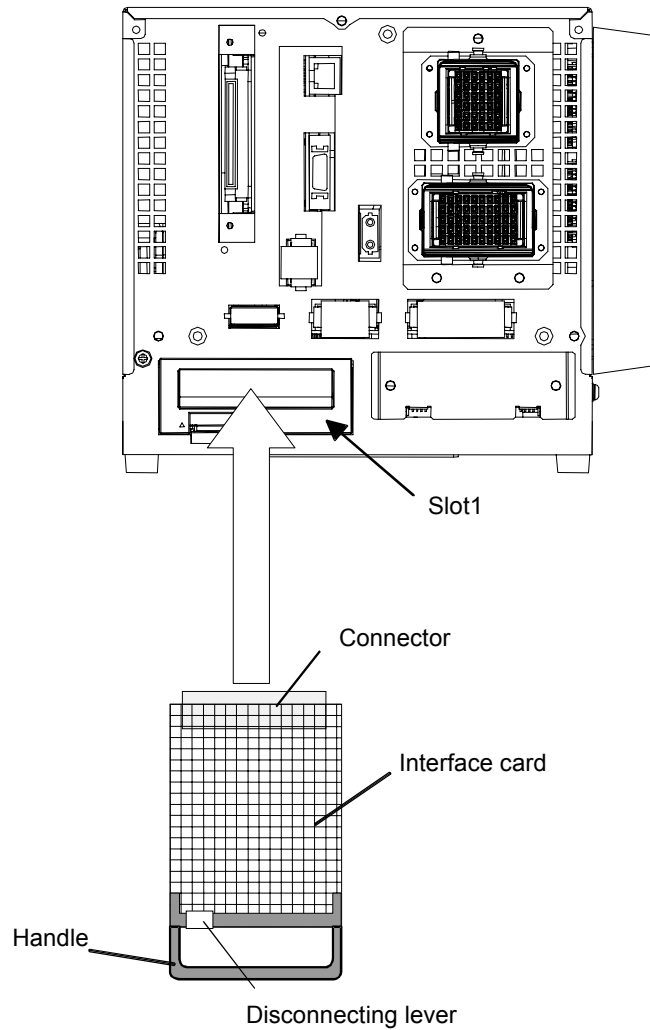


Figure 4-1 Installing 2D-TZ571 Card (in the case of CR1D Controller)

### 4.1.2 For CR2D Controller

Remove any one of the interface covers provided for the option slots 1 to 3 on the rear of the Controller and install a 2D-TZ571 Card into the slot. During installation, use the handle fitted to the Card.

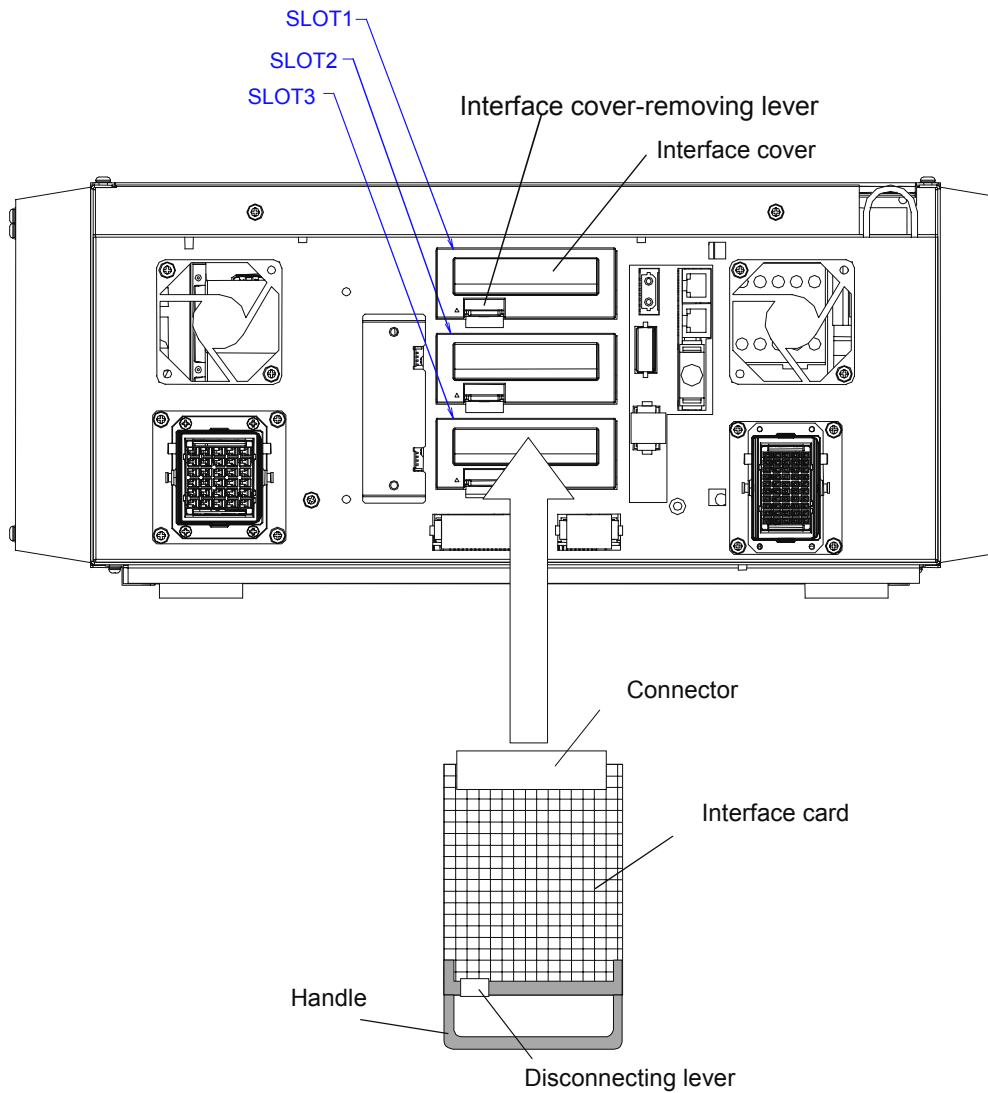


Figure 4-2 Installing 2D-TZ571 Card (in the case of CR2D Controller)

### 4.1.3 For CR3D Controller

Open the door of the Robot Controller and you will see R700 CPU unit located at the right-hand end. Remove any one of the interface covers provided for the option slots 1 to 3 on the CPU unit and install a 2D-TZ571 Card into the slot.

During installation, use the handle fitted to the Card.

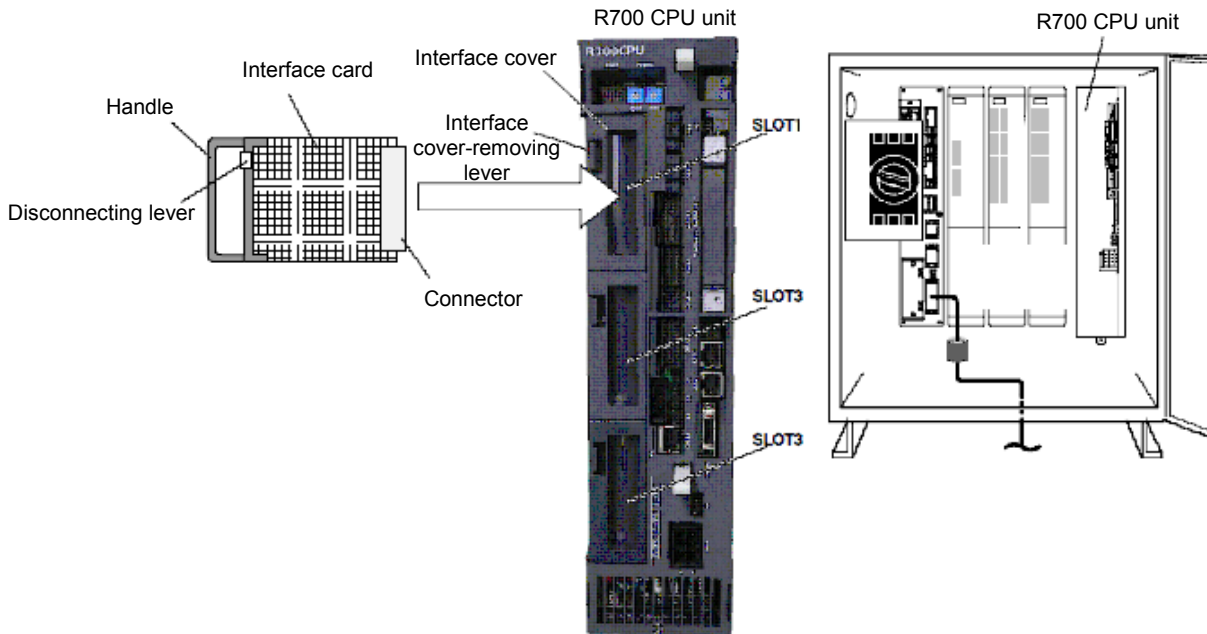


Figure 4-3 Installing 2D-TZ571 Card (in the case of CR3D Controller)

## 4.2 Connecting Communication Cable to 2D-TZ571 Card

### 4.2.1 Connecting Communication Cable

The DeviceNet connector on the 2D-TZ571 Card is arranged as shown below. It is affixed with adhesive labels, each having a color corresponding to the color of the communication cable. Connect the communication cable, noting the color-coding of the connector labels and the cables.

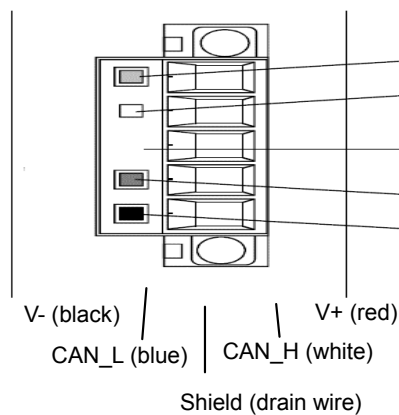


Figure 4-4 DeviceNet Connector Pin Assignment

### 4.2.2 Grounding Network

The DeviceNet network uses a single-point ground. Establish a ground near the mid-part of the network.

Connect the shield (drain wire) of the cable to the ground of the power supply unit, using Class D (Class 3) grounding.

If more than one power supply unit exists on the network, ground only the power supplier unit closer to the mid-part of the network, doing away with grounding elsewhere.

Also, if more than one power supply unit is employed on the network, use a power supply tap.

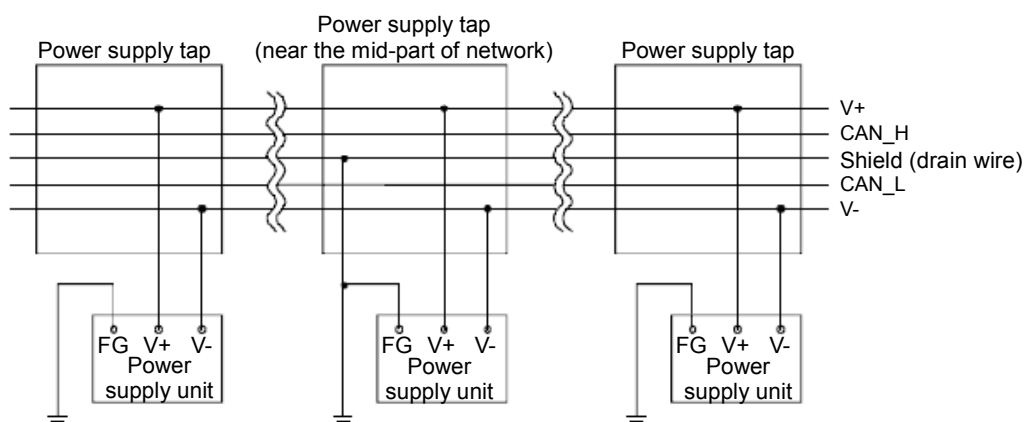


Figure 4-5 Grounding DeviceNet Network

## 4.3 Precautions about Network Power Supply

### 4.3.1 Arranging Network Power Supply Unit(s)

Follow the procedure given below to decide on the arrangement of network power supply unit(s):

- [1] Figure up a sum of current consumptions by individual stations which are connected to the network.
- [2] Take measurement of the network's total length.
- [3] Referring to Table 4-1 Maximum Current Capacity Sufficient for Master/Slave Stations Relative to Length of Thick-cable Network and Table 4-2 Maximum Current Capacity Sufficient for Master/Slave Stations Relative to Length of Thin-cable Network, determine a maximum current capacity which corresponds to the distance covered by the network and the type of cable used.
- [4] If the sum obtained in Step [1] is no greater than that obtained in Step [3], any of the power supply unit arrangements described in the next subsection may be used.
- [5] If the sum obtained in Step [1] is greater than that obtained in Step [3], check to see, by reference to the description in the next subsection, whether a power supply unit being located near the mid-part of the network is sufficient to supply power to all the stations.

If the check made in Step [5] shows that a single power supply unit is not sufficient to feed all the stations, increase the number of power supply units.

Table 4-1 Maximum Current Capacity Sufficient for Master/Slave Stations  
Relative to Length of Thick-cable Network

Length of network (m)	0	25	50	100	150	200	250	300	350	400	450	500
Maximum current (A)	8.00	8.00	5.42	2.93	2.01	1.53	1.23	1.03	0.89	0.78	0.69	0.63

Table 4-2 Maximum Current Capacity Sufficient for Master/Slave Stations  
Relative to Length of Thin-cable Network

Length of network (m)	0	10	20	30	40	50	60	70	80	90	100
Maximum current (A)	3.00	3.00	3.00	2.06	1.57	1.26	1.06	0.91	0.80	0.71	0.64



### Caution

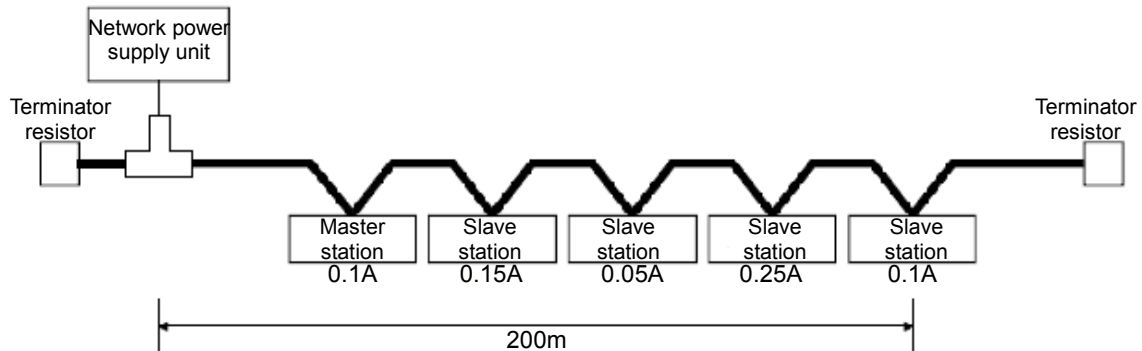
#### About current capacity of network power supply unit

Network power supply unit should be such that current capacity available is greater than total current consumption required. If current capacity is found insufficient, more than one power supply unit may be used. However, when using plural power supply units, install a power supply tap.

### 4.3.2 Arrangement of Network Power Supply Unit and Calculation of Current Capacity

#### (1) In the case power supply unit is connected at the end of network

Calculation of current capacity is shown below, provided that a power supply unit is connected at the end of a network which is 200m in total length and uses thick cable.



Total length of cable receiving power = 200m

Total current capacity =  $0.1A + 0.15A + 0.05A + 0.25A + 0.1A = 0.65A$

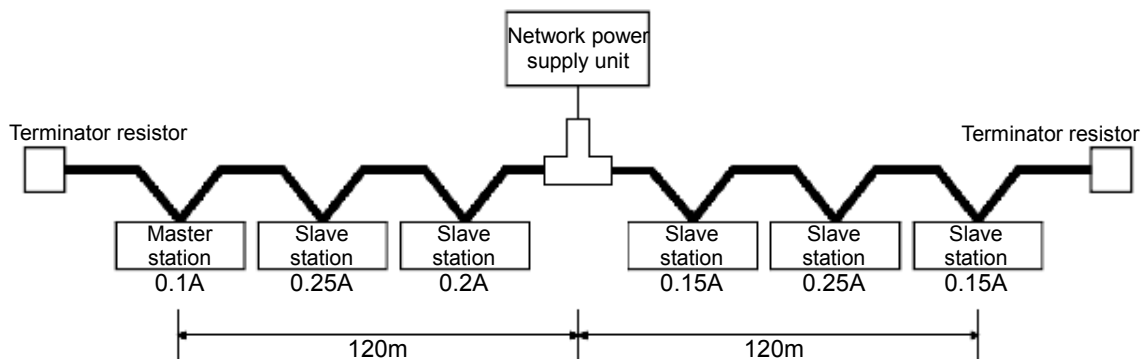
Maximum amount of current allowed to flow through the 200m-long thick-cable network (see Table 4-1 Maximum Current Capacity Sufficient for Master/Slave Stations

Relative to Length of Thick-cable Network) = 1.53A

Therefore, this arrangement allows power to be supplied to all the stations that are connected.

#### (2) In the case power supply unit is connected near the mid-part of network

Calculation of current capacity is shown below, provided that a power supply unit is connected near the mid-part of a network which is 200m in total length and uses thick cable. This arrangement allows twice as much current to flow as the one having a power supply unit connected at the end.



Total length of cable receiving power on the left side = total length of cable receiving power on the right side = 120m

Total current capacity on the left side =  $0.1A + 0.25A + 0.2A = 0.55A$

Total current capacity on the right side =  $0.15A + 0.25A + 0.15A = 0.55A$

Maximum amount of current allowed to flow through the 120m-long thick-cable network section (see Table 4-1 Maximum Current Capacity Sufficient for Master/Slave Stations

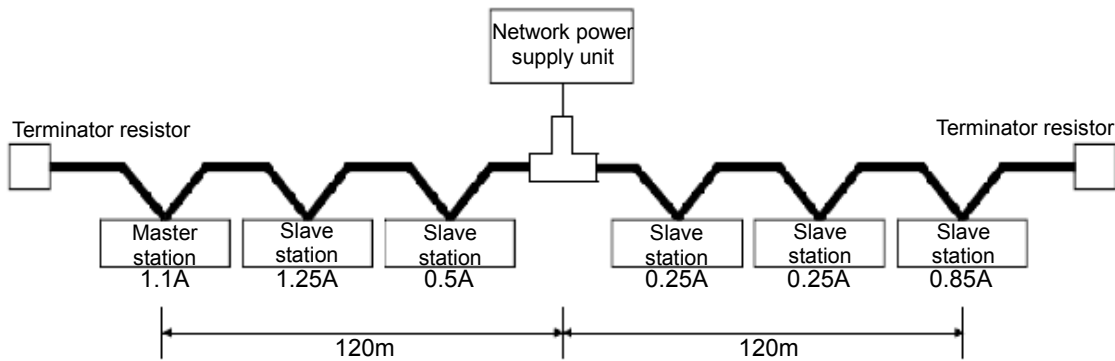
Relative to Length of Thick-cable Network)

= roughly 2.56A (determined by linear approximation in the interval between 100m and 150m)

Therefore, this arrangement allows power to be supplied to all the stations that are connected.

**(3) In the case the current capacity of a network power supply unit is insufficient**

This involves an arrangement of a network power supply unit in a thick-cable network as shown below.



Total length of cable receiving power on the left side = total length of cable receiving power on the right side = 120m

Total current capacity on the left side = 1.1A + 1.25A + 0.5A = 2.85A

Total current capacity on the right side = 0.25A + 0.25A + 0.85A = 1.35A

Maximum amount of current allowed to flow through the 120m-long thick-cable network section (see Table 4-1

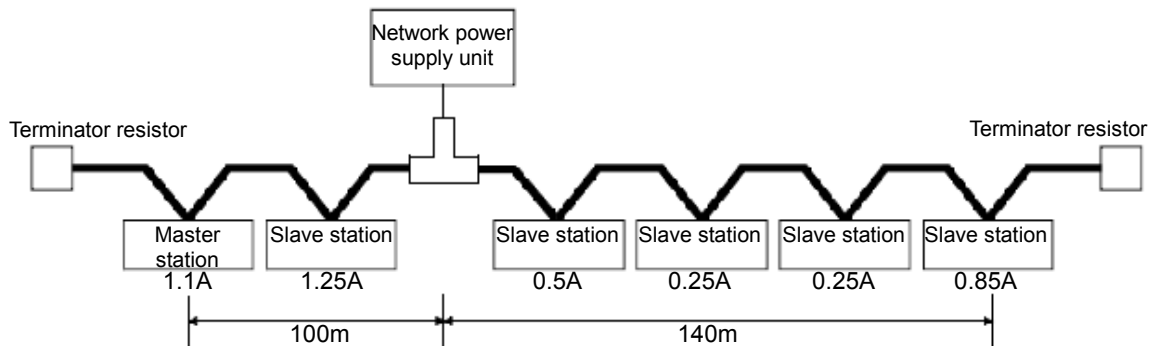
Maximum Current Capacity Sufficient for Master/Slave Stations

Relative to Length of Thick-cable Network)

= roughly 2.56A (determined by linear approximation in the interval between 100m and 150m)

As stated above, this arrangement is deficient in current capacity on the left side.

To get rid of the deficiency, the network power supply unit should be shifted in the direction where the deficiency is noted (to left side in the figure above).



Total length of cable receiving power on the left side = 100m

Total length of cable receiving power on the right side = 140m

Total current capacity on the left side = 1.1A + 1.25A = 2.35A

Total current capacity on the right side = 0.5A + 0.25A + 0.25A + 0.85A = 1.85A

Maximum amount of current allowed to flow through the 100m-long thick-cable network section

(see Table 4-1 Maximum Current Capacity Sufficient for Master/Slave Stations

Relative to Length of Thick-cable Network) = roughly 2.93A

Maximum amount of current allowed to flow through the 140m-long thick-cable network section

(see Table 4-1 Maximum Current Capacity Sufficient for Master/Slave Stations

Relative to Length of Thick-cable Network) = roughly 2.19A

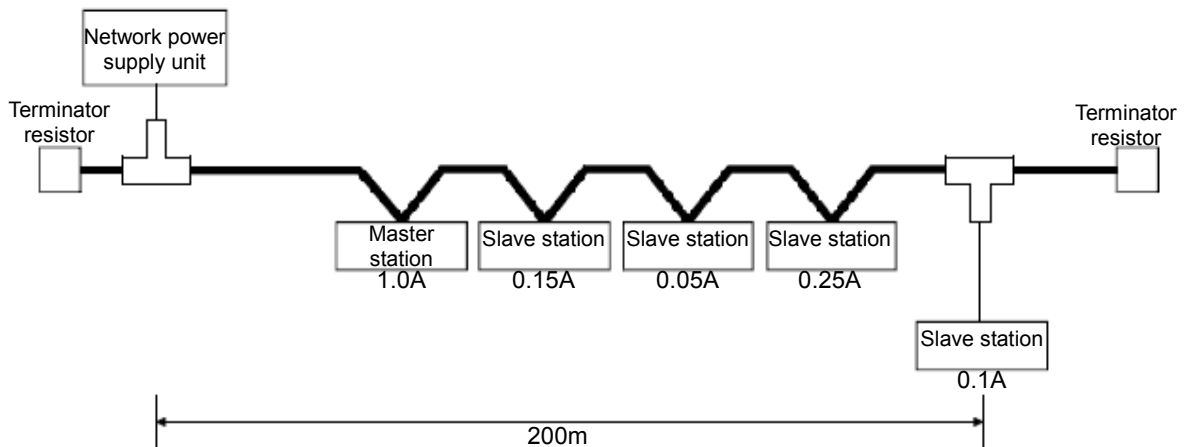
(Last two values determined by linear approximation in the interval between 100m and 150m)

As a result of the power supply unit being shifted so as to rectify the deficiency, the arrangement has become

capable of allowing power to be supplied to all the stations that are connected.

**(4) In the case both a trunk line and a drop line are included in a network**

Calculation of current capacity is shown below, provided that a power supply unit is connected to a network comprised of a 200m-long thick-cable trunk line and a 6m-long thin-cable drop line.



Total length of thick cable receiving power = 200m

Total length of thin cable receiving power = 6m

Total current capacity =  $0.5A + 0.15A + 0.05A + 0.25A + 0.1A = 1.05A$

Maximum amount of current allowed to flow through the 200m-long thick-cable section

(see Table 4-1 Maximum Current Capacity Sufficient for Master/Slave Stations

Relative to Length of Thick-cable Network) = 1.53A

Maximum amount of current allowed to flow through a 6m-long drop line

(see Table 4-3 Maximum Current Capacity Corresponding to Length of Drop-line Cable) = 0.75A

Total amount of current to equipment connected to the drop line = 0.1A

Therefore, this arrangement allows power to be supplied to all the stations that are connected.

Table 4-3 Maximum Current Capacity Corresponding to Length of Drop-line Cable

Length of drop line (m)	0.30	0.90	1.50	2.25	3.00	4.50	6.00
Maximum amount of current (A)	3.00	3.00	3.00	2.00	1.50	1.00	0.75

## 4.4 Checking Connections

Before placing the 2D-TZ571 Card in service, go through the following checklist to avoid any oversights.

Table 4-4 Checklist for Proper Connections

No.	Item confirmed	Check
1	Is the 2D-TZ571 Card securely installed into the Controller's slot?	
2	Is the DeviceNet Cable link between the 2D-TZ571 Card and the user's external equipment properly established?	
3	Is the equipment installed at each end of the DeviceNet network provided with a terminator resistor?	
4	Is the ferrite core is installed in place?	

## 5. Communication Testing

This section describes the procedure followed to perform transmission/reception tests on the 2D-TZ571 Card being connected one-to-one to other DeviceNet devices over a communication cable.

There are no limits to the number settings for the stations at the other end of the line, but they may not overlap those for the 2D-TZ571 Card. The description below assumes that settings for the master station are completed. For instructions on settings for the master station, refer to the manual that accompanies.

### 5.1 Communication Test Procedure

- [1] Set the station number switch on the 2D-TZ571 Card to an appropriate number.
  - [2] Set the mode switch on the 2D-TZ571 Card to any of A, B, and C. (Communication speed of the Card need to be matched to that of the DeviceNet device at other end of the line.)
  - [3] Install the 2D-TZ571 Card into the option slot on the Robot Controller.
  - [4] Connect the 2D-TZ571 Card to the DeviceNet device at other end of the line using the DeviceNet Cable.
  - [5] Turn on power to the network.
  - [6] Turn on power to the DeviceNet station at other end of the line.
  - [7] Turn on power to the Robot Controller.
  - [8] The 2D-TZ571 Card will automatically begin a communication test, and the MS LED will keep on flashing green during the test.
  - [9] If the MS LED is lit green while the ERR LED is off, this indicates a normal completion of the test.
    - \* Normal completion will result in the occurrence of Error 8490 (DeviceNet communication test mode).
- If the MS LED is off while the ERR LED is lit, this indicates an abnormal completion of the test.
- \* Abnormal completion will result in the occurrence of Errors 8491-8494



#### **CAUTION**

##### ***About the operation of the Robot Controller while in communication test mode***

While in communication test mode, the Robot Controller operates as it would if the DeviceNet Interface Card is not installed.

## 6. Startup Procedure

This section describes the procedure which is necessary when constructing a DeviceNet system. Note: The description below assumes that the master station and other network components are in a state of readiness to operate and that the initial setup of the robot is completed.

### 6.1 Initial Startup

The following procedure is used to accomplish initial startup:

- [1] Set the station number switch on the 2D-TZ571 Card to an appropriate number.
- [2] Set the mode switch on the 2D-TZ571 Card to any of 3, 4, and 5. (Communication speed of the Card need be matched to that of the devices on the network.)
- [3] Install the 2D-TZ571 Card into the option slot on the Robot Controller.
- [4] Connect the DeviceNet cable to the 2D-TZ571 Card.
- [5] Turn on power to the network.
- [6] Turn on power to the other devices on the network.
- [7] Turn on power to the Robot.
- [8] If any error associated with the DeviceNet network is generated on the robot side, set parameter E8430 or DNERR to enable a temporary recovery from such error. (Resetting step will permit you to clear such error.)
- [9] Specify the number of reception bytes (DNRDLN) and the number of transmission bytes (DNSDLN). (For information about the relevant parameters, see "Table 2-4 A Listing of Robot Parameters Used in DeviceNet".)
- [10] Turn off power to the robot, and then back on.

### 6.2 Normal Operation

For normal operation, the following startup procedure is used:

- [1] Turn ON power to the network.
- [2] Turn ON power to the other devices on the network.
- [3] Turn ON power to the Robot.

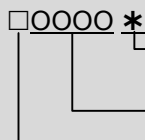
This will let the robot to establish connection with the DeviceNet network and start I/O communications with the master station.

## 7. Troubleshooting

Check this section before concluding that your system is out of order.

### 7.1 A Listing of Errors

◇◆◇ An error number contains information as listed below ◇◆◇



- An error marked with an asterisk \* requires a power reset.  
Take a corrective action which is stated in the "Solutions" section of the table below.
- The type of error is indicated by a 4-digit number.
- Errors are sorted into three classifications:  
H: High-level error ..... Servo mechanism is shut down.  
L: Low-level error ..... Operation is suspended.  
C: Caution ..... Operation is allowed to continue.

Table 7-1 A Listing of DeviceNet-related Errors

Error No.	Causes and Solutions	
H.8410*	Error message	DEVICENET Card failure
	Cause	Abnormality of the DEVICENET card is detected
	Solution	Please exchange the DEVICENET card
H.8420*	Error message	DEVICENET Mode switch is outside
	Cause	The mode switch is outside
	Solution	Please correct the mode switch
H.8421*	Error message	DEVICENET Unit number switch is outside
	Cause	The unit number switch is outside
	Solution	Please correct the unit number switch
H.8430	Error message	DEVICENET Communication error
	Cause	Network fail or Master setting is illegal
	Solution	Please confirm the network (speed, cable, terminator) or the master unit
H.8440	Error message	DEVICENET Unit number overlaps
	Cause	There are more than one unit with the same unit number on the network
	Solution	Please confirm the other unit number
H.8441	Error message	DEVICENET Network power failure
	Cause	Network power is turned off
	Solution	Please turn on network power
H.8442	Error message	DEVICENET Other units not found
	Cause	Other units are not connected on the network
	Solution	Please confirm the other units
H.8450	Error message	DEVICENET Install more than one
	Cause	Only one 2D-TZ571 card can be installed
	Solution	Please install only one 2D-TZ571 card
H.8451	Error message	DEVICENET Set other fieldbus
	Cause	Only one. fieldbus card can be installed
	Solution	Only one fieldbus card is installed
L.8460	Error message	DEVICENET Timeout
	Cause	The I/O communication was can not be done in time.
	Solution	Please confirm the other units or power supply of network.

H.8470*	Error message	DEVICENET Param load write error (*1)
	Cause	Parameter can not be load and written
	Solution	Turn the power OFF and ON once
H.8471*	Error message	DEVICENET Send byte is outside
	Cause	Send byte number setting of is out of range
	Solution	Please correct the send byte number setting
H.8472*	Error message	DEVICENET Receive byte outside
	Cause	Receive byte number setting is outside
	Solution	Please correct the receive byte number setting
H.8473*	Error message	DEVICENET Send-receive are 0
	Cause	Both receive and send byte number setting are 0
	Solution	Please change receive or send byte number setting
C.8490	Error message	DEVICENET Communication test mode
	Cause	It is communication test mode.
	Solution	Please change the mode switch to 3-5 after the test ends.
H.8491*	Error message	DEVICENET Comm-test unit number (*2)
	Cause	Unit numbers overlap is detected by communication test
	Solution	Please confirm the other units number
H.8492*	Error message	DEVICENET Comm-test busoff (*2)
	Cause	Busoff is detected by communication test
	Solution	Please confirm communication speed, cable, terminator
H.8493*	Error message	DEVICENET Comm-test net power (*2)
	Cause	Network power off is detected by communication test
	Solution	Please turn on network power
H.8494*	Error message	DEVICENET Comm-test send-receive (*2)
	Cause	Data can not send and receive normal by communication test
	Solution	Please confirm connection situation of others, communication speed, cable and terminator

(\*1)Pram : Parameter

(\*2)Comm : Communication

## 7.2 At the Occurrence of Error 8460

### (DEVICENET Timeout)

When this error occurred, take the corrective action suggested in the troubleshooting chart in Section 7.1. If the error still persists, check to see the following:

- (1) Is power to the Master Station unit on?
- (2) Is the Master Station functioning properly?
- \* 8460 occurs unless the Master Station is up and running before power is turned on to the Robot Controller.
- \* If Master Station provides function to set it's parameter automatically and the function is used, it is late for running and 8460 may occur.
- (3) Is the Master Station properly connected?
- (4) Are the parameter settings on the Master Station consistent with those on the Robot Controller?
- (5) Doesn't any of the peripheral equipment contain a noise emission source?
- (6) If it is desired to ignore Error 8460, change DNERR parameter setting.

## 8. Appendix

### 8.1 Displaying Information about Optional Cards

RT ToolBox2 (Options) lets you to have information about the option cards displayed on the screen.

Expand the workspace tree and click "Slotn:DEVICENT" entry under "Option Cards." Information about the 2D-TZ571 Card will appear on the property window.

Properties are displayed.

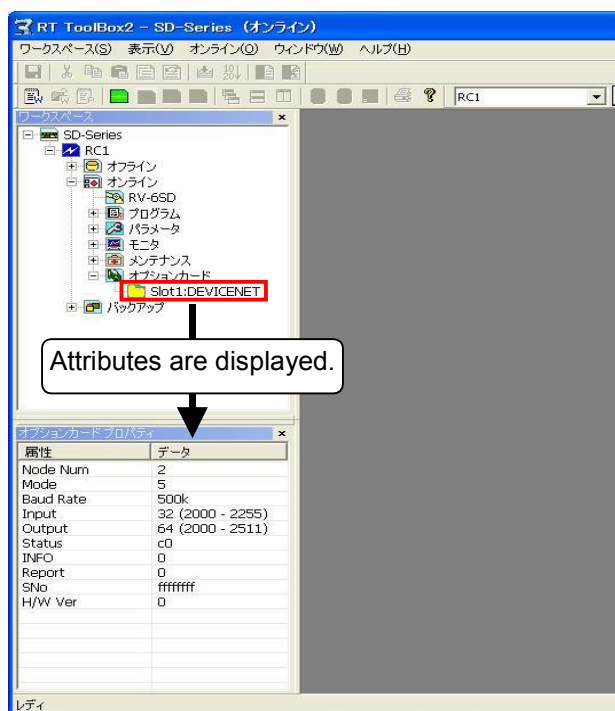


Figure 8-1 Information about Optional Cards from RT ToolBox2

Table 8-1 Information about the 2D-TZ571 Card

Display item	Example	Meaning	Remark	
Card name	DEVICENET	Card designation		
Card information	[Node Num]	63	Station number switch	Station number: 0~63
	[Mode]	3	Mode switch	Mode switch (0~F)
	[Baud Rate]	125k	Communication speed	125k 250k 500k
	[Input]	8(2000 - 2063)	Number of reception bytes (signal number)	0 (-) ~ 128 (2000 - 3023)
	[Output]	8(2000 - 2063)	Number of transmission bytes (signal number)	0 (-) ~ 128 (2000 - 3023)
	[Status]	00C0	I/O communication state	0000: offline 0040: stop 0080: communication-ready 00C0: I/O communication going on
	[Info]	0000	Error information	Slave function error code
	[SNo]	12345678	Serial number	Serial number
[H/W Ver]	0	Card group number		



**HEADQUARTERS**

MITSUBISHI ELECTRIC EUROPE B.V. **EUROPE**  
 German Branch  
 Gothaer Straße 8  
**D-40880 Ratingen**  
 Phone: +49 (0)2102 / 486-0  
 Fax: +49 (0)2102 / 486-1120

MITSUBISHI ELECTRIC EUROPE B.V. **CZECH REPUBLIC**  
 Czech Branch  
 Avenir Business Park, Radlická 714/113a  
**CZ-158 00 Praha 5**  
 Phone: +420 - 251 551 470  
 Fax: +420 (0)251-551-471

MITSUBISHI ELECTRIC EUROPE B.V. **FRANCE**  
 French Branch  
 25, Boulevard des Bouvets  
**F-92741 Nanterre Cedex**  
 Phone: +33 (0)1 / 55 68 55 68  
 Fax: +33 (0)1 / 55 68 57 57

MITSUBISHI ELECTRIC EUROPE B.V. **IRELAND**  
 Irish Branch  
 Westgate Business Park, Ballymount  
**IRL-Dublin 24**  
 Phone: +353 (0)1 4198800  
 Fax: +353 (0)1 4198890

MITSUBISHI ELECTRIC EUROPE B.V. **ITALY**  
 Italian Branch  
 Viale Colleoni 7  
**I-20041 Agrate Brianza (MB)**  
 Phone: +39 039 / 60 53 1  
 Fax: +39 039 / 60 53 312

MITSUBISHI ELECTRIC EUROPE B.V. **POLAND**  
 Poland Branch  
 Krakowska 50  
**PL-32-083 Balice**  
 Phone: +48 (0)12 / 630 47 00  
 Fax: +48 (0)12 / 630 47 01

MITSUBISHI ELECTRIC EUROPE B.V. **SPAIN**  
 Spanish Branch  
 Carretera de Rubí 76-80  
**E-08190 Sant Cugat del Vallés (Barcelona)**  
 Phone: 902 131121 // +34 935653131  
 Fax: +34 935891579

MITSUBISHI ELECTRIC EUROPE B.V. **UK**  
 UK Branch  
 Travellers Lane  
**UK-Hatfield, Herts. AL10 8XB**  
 Phone: +44 (0)1707 / 27 61 00  
 Fax: +44 (0)1707 / 27 86 95

MITSUBISHI ELECTRIC CORPORATION **JAPAN**  
 Office Tower "Z" 14 F  
 8-12, 1 chome, Harumi Chuo-Ku  
**Tokyo 104-6212**  
 Phone: +81 3 622 160 60  
 Fax: +81 3 622 160 75

MITSUBISHI ELECTRIC AUTOMATION, Inc. **USA**  
 500 Corporate Woods Parkway  
**Vernon Hills, IL 60061**  
 Phone: +1 847 478 21 00  
 Fax: +1 847 478 22 53

**EUROPEAN REPRESENTATIVES**

GEVA **AUSTRIA**  
 Wiener Straße 89  
**AT-2500 Baden**  
 Phone: +43 (0)2252 / 85 55 20  
 Fax: +43 (0)2252 / 488 60

Koning & Hartman b.v. **BELGIUM**  
 Woluwelaan 31  
**BE-1800 Vilvoorde**  
 Phone: +32 (0)2 / 257 02 40  
 Fax: +32 (0)2 / 257 02 49

INEA BH d.o.o. **BOSNIA AND HERZEGOVINA**  
 Aleja Lipa 56  
**BA-71000 Sarajevo**  
 Phone: +387 (0)33 / 921 164  
 Fax: +387 (0)33 / 524 539

AKHNATON **BULGARIA**  
 4 Andrej Ljapchev Blvd. Pb 21  
**BG-1756 Sofia**  
 Phone: +359 (0)2 / 817 6004  
 Fax: +359 (0)2 / 97 44 06 1

AutoCont C.S. s.r.o. **CZECH REPUBLIC**  
 Technologická 374/6  
**CZ-708 00 Ostrava-Pustkovec**  
 Phone: +420 595 691 150  
 Fax: +420 595 691 199

B:ELECTRIC, s.r.o. **CZECH REPUBLIC**  
 Mladoboleslavská 812  
**CZ-197 00 Praha 19 - Kbely**  
 Phone: +420 286 850 848, +420 724 317 975  
 Fax: +420 286 850 850

Beijer Electronics A/S **DENMARK**  
 Lykkegårdsvej 17, 1.  
**DK-4000 Roskilde**  
 Phone: +45 (0)46 / 75 76 66  
 Fax: +45 (0)46 / 75 56 26

Beijer Electronics OY **FINLAND**  
 Jaakonkatu 2  
**FIN-01620 Vantaa**  
 Phone: +358 (0)207 / 463 500  
 Fax: +358 (0)207 / 463 501

UTECO A.B.E.E. **GREECE**  
 5, Mavrogenous Str.  
**GR-18542 Piraeus**  
 Phone: +30 211 / 1206 900  
 Fax: +30 211 / 1206 999

AXICONT AUTOMATIKA KFT. **HUNGARY**  
 (ROBOT CENTER) Reitter F. U. 132  
**HU-1131 Budapest**  
 Phone: +36 1 / 412-0882  
 Fax: +36 1 / 412-0883

ALFATRADE Ltd. **MALTA**  
 99, Paola Hill  
**Malta- Paola PLA 1702**  
 Phone: +356 (0)21 / 697 816  
 Fax: +356 (0)21 / 697 817

HIFLEX AUTOM. TECHNIK B.V. **NETHERLANDS**  
 Woluweverstraat 22  
**NL-2984 CD Ridderkerk**  
 Phone: +31 (0)180 - 46 60 04  
 Fax: +31 (0)180 - 44 23 55

**EUROPEAN REPRESENTATIVES**

Koning & Hartman b.v. **NETHERLANDS**  
 Haarlerbergweg 21-23  
**NL-1101 CH Amsterdam**  
 Phone: +31 (0)20 / 587 76 00  
 Fax: +31 (0)20 / 587 76 05

Beijer Electronics AS **NORWAY**  
 Postboks 487  
**NO-3002 Drammen**  
 Phone: +47 (0)32 / 24 30 00  
 Fax: +47 (0)32 / 84 85 77

SIRIUS TRADING & SERVICES SRL **ROMANIA**  
 Aleea Lacul Morii Nr. 3  
**RO-060841 Bucuresti, Sector 6**  
 Phone: +40 (0)21 / 430 40 06  
 Fax: +40 (0)21 / 430 40 02

INEA SR d.o.o. **SERBIA**  
 Izletnicka 10  
**SER-113000 Smederevo**  
 Phone: +381 (0)26 / 617 163  
 Fax: +381 (0)26 / 617 163

CS MTrade Slovensko, s.r.o. **SLOVAKIA**  
 Vajanskeho 58  
**SK-92101 Piestany**  
 Phone: +421 (0)33 / 7742 760  
 Fax: +421 (0)33 / 7735 144

INEA d.o.o. **SLOVENIA**  
 Stegne 11  
**SI-1000 Ljubljana**  
 Phone: +386 (0)1 / 513 8100  
 Fax: +386 (0)1 / 513 8170

Beijer Electronics Automation AB **SWEDEN**  
 Box 426  
**SE-20124 Malmö**  
 Phone: +46 (0)40 / 35 86 00  
 Fax: +46 (0)40 / 35 86 02

Omni Ray AG **SWITZERLAND**  
 Im Schörlí 5  
**CH-8600 Dübendorf**  
 Phone: +41 (0)44 / 802 28 80  
 Fax: +41 (0)44 802 / 28 28

GTS **TURKEY**  
 Bayraktar Bulvarı Nutuk Sok. No:5  
**TR-34775 Yukari Dudullu-Umraniye-ISTANBUL**  
 Phone: +90 (0)216 526 39 90  
 Fax: +90 (0)216 526 3995

CSC Automation Ltd. **UKRAINE**  
 4-B, M. Raskovoyi St.  
**UA-02660 Kiev**  
 Phone: +380 (0)44 / 494 33 55  
 Fax: +380 (0)44 / 494-33-66

**MIDDLE EAST REPRESENTATIVE**

ILAN & GAVISH Ltd. **ISRAEL**  
 24 Shenkar St., Kiryat Arie  
**IL-49001 Petaht-Tiqva**  
 Phone: +972 (0)3 / 922 18 24  
 Fax: +972 (0)3 / 924 0761

**AFRICAN REPRESENTATIVE**

CBI Ltd. **SOUTH AFRICA**  
 Private Bag 2016  
**ZA-1600 Isando**  
 Phone: + 27 (0)11 / 977 0770  
 Fax: + 27 (0)11 / 977 0761