

Release Notes

Version	Comment	Supported	Interface
		Grippers	
1.0.6 Compatibility: E-Series Robots Polyscope 5.20.0	Changelog: Added Toolbar Required Options: - Known Issues:	EGU: all types with firmware version <= 5.3 EGK: all types with firmware version <= 5.3 EZU: all types with firmware version = 5.3	Modbus RTU at tool interface
1.0.5 Compatibility: E-Series Robots Polyscope 5.17.3	Changelog: Added firmware V5.3 support: - Support for new gripper type EZU Changed the Set Brake toggle button to a checkbox Added quick help popups to for all installation and program nodes Added information on the maximum allowed velocity when jogging the gripper Set default value for bit 31 (use GPE) to false Timeout for the function "Wait until complete" changed to 16.5s Corrected calculation of maximum grip velocity when using soft mode Changed UI of the Relative Position Program Node to allow negative target position input	EGU: all types with firmware version <= 5.3 EGK: all types with firmware version <= 5.3 EZU: all types with firmware version = 5.3	Modbus RTU at tool interface

	Required Options: - Known Issues: Fixed bug that caused wrong appearance of program nodes after loading a program.		
1.0.4 Compatibility: E-Series Robots Polyscope 5.14.2	Changelog: Added firmware V5.2 support: - “Brake Test” - Command available - “Not feasible”, reason is shown in the status bar to provide more information why the command is not executed by the gripper. - Jogging the gripper is now possible with a target velocity Changed appearance of testing UI in the installation node Required Options: - Known issues: Fixed bug that caused the pendant to freeze when loading a program with a “Grip”-program node. Added “EGUEGK_” prefix to all program variables to avoid name conflicts with other variables.	EGU: all types with firmware version <= 5.2 EGK: all types with firmware version <= 5.2	Modbus RTU at tool interface
1.0.2 Compatibility: E-Series Robots Polyscope 5.13	Changelog: Changed maximum velocity to 80 mm/s for EGU 50 grippers only. Removed the command “workpiece gripping at expected position” for EGU 50 grippers only. Changed number of digits of the target velocity to 2	EGU: all types with firmware version 5.1 EGK: all types with firmware version 5.1 Firmware version 5.2 is compatible but new functions of version 5.2 are not supported	Modbus RTU at tool interface

	Fixed Bug that led to high target positions or target velocities when using the + and – Buttons in the program nodes Corrected range for gripper parameters Required Options: - Known issues: Comma as number delimiter used by European languages causes errors. Plugin is only working when the robot language is set to English. Parameter “grip position margin” is not considered when calculating position ranges in program nodes If the gripper is not connected when the robot is started, gripper parameters are set to default values in the program nodes		
1.0.1 Compatibility: E-Series Robots Polyscope 5.13	Changelog: Initial Version Required Options: - Known issues: High target velocities for EGU 50 cause the robot arm to shut down Setting gripper parameters outside of the parameter’s range cause the plugin to stop communicating with the gripper	EGU: all types with firmware version 5.1 EGK: all types with firmware version 5.1	Modbus RTU at tool interface