

PROJECT IDENTIFICATION		
Project Name	Project Number	Date Created
Customer Name	Project Owner	
UR Integrator Name	Project Manager	
Factory Line / Station		
Completed by		

ROBOT			
Tag	Robot Type (UR3/5/10/16/20)	Serial Number	Describe

APPLICATION						
				Complexity		
Line Tag	Type	Yes	No	Low	Medium	High
	Assembly	☐	☐	☐	☐	☐
	Quality Inspection	☐	☐	☐	☐	☐
	Machine Tending	☐	☐	☐	☐	☐
	Packaging	☐	☐	☐	☐	☐
	Palletizing	☐	☐	☐	☐	☐
	Pick & Place	☐	☐	☐	☐	☐
	Other (describe):	☐	☐	☐	☐	☐

Installation

TCP						
Name	X	Y	Z	RX	RY	RZ

PAYLOAD					
Name	Mass	CX	CY	CZ	Inertia Matrix

ROBOT MOUNTING			
Type	Yes	Type	Yes
Tabletop	☐	Angle	☐
Ceiling	☐	Wall	☐

INPUTS/OUTPUTS					
Input	Tag	Name	Output	Tag	Name
DI[0]			DO[0]		
DI[1]			DO[0]		
DI[2]			DO[0]		
DI[3]			DO[0]		
DI[4]			DO[0]		
DI[5]			DO[0]		
DI[6]			DO[0]		
DI[7]			DO[0]		
ANALOG I/O					
AI[0]			AO[0]		
AI[1]			AO[0]		
TOOL I/O					
TI[0]			TO[0]		
TI[1]			TO[0]		
AI[2] Tool					
AI[3] Tool					

ROBOT LIMITS	
Factory Restriction Limits	Value
(1-4) (Min-Max)	

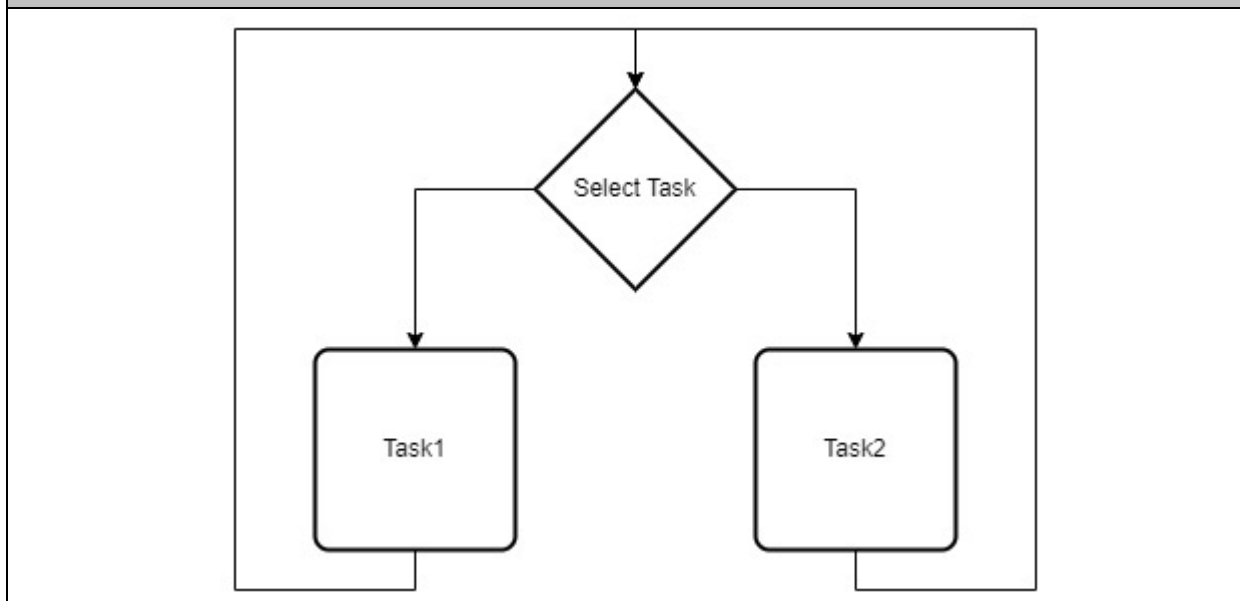
SAFETY I/O					
Input	Tag	Name	Output	Tag	Name
C_In[0], C_In[1]			C_Out[0], C_Out[1]		
C_In[2], C_In[3]			C_Out[2], C_Out[3]		
C_In[4], C_In[5]			C_Out[4], C_Out[5]		
C_In[6], C_In[7]			C_Out[6], C_Out[7]		

SAFETY CONFIGURATION	
Checksum Value	

REFERENCE FEATURES						
Name	X	Y	Z	RX	RY	RZ

Program

WAYPOINTS							
Name	X	Y	Z	RX	RY	RZ	Ref Feature

PROGRAM FLOWCHART

PROGRAMS (SUBPROGRAMS)

Name	Description
Program1	Main
Subprogram	Tool Change

URCAPS

Name	Version

SYSTEM	
Item	Value
Remote Control	
Network (IP Address)	
Network (Subnet Mask)	
Network (Gateway)	
Profinet Name	

DEVICES					
Port n#	IP Address	Type	Yes	No	Comments
	1.1.1.1	PLC Protocol used	☐	☐	Type:
	1.1.1.1	Vision (camera)	☐	☐	URCap:
	1.1.1.1	AGV/AMR integration	☐	☐	Type:
	1.1.1.1	MES	☐	☐	
	1.1.1.1	Gateway (Remote Access)	☐	☐	Type:
	1.1.1.1	Welding machine	☐	☐	Type:
	1.1.1.1	Screwdriving machine	☐	☐	Type:

PASSWORDS	
Item	Value
Administrator	
Mode (Auto/Manual)	
Safety	

ROBOT CONFIGURATION				
		Configured?		
Number	Installation & Programs	Yes	No	Additional info
1	TCP and CoG added	☐	☐	
1	More than 1 TCP is used	☐	☐	
1	Tool payload added	☐	☐	
2	TCP attached to moved	☐	☐	
2	TCP changes along the program	☐	☐	
2	Product payload is set	☐	☐	
3	Waypoint with Blend Radius	☐	☐	
3	Speed changes	☐	☐	Values:
3	Acceleration changes	☐	☐	Values:
3	Interrupted motion / Continually Evaluated conditions			
3	Robot is close to Singularity	☐	☐	
4	Safety limits according to TS15066 and local standards	☐	☐	
4	Protective and Emergency Stop properly integrated	☐	☐	Check UR best practices
4	Smooth transition used	☐	☐	
4	Total payload (tool + product) is close to robot max. capacity	☐	☐	
4	Faults are met <40h	☐	☐	Stop the robot and call UR DI
4	Warnings and errors are met	☐	☐	Check 30 days after commissioning
5	PLC interface used	☐	☐	Socket communication properly
5	External programming (not in PolyScope)	☐	☐	Python or Java Script
6	Stable Single-phase power	☐	☐	Voltage:
6	No-Break used	☐	☐	Type/Power:

OTHER CONSIDERATIONS				
Topics	Consideration			Additional info
Collaboration level	☐ High	☐ Med.	☐ Low	
Robot caged	☐ Yes	☐ No		
UR Training needed	☐ Core	☐ Adv.	☐ M&T	
UR Maintenance met	☐ Yes	☐ No		
myUR rregistration	☐ Yes	☐ No		
Backup and Log_file	☐ Yes	☐ No		
Pre-Configured Safety Settings	☐ Yes	☐ No		Data:
Safety checksum (code)	☐ Yes	☐ No		Data:
User Password	☐ Yes	☐ No		Data:
Safety Password	☐ Yes	☐ No		Data:

VERSION				
Date	Version	Modification	Editor	Robot backup (after modification)
1/1/2000	V1.0	Set up	Name	20230223_UR10_ST145