
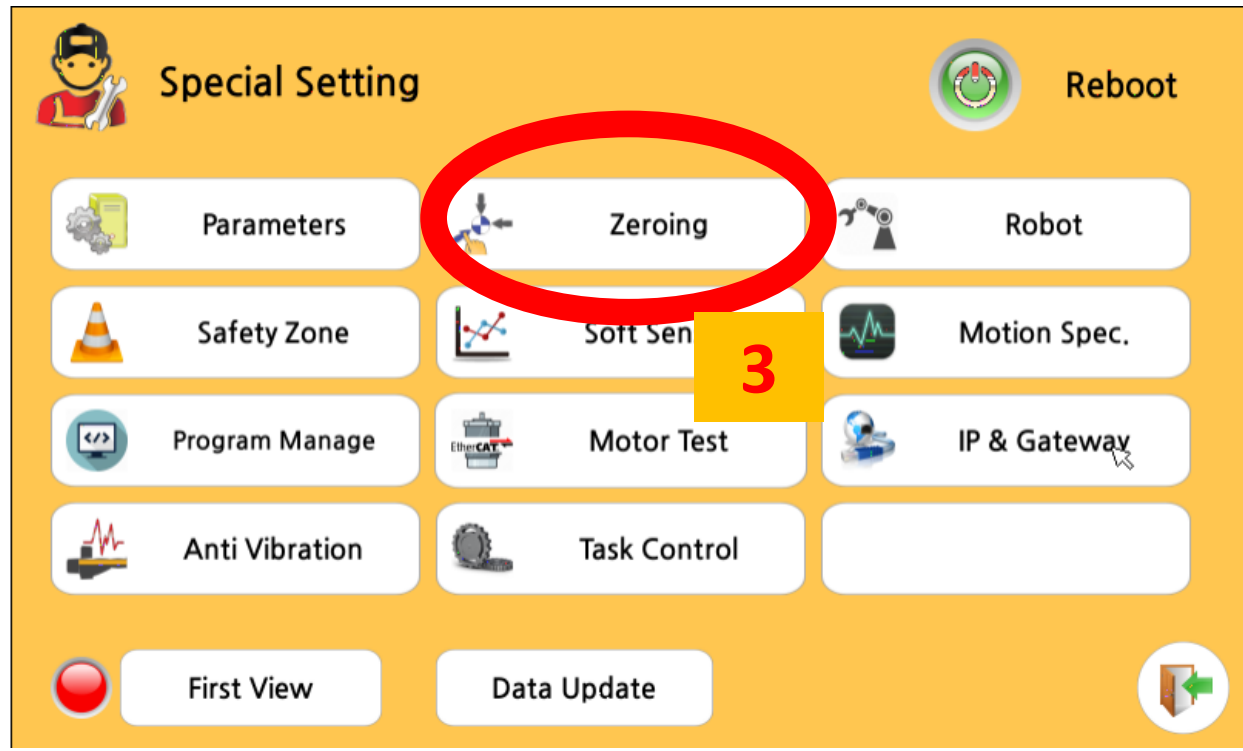
A decorative graphic in the top-left corner consisting of several overlapping squares in various shades of blue, ranging from light to dark, arranged in a grid-like pattern that tapers off towards the right.

# H5 Zeroing & Multi-turn Data Clearing

A decorative graphic in the bottom-right corner, similar to the one in the top-left, consisting of overlapping blue squares in various shades, arranged in a grid-like pattern that tapers off towards the left.

# 1. Motor Multi-turn Data Clearing

Level 7



# 1. Motor Multi-turn Data Clearing

The screenshot shows the 'Mechanical Zero Setting' interface. It features a table with 'Trans' and 'Joint' columns. The 'Joint' column contains five entries: J1, J2, J3, J4, and J5, each circled in red. To the right of the table are several control buttons: 'Zeroing', 'Jogging', 'Inching', a battery level indicator at 5%, and a 'J' button. The interface also shows a user profile icon with the number 7 and a 100% battery indicator.

	Trans	Joint	
X	108.85	J1	108.85
Y	955.45	J2	14.93
Z	-32.03	J3	32.58
A	-90.00	J4	55.26
B	102.77	J5	-0.00
C	90.00		

- If the motor/driver cable is disconnected or the battery life is over, the robot position value will be lost.
- In this case, multi-turn data clearing is needed.

- Press the button (Red circle), and clear multi-turn data.

- Clear multi-turn data first before zeroing.

- If alarm goes off (ex. Driver Alarm 27.1), reboot the robot.

# 2. Zeroing

Trans		Joint	
X	108.85	J1	108.85
Y	955.45	J2	14.93
Z	-32.03	J3	32.58
A	-90.00	J4	55.26
B	102.77	J5	-0.00
C	90.00		

Zeroing

Jogging Inching

5%

10 1 0.1 0.01

J

- Check servo is ON



- Move each joint to each zeroing position.  
(See appendix for the positions)

- Use zeroing pin provided.

# 2. Zeroing – method #1

Method #1. Zeroing all the joint *at the same time*

Method #2. Zeroing each joint *individually*.

Mechanical Zero Setting [2] training 7 100%

Trans		Joint	
X	108.85	J1	108.85
Y	955.45	J2	14.93
Z	-32.03	J3	32.58
A	-90.00	J4	55.26
B	102.77	J5	-0.00
C	90.00		

Zeroing

Jogging Inching

5%

10 1 0.1 0.01

Power Jog J Home

## Method 1

- If all joints are in zeroing position, press Zeroing button (Red circle)
- When you press 'Zeroing' button, all joints position values will be reset at the same time
- Do double check if all joints are in zeroing position.

## 2. Zeroing – method #2

Method #1. You can zeroing all the joint *at the same time*

Method #2. You can zeroing each joint *individually*.



The screenshot shows the 'Mechanical Zero Setting' interface. It features a table with columns for 'Trans' and 'Joint'. The 'Joint' column lists J1 through J5. The values for each joint are: J1 (108.85), J2 (14.93), J3 (32.58), J4 (55.26), and J5 (-0.00). A red circle highlights the zeroing button for each joint, and a red circle highlights the zeroing value for each joint. The interface also includes a 'Zeroing' button, a 'Jogging' button, an 'Inching' button, a progress indicator at 5%, and various control buttons like power, reset, and joint selection.

Trans	Joint
X	108.85
Y	955.45
Z	-32.03
A	-90.00
B	102.77
C	90.00

## Method 2

- Press button (Red circle) to zeroing each joint.
- When zeroing Joint 4, Joint 5 zeroing value may be changed correspondingly.
- So make sure Joint 5 zeroing position as well

# Appendix A. Zeroing Tools



Zeroing Pin



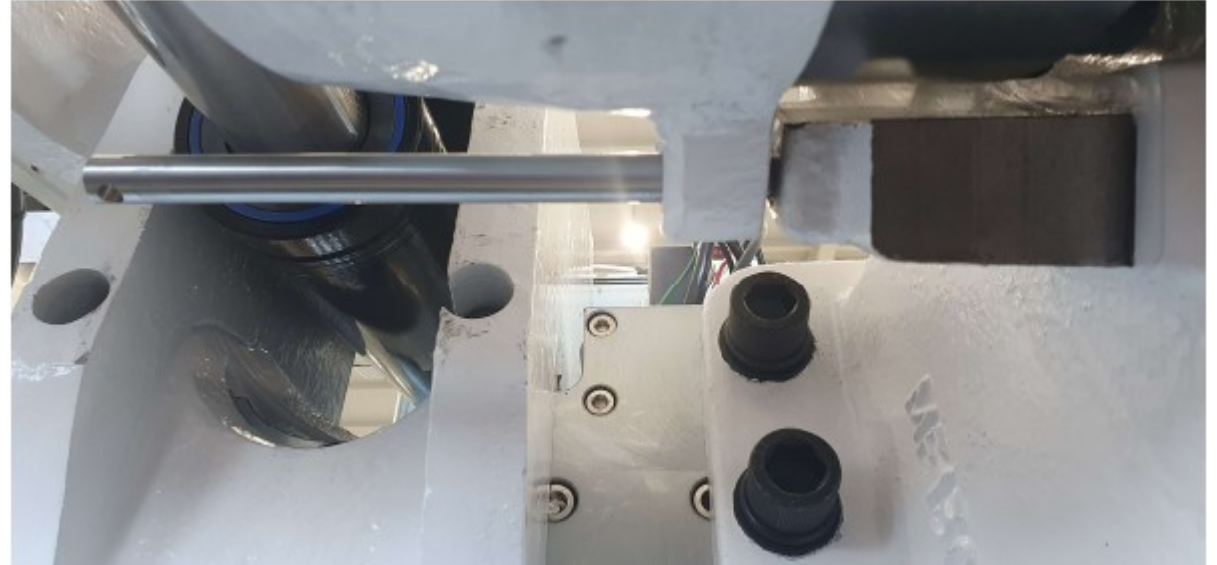
Zeroing EOAT

# Appendix B. J1 Zeroing position





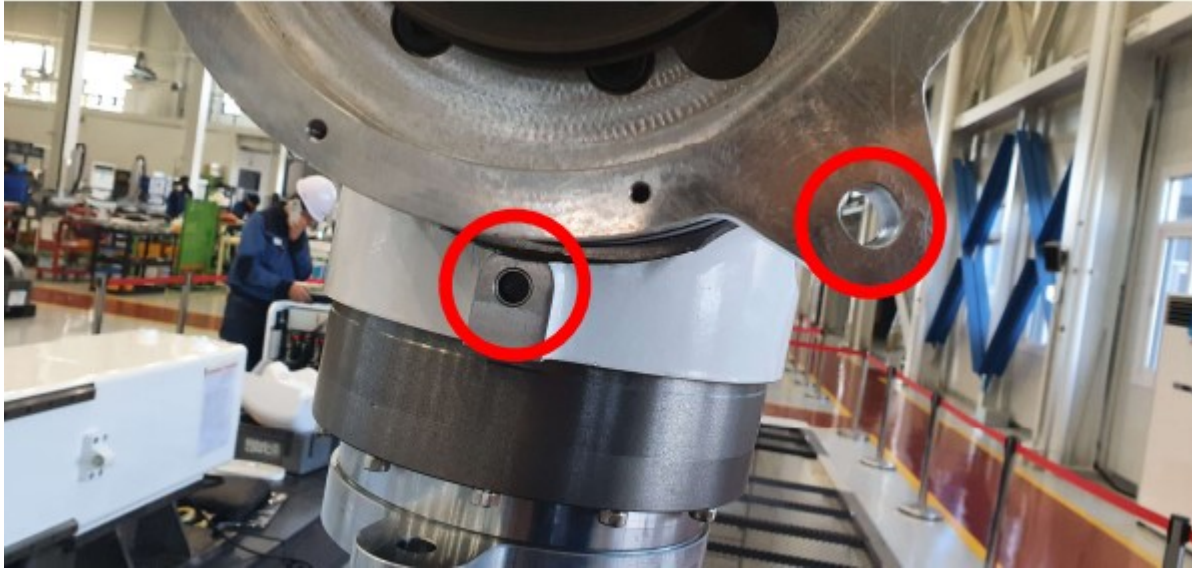
# Appendix B. J2 Zeroing position



# Appendix B. J3 Zeroing position



# Appendix B. J4 Zeroing position



# Appendix B. J5 Zeroing position

