
Mech-Mind User's Manual

Mech-Mind

Mar 07, 2023

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This section introduces the process of setting up master control of an Dobot robot.

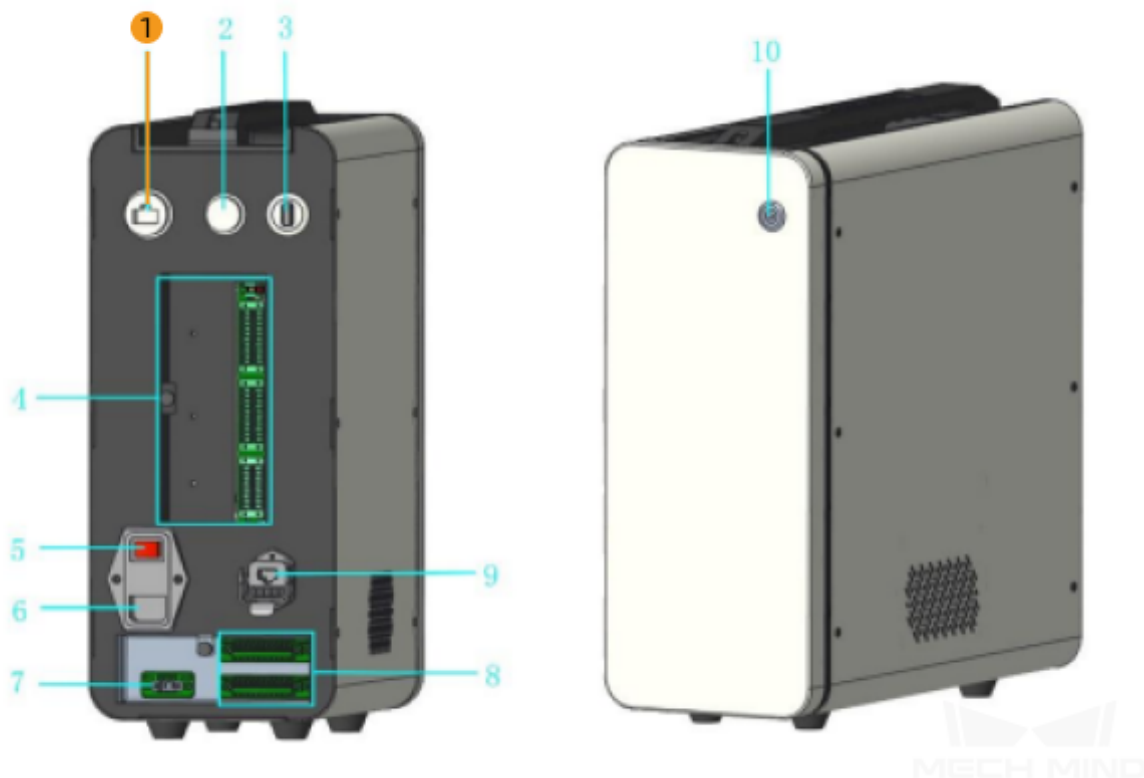
CHECK CONTROLLER AND SOFTWARE COMPATIBILITY

- Controller software version : 3.5.2 or above.
- Mech-Mind Software Suite: 1.6.0 or above.

SETUP THE NETWORK CONNECTION

2.1 Hardware Connection

Plug one end of the Ethernet cable into the network port of the IPC and the other end into the network port of the robot controller.

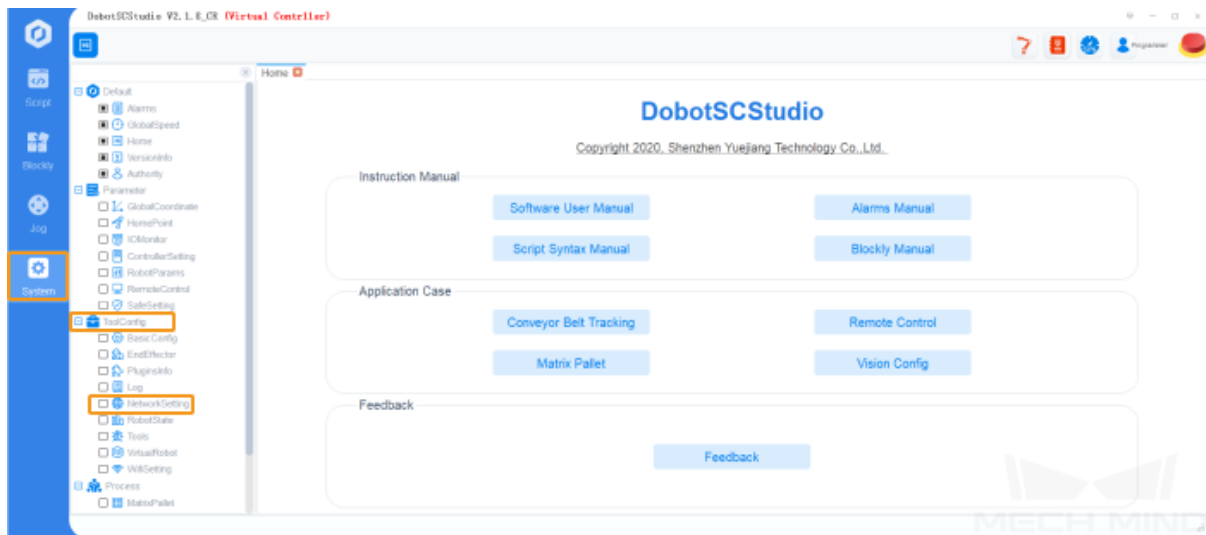


10 is the network port of the robot controller.

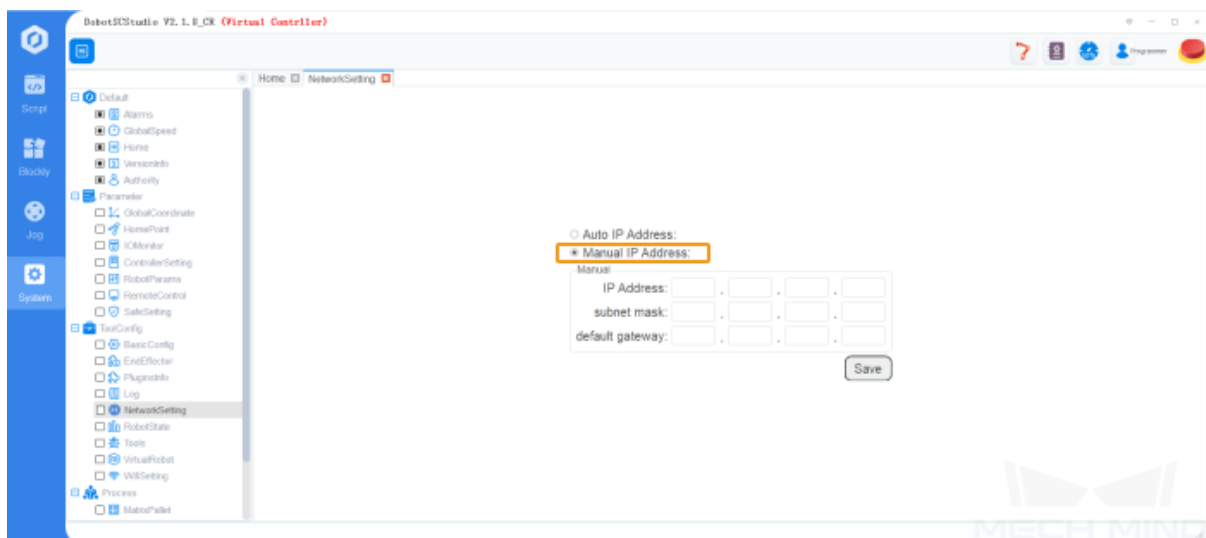
2.2 IP Configuration

To allow communication between the IPC and the robot controller, the IPC's network port connected to the robot controller should be in the same subnet as the robot. This means that the network portions and subnet masks of the IP addresses should be the same. For example, 192.168.100.1/255.255.255.0 and 192.168.100.2/255.255.255.0 are in the same subnet.

1. Please refer to `set_ipc_ip` to check the IP address of the corresponding port in the IPC.
2. Press **System** in DobotSCStudio and go to *ToolConfigure* → *NetworkSetting* .



3. If the IP address isn't in the same subnet as the IPC, select **Manual IP Address** and set the IP address manually, and click **Save** .



TEST ROBOT CONNECTION

CAUTIONS

1. Do not use Mech-Viz and DobotSCStudio at the same time. Otherwise Mech-Viz may not connect to the robot properly.
2. Do not use Mech-Viz when operating the teach pendant.
3. If you set the "Motion type" parameter to "Linear move" in Mech-Viz, the robot will get TCP. In this case, you must manually set TCP in the teach pendant and select it, then reconnect the robot. Otherwise the robot receives wrong poses.