

MELFA Technical News

September 2017

Subject: How to respond when C0152 "Robot arm serial number mismatch" error.**Applicable to: FR series**

Thank you for your continued support of Mitsubishi industrial robot MELFA series.
This Technical News explains the How to respond when C0152 "Robot arm serial number mismatch" error.

1. Model and part

FR series

2. Details of the Design Change

When the power is turned on, the robot controller (hereinafter referred to as RC) confirms the consistency between the robot main body serial number data stored in the RC and the robot arm serial number data connected to the RC, and if different, generates a C0152 error It is specification. This is because if you mistakenly connect a combination of RC and robot arm after parameter setting and program creation and launching as a production facility, it is executed with setting and program that are different from original, and in order to prevent damaging production equipment We are carrying out.

3. How to respond when C0152 "Robot arm serial number mismatch" error

Intentionally change the combination of RC and robot arm, if "C0152" error occurred, execute one of the methods [Attachment 1 - 3: Writing method of robot arm serial number data].

[Attachment-1: Writing method of robot arm serial number data with R32TB]

Please input the serial number of the robot arm into Parameter: RBSERIAL.
The serial number is printed to the rating name board on the back of the robot arm.

- 1) Press the [RESET] key of T/B and cancel the error of T/B.
- 2) Press the [EXE] key of T/B and display the menu panel.

```
MELFA CR800-D          Ver A1
RH-3FRH5515-D

COPYRIGHT (C) 2017 MITSUBISHI ELECTRIC CORPORATION ALL RIGHTS RESERVES
```



```
<MENU>
1. FILE/EDIT          2. RUN
3. PARAM.             4. ORIGIN/BRK
5. SET/INIT.         6. ENHANCED

123  CLOSE
```

- 3) Press the [3] key of T/B and display the parameter.

```
<MENU>
1. FILE/EDIT          2. RUN
3. PARAM.             4. ORIGIN/BRK
5. SET/INIT.         6. ENHANCED

123  CLOSE
```



```
<PARAMETER>  NAME ( _ )
ELE ( )

DATA
( )

DATA  Prev  123  Next  CLOSE
```

- 4) Input "RBSERIAL" into the name.

```
<PARAMETER>  NAME ( _ )
ELE ( )

DATA
( )

DATA  Prev  123  Next  CLOSE
```



```
<PARAMETER>  NAME (RBSERIAL_ )
ELE ( )

DATA
( )

DATA  Prev  123  Next  CLOSE
```

- 5) Press the function key ([F1]) corresponding to the "data", and input the serial number of the robot arm.

```
<PARAMETER>  NAME (RBSERIAL_ )
ELE ( )

DATA
(XXXXXXXXXX)

DATA  Prev  123  Next  CLOSE
```



```
<PARAMETER>  (RBSERIAL ) ( )

XXXXXXXXXX —

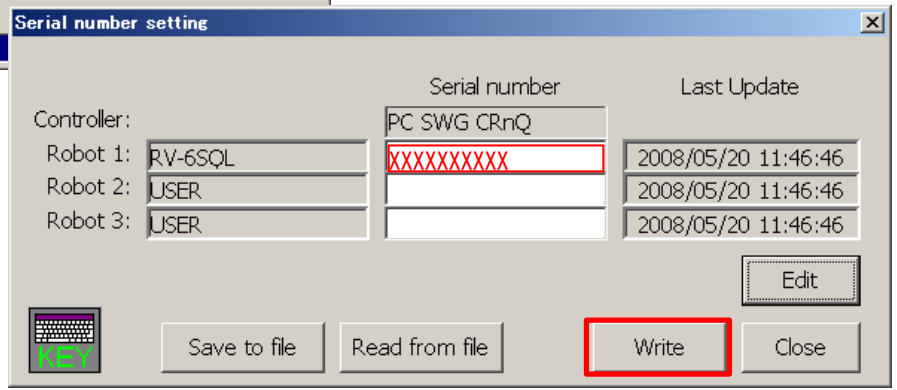
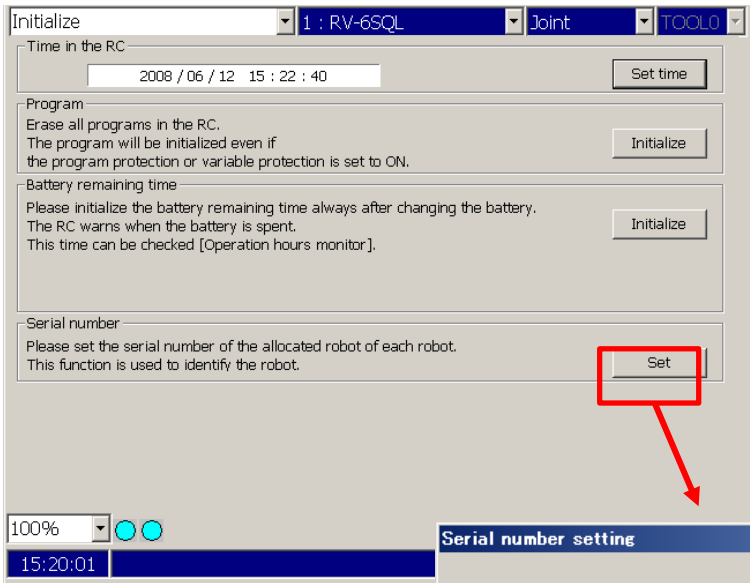
DATA  Prev  123  Next  CLOSE
```

The serial number recorded on the robot arm is displayed

Press the [EXE] key, the serial number as it is

Press the [EXE] key, and fix the value with sound, and return to the parameter screen.

[Attachment-2: Writing method of robot arm serial number data with R56TB]
For R56TB, please write from the initialization - serial number screen.



[Attachment-3: Writing method of robot arm serial number data with RT Toolbox3]
For RT Toolbox3, please write from the initialization - serial number screen.

