

# How to apply the default SICK configuration on MiR100 and MiR200

Date: 2022-06-10

Document version: 1.5

Valid for: MiR100 and MiR200

Valid for software version: All

Valid for hardware version: All

This article describes how to apply the factory default configuration to the SICK safety system used in MiR100 and MiR200.

## Things you'll need

- A PC with the SICK Flexi Soft Designer application. This can be downloaded from SICK's website.
- The correct project file for your robot. Below you will find a list of MiR hardware versions and their corresponding SICK configuration files. It is important that the correct file is used, or the robot will be locked in Protective stop until the correct file is applied.

Table 1.1. SICK configuration files for MiR100			
Original name	HW version	Configuration file	Flexi Soft Designer version
R0000 – R0353	1.0–1.8	<a href="#">MiR100-HW 1.0-1.8</a>	1.9.2 Sp1
R0354–R0599	1.9	<a href="#">MiR100-HW 1.9</a>	1.9.2 Sp1

Original name	HW version	Configuration file	Flexi Soft Designer version
R0600–R1080	2.0–2.2	<a href="#">MiR100-HW 2.0-2.1-2.2</a>	1.9.2 Sp1
R1081–R1335	3.0	<a href="#">MiR100-HW 3.0</a>	1.9.2 Sp1
R1336–R1499	4.0	<a href="#">MiR100-HW 4.0</a>	1.9.2 Sp1
R1530 and higher or MiR_ 201700001– MiR_ 201703999	5.0	<a href="#">MiR100-HW 5.0</a>	1.9.2 Sp1
MiR_ 201704000 and higher	6.0–7.0	<a href="#">MiR100-HW 6.0-7.0</a>	1.9.2 Sp1

**Table 1.2.**  
SICK configuration files for MiR200

Original name	HW version	Configuration file	Flexisoft Designer version
S0001–S0178	1.0	<a href="#">MiR100-HW 1.0</a>	1.9.2 Sp1
S0179–S0607	1.1–1.3	<a href="#">MiR100-HW 1.1-1.2-1.3</a>	1.9.2 Sp1
S0608–S0905	2.0	<a href="#">MiR100-HW 2.0</a>	1.9.2 Sp1
S0906–S1109	3.0	<a href="#">MiR100-HW 3.0</a> (version described in <i>SICK configuration file release note</i> )	1.9.2 Sp1

Original name	HW version	Configuration file	Flexisoft Designer version
S1110 and higher or MiR_ 201900001- MiR_ 201904999	5.0	<a href="#">MiR100-HW 5.0</a> (version described in <i>SICK configuration file release note</i> )	1.9.2 Sp1
MiR_ 201905000 and higher	6.0	<a href="#">MiR200-HW 6.0</a>	1.9.2 Sp1

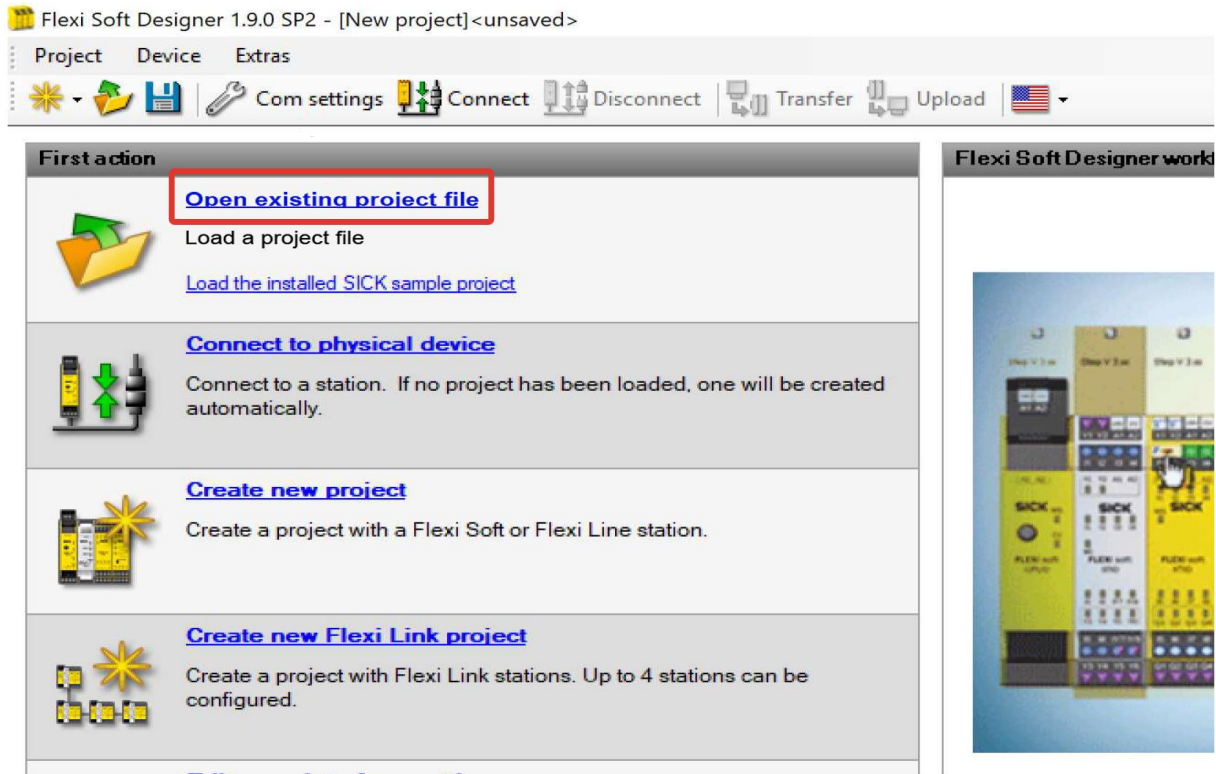
## Connecting to the robot

**Step 1: Turn on the robot you want to reconfigure, and connect to its WiFi access point.**

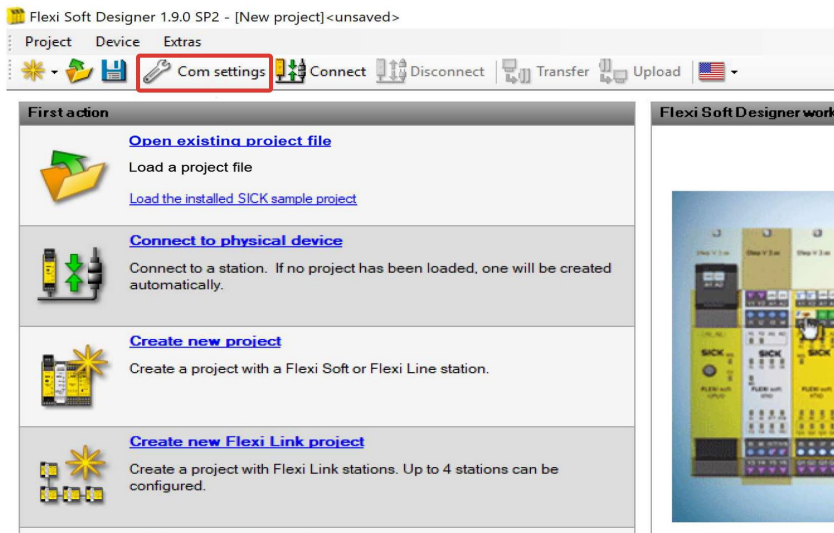
**Step 2: Launch Flexi Soft Designer.** Make sure you have Flexi Soft version 1.9.2 SP1.

**Step 3: Select [Open existing project file](#) and choose the file for the robot you want to configure.** Check that the file you've chosen is for the right robot and the right hardware version

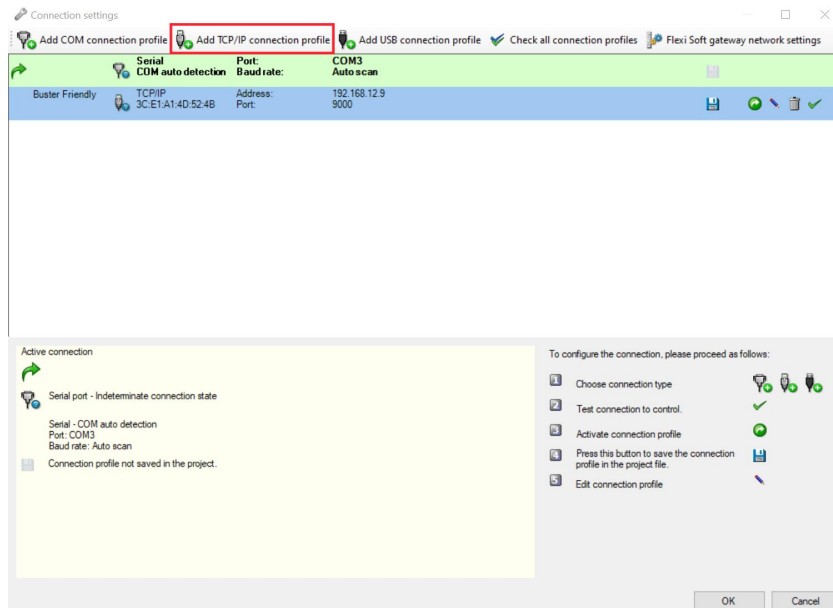
- If you apply the wrong file, the robot will enter Protective stop. You can release it by applying the correct file version
- Find your robot's hardware version on the identification label on the robot or in the Declaration of Conformity you received when you purchased the robot.



#### Step 4: Select **Com settings** to set up a connection to the robot.

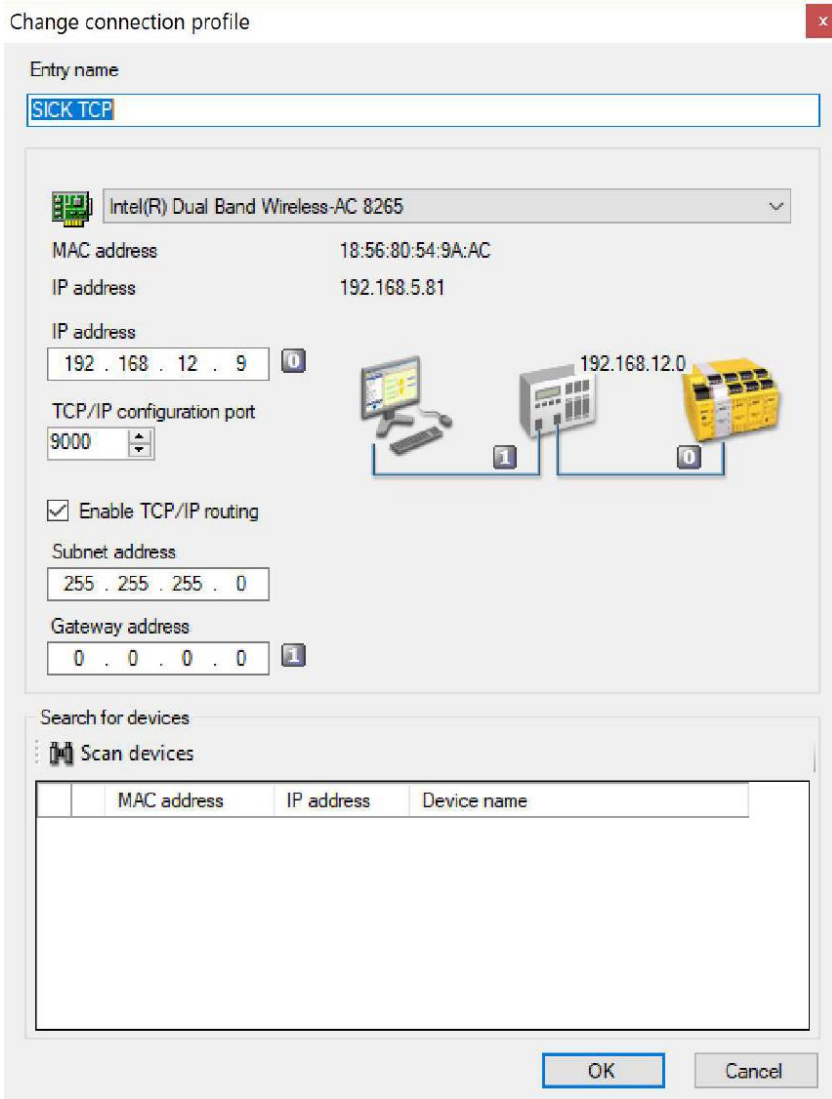


**Step 5: In the displayed window, select **Add TCP/IP connection profile**.**



**Step 6: Enter a profile name of your choice, and select your TCP/IP interface.** Set the parameters as follows:

- Choose your wireless network adapter from the drop-down menu. This must be the network used to connect to the robot.
- Enter the IP address: 192.168.12.9
- Enter the TCP/IP configuration port: 9000
- Check Enable TCP/IP routing
- Enter Subnet Address: 255.255.255.0
- Select **OK** to save the profile.



**Step 7: Select the green check mark on the right side of the newly-added connection profile to test the connection.**

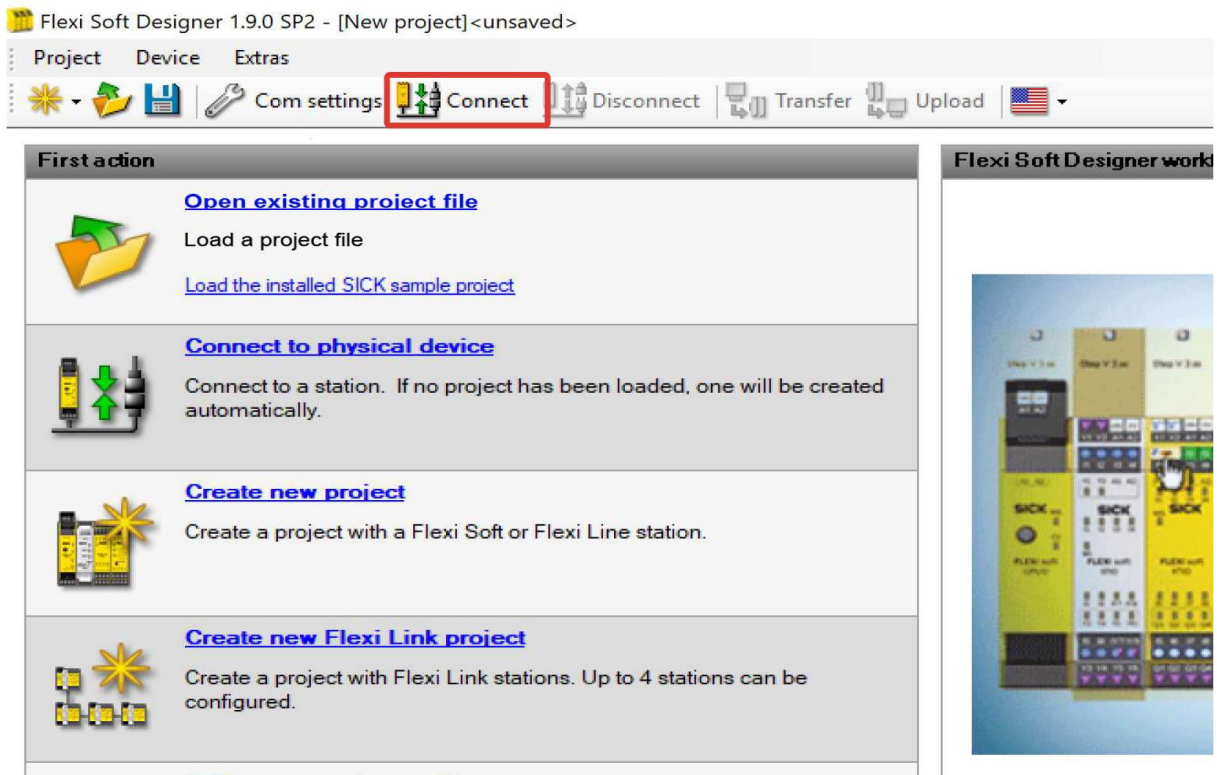


- If you see a green check mark next to the small connector icon, proceed to the next step.
- If you see a red or white X, select **Edit Connection** and make sure you chose the correct network adapter.
- If you are offline or the network is not appearing in the drop-down menu, connect an Ethernet cable to the top of the robot.
- If you are still having trouble connecting to the robot:
  - Right click the network icon in the system tray.
  - Select **Open network settings**.
  - Select **Wifi** in the sidebar and scroll down to **Change adapter options**.
  - Right click the WiFi adapter, and go to properties.
  - Uncheck **Internet Protocol Version 6 (TCP/IPv6)** and select **OK**.

**Step 8: Select the green arrow to activate the new profile.** Select **OK** once you have activated the profile.



## Step 9: In the main window, select **Connect**.



## Uploading the SICK configuration file

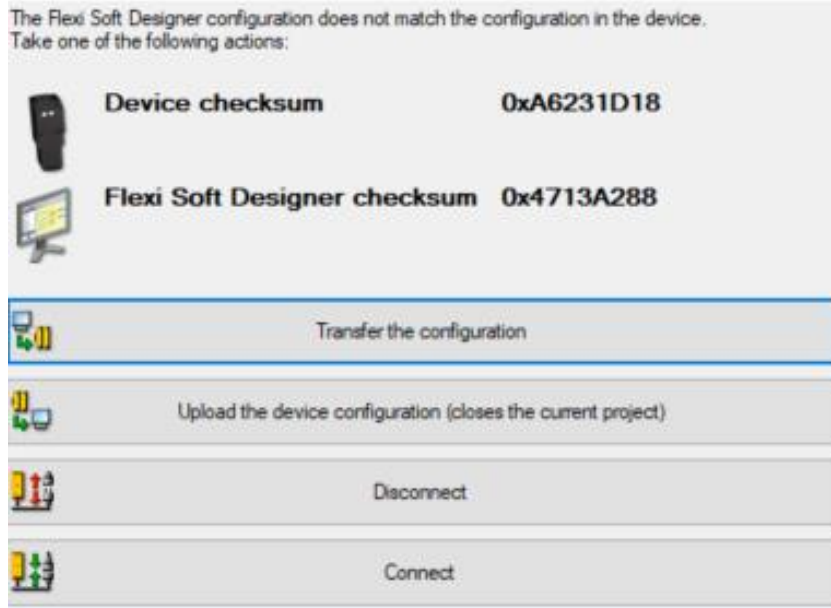
**Step 1: Select **Transfer the configuration** to transfer the project to the robot when the next pop-up appears.** This is a warning that the loaded project is not identical to the current device configuration.



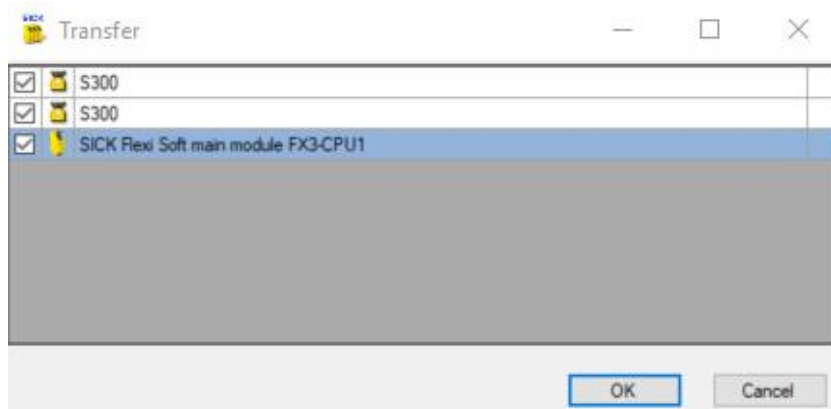
The warning might not appear if the loaded project and the current device configuration are similar. If the warning does not appear, manually start the transfer.



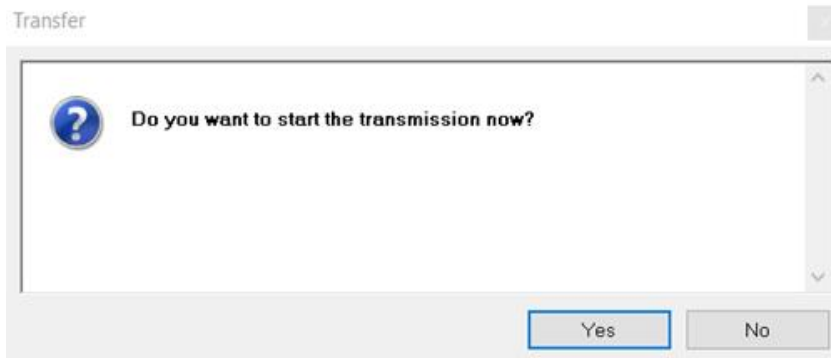
The configurations in Flexi Soft Designer and the device do not ... ✕



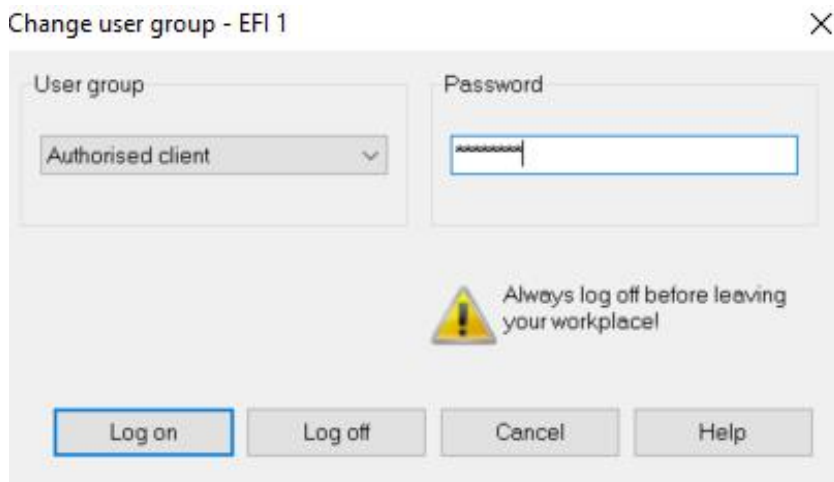
**Step 2: Select all the configurations when the transfer dialog appears.**  
Ensure all the boxes are checked, and select **OK**.



**Step 3: Select **Yes** when asked if you want to start the transmission.**



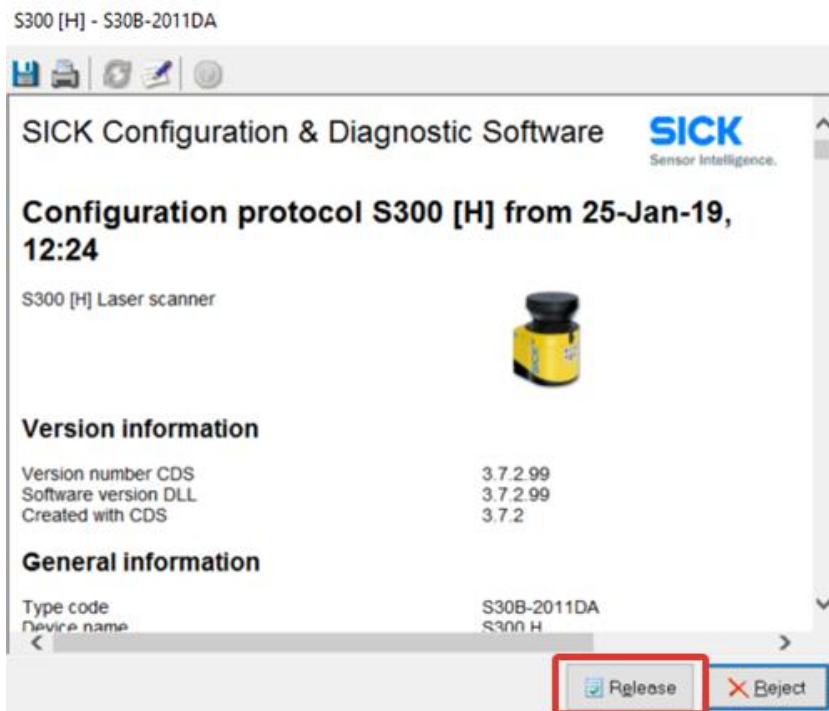
**Step 4: Under **User group**, select **Authorised client**, enter the **SICK safety system password**, and then select **Log on**.** If you have a robot with a 15-digit serial number, see SICK's documentation for the default password. If you have a robot with a nine-digit serial number, use the unique password for the SICK safety system you received with the robot.



**Step 5: Dismiss the warning that pops up by selecting **OK**.** If you are asked if you are sure you want to begin transmitting, select **YES**.

**Step 6: When the next dialog box appears, select **Release** to accept the report that Flexi Soft has created.** You can also save the report by clicking the save icon in the top left.

- Flexi Soft designer will create a safety report for each device configured that shows the changes that have been made to the safety zones.

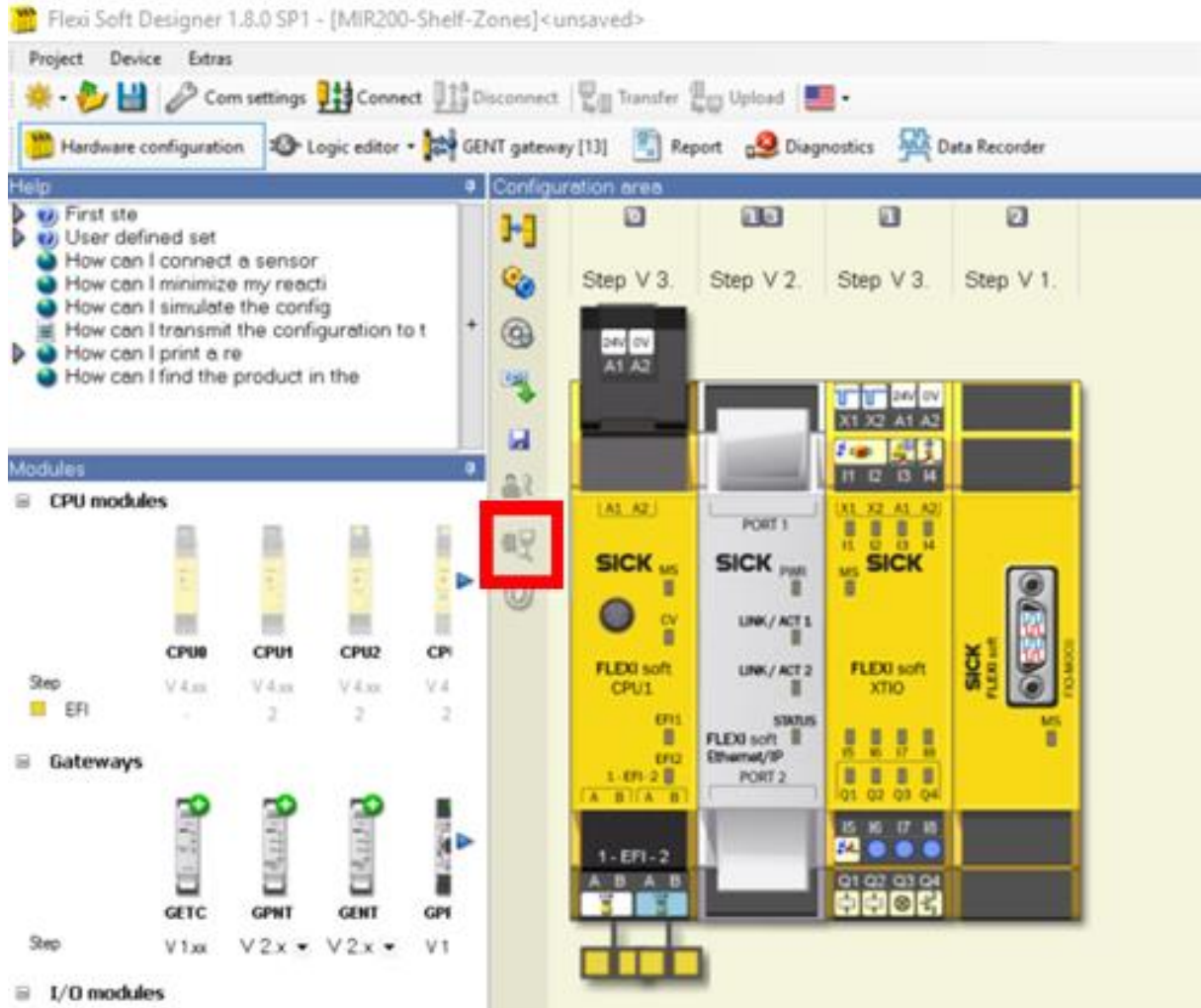


**Step 7: Select **OK** when the successful configuration window appears.** You will now go on to configure the other scanner and the safety PLC itself.

**Step 8: Repeat steps 3-7.** You must complete a transmission for each scanner and then for the safety PLC itself.

**Step 9: Select **YES** when asked if you want to download the configuration, and select **YES** if you are asked: **Do you want to run the head device?**** This may not occur every time, depending on the state of the SICK system.

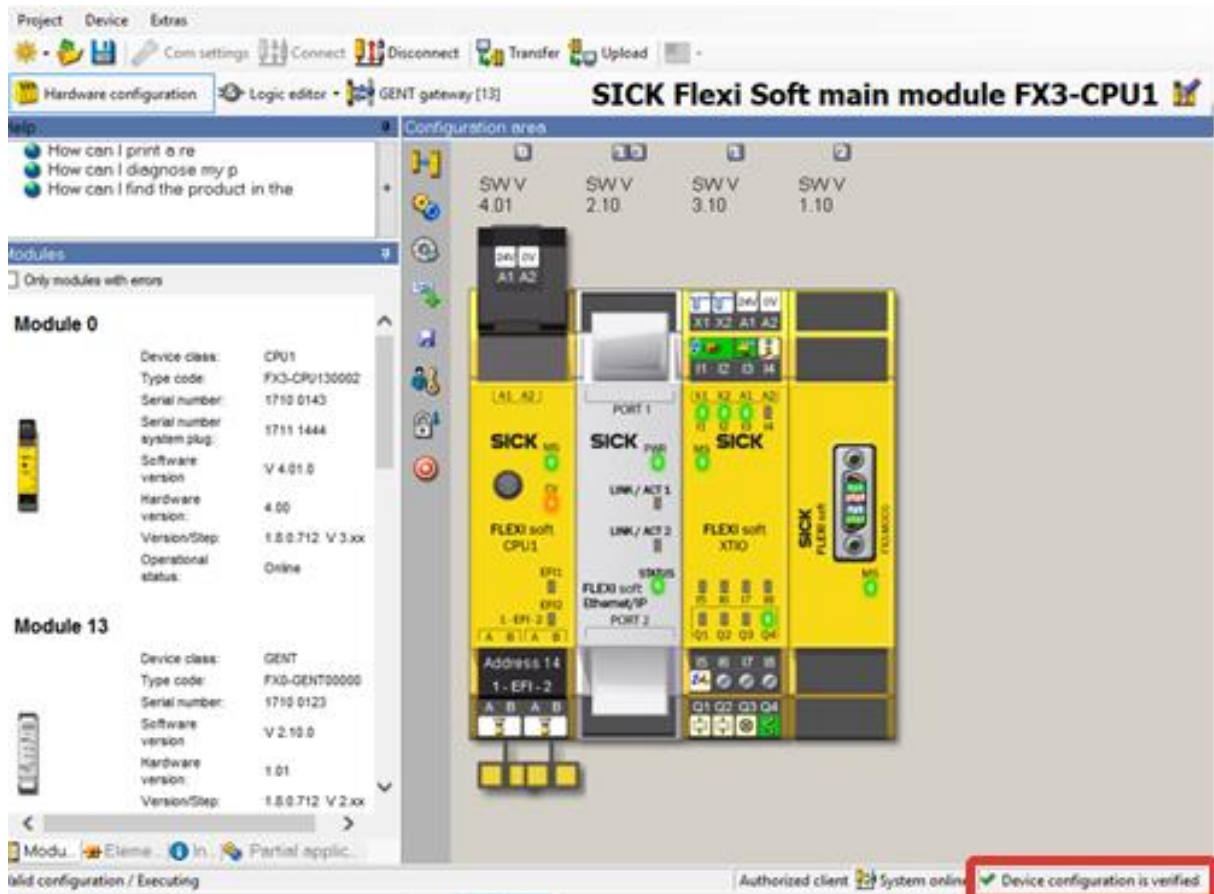
**Step 10: Select the blinking Verify configuration button.** You will need to do this before you can use the new configuration.



**Step 11: Select OK when prompted.** A pop-up asking to download passwords might appear. Uncheck everything and go on without doing this.

**Step 12: Select YES when asked Set device to verified?.**

**Step 13: Check that the system is online and the Device configuration is verified.** Look for confirmation at the bottom right of the screen.



**Step 14: Close the Flexi Soft window without saving changes.** Select **No** when prompted whether you want to save the current changes.

## Testing the new safety zones

It is important to perform a test to ensure the zones are switching correctly. To do this, power on the robot and test the safety features:

- Emergency stop. Test the Emergency stop button by pressing and releasing it. The robot's status lights should turn red when the button is pressed.
- Protective stop. Test the scanner safety zones by placing an object in front of the scanners and making sure the robot enters Protective stop (the status lights turns red).

## Document history

Version	Date	Description
1.5	2022-06-10	Added SICK configuration files for HW 6.0 and 7.0.
1.4	2021-05-03	Improvements throughout the guide.
1.3	2021-04-23	Added robots with 9-digit serial numbers to the overview table.
1.2	2020-09-02	Updated SICK password information. Small corrections throughout the guide.
1.0-1.1	2020-06-15	Undocumented changes.