

# Reference guide



## MiRFleet

en

Revision: 1.1  
Date: 2019/03



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CVR: 35251235



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# 1. About this document

This document describes the MiRFleet interface. The manual is intended for administrators of the system and users responsible for updating the system regularly, e.g. defining new missions or setting up new users in the system.

## 1.1. Where to find more information

At [www.mir-robots.com](http://www.mir-robots.com), the following extra resources are available. To access the pages in the Distributor site, sign in with your distributor account at <http://www.mobile-industrial-robots.com/en/account/>.

- Distributor site  
<http://www.mobile-industrial-robots.com/en/account/>  
This page contains various documents related to MiR products.
- Distributor site > How to  
<http://www.mobile-industrial-robots.com/en/account/how-to/>  
This page contains how-to articles that describe how to perform specific tasks.

## 1.2. Document history

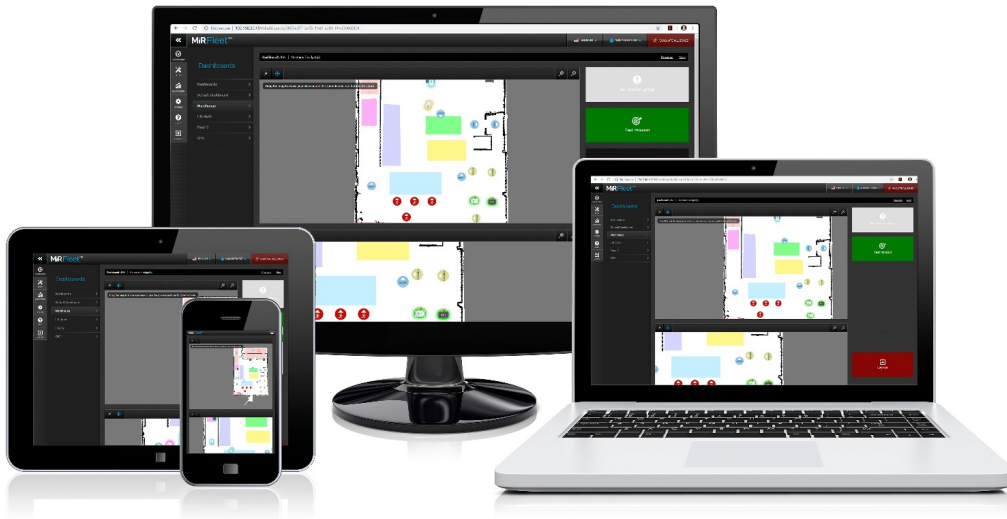
This table shows latest and previous versions of this document and their interrelations with product software releases.

Revision	Release date	Description	SW version
1.0	2019-01-17	First release	2.5.0
1.1	2019-03-06	Update to SW version 2.6.0. New features in the fleet interface: <ul style="list-style-type: none"><li>• Map zones have been reconstructed and new zone settings are available.</li><li>• Minor corrections and improvements throughout the manual.</li></ul>	2.6.0

## 2. MiRFleet interface

This section gives a quick overview of the MiRFleet interface.

The interface is responsive and automatically adapts to your use of smartphone, tablet or PC and also to the way you hold your tablet or smartphone in upright or portrait view.



### 2.1. Signing in

The interface comes with three default access levels:

- Distributor - the MiR distributor
- Administrator - the end-customer's production engineer with technical responsibility for the robot
- User - the daily operator(s) of the robot.

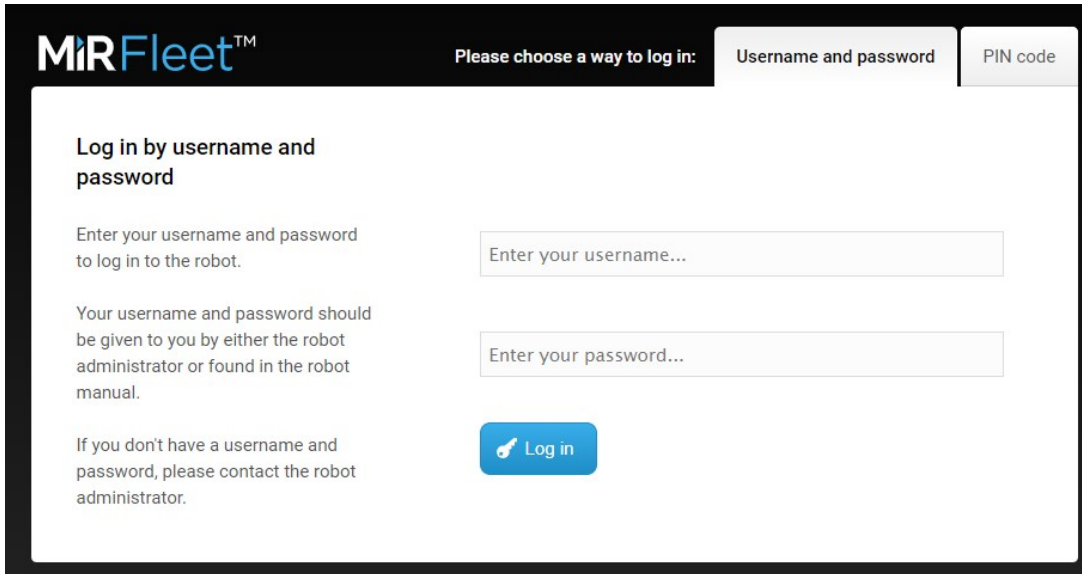
There are two ways in which you can sign in to the MiRFleet interface:

- Username and password
- PIN code

System permissions are handled per user group whereas login credentials are handled per individual user. Read more in Users and User groups.

## Username and password

Enter your username and password to sign in to the MiRFleet interface.



The screenshot shows the MiRFleet login interface. At the top left is the 'MiRFleet™' logo. To its right is a dark bar with the text 'Please choose a way to log in:'. Below this bar are two tabs: 'Username and password' (which is active) and 'PIN code'. The main content area is titled 'Log in by username and password'. It contains three paragraphs of text: 'Enter your username and password to log in to the robot.', 'Your username and password should be given to you by either the robot administrator or found in the robot manual.', and 'If you don't have a username and password, please contact the robot administrator.' To the right of the text are two input fields: 'Enter your username...' and 'Enter your password...'. Below these fields is a blue button with a key icon and the text 'Log in'.

## Default login credentials

The default usernames and passwords are:

### Distributor

- Username: Distributor
- Password: contact MiR Support

### Administrator

- Username: Admin
- Password: admin

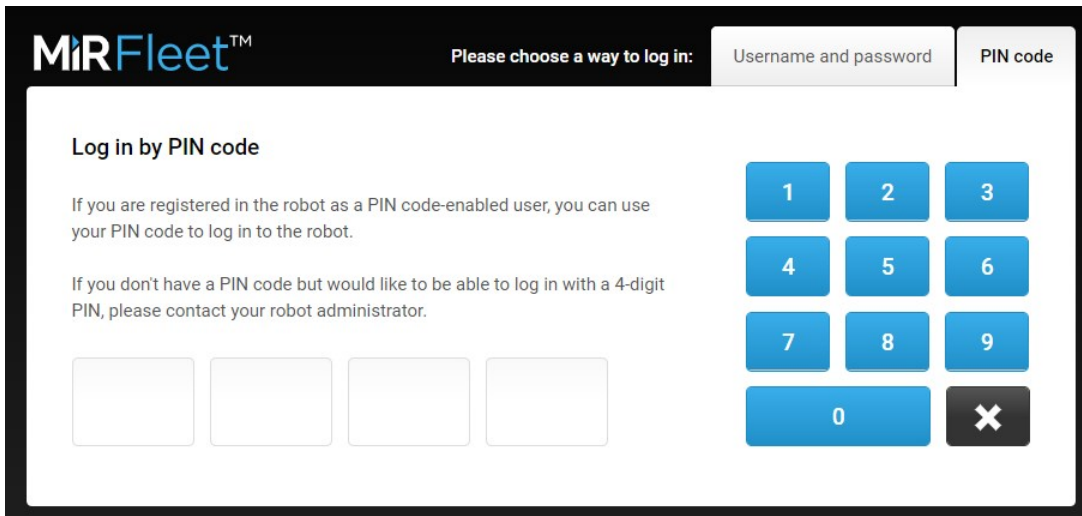
### User

- Username: User
- Password: user



## PIN code

Select the PIN code tab and enter a four-digit PIN code. There is no preconfigured PIN code.



**MiRFleet™** Please choose a way to log in: Username and password PIN code

**Log in by PIN code**

If you are registered in the robot as a PIN code-enabled user, you can use your PIN code to log in to the robot.

If you don't have a PIN code but would like to be able to log in with a 4-digit PIN, please contact your robot administrator.

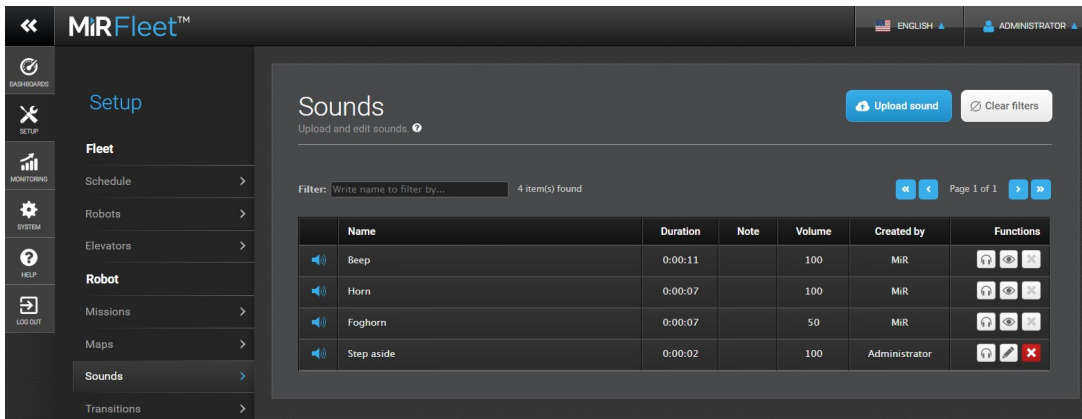
Four empty input boxes for the PIN code.

Numeric keypad with buttons 1-9, 0, and a delete button (X).

## 2.2. Navigating the MiRFleet interface

The MiRFleet interface has a straight-forward structure and an intuitive design. From the main menu, you never have to open more than one submenu to find the wanted section. When you click on a main menu, the related submenus appear, and with the next click, you access the wanted section.

For example, to go to the Sounds section, click on Setup on the main menu bar, then select Sounds on the submenu bar.



**MiRFleet™** ENGLISH ADMINISTRATOR

**Setup**

**Fleet**

- Schedule
- Robots
- Elevators

**Robot**

- Missions
- Maps
- Sounds**
- Transitions

**Sounds** Upload and edit sounds.

Upload sound Clear filters

Filter: Write name to filter by... 4 item(s) found

Name	Duration	Note	Volume	Created by	Functions
Beep	0:00:11		100	MiR	[Icons]
Horn	0:00:07		100	MiR	[Icons]
Foghorn	0:00:07		50	MiR	[Icons]
Step aside	0:00:02		100	Administrator	[Icons]

## 2.3. Getting started

The interface supports multi-level user access, and tailored dashboards make it easy for all users to have their daily functions at the fingertips.

### User setup

To get started, users must be set up in the system. This implies the following:

1. Set up users, see [Users on page 55](#).
2. Define user groups, see [User groups on page 57](#).
3. Create dashboards tailored to different users' tasks, see [Dashboards on page 10](#).

### System setup

One or more maps for the robot to navigate in and missions defining various robot tasks are the basics to get the robot up and running. Features added to maps such as positions and preferred drive zones, forbidden zones etc. make the robot move smoothly in the area.

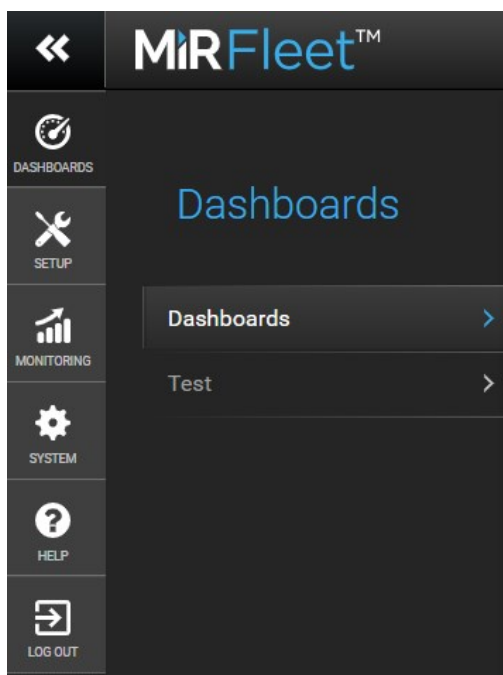
- Create a map, see [Maps on page 43](#).
- Edit the map: add positions, drive zones etc., see [Mapping tools on page 45](#).
- Create missions, see [Missions on page 21](#).

## 3. Dashboards

This section describes the items in the Dashboards menu.

The Dashboards submenu displays all Dashboards currently available on the robot.

In the Dashboards section, you can create new dashboards and edit the existing ones. Click on the Dashboards title to open the list of dashboards, and click the Create dashboard button to open the dashboard designer.



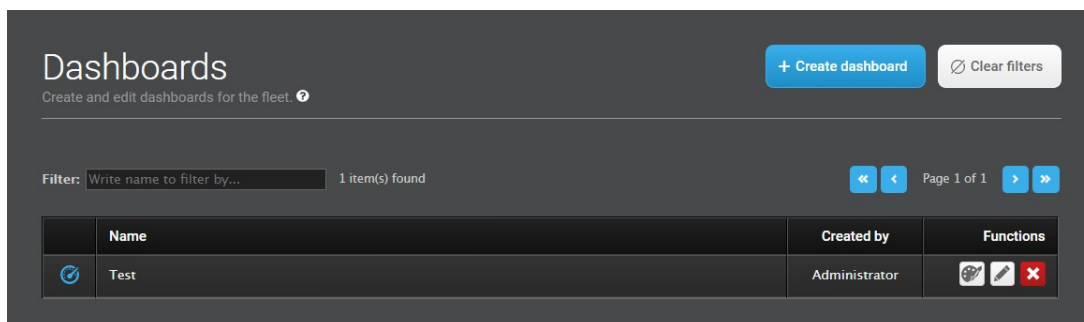
The Dashboards menu contains the following items:

<b>3.1. Dashboards</b>	<b>10</b>
<b>3.2. Widgets</b>	<b>12</b>

## 3.1. Dashboards

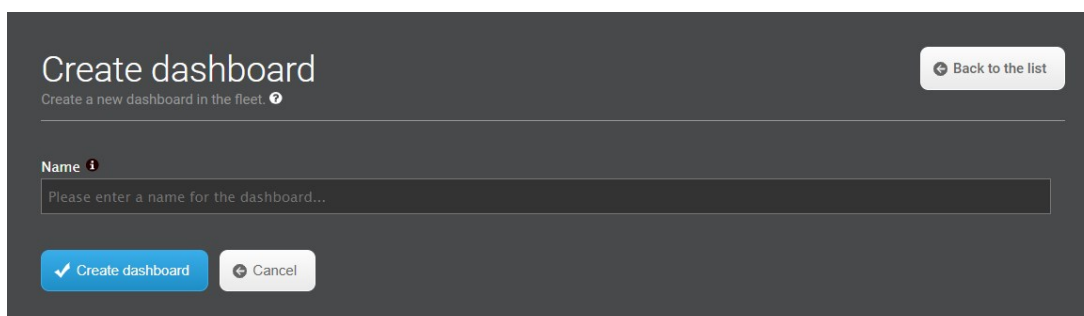
Dashboards are an easy way for different user groups to control the fleet giving direct access to their individual key functions. A dashboard is made up of a number of widgets each representing a feature in the system, e.g. a particular mission, the map the robots are running in or the current mission queue.

The system comes with a Default dashboard and, in addition, you may create an unlimited number of customized dashboards.



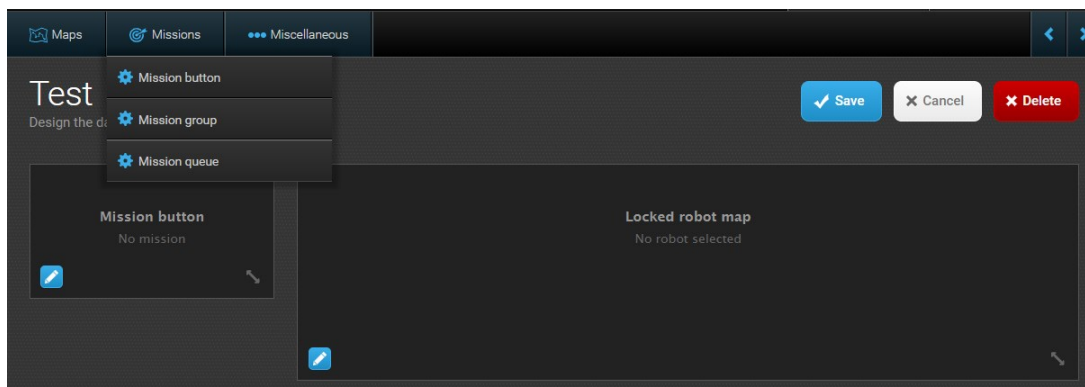
### 3.1.1. Create dashboard

To create a dashboard, first fill in the name field and then click the Permissions button to specify which user groups should have access to edit the dashboard. Continue to the Design section by clicking the Create dashboard button. Design the dashboard by adding widgets that represent the features you want to assign to the dashboard.



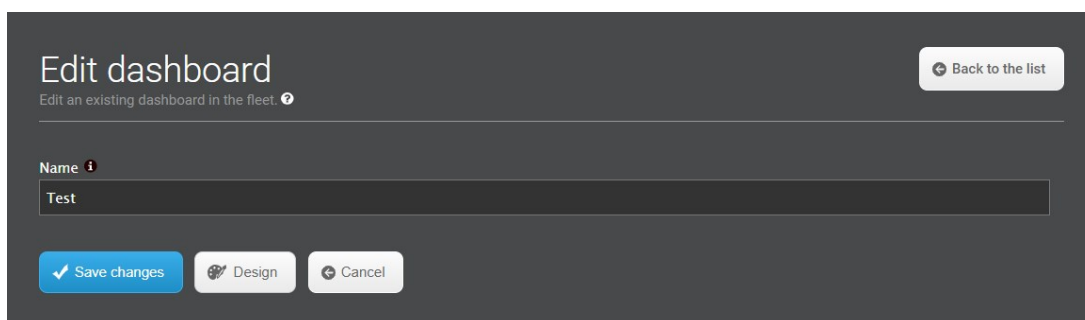
### 3.1.2. Dashboard designer

Design the dashboard by selecting widgets from the menus in the top bar of the user interface. Resize the widgets by pulling the arrow in the lower right-hand corner and rearrange their order by click-dragging. Some widgets require further settings, for example you must select a particular mission for mission buttons. To do this, click the pen icon in the lower left-hand corner and select the wanted action.



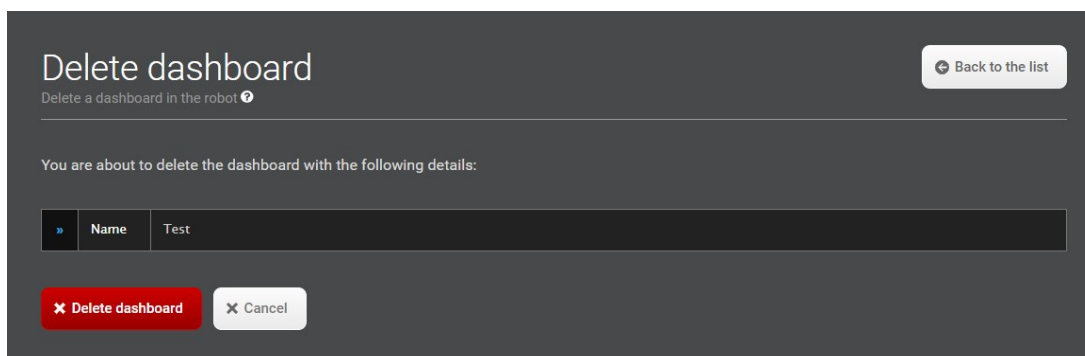
### 3.1.3. Edit dashboard

The dashboard design can be edited and widgets added or removed.



### 3.1.4. Delete dashboard

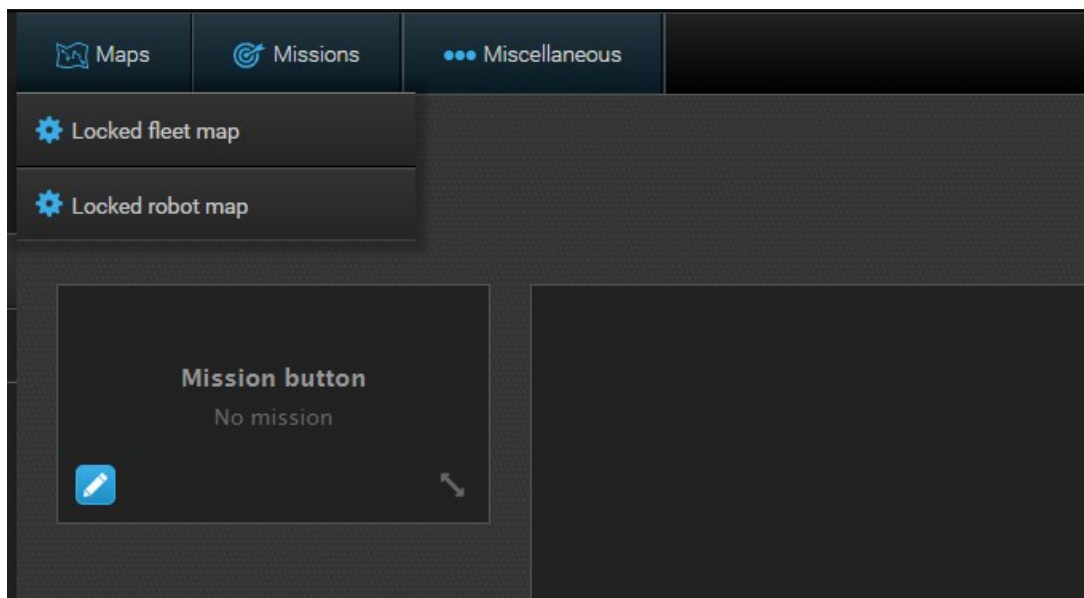
You can delete all dashboards that are created by you or another member of the user group you belong to.



## 3.2. Widgets

This section describes the dashboard widgets.

### 3.2.1. Maps



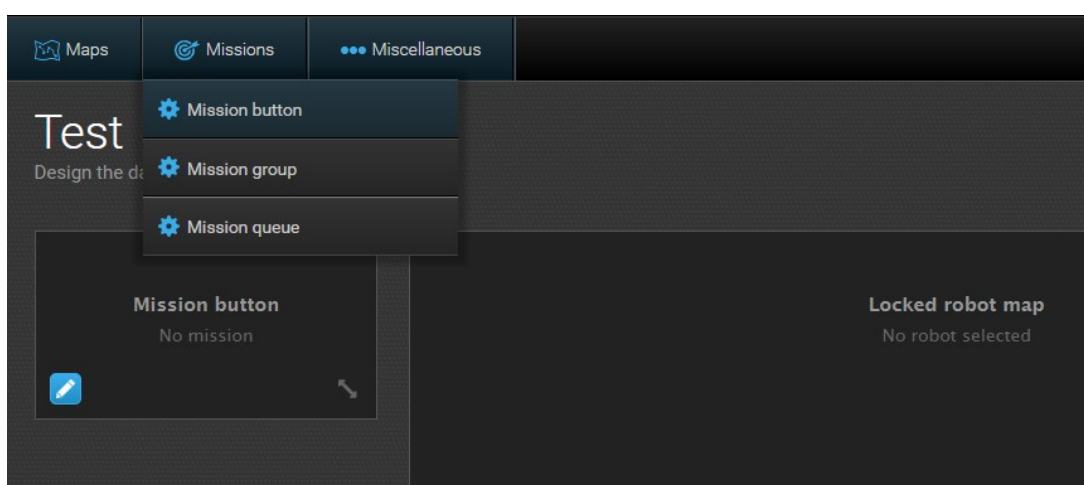
#### Locked fleet map

A locked fleet map widget makes the selected map visible on the dashboard. Select the map that should be used for the locked fleet map.

#### Locked robot map

A locked robot map widget makes the active map of the selected robot visible on the dashboard. The robot is always shown in the middle of a locked map. Select the robot you want shown on the dashboard.

### 3.2.2. Missions



### Mission button

You can start a mission from the dashboard by adding a Mission button wizard and selecting a predefined mission.

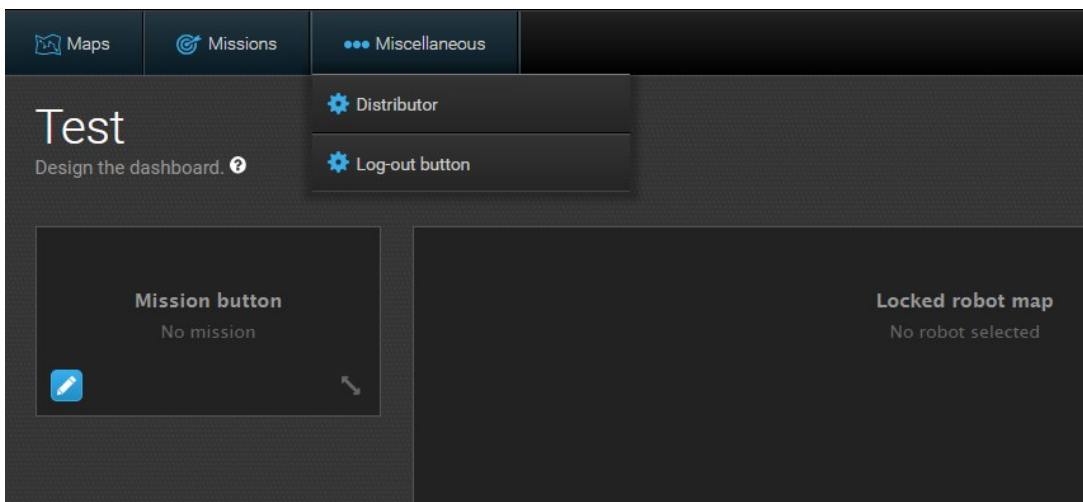
### Mission queue

You can have the mission queue displayed on the dashboard by selecting a Mission queue wizard.

### Mission group

You can select a mission group and have all missions from that group displayed on the dashboard by adding a Mission group wizard.

## 3.2.3. Miscellaneous



### Distributor

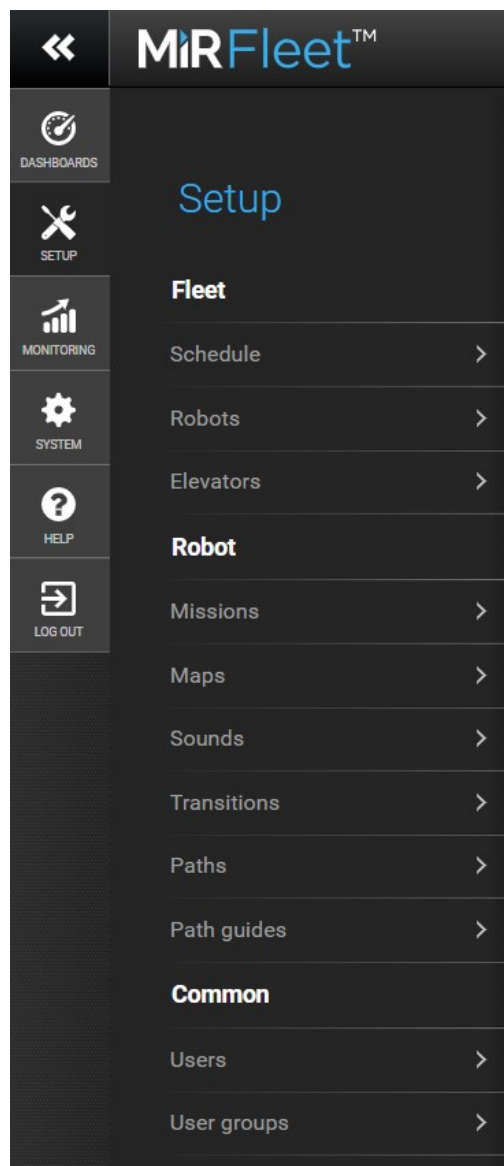
This widget shows information about the distributor if any distributor data has been entered in the Distributor data section under System > Settings.

### Log-out button

The log-out button allows you to log off via the dashboard. This is useful on small devices where there is no other log-out button.

## 4. Setup

This section describes the items in the Setup menu.



The Setup menu contains the following items:

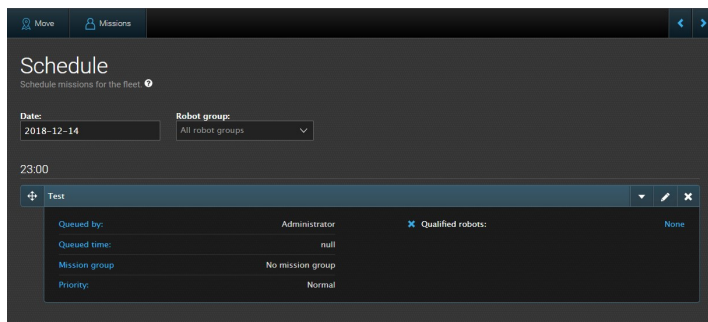
<b>4.1. Schedule</b>	<b>15</b>
<b>4.2. Robots</b>	<b>16</b>
<b>4.3. Elevators</b>	<b>19</b>
<b>4.4. Missions</b>	<b>21</b>
<b>4.5. Maps</b>	<b>43</b>
<b>4.6. Sounds</b>	<b>53</b>
<b>4.7. Transitions</b>	<b>53</b>
<b>4.8. Users</b>	<b>55</b>
<b>4.9. User groups</b>	<b>57</b>
<b>4.10. Paths</b>	<b>60</b>
<b>4.11. Path guides</b>	<b>60</b>



## 4.1. Schedule

Jobs to be carried out by MiRFleet robots can be arranged in Schedule. It is possible to schedule what robot group should carry out a job, date and time and priority.

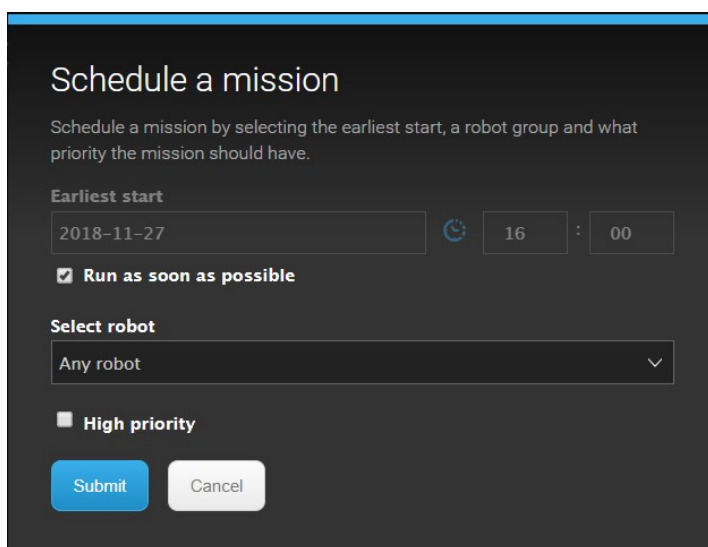
Missions and robot groups should be created before proper scheduling can be done. Go to Robot > Missions to create new missions or go to Fleet > Robots to create robot groups.



The screenshot shows the 'Schedule' window in the MiRFleet software. At the top, there are tabs for 'Move' and 'Missions'. The 'Schedule' title is followed by the subtitle 'Schedule missions for the fleet'. Below this, there are two input fields: 'Date' with the value '2018-12-14' and 'Robot group' with a dropdown menu showing 'All robot groups'. A time display shows '23:00'. Below the time display, there is a table with a header row containing a plus icon, the text 'Test', a dropdown arrow, an edit icon, and a close icon. The table has four columns: 'Queued by:', 'Queued time:', 'Mission group:', and 'Priority:'. The values in the table are: 'Administrator', 'null', 'No mission group', and 'Normal'. There is also a 'Qualified robots:' column with the value 'None'.

### 4.1.1. Schedule a mission

Schedule a mission by selecting the earliest start, a robot and what priority the mission should have. Run as soon as possible schedules the mission to the queue of missions. High priority schedules the mission to run as the first mission before all other scheduled missions.



The screenshot shows the 'Schedule a mission' dialog box. The title is 'Schedule a mission'. Below the title is the instruction: 'Schedule a mission by selecting the earliest start, a robot group and what priority the mission should have.' There are three sections: 'Earliest start' with a date input field showing '2018-11-27', a clock icon, and time input fields showing '16' and '00'; 'Run as soon as possible' with a checked checkbox; 'Select robot' with a dropdown menu showing 'Any robot'; and 'High priority' with an unchecked checkbox. At the bottom, there are two buttons: 'Submit' and 'Cancel'.

### 4.1.2. Edit schedule for mission

The screenshot shows a dark-themed dialog box titled "Edit schedule for mission". Below the title, it says "Edit: 2 -". There are three main sections: "Earliest start" with a date field set to "2018-12-14", a clock icon, and time fields set to "23" and "00"; a checkbox labeled "Run as soon as possible" which is currently unchecked; and "Select robot" with a dropdown menu showing "Any robot". At the bottom, there is a checkbox labeled "High priority" which is also unchecked, and two buttons: "Submit" and "Cancel".

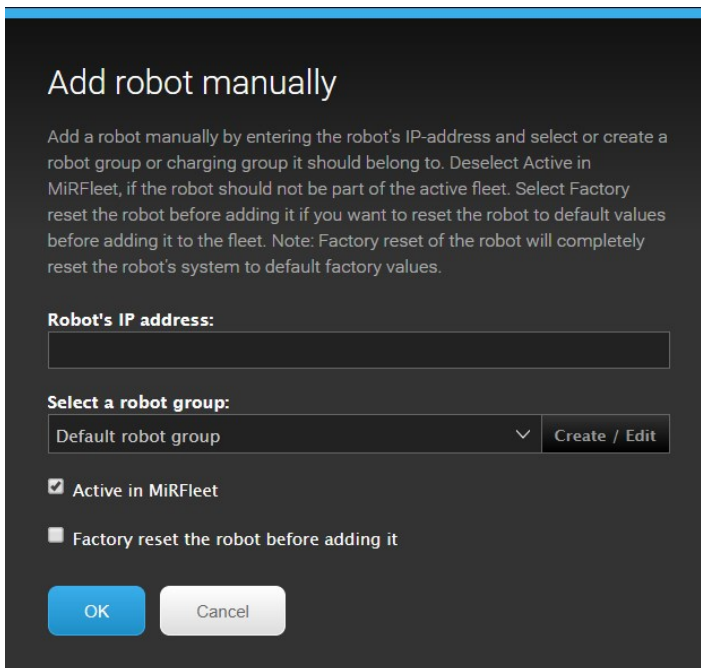
## 4.2. Robots

In the overview of robots, it is possible to add new robots to the fleet and arrange them in groups. To find robots for the fleet, you can scan for robots nearby or add a robot's IP-address manually. Robots that are found after a scan or added manually will appear under Available robots and are not an active part of the fleet yet. A robot that has not been added or has been removed from the fleet or a group has a red cross displayed in the top left corner. To add a robot to a group in the fleet, select the button Add robot to a group. A robot that is active and in a group in the fleet has a blue checkmark displayed in the top left corner. When the robots are added, it is possible to create robot or charging groups and arrange the robots in them. Select the button Show info to see details for the specific robot in the fleet.

The screenshot shows the "Robots" overview page. At the top, there's a header with the title "Robots" and a subtitle "Add and edit robots for the fleet. ⓘ". To the right of the header are four buttons: "Scan for robots" (with a Wi-Fi icon), "+ Add robot manually", "Scan ranges" (with a gear icon), and "Robot groups" (with a gear icon). Below the header, there's a section titled "New robots" which contains a card for robot "R717". This card has a red cross icon in the top left corner and displays the following information: Version: 2.4.0, IP address: 192.168.15.115, Model: MiR100, and a "+ Add robot" button. Below this, there's a section titled "Default robot group" which contains two cards. The first card is for a group named "mir" and has a blue checkmark icon in the top left corner. It displays: Version: ...te-2.4.0-948, IP address: 192.168.17.168, Model: MiR500, State: EmergencyStop, and Battery: 0%. The second card is for a group named "R2D2" and also has a blue checkmark icon. It displays: Version: ...te-2.4.0-948, IP address: 192.168.17.106, Model: MiR100, State: Pause, and Battery: 31%. Both cards in the "Default robot group" section have a "Show info" button at the bottom.

### 4.2.1. Add robot manually

Add a robot manually by entering the robot's IP-address and select or create a robot group or charging group it should belong to. Deselect Active in MiRFleet, if the robot should not be part of the active fleet. Select Factory reset the robot before adding it if you want to reset the robot to default values before adding it to the fleet. Note: Factory reset of the robot will completely reset the robot's system to default factory values.



The screenshot shows a dark-themed dialog box titled "Add robot manually". Inside, there is a paragraph of text explaining the process. Below the text, there is a label "Robot's IP address:" followed by a text input field. Underneath that is a label "Select a robot group:" followed by a dropdown menu showing "Default robot group" and a "Create / Edit" button. Below the dropdown are two checkboxes: "Active in MiRFleet" (checked) and "Factory reset the robot before adding it" (unchecked). At the bottom are two buttons: "OK" and "Cancel".

### 4.2.2. Scan for robots

Scan for robots is a fast way to add robots nearby to the fleet. It searches for the nearest robot WiFi addresses and adds them to the fleet.

### 4.2.3. Groups

Robots controlled by MiRFleet may be organized in different groups, e.g. MiRHook robots to do laundry transportation jobs and MiR100 robots to transport medicine. It is also possible to create charging groups. Charging groups can contain one or more charging stations, for example a group of stations for MiR100/MiR200 and another one for MiR500, or groups of charging stations located in the same area. Robots in the fleet may subsequently be assigned to a charging group ensuring that they go to a charging station in the selected group only. Robots that are not assigned to a charging group will be sent to any matching charging station that is not part of a charging group. No robot or charging groups will exist until they have been created in the Groups section.

#### Create robot or charging group

Create a group by selecting a name and choose if it should be a robot group or a charging group. If you create a robot group, deselect Allow all mission groups to select the specific mission groups the robot group is allowed to run.

## Create/Edit groups

Robots controlled by MiRFleet may be organized in different groups, e.g. MiRHook robots to do laundry transportation jobs and MiR100 robots to transport medicine. It is also possible to create charging groups. Charging groups can contain one or more charging stations, for example a group of stations for MiR100/MiR200 and another one for MiR500, or groups of charging stations located in the same area.

### Create/Edit groups

Default robot group

OK

## Edit group

Edit the name of the robot or charging group. Deselect Allow all mission groups to select the specific mission groups the robot group is allowed to run.

## Edit group

Edit the name of the robot or charging group. Deselect Allow all mission groups to select the specific mission groups the robot group is allowed to run.

**Name:**

Default robot group

☒ Allow all mission groups

Save changes Cancel

## Robot details

The robot settings allows you to see and edit the particular robot's details, fx name and robot group. You can also view statistics of the particular robot's performance in percentage, fx errors, idle time, charging and missions. You can also see the robot's map. Select Go to robot interface to open the particular robot's interface in a new tab.

## R2D2

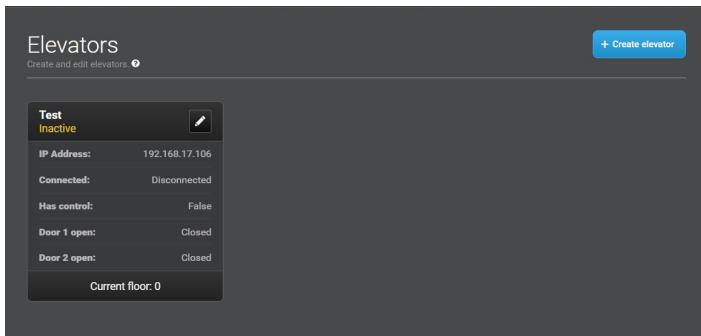
Details and settings for a robot in the fleet

[✓ Activate](#)
[✗ Delete robot](#)
[⚙ Go to robot interface](#)
[⏮ Go back](#)

Robot name	R2D2
IP address	192.168.17.106
Robot model	Unknown
Serial number	
Robot group	Default robot group
Groups	
Created by	Distributor

## 4.3. Elevators

In installations with an elevator, transitions from one map (floor) to another are handled automatically by MiRFleet. When an order is given to move to a position in a map representing a different floor, the fleet control takes over and brings the robot into the elevator and out again on the correct floor. MiRFleet then handles the map switch internally.



### 4.3.1. Create elevator

Setting up an elevator makes it possible for the robots in a fleet to travel between different floors in a building. The elevator information should be set up first and then several floors and commands can be set up after.

A screenshot of the 'Create elevator' dialog form. It has a title 'Create elevator' and a subtitle 'Create a new elevator'. There is a 'Go back' button. The form contains several fields: 'Name' with a placeholder 'Enter name', 'IP address' with a placeholder 'Enter ip', 'Turn in place' with a dropdown menu set to 'Yes', and 'Active' with a dropdown menu set to 'Yes'. At the bottom, there is a blue button with a checkmark and the text 'Create elevator'.

The **Create elevator** dialog has the following fields:

- **Name**  
Enter a name for the elevator
- **IP address**  
Enter a valid IP address for the elevator. The IP address is provided by the elevator system integrator.
- **Turn in place**  
Select whether or not the robot is allowed to turn in the elevator. Turning in the elevator might be relevant if the robot enters and exits the same elevator door and it must face front in both instances.
- **Active**  
Select whether or not the elevator should be actively used in the fleet.

### 4.3.2. Edit elevator

In Edit elevator you can change the settings of an elevator. Any of the settings can be changed. Select Add floor to add a floor with details.

**Edit elevator**  
Edit an existing elevator

**Name**  
Elevator

**IP address**  
192.168.30.21

**Turn in place**  
No

**Active**  
Yes

Floor	Map	Position In The El...	Position In Front ...	Entry Mission	Exit Mission	Door
1						

+ Add floor

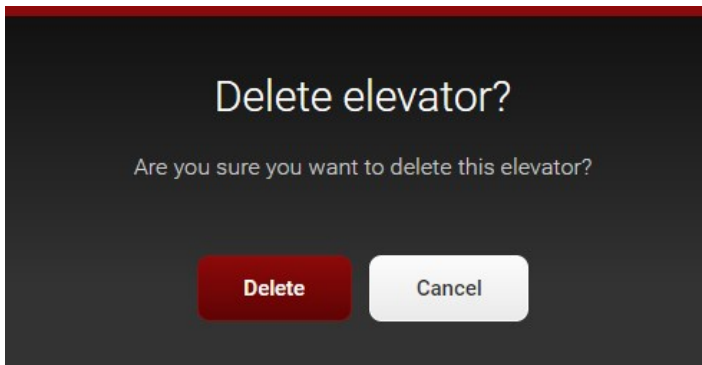
Update elevator

The **Edit elevator** dialog has the following fields:

- **Floor**  
Enter the specific floor number. Floor designations must be numbers, which means that for example Ground floor could be represented by 0, Basement by -1 etc.
- **Map**  
Select the map, e.g. "Ground floor". The map must have been created in the robot's web interface and include two elevator positions that will enable the switching from one map to another.
- **Position in the elevator**  
Select the robot position representing the robot inside the elevator. The position must have been defined in the robot's web interface.
- **Position in front of the elevator**  
Select the robot position representing the robot outside the elevator. This is the position the robot goes to while waiting for the elevator to arrive and the doors to open. The position must have been defined in the robot's web interface.
- **Entry mission**  
Select the entry mission
- **Exit mission**  
Select the exit mission
- **Door**  
Select one or two doors depending on the number of doors inside the elevator and which one(s) the robot should use.
  1. The robot makes a 180° turn inside the elevator and leaves through the same door it entered.
  2. The robot does not turn and leaves through the door opposite the entry door.

### 4.3.3. Delete elevator

Delete an elevator by pressing the Delete button in the Edit elevator section.



## 4.4. Missions

A mission is a predefined series of actions that the robot can be set to perform by the click of a button. A mission can be a simple transportation task between defined positions or a more complex job that includes both moving between positions and performing actions, such as opening an automatic door via Bluetooth signal, sounding a horn or sending an email on arrival at a position.

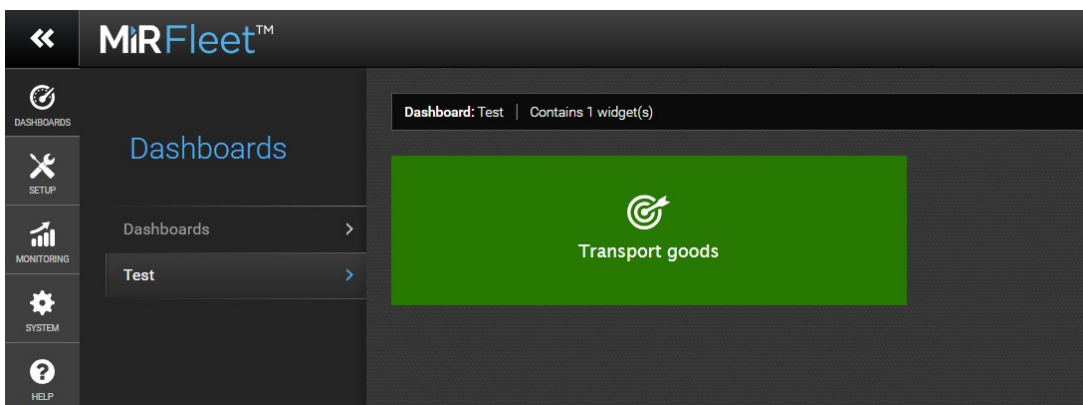
Missions are started easily by adding a given mission to the mission queue. The robot will perform the missions in the order they are added, and an operator may rearrange the queued missions if needed.

### 4.4.1. Start mission

You can start a mission in one of the following ways.

#### From a dashboard

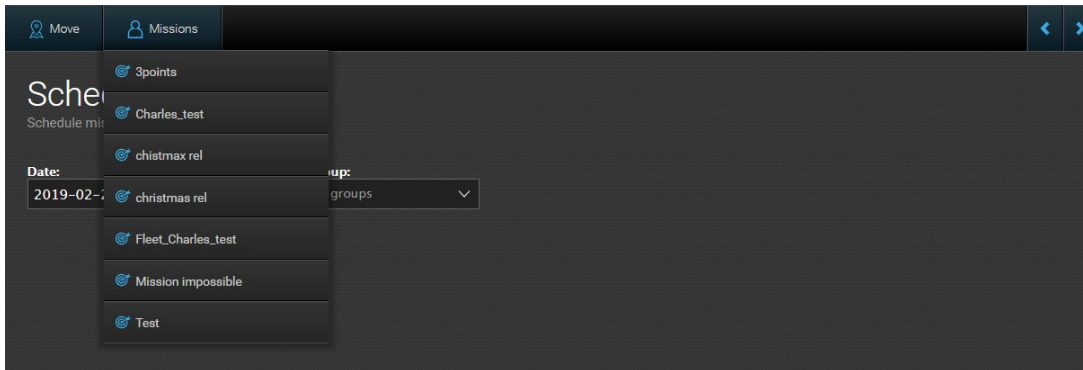
You can configure a Mission button widget on a dashboard.



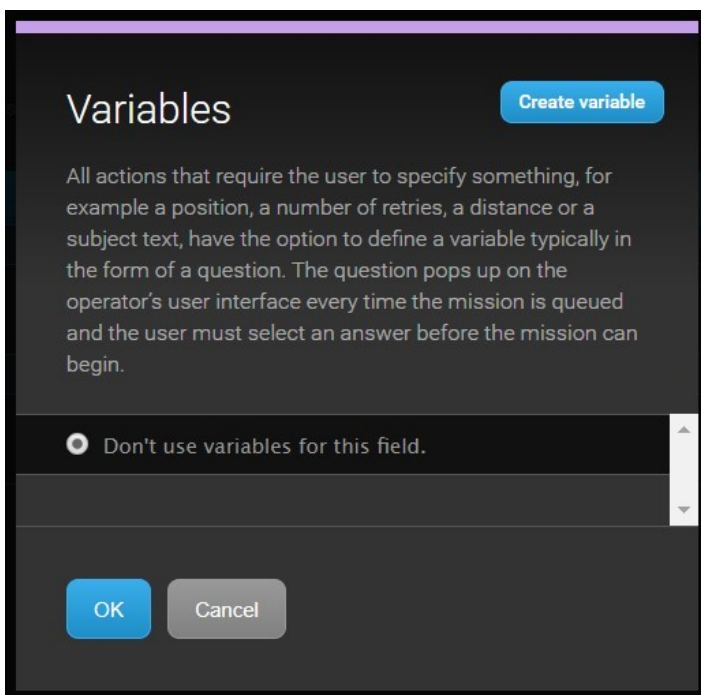
## From the Schedule menu

To start a mission:

- Go to: Setup > Schedule.
- Click Missions to schedule and run a mission.



If there are variable parameters in a mission, for example a variable position, you will be asked to select the position when adding the mission to the queue.



The selected parameters are shown in blue text.



### 4.4.2. Create mission

A mission is made up of actions such as: Move actions, logic actions, cart pick-up/delivery and sounds which can be put together as building blocks to form as many different missions as needed. Most actions have parameters to fill in, for example which position to go to. Instead of setting a fixed position, it is possible also to put in a variable position which means that the operator is asked which position the robot should go to every time the mission is added to the queue. This may be practical, for example if the robot should perform the same series of actions in different areas of the facility, e.g. picking up something from one place and delivering it to another.

Actions are grouped, and you can select which group the new mission should belong to or use the default Missions group.

The form contains the following elements:

- **Name**

The name must be unique and is used to identify the mission.

One way of naming missions is to select names that characterize the task that the robot should perform, e.g. “Go to charging station” or “Deliver spare parts”. Another way to name a mission would be to include “from” and “to” positions in the name, e.g. “Warehouse to production line 1”.

- **Mission group**

Select which group you want the mission be placed in.

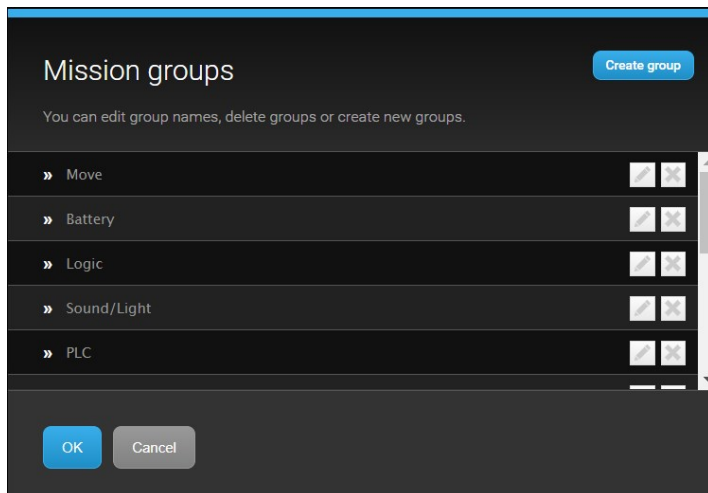
- **Site**

If more than one site exists, select which site you want the mission belong to from the list.

Click **Create mission** to save the settings.

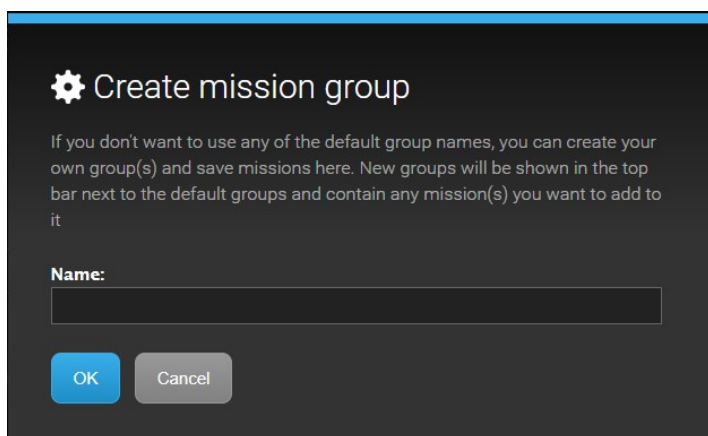
## Mission groups

Each group has a number of pre-defined actions that can be selected when you build the mission; one mission can contain actions from several groups. When you save the new mission, it will be placed in the selected group and can be used as an embedded mission of other missions.



## Create mission group

If you don't want to use any of the default group names, you can create your own group(s) and save missions here. New groups will be shown in the top bar next to the default groups and contain any mission(s) you want to add to it



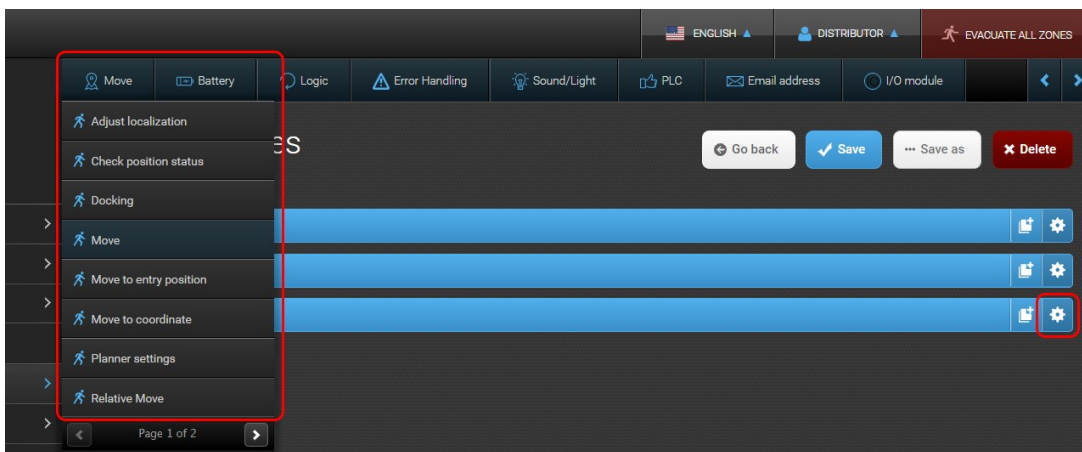
### 4.4.3. Mission editor

A mission is built from actions that you pick from the menus in the top bar. You can also pick already created missions and embed them in new missions. The idea is that such missions, typically limited to a specific purpose, for example to go to a charging station, can be shared among several larger missions that require the same behavior as part of the mission.

Actions and missions are grouped together in the top bar menus: All predefined actions are identified by a running-man icon. User created missions are placed together with actions in the group to which you append them and can be distinguished from actions by a target icon next to their names.

When you have picked the actions you want to build the mission from, you have a number of options:

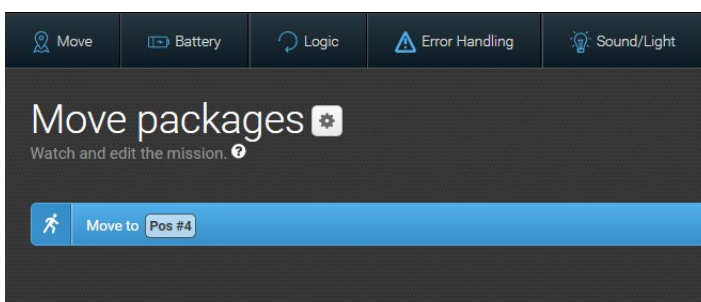
1. Drag the actions up or down with the four-headed arrow at the far left of the action line to sort them in the desired order. The actions are executed in a top-to-bottom order.
2. Set the parameters for the selected action by clicking the gear icon at the far right of the action line.



#### 4.4.3.1. Change mission settings

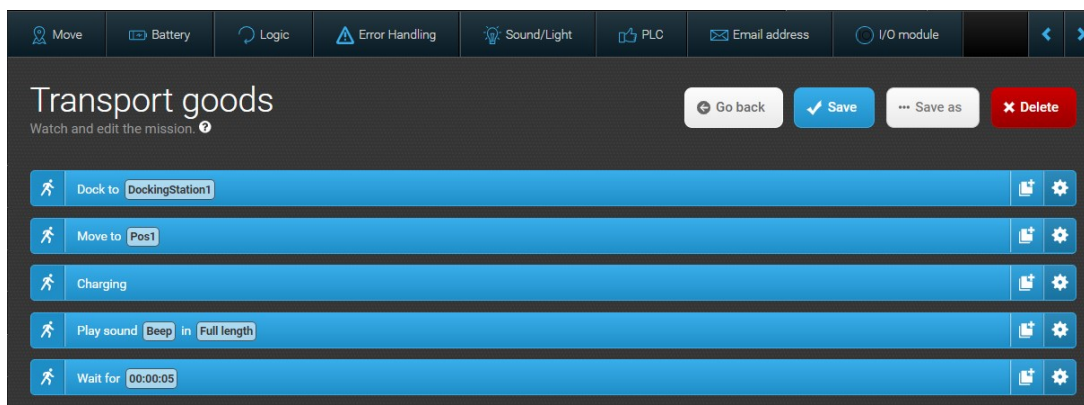
The name of the mission and the group it belongs to may be changed.

In the Mission editor window, move the mouse over the name of the mission and click on the gearwheel that appears.



#### 4.4.3.2. Save mission

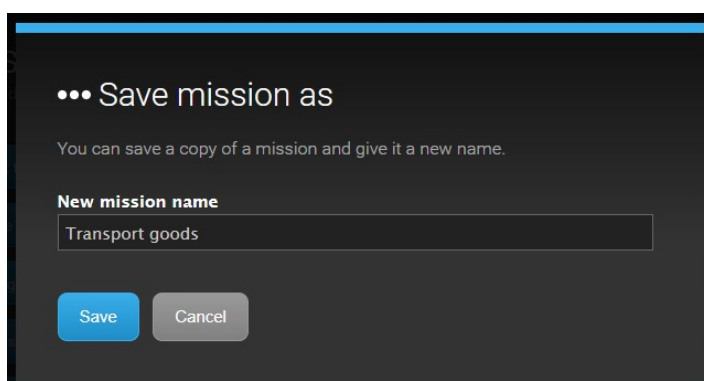
When you have completed the missions; i.e. added all actions and sorted them in the wanted order, click **Save** to save the mission.



#### 4.4.3.3. Save mission as

You can save a copy of a mission and give it a new name. That way it is easy to create a new mission based on the settings of an existing one.

In the Mission editor window, select **Save as**.



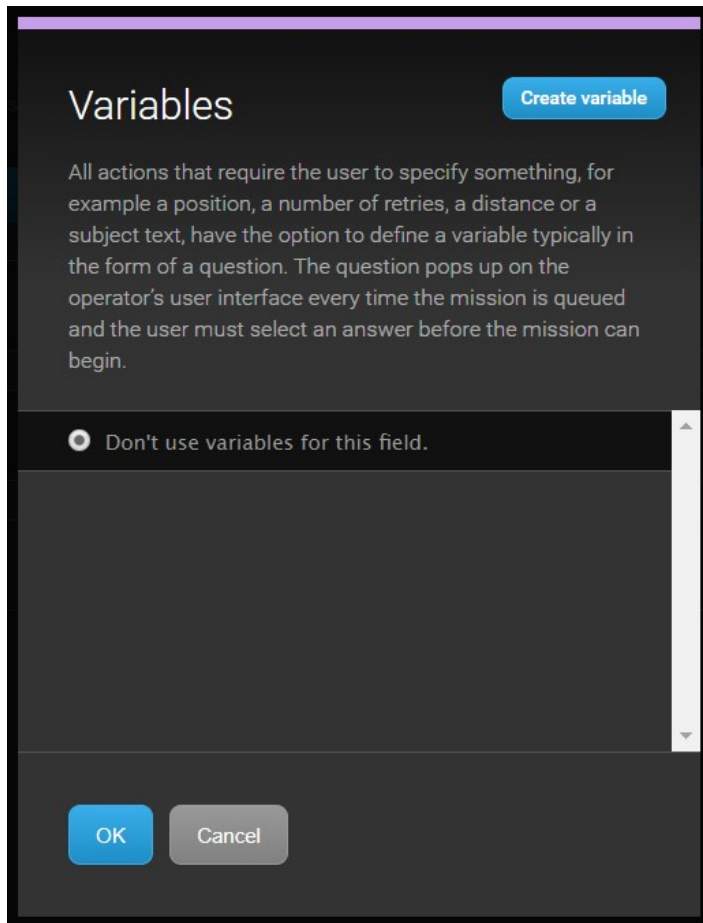
#### 4.4.4. Mission actions

Actions used in missions are in the Groups tool bar at the top of the window.



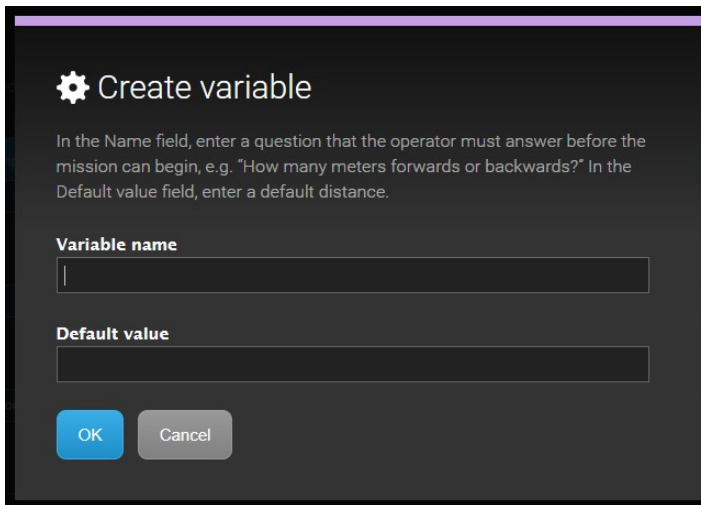
#### 4.4.4.1. Variables

All actions that require the user to specify something, for example a position, a number of retries, a distance or a subject text, have the option to define a variable typically in the form of a question. The question pops up on the operator's user interface every time the mission is queued and the user must select an answer before the mission can begin.



#### 4.4.4.2. Create variables

In the Name field, enter a question that the operator must answer before the mission can begin, e.g. "How many meters forwards or backwards?" In the Default value field, enter a default distance.



**Create variable**

In the Name field, enter a question that the operator must answer before the mission can begin, e.g. "How many meters forwards or backwards?" In the Default value field, enter a default distance.

**Variable name**

**Default value**

OK Cancel

#### 4.4.4.3. Move

This group contains the following actions.

##### Adjust localization

An Adjust localization action adjusts the robot to the correct position in the map, for example if it has to move through an area with many dynamic obstacles where the localization is likely to drift.

##### Check position status

Positions of the following types can have states **free** or **occupied**:

- Robot position.
- Cart position.
- Shelf position.
- Pallet rack position.
- Staging position.

This action checks the state of the position for a given time. If the condition in the action is satisfied, the robot continues executing the mission. Otherwise the robot raises the error.

Example: Use this action for the following purposes:

- Check whether the load is on the pallet rack before docking to the rack.
- Check whether the cart is in position before picking it up with the hook.
- Check whether the target position is free.

##### Available fields:

###### Position

Select a position from the drop-down list, or select the XYZ icon to define a variable.

**Option**

Choose between checking for a position being empty or a occupied, or select the XYZ icon to define a variable

**Timeout (seconds)**

Enter the maximum time during which the robot checks the position status. If the position status does not match the option selected for this position (free, occupied, etc.) and the time expires, the robot shows an error.

**Docking**

A Docking action sets a position the robot should dock to, for example a charging station or a V, VL or L marker.

**Available fields:****Marker**

Select a marker from the drop-down list or select the XYZ icon to define a variable.

**Move**

A Move action defines a map position the robot should move to.

**Available fields:****Position**

Select a position from the drop-down list, or select the XYZ icon to define a variable.

**Retries (Blocked Path)**

Set the number of times the robot should try to reach the position if the path is blocked, or select the XYZ icon to define a variable. If, after the number of retries, the path is still blocked, the robot stops and produces an error message.

**Distance threshold**

Depending on how accurately the robot is required to position itself on the goal position, the threshold can be increased or decreased. The default is 0.1 m.

**Move to entry position**

Use this action to send the robot to an entry position. Entry positions are positions from which the robot can dock to markers, pick up carts, etc.

**Available fields:****Position**

Select a position from the drop-down list, or select the XYZ icon to define a variable.

**Retries (Blocked Path)**

Set the number of times the robot should try to reach the position if the path is blocked, or select the XYZ icon to define a variable. If, after the number of retries, the path is still blocked, the robot stops and produces an error message.

### Distance threshold

Depending on how accurately the robot is required to position itself on the goal position, the threshold can be increased or decreased. The default is 0.1 m.

### Entry Position

Select an entry position from the list, or select the XYZ icon to define a variable.

### Move to coordinate

A Move to coordinate action defines a X, Y position on the map the robot should move to. The map's 0,0 position with 0 orientation were created in the moment the mapping started.

If in doubt of the map's 0,0 position and 0 orientation, you may create a fixed position with those values as a reference point for the Move to coordinate position you wish to create.

### Available fields:

#### X

Enter the X (horizontal) map position the robot should move to, or select the XYZ icon to define a variable.

#### Y

Enter the Y (vertical) map position the robot should move to, or select the XYZ icon to define a variable.

### Orientation

Enter the orientation in degrees, i.e. the way the robot should turn relatively to the 0-orientation when landing on the position, e.g. 5 for 5 degrees clockwise or -5 for 5 degrees counterclockwise, or select the XYZ icon to define a variable.

### Retries (Blocked Path)

Set the number of times the robot should try to reach the position if the path is blocked, or select the XYZ icon to define a variable. If, after the number of retries, the path is still blocked, the robot stops and produces an error message.

### Distance threshold

Depending on how accurately the robot is required to position itself on the goal position, the threshold can be increased or decreased. The default is 0.1 m.

### Planner settings

A Planner settings action. The same changes can be made through Settings > Planner.

### Available fields:

#### Planner settings

Planner settings contain three different action options: Desired speed, Path deviation and Path timeout.

Desired speed: Select the desired speed of the robot from the drop-down list. This adds flexibility to the control of the robot's speed.

Path deviation: maximum distance that the robot is allowed to deviate from the path.



Path timeout: the amount of time where the robot keeps trying and will not deviate from the current path, e.g. if the path is blocked by an obstacle. A new path will not be created before the user set timeout has been reached.

### Value

Change the desired speed of the robot (Default: 0.8, minimum: 0.1, maximum: 1.5 m/s).

### Relative Move

A Relative move action is a move away from the robot's current position defined as an X-distance, a Y-distance and the final orientation. The X value is forwards/backwards (plus/minus) and the Y value is right/left (plus/minus). A relative move can be used for example to move the robot away from docking positions in narrow passages.



#### Note

When using a relative move, please be aware that the robot can move into forbidden zones and through walls in the map. The robot will still drive with collision detection and will not hit anything, but if there is a black line in the map and the wall does not exist in the real world, it will drive through it.

### Available fields:

#### X

Enter a value in meters for how much the robot should move forwards or backwards from its current position, e.g. 1 for 1 meter forwards or -1 for 1 meter backwards, or select the XYZ icon to define a variable.

#### Y

Enter a value in meters for how much the robot should move to the left or right, e.g. 1 for 1 meter to the right or -1 for 1 meter to the left, or select the XYZ icon to define a variable.

#### Orientation

Enter a value in degrees for how much the robot should turn (yaw) when finalizing the relative move, e.g. 5 for 5 degrees clockwise or -5 for 5 degrees counterclockwise, or select the XYZ icon to define a variable.

#### Max Linear Speed

Enter a value in meters/second for the max. forward or backward speed during the relative move, or select the XYZ icon to define a variable.

#### Max Angular Speed

Enter a value in meters/second for the max. turn speed during the relative move, or select the XYZ icon to define a variable.

#### Collision Detection

Select the check box to set automatic collision detection to on. Collision detection may be turned off if the robot needs to turn around its own center in tight spaces, for example in an elevator. If collision detection is on, the robot will try to turn, but will go into emergency stop as soon as it detects the surrounding walls.

## Set footprint

A Set footprint action makes it possible to change the robot's default footprint. This can be necessary, for example if the robot carries a top module with larger proportions than the robot's own or you want to extend the footprint when the robot tows a cart. The footprint is shown as a shadow around the robot on the map.

### Available fields:

#### Footprint

Set the footprint, or select the XYZ icon to define a variable. Footprint values must be entered in meters and the format of the input should be `[[x,y], [x,y], [x,y], [x,y]]` defining coordinates from the center of the robot. If needed, e.g. when driving with carts, extra points may be added to the footprint. The default footprint sets a point in each corner of the robot: `[[0.506,-0.32],[0.506,0.32],[-0.454,0.32],[-0.454,-0.32]]`

## Switch Map

A Switch map action is required if the robot needs to switch automatically from one map to another within a mission, for example if the robot is operating in a large site that includes more than one map. The maps must have overlapping areas where the robot can locate itself in the physical environment. Switch map actions are the basis for Transitions (Setup > Transitions) which handle map switches automatically once they are set up. The robot automatically chooses the start position when sent to a position in another map.

### Available fields:

#### Entry Position

Select the position in the "to" map which the robot should start from after map transition, or select the XYZ icon to define a variable.

The Switch map action must be preceded by a move action to the position in the current map that physically overlaps the Goal position you select here. The overlap of the entry and goal positions in the physical area is important for the robot to localize itself in the new map.

#### 4.4.4.4. Battery

This group contains the following actions.

### Charging

A Charging action is used to make the robot go to a charging station for automatic battery recharge. The action is defined by setting a minimum charging time and a minimum charging percentage. When the first of those are reached, the action is completed. For example, if you set the minimum time to 30 minutes and the minimum percentage to 80%, the robot will charge for minimum 30 minutes or until it reaches a battery level of 80%. You may also choose to ignore either time or percentage.

A Charging action must be preceded by a Docking action where the robot moves to a previously defined charging position near the charging station.

## Available fields:

### Minimum Time

Set a minimum amount of time the robot should charge before it moves on, or select the XYZ icon to define a variable. The system will compare the set minimum time with the minimum percentage, and when the first of those two requirements is fulfilled, the mission continues.

You may skip defining a minimum time by selecting the Ignore value check box. The robot will then charge until the minimum battery percentage level is reached.

### Minimum Percentage

Enter the minimum battery level the robot should charge to before it moves on, or select the XYZ icon to define a variable. The system will compare the set minimum percentage with the minimum time, and when the first of those two requirements is fulfilled, the mission continues. You may skip defining a minimum percentage by selecting the Ignore value check box. The robot will then charge until the minimum charge time is reached.

### Charge until new mission in queue

Select this check box if you want the robot to continue charging until it receives a new mission. If selected, the robot stays in the charging station until it receives a new mission, but not until one or the other of the criteria for minimum time or minimum percentage is reached.

If deselected, the robot leaves the charging station when either of the two charging criteria are reached regardless of queued missions.

## 4.4.4.5. Logic

This group contains the following actions.

### Break

A Break action is used to interrupt a loop action.

### Continue

A Continue action is used to abort the rest of a loop action and continue from the start.

### If

If actions make it possible to check battery level, number of pending missions, PLC registers or input from I/O modules and then define which actions or missions should be performed if the conditions return either true or false. You may use one or more actions or missions to define both True and False conditions.

**Battery Percentage:** An If action on battery percentage checks if the battery percentage is below, above or equal to a set limit and, depending on the result either sends the robot to a charging station or continues the mission. The True action could be a previously defined charging mission. The False action could be any alternative actions or missions, but may also be left blank. In that case, the robot will continue to the next step in the mission.

**Pending missions:** An if action on Pending missions checks if the number of pending (queued) missions is below, above or equal to a set number. You then set actions that define what the robot should do if the set condition returns True or False. An example could be to send the robot to a charging station if the number of queued missions exceeds a certain amount.

**PLC Register:** An If action on a PLC register checks if the register is set to a certain value, for example register 6=1 indicating that a lift is lowered when the robot arrives at a shelf. The True action (the lift is lowered) could then be a Wait for PLC Register action, for example wait for register 6 to reset to 0.

**I/O input:** An If action on an I/O input checks if the register is set to a certain value, for example register 6=1 indicating that a lift is lowered when the robot arrives at a shelf. The True action (the lift is lowered) could then be a Wait for PLC Register action, for example wait for register 6 to reset to 0.

### Available fields:

#### Compare

Select either Battery Percentage, PLC Register, Pending Missions or I/O input, or select the XYZ icon to define a variable.

#### Module

Select an I/O module from the drop-down list, or select the XYZ icon to define a variable.

#### Index

For PLC registers: enter the required index number (Integer registers 1-100, Floating point registers 101-200), or select the XYZ icon to define a variable.

#### Operator

Select the arithmetic operator you want to use, or select the XYZ icon to define a variable.

**Operators** are arithmetic operators used to specify the compare mission, e.g. use the < operator to specify “If Battery percentage is below 50 percent”.

The available operators are:

== 'equal to'

!= 'not equal to'

> 'greater than'

>= 'greater than or equal to'

< 'lesser than'

>= 'lesser than or equal to'.

#### Value

Enter the value for the selected register, or select the XYZ icon to define a variable.

### Loop

A Loop action makes it possible to have the robot repeat a mission either a specified number of times or 'endlessly' (until stopped by an operator). Drag actions or predefined missions into the loop action to define the sequence of actions the robot will repeat. A loop can be interrupted with a Break action.

### Available fields:

#### Iterations

Set the number of times, the robot should run the loop, or select the XYZ icon to define a variable.

## Content

### Pause

A Pause action pauses the mission execution until an operator presses the Continue button.

This can be used in missions where the robot should wait for an operator to do something, for example placing items on the robot and manually sending the robot on to another position by pressing the Continue button.

### Prompt User

A Prompt user action can be used when it is required to stop and ask the operator what the next step in the mission should be. The action consists of a Yes action, a No action and a Time-out action. The operator will be asked, for example, “Do you want to go to position X?”. If the operator answers Yes, the robot will go to position X. If the operator answers No, the robot will carry on to the defined No action, for example move to an alternative position. If the operator does not answer yes or no within a given time, the Time-out action will be executed, for example sending an email.

### Available fields:

#### Question

Write a question which can be answered with a yes or a no, or select the XYZ icon to define a variable. The operator will be asked to answer yes or no to the question, and if the answer is no, the robot will carry on with the No action.

#### User group

Select which User group the mission is intended for or select the XYZ icon to define a variable.

#### Timeout (seconds)

Set a timeout for when the robot should continue if the user does not answer the question. If the timeout is reached, the robot will execute the actions in the Timeout scope.

#### Timeout (seconds)

### Return

A Return action is used to abort a mission. It can be used, for example as catch action in a Try/Catch action.

### Wait

A Wait action pauses the mission in a given period of time.

### Available fields:

#### Time

Set an amount of time the robot should wait before moving to next action in the mission.

### While

While actions make it possible to check battery level, number of pending missions, PLC registers or input from I/O modules and then define which actions or missions should be performed if the conditions return either true or false. You may use one or more actions or missions to define the “while” conditions.

**Battery Percentage:** A While action on battery percentage checks if the battery percentage is below or above a set limit and, depending on the result, either sends the robot to a charging station or continues the mission.

**PLC Register:** A While action on a PLC register checks if the register is set to a certain value, for example register 6=1 indicating that a lift is lowered when the robot arrives at a shelf.

**Pending missions:** A While actions on Pending missions checks if the number of pending (queued) missions is below, above or equal to the set number. You then set an action that defines what the robot should do if the set condition returns True. An example could be to send the robot to a charging station if the number queued missions exceeds a certain amount.

**I/O input:** A While action on an I/O input checks if the register is set to a certain value, for example register 6=1 indicating that a lift is lowered when the robot arrives at a shelf. The True action (the lift is lowered) could then be a Wait for PLC Register action, for example wait for register 6 to reset to 0.

### Available fields:

#### Compare

Select either Battery Percentage, PLC Register, Pending Missions or I/O input, or select the XYZ icon to define a variable.

#### Module

Select an I/O module from the drop-down list, or select the XYZ icon to define a variable.

#### Index

For PLC registers: enter the required index number (Integer registers 1-100, Floating point registers 101-200), or select the XYZ icon to define a variable.

#### Operator

Select the arithmetic operator you want to use, or select the XYZ icon to define a variable.

**Operators** are arithmetic operators used to specify the compare mission, e.g. use the < operator to specify “If Battery percentage is below 50 percent”.

The available operators are:

== 'equal to'

!= 'not equal to'

> 'greater than'

>= 'greater than or equal to'

< 'lesser than'

<= 'lesser than or equal to'.

#### Value

Enter the value for the selected register, or select the XYZ icon to define a variable.

### 4.4.4.6. Error handling

This group contains the following actions.

## Create Log

A Create log action is used to create user generated error logs. A Create log action can be generated as an error log (Monitoring > Error logs) under the module name User, showing the description entered here. This is useful in for example a try/catch action where a log is created when catching an unsuccessful try.

### Available fields:

#### Description

Enter a description for the log type you want to create, or select the XYZ icon to define a variable. An example of a description could be "Mission x fail log"

## Throw Error

A Throw error action is used to enter an error message that will be shown in the user interface when the mission is run.

### Available fields:

#### Message

Enter the message you want displayed on the user interface when the mission is run, or select the XYZ icon to define a variable.

## Try/Catch

A Try/Catch action is a way to reinforce missions by defining an alternative action if the first choice action fails. This will in many cases prevent a mission from discontinuing in case, for example a position is blocked. A Try/Catch action consists of one action Try which the robot should attempt to complete, and a second action Catch which is used in case the first one fails.

### Available fields:

#### Try

#### Catch

## 4.4.4.7. Sound/Light

This group contains the following actions.

### Show Light

A show light action sets a light that the robot will show at a given point in the mission. The action is a combination of light effect, speed, color and intensity.

### Available fields:

#### Effect

Select a light effect from the drop-down list, e.g. 'Blink', or select the XYZ icon to define a variable.

#### Speed

Select a fast or slow speed from the drop-down list, or select the XYZ icon to define a variable.

### Color 1

Select a color from the drop-down list, or select the XYZ icon to define a variable. If you select two different colors for Color 1 and 2, the robot will alternate between the two.

### Color 2

Select a color from the drop-down list, or select the XYZ icon to define a variable. If you select two different colors for Color 1 and 2, the robot will alternate between the two.

### Intensity

Set the intensity of the light, or select the XYZ icon to define a variable. The intensity is defined as a percentage where 100 is full intensity.

### Timeout (seconds)

Set an amount of time the light should show, or select the XYZ icon to define a variable.

## Play sound

A Play sound action sets a sound, for example a beep, a horn or a voice message that the robot will play at a given stage in the mission or for the whole duration of the mission. There is a selection of standard sound bites to choose from, or you can upload own sounds to the robot in the section Setup > Sounds.

### Available fields:

#### Sound

Select a sound from the list, or select the XYZ icon to define a variable.

If you want to hear the sounds before selecting one, go to Setup > Sounds. You can hear the sounds on your computer by selecting the headset symbol.

#### Volume

Set the volume of the sound (0-100), or select the XYZ icon to define a variable. 100% is approximately 80 dB.

#### Mode

Select how the sound should be used in the mission:

**Full length** plays the sound from start to finish, starting at the point in the mission where it is inserted and ending when the sound file finishes.

**Loop** keeps repeating the sound file until the mission is completed.

**Custom length** plays the sound for the duration of time you set in the Duration window. If the set duration exceeds the duration of the sound file itself, the sound file will loop for the duration of the set time.

You can insert a Stop sound action anywhere in the mission. This will stop the playing of the current sound no matter which mode you have selected.

#### Duration

Set an amount of time the sound should play, or select the XYZ icon to define a variable.

## Stop sound

Stop playing the current sound.



#### 4.4.4.8. PLC

This group contains the following actions.

##### Set PLC register

A Set PLC register action is used to set a value in a register. The register can be set in three ways: Set: sets a value every time the mission is executed. Add: adds a value every time the mission is executed. Subtract: subtracts a value every time the mission is executed.

##### Available fields:

###### Register

Select a specific PLC register, or select the XYZ icon to define a variable. Registers 1 to 100 are reserved for integers and registers from 101-199 for floating point numbers.

###### Action

Select an action from the dropdown list, or select the XYZ icon to define a variable. The options are Set, Add and Subtract.

###### Value

Enter a value for the selected register, or select the XYZ icon to define a variable. If the selected register is between 1 and 100, the value must be an integer. If the selected value is between 101 and 200, the value must be a floating point number.

##### Wait for PLC register

A Wait for PLC register action is used to wait for a value and continue to the next action when the value is found in the set register.

##### Available fields:

###### Register

Select a specific PLC register, or select the XYZ icon to define a variable. Registers 1 to 100 are reserved for integers and registers from 101-199 for floating point numbers.

###### Value

Enter a value for the selected register, or select the XYZ icon to define a variable. If the selected register is between 1 and 100, the value must be an integer. If the selected value is between 101 and 200, the value must be a floating point number.

###### Timeout (seconds)

Define how long the robot should wait for the value in the set register before giving an error.

#### 4.4.4.9. Email address

This group contains the following actions.

## Send email

A Send email action is used to send email messages to selected recipients as part of a mission, for example to let an operator know that it has arrived at a specific location. Recipients must be set up in the Users section (Setup > Users) with an email address. Furthermore, an email account must be set up in the robot (System > Settings > Email configuration).

### Available fields:

#### Recipient

Select a recipient from the drop-down list, or select the XYZ icon to define a variable. The recipients on the list come from the Users section.

#### Subject

Type a subject of the email, or select the XYZ icon to define a variable.

#### Message

Write the message that the robot should send to the selected email address when the mission is executed, or select the XYZ icon to define a variable.

## 4.4.4.10. I/O module

This group contains the following actions.

### Connect Bluetooth

A Connect Bluetooth action is used when the robot must connect and stay connected to a Bluetooth module.

### Available fields:

#### Module

Select a Bluetooth module from the drop-down list, or select the XYZ icon to define a variable. Bluetooth modules are set up in the Bluetooth relays section (Setup > Bluetooth relays).

### Disconnect Bluetooth

A Disconnect Bluetooth action is used when the robot must close the connection to a Bluetooth module.

### Set output

I/O action is used when the robot needs to send a command to an I/O module.

### Available fields:

#### Module

Select an I/O module from the drop-down list, or select the XYZ icon to define a variable. I/O modules are set up in the section Setup > I/O modules.

#### Output

Enter which output port relay should be activated (1-4) , or select the XYZ icon to define a variable.

**Operation**

Set operation to On or Off, or select the XYZ icon to define a variable. For example: Select On if the I/O module is used to open a door.

**Timeout (seconds)**

Set an amount of time the relay should stay on, or select the XYZ icon to define a variable.

**Wait for input**

Wait for input action is used when the robot needs to wait for an I/O module to respond.

**Available fields:****Module**

Select an I/O module from the drop-down list, or select the XYZ icon to define a variable. I/O modules are set up in the section Setup > I/O modules.

**Input**

Enter the input port number or select the XYZ icon to define a variable.

**Value**

Set operation to On or Off, or select the XYZ icon to define a variable. For example: Select Off if the Wait for input action is used to stop a conveyor belt.

**Timeout (seconds)**

Define how long the robot should wait for the input to match the state set in Value before giving an error.

**4.4.4.11. Cart**

This group contains the following actions.

**Pick up cart**

Go to a position and pick up a cart.

**Available fields:****Position**

Select a position from the drop-down list, or select the XYZ icon to define a variable.

**Cart**

Select either a specific cart or “Any valid cart” from the drop-down list, if a specific cart is chosen and another cart is at the position the action will produce an error.

**Place cart**

Place the cart currently attached to the robot at a specific position.

**Available fields:****Position**

Select a position from the drop-down list, or select the XYZ icon to define a variable.

### Release cart

Choose whether or not to release the cart after arriving at the position.

### Reverse into place

You can choose to allow the robot to reverse into place. "Yes, with collision check" means that the robot will scan the area and check for obstacles before moving the cart to the drop-off position. "Yes, without collision check" means that the robot will move the cart into place without scanning for obstacles. This can be necessary when the robot docks into alignment fixtures.

#### 4.4.4.12. Shelf

This group contains the following actions.

##### Pick up shelf

Go to a position and pick up a shelf.

##### Available fields:

###### Position

Select a position from the drop-down list, or select the XYZ icon to define a variable.

###### Shelf type

Select the type of shelf to pick up, or select the XYZ icon to define a variable.

###### Final movement

Select which movement to perform after picking up the shelf, "Auto" will choose either forward or backwards depending on whether or not there is room for the robot, "None" means no movement after picking up the shelf.

##### Place shelf

Place the shelf currently attached to the robot at a specific position.

##### Available fields:

###### Position

Select a position from the drop-down list, or select the XYZ icon to define a variable.

###### Final movement

Select which movement to perform after dropping off the shelf, "Auto" will choose either forward or backwards depending on whether or not there is room for the robot, "None" means no movement after dropping off the shelf.

#### 4.4.4.13. UR

This group contains the following actions.

##### Run UR program

A Run UR program action is used to communicate with a Universal Robots application. The action starts a .urp file saved on the Universal robot. The program name is [program name].urp. Leave out .urp when you type the name. The MiR robot will continue until the given UR program has been executed.

## Available fields:

### Program name

Enter the name of the UR program (without the urp extension), or select the XYZ icon to define a variable.

## 4.5. Maps

In the Maps section, you create or edit the maps the robots use to navigate by. All maps must belong to a site, which is the overall container for one or more maps used in the same facility. A site may, for example, have one map per floor or one per section of a large production hall. The important thing is that the maps are contained in the same site for the robot to be able to move from one map to another.

Name	Created by	Functions
<b>ConfigurationSite</b>		
ConfigurationMap	MiR	View, Edit, Delete
<b>GlennsSite</b>		
TestMap	Administrator	View, Edit, Delete, Export
<b>KristinasSite</b>		
TestMap2	Administrator	View, Edit, Delete, Export

### 4.5.1. Import and export sites

A site can be exported and imported into other robots.

A site contains the following information:

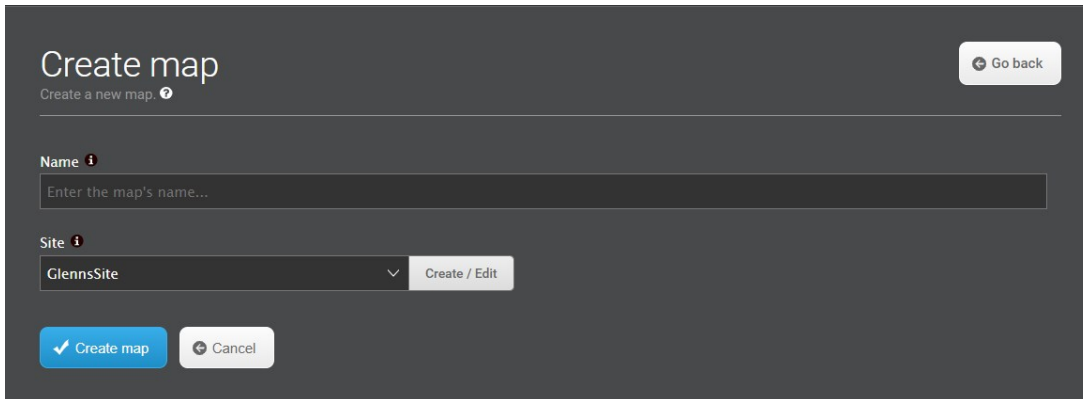
- Maps
- Users and User groups
- Added map features: positions, markers, walls, floors and all types of zones
- Paths
- I/O modules
- User-created sounds
- Carts, cart types and calibrations
- Shelf types
- Missions and Mission groups
- Dashboards
- Path guides

To export a site, simply click on the **Export site** button next to the site you want to export. The exported file is named [Site name]\_[Robot name]\_[SW version]\_[Date].site

To import a site, click the **Import site** button and select the site file.

### 4.5.2. Create map

To create a map, first enter a name for the map and select the site, the map should belong to. When you press the Create map button, you are directed to the map draw and edit section where you find the tools to draw the map and add various features.



The 'Create map' dialog box has a dark grey background. At the top left, it says 'Create map' in white, with a smaller subtitle 'Create a new map.' and a help icon. At the top right is a 'Go back' button. Below the title is a 'Name' field with a red exclamation mark icon and a placeholder text 'Enter the map's name...'. Underneath is a 'Site' dropdown menu showing 'GlennsSite' and a 'Create / Edit' button. At the bottom are two buttons: 'Create map' (with a checkmark icon) and 'Cancel' (with a close icon).

#### Name

Enter a name that describes the map.

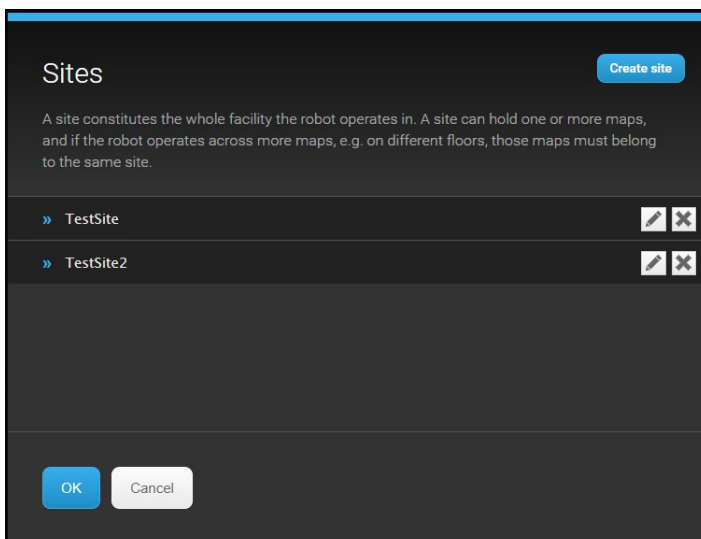
The name is used to identify a certain area of the site.

One way of naming maps is to select names that relate to the area of the map, e.g. Ground floor or Hall A.

#### Site

Select which site the map should be part of or click Create/Edit to create a new or edit the name of an existing site.

A site is the whole facility where MiRFleet operates. A site can hold one or more maps, and if the robot operates across more maps, e.g. on different floors, those maps must belong to the same site.



The 'Sites' dialog box has a dark grey background. At the top left, it says 'Sites' in white. At the top right is a 'Create site' button. Below the title is a descriptive text: 'A site constitutes the whole facility the robot operates in. A site can hold one or more maps, and if the robot operates across more maps, e.g. on different floors, those maps must belong to the same site.' Below this is a list of sites: '» TestSite' and '» TestSite2'. Each site name has edit and delete icons to its right. At the bottom are two buttons: 'OK' and 'Cancel'.

Click **Create site** to create a new site. Name the site and click **OK**.

Click **Create map** to save the map.

### 4.5.3. Mapping tools

The built-in mapping functionality makes it possible to draw a map by manually driving the robot around the facility using the joystick while the robot uses the laser sensors to map the area.

The map editing tools are all found on the icon tool bar, and the drop-down list contains all the features you can add to your map. Different tools are displayed on the icon toolbar depending on which feature you have selected from the drop-down list.



#### Mapping tools



Press the 3-dots icon to open the Upload, download and record map dialog. This toolbar has options for recording a new map or uploading/downloading existing ones.

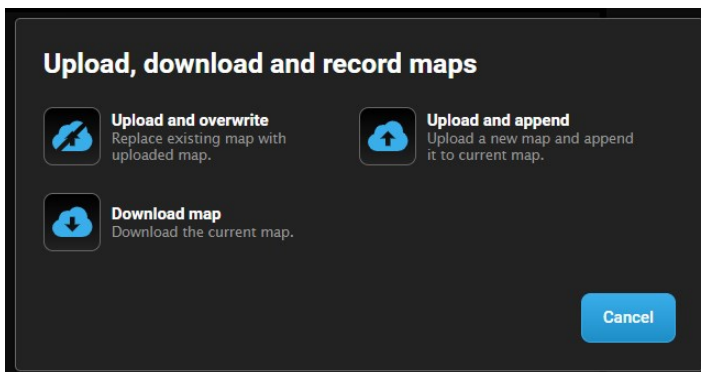
You may upload a map from your computer in PNG format. For example, if CAD drawings of the facility are available, it is possible to use those instead of mapping the area with the robot, but you can also upload maps previously created with the robot and downloaded to your PC.



#### Note

When you download a map, only the recorded map data are saved, i.e. any added features such as positions and zones are not saved with the map file. If you want to save a map including all details, you should export the whole site to which the map belongs.

The Upload, download and record maps dialog has the following options.



- **Upload and overwrite**  
The Upload and overwrite option erases the existing map and replaces it with the map you upload.
- **Upload and append**  
The Upload and append option adds the uploaded map to the existing one.
- **Download map**  
The Download map option saves the map to your PC as a PNG file.

### 4.5.4. Editing a map

When the map recording is done, complete the map by removing unwanted “noise”, adding virtual walls, preferred or unpreferred drive zones, positions and much more to get a reliable map that allows the robots to maneuver smoothly and efficiently in the area.

## Left-hand side tool bar

The left-hand side tool bar has the basic tools for saving, undoing and navigating in the map you are working on. Furthermore, different tools appear on the tool bar depending on which map layer you select from the Object types drop-down list. These are presented on the following pages.

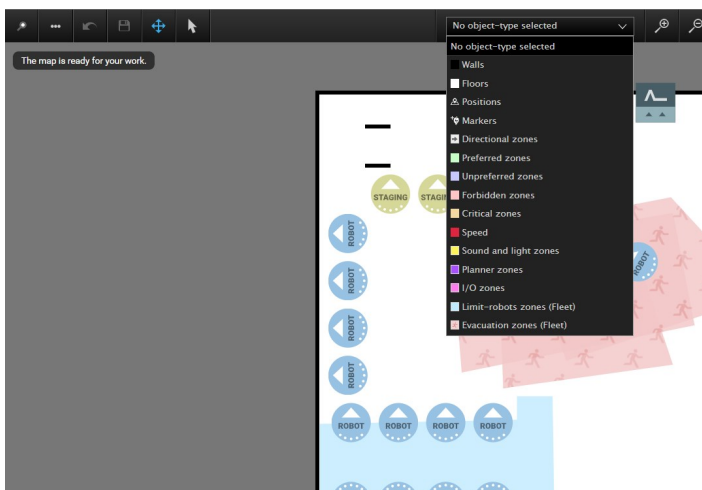


The toolbar contains the following elements:

- **Find position**  
Select the magnifying glass to search for a position on the map.
- **Download, upload and record map**  
Click to upload, download and record maps.
- **Undo icon**  
Press one or more times to undo your last operation(s). While you are drawing a shape or line in the map, the Undo tool is not available. But as soon as you finish by clicking the check mark, you can undo the whole shape or line.
- **Save icon**  
Click to save the changes to the map. For the changes to take effect, you'll need to reload the map.
- **Navigate icon**  
Click to view the map with all added details, and drag to move the view.

## Select object

From the list, select which part of the map you want to edit. Walls and Floors lets you remove unwanted objects and add nice straight lines to create a more legible map. The other objects define where and how the robot should move, or not move





## Right-hand side tool bar

The right-hand side tool bar has tools for controlling the map view and synchronizing the robot's position with the map view.



- **Zoom in**  
Zoom in on the map.
- **Zoom out**  
Zoom out on the map.

## 4.5.5. Object types

### 4.5.5.1. Walls

When mapping, physical objects detected by the scanners are recorded as “walls” in the system. Apart from real walls, these objects could also be shelves, chairs, tables and even people passing by. Some of these recordings are regarded as “noise” and will, if they are not removed, potentially send the robot on unnecessary detours during its path planning. It is therefore recommended to remove the objects that are not permanent.

Use the Eraser or the Erase by selection-tool to remove unwanted obstacles from the map. Use the Draw new line tool to add new walls to the map, and replace the coarse pixelated lines. The tool works by adding lines between each point you add to the map. Click the check mark when the line is done.

Use the Select shape or line tool to change an added object. You can add extra points or move the existing ones to change the shape. To erase a whole shape, select the Erase shape or line-tool and click on a shape to delete it.

### 4.5.5.2. Floors

When mapping, the floor is created automatically. You can use the Floor tool to touch up the existing floor, for example if the mapped floor contains gray areas, which the robot is not able to pass. You may also add a whole new floor on top of the existing one

Use the Eraser or the Erase by selection-tool to remove unwanted areas of the floor from the map. Use the Draw a new shape tool to add new a new floor or patch up the exiting one. The tool works by filling the area between each point you add to the map with gray color. You may add as many points as needed and drag to move them in the map. Click the check mark when the shape is done. The gray shape will be converted to white indicating that it represents floor.

Use the Select shape or line tool to change an added object. You can add extra points or drag the existing ones to change the shape. To erase a whole shape, select the Erase shape or line tool and click on a shape to delete it.

Hold down the shift key while drawing a line or an area if you want straight lines.

### 4.5.5.3. Positions

Positions are defined as X-Y coordinates in the map and are used as part of missions.

Positions are used either as destination positions or as via positions on a route. To define a position, select the Position tool, click somewhere on the map and rotate the icon until the arrow points in the direction you want the robot to orient to when landing. In the dialog window that opens, it is then possible to adjust the position and the orientation manually or click the Use robot position button to use the current position of the robot.

If two or more positions of the same kind overlap, it is easy to select underlying ones by clicking and selecting the position from a list.

**Note**

The Use robot position button is available only if you are editing the currently active map.

Optional positions:

- Hook positions for picking up and dropping off carts become available if a hook is applied.
- Shelf positions for picking up and placing shelves become available if a shelf lift is applied.
- Staging positions used as waiting positions become available when the robot is part of a fleet.

**Note**

Hook, Shelf or Fleet must be enabled in the Features section under System > Settings before the positions can be viewed.

#### 4.5.5.4. Markers

**Markers:** Markers are position types used by the robot to dock to physical V, VL or L shaped objects. Markers are used for example to make the robot dock to a conveyor belt or a charging station. To define a marker, first place the robot either facing front or rear to the V, VL or L marker, depending on how you want it to dock to the marker. For Charging station markers, the robot must always be placed facing front. When you select the Marker tool, the quickest way to set the position is to use the Detect marker button. If the robot can detect the marker, the position, offset and orientation fields will automatically fill. Otherwise move the robot a bit closer, and try again. The values can be adjusted manually afterwards if required.

**Note**

The Detect marker button is available only if you are editing the currently active map.

You can see and edit the entry position of a marker by clicking on the marker and selecting Show entry position(s). The entry position stays visible until you click again and select Hide entry position(s).

#### 4.5.5.5. Directional zones

Directional zones let you organize the motion of robots by specifying the directions in which the robots can move in specific zones. When you create a directional zone, you specify its direction, and the map shows the direction with arrows drawn on the zone.

When a robot is in a directional zone, the following rules apply to the motion of the robot:

- The robot is not allowed to move in the direction opposite to the direction of the arrow.
- The robot can move perpendicular to the direction of the arrow or at any angle less than 90° to the arrow.

There are two types of directional zones: directional shape and directional line. A directional shape is a shape on the map with a direction defined. The direction on a shape can have any value from 0° to 360° with an increment of 45°.

A directional line is a line with a direction defined. The direction of a line is from one of its ends to the other end.

To work with directional zones: In the map editor, in the drop-down menu, select Directional zones.

### Creating a directional shape

To create a directional shape:

- In the toolbar, click Draw a new shape and create a shape by placing points on the map.
- To specify the direction of the zone: In the toolbar, click Select the direction of a directional zone. The Select direction dialog appears. Click a direction to select it and close the dialog.
- Click the check mark to finish editing the zone.

### Creating a directional line

To create a directional line:

- In the toolbar, click Draw a new line and create a line by placing points on the map.
- Click Line settings to change the width of the line. Use one of the presets or enter a custom width. Click Close when done.
- Click the check mark to finish editing the line.

To reverse the direction of a line, select a line and click Reverse direction in the toolbar.

Directional zones in combination with forbidden and unpreferred zones let you organize efficient robot traffic.

### One-way lanes

When a robot moves in a long corridor, it places itself in the middle of the corridor. If there is another robot going in the opposite direction, the two robots may block each other's way. A way to solve this issue is to create a configuration for robots with two lanes and a lane separator, similar to a street with two lanes and a solid (or dashed) white line. The following steps describe how to create such configuration using directional zones:

- Create a thin forbidden zone in the middle of the corridor parallel to the corridor walls. This is the lane separator.
- Create directional zones on both sides of the forbidden zone. Make the directions of the zones opposite.

With such a configuration, robots going in the opposite directions use different lanes and do not get in each other's way. Replacing the forbidden zone with an unpreferred zone gives robots more space for maneuvers.

#### 4.5.5.6. Preferred, Unpreferred, Forbidden and Critical zones

Zones are actions that are automatically triggered when a robot enters the area in which one of these actions apply. The zones apply both when the robot operates autonomously and when it is driven in manual mode. It is possible to create overlapping zones so that multiple events have affect at the same time, e.g. blinking and slowing down the speed of the robot when it drives in a certain zone.

Each zone has its own color in the map. To add a zone, select it on the drop-down list, then select the shape or line tool on the icon bar and draw the shape or line where you want it on the map.

Hold down the shift key while drawing a line or an area if you want straight lines.

Select the check mark on the tool bar to finish the shape or line. To edit or remove a shape or line, select the type, e.g. Preferred zones, on the drop-down list. Then, to edit, select the Select shape or line tool and select object to edit. You can change a shape or line by pulling the points, add extra points or change the thickness of a line. To add extra points, first click on an existing point, then click where you want to add the point and pull to change the shape if needed. To delete a line or shape, select the Erase shape or line tool and select the object to delete.

Preferred, Unpreferred, Forbidden and Critical zones are drive zones that are used to control the robot's global planner when it calculates paths between positions

### Preferred zones

The robot tries to run within a preferred area taking into account dynamic obstacles.

### Unpreferred zones

The robot tries to avoid an unpreferred zone but may go into it if there are no other possibilities.

### Forbidden zones

The robot never enters a forbidden zone.

### Critical zones

The sensors are turned off, allowing the robot for example to move through a narrow doorway without entering emergency stop. As soon as the robot leaves the zone, the sensors are turned on again.

#### 4.5.5.7. Zone settings

Zone settings allow the user to customize a certain zone to their needs. One or more actions can be set. While the robot is in the zone, it will perform the actions. When the robot leaves the zone, it will go back to the default settings.

The following zones have zone settings.

#### 4.5.5.8. Speed zones

The robot slows down or increases its speed when driving in the zone. Slowing down may be used if driving in a zone with many people, and speeding may be used to traverse a zone free of people and obstacles quickly.

#### Zone settings

- Speed zones

The desired default speed of the robot. The value can be changed here, by a mission actions or a REST call. (Default: 0.8, minimum: 0.1, maximum: 1.5 m/s)

#### 4.5.5.9. Sound and light zones

The robot can play a sound and/or blink when driving in the zone. May be used to warn people about the presence of the robot.

##### Zone settings

- Light  
A show light action sets a light that the robot will show at a given point in the mission. The action is a combination of light effect, speed, color and intensity.
- Sound  
A Play sound action sets a sound, for example a beep, a horn or a voice message that the robot will play at a given stage in the mission or for the whole duration of the mission. There is a selection of standard sound bites to choose from, or you can upload own sounds to the robot in the section Setup > Sounds.

#### 4.5.5.10. Planner zones

The robot can turn off the laser scanners and localize with encoders, decrease the field of view to run smoothly in populated areas, optimize the time and distance of paths and ignore obstacles.

##### Zone settings

- No-localization  
The robot turns off the laser scanners and uses encoders only to localize. Useful for special driving like ramps.
- Look-ahead  
Decreases the robot's field of view to help it run smoothly in populated areas.
- Path deviation  
Maximum allowed distance that the robot can deviate from the path. Default is 0,5. Minimum is 0. Maximum is 3.
- Path timeout  
The amount of time the robot keeps trying and will not deviate from the current path, if the path is blocked by an obstacle. A new path will not be created before the timeout has been reached.
- Ignore obstacles  
The robot detects all obstacles with the 3D camera, but they are ignored with this action. This is useful if you experience problems with the robot stopping in front of windows because of sunlight.

#### 4.5.5.11. I/O module zones

The robot activates an I/O module when entering the zone. An I/O zone may be used instead of controlling I/O activation through a mission.

##### Zone settings

- I/O module  
I/O modules (Bluetooth and WISE) are used for receiving and giving input and output to be able to communicate with e.g. doors, elevators, pallet lifts etc.

- PLC registers

A Set PLC register action is used to set a value in a register. The register can be set in three ways: Set: sets a value every time the mission is executed. Add: adds a value every time the mission is executed. Subtract: subtracts a value every time the mission is executed.

#### 4.5.5.12. Limit-robots zones (Fleet)

Applies only when robots are controlled by MiRFleet. Only one robot at a time may enter the zone. Used to keep a zone clear of other robots, for example in areas where MiRHook robots unload and pick up carts.

##### Zone settings

- Limit-robots  
Limit the number of robots driving in the same zone. Used to keep a zone clear of other robots, for example in areas where MiRHooks unload and pick up carts.

#### 4.5.5.13. Evacuation zones (Fleet)

**Evacuation zones** make it possible to evacuate all robots in case of an emergency situation.

One or more evacuation zones can be marked up on the map and will appear on a list under **Evacuation zones**. It is possible to evacuate one certain zone or all zones at once.

Select **Evacuate all zones** to evacuate all zones (in the top bar or under Evacuation zones) or select **Evacuate** next to a specific evacuation zone to evacuate that zone. All robots will leave the selected evacuation zones and go to the nearest evacuation positions.

To give the all clear when the emergency is over, remove the ticks from the boxes from one or more zones under **Evacuated**. When the all clear has been given, the robot(s) will wait at their Evacuation position(s) for new missions.

Evacuation zones should only be used in case of an emergency as all missions are discontinued.

Note: There must be at least one evacuation position per robot when Evacuation zones are applied.

##### Zone settings

- Evacuation zones  
Evacuation zones make it possible to evacuate all robots in case of an emergency situation.

#### 4.5.6. Delete map

You can delete maps that are created by you or another member of the user group you belong to.

Delete map

[Go back](#)

You are about to delete the map with the following details:

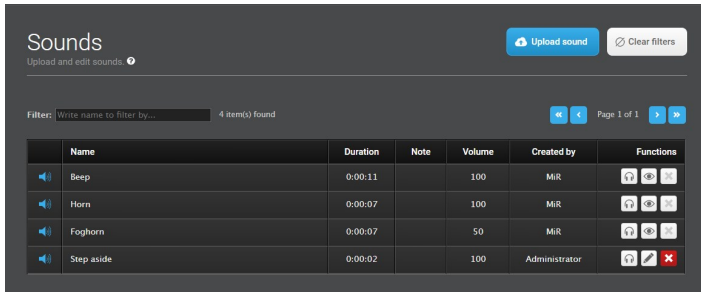
Name	TestMap2
X-position	0
Y-position	0
Theta	0

[Delete map](#) [Cancel](#)

## 4.6. Sounds

In the Sounds menu, you can upload new sounds to the robots or edit the volume and length of the sounds.

Sounds are used in missions and can be used as alerts: “Please step aside” or to attract peoples attention for example when the robots have arrived at a position.



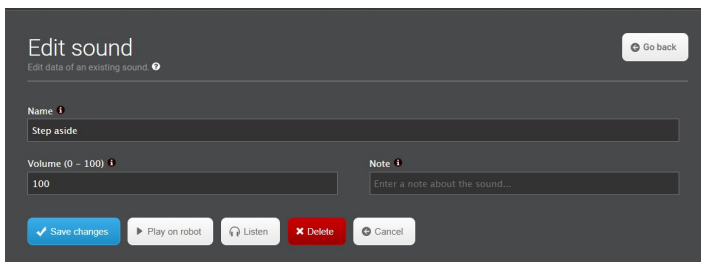
### 4.6.1. Edit sound

You may rename any of the user added sounds on the robot and adjust the volume.

Press the Play on robot button to listen to the sound on the robot itself.

Press the Listen button to listen to the sound on your computer.

Note: The volume can only be checked by playing the sound on the robot itself.



The **Edit sound** dialog contains the following fields:

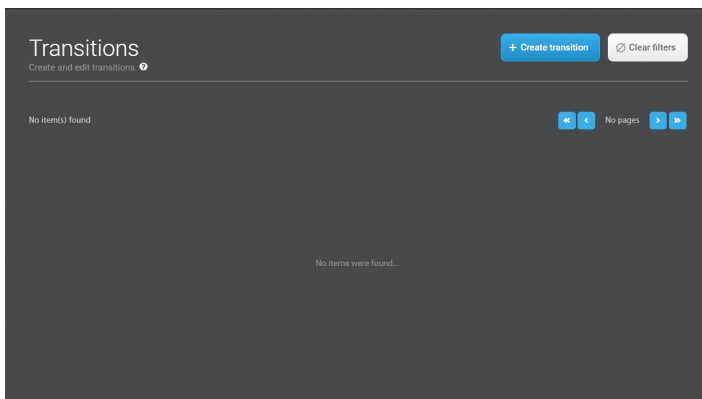
- **Name**  
You may change the names of user uploaded sounds. The names of the standard system sounds cannot be changed.
- **Volume (0-100)**  
The maximum of 100 is approximately 80 dB.
- **Note**  
You can write a small note about the selected sound (optional).
- **Delete**  
You can delete user uploaded sounds from the robot.
- Select **Save changes** to save the settings.

## 4.7. Transitions

Transitions are used to handle changeovers from one map to another within the same site. Map transitions are used, for example where two adjoining production halls have separate maps.

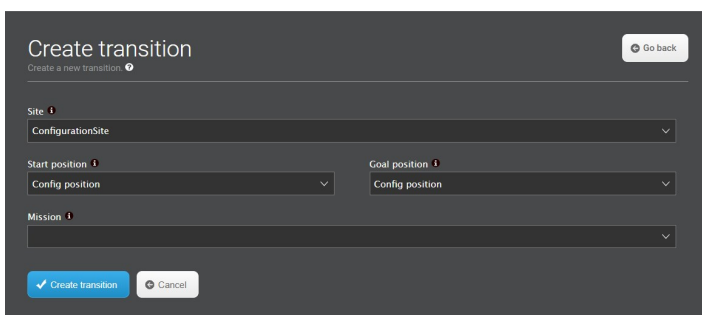
A transition entry consists of two robot positions, a start and a goal position, one in each map at a physical point where the two maps overlap. Furthermore, it requires pre-defined missions including Switch map actions. Going from map A to map B and from map B to map A requires two different missions.

Once the transition is set up in the user interface, the robot handles switches from one map to another automatically. You just set up your mission as you would in a single map-environment, and the system will include the switch positions, the switch map mission and the transition action invisibly. The transition is visible only in the way that the robot stops for a short while at the switch positions while positioning itself in the new map.



#### 4.7.1. Create transition

To create a transition, select a start position and a goal position in two different maps at a point where the maps overlap. The positions must have been predefined as Robot positions in the two maps.



The **Create transition** dialog contains the following fields:

- **Site**  
Select the site in which the two maps are represented.  
Both maps must be part of the same site for a map transition to be possible.
- **Start position**  
Select the start position of the transition.  
The start position must be of the type Robot position and have been created in advance in a place where the two maps overlap. Start and goal positions must be placed on the exact same spot physically but named differently, for example "Map A\_posA" and "MapB\_posA" to indicate the relation between the two.



- **Goal position**

Select the goal position of the transition.

The goal position must be of the type Robot position and have been created in advance in a place where the two maps overlap. Start and goal positions must be placed on the exact same spot physically but named differently, for example "Map A\_posA" and "MapB\_posA" to indicate the relation between the two.

- **Mission**

Select a mission that includes a switch map action.

The switch map mission must have been created in advance and include two Switch map actions: the first switch map action must include the "from" map and the defined Start position, and the second one must include the "to" map and the defined Goal position.

Select **Create transition** to save the settings.

## 4.7.2. Edit transitions

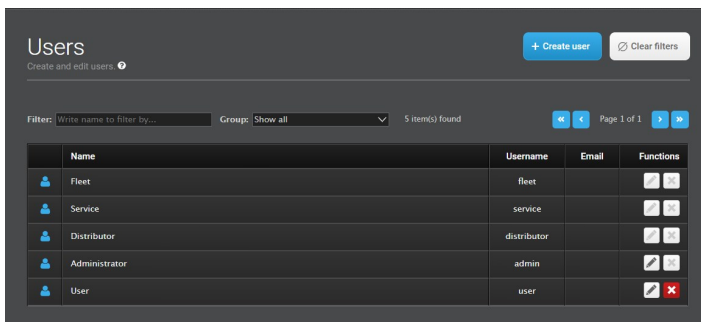
To edit a transition you must select a start position and a goal position in two different maps at a point where the maps overlap. The positions must have been predefined as Robot positions in the two maps.

## 4.7.3. Delete transitions

You can delete transitions that are created by you or another member of the user group you belong to. If you delete a transition, the start and goal positions, and attached mission are deleted as well.

## 4.8. Users

All users of the fleet - from daily operators to system administrators - must have a user profile in the system. Users are administered in the Users section where you set up, edit and delete system users.



Name	Username	Email	Functions
Fleet	fleet		[edit] [delete]
Service	service		[edit] [delete]
Distributor	distributor		[edit] [delete]
Administrator	admin		[edit] [delete]
User	user		[edit] [delete]

### 4.8.1. Create user

In Create Users you set up new users by entering master data such as name, email, login credentials and access rights. Access rights are given by associating each user with a User group that delimits which sections of the user interface the user has access to.

Note: User groups should be defined prior to setting up Users.

The Create user dialog has the following fields:

- **Name**  
Enter the name of the user, e.g John Smith.  
The name is shown in the upper right-hand corner of the web interface when the user is logged in and is not to be confused with the Username.
- **Username**  
Enter the name that the user should use to log in to the system, e.g. John.
- **Password**  
Enter a password that the user should use to log in to the system. Passwords are case sensitive.  
Users can change their own password when logged in by selecting their login name in the upper right-hand corner of the window and changing the password in the window that pops up.
- **Email address**  
Enter the user's email address.  
Email addresses can be used as part of a mission, for example to notify a user about a completed mission.  
See Create mission (Setup > Missions > Create Mission).
- **User group**  
Select a user group for the user. Each user must be attached to a pre-defined user group. The user group specifies which parts of the system the user has access to.  
User group permissions are defined for each system command or feature and are granted as read-only or write permissions.

- **SingleDashboard user**

Select the check box if the user's only task is to control the robot(s) from a dashboard, for example if the user's task is to start missions from a tablet attached to a top module.

Single dashboard users do not have access to any other parts of the user interface.

Select a dashboard for the SingleDashboard user.

When the SingleDashboard user logs in, the selected dashboard will be the one that's available to this user.

- **PIN code**

Select the check box if the user is allowed to enter the system using a PIN code.

Enter a 4-digit PIN code.

Each PIN code user must have a unique code.

Select **Create user** to save the settings.

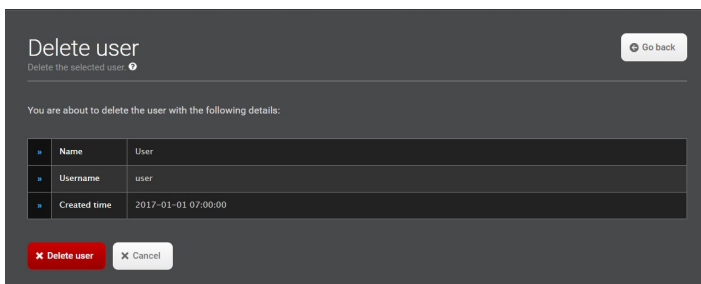
## 4.8.2. Edit user

In Edit user you can change the settings of a user's profile.

Any of the settings can be changed, except for the password. If a user wants to change password, he or she can select the login name in the upper right-hand corner of the window and changing the password in the window that pops up.

## 4.8.3. Delete user

When you select Delete user, only the user's master data as shown below disappear. All possible settings and updates made in the system by the user in question stay unchanged.



**Delete user**  
Delete the selected user

You are about to delete the user with the following details:

Name	User
Username	user
Created time	2017-01-01 07:00:00

## 4.9. User groups

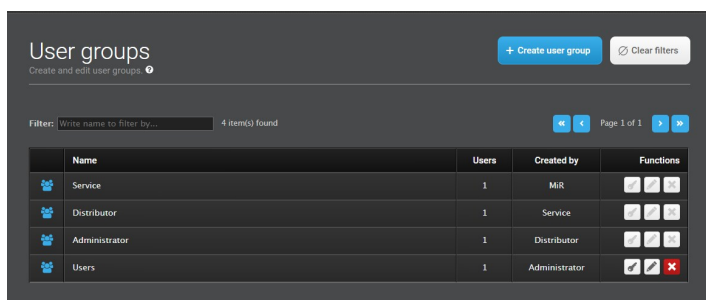
The User groups section, is used to create user groups and assign permissions to each group.

A user group defines which sections of the user interface users have access to and whether the access rights should involve viewing only or give full write access. To edit permissions for a group, click the key icon next to the name of the user group to open the User group permissions section.

The MiR user interface comes with a number of default user groups:

- Distributors have full read/write access to the user interface and can administer the permissions of the Administrators and Users groups.
- Administrators per default have full read/write access to the user interface and can administer the permissions of the Users group.
- Users per default have access to view the whole user interface and permission to create and edit dashboards. Users with write access to the User groups section, e.g. Administrators may also create additional user groups.

Related items: When setting up users in the Users section, each user must be assigned to a user group.



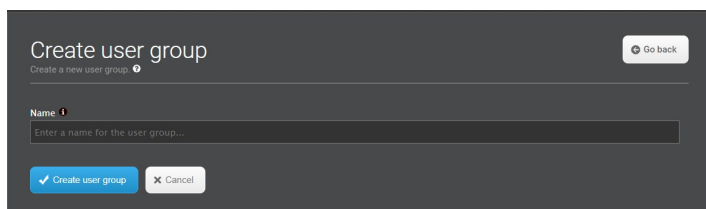
Name	Users	Created by	Functions
Service	1	MiR	[Icons]
Distributor	1	Service	[Icons]
Administrator	1	Distributor	[Icons]
Users	1	Administrator	[Icons]

### 4.9.1. Create user group

Fill out the name field to create a new user group.

Besides the default user groups, you can create as many additional user groups as needed. The number of user groups needed depends on how many different tasks and permission levels are required. Several users carrying out the same tasks can belong to the same user group.

You can give permissions to all sections of the user interface that you have access to.



- **Name**

The name must be unique and is used to identify the group of users it represents. One way of naming user groups is to select names that characterize the tasks of the users in the particular group. For example, a group of users operating the robot by starting and queuing missions could be named Operators.

Select **Create user group** to save the settings.

### User group permissions

Permissions can be given to all parts of the system that are available to the user group, the creator belongs to.

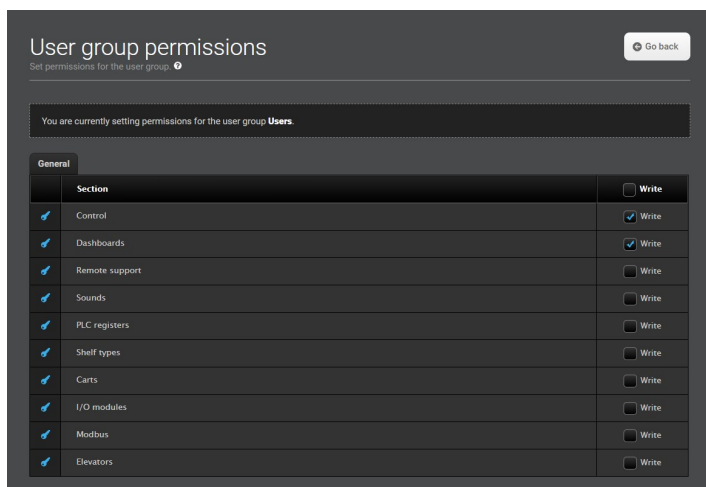


#### Note

It is not possible to edit user group permissions for your own user group, but only for other user groups administered by your user group.

Select which sections of the system the user group should have access to. User group permissions are divided into groups of related items, e.g. Maps and positions, and you can select a whole group or individual items in a group.

The user group will have access to all the items you select for the group. All other items will be visible but not editable to the users of the group.

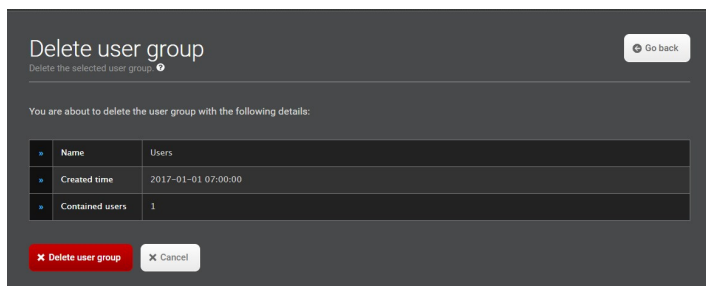


Section	Write
Control	<input checked="" type="checkbox"/> Write
Dashboards	<input checked="" type="checkbox"/> Write
Remote support	<input type="checkbox"/> Write
Sounds	<input type="checkbox"/> Write
PLC registers	<input type="checkbox"/> Write
Shelf types	<input type="checkbox"/> Write
Carts	<input type="checkbox"/> Write
I/O modules	<input type="checkbox"/> Write
Modbus	<input type="checkbox"/> Write
Elevators	<input type="checkbox"/> Write

## 4.9.2. Delete user group

A User group can be deleted by users that belong to the group which created the group. When you delete a user group, all users belonging to that group will be deleted as well.

If you want to keep one or more users of the group you are about to delete, then go to the Users section and associate those users with a different user group.



Name	Users
Created time	2017-01-01 07:00:00
Contained users	1

## 4.10. Paths

Paths are saved routes between two positions.

The first time the robot runs the route between two positions, the calculated path is saved and used every time the robot runs the same route, thereby saving time for route calculation. A path is automatically recalculated only in the event that one of its positions is modified.

If you find that an automatically calculated path is unnecessarily long, for example if the robot had to go around a dynamic obstacle at the time it was created, you may delete it, and the robot will then calculate a new path the next time it runs between those two positions.

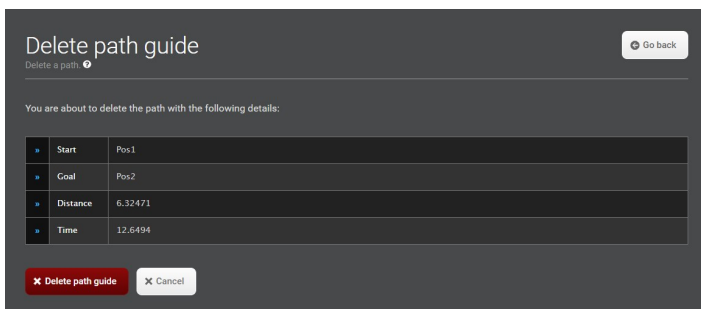
Paths can also be created manually by drawing Preferred zones in the Maps section. To do this, you must first delete any automatically created paths between the affected positions before the preferred zone will take effect.

- **View a path**

The path is shown as a dotted line between two positions on the map. The view can be used to check if calculated paths look appropriate.

### 4.10.1. Delete path

Paths may be deleted if you want the robot to recalculate the route between two positions or if you have manually created a preferred path on the map.



## 4.11. Path guides

A path guide makes it possible to define paths that the robot(s) should follow between two positions. Path guides can be very useful in locations where you want the robot to follow a certain path for example along a wall. In environments where multiple robots operate, an obvious application of path guides would be to create right-hand drive paths where two robots can pass each other without stopping to recalculate each time they meet. This is done by creating one path guide going from A to B and another one in the opposite lane going from B to A.

To create a path guide, you must first create a number of robot positions, waypoints, on the map. The positions must be placed on the path in succession, for example with a distance of 3-5 meters and they must be oriented in the driving direction.

When the positions are made, you create the path guide. A path guide consists of one or more start positions, one or more goal positions and a number of waypoints in between. You may use the same path to go between more start and goal positions.

**Note!** When you set up missions that include positions used as start and end positions, the robot will automatically use the path guide.

## Two examples

The two examples below illustrate how robots avoid planning around each other every time they pass each other while crossing the production hall.

Path guide 1 forces the robot to follow one lane going south to north, and Path guide 2 forces the robot to follow another lane going north to south. The same two positions are used for start and end positions but reversed in the two path guides.

### 4.11.1. Create a path guide

To create a path guide, first enter a name for the path guide and select the map it should belong to. When you press the Create path guide button, you are directed to the section where you select start and goal positions as well as the waypoints that make up the path guide between them.

- **Add start**  
Select one or more start positions for this path guide.
- **Add waypoint**  
Select the waypoints created for this path guide.  
Note! The waypoints must have been created pointing in the driving direction.
- **Add goal**  
Select one or more end positions for this path guide.

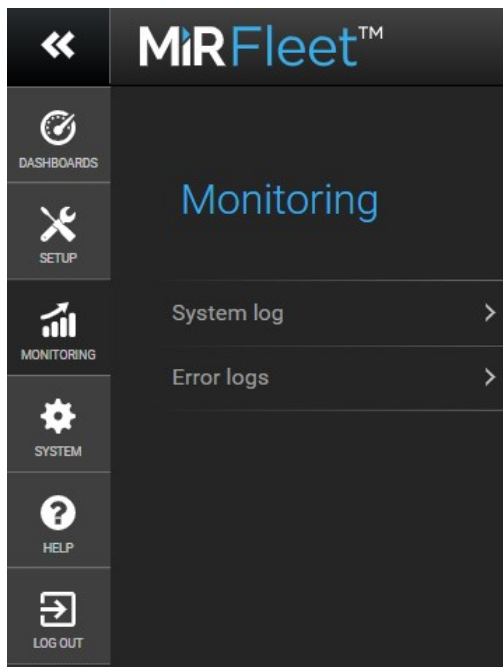
### 4.11.2. Delete path guide

You can delete path guides that are created by you or another member of the user group you belong to.

Name	Path1
Start positions	0
Waypoints	0
Goal positions	0

## 5. Monitoring

This section describes the items in the Monitoring menu.



The Monitoring menu contains the following items:

<b>5.1. System log .....</b>	<b>63</b>
<b>5.2. Error logs .....</b>	<b>63</b>



## 5.1. System log

The system log contains events that are logged by the operating system components. The system log contains information about system state at a given time (shown by color-codes), the affected module, a short explanation and a time stamp.

The system log is mainly used by system supporters for troubleshooting.

System log  
Read the system log from the fleet

State	Module	Message	Time
●	robot_manager	Scanning on IP: 192.168.10.254	08:44:32
●	robot_manager	Scanning on IP: 192.168.10.250	08:44:32
●	robot_manager	Scanning on IP: 192.168.10.249	08:44:32
●	robot_manager	Scanning on IP: 192.168.10.252	08:44:32
●	robot_manager	Scanning on IP: 192.168.10.251	08:44:32
●	robot_manager	Scanning on IP: 192.168.10.248	08:44:32
●	robot_manager	Scanning on IP: 192.168.10.244	08:44:32
●	robot_manager	Scanning on IP: 192.168.10.242	08:44:32
●	robot_manager	Scanning on IP: 192.168.10.245	08:44:32
●	robot_manager	Scanning on IP: 192.168.10.241	08:44:32
●	robot_manager	Scanning on IP: 192.168.10.238	08:44:32

The System log table has the following columns:

- **State**  
State is a visual color-indication of the system state at the time of logging.
- **Module**  
Module indicates in which module the logged event has taken place.
- **Message**  
The message is a short description of the logged event.
- **Time**  
The time the event was recorded; hh:mm:ss.

## 5.2. Error logs

The error log is a list of all detected system errors. Each entry is shown with a description, an indication of which module is affected and the time when the error occurred.

When further examination of a log entry is required, it can be downloaded in an encrypted file format and sent to MiR Support. Each file contains detailed information plus a recording of the last 30 seconds of robot action(s) before the error occurred.

It is also possible to create a user generated log with a recording of the last 30 seconds of the robot's actions.

Click the Generate log button to record the last 30 seconds of the robot's actions.

Click Delete all to delete the entire error log.

Error logs  
Download and delete error logs

Generate log Delete all

Filter: Write name to filter by... 1 item(s) found

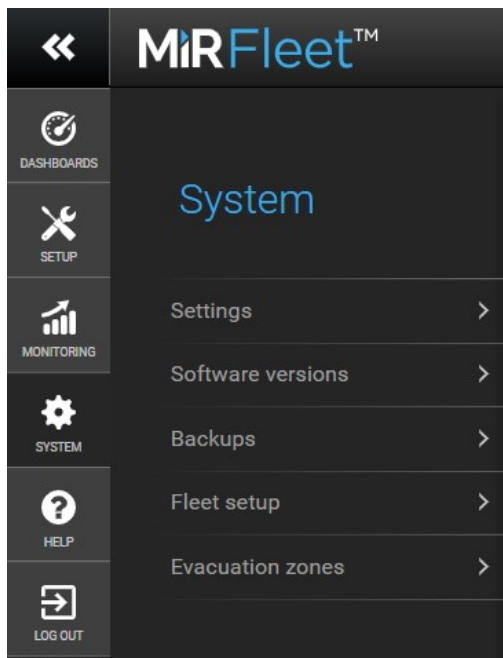
Description	Module	Time	Functions
Generated from web interface by 'Service'	User	2019-01-09T10:53:43	Download Delete

The Error logs table has the following columns:

- **Description**  
A short description of the logged event.
- **Module**  
Shows which of the robot's modules has caused the error, e.g. /Hook/Connection.
- **Time**  
Shows the exact time the error occurred.
- **Download**  
Click the Download icon to download the log entry in an encrypted file format.
- **Delete error log**  
Log entries can be deleted individually by clicking the x-icon next to the selected entry.

## 6. System

This section describes the items in the System menu.



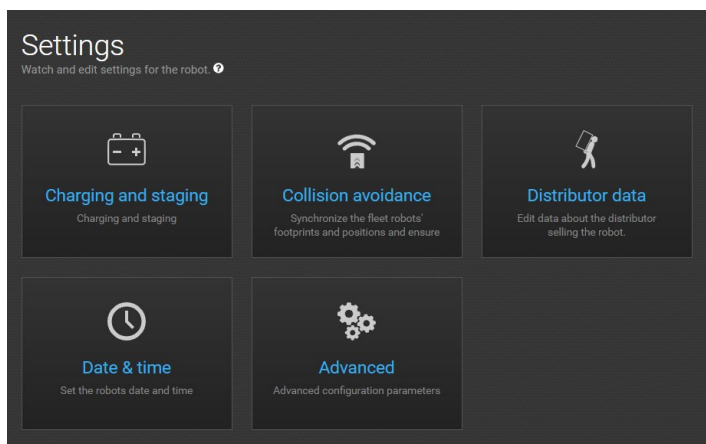
The System menu contains the following items:

<b>6.1. Settings</b>	<b>66</b>
<b>6.2. Software versions</b>	<b>68</b>
<b>6.3. Backups</b>	<b>68</b>
<b>6.4. Fleet setup</b>	<b>69</b>
<b>6.5. Evacuation zones</b>	<b>69</b>

## 6.1. Settings

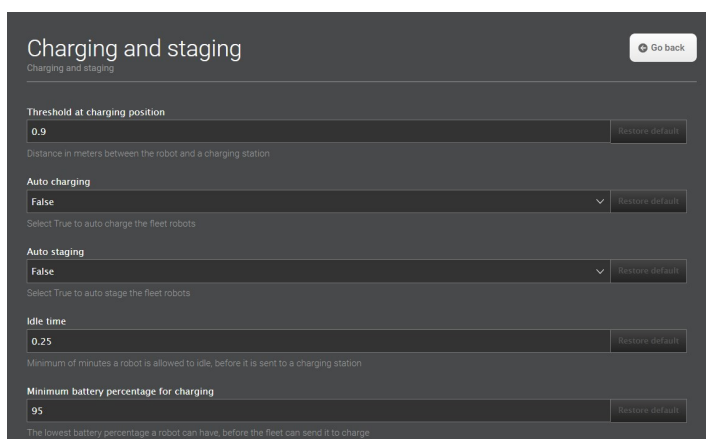
The Settings section contains the MiRFleet parameter settings.

The settings are divided into sub group, and all parameters have context help texts.



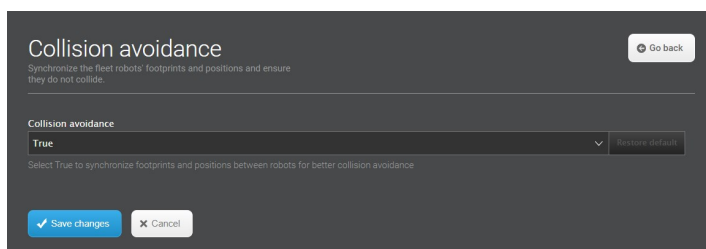
### 6.1.1. Charging and staging

In the Charging and staging section, you can set and change charging and staging settings for the robots in the fleet.



### 6.1.2. Collision avoidance

Synchronize the fleet robots' footprints and positions and ensure they do not collide.



### 6.1.3. Distributor data

Edit data about the distributor selling MiRFleet.

### 6.1.4. Date and time

You can set the system date and time manually by entering values in the fields, or automatically by selecting **Load from device**. The latter option sets the system time to the time of the computer connected to MiRFleet.

### 6.1.5. Advanced

Advanced configuration parameters

The dialog contains the following fields:

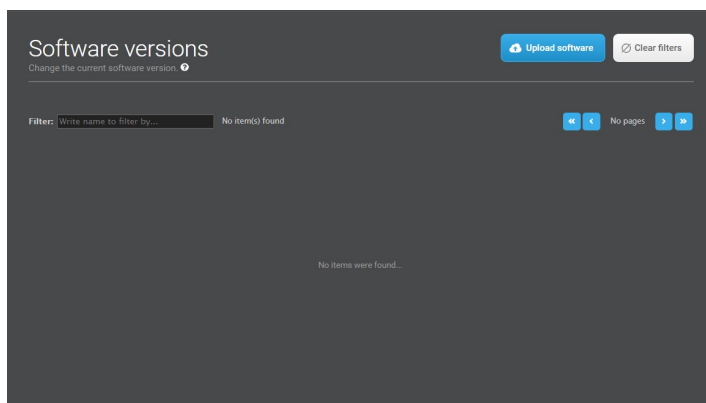
- **Restart fleet software**  
If something in the fleet system is not responding you can try restarting the fleet software.
- **Factory reset**  
Resetting the system will completely restore the system to default values. Only do this if you really want to reset the system completely.

## 6.2. Software versions

In the Software versions section, you can update the fleet to run the newest software and see a list of all previous versions installed on the fleet.

Click the Upload software button, select the software file on your computer to start the upload. You can follow the upgrade process on-screen. When finished, turn the fleet off and on, and log on to the interface again. The fleet is now ready to operate with the new software version.

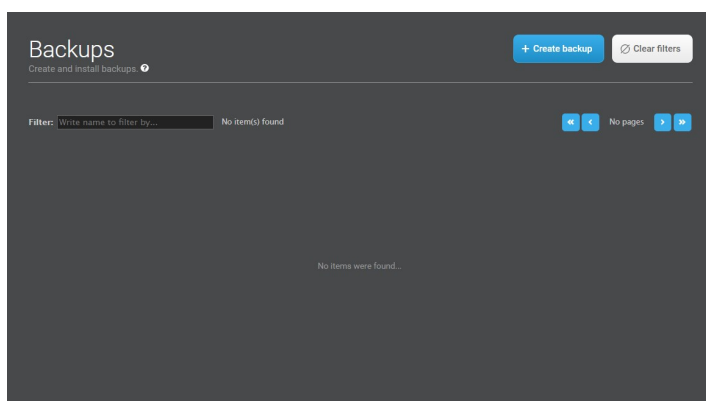
**Note:** If a hook is mounted on the robot, the hook must be updated to the same software version. Go to Hook > Software versions and follow the same procedure as for updating the robot.



## 6.3. Backups

In the Backups section, you can create a backup of the current system state and restore to a previous version of the software.

Click the Backup to create a backup of the current version. It can be useful to create a backup (snapshot) if you want to be able to revert to the exact state of the current software including data such as settings, missions, reports etc. at a later stage.



It can be useful to create a backup (snapshot) if you want to be able to revert to the exact state of the current software including data such as settings, missions, reports etc. at a later stage.

### 6.3.1. Delete backup

Backups may be deleted individually. Click the Delete backup button to remove the selected file from the system.

## 6.4. Fleet setup

This section contains the basic configuration properties.

### Configuration

You can edit the name of the product in the **Name** field.

Configuration	
Name	<input type="text"/>

## 6.5. Evacuation zones

In case of an emergency, all robots can be evacuated from one or all zones.

**Evacuation zones** make it possible to evacuate all robots in case of an emergency situation.

One or more evacuation zones can be marked up on the map and will appear on a list under **Evacuation zones**. It is possible to evacuate one certain zone or all zones at once.

Select **Evacuate all zones** to evacuate all zones (in the top bar or under Evacuation zones) or select **Evacuate** next to a specific evacuation zone to evacuate that zone. All robots will leave the selected evacuation zones and go to the nearest evacuation positions.

To give the all clear when the emergency is over, remove the ticks from the boxes from one or more zones under **Evacuated**. When the all clear has been given, the robot(s) will wait at their Evacuation position(s) for new missions.

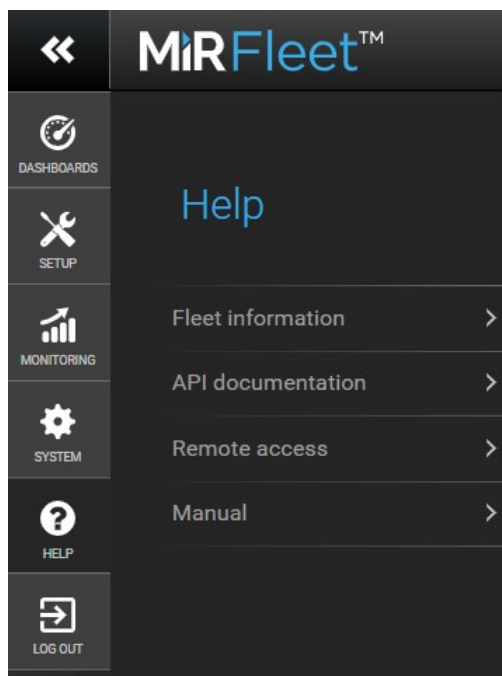
Evacuation zones should only be used in case of an emergency as all missions are discontinued.

Note: There must be at least one evacuation position per robot when Evacuation zones are applied.

Evacuation zones	
In case of an emergency, all robots can be evacuated from one or all zones.	
Name	Evacuated

## 7. Help

This section describes the items in the Help menu.



The Help menu contains the following items:

<b>7.1. MiRFleet information</b>	<b>71</b>
<b>7.2. API documentation</b>	<b>71</b>
<b>7.3. Remote access</b>	<b>71</b>
<b>7.4. Manual</b>	<b>71</b>



## 7.1. MiRFleet information

This menu item contains the following information:

- **MiRFleet name**  
This field shows the MiRFleet name.
- **MiRFleet serial**  
This field shows the MiRFleet serial number.

## 7.2. API documentation

All functionality found in the fleet interface can also be accessed through the fleet's REST API. In fact, the REST API is what the fleet interface uses to communicate with the robots - and so can your software.

You can connect to the fleet using either **<http://mir.com:8080>** or **<http://mir.com/api>**. Alternatively you can use the fleet's IP address if you are not connected to the fleet's own WiFi.

For authorization, please refer to the given example, automatically generated when you enter your username and password.

Select **Launch API documentation** to get the list of available commands. Clicking a particular command opens the dialog with extra details and the **Try it out** button.

## 7.3. Remote access

MiR Remote makes it possible to give members of the MiR Support team remote access to the fleet's software. This will in many cases help solving a software problem quickly and will save you, as customer, time on complex problem descriptions.

You have command of the remote session, which means that you can retrieve access at any time by clicking the Disconnect button.

During the remote access session, you can continue using the fleet if the problem you need solved allows it.

## 7.4. Manual

A copy of this reference guide is available in the interface. To access the guide, go to: Help > Manual.