

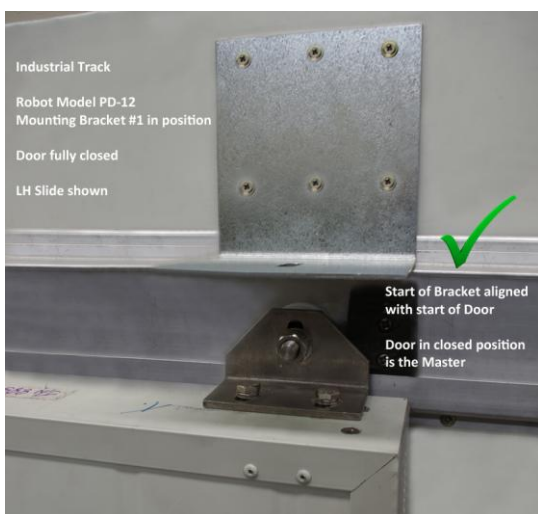
INSTALLATION INSTRUCTIONS ROBOT MODEL PD-12

1/ Doors and door tracks must **not** be damaged in any way and be in perfect working order, with no binding of door or door track components. Door must **easily** roll in tracks when operated manually by hand.

2/ Close door fully. Mount securely to wall 1off mounting bracket, positioning the bracket on top of the door track and align the start of the bracket with the start of the door



RH Slide shown, Commercial Track



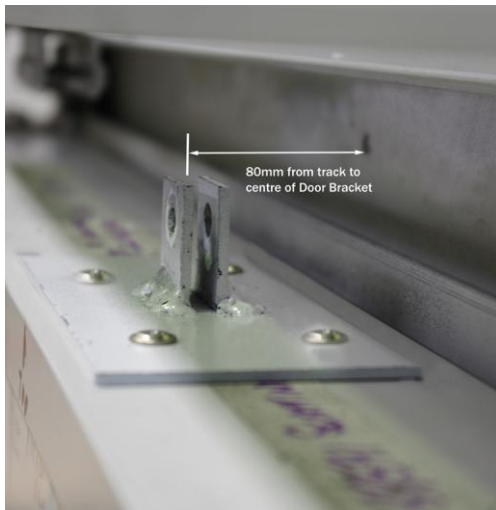
LH Slide shown, Industrial Track

3/ After 1st mounting bracket is in position measure back position of 2nd mounting bracket in relation to mounting bolts on the Robot and securely fix 2nd bracket to wall also sitting on the track as with the 1st bracket



RH Slide Door fully closed. 2 mounting brackets in position ready to accept Robot Door opener

4/ Mount Door Bracket with Release Arm on top of door capping. Centre of door Bracket legs 80mm out from wall or track



Door Bracket securely fixed to capping

And from the start of door back 600mm to the centre of bolt hole on door bracket if the clear opening is up to 1200mm. (200mm release arm used)

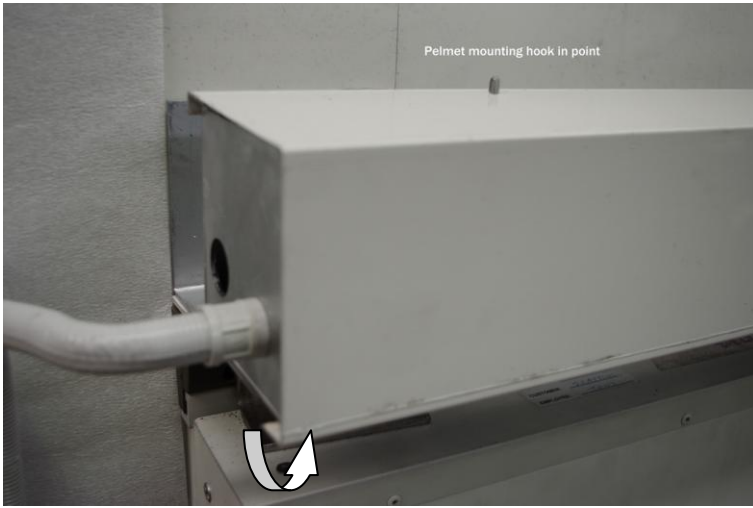
And from the start of the door back 700mm to the centre of bolt hole on door bracket if the clear opening is 1300mm to 1400mm. (300mm release arm used). As in following diagram.



5/ Position Robot PD-12 opener onto mounting brackets. Centre of mounting bolts and centre trolley 80mm out from the wall or track. It is advised Colorbond pelmet be removed from Robot prior to mounting Robot onto brackets to prevent damage to pelmet cover. Pull out pelmet from bottom edge of both front and rear Robot base plates and lift off from hook in studs.

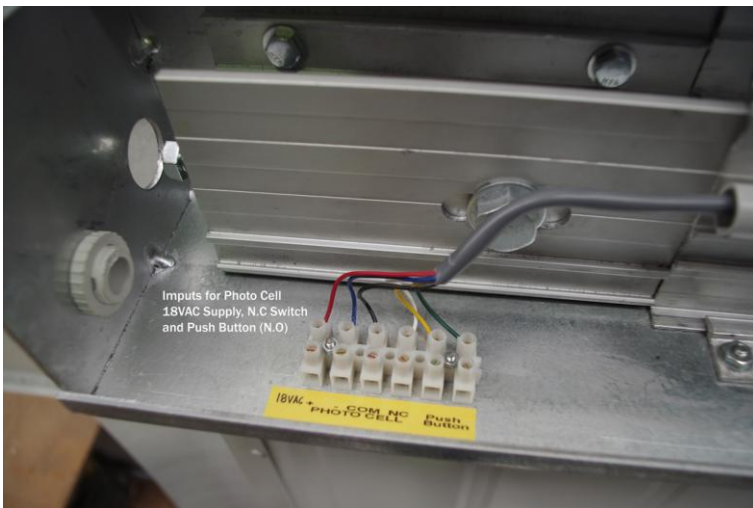


centre of trolley and centre of mounting bolts 80mm out from wall or track



pelmet hook in stud and pelmet wrapped around base plate. Arrow shows Pelmet removal.

6/ Install Push Buttons and wire up via terminal strip mounted on base plate



20mm conduit adapter entry for wiring



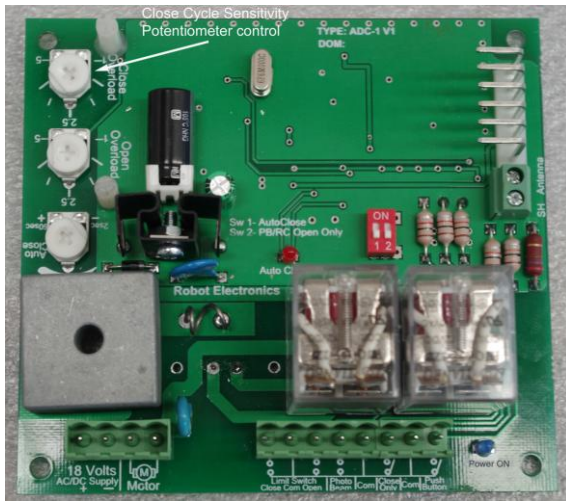
RH Slide shown. Robot PD-12 installed C/W Push Button, without pelmet

7/ Connect release arm via quick release to Robot trolley.



Reed switch and Quick release

Run Robot with door attached. ENSURE DOOR DOES NOT RUN INTO STOPPERS. Adjust door travel via reed switches in Robot track, (move in adjustment slot). Stop door travel 10 - 15mm before stoppers.



8/ Robot Model PD-12 is fitted with a potentiometer controlled auto reverse sensitivity setting on the closing cycle. If the door comes in contact with an obstruction upon closing cycle it will reverse back automatically to the open position. Adjust sensitivity closing force if required. If sensitivity is set too light door may auto reverse on its own without any obstruction, and with a setting too heavy the door will keep driving and not automatically reverse when an obstruction is met. Close force adjustment potentiometer is found on the PCB, under the Module cover. On open cycle, if the door is met with an obstruction, the Robot will cut out on overload and stop. This adjustment potentiometer is factory set and should not need adjusting. Additional PCB programmable functions via ON/OFF dipswitches are Auto Close timer (2sec - 60sec) and Push Button/Radio Control OPEN ONLY. This function can also be utilized for Microwave Radar Sensors to open the door or Floor Induction Loops to open the door by connecting the switch wires from these devices to the Push Button connections on the base plate terminal strip.

9/ Fit Colorbond Pelmet cover by locating the 2 holes in the Pelmet cover over the hook in studs on top of the base plates and then snap fit the front lower edge of the pelmet cover around the lower edge of the base plates