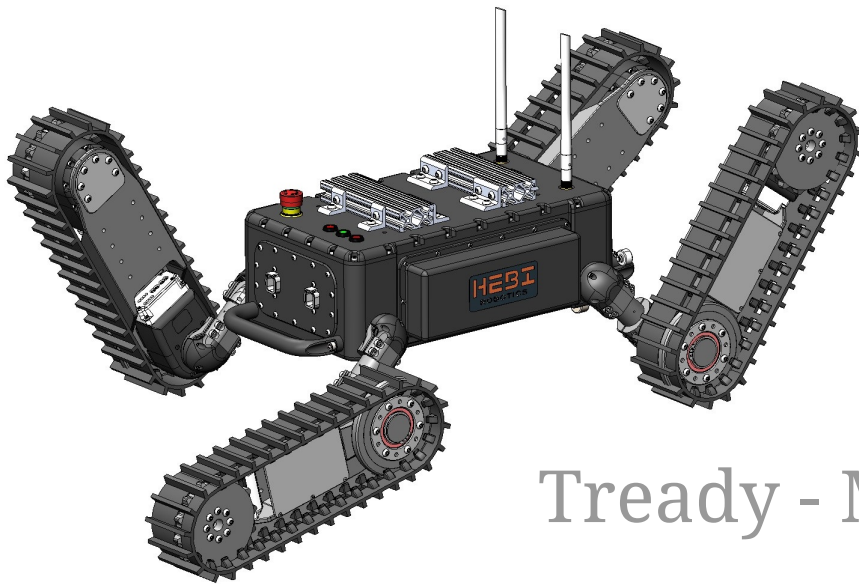


HEBI

ROBOTICS



Tready - Manual

HEBI Robotics

Version 2.0, 19 Aug, 2024

Contents

Revisions	1
1. Overview	2
1.1. Videos	2
1.2. Technical Specifications	2
1.3. Main Components and Features	3
1.4. Buttons and Bulkheads	5
1.5. Accessories	7
2. Startup	10
2.1. Power On	10
2.2. Control Interface (HEBI Mobile IO App)	12
3. Batteries	13
3.1. Charging	13
3.2. Installing / Swapping	14
4. Documentation	15
4.1. Datasheets and Drawings	15
4.2. Wiring Diagrams	18
5. For More Information	20
5.1. HEBI Documentation (docs.hebi.us)	20
5.2. HEBI Community Forum (forums.hebi.us)	20
5.3. HEBI CAD Repository (cad.hebi.us)	20
5.4. Contact Us	20

Revisions

Rev.	Date	Author	Description
0.1	21 Nov, 2022	A Willig	Initial manual draft.
1.0	25 Feb, 2023	A Willig	Updated Drawings and Manual with newest Tready Design. Dual panel bulkheads front and back, updated bulkhead connectors. Official Release.
2.0	19 Aug, 2024	A Willig	Updated with newest Tready Design incorporating HEBI Wattman Batteries, long-range WiFi, and updated bulkheads.

1. Overview

This manual documents the setup and operation of the HEBI Tready Mobile Base Kit.

1.1. Videos

- Kit Release Video: <https://www.youtube.com/watch?v=RyusD0KFCp8>
- Inspection Robots Video: <https://www.youtube.com/watch?v=tEoKngE73xk>

1.2. Technical Specifications

Specifications subject to change without notice.

Onboard Computer

Computer Model: Intel NUC Pro 13

OS: Ubuntu 22.04 Desktop

Username: hebi

Password: hebi1234

IP Address (on robot network): 10.10.1.2

Onboard Router

Router Model: Mikrotik hEX RB750Gr3 Gigabit Router

Configuration: Ethernet ports bridged, DHCP server on bridge.

IP Address: 10.10.1.1

Router Login: admin

Router Password: hebi1234

https://mikrotik.com/product/hap_ac3

WiFi Access Point: TP-Link EAP225 Outdoor

Wifi Bands: 2.4Ghz & 5Ghz (802.11a/b/g/n/ac)

2.4Ghz Wifi Network Name: Tready-<customer-name>

5Ghz Wifi Network Name: Tready-<customer-name>-5

Wifi Password: hebi1234

Batteries: <https://docs.hebi.us/hardware.html#battery>

4X HEBI Wattman Lithium Ion Battery

Capacity: 93.6 Watt Hours each (36V, 2.6Ah)

Discharge Profile: 7.8A continuous, 13A max each (27.5V Cutoff)

Operating Time: 2-3 Hours continuous operation

Dimensions: 206 x 80 x 25 mm

Weight: 650 g (1.43b) per battery

The system uses 4 HEBI Wattmann batteries (2 on each side) to provide approximately 400 Wh of energy and a minimum of 2 hours of continuous robot operation on a full charge.



Please refer to [Chapter 3](#) for instructions on working with the Wattman batteries in the Tready system.

1.3. Main Components and Features

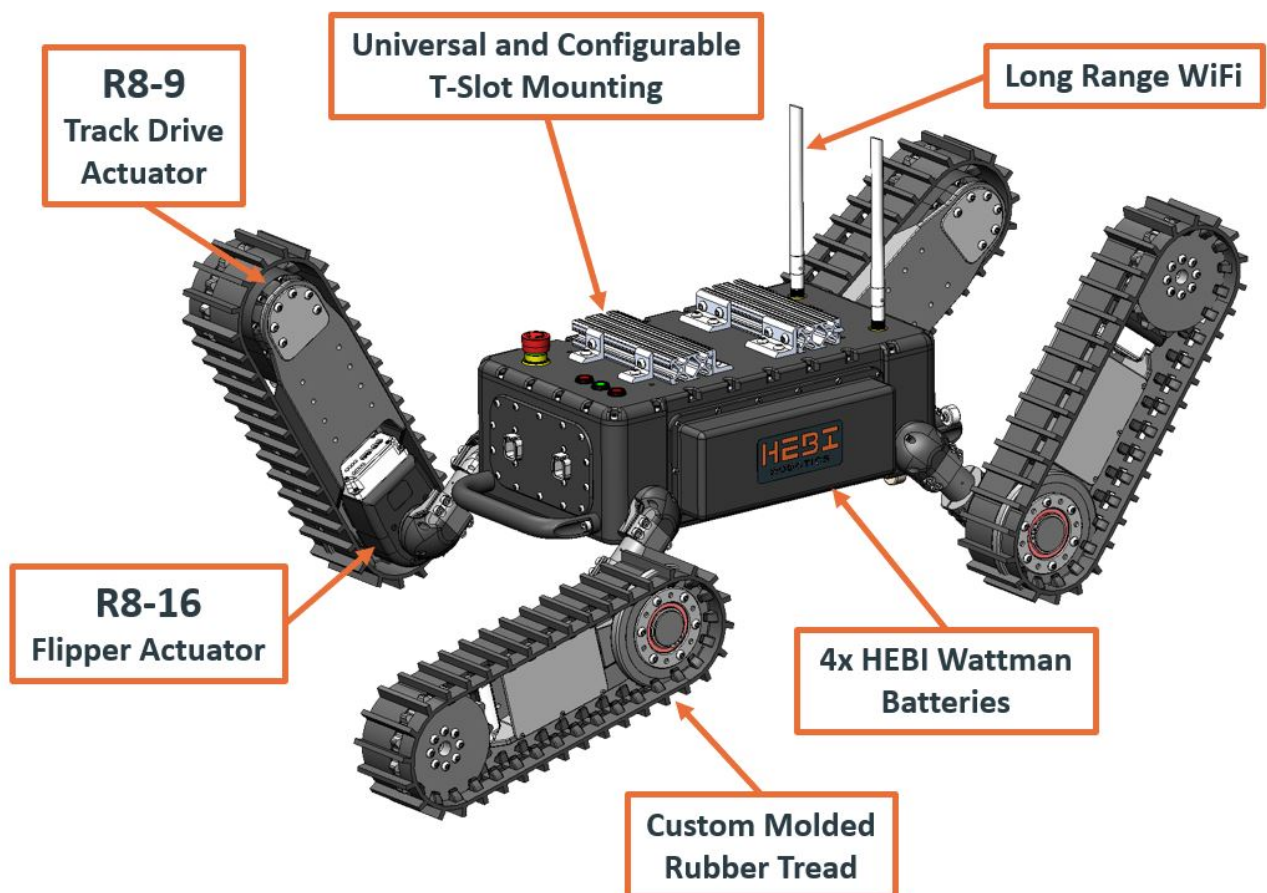
The Tready Mobile Robot Kit comes standard with an IP67 field deployable chassis that includes:

- ergonomic handles to assist with handling the robot
- sealed bulkheads for all connections required for connecting power and communications to additional components or external computers
- universal and configurable T-Slot mounting to the top of the robot using an optical bench style mechanical interface
- 4 mounted HEBI Wattman Lithium Ion batteries

In addition to the field chassis, Tready comes with 4 modular track units that includes:

- an R8-16 Actuator to control the independant flipper motion
- an R8-9 Actuator to control the driving of the track (swappable to R8-3 for higher speed, but reducing overall payload capability)
- a custom designed molded track.

a. Tready Robot Main Features



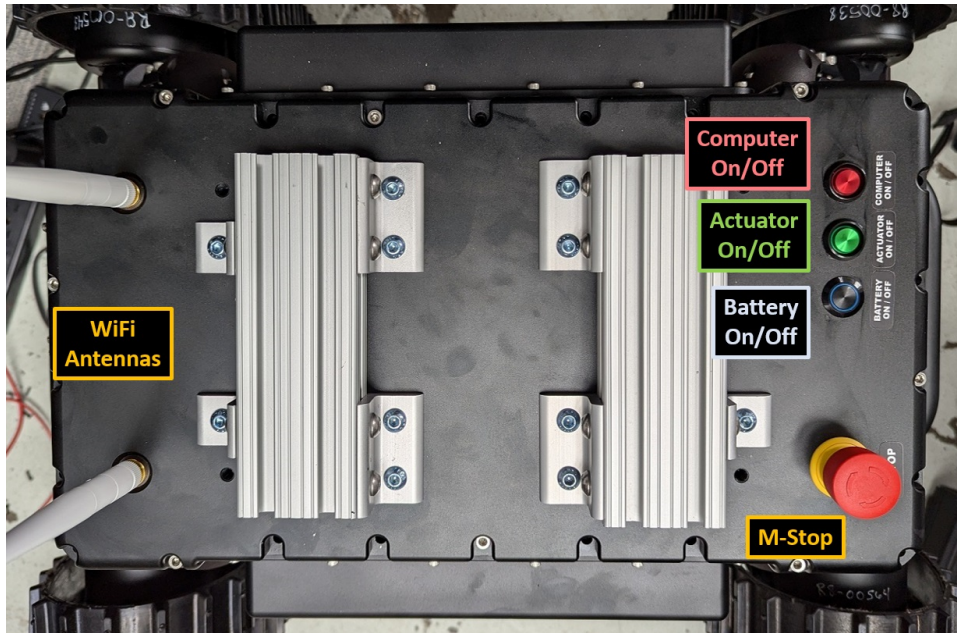
b. Robot example addition - 6-DoF R-Series Arm with Gripper



1.4. Buttons and Bulkheads

The following figures depict the various buttons and bulkheads on the main robot chassis and their function. Additionally, Tready's front and rear bulkhead panels can be customized different from the standard configurations shown in this manual to better fit the specific application the platform will be used for. Please contact engineering@hebirobotics.com for more information on customizing these bulkheads.

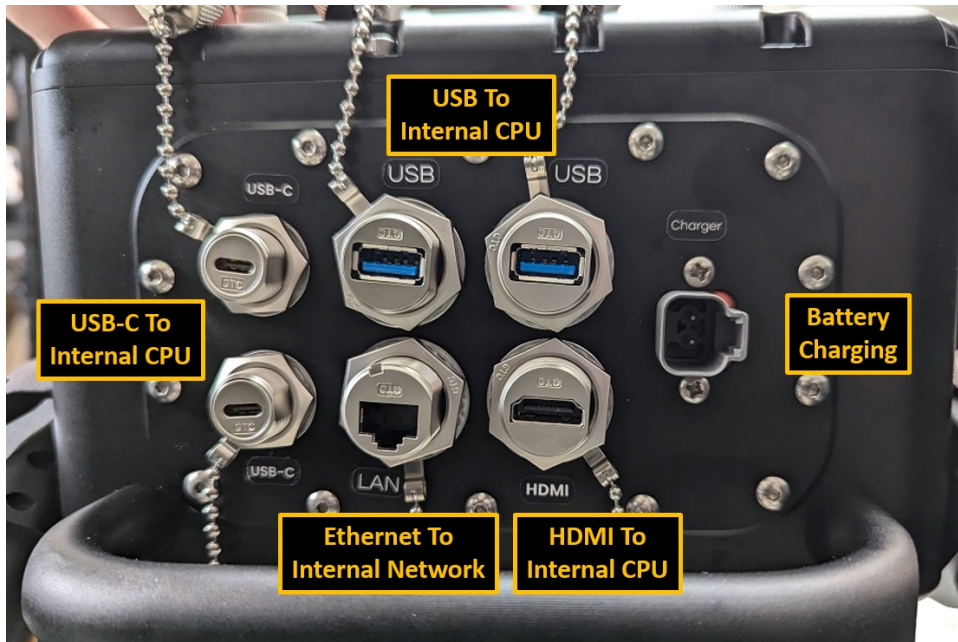
- a. Top view of robot chassis and associated buttons and bulkhead components.



- b. Front view of robot chassis and associated bulkhead components.
 (1: V+ | 6: GND | 2: MS+ | 5: MS- | 3-4: Plastic Optical Fiber Data)



c. Rear view of robot chassis and associated bulkhead components.

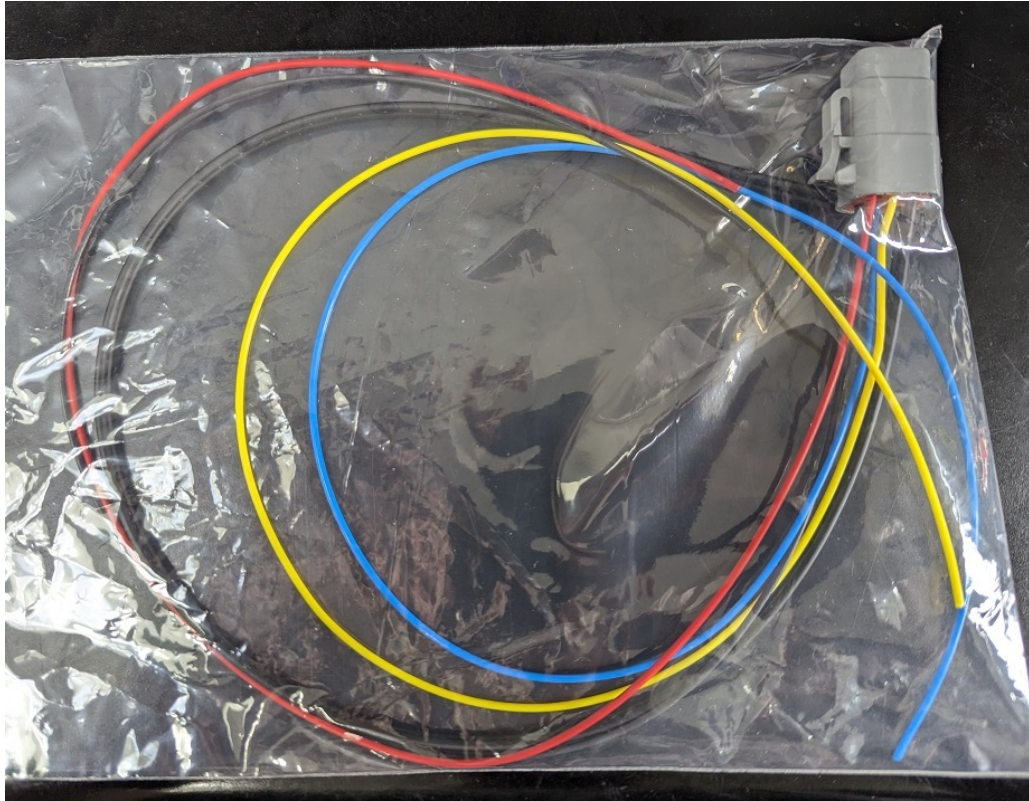


1.5. Accessories

a. Accessory Power, M-Stop, and Data Connection

(Red: V+ | Black: GND | Yellow: MS+ | Blue: MS- | Plastic Optical Fiber Data)

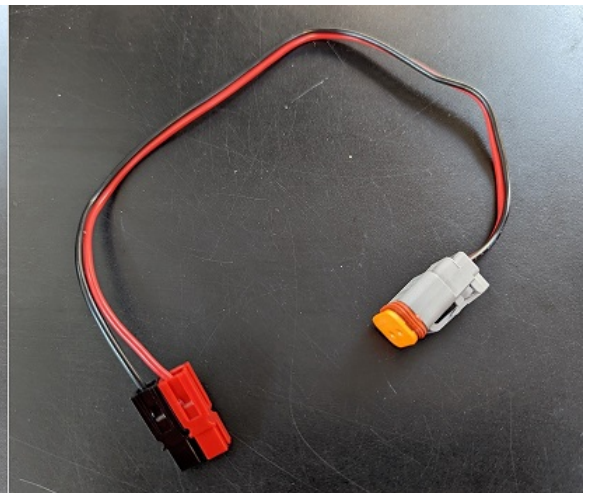
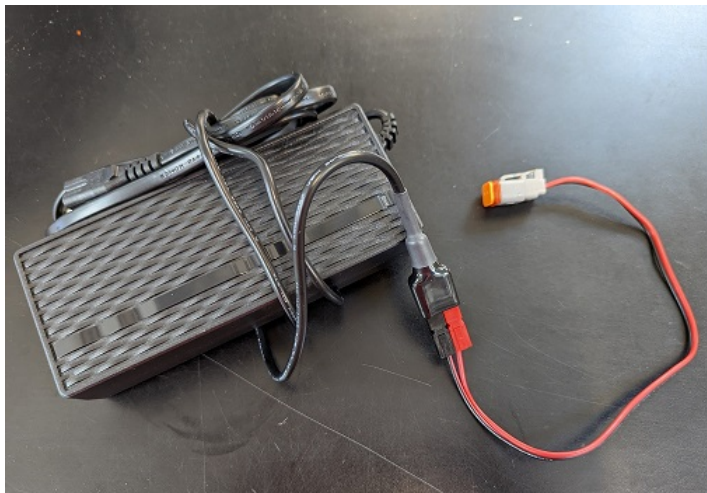
[ATM06-6S Connector Kit](#)



b. Battery charging bulkhead adapter & Charger

[DT06-2S Connector Kit](#)

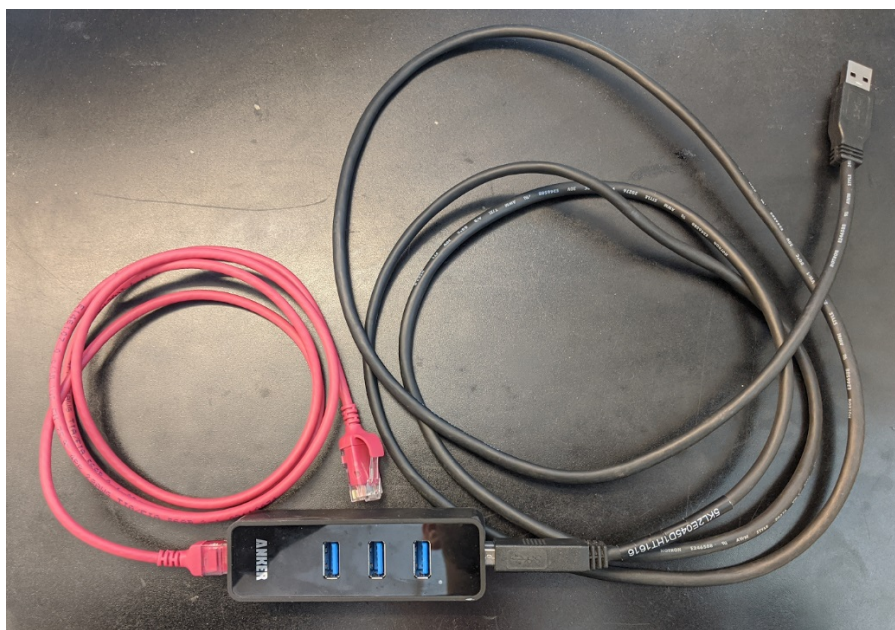
[Powerpole Connector Kit](#)



c. Track tensioning tool



d. Ethernet-to-USB Adapter and USB Hub for Network-to-Computer communications
3-Port USB Hub with Gigabit Ethernet Converter (Amazon)

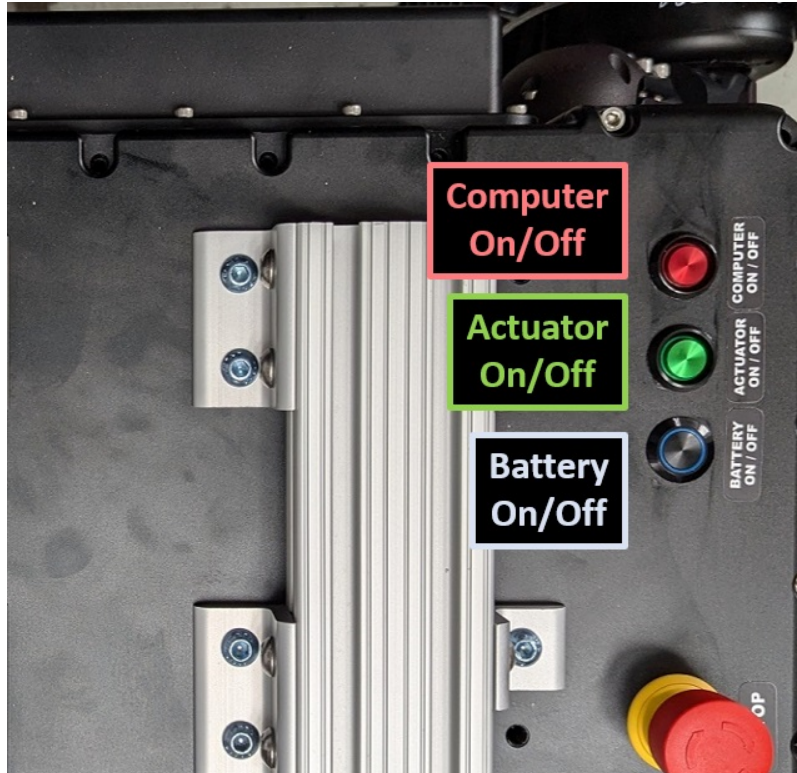


e. Connection Toolbox
(Includes tools for both R-Series Actuators and Tready Robot)

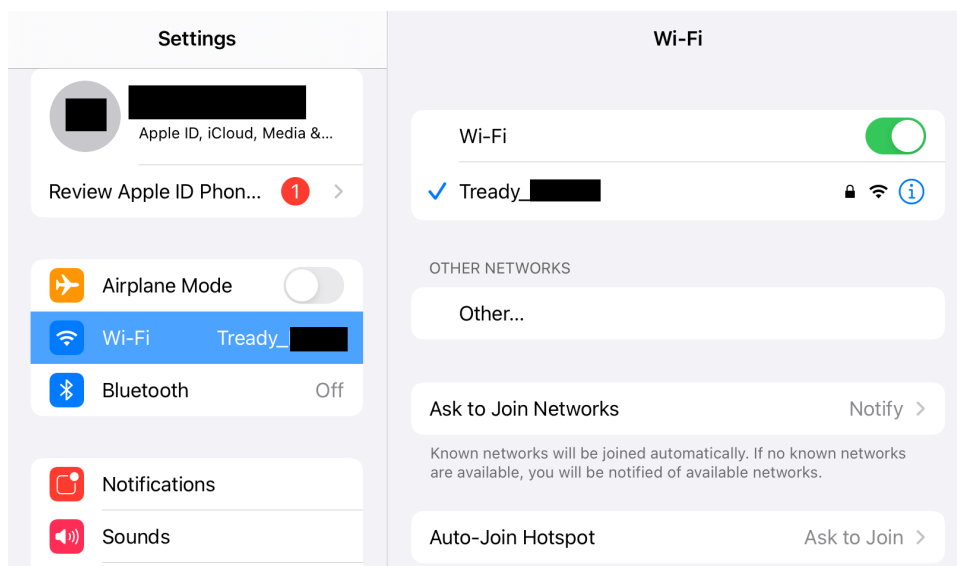


2. Startup

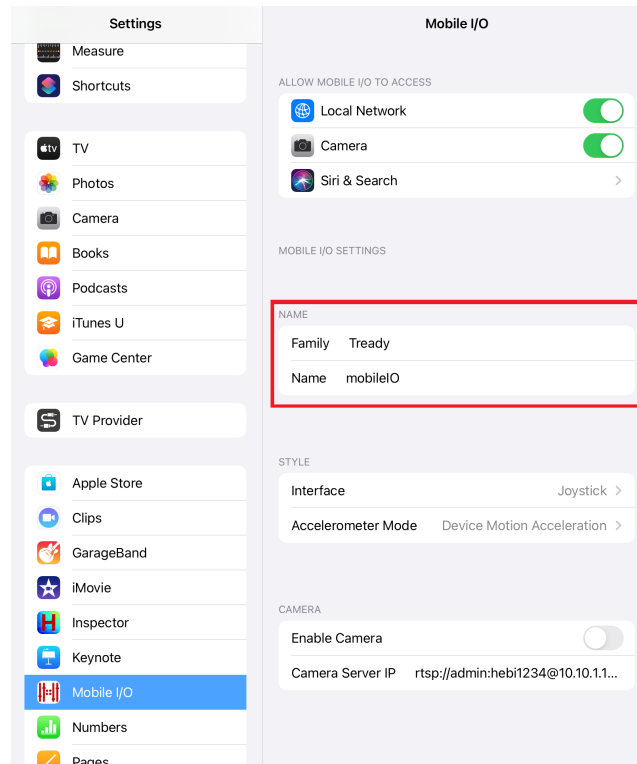
2.1. Power On



1. Press and hold the "Battery On/Off" Button (Blue) until you hear a faint beep from the batteries and the button's LED lights up. This turns battery power on which power on the robot's networking system.
2. On your mobile control device check for Tready's WiFi to appear and connect to it (Password: hebi1234)



3. Make sure that the correct Family and Name are set on your mobile device in the "Mobile I/O" Settings.



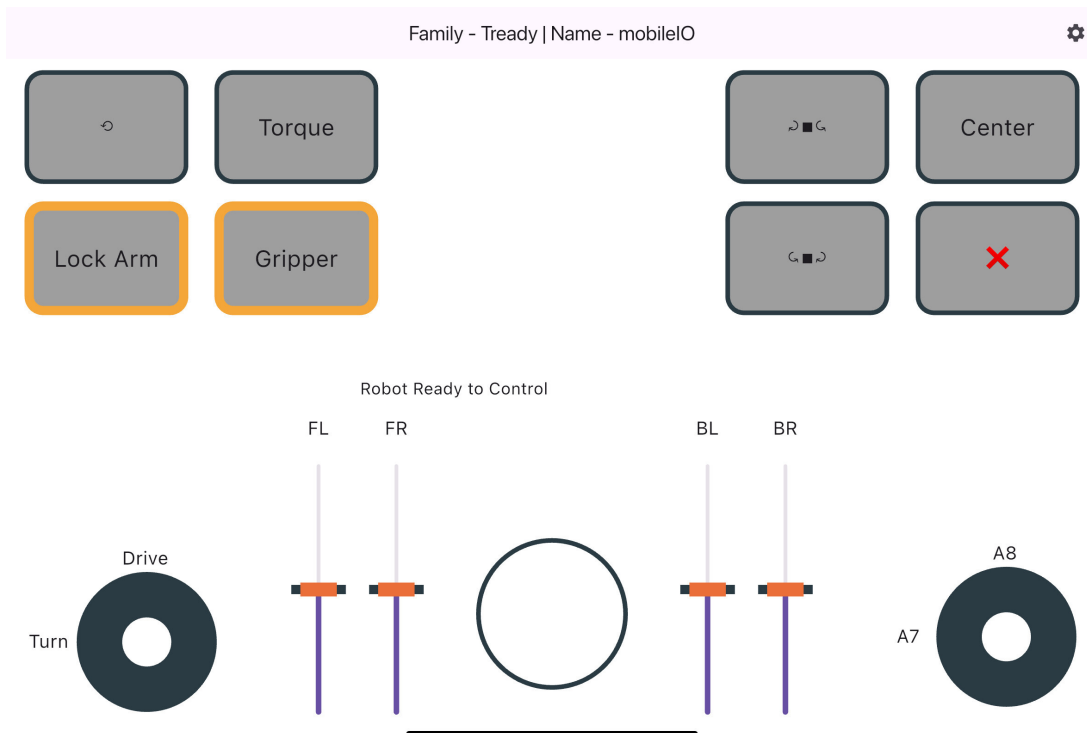
4. Press and hold the "Actuator On/Off" Button (Green) until the button's LED lights up. This sends power to the R-Series Actuators on Tready's tracks as well as the front bulkhead panel for any other accessory components.
5. Wait for the actuators to go from a LED status of green/orange blink to slow green fade. This means that they have acquired an IP Address from the robot's network.



6. Press and hold the "Computer On/Off" Button (Red) until the button's LED lights up. This powers on the system's internal CPU. Tready's control code will autostart as long as you have the mobile device connected to the robot's WiFi and the HEBI Mobile I/O App open. <<<

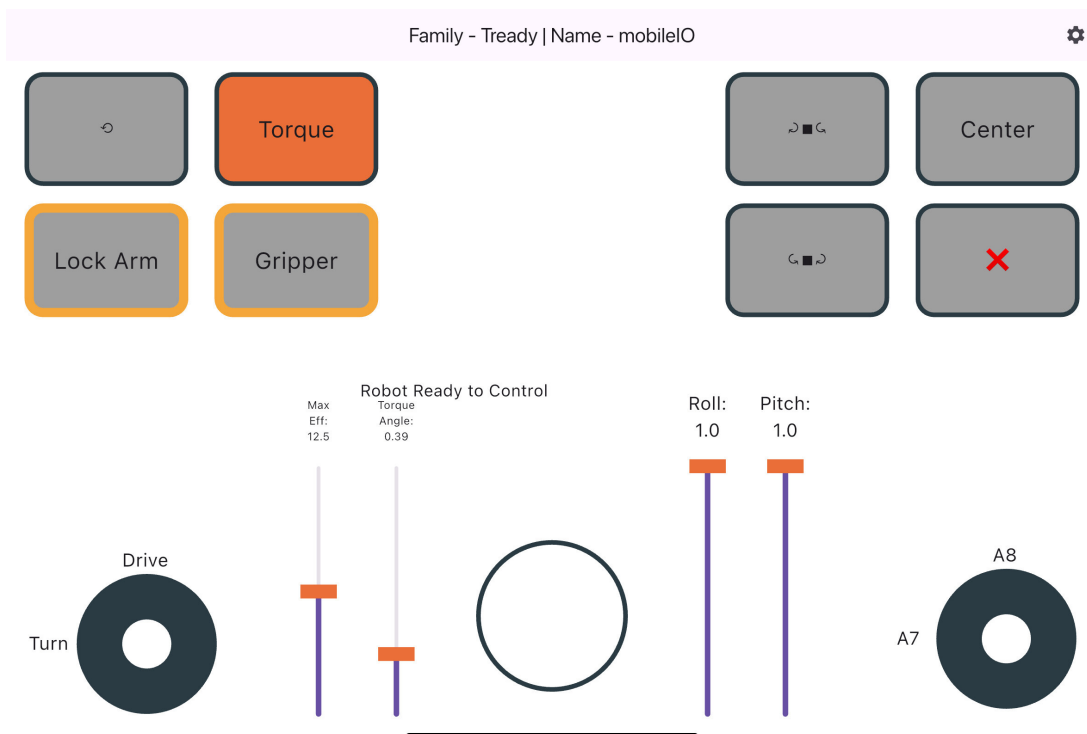
2.2. Control Interface (HEBI Mobile IO App)

1. Main Control Screen



2. Flipper Torque Control Mode Screen.

In this mode Tready's tracks use torque control to interact with the ground in order for better base stabilization. The **Roll** and **Pitch** sliders can be used to adjust how level the chassis of the system is kept relative to gravity.



3. Batteries

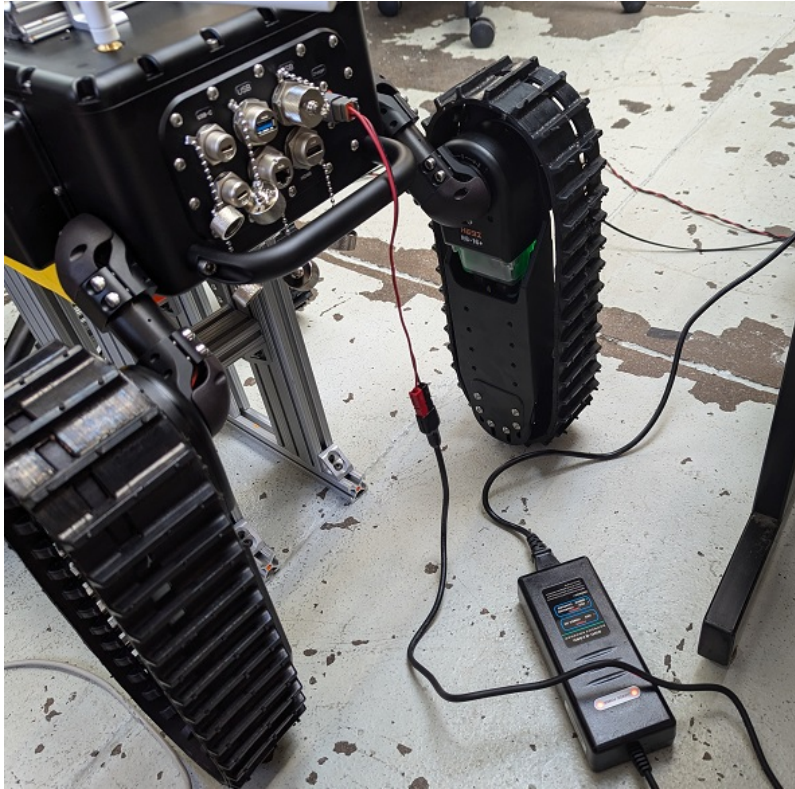
3.1. Charging



Chargers must be 42V and ~1-1.5A per battery.

To charge the HEBI Wattman Batteries they must be powered on.

While in Tredy's chassis Power on the batteries on Tredy using the "Battery On/Off" (Blue) Button and then plug in the Charger to the rear charger bulkhead.



To charge batteries not in Tredy's chassis use a Battery Connector Cap to turn on and connect the Wattman battery to a charger.

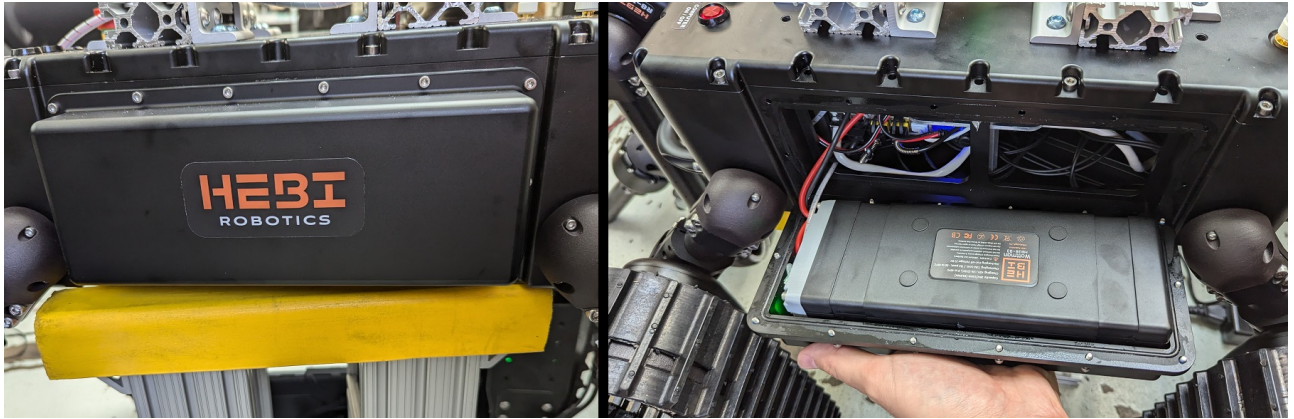


3.2. Installing / Swapping

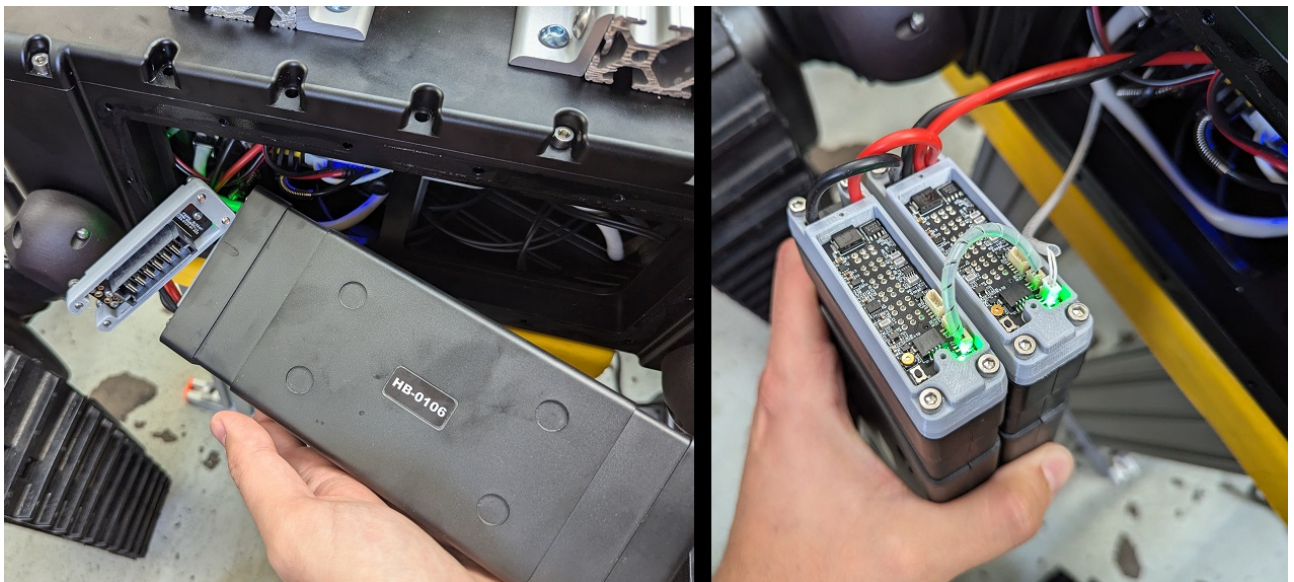


Make sure battery power is OFF when doing an install or swap.

1. In order to install or swap out batteries in Tready unscrew the side cover from the chassis.



2. Remove the side cover and carefully take the batteries down from the side cavity in the chassis.
3. Unscrew the connector caps from the batteries and install/swap the batteries.



4. Install the batteries back into the cavity with the covers.



Be mindful of the small wires that go between the battery connectors in the Tready chassis. These are integral for controlling the batteries together with the button on the chassis lid.

4. Documentation

4.1. Datasheets and Drawings

a. R-Series Actuator Datasheet

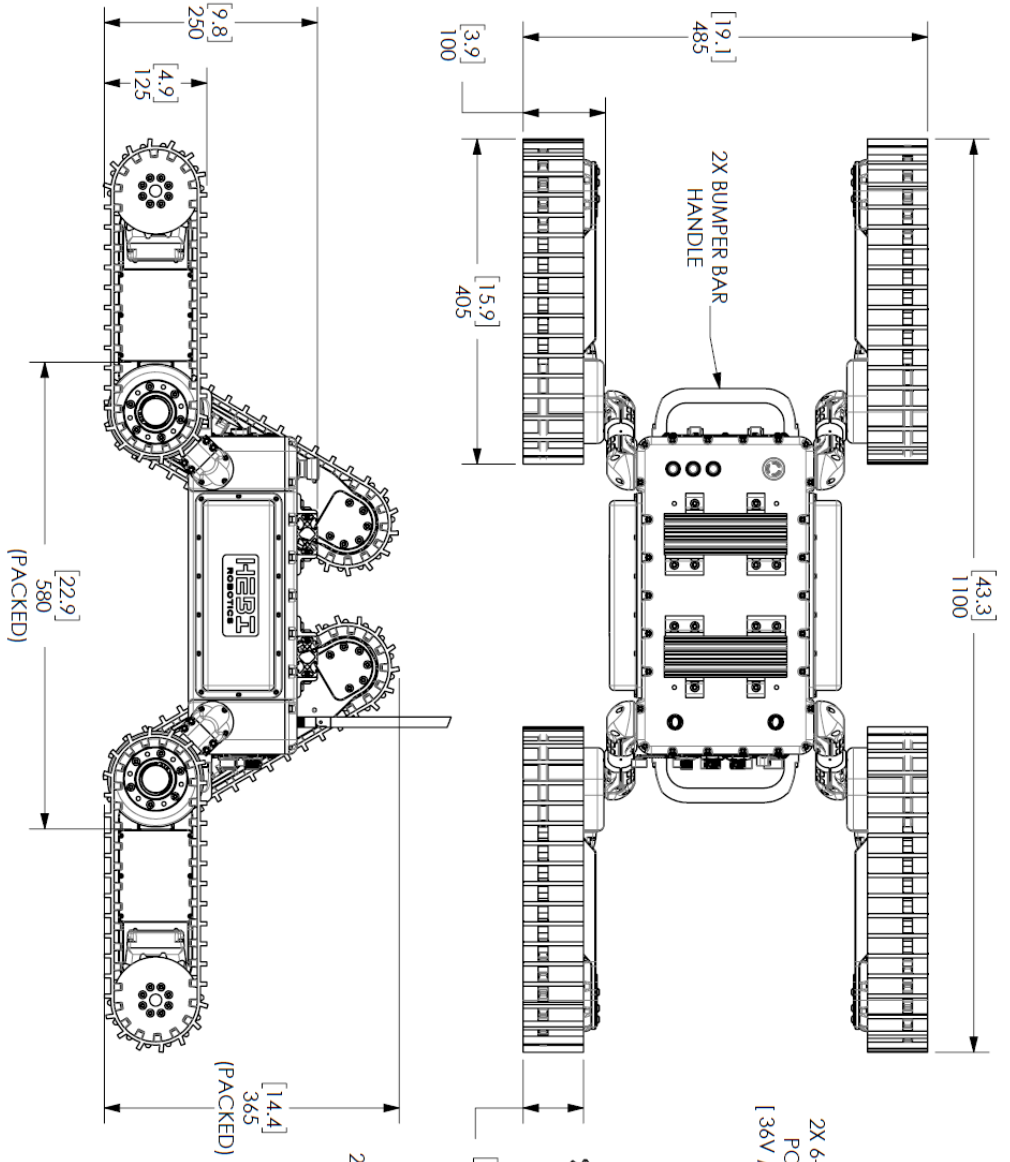
R-SERIES ACTUATOR – TECHNICAL SPECIFICATIONS

CONFIGURATION	R8-3	R8-9	R8-16
Peak Torque	7 N-m	20 N-m	38 N-m
Cont. Torque	3 N-m	8 N-m	16 N-m
Max Speed	84 RPM	30 RPM	15 RPM
Mass	670g	685 g	715 g
Dimensions	156mm x 78mm x 51mm 15mm hollow bore		
Power	24-48V DC Cont. Current: 1.3 A @ 36V Peak Current: 3.0 A @ 36V		
Environment	-10°C to 50°C Ambient / IP67		
Communication	2X 100 Mbps Plastic Optical Fiber (Optolock®)		
Angular Resolution	0.005°		
Torque Resolution	0.01 Nm		
Backlash	+/- 0.25°		
Sensing	Angular Position (multi-turn absolute, +/- 4 turns) Angular Velocity Output Torque 3-axis Accelerometer / Gyro Temperature Voltage Current Internal Pressure		
API Support	MATLAB (Windows / Linux / OS X) ROS (Linux) Python (Windows / Linux / OS X) C/C++ (Windows / Linux / OS X) C# (Windows)		

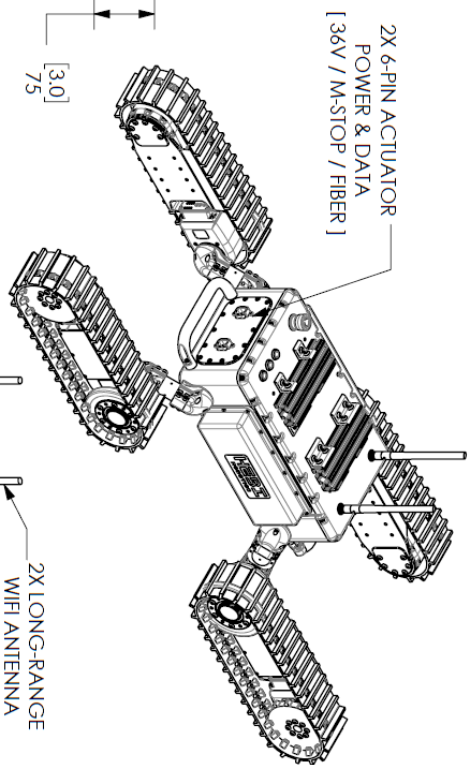
Each order of R-Series Actuator includes a standard connection kit.
Additional technical documentation at docs.hebi.us
Updated on October 1, 2021. Specifications subject to change without notice.

b. Tredy robot platform mechanical drawing.

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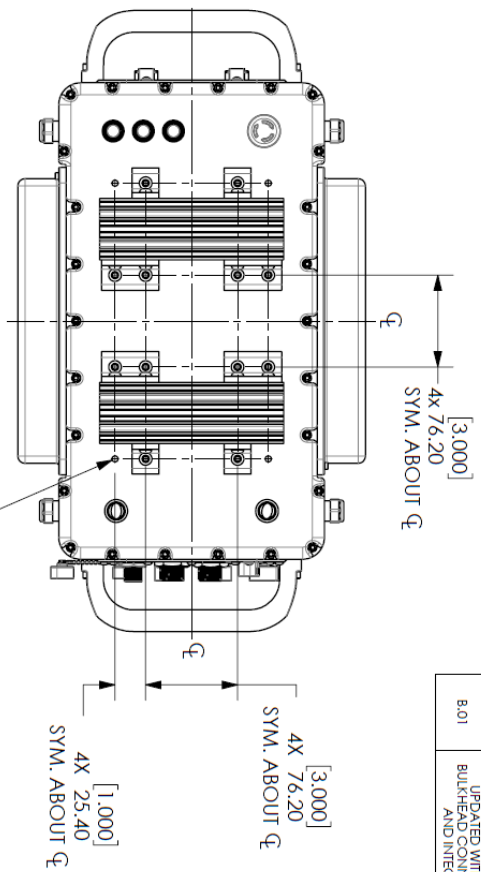
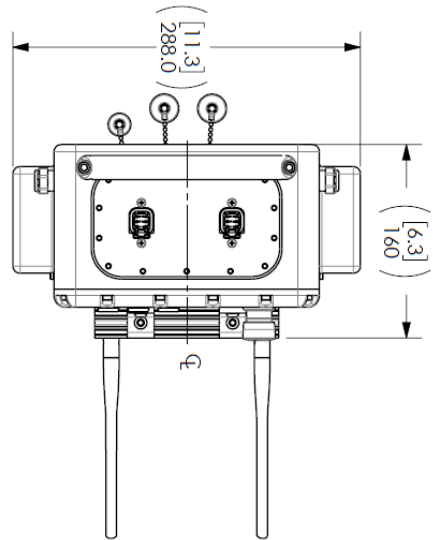
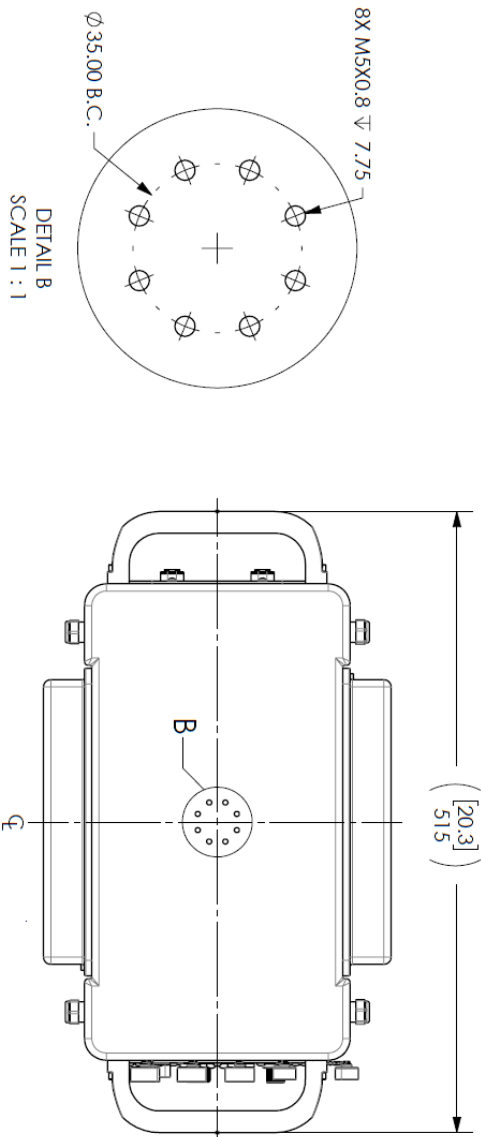
REV.	DESCRIPTION	DATE	APPROVED
A.01	INITIAL DRAFTING AND LAYOUT.	10 AUG 2021	A WILLIG
A.03	CHANGED BULKHEAD CONNECTORS.	OCT 2022	A WILLIG
B.01	UPDATED WITH LONG-RANGE WIFI, IMPROVED BULKHEAD CONNECTORS, RELOCATED HANDLE BAR, AND INTEGRATED WATTMAN BATTERIES.	12 AUG 2024	A WILLIG



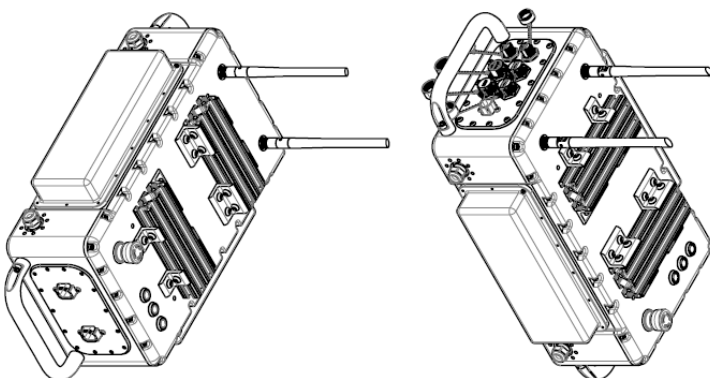
AUTHORIZATION		HEBI ROBOTICS, INC.	
DATE	AUG 2021	91 43rd St, Suite 200	
DESIGNER	A WILLIG	Pittsburgh, PA 15201	
DATE	2021	PROJECT	HEBI Kits
UNLESS OTHERWISE SPECIFIED DIMENSIONS ARE IN MM			
DO NOT SCALE DRAWING			
TOLERANCES:	X.X	±.30	REV. VER
	X.XX	±.08	B.01
ANGLES	±1.00°		
SCALE:	1:6	WEIGHT:	25 KG
		SHEET:	1 OF 1
R-Series Tredy Robot Kit			

c. Field chassis mechanical drawing.

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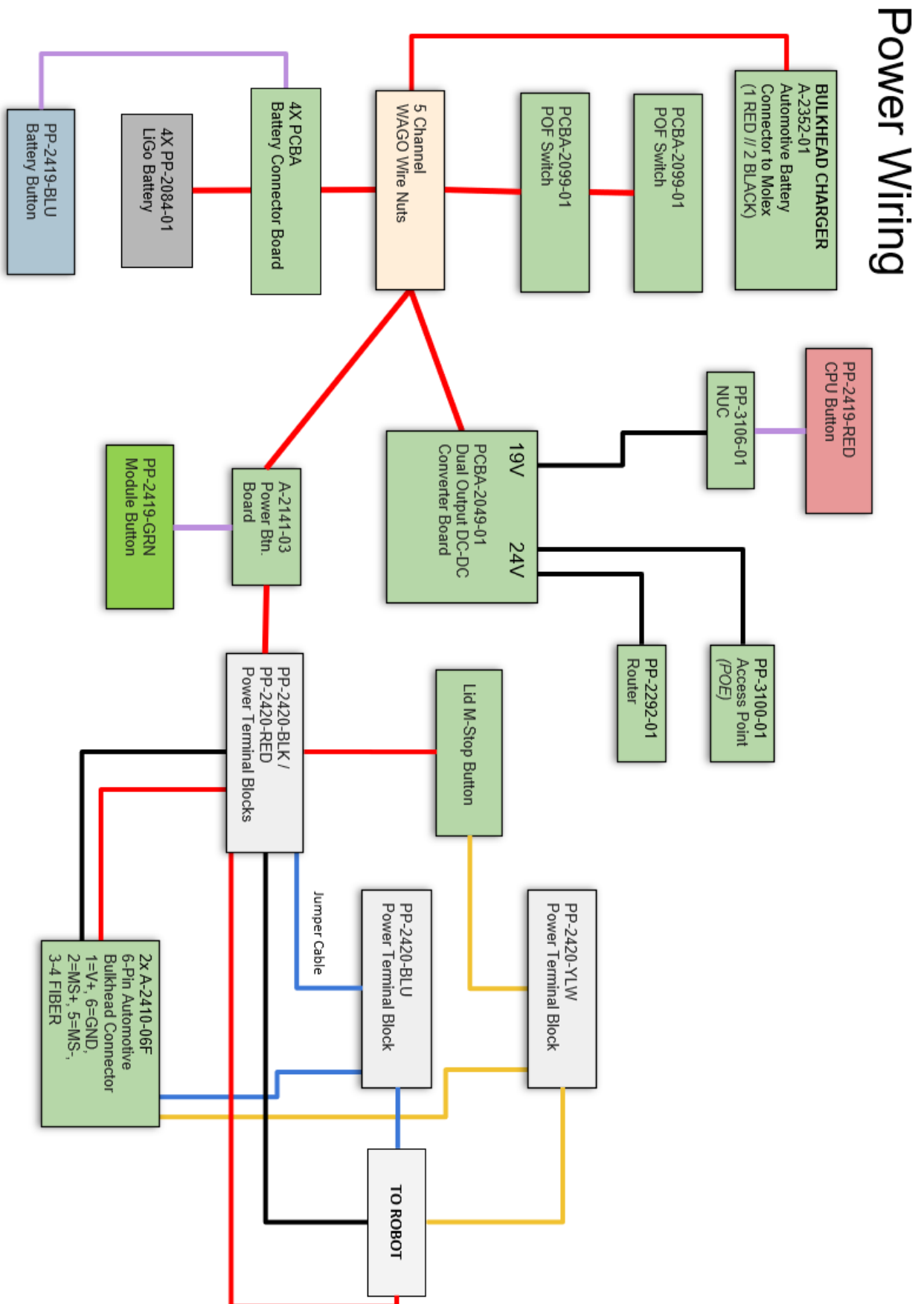
REVISIONS		DESCRIPTION	DATE	APPROVED
REV.	A.01	INITIAL DRAFTING AND LAYOUT.	11 AUG 2021	A WILLIG
	A.02	CHANGED FRONT TO BULKHEAD PANEL.	24 FEB 2023	A WILLIG
	B.01	UPDATED WITH LONG-RANGE WIR. IMPROVED BULKHEAD CONNECTORS, RELOCATED HAND LEVER, AND INTEGRATED WATTMAN BATTERIES.	12 AUG 2024	A WILLIG



AUTHORIZATION		HEBI ROBOTICS, INC.	
DESIGNED BY	A WILLIG	91 43rd St, Suite 200	
DESIGNED DATE	AUG 2021	Pittsburgh, PA 15201	
CHECKED BY	A WILLIG	PROJECT	HEBI KITS
DATE	2021	HEBI Field Chassis Assembly	
UNLESS OTHERWISE SPECIFIED DIMENSIONS ARE IN MM			
DO NOT SCALE DRAWING			
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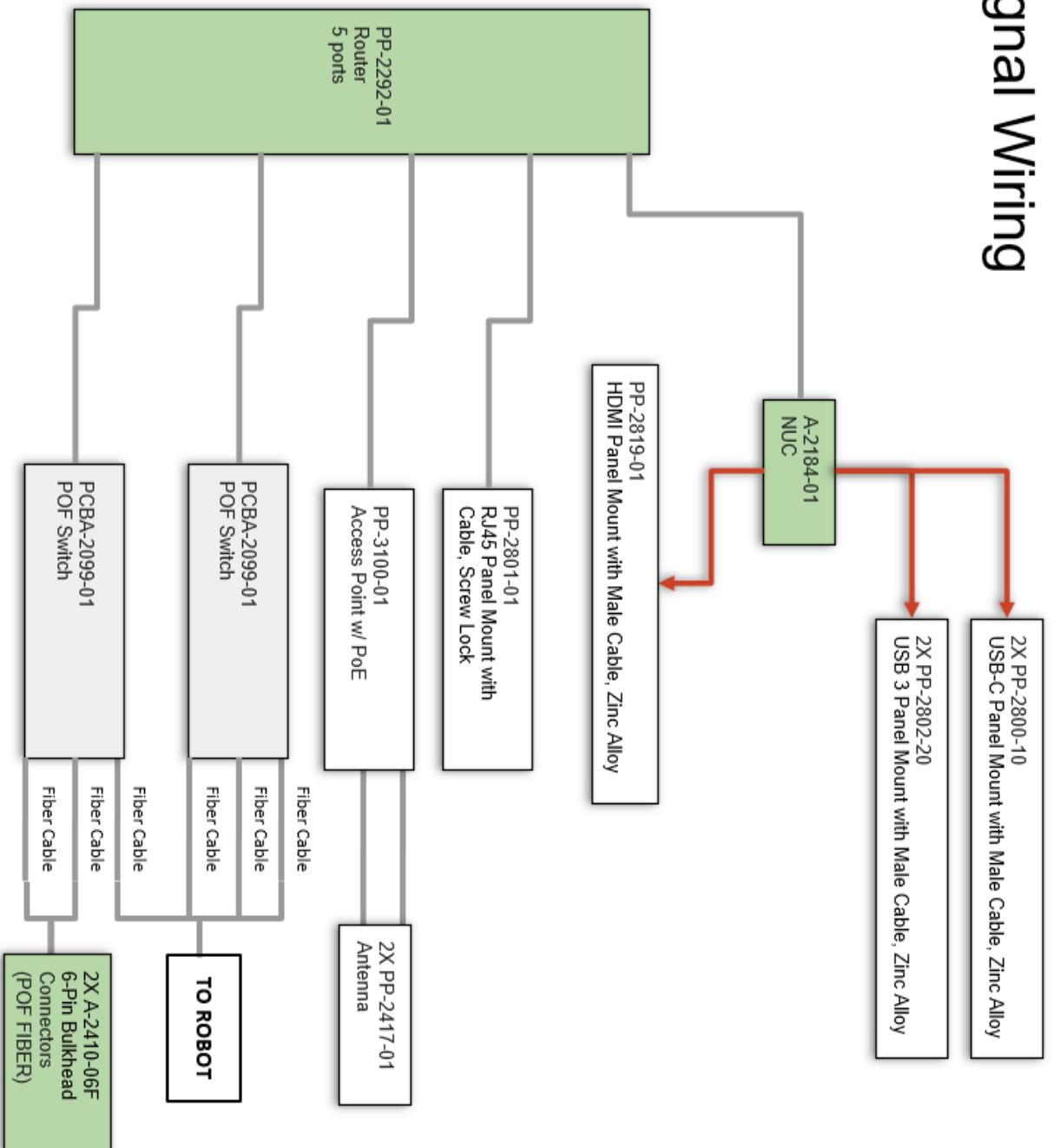
4.2. Wiring Diagrams

a. Power wiring schematic for Tready robot platform.



b. Signal wiring schematic for Tready robot platform.

Signal Wiring



5. For More Information

5.1. HEBI Documentation (docs.hebi.us)

- Quick-start guides
- Core concepts background information
- Mechanical documentation
- Software walkthroughs
- Downloads

5.2. HEBI Community Forum (forums.hebi.us)

- Regularly monitored by HEBI Engineers
- Collaborate with fellow HEBI users
- A platform to share your successes

5.3. HEBI CAD Repository (cad.hebi.us)

- CAD files and drawings

5.4. Contact Us

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