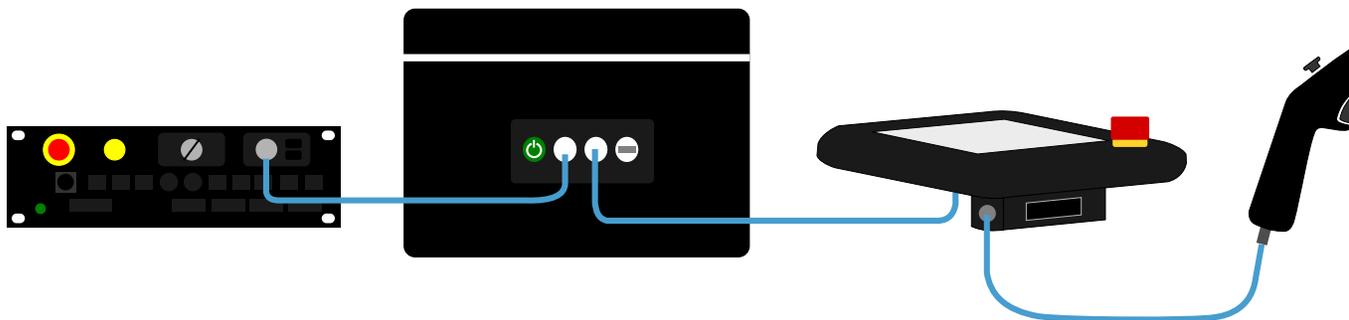


1 Connect the SIM to the case

2 Connect the tablet to the case

3 Connect the wand to the under side of the tablet

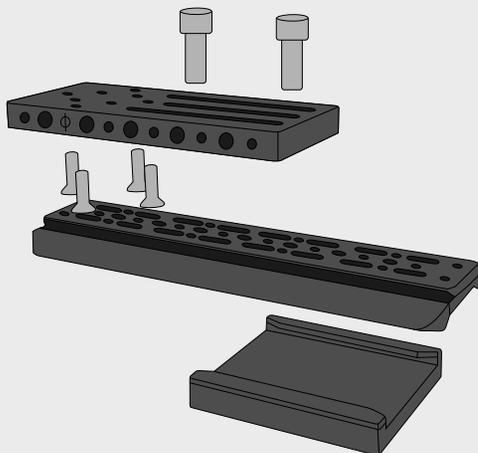


4 Connect the reference switch near the robot arm to the robot cabinet

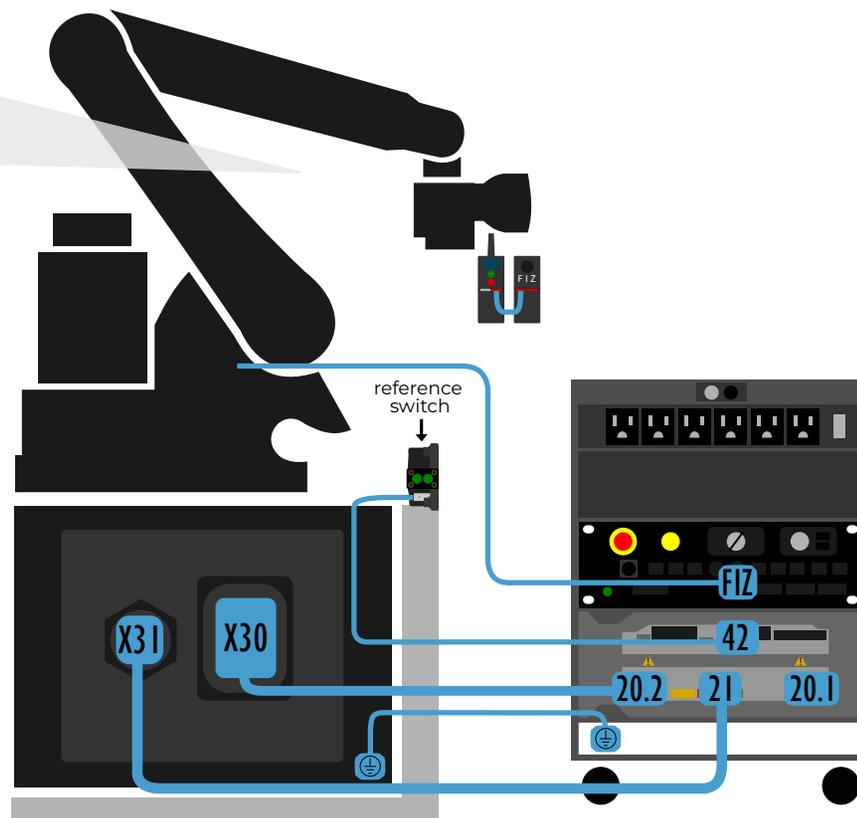
5 Connect the robot to the robot cabinet via the ground wire and main connectors

6 Mount the camera and connect the FIZ motors to the SIM

### CAMERA MOUNT GUIDE



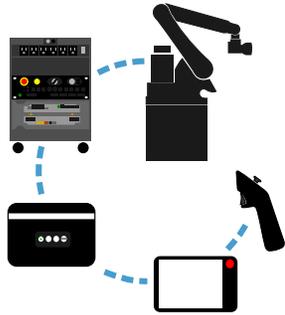
- 1) Mount cheese plate to robot with the front towards the unthreaded hole
- 2) Mount dovetail to cheese plate
- 3) Mount dovetail clamp to camera
- 4) Slide camera/clamp assembly onto dovetail



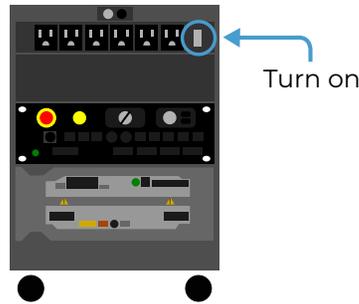
Place the case at least 3 ft. above the ground.

Start Up

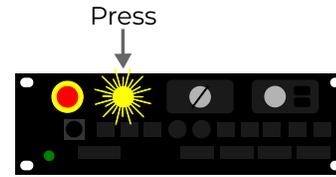
1 Connect basic robot cable connections (refer to page 1) 



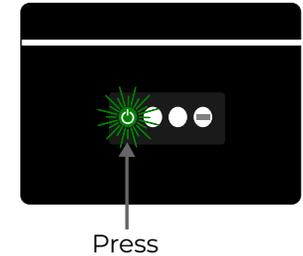
2 Open cabinet & turn on power



3 Press safety reset on the SIM

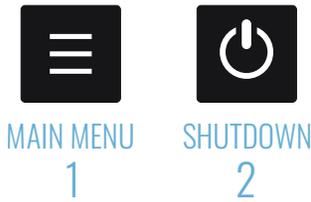


4 Turn on case



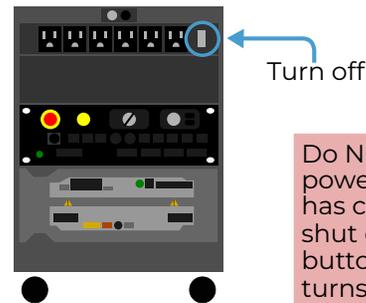
Shut Down

1 Shut down on tablet: Main Menu → Shutdown 



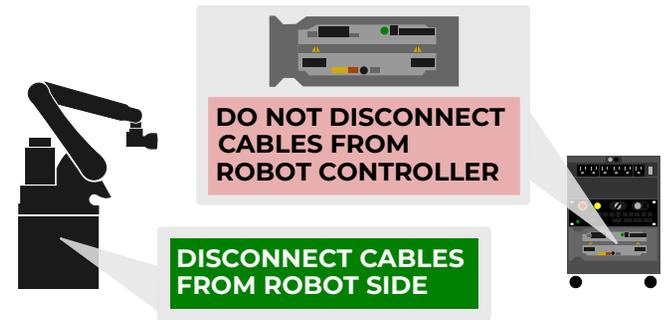
System is completely shut down when case power button is no longer lit

2 Turn off power bar



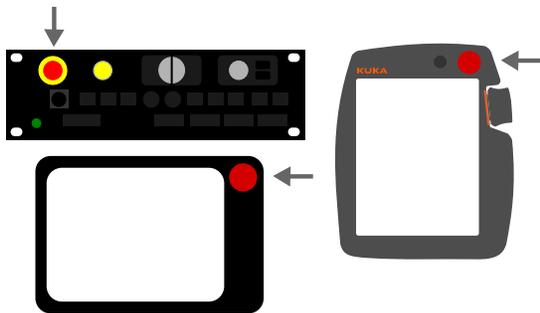
Do NOT turn off power bar until case has completely shut down (power button light on case turns off)

3 OPTIONAL: Disconnect basic robot cable connections 

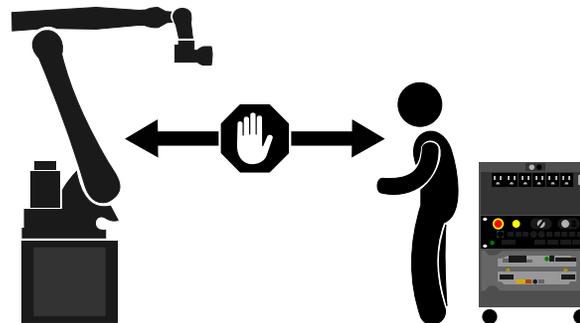


Robot Emergency Stop

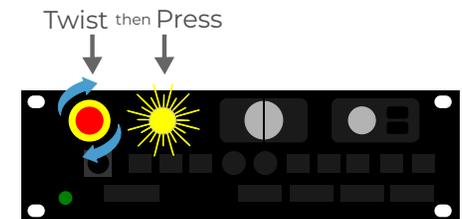
1 Emergency Robot Stop: Push one of the emergency stop buttons



2 Clearing Emergency Robot Stop: Check that area is clear

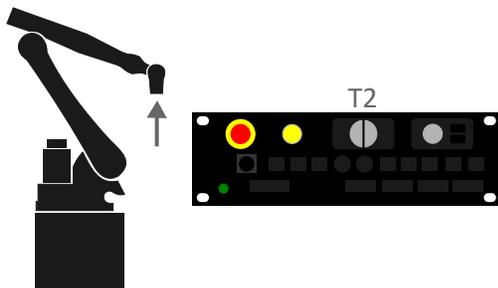


3 Twist E-stop button and push safety reset



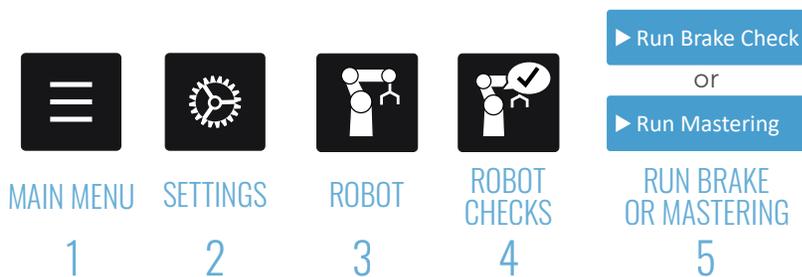
Mastering & Brake Check

1 Remove camera and dovetail clamp from the end of the robot and set mode switch to T2



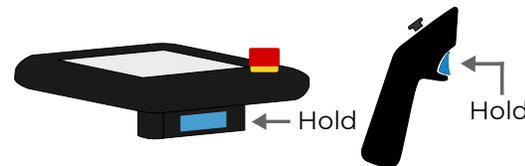
Clear the space of all obstacles before running brake or mastering check

2 Tablet: Main Menu → Settings → Robot → Robot Checks → Run Brake or Mastering



The mastering AND check should be done after every robot reboot and before each day of robot usage

3 Hold enable button and squeeze and hold trigger until check succeeds

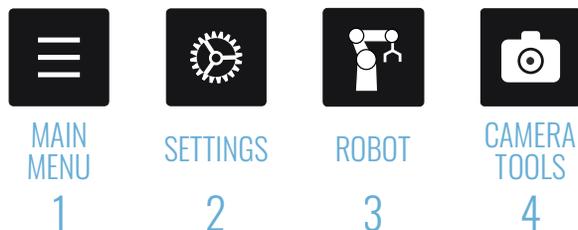


Immediately release enable button in the event of a collision

If the checks fail, you must restart the system and run the check again. See manual for other possible solutions

Calibrating Camera

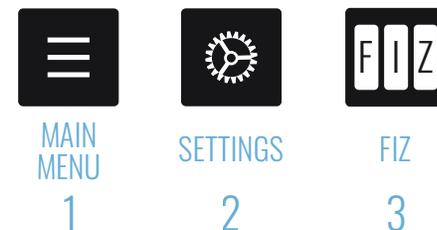
1 Set camera tool: Main Menu → Settings → Robot → Camera Tools



2 Calibrate FIZ: FIZ Notifier → Initialize FIZ



3 Set lens configuration: Main Menu → Settings → FIZ

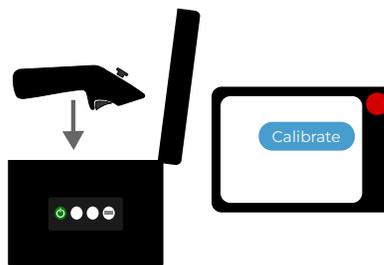


Calibrating Wand

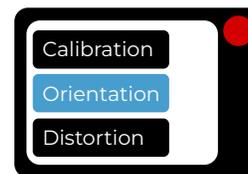
1 Open wand settings and select Calibration



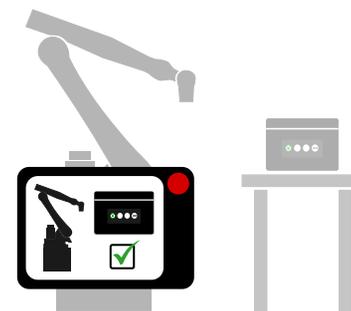
2 Set wand in case. Select Calibrate button



3 Select Orientation



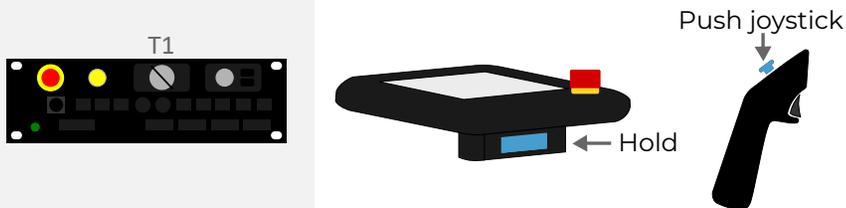
4 Turn virtual case and robot until they match what you see in real life. Exit settings



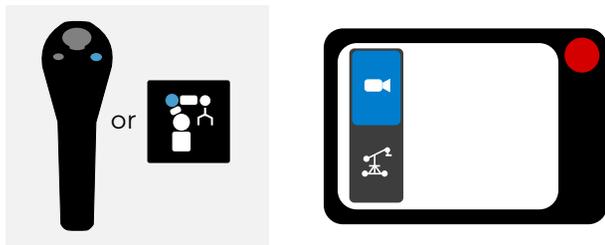
**1 Trigger control:**  
Set key switch to T1. Hold down enable button and trigger. Move hand and arm to initiate robot movement



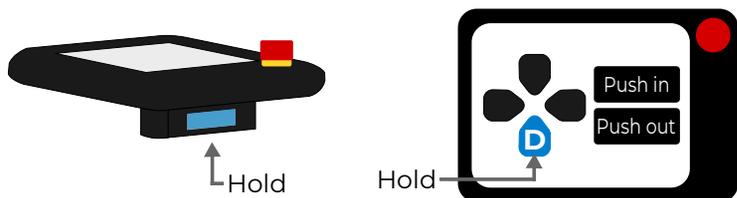
**2 Joystick control:**  
Set key switch to T1. Hold down enable button. Push joystick to move robot



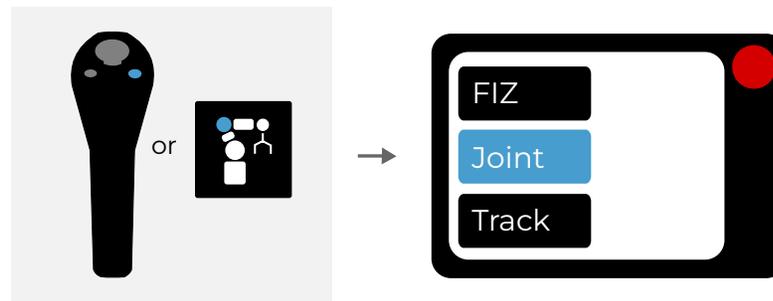
**3a Onscreen Controller:**  
Press the right button on the wand OR select the Robot icon. Select Robot OR Camera icon



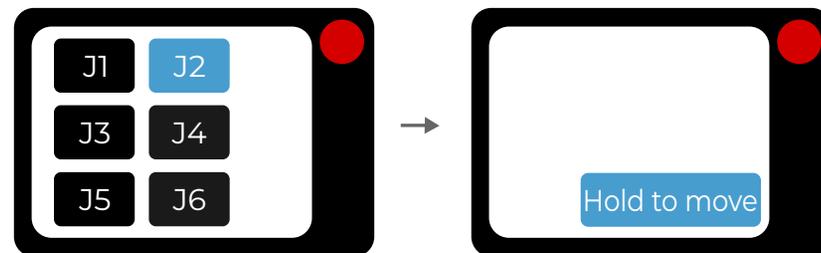
**3b** Hold the enable button, then press and hold the desired direction button to move the camera



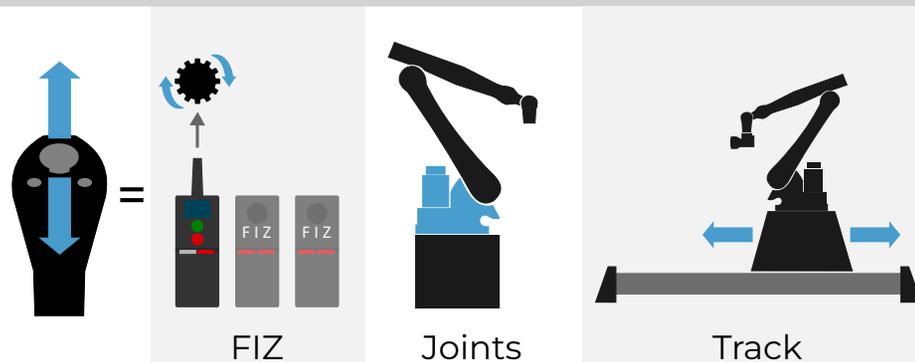
**1** Press the right button on the wand OR select the Robot icon. Select either FIZ, Joint, or Track



**2a Move with tablet:**  
Select desired component. Press Hold to move



**2b Move with controller joystick:**  
Select component. Move joystick UP or DOWN to move component



Writing Program #1

1 Set Lens Configuration:

Main Menu → Settings → FIZ



MAIN MENU 1, SETTINGS 2, FIZ 3

2 Set Camera Tool:

Main Menu → Settings → Robot → Camera Tool



MAIN MENU 1, SETTINGS 2, ROBOT 3, CAMERA TOOLS 4

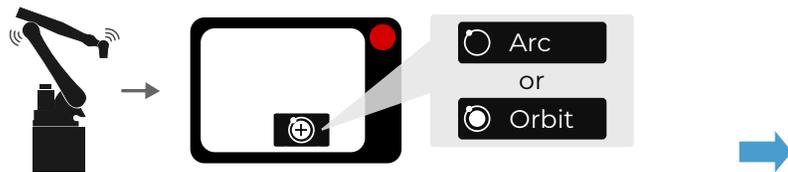
3a Move Robot and Add Keyframes:

- a) Move the robot to the desired position
- b) Click the left wand button or the Add Keyframe button



3b Add Template Moves (i.e. Arc, Orbit)

- a) Move the robot to the desired position
- b) Click the Add Move button and select Arc or Orbit

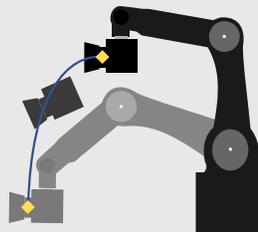


4 Choose move type (for camera and target channel):

Click on the move type in front of keyframe. Choose from options

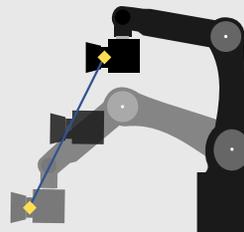


JOINT MOVE



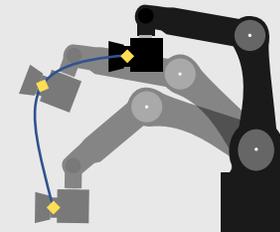
The path in between the keyframe points is not controlled

LINEAR MOVE



The selected camera center moves in a straight line between keyframe points

PATH MOVE



Will pass through all points exactly but the path in between the points is undetermined

Writing Program #2

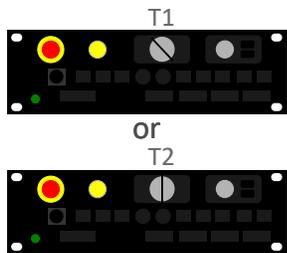
5 Preview program:

Click on preview button to preview program before running it



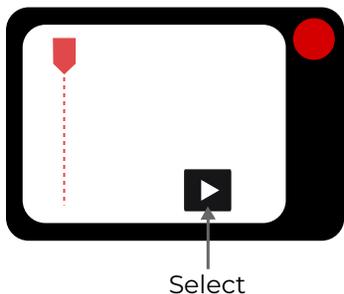
Running the Program

1 Set mode switch to T1 or T2

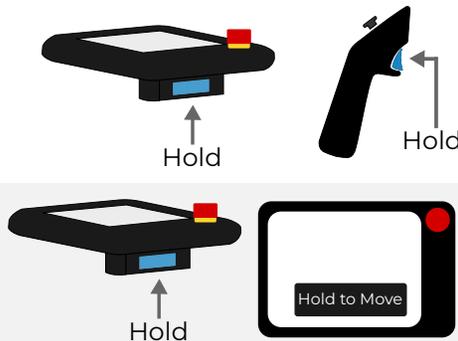


DANGER: Robot can run at 100% speed in T2 mode

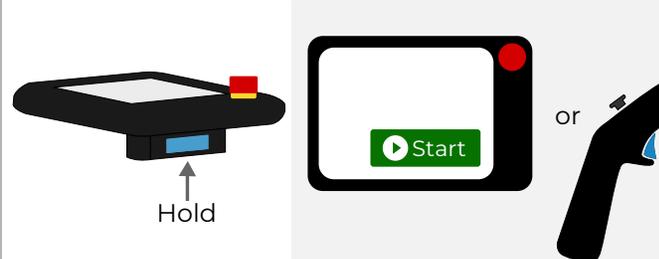
2 Tablet: Set cursor to start time → Run Program button



3 Hold enable button and press trigger OR press Hold to Move button to reset robot to cursor position



4 Hold enable button and use the Start/Pause button OR the trigger to move the robot



You can control the speed at which the program will run by how hard you squeeze the trigger

### 1 Quick Motion Quick Set Icons

(Manual: section 5.7)

<b>TRANSLATION / ROTATION</b>			<b>MOVE SPEED</b>		
Free Motion Mode	Translation Only Mode	Rotation Only Mode	Fast Speed	Slow Speed	
<b>JOYSTICK REFERENCE</b>		<b>SNAP to AXIS</b>		<b>HORIZON LOCK</b>	
Camera Reference	Crane Reference	Snap to Axis ON	Snap to Axis OFF	Horizon Lock ON	Horizon Lock OFF

### 2 Header Actions

(Manual: section 6.3.2)

<b> RIPPLE FUNCTION </b>		<b> ZOOM FUNCTION </b>		
Ripple ON	Ripple OFF	Zoom OUT	Zoom IN	
<b> SYSTEM BUTTONS </b>			<b> TIMELINE ACTIONS </b>	
Main Menu	Help Page	Timeline Properties	Undo Action	Redo Action

### 3 Robot and Program Buttons

(Manual: chapter 6)

Joint Mode	Go To Location	Run Program	Preview Program	Add Move	Arc Orbit	Add Keyframe

### 4 Channel Icons

(Manual: sections 6.4 & 6.6)

Camera Channel	Focus Channel	Target Channel	Iris Channel	Zoom Channel	Trigger Channel	Record Channel

### 5 Mode Indicators

(Manual: section 4.4)

Wand Calibrated	Wand Calibrating	Wand Disconnected	Wand Not Calibrated	Track Calibrated
FIZ Calibrated	FIZ Calibrating	FIZ External / Disconnected	FIZ Not Calibrated	Track Not Calibrated
Robot Engaged	Robot Disengaged	Robot Disconnected	Robot Safety Stop	Track Disconnected

For additional help please consult the user's manual or contact SISU Cinema Robotics support:  
[support@sisucinemarobotics.com](mailto:support@sisucinemarobotics.com)  
 512-770-9518 (call or text)

