

CHECK VACUUM CONFIRM SIGNAL WHILE TRAVERSING

EPIK / UNIK

HY ROBOTICS

24%

TEACH 7

Settings

| | | |
|-------------------|-------------------------------------|--------|
| User | teacher | |
| Level | 7 | Logout |
| Control authority | <input checked="" type="checkbox"/> | |
| Language | English | |

Details

Displaylock

Robot control authority

Control authority

Device: T70IMM (SIM)

Device IP: 192.168.100.3

Settings Users Version Info Network

Menu Mold Speed Timer Signals

**Log in as
Level 7 or above.**



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100%

TEACH 7

MODSettings general Main

Step

RobotArmSet Main

Method Method Settings

WaitMode WaitPos (R... ▾

MainArmTake-out Clamp (Side) ▾

MoldCloseStart Up Complete ▾

EOATRotation No Rotation ▾

InsertGrip No Use ▾

Main Arm Release Off ▾

MainArmRelease Off ▾

Param Pos Prog Config Signals

Go to
line by line program screen

The screenshot shows a robot programming interface. At the top, there is a status bar with a yellow warning icon, the text 'master', a battery level indicator at '31%', and the 'HYROBOTICS' logo. Below this is a toolbar with icons for 'T1', a stop button, a refresh button, a 'I' icon, a cube icon, an up arrow icon, and a 'TEACH' button with the number '7'. The main area is a 'Program' editor with a list of commands: line 20: `HYTakeOutPosition(TakeOutPos, vpTakeOutPos, rKickReturnE`; line 21: `HYUpPosition(UpPos, vpUpPos, rUpDelay)` (highlighted in green); line 22: `HYRunnerRelease(SubArmReleasePos, vpSubArmReleasePos, rS`; line 23: `HYMainRelease(MainArmReleasePos, vpMainArmReleasePos, rM`; line 24: `HYRunnerReturnRelease(SubArmReleasePos, vpSubArmReleaseP`; line 25: `HYInsertGripWaiting(InsertGripWaitingPos, vpInsertGripE`; line 26: `HYInsertGrip(InsertGripPos, vpInsertGripPos, rInsertGrip`; line 27: `HYToWaitingPos(home position, vpWaitingPos, rDownDelay)`; line 28: `// END_EDIT`. A red arrow points from the 'SetDO' command in the 'I/O-Control' section of the 'Movement' palette to the 'HYUpPosition' command in the program editor. The 'Movement' palette has three sections: 'Movement' with 'SetDO' (highlighted in a red box), 'I/O-Control' with 'PulseDO', and 'Timing'. At the bottom, there is a toolbar with icons for 'Param', 'Pos', 'Prog', 'Config', and 'Signals'.

After UP position,

Add "SetDO" command

The screenshot shows a dialog box for configuring a 'SetDO' command. The text 'SetDO(douChuck)' is entered in the input field. Below the input field, there are four buttons: 'Modify' (highlighted in a red box), 'Keyboard', 'add DO', and 'Cancel'. To the right of the 'add DO' button is an 'Ok' button.

Press Modify

SetDO

Output (DOUT) **S** douVacuum

State **ON**

Set output while robot is moving

Feedback (DIN) **S** digVacuumConfirm

Feedback timeout [s] \emptyset < no Value >

Halt program until feedback signal is set

Program

```
// 2.00a.12
20 HYTakeOutPosition(TakeOutPos, vpTakeOutPos, rKickReturnI
21 HYUpPosition(UpPos, vpUpPos, rUpDelay)
22 HYRunnerRelease(SubArmReleasePos, vpSubArmReleasePos, rS
23 HYMainRelease(MainArmReleasePos, vpMainArmReleasePos, rM
24 HYRunnerReturnRelease(SubArmReleasePos, vpSubArmReleaseE
25 HYInsertGripWaiting(InsertGripWaitingPos, vpInsertGripPc
26 HYInsertGrip(InsertGripPos, vpInsertGripPos, rInsertGrip
27 HYToWaitingPos(home position, vpWaitingPos, rDownDelay)
28 // END_EDIT
```

Edit Selection Cancel **Ok**

Vacuum 1
Turn ON

Choose Vacuum1 Confirm

Check mark
“Halt program until
feedback signal is set”

Press OK

Program

```
19 // 2.00a.12
20 HYTakeOutPosition(TakeOutPos, vpTakeOutPos, rKickReturnL
21 HYUpPosition(UpPos, vpUpPos, rUpDelay)
22 SetDO(douVacuum, ON, FALSE, digVacuumConfirm, , TRUE)
23 HYRunnerRelease(SubArmReleasePos, vpSubArmReleasePos, rS
24 HYMainRelease(MainArmReleasePos, vpMainArmReleasePos, rM
25 HYRunnerReturnRelease(SubArmReleasePos, vpSubArmReleaseP
26 HYInsertGripWaiting(InsertGripWaitingPos, vpInsertGripPc
27 HYInsertGrip(InsertGripPos, vpInsertGripPos, rInsertGrip
28 HYToWaitingPo
29 // END_EDIT
```

After UP position,
Vacuum 1 is ON, (already vacuum should be ON at Takeout step)
and keep checking the confirm signal until Vacuum 1 OFF command in Main
Release sub-program.

If parts drop during traverse movement, the robot stops and buzzer ON

If the robot uses vacuum 2, simply add another Set Do command.

THANKS