How to generate Elite EC robot offline program in RoboDK and then run the program in robot
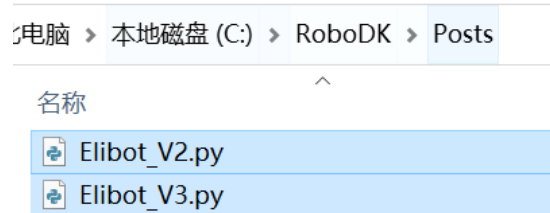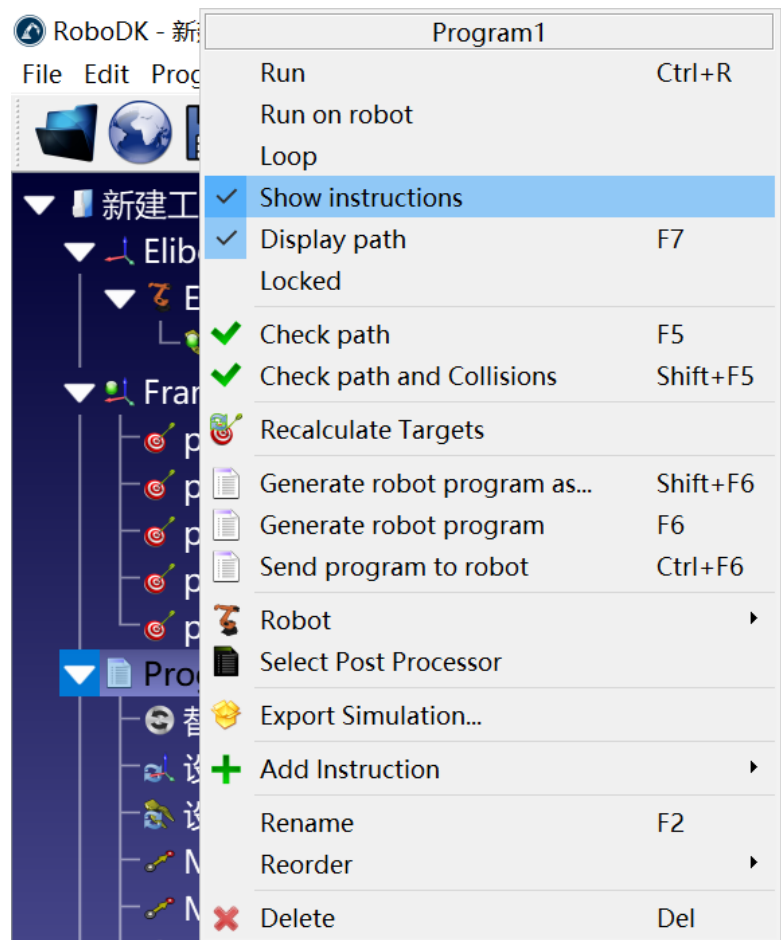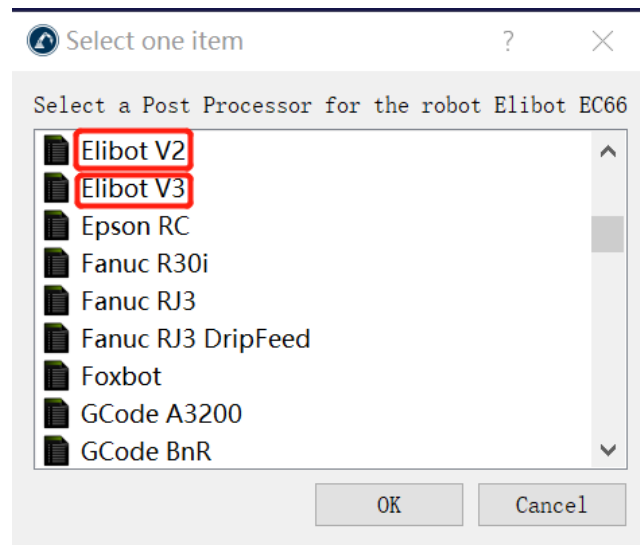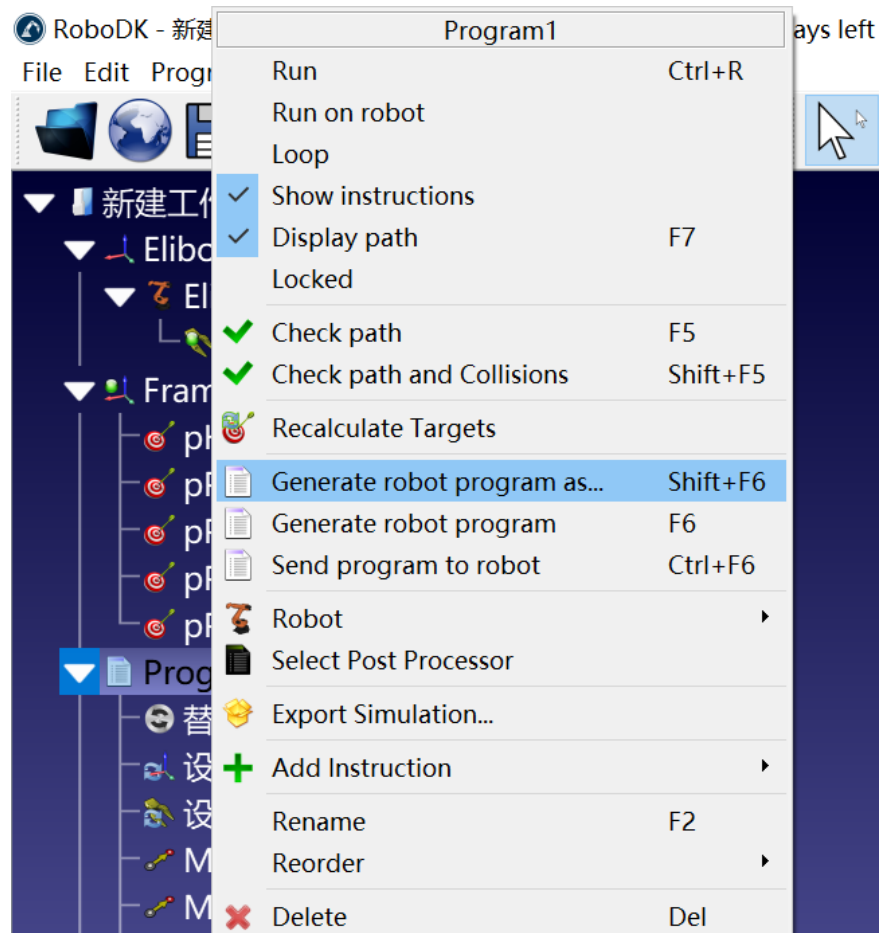
1. Copy and paste the Elibot_V2.py and Elibot_V3.py to the folder "Posts" under the RoboDK installation path

2. Process the track and create program in RoboDK as needed.

3. Right-click on the generated program, we can select to show the instructions.

4. Right-click on the program, choose "Generate robot program as",

-Choosing Elibot_V2.py will generate SETJOINT and corresponding MOVJ Pxxx format, without coordinates. The first line of the program is automatically set to the corresponding tool. Copy and save as a JBI file and download to the robot. Please ensure the CR in first line and last line is 0.

-Choosing Elibot_V3.py will generate SETPOSE and corresponding MOVL Vxxx format，The first line of the program is to set the TOOL and user coordinate system content (it's adviced to use Elibot_V3.py in practical case, only need to modify the user coordinate), using tool1 and user1. You need to import the robodk_transfer_user.lua into the robot first. Copy and save as a JBI file and download to the robot. When running the program, robodk_transfer_user.lua will convert pose under user1 to pose under base.