**Controlling a Universal Robotics Cobot Arm with Python**

**Configure the Robot’s Network Settings**

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| Step # | Instruction | Illustration |
| 1 | On the teach pendant, navigate to ‘Setting > Network > Static Mode’ |  |
| 2 | Change the IP of the robot to ‘192.168.0.100’ the Subnet Mask to ‘255.255.255.0’ and the default gateway to ‘192.168.0.100’ |

**Configure the Computer’s Network settings**

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| Step # | Instruction | Illustration |
| 1 | Ensure your computer is connected to the robot via LAN |  |
| 2 | Press ‘Win + R’ on your Windows computer and type ‘ncpa.cpl’ |

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| 3 | Choose the corresponding network interface and open it |  |
| 4 | Open ‘Properties’ |
| 5 | Open ‘Internet Protocol Version 4’ |
| 6 | Select ‘Use the following IP address’ and set the IP address to ‘192.168.0.101’ and the Subnet Mask to ‘255.255.255’ |  |
| 7 | Exit the settings and enable remote control at the top right |

**Install Python 3.9.1**

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| Step # | Instruction | Illustration |
| 1 | Install Python using the official [Python website](https://www.python.org/downloads/release/python-391/#:~:text=Windows%20installer%20(64%2Dbit)) |  |

**Install ‘ur\_rtde’ Library**

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| Step # | Instruction | Illustration |
| 1 | Open command prompt by pressing ‘Win,’ typing ‘cmd’ and pressing ‘Enter’ |  |
| 2 | Type ‘pip3 install ur\_rtde’ and press ‘Enter’ |
| 3 | The documentation of this library is [here](https://sdurobotics.gitlab.io/ur_rtde/api/api.html) |

**Prepare Python**

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| Step # | Instruction | Illustration |
| 1 | Download the code [here](https://github.com/Doomsy1/Pollinator/blob/main/robot.py) |  |
| 2 | Change the actions you want to do under main() |
| 3 | Run the code |