

## **3.1 A**

### **3.1.1 ACAL Alarm Code**

#### **3.1.1.1 ACAL-000 Fail to run DETECT Motn**

**Cause:** The AccuCal2 Motion failed to run. The AccuCal2 motion cannot be started.

**Remedy:** Clear all the errors before executing AccuCal2.

#### **3.1.1.2 ACAL-001 Robot is not ready.**

**Cause:** The robot is not ready. The system cannot issue motion because it is in an error state.

**Remedy:** Clear all faults, then retry the operation.

#### **3.1.1.3 ACAL-002 Fail to fit circle.**

**Cause:** AccuCal2 cannot converge within the set threshold.

**Remedy:** Perform the following:

- Increase the number of iterations allowed.
- Increase the convergence threshold setting.
- Make sure the TCP has not been changed.

#### **3.1.1.4 ACAL-003 Contact before search.**

**Cause:** The robot is in contact with the part before starting a search motion.

**Remedy:** Reteach the starting position.

#### **3.1.1.5 ACAL-004 No contact detected.**

**Cause:** No contact was made during the AccuCal2 motion.

**Remedy:** Make sure the sensor and software are installed correctly.

#### **3.1.1.6 ACAL-005 Undefined program name.**

**Cause:** The AccuCal2 program name was not defined.

**Remedy:** Select an AccuCal2 teach pendant program before pressing the EXEC key.

#### **3.1.1.7 ACAL-006 TPE operation error.**

**Cause:** This is an internal teach pendant editor program error.

**Remedy:** Abort the program and run again. If this doesn't resolve the problem, cycle power and try again. If this doesn't resolve the problem, reinstall the controller software. Refer to the Software Installation Manual for information on installing software.

#### **3.1.1.8 ACAL-007 Calibration internal error.**

**Cause:** This is an AccuCal2 internal error.

**Remedy:** Turn off the controller, and turn it on again to recover. If the problem persists, reinstall the controller software. Refer to the Software Installation Manual for more information.

#### **3.1.1.9 ACAL-008 File open error.**

**Cause:** The output file cannot be opened.

**Remedy:** Check the path, and file name to be sure they are correct.

#### **3.1.1.10 ACAL-009 No matching Start inst.**

**Cause:** You are trying to execute a CALIB END instruction without a matching CALIB START instruction.

**Remedy:** Add a CALIB START instruction before the CALIB END.

**3.1.1.11 ACAL-010 Invalid schedule number.**

**Cause:** The schedule number in CALIB, UTOOL, or UFRAME START is invalid.

**Remedy:** Provide a correct schedule number in CALIB (or UTOOL or UFRAME) START[] teach pendant instruction.

**3.1.1.12 ACAL-011 Cannot access \$MNUFRAME.**

**Cause:** The current \$MNUFRAMENUM[] is incorrect and cannot be accessed.

**Remedy:** Go to the USER FRAME menu to select a valid user frame.

**3.1.1.13 ACAL-012 Cannot access \$MNUTOOL.**

**Cause:** Cannot access \$MNUTOOL. The current \$MNUTOOLNUM[] is incorrect.

**Remedy:** Display the FRAME menu to select a valid tool frame.

**3.1.1.14 ACAL-013 Backward execution ignored.**

**Cause:** Backward execution were ignored. The AccuCal2 instructions can not be executed backward.

**Remedy:** The backward execution of the AccuCal2 instructions is ignored. Rewrite the instructions if you do not want this to happen.

**3.1.1.15 ACAL-014 System loading error.**

**Cause:** System loading error. The AccuCal2 is loaded incorrectly.

**Remedy:** Reload the controller. Refer to the Software Installation Manual for more information.

**3.1.1.16 ACAL-015 Not enough data.**

**Cause:** Not enough data exists to compute the frame offset.

**Remedy:** Add more Detect instructions in the AccuCal2 program.

**3.1.1.17 ACAL-016 No Preplan motion for Detect**

**Cause:** The Detect instruction does not allow pre-plan motion.

**Remedy:** None.

**3.1.1.18 ACAL-017 Wrong number of searches.**

**Cause:** An incorrect number of searches was performed.

**Remedy:** Re-teach the AccuCal2 program with an appropriate number of searches. Refer to the application-specific Setup and Operations Manual for information on the number of searches required for each calibration type.

**3.1.1.19 ACAL-018 Nonorthogonal search vector**

**Cause:** The 3 planes method requires three search directions be normal to each other.

**Remedy:** Re-teach the cell finder program with three search directions that are normal to each other.

**3.1.1.20 ACAL-019 Positions are too close.**

**Cause:** Positions are too close. The taught positions are too close to each other.

**Remedy:** Re-teach the cell finder program so that the contact positions are at least 10mm apart.

**3.1.1.21 ACAL-020 Invalid Frame number.**

**Cause:** The current frame number setting is invalid.

**Remedy:** Use the SETUP/FRAME menu to set up the correct frame.

**3.1.1.22 ACAL-021 Large Frame deviation.**

**Cause:** The computed frame offset exceeds the pre-set value.

**Remedy:** Run the calibration program again to make sure the robot makes solid contacts with the part. Change the XYZ and ORNT change value in the schedule if these numbers are very small.

**3.1.1.23 ACAL-022 Detect without mastering**

**Cause:** An AccuCal2 teach pendant program is running without performing mastering it first.

**Remedy:** Display the AccuCal2 menu, and master the program first.

**3.1.1.24 ACAL-023 No EXEC at Single Step Mode.**

**Cause:** The robot cannot execute an AccuCal2 program in Single Step Mode.

**Remedy:** Turn off Single Step before executing the cell finder program.

**3.1.1.25 ACAL-024 Master Update failed.**

**Cause:** A failure occurred while trying to update the master data in a FIND instruction.

**Remedy:** Re-master the frame search teach pendant program.

**3.1.1.26 ACAL-025 Large frame shift.**

**Cause:** A very large frame shift has occurred.

**Remedy:** Check the UTOOL and the fixture to make sure that they are properly installed.

**3.1.1.27 ACAL-026 No CALIB END instruction.**

**Cause:** No CALIB END instruction. AccuCal2 program does not have a FIND END instruction.

**Remedy:** Add CALIB END instruction at the end of the frame search teach pendant program.

**3.1.1.28 ACAL-027 Counts do not match.**

**Cause:** The number of master data and number of run time data does not match each other.

**Remedy:** Run the finder program again.

**3.1.1.29 ACAL-028 No logged frame data.**

**Cause:** No logged frame data exists and the frame cannot be restored.

**Remedy:** Select a logged frame.

**3.1.1.30 ACAL-029 Zero offset, No Update.**

**Cause:** No change occurred in the offset frame.

**Remedy:** Run Cell Finder again to compute a new offset.

**3.1.1.31 ACAL-030 Frame Log is disabled.**

**Cause:** The Frame data log is disabled.

**Remedy:** Enable the frame log first.

**3.1.1.32 ACAL-031 Cold start to set \$USEUFRAME**

**Cause:** \$USEUFRAME is set to FALSE. AccuCal2 reset it to TRUE.

**Remedy:** Turn off the controller, then turn it on again to perform a Cold start.

**3.1.1.33 ACAL-032 Invalid motion group.**

**Cause:** The motion group number is invalid.

**Remedy:** Use only one group in the program and make sure the group is available.

**3.1.1.34 ACAL-033 Other group is running.**

**Cause:** The other program has motion control.

**Remedy:** Abort the other running program.

**3.1.1.35 ACAL-034 Group mismatched.**

**Cause:** The motion group number is not right.

**Remedy:** Use only one group in the program, and make sure group is available.

**3.1.1.36 ACAL-035 Press Shift Key.**

**Cause:** The SHIFT key was not pressed.

**Remedy:** Press the SHIFT key.

**3.1.1.37 ACAL-036 Failed to create TPE program**

**Cause:** The teach pendant program could not be created.

**Remedy:** Check the following:

- Make sure enough memory is available.
- Make sure the program is not being edited.
- Make sure the program is not write protected.

**3.1.1.38 ACAL-037 TPE Position is not recorded**

**Cause:** The teach pendant position has not been recorded. Make sure the program is not write protected.

**Remedy:** Unprotect the write protected program.

**3.1.1.39 ACAL-038 TPE Program does not exist.**

**Cause:** The selected teach pendant program was not found and does not exist.

**Remedy:** Select an existing teach pendant program.

**3.1.1.40 ACAL-039 Move to recorded posn failed**

**Cause:** The robot could not move to the recorded position.

**Remedy:** Make sure the position is reachable and that another program does not have motion control.

**3.1.1.41 ACAL-040 Invalid Detection TP program**

**Cause:** The detection teach pendant program is not usable.

**Remedy:** Load a proper detection program.

**3.1.1.42 ACAL-041 Override should be 100%.**

**Cause:** The speed override is not 100%.

**Remedy:** Before running the program, increase the override to 100%.

**3.1.1.43 ACAL-042 Large orientation change.**

**Cause:** The found orientation is larger than the tolerance allows.

**Remedy:** Adjust the object so that orientation is smaller. Increase the orientation tolerance.

**3.1.1.44 ACAL-043 Points & solution mismatch.**

**Cause:** The number of search points does not match the selected solution type.

**Remedy:** Select a different solution type, or adjust number of detect statements.

**3.1.1.45 ACAL-044 Solution type error.**

**Cause:** An unsupported solution type error was selected.

**Remedy:** Choose a different solution type.



**3.1.1.46 ACAL-045 Failed to set register.**

**Cause:** The specified register was not set.

**Remedy:** Make sure the specified register exists.

**3.1.1.47 ACAL-046 Failed to convert position.**

**Cause:** The position failed to convert. The internal position was not set.

**Remedy:** Make sure the points are taught in the proper sequence and are not near limits.

**3.1.1.48 ACAL-047 Too many points used.**

**Cause:** Too many points are used.

**Remedy:** Reduce the number of detect points.

**3.1.1.49 ACAL-048 Solution failed.**

**Cause:** The solution failed to complete.

**Remedy:** Make sure the correct number of points are taught in the correct directions and orientation.

**3.1.1.50 ACAL-049 Motion limit error.**

**Cause:** This is a motion limit error. The detect motion failed due to a limit error for the destination position.

**Remedy:** Move the robot away from the joint limit, or reduce the search distance in the detection schedule.

**3.1.1.51 ACAL-050 iRCal. TCP is not loaded.**

**Cause:** TCP Cal is not loaded.

**Remedy:** Try to run the TCP Calibration instruction without the TCP Cal software. Perform a Controlled start, and load the TCP Cal software from the option menu.

**3.1.1.52 ACAL-051 iRCal. Frame is not loaded.**

**Cause:** Cell Cal is not loaded.

**Remedy:** Try to run the Cell Calibration instruction without the Cell Cal software. Perform a Controlled start, and load the Cell Cal software from the option menu.

**3.1.1.53 ACAL-052 iRCal. Master is not loaded.**

**Cause:** Robot Cal is not loaded. The robot tried to run the robot Calibration instruction without the Robot Cal software.

**Remedy:** Perform a Controlled start, and load the Robot Cal software from the OPTION menu.

**3.1.1.54 ACAL-053 No calibration software.**

**Cause:** No calibration software. The robot tried to run a detect instruction without Calibration software.

**Remedy:** Perform a Controlled start, and load one of the Calibration software options from the OPTION menu.

**3.1.1.55 ACAL-054 Invalid Calibration program.**

**Cause:** Invalid Calibration program. The calibration program type does not match the calibration menu.

**Remedy:** Check the teach pendant program's calibration start instruction so it matches the calibration menu.

**3.1.1.56 ACAL-055 Too Many Parallel Searches.**

**Cause:** Too Many Parallel Searches have occurred. More than three parallel searches occurred when the total number of searches is less than 7.

**Remedy:** Teach more searches, or change the excess parallel searches to be in a different direction.

**3.1.1.57 ACAL-056 Skip Update Frame Inst.**

**Cause:** The robot executed an UPDATE FRAME instruction in a non-Cell calibration program.

**Remedy:** UPDATE FRAME only works in Cell Calibration programs with Uframe Start instruction. Remove the UPDATE FRAME instruction from the non-CellCal program.

**3.1.1.58 ACAL-057 Large Calibration Error**

**Cause:** Residual maximum calibration has exceeded the limit allowed by the specified schedule.

**Remedy:** Verify solid tooling and good contact is made during all searches. Increase the limit in the schedule.

**3.1.1.59 ACAL-058 UFRAME Change Not Allowed**

**Cause:** The UFRAME was changed during UTOOL calibration and this is not allowed.

**Remedy:** Use the same UFRAME for all points during the initial UTOOL calib.

**3.1.1.60 ACAL-059 All Positions Not Recorded**

**Cause:** All required positions are not recorded.

**Remedy:** Record all necessary positions, and retry the operation.

**3.1.1.61 ACAL-060 Excessive Accumulated offset**

**Cause:** The accumulated offset exceeds the tolerance specified in the schedule.

**Remedy:** Repair the tool so that the TCP is closer to the reference TCP, or increase Accumulated Error Threshold in the tool calibration schedule.

**3.1.1.62 ACAL-061 UFrame mismatch.**

**Cause:** A UFrame mismatch has occurred. The current MNUFRAME number does not match the program's uframe.

**Remedy:** Change the current user frame number to match the program's user frame number.

**3.1.1.63 ACAL-062 Too many moves in a program.**

**Cause:** Too many moves have been attempted in a program. The Calibration program has too many motion lines in it.

**Remedy:** Limit the number of move instructions in a calibration program to less than 256.

**3.1.1.64 ACAL-063 Failed to update master data**

**Cause:** The master data failed to update. The master count cannot be updated when the robot is in motion.

**Remedy:** Abort the robot motion and then press the UPDATE soft key again.

**3.1.1.65 ACAL-064 UTool Mismatch.**

**Cause:** A UTool mismatch has occurred. The current MNUTOOL number does not match the program's utool.

**Remedy:** Change the current tool number to match the program's utool number.

**3.1.1.66 ACAL-065 TCP calibration failed**

**Cause:** The TCP calibration failed to complete.

**Remedy:** Review the previous error to identify the cause.

**3.1.1.67 ACAL-066 Frame calibration failed**

**Cause:** Cell calibration failed to complete.

**Remedy:** Review the previous error to identify the cause.

**3.1.1.68 ACAL-067 Circle fit error %s**

**Cause:** The circle fit error exceeds the threshold.

**Remedy:** Check for a lost fixture or tool, or change the fit error tolerance in the detection schedule.

**3.1.1.69 ACAL-068 Radius err %s**

**Cause:** Circle radius error exceeds threshold.

**Remedy:** Check for a lost fixture or tool, or change the radius error tolerance in the detection schedule.

**3.1.1.70 ACAL-069 Auto Update is ON.**

**Cause:** Auto Update is on therefore the frame has been updated automatically.

**Remedy:** An update is not required.

**3.1.1.71 ACAL-070 No update on record points.**

**Cause:** No update on record points. The teach pendant program has a different number of DETECT instructions than expected. The positions cannot automatically update in the screen.

**Remedy:** Manually record positions to create the calibration program.

**3.1.1.72 ACAL-071 Invalid joint number.**

**Cause:** The axis number specified in the DETECT Joint instruction is invalid.

**Remedy:** Change the axis number to a valid one.

**3.1.1.73 ACAL-072 Invalid joint sensor type.**

**Cause:** The Detect Joint instruction cannot use TOS WRIST sensor type for contact detection.

**Remedy:** Change sensor type to either IO or TOS all axes in the detection schedule.

**3.1.1.74 ACAL-073 Skip Detect Joint**

**Cause:** The Detect Joint instruction is not valid for TCP or CELL calibration.

**Remedy:** The Detect Joint instruction is for ROBOT calibration only. Change the calibration start instruction to CALIB START or delete the instruction from the program.

**3.1.1.75 ACAL-074 No motion before DETECT.**

**Cause:** No motion exists before the DETECT instruction. Detect instructions require a motion line preceeding them.

**Remedy:** Add a MOVE instruction before the DETECT instruction.

**3.1.1.76 ACAL-075 Mixed Detect instructions.**

**Cause:** Mixed Detect instructions have occurred. The Detect Joint instruction cannot be used with other Detect instructions within the same Calib Start - Calib End instructions.

**Remedy:** Delete the other DETECT instrucion from the program.

**3.1.1.77 ACAL-076 More than one Detect Joint.**

**Cause:** More than one Detect Joint instruction exists. Only one Detect Joint instruction is allowed between Calib Start and Calib End instructions.

**Remedy:** Delete the extra DETECT JOINT instructions.

**3.1.1.78 ACAL-077 No Detect Joint in Init. Cal**

**Cause:** No Detect Joint should exist in Initial Calibration. The Detect Joint instruction does not apply to the initial robot calibration.

**Remedy:** Run the program from the robot master recovery menu.

**3.1.1.79 ACAL-078 Skip Update Tool instruction**

**Cause:** Execute the Update Utool instruction in a non-TCPCal program.

**Remedy:** Update Tool only works in TCP Calibration programs with a UTool Start instruction.

**3.1.1.80 ACAL-079 Large approach angle error.**

**Cause:** The search start position's appraoch vector does not align with the plate's normal vector.

**Remedy:** Touch up the search start position so that the position's approach vector is aligned to the plate's normal vector.

#### **3.1.1.81 ACAL-080 Failed to update TPE program**

**Cause:** Failed to update the teach pendant program's search start position.

**Remedy:** Make sure there is no system fault before pressing UPDATE. If the problem persists, perform a Cold start.

#### **3.1.1.82 ACAL-081 Destination %s Limit Error**

**Cause:** The recorded position is too close to the joint limit.

**Remedy:** Re-teach the position away from joint limit.

#### **3.1.1.83 ACAL-082 Tool is 180 degree off in Z**

**Cause:** The Tool approach vector is 180 degrees off in Z from the search direction.

**Remedy:** Change the system variable \$cb\_vars.\$z\_out to FALSE if it is set to TRUE, or vice versa.

#### **3.1.1.84 ACAL-083 Invalid TPE instruction.**

**Cause:** Invalid teach pendant calibration instruction.

**Remedy:** The teach pendant program memory might be corrupted. Replace the instruction with a new one.

#### **3.1.1.85 ACAL-084 Failed to access Karel vars.**

**Cause:** Failed to access the calibration program's KAREL variables.

**Remedy:** Cold start the controller. If the problem persists, re-install the calibration option again.

**3.1.1.86 ACAL-085 UFrame is too small**

**Cause:** The specified UFrame is zero or small, and Calibrate UFrame is disabled.

**Remedy:** Set UFrame to be the precision calibration fixture location or enable UFrame calibration in the calibration schedule.

**3.1.1.87 ACAL-086 UTool is too small**

**Cause:** The specified UTool is zero or small, and the Calibrate UTool is disabled.

**Remedy:** Set UTool to be the precision calibration fixture location or enable UTool calibration in the calibration schedule.

**3.1.1.88 ACAL-087 Joint[%s^1] rotation is small**

**Cause:** The joint angle motion is too small.

**Remedy:** Modify calibration points to provide more motion on the specified axis. Or, disable calibration of one or more joints.

**3.1.1.89 ACAL-088 Points are colinear**

**Cause:** Three or more points with the same search direction are colinear or nearly colinear.

**Remedy:** Reteach one of the points so that the points are not colinear, or teach another non-colinear point.

**3.1.1.90 ACAL-089 Not enough search direction**

**Cause:** There must be at least three different search directions that are close to perpendicular to each other. There must also be at least three non-colinear points in one search direction and at least two points in another search direction.

**Remedy:** Add more search points or reteach existing points to have sufficient search directions and a sufficient number of points in the search directions.



### **3.1.1.91 ACAL-090 Large joint angle correction**

**Cause:** Calibration joint angle correction exceeds the limit

**Remedy:** Identify the cause of the large correction. If the robot joint angle is actually off by that large amount, then you can either increase the tolerance in the schedule or manually remaster the robot to reduce the error and touchup the calibration points and rerun the calibration. If the calibration result is incorrect, then check that Calibrate UFrame is TRUE unless you are doing calibration recovery or use a precision fixture. Check that Calibrate UTool is TRUE unless you are doing calibration recovery or use a precision calibration tool. If you are doing recovery then check that the calibration fixture is in the correct location and the UFrame is the same as the original UFrame from when the calibration was run in MASTER mode. If recovering J6, then verify that UTool and the calibration tool are the same as when the calibration was run in MASTER mode

### **3.1.1.92 ACAL-091 UFrame orientation not zero**

**Cause:** The UFrame orientation must be zero.

**Remedy:** Use a UFrame with WPR values where all are set to zero.

### **3.1.1.93 ACAL-092 Position close to joint limit**

**Cause:** The search destination position is too close to the joint limit.

**Remedy:** Re-teach the position away from joint limits.

### **3.1.1.94 ACAL-093 Invalid CD pair number**

**Cause:** The Coordinate Motion Pair number is invalid.

**Remedy:** Check the CD pair setup to make sure the CD pair has been set up correctly.

### **3.1.1.95 ACAL-094 Invalid Process Sync Setup**

**Cause:** Invalid Process Sync Set up

**Remedy:** Check the Process Sync setup to make sure the Process Sync has been set up correctly.

**3.1.1.96 ACAL-095 No Coordinate Motion software**

**Cause:** The CD pair calibration requires Coordinate Motion Software.

**Remedy:** Load the Coordinate Motion software on the controller.

**3.1.1.97 ACAL-096 No Process Sync software**

**Cause:** Robot Link calibration requires Robot Link Software.

**Remedy:** Load the Robot Link software on the controller.

**3.1.1.98 ACAL-097 MultiCal is not loaded.**

**Cause:** The user is trying to run the MultiCal instruction without MultiCal software.

**Remedy:** Perform a Control start and load the MultiCal software from option menu.

**3.1.1.99 ACAL-098 Bar method is not supported**

**Cause:** Calibration Bar is not support in the V7.20 MultiCal Release.

**Remedy:** The calibration bar method will be supported in future releases.

**3.1.1.100 ACAL-099 Positioner is not supported**

**Cause:** Positioner calibration is not supported in the V7.20 MultiCal release.

**Remedy:** The positioner calibration will be supported in future releases.

**3.1.1.101 ACAL-100 Program Group Mismatch**

**Cause:** The read in the program group does not match the current default motion group.

**Remedy:** Use the FCTN key to change the current motion group or select another calibration program.

**3.1.1.102 ACAL-101 TCP Alignment error**

**Cause:** The maximum alignment distance was exceeded.

**Remedy:** Fix the TCP Alignment and run TCPCal again.

**3.1.1.103 ACAL-102 Process is not yet completed**

**Cause:** Cannot execute current step without completing previous steps.

**Remedy:** Complete all steps leading to the current step.

**3.1.1.104 ACAL-104 No Analog port data file**

**Cause:** There is no associated Analog data file in FRS: for the specified analog port number.

**Remedy:** Copy the analog data file to the FRS: directory and cold start the controller.

**3.1.1.105 ACAL-105 Option does not support AIN**

**Cause:** RobotCal and MultiCal does not support analog sensor.

**Remedy:** Select a different sensor type in the detection schedule.

**3.1.1.106 ACAL-106 No analog sensor support**

**Cause:** The Detect Circle and Detect Joint instructions do not support an analog sensor.

**Remedy:** Select a different sensor type in the detection schedule.

**3.1.1.107 ACAL-107 Invalid AIN port number**

**Cause:** The AIN port number is not valid.

**Remedy:** Select a different AIN port number that has its data file in an FRS: directory.

**3.1.1.108 ACAL-108 Dynamic UFrame setup error**

**Cause:** Dynamic Uframe setting require cd pair setting in its schedule.

**Remedy:** Set the cd pair number in the schedule or change the CellCal calibration mode in the setup menu

**3.1.1.109 ACAL-109 Standard UFrame setup error**

**Cause:** The schedule used by UFrame has a cd\_pair set.

**Remedy:** Select a new schedule or change the cd\_pair variable to 0 in the current schedule.

**3.1.1.110 ACAL-110 Please turn off single step**

**Cause:** Disable single step mode.

**Remedy:** Press the STEP key to disable single step.

**3.1.1.111 ACAL-115 Joint position not allowed**

**Cause:** TP program has position with joint representation. This is not allowed in High Accuracy Mode

**Remedy:** 1. Exit High Accuracy Mode 2. Move to the position 3. Enable High Accuracy Mode 4. Change to Cartesian rep.

**3.1.1.112 ACAL-116 Joint motion not allowed**

**Cause:** Joint motion is not allowed in High Accuracy Mode

**Remedy:** Change motype to Linear or exit High Accuracy Mode

**3.1.1.113 ACAL-117 UTool change not allowed**

**Cause:** UTool change is not allowed in High Accuracy Mode

**Remedy:** Exit High Accuracy Mode before changing UTool

**3.1.1.114 ACAL-118 Wristjoint not allowed**

**Cause:** WJNT motion is not allowed in High Accuracy Mode

**Remedy:** Exit High Accuracy Mode before using WJNT motion.

**3.1.1.115 ACAL-120 Remote TCP not allowed**

**Cause:** RTCP motion is not allowed in High Accuracy Mode

**Remedy:** Exit High Accuracy Mode before using RTCP motion.

**3.1.1.116 ACAL-121 Coord motion not allowed**

**Cause:** COORD motion is not allowed in High Accuracy Mode

**Remedy:** Exit High Accuracy Mode before using COORD motion.

**3.1.1.117 ACAL-122 Gravity comp. not allowed**

**Cause:** Gravity compensation is not allowed with High Accuracy

**Remedy:** Disable Gravity Compensation Go through robot library setup at controlled start

**3.1.1.118 ACAL-123 Softfloat not allowed**

**Cause:** Softfloat is not allowed in High Accuracy Mode

**Remedy:** Exit High Accuracy Mode before using Softfloat.

**3.1.1.119 ACAL-124 High Acc Mode not entered**

**Cause:** High Accuracy Mode failed to be entered

**Remedy:** Check alarm history and correct problem

**3.1.1.120 ACAL-125 Problem with Sec. Encoders**

**Cause:** Secondary encoder mode failed to be entered

**Remedy:** Check alarm history and correct problem

**3.1.1.121 ACAL-126 High Acc. Mode entered**

**Cause:** Information status. High Accuracy Mode successfully entered

**Remedy:** No action necessary

**3.1.1.122 ACAL-127 High Acc. Mode exited**

**Cause:** Information status. High Accuracy Mode successfully exited

**Remedy:** No action necessary

**3.1.1.123 ACAL-128 Already in High Acc. mode**

**Cause:** Information status. Already in High Accuracy Mode.

**Remedy:** No action necessary

**3.1.1.124 ACAL-129 Not in High Acc. mode**

**Cause:** Information status. Not in High Accuracy Mode.

**Remedy:** No action necessary

**3.1.1.125 ACAL-130 Filter not empty**

**Cause:** Motion is still active

**Remedy:** Use FINE termttype