void CGmawVM::robotDATInitDunp(ostream &p\_os) const

{

//参数初始化

p\_os<<"&ACCESS RVP"<<'\n'<<"&REL 12"<<'\n'<<"&PARAM DISKPATH = KRC:\\R1"<<endl;

p\_os<<"DEFDAT MAINPROGRAM"<<'\n'<<"EXT BAS (BAS\_COMMAND :IN,REAL :IN )"<<'\n'<<"DECL INT SUCCESS"<<endl;

p\_os<<endl;

//坐标系设定

p\_os<<"DECL FDAT FP0={TOOL\_NO 3,BASE\_NO "<<m\_GmawPropertySetting.baseNumber<<",IPO\_FRAME #BASE,POINT2[]"<<" \" \" "<< ",TQ\_STATE FALSE}"<<endl;

//LINE指令相关参数设置

//Arc Off

//Arc Switch

p\_os<<"DECL LDAT LCPDAT0={ACC 100.000,APO\_DIST 100.000,APO\_FAC 50.0000,AXIS\_VEL 100.000,AXIS\_ACC 100.000,ORI\_TYP #VAR,CIRC\_TYP #BASE,JERK\_FAC 50.0000,GEAR\_JERK 50.0000,EXAX\_IGN 0}"<<endl;

//PTP指令相关参数

p\_os<<"DECL PDAT PPDAT0={ACC 100.000,APO\_DIST 100.000,APO\_MODE #CPTP,GEAR\_JERK 50.0000}"<<endl;

//启弧参数0.00603333377

p\_os<<"DECL ATBg\_Start\_T AS\_WDAT0={JobModeId 732750510,ParamSetId -243025295,StartTime 0.200000,PreFlowTime 0.500000,Channel1 1.00000,Channel2 0.0,Channel3 0.0,Channel4 0.0,Channel5 0.0,Channel6 0.0,Channel7 0.0,Channel8 0.0,PurgeTime 0.0}"<<endl; //送气

p\_os<<"DECL ATBg\_Weld\_T AW\_WDAT0={JobModeId 732750510,ParamSetId -1540567493,Velocity "<<m\_GmawPropertySetting.weldSpeed<<",Channel1 1.00000,Channel2 0.0,Channel3 0.0,Channel4 0.0,Channel5 0.0,Channel6 0.0,Channel7 0.0,Channel8 0.0}"<<endl;

p\_os<<"DECL WTCg\_WeaveDefinition\_T WV\_WDAT0={Pattern #None,Length 4.00000,Amplitude 2.00000,Angle 0.0}"<<endl;

//中间过渡参数与启弧参数

//p\_os<<"DECL ATBg\_Weld\_T AW\_WDAT2={JobModeId 732750510,ParamSetId -1540567493,Velocity 0.00603333377,Channel1 1.00000,Channel2 0.0,Channel3 0.0,Channel4 0.0,Channel5 0.0,Channel6 0.0,Channel7 0.0,Channel8 0.0}"<<endl;

//息弧参数

p\_os<<"DECL ATBg\_Crater\_T AC\_WDAT0 = {JobModeId 732750510,ParamSetId 885173050,CraterTime 0.400000,PostflowTime 0.200000,Channel1 1.00000,Channel2 0.0,Channel3 0.0,Channel4 0.0,Channel5 0.0,Channel6 0.0,Channel7 0.0,Channel8 0.0}"<<endl;

}

void CGmawVM::robotSRCInitDunp(ostream &p\_os) const

{

//参数初始化

p\_os<<"&ACCESS RVP"<<'\n'<<"&REL 12"<<'\n'<<"&PARAM DISKPATH = KRC:\\R1"<<endl;

p\_os<<"DEF MAINPROGRAM()"<<'\n';

p\_os<<";FOLD Moduleparameters;%{h}"<<endl;

p\_os<<";Params Kuka.MoveDataPtpName=PDAT1; Kuka.VelocityPtp=50; Kuka.PointName=P5; Kuka.BlendingEnabled=True; Kuka.FrameData.tq\_state=False; Kuka.FrameData.base\_no=8; Kuka.FrameData.tool\_no=5; Kuka.FrameData.ipo\_frame=#BASE; Kuka.MovementDataPdat.apo\_mode=#CPTP; Kuka.MovementDataPdat.apo\_dist=100; Kuka.MovementData.acc=100; Kuka.MovementData.gear\_jerk=50; ArcTech.WdatVarName=WDAT5; Kuka.MoveDataName=CPDAT4; Kuka.VelocityPath=2; Kuka.MovementData.apo\_fac=50; Kuka.MovementData.apo\_dist=100; Kuka.MovementData.axis\_acc=100; Kuka.MovementData.axis\_vel=100; Kuka.MovementData.circ\_typ=#BASE; Kuka.MovementData.exax\_ign=0; Kuka.MovementData.jerk\_fac=50; Kuka.MovementData.ori\_typ=#CONSTANT; Kuka.FrameData.point2="<<endl;

p\_os<<";ENDFOLD Moduleparameters"<<'\n'<<";FOLD INI;%{PE}"<<'\n'<<" ;FOLD BASISTECH INI"<<endl;

p\_os<<"GLOBAL INTERRUPT DECL 3 WHEN $STOPMESS==TRUE DO IR\_STOPM ( )"<<'\n'<<"INTERRUPT ON 3"<<'\n'<<"BAS (#INITMOV,0 )"<<endl;

p\_os<<" ;ENDFOLD (BASISTECH INI)"<<'\n'<<" ;FOLD USER INI"<<'\n'<<" ;Make your modifications here\n"<<'\n'<<" ;ENDFOLD (USER INI)"<<'\n'<<";ENDFOLD (INI)"<<endl;

p\_os<<endl;

}

//焊接

void CGmawVM::robotSRCDunp(ostream &p\_os, int p\_size) const

{

//回零

p\_os<<"$BWDSTART=FALSE"<<'\n'<<"PDAT\_ACT=PDEFAULT"<<'\n'<<"FDAT\_ACT=FHOME"<<'\n'<<"BAS(#PTP\_PARAMS,10)"<<'\n'<<"$H\_POS=XHOME"<<'\n'<<"PTP XHOME"<<endl;

p\_os<<endl;

for (int j = 0; j < p\_size; ++j)

{

//启弧

if (j == 0)

{

p\_os<<"PDAT\_ACT=PPDAT0"<<'\n'<<"FDAT\_ACT=FP0"<<'\n'<<"BAS(#PTP\_PARAMS, 1.0)"<<endl;

p\_os<<"TRIGGER WHEN DISTANCE = 1 DELAY=ATBg\_PreDefinitionTime DO Arc\_DefineStrikeParams(1, AS\_WDAT0) PRIO = -1"<<'\n'<<"Arc\_DefineCpPattern(#OffInAdvance, WV\_WDAT0, TRUE)"<<endl;

p\_os<<"PTP XP"<<j<<endl;

p\_os<<"Arc\_On(1, AS\_WDAT0, ATBg\_StartErrSetField[1], AW\_WDAT0, WV\_WDAT0, ATBg\_WeldErrSetField[1], #StdArcOn,"<<" \" \")"<<endl;

p\_os<<"Arc\_DefineCpPattern(#OnInAdvance, WV\_WDAT0, TRUE)"<<endl;

p\_os<<endl;

}

//息弧

else if (j == p\_size - 1)

{

p\_os<<"BAS(#CP\_PARAMS, ATBg\_BAS\_VELDefinition)"<<endl;

p\_os<<"LIN XP"<<j<<endl;

p\_os<<"Arc\_Off(1, AC\_WDAT0)"<<endl;

p\_os<<endl;

}

//中间焊接过程

else

{

p\_os<<"LDAT\_ACT=LCPDAT0"<<'\n'<<"LDAT\_ACT.APO\_Dist = ATBg\_APODistanceArcTech"<<'\n'<<"BAS(#CP\_PARAMS, ATBg\_BAS\_VELDefinition)"<<endl;

p\_os<<"TRIGGER WHEN DISTANCE = 1 DELAY = 0 DO Arc\_Swi(1, AW\_WDAT0, WV\_WDAT0, ATBg\_WeldErrSetField[1]) PRIO = -1"<<endl;

p\_os<<"LIN XP"<<j<<" C\_Dis C\_Dis"<<endl;

p\_os<<"ATB\_Definition(AW\_WDAT0)"<<endl;

p\_os<<endl;

}

}

//回零

p\_os<<"$BWDSTART=FALSE"<<'\n'<<"PDAT\_ACT=PDEFAULT"<<'\n'<<"FDAT\_ACT=FHOME"<<'\n'<<"BAS(#PTP\_PARAMS,10)"<<'\n'<<"$H\_POS=XHOME"<<'\n'<<"PTP XHOME"<<endl;

p\_os<<"END"<<endl;

p\_os<<endl;

}