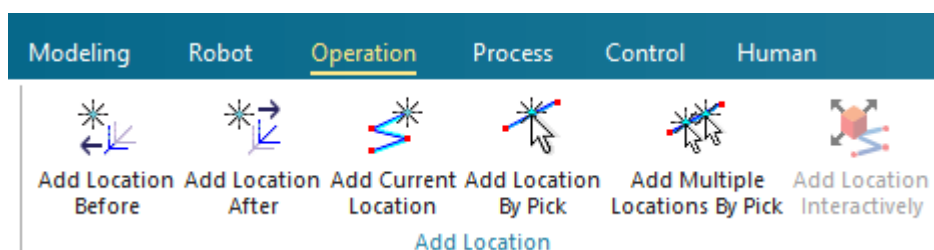


Sa modelom robota YuMi postoje određeni bugovi.

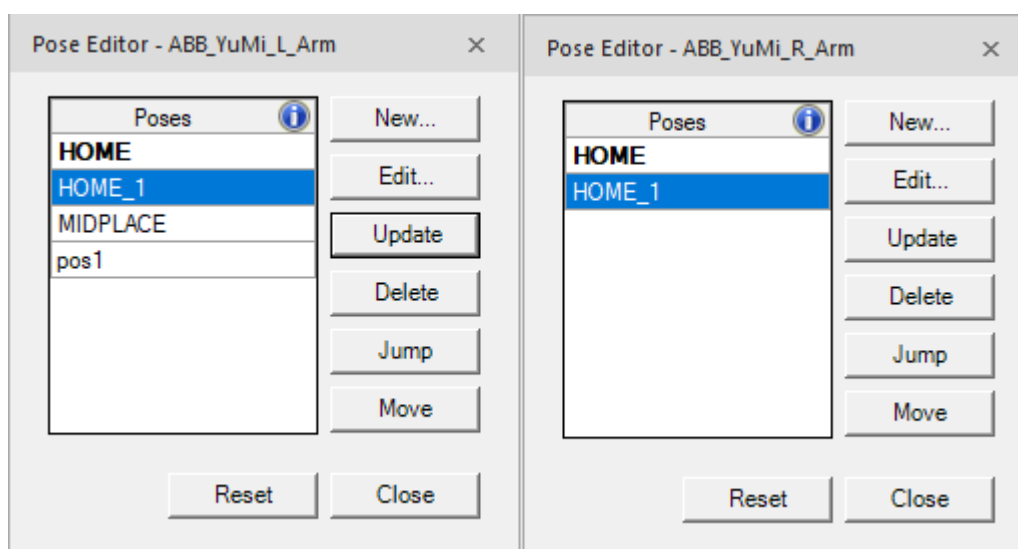
Nakon otvaranja projekta izbrisati sa tipkom Delete i ponovno postaviti točku via 78 pomoću Add Location Before.

Path Editor - ABB_YuMi_L_Arm		
Paths & Locations	Attachment	Duration
YuMi_L_ARM_P...		5.70
via60		0.00
via78		2.40
via61		0.46
via63		0.45
via64		2.40











Izabrati svaku ruku robota YuMi i ući u „Pose Editor“ (desni klik na robotsku ruku). Zatim svaku ruku pomaknuti u HOME_1 sa naredbom Move. Ponoviti svaki put kada robot odradi sklapanje.

Pose Editor



Nakon sklapanja i postavljanja ruku u poziciju HOME_1 provjeriti da su signali ABB_YuMi_L_Arm_at_HOME_1 i ABB_YuMi_R_Arm_at_HOME_1 aktivni. Ako nisu samostalno pritisnuti Input i aktivirati onaj koji je neaktivan unutar Simulation Panel prozora.

Simulation Panel		
		
Simulation	Inputs	Outp.
 ABB_YuMi_R_Arm_at_HOME		
 ABB_YuMi_L_Arm_at_HOME_1		
 ABB_YuMi_L_Arm_at_MIDPLACE		
 ABB_YuMi_R_Arm_at_HOME_1	