

ITIA

Information Model Robot

Lab Report

Stefan Adelmann (01633044)
Hannes Brantner (01614466)

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1 OPC UA Gateway

OPC UA Gateway	
Device:	RaspberryPi 3
ID:	BCM2835 (a02082)
MAC:	b8:27:eb:09:db:ca
IP:	192.168.162.84/25
Port:	4840

2 Robot Controller

Robot Controller	
Device:	Robot Controller
ID:	CR750-D
MAC:	38:e0:8e:9e:89:8d
IP:	192.168.162.82/25
PORT:	10003

3 I/O Mapping

Sensors	
Index	Description
1	Robot handling module - workpiece alignment
2	Robot handling module - workpiece in pick-up position
3	Control panel - Start (make contact)
4	Control panel - Stop (normally closed)
5	Control panel - Reset (NO contact)
7	Control panel - COM bridge (I7)
8	Robot assembly module (spring magazine) - Slider retracted
9	Robot assembly module (spring magazine) - Slide extended
10	Module robot assembly (spring magazine) - spring available
12	Robot assembly module (lid magazine) - Slide retracted
13	Robot assembly module (lid magazine) - Slide extended
15	Module robot assembly (lid magazine) - lid on tray
900	Robot module (hand) - part not black

Actuators	
Index	Description
0	Control panel - Start (LED)
1	Control panel - Reset (LED)
2	Control panel - Q1 (LED)
3	Control panel - Q2 (LED)
4	Control panel - COM bridge (Q4)
8	Robot assembly module (spring magazine) - Slide out
12	Robot assembly module (lid magazine) - Slide out

4 OPC UA Methods

OPC UA Methods			
Method	Description	ObjectId	MethodId
ReadInput(Index)	Returns the Value of the input at the given Index	ns=4;i=1066	ns=4;i=1067
WriteOutput(Index, Value)	Sets the output at the given Index to the given Value	ns=4;i=1066	ns=4;i=1111
GetMostRecentError()	Returns the most recent error that occurred	ns=4;i=1103	ns=4;i=1105
GetRecentErrors(NumberOfErrors)	Returns the last NumberOfErrors errors that occurred	ns=4;i=1066	ns=4;i=1140
ResetError()	Resets the error state of the robot controller	ns=4;i=1102	ns=4;i=1108
OpenGripper()	Opens the multi function gripper	ns=4;i=1130	ns=4;i=1131
CloseGripper()	Closes the multi function gripper	ns=4;i=1130	ns=4;i=1134
Move(X,Y,Z,A,B,C)	Translates the robot arm to the position (X,Y,Z) with the rotation (A,B,C)	ns=4;i=1130	ns=4;i=1137
MoveToSafePosition()	Moves the robot arm into the predefined safety position	ns=4;i=1113	ns=4;i=1115
RestartServer()	Reboots the OPC UA Gateway device	ns=0;i=2253	ns=4;i=1164