10.5.8. Basic Program Nodes: Waypoints

Description

Waypoints are one of the most central parts of a robot program, telling the robot arm where to go one movement at a time.

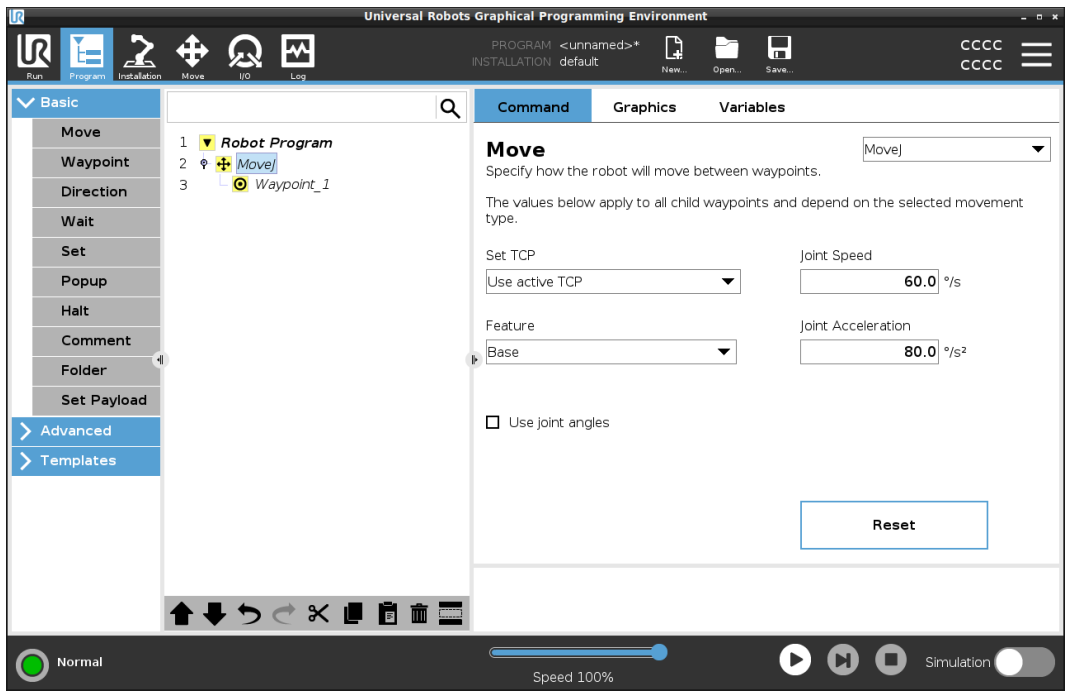
Add Waypoints

A waypoint accompanies a Move, so adding a Move is required for the first waypoint.

Add a waypoint to a robot program

1. In your Robot Program, select the place where you wish to add a Move.
2. Under Basic, tap **Move**.

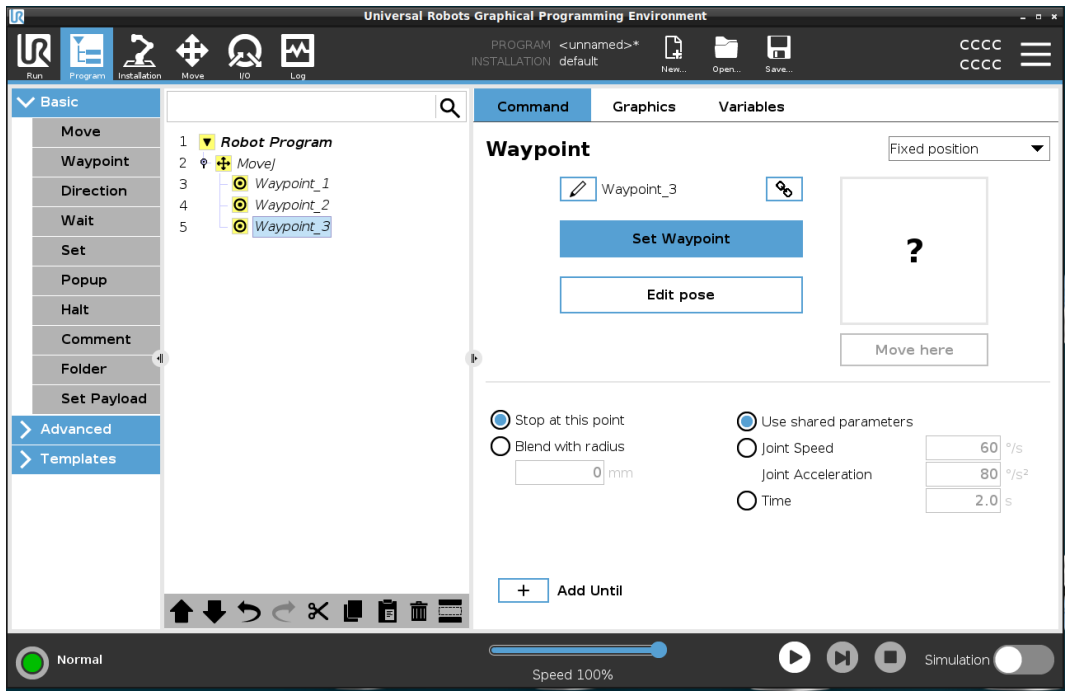
   A waypoint is added to the robot program together with the Move node.



Add additional waypoints to a Move or Waypoint

1. In your Robot Program, select a Move node or Waypoint node.
2. Under Basic, tap **Waypoint**.

   The additional waypoint is added in the Move node. This waypoint is part of the Move command.



The additional waypoint is added under the waypoint that you selected in the robot program.

Detail

Using a waypoint means applying the taught relationship between the feature and the TCP from the Move command. The relationship between the feature and the TCP, applied to the current selected feature, achieves the desired TCP location. The robot calculates how to position the arm to allow the current active TCP to reach the desired TCP position.

10.5.9. Set Payload

Description

The Set Payload command allows you to configure the payload for the robot. Payload is the combined weight of everything attached to the robot tool flange.
When to use:

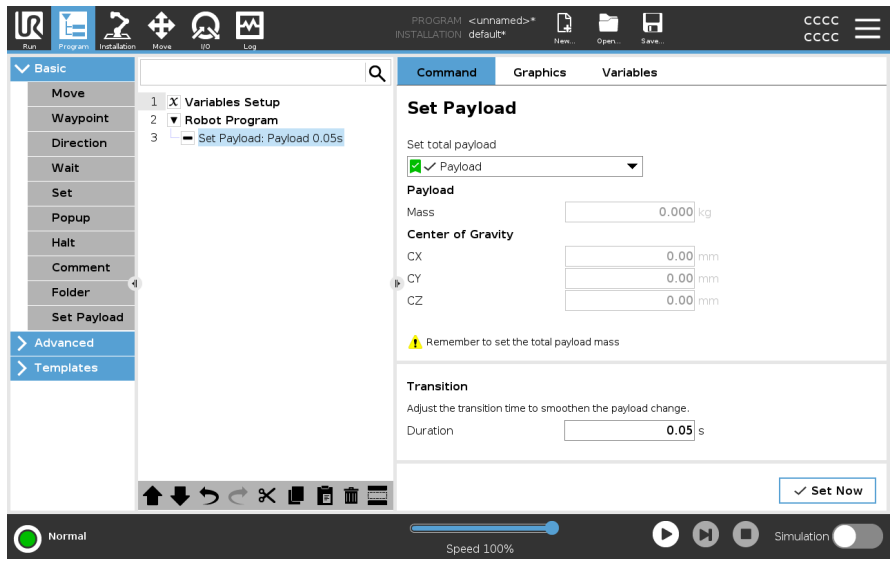
- When adjusting the payload weight to prevent the robot from triggering a robot stop. A correctly configured payload weight ensures optimal robot movement.

  Setting the payload correctly ensures optimal motion performance and avoids robot stops.
- When setting up the payload for use in a pick and place program, using a gripper.

Set Payload

Use the Set Payload command

1. In your robot program, select the place or node where you wish to add a Set command.
2. Under Basic, tap **Set Payload**.
3. Use the drop-down, under **Select Payload**.
    a. Select one of the payloads already configured.
    b. Or, use the drop-down to configure a new payload by selecting **Custom Payload** and completing the mass and CoG fields.



Tip You can also use the **Set Now** button to set the values on the node as the active payload.

Use tip Remember to always update your payload when making any changes to the configuration of the robot program.

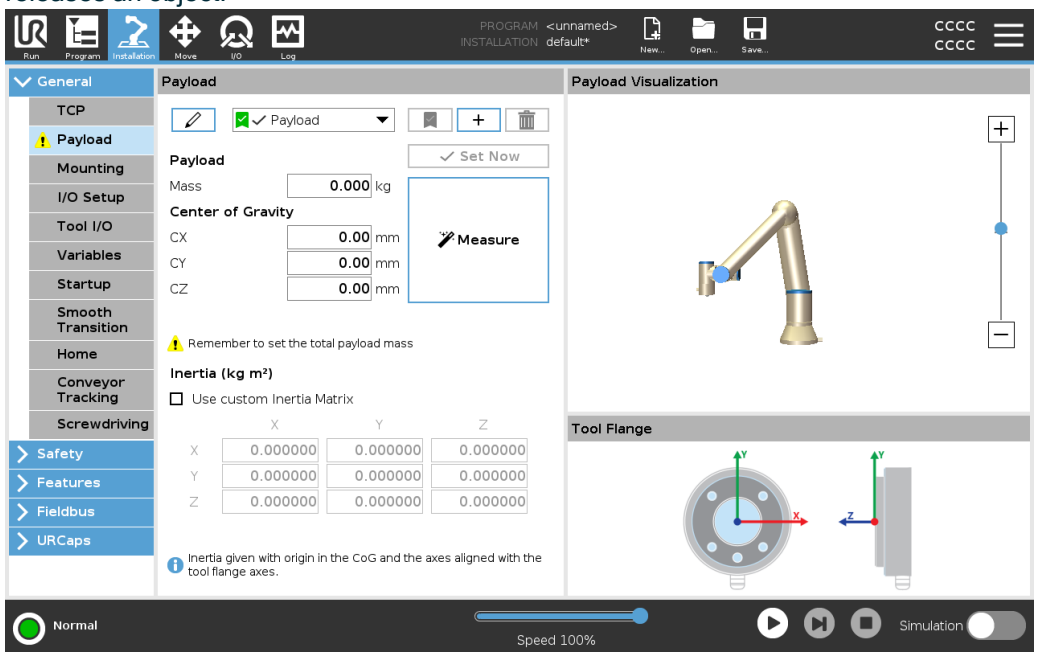
Example: Set Payload In a pick and place program, you would create a default payload in the installation. Then you add a Set Payload when picking up an object. You would update the payload after the gripper closes, but before starting to move.
Additionally, you would use the Set Payload after the object has been released.

Payload Transition Time This is the time it takes the robot to adjust for a given payload. At the bottom of the screen, you can set the transition time between different payloads.
You can add a payload transition time in seconds.
Setting a transition time larger than zero, prevents the robot from doing a small "jump", when the payload changes. The program continues while the adjustment is taking place.
Using the Payload Transition Time is recommended when
picking up or releasing heavy objects or using a vacuum gripper.

10.5.10. Payload

Description

You must set the Payload, the CoG and the inertia for the robot to perform optimally. You can define multiple Payloads, and switch between them in your program. This is useful in Pick and Place applications, for example, where the robot picks up and releases an object.



Adding, Renaming, Modfying and Removing Payloads

You can start configuring a new Payload with the following actions:

- Tap the + to define a new Payload with a unique name. The new payload is available in the drop-down menu.
- Tap the ✎ to rename a Payload.
- Tap the 🗑 to remove a selected Payload. You cannot remove the last Payload.

Active Payload

The checkmark in the drop-down indicates which payload is active ✓ Payload. The active Payload can be changed using the ✓ Set Now.

Default Payload

The default Payload is set as the active Payload before the program starts.

- Select the desired Payload and tap **Set as default** to set a Payload as the default.

The green icon in the drop-down menu indicates the default configured Payload ✓ Payload.

Setting the Center of Gravity

Tap the fields `CX`, `CY` and `CZ` to set the center of gravity. The settings apply to the selected Payload.

Payload Estimation

This feature allows the robot to help set the correct Payload and Center of Gravity (CoG).

Using the Payload Estimation Wizard

1. In the Installation Tab, under General, select **Payload**.
2. On the Payload screen, tap **Measure**.
3. In the Payload Estimation Wizard tap **Next**.
4. Follow the steps in the Payload Estimation Wizard to set the four positions. Setting the four positions requires moving the robot arm into four different positions. The load of the payload is measured at each position.
5. Once all measurements are complete, you can verify the result and tap **Finish**.

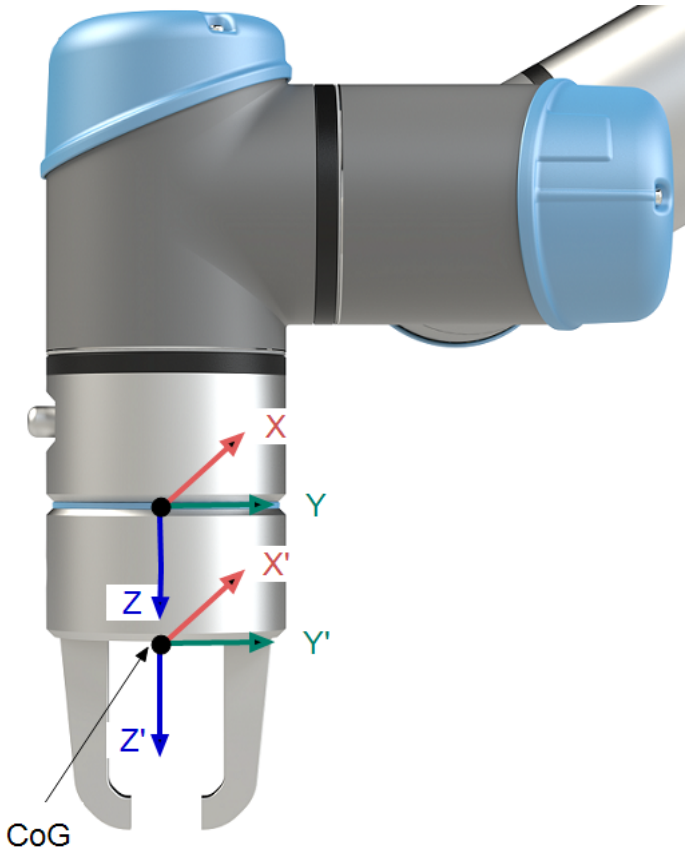
NOTICE

Follow the these guidelines for best Payload Estimation results:

- Ensure the TCP positions are as different as possible from each other
- Perform the measurements within a short timespan
- Avoid pulling on the tool and/or attached payload before and during estimation
- Robot mounting and angle must be correctly defined in the installation

Setting Inertia Values

You can select **Use custom Inertia Matrix** to set inertia values.
Tap the fields: `IXX`, `IYY`, `IZZ`, `IXY`, `IXZ` and `IYZ` to set the inertia for the selected Payload.
The inertia is specified in a coordinate system with the origin at the Center of Gravity (CoG) of the payload and the axes aligned with the tool flange axes.
The default inertia is calculated as the inertia of a sphere with the user specified mass, and a mass density of $1 g/cm^3$



10.5.11. Mounting

Description

Specifying the mounting of the Robot arm serves two purposes:

1. Making the Robot arm appear correctly on screen.
2. Telling the controller about the direction of gravity.

An advanced dynamics model gives the Robot arm smooth and precise motions, as well as allows the Robot arm to hold itself in **Freedrive Mode**. For this reason, it is important to mount the Robot arm correctly.

WARNING

Failure to mount the Robot's arm correctly may result in frequent robot stops, and/or the Robot arm will move when pressing the **Freedrive** button.

If the Robot arm is mounted on a flat table or floor, no change is needed on this screen. However, if the Robot arm is **ceiling mounted**, **wall mounted**, or **mounted at an angle**, this needs to be adjusted using the buttons.
The buttons on the right side of the screen are for setting the angle of the Robot arm's mounting. The top three right side buttons set the angle to **ceiling** (180°), **wall** (90°), **floor** (0°). The **Tilt** buttons set an arbitrary angle.