

19.1. Table 1a

Reduced Mode SF parameter settings change

Description	PFH _D	Affects
<p>Reduced Mode can be initiated by a safety plane/ boundary (starts at 2cm of the plane and reduced mode settings are achieved within 2cm of the plane) or by use of an input to initiate (will achieve reduced settings within 500ms). When the external connections are Low, Reduced Mode is initiated. Reduced Mode means that ALL reduced mode limits are ACTIVE.</p> <p>Reduced mode is not a safety function, rather it is a state change affecting the settings of the following safety function limits: joint position, joint speed, TCP pose limit, TCP speed, TCP force, momentum, power, stopping time, and stopping distance.</p> <p>Reduced mode is a means of parametrization of safety functions in accordance with ISO 13849-1. All parameter values need to be verified and validated as to whether they are appropriate for the robot application.</p>	Less than 1.8E-07	Robot

Safeguard Reset

Description	PFH _D	Affects
When configured for Safeguard Reset and the external connections transition from low to high, the safeguard stop RESETS. Safety input to initiate a reset of safeguard stop safety function.	Less than 1.8E-07 Input to SF2	Robot

3-Position Enabling Device INPUT

Description	PFH _D	Affects
<p>When the external Enabling Device connections are Low, a Safeguard Stop (SF2) is initiated. Recommendation: Use with a mode switch as a safety input. If a mode switch is not used and connected to the safety inputs, then the robot mode will be determined by the User Interface. If the User Interface is in:</p> <ul style="list-style-type: none"> “running mode”, the enabling device will not be active. “programming mode”, the enabling device will be active. It is possible to use password protection for changing the mode by the User Interface. 	Less than 1.8E-07 Input to SF2	Robot