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| Mini Project  Control station with a robot controlled by PLC |  |
| Team members   |  |  |  |  | | --- | --- | --- | --- | | Last name | First name | Last name | First name | |  |  |  |  | | Students |
| Prepared by:   |  |  |  | | --- | --- | --- | | Name | Signature | Date | |  |  |  | | **One team member** |
| Controlled by:   |  |  |  | | --- | --- | --- | | Name | Signature | Date | |  |  |  | | **Second team member** |
| Approved by:   |  |  |  | | --- | --- | --- | | Name | Signature | Date | |  |  |  | | **Supervisor** |
|  | Sion, April 08, 2022 |
| Operational Qualification |  |

# The operator shall be able to use the Emergency stop of the robot and monitor the state of the system on the HMI TP700s.

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| --- | --- |
| **OQ ID** | **Check Emergency Stop** |
| 1 | While the system is in Execute state, the operator presses and Emergency Stop.  The final state on the HIM TP700s is:  Aborted |

# The robot shall be able to pick a part depending on its position on station one (1) and move it in front of a sensor on station two (2).

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| --- | --- |
| **OQ ID** | **The robot picks a part on station one and move the part in front of sensor in station 2** |
| 2 | The operator stars manually motion number… 1  The robot picks the part N… 1 in station one.  The robot moves to station… 2. |