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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 |
| User Requirements Specification |  |

# Capabilities

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| --- | --- |
| **URS ID** | **Description** |
| 1.1 | The operator shall be able to use the Emergency stop of the robot and monitor the state of the system on the HMI TP700. |
| 1.2 | The operator shall be able to hold the system for a break. |
| 1.3 | … |

# Functional requirements

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| --- | --- |
| **URS ID** | **Description** |
| 2.1 | 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). |
| 2.1 | The robot shall be able to place a part in two different positions on station three (3) depending on its hue in station two (2). |
| 2.3 | … |