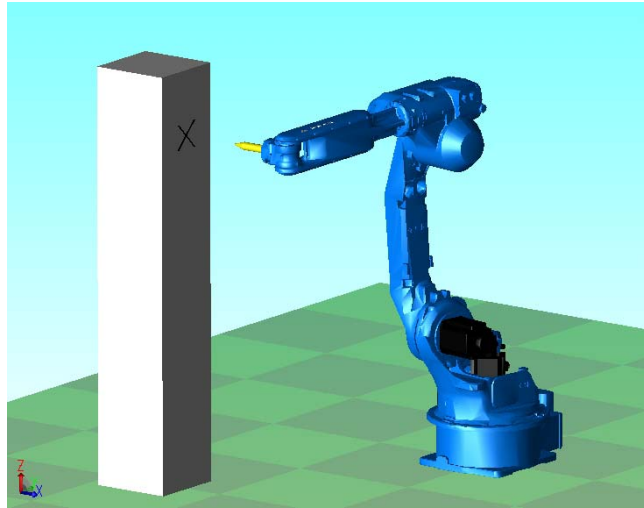


## 6.3 Checking of the Check Program

### 6.3.1 Motion of the Check Program

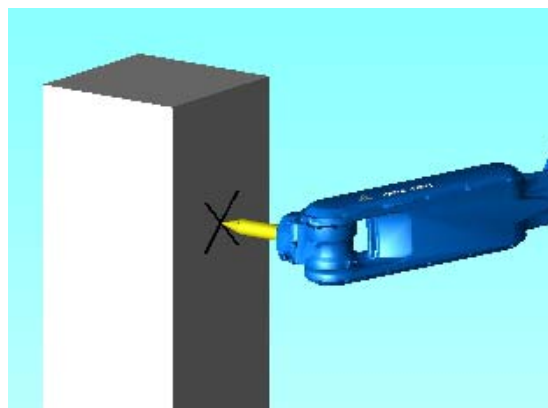
Call up the check program in which the check point is taught (the job for avoiding the position deviation) and operate the manipulator at low speed.



### 6.3.2 Checking of the Check Program

Check the deviation in to the check point. If the tool tip position is deviated, there is a deviation.

When the motor or encoder, etc. was replaced, move the replaced axis only, when the stored memory was cleared or the manipulator was hit against a workpiece, move all axes, to the check point by joint motion.



### 6.3.3 Home Position Data Correction

When there is a deviation from the positions, correct the home position data in accordance with the following procedures.

1. Investigate the values of the following pulses.
  - If there is no deviation, the following two values coincide. Then, proceed to *chapter 6.4 “Setting the Second Home Position (Check Point)”*.
  - If there is a deviation, execute the following procedures to correct it.

**(1) Command position pulse of the check point which was taught in advance**

Displaying the Command Position Pulse

- I) Select {ROBOT} under the main menu.
- II) Select {COMMAND POSITION}.

**(2) Current position pulse where the manipulator (tool tip) was moved to the check point after performing the check program**

Displaying the Current Position Pulse

- I) Select {ROBOT} under the main menu.
- II) Select {CURRENT POSITION}.

2. Calculate the difference between the command position pulse and the current position pulse.

The difference pulse = Command position pulse – Current position pulse

3. On the HOME POSITIONING window, add the difference pulse value to the absolute data of the axis whose motor or encoder, etc. was replaced.
4. Modify the home position data in accordance with the procedures described in *chapter 6.1.2.3 “Changing the Absolute Data”* in *chapter 6.1.2 “Calibrating Operation”*.
5. Confirm that the command position pulse coincides with the current position pulse.
  - The home position data have been corrected.
  - Perform the procedures in *chapter 6.4 “Setting the Second Home Position (Check Point)”*.