

3	Home Position Return
3.1	Home Position Return after Motor Replacement

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3.1.1 Home Position Return by Robot Calibration (MOTOCALV EG)

The MOTOCALV EG allows the home position reset by teaching the five-point-in-five-posture.

Refer to "MOTOCALV EG for Windows Operator's Manual" (manual No. HW0483085) for details on the operation.

3.1.2 Home Position Return by Setting the Teaching Point for Home Position Setting before Replacement

The YRC1000 holds the position data of the job program (hereinafter called as JOB) as the pulse number from the home position of each axis. Stated differently, the precise adjustment of home position allows use of the JOB, which had been used before the motor replacement, without correction even after the motor replacement.

■ Preparation before Replacement

- Refer to the *fig. 3-1 "Preparation before Replacement (Example)"*.

Before replacement, create the standard position (hereinafter called the check-point) for home position adjustment after replacement. The check-point must satisfy the conditions below. Furthermore, create the JOB so that the manipulator safely moves to the check-point from the standby position. (The JOB created in this manner will be hereinafter called the check-JOB.)

① The position should not be deviated by turning the power ON or OFF, or lowering air pressure. Do not create the check point in the working part of the tool (end effector) or the jigs (related unit including the rotary table). It is recommended to use a specific jig if necessary.

② Use pointed jigs to create the position so that the deviation is easily found.

Keep a distance as long as possible from the rotational center of the replacing axis.

③ Considering the moving direction of the replacing axis, create the position at the point where any deviation is easily found and the axis will not interfere with jigs even if it is deviated.