# Error Code: -10001

Description:

Solution: 待补充

# Error Code: -10002

Description: The load detected does not match the theoretical value!

Solution: 待补充

# Error Code: -10003

Description:

Solution: 待补充

# Error Code: -10004

Description:

Solution: 待补充

# Error Code: -10005

Description: The robot is in the virtual wall!

Solution: Please go back to the range of virtual wall.

# Error Code: -10006

Description:

Solution: Please stop other tasks before entering free driving.

# Error Code: -10007

Description: Joints position is out of soft range!

Solution: Please go back to the soft range.

# Error Code: -10008

Description: calling on\_joints\_plan\_service while conveyor is being tracked.

Solution: Make sure conveyor is untracked before calling joints\_plan.

# Error Code: -10009

Description: The Conveyor that being tracked is not be enabled!

Solution: Make sure conveyor is enabled while tracking.

# Error Code: -10010

Description: Unsupported free driving mode.The request was denied.

Solution: 待补充

# Error Code: -10011

Description: Unsupported null space free driving mode.The request was denied.

Solution: 待补充

# Error Code: -20001

Description: Unable to reach the specified trajectory speed.

Solution: Trajectory speed is reduced automatically.

# Error Code: -20002

Description: Unable to reach the specified trajectory acceleration.

Solution: Trajectory acceleration is reduced automatically.

# Error Code: -20003

Description: Joint position limit reached.

Solution: Move the joint back into its allowable range.

# Error Code: -20004

Description: TCP position limit reached.

Solution: Move the tcp back into its allowable range.

# Error Code: -20005

Description: Elbow position limit reached.

Solution: Move the elbow back into its allowable range.

# Error Code: -20000

Description:

Solution: 待补充