

RunProgramInstallationMoveI/OLog

PROGRAM <unnamed>\*  
INSTALLATION rips\*

New...Open...Save...

LocalC C C

Basic

MoveWaypointDirectionWaitSetPopupHaltCommentFolder

Robot Program

- Movej
- Waypoint\_1

Command

Graphics

Variables

Move

Specify how the robot will move between waypoints.

The values below apply to all child waypoints and depend on the selected movement type.

Set TCP

Use active TCP

Joint Speed

60 %/s

Feature

Base

Joint Acceleration

80 %/s²

☐ Use joint angles

Reset

Normal

Speed 100%

Simulation

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Waypoint

Fixed position

Waypoint\_1

Set Waypoint

Edit pose

Move here

☒ Stop at this point

☐ Blend with radius

0 mm

☒ Use shared parameters

☐ Joint Speed

60 %/s

☐ Joint Acceleration

80 %/s²

☐ Time

2 s

+ Add Until

Normal

Speed 100%

Simulation

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- Set
- Wait

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Wait

Please select what should trigger the robot's next action;

☐ No Wait

☐ Wait

0.01 seconds

☐ Wait for Digital Input

<Di.Input>

Low

☐ Wait for

<An.Input>

>

4.0 mA

☐ Wait for

f(x)

Normal

Speed 100%

Simulation

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Set

Select the action you wish the robot to perform at this point in the program. You can also specify changes in the robot's payload.

☐ No Action

☐ Set Digital Output

<Di.Output>

Low

☐ Set Analog Output

<An.Output>

4.0 mA

☐ Set

<Output>

f(x)

☐ Set Single Pulse

<Di.Output>

0.500 s

☐ Increment installation variable by one:

<Variable>

☐ Set Total Payload

0.00 kg

☐ Use active TCP as center of gravity

☐ Set TCP

Test

Normal

Speed 100%

Simulation