```
MODULE MainModule
    CONST robtarget
P10:=[[484.31,-66.55,551.61],[0.728696,0.0560697,0.681994,-0.0272453],[-1,-1,-4,
1],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];
    CONST robtarget
P20:=[[439.64,17.17,239.59],[0.706915,0.0144669,0.707002,0.0144917],[0,0,-4,1],[
9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];
    CONST robtarget
P40:=[[537.11,-255.43,493.27],[0.707005,0.0147762,0.706914,0.0140655],[-1,-1,-4,
1],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];
    CONST robtarget
P30:=[[537.24,-255.44,241.66],[0.706928,0.0145277,0.706989,0.0144125],[-1,-1,-4,
1],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];
    VAR num Z;
    CONST robtarget
p20_2:=[[439.64,17.17,239.59],[0.706915,0.0144669,0.707002,0.0144917],[0,0,0,1],
[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];
    CONST robtarget
p30_2:=[[537.24,-255.44,241.66],[0.706928,0.0145277,0.706989,0.0144125],[-1,-1,0
,1],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];
    CONST robtarget
Inicio:=[[419.304056939,0,451.355777519],[0.7268513,0,0.686794866,0],[0,0,0,1],[
9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];
    CONST robtarget
p40_2:=[[356.13613238,5.133764685,449.475262541],[0.723905658,0.00218937,0.68989
2083,0.002172027],[0,0,-1,1],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];
    PROC main()

      IF DI10_2 =1 THEN
          path_30;

      ENDIF

    ENDPROC

    PROC Path_30()

        Z:=0;

        FOR i FROM 1 TO 3 DO
        MoveL Inicio,v1000,z100,Ventosa\WObj:=wobj0;
        MoveL p20_2,v500,fine,Ventosa\WObj:=WO_ventosa;
        SetDO DO10_1,1;

        IF DI10_1 =0 THEN
        GOTO OUT;
        ENDIF

        WaitTime 2;
        MoveL Offs (p30_2,0,0,Z),v500,fine,Ventosa\WObj:=WO_ventosa;
        Z:=Z+60;
        SetDO DO10_1,0;
        WaitTime 2;
        MoveL p40_2,v1000,z100,Ventosa\WObj:=WO_ventosa;
```

```
        MoveL Inicio,v500,z100,Ventosa\WObj:=wobj0;
        ENDFOR

    OUT:
     SetDO DO10_1,0;
     MoveL Inicio,v500,z100,Ventosa\WObj:=WO_ventosa;

  ENDPROC



ENDMODULE
```