a = from start position

1. 0.5,8
2. Circular,3.5,9
3. Circular,6,8
4. Circular,6.35,7
5. CIRCULAR,6.5,6
6. Linear,6.5,0
7. Linear,6.5,1.3
8. Circular,3.5,0 finev5
9. Circular,0,2.5 fine v5
10. CIRCULAR,1,4.5
11. Circular,3,5
12. Linear,6.5,5

b = from start position

1. 0, 14
2. 0,0
3. 0,2
4. circular 3.5,0
5. circular 6,2
6. circular 6.5,5
7. circular 5.5,8
8. Circular 3,9
9. circular0,7

c =

1. 6,8
2. circular3,9fine v5
3. circular0,5fine v5
4. circular3,0.5fine v5
5. circular6,1 finev5

d =

1. 6.5,14
2. 6.5,0
3. 6.5,2
4. Circular 3.5,0
5. circular0.5,2
6. circular0,5
7. circular1.2,8
8. circular3.5,9
9. circular6,7

e =

1. 7,1
2. circular4,0 zone v5
3. circular1,1zonev5
4. circular0,5zonev1
5. circular1,8zonev1
6. circular5.5,9 zonev1
7. circular7,5zonev1
8. 0,5

f =

1. 2,0
2. 2,11
3. circular3,13
4. circular5.5,13
5. 5.5,13,20
6. 0,9
7. 5,9

g =

1. 1.5,1
2. circular0,-1zone1
3. circular1,-3zone1
4. circular3.5,-3.5zone5
5. circular6,-2.5zone5
6. circular7,-1zone5
7. circular6,1 zone5
8. 1.5,1
9. circular0,2.5
10. circular1,4
11. circular0,6.5
12. circular3,9
13. 7.5,9
14. 4,9
15. Circular 6,7 zone1
16. Circular 6,5 zone1
17. Circular 3.5,3.5
18. Circular 1,4

h =

1. 0,0
2. 0,14
3. 0,7
4. 2,8
5. 4,9 z5
6. circular5.8,7.2
7. circular 6,6
8. 6,0

i =

1. 0,0
2. 0,9.5
3. 0,9.5,20
4. 0,12,20
5. 0,12
6. 0,12.1

j =

1. -3,-3
2. circular -1,-2.5
3. circular 0.-1
4. 0,9.5
5. 0,9.5,20
6. 0,12,20
7. 0,12
8. 0,12.1

k =

1. 0,14
2. 0,0
3. 0,5
4. 5.8,9
5. 0,5 z1
6. 6.2,0

l =

1. 0,0
2. 0,14

m =

1. 0,0
2. 0,9.5
3. 0,7
4. 2,8.5
5. Circular 4,9 z5
6. Circular 6,8 z5
7. 6,0
8. 6,7 z5
9. 7.4,8.60 z1
10. Circular 10,9 z5
11. Circular 12,8 z5
12. 12,0

n =

1. 0,0
2. 0,9.5
3. 0,7
4. 2,8.5
5. Circular 4,9 z5
6. Circular 6,8 z5
7. 6,0

o =

1. 2,0.5
2. circular2,7.5
3. circular6.5,7.5
4. circular6.5,0.5
5. circular2,0.5

p =

1. 0,-3.5
2. 0,9
3. 0,7
4. Circular3,9
5. Circular6,8
6. Circular7,4.5
7. Circular6,1
8. Circular4,0
9. Circular0,2

q =

1. 7,-4
2. 7,9
3. 7,7
4. Circular4,9
5. Circular1,8
6. Circular0,4.5
7. Circular1,1
8. Circular3,0
9. Circular7,2

r =

1. 0,0
2. 0,9.5
3. 0,7
4. 2,8.5
5. Circular 4,9
6. Circular 6,8

s = all circular

1. 0,2
2. 2.5,0 z5
3. 5,1 z5
4. 5.5,2 z5
5. 4,4 z5
6. Linear 1,6 z5
7. 0.5, 7.5 z5
8. 1,9 z5
9. 4,9.5
10. 5.5,8

t =

1. 2,12
2. 2,2
3. circular3,0.5
4. circular5,1
5. 5,1,20
6. 0,9
7. 5,9

u =

1. 6,9.5
2. 6,0
3. 6,2
4. 4,1
5. Circular2,0.5
6. Circular0,1.5
7. 6,9.5

v =

1. 0,9
2. 4,0
3. 8,9

w =

1. 0,9
2. 4,0
3. 8,9
4. 12,0
5. 16,9

x =

1. 0,0
2. 6,9
3. 6,9,20
4. 0,9,20
5. 0,9
6. 6,0

y =

1. 6,9
2. 2.5,-3
3. 3,0
4. 0,9

z =

1. 0,9
2. 5.5,9
3. 0,0
4. 6,0

Dash =

1. 0,5
2. 4.5,5

dot = all circular

1. 0,0.75
2. 0.75,1.5
3. 1.5,.75
4. .75,0
5. 0,0.75

? =

1. 0,12 circular
2. 3,13 circular
3. 6,10circular
4. 5,7circular
5. 2.5,6.5circular
6. 2.5,3
7. 2.5,3,20
8. 1.75,0.75,20
9. 1.75,0.75
10. 2.5,1.5
11. 3.25,.75
12. 2.5,0
13. 1.75,0.75

PROC a()

MoveL a\_1,v50,fine,MyNewTool\WObj:=A3;

MoveC a\_2,a\_3,v50,fine,MyNewTool\WObj:=A3;

MoveC a\_4,a\_5,v50,fine,MyNewTool\WObj:=A3;

MoveL a\_6,v50,fine,MyNewTool\WObj:=A3;

MoveL a\_7,v50,fine,MyNewTool\WObj:=A3;

MoveC a\_8,a\_9,v50,fine,MyNewTool\WObj:=A3;

MoveC a\_10,a\_11,v50,z5,MyNewTool\WObj:=A3;

MoveL a\_12,v50,fine,MyNewTool\WObj:=A3;

ENDPROC

CONST robtarget a\_1:=[[10.5,18,0],[0,1,0,0],[0,0,0,0],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];

CONST robtarget a\_2:=[[13.5,19,0],[0,1,0,0],[0,0,0,0],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];

CONST robtarget a\_3:=[[16,18,0],[0,1,0,0],[0,0,0,0],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];

CONST robtarget a\_4:=[[16.35,17,0],[0,1,0,0],[0,0,0,0],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];

CONST robtarget a\_5:=[[16.5,16,0],[0,1,0,0],[0,0,0,0],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];

CONST robtarget a\_6:=[[16.5,10,0],[0,1,0,0],[0,0,0,0],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];

CONST robtarget a\_7:=[[16.5,11.3,0],[0,1,0,0],[0,0,0,0],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];

CONST robtarget a\_8:=[[13.5,10,0],[0,1,0,0],[0,0,0,0],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];

CONST robtarget a\_9:=[[10,12.5,0],[0,1,0,0],[0,0,0,0],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];

CONST robtarget a\_10:=[[11,14.5,0],[0,1,0,0],[0,0,0,0],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];

CONST robtarget a\_11:=[[13,15,0],[0,1,0,0],[0,0,0,0],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];

CONST robtarget a\_12:=[[16.5,15,0],[0,1,0,0],[0,0,0,0],[9E+09,9E+09,9E+09,9E+09,9E+09,9E+09]];