File Edit Action Flow Special

● Collborating

	2	**Gripper** (open gripper 0%)	
	3	**Loop** (repeat until 'DIn27') - robot stop switch	
	4	**Joint** (constant: A1=45.0°, A2=0.0°, A3=0.0°, A4=90.0°, vel=40%, acc=40%, smooth=0%) - First robot picking the work piece	
	5	**Linear** (constant: X=170 mm, Y=170 mm, Z=398 mm, A=-135.0°, B=0.0°, C=180.0°, vel=100 mm/s, acc=40%, smooth=0%)	
	6	**Linear** (constant: X=170 mm, Y=170 mm, Z=100 mm, A=-135.0°, B=0.0°, C=180.0°, vel=100 mm/s, acc=40%, smooth=0%)	
	7	**Wait** (wait for 2 s)	
	8	**Gripper** (open gripper 100%)	
	9	**Relative** (base: X=0 mm, Y=0 mm, Z=-50 mm, vel=100 mm/s, acc=40%, smooth=0%)	
	10	**Wait** (wait for 2 s)	
	11	**Gripper** (open gripper 30%)	
	12	**Relative** (base: X=0 mm, Y=0 mm, Z=50 mm, vel=100 mm/s, acc=40%, smooth=0%)	
	13	**Linear** (constant: X=170 mm, Y=170 mm, Z=398 mm, A=-135.0°, B=0.0°, C=180.0°, vel=100 mm/s, acc=40%, smooth=0%)	
	14	**Joint** (constant: A1=0.0°, A2=0.0°, A3=0.0°, A4=0.0°, vel=40%, acc=40%, smooth=0%)	
	15	**If** (if 'DIn21') - Second robot connect to Input Module	
	16	**Joint** (constant: A1=0.0°, A2=0.0°, A3=0.0°, A4=0.0°, vel=40%, acc=40%, smooth=0%)	
	17	**Gripper** (open gripper 100%)	
	18	**Relative** (base: X=150 mm, Y=0 mm, Z=0 mm, vel=100 mm/s, acc=40%, smooth=0%)	
	19	**Wait** (wait for 2 s)	
	20	**Gripper** (open gripper 30%)	
	21	**Relative** (base: X=-150 mm, Y=0 mm, Z=0 mm, vel=100 mm/s, acc=40%, smooth=0%)	
	22	**Joint** (constant: A1=-45.0°, A2=0.0°, A3=0.0°, A4=90.0°, vel=40%, acc=40%, smooth=0%)	
	23	**Linear** (constant: X=170 mm, Y=-170 mm, Z=398 mm, A=135.1°, B=0.0°, C=180.0°, vel=100 mm/s, acc=40%, smooth=0%)	
	24	**Linear** (constant: X=170 mm, Y=-170 mm, Z=100 mm, A=-135.0°, B=0.0°, C=180.0°, vel=100 mm/s, acc=40%, smooth=0%)	
	25	**Relative** (base: X=0 mm, Y=0 mm, Z=-50 mm, vel=100 mm/s, acc=40%, smooth=0%)	
	26	**Wait** (wait for 2 s)	
	27	**Gripper** (open gripper 100%)	
	28	**Wait** (wait for 2 s)	
	29	**Linear** (constant: X=170 mm, Y=-170 mm, Z=200 mm, A=-135.0°, B=0.0°, C=180.0°, vel=100 mm/s, acc=40%, smooth=0%)	
	30	**Linear** (constant: X=170 mm, Y=-170 mm, Z=398 mm, A=135.1°, B=0.0°, C=180.0°, vel=100 mm/s, acc=40%, smooth=0%)	
	31	**Joint** (constant: A1=0.0°, A2=0.0°, A3=0.0°, A4=90.0°, vel=40%, acc=40%, smooth=0%)	
	32	**Gripper** (open gripper 0%)	
	33	**Else**	

Saved file: C:\Users\kalya\Desktop\IES\igus\iRC-igusRobotControl\Data\Programs\assembling.xml

23°C
Cloudy

ENG
IN

20:52
06-10-2022