

•Assignmnet 2

+	0	Start - iRC V902-13-023, igus Arm (robolink-legacy\RL-D-DCi-4S-M), without gripper	↑	↓	✕
+	• 1	Joint (constant: A1=0.0°, A2=0.0°, A3=0.0°, A4=90.0°, vel=40%, acc=40%, smooth=0%)	↑	↓	✕
+	2	Gripper (open gripper 0%)	↑	↓	✕
+	3	Loop (repeat until 'Dln27')	↑	↓	✕
+	4	Joint (constant: A1=45.0°, A2=0.0°, A3=0.0°, A4=90.0°, vel=40%, acc=40%, smooth=0%)	↑	↓	✕
+	5	Linear (constant: X=170 mm, Y=170 mm, Z=347 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=347 mm, A=-135.0°, B=0.0°, C=180.0°, vel=100 mm/s, acc=40%, smooth=0%)	↑	↓	✕
+	14	Joint (constant: A1=-45.0°, A2=0.0°, A3=0.0°, A4=90.0°, vel=40%, acc=40%, smooth=0%)	↑	↓	✕
+	15	Linear (constant: X=170 mm, Y=-170 mm, Z=347 mm, A=135.0°, B=0.0°, C=180.0°, vel=100 mm/s, acc=40%, smooth=0%)	↑	↓	✕
+	16	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%)	↑	↓	✕
+	17	Relative (base: X=0 mm, Y=0 mm, Z=-50 mm, vel=100 mm/s, acc=40%, smooth=0%)	↑	↓	✕
+	18	Wait (wait for 2 s)	↑	↓	✕
+	19	Gripper (open gripper 100%)	↑	↓	✕
+	20	Wait (wait for 2 s)	↑	↓	✕
+	21	Linear (constant: X=170 mm, Y=-170 mm, Z=347 mm, A=135.0°, B=0.0°, C=180.0°, vel=100 mm/s, acc=40%, smooth=0%)	↑	↓	✕
+	22	Joint (constant: A1=0.0°, A2=0.0°, A3=0.0°, A4=90.0°, vel=40%, acc=40%, smooth=0%)	↑	↓	✕
+	23	EndLoop	↑	↓	✕