

Program Editor

File Edit Action Flow Special

<empty> assembling

0	Start	- IRC V902-13-023, igus Arm (robolink-legacy\RL-D-DCI-45-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=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=-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=398 mm, A=135.1°, 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=100 mm, A=-135.0°, B=0.0°, C=180.0°, vel=100 mm/s, acc=40%, smooth=0%)	
22	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%)	
23	Joint	(constant: A1=0.0°, A2=0.0°, A3=0.0°, A4=90.0°, vel=40%, acc=40%, smooth=0%)	
24	Gripper	(open gripper 0%)	
25	Joint	(constant: A1=45.0°, A2=0.0°, A3=0.0°, A4=90.0°, vel=40%, acc=40%, smooth=0%)	
26	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%)	
27	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%)	
28	Wait	(wait for 2 s)	
29	Gripper	(open gripper 100%)	
30	Relative	(base: X=0 mm, Y=0 mm, Z=-50 mm, vel=100 mm/s, acc=40%, smooth=0%)	
31	Wait	(wait for 2 s)	
32	Gripper	(open gripper 30%)	

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