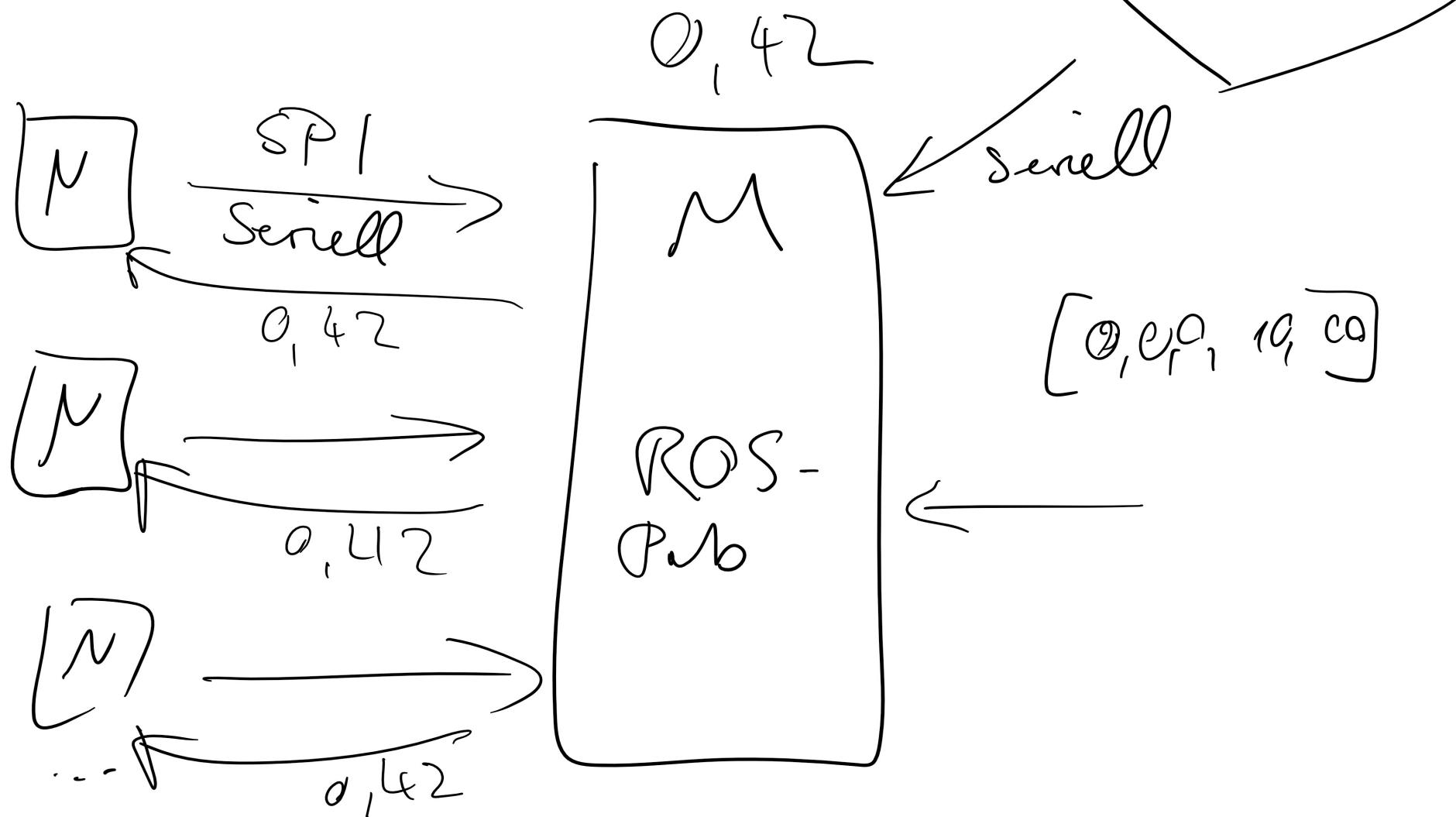


7 x Nano \rightarrow per Achse

1x Mega \rightarrow

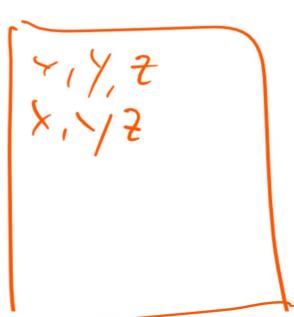


Teachen

P1 (x,y,z,a,b,c)

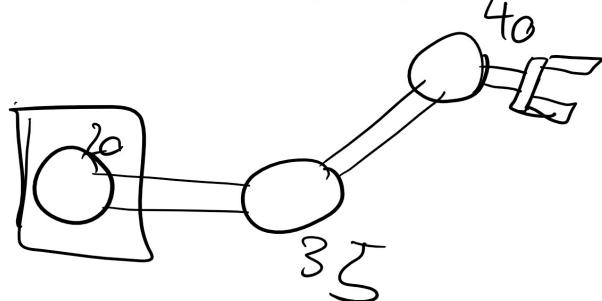
P2 (x,y,z,a,b,c)

P3 (x,y,z,a,b,c)



Add P

Save to P[0]



- Move P1
- Move P2
- Gripper Close
- Move P2
- Move P3
- Gripper Open
- Wait 1s → sleep
- Move P3
- Move P1
- ~~Wait_for_Input Ext1~~

move [x, y, z]
move [x, y, z]

[D / 100] Execute

Test

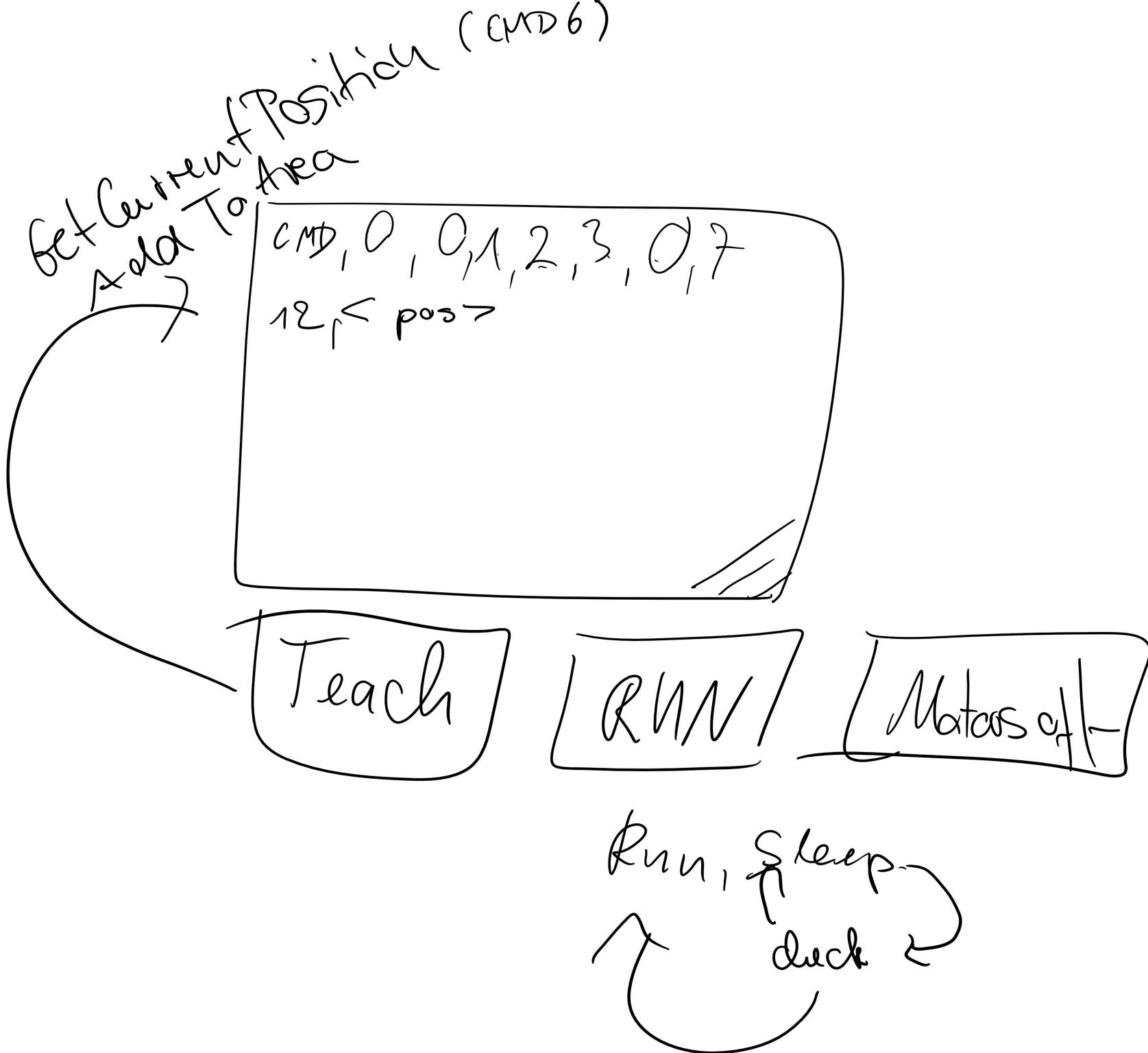
J1 J2 J3 J4 J5 J6 Gr
 ① ② ③ ④ ⑤ ⑥ ⑦

Drive

J1 + -
 J2 + -
 J3 + -
 J4 + -
 J5 + -
 J6 + -

Greifer
 1 100 Steps

↑
 Gr



Move Robot Arm to Relative position

Drive by Hand

rel-drive \Rightarrow drive-joint

J1 - Z Axis

+ $10, <\text{Step}>, 0, 0, 0, 0, 0, 0 \backslash n$ - $- <\text{Step}> \dots$

J2 - Shoulder

+ $10, 0, <\text{Step}>, 0, 0, 0, 0, 0 \backslash n$ -

J3 - Ellbow

+ $10, 0, 0, <\text{Step}>, 0, 0, 0, 0 \backslash n$ -

J4 - Hand - UAJ

+ $10, 0, 0, 0, <\text{Step}>, 0, 0, 0 \backslash n$ -

J5

+ $10, 0, 0, 0, 0, <\text{Step}>, <\text{Step}>, 0 \backslash n$ - $\dots - <\text{Step}>, - <\text{Step}>$

J6

+ $10, 0, 0, 0, <\text{Step}>, - <\text{Step}>, 0 \backslash n$ - $\dots - <\text{Step}>, <\text{Step}>, 0 \backslash n$

Gripper

+ $5 + 100 \text{ Gripper}$ - $- 100 \text{ Gripper}$

100

$10, 0, 0, 0, 0, 0, 0, <\text{Step}> \backslash n$

Default,

Current Point: [0, 0, 0, 0, 0, 0, 0]

$10 \rightarrow \text{drive-distance}$

Robot Parameters

Home, Zone and Toggle Motor

2,1\n
Toggle Motor On Off 2,0\n
Home Zero Axis 1\n

visual Indicator!

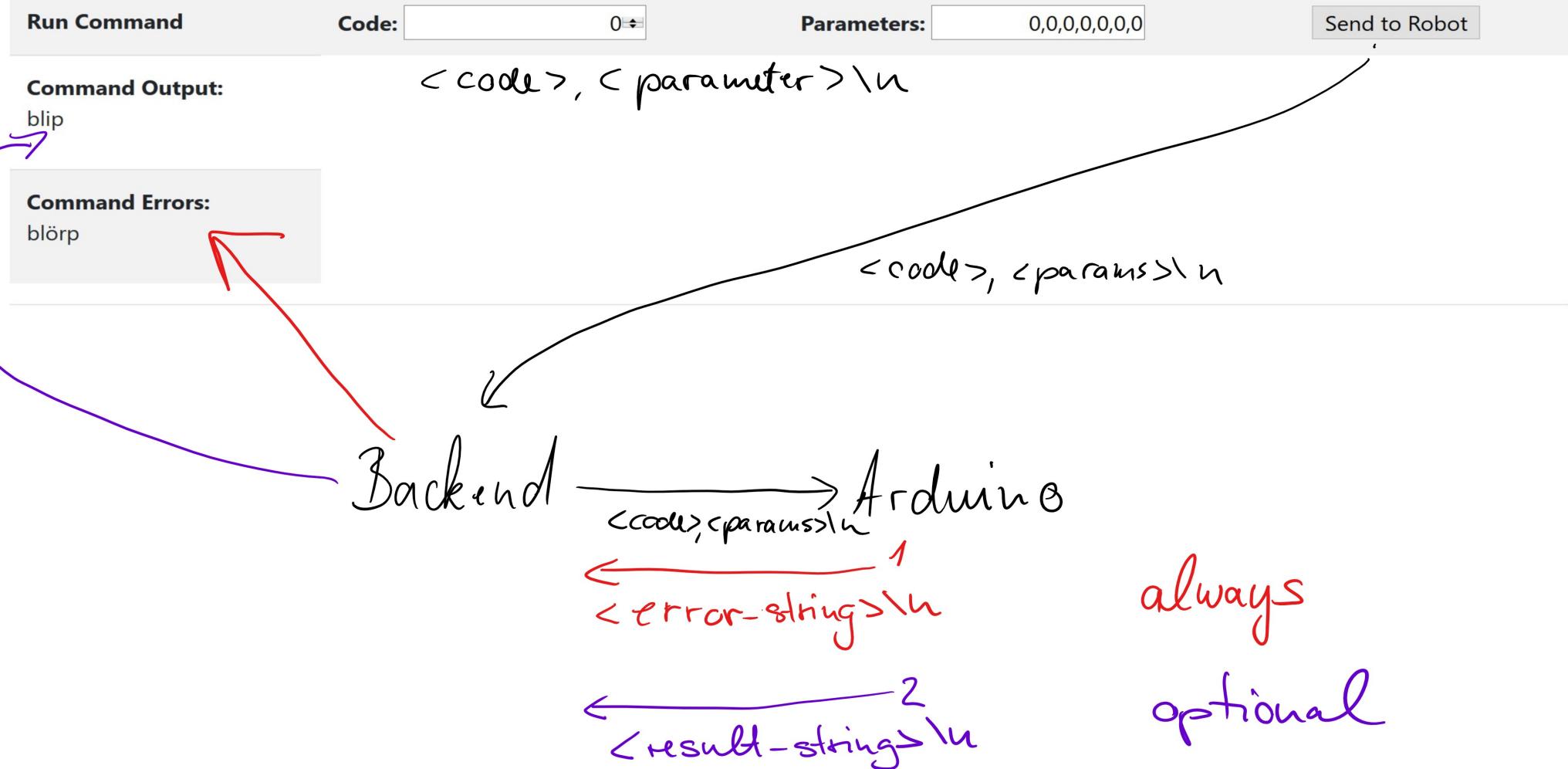


Zone 100
16,<zone>\n

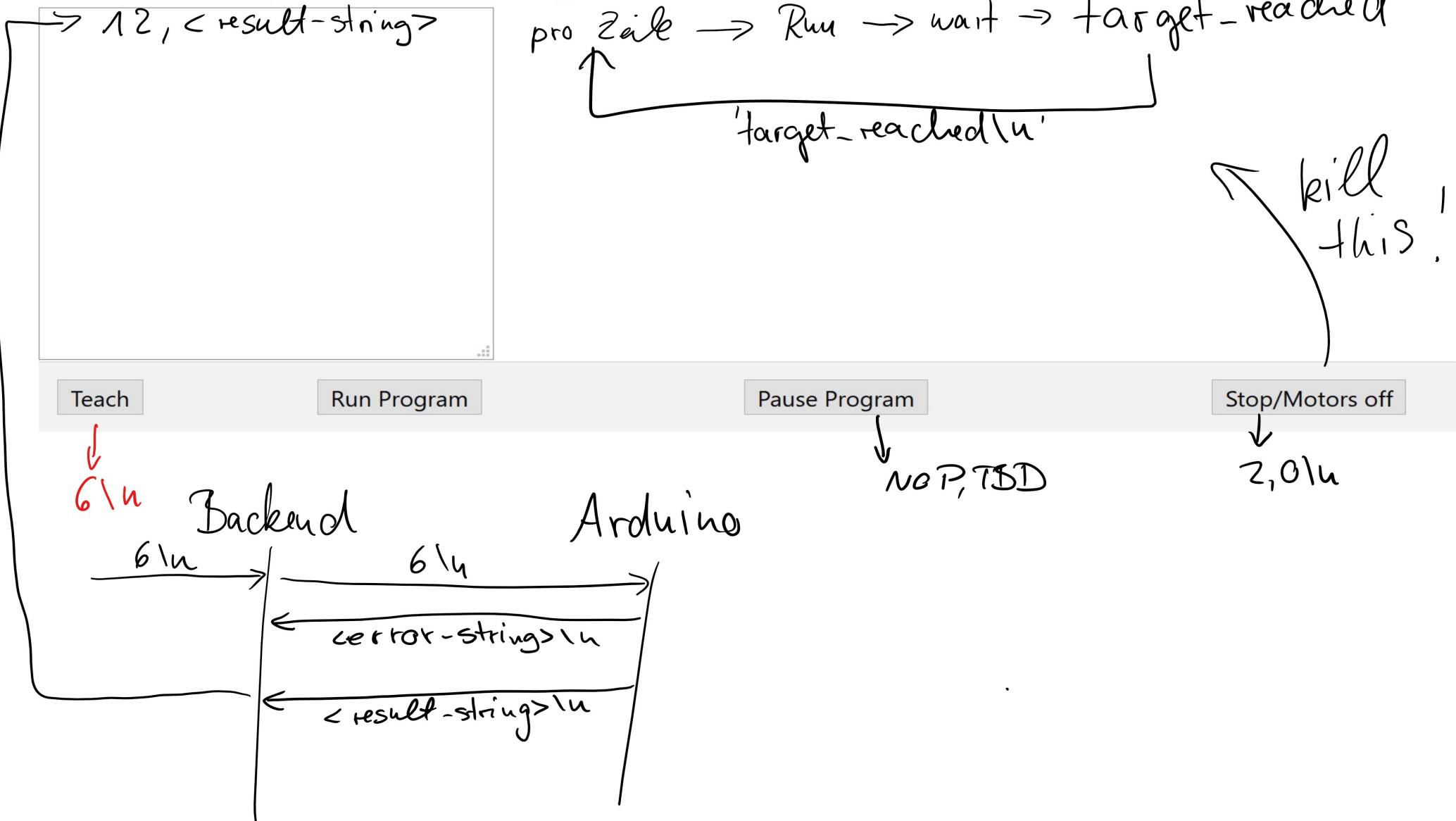
Speed 100
15,<speed>\n

Set Parameters

Custom Commands



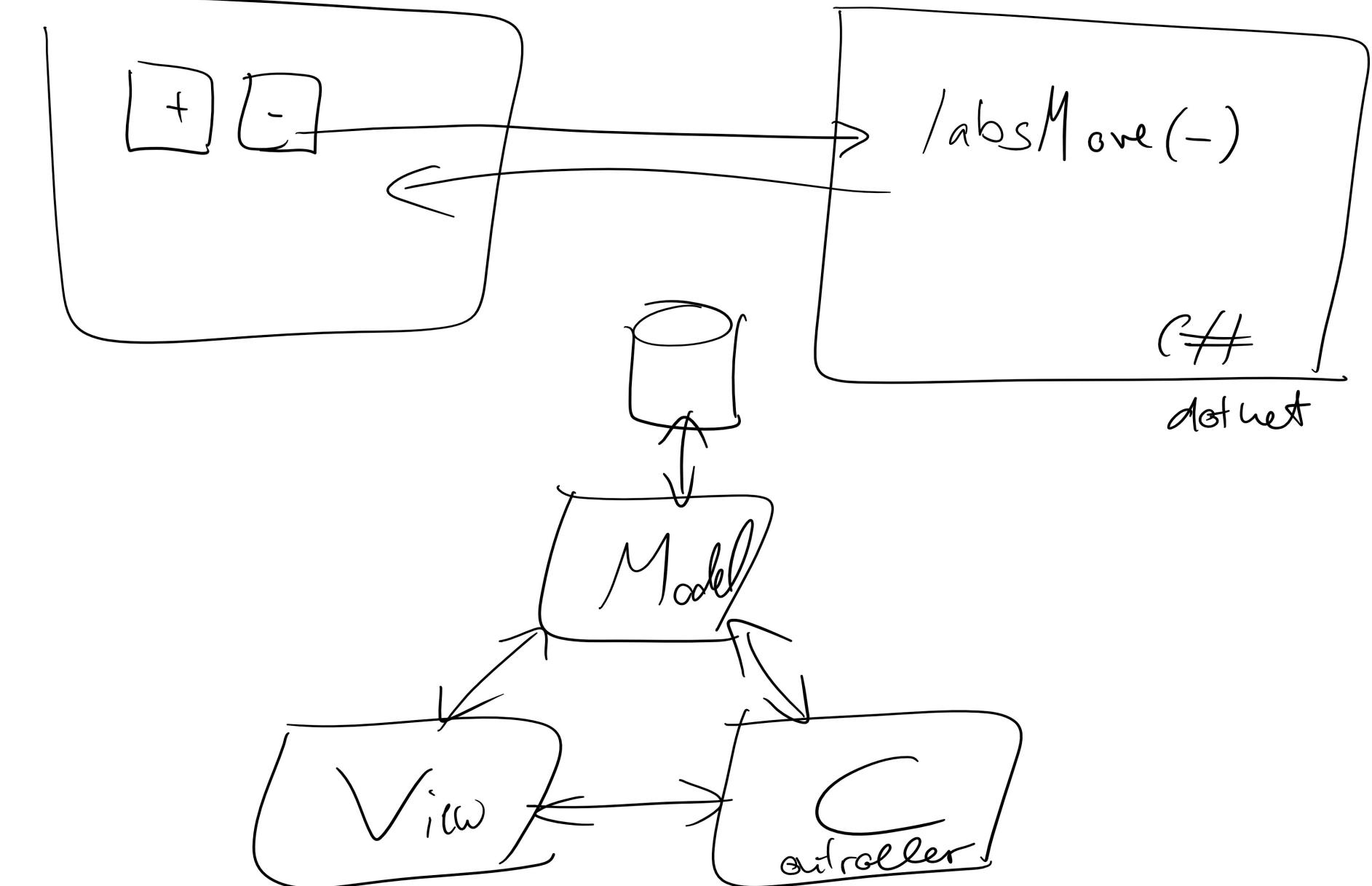
Define Simple Robot Program



lokal

Browser

Backend



Aktionen

- Bewegen
- Wo bin ich? akt. Position
- Operation / idle
- Punkt definieren + wiederherstellen
- Programme definieren, Befehlssatz

