

HOW TO LOWER THE WAITING POSITION IN KEBA CONTROLLER



WARNING

THIS MODIFICATION MAY CAUSE SERIOUS DAMAGE
ON THE ROBOT ARM, EOAT, AND THE MOLD MACHINE.

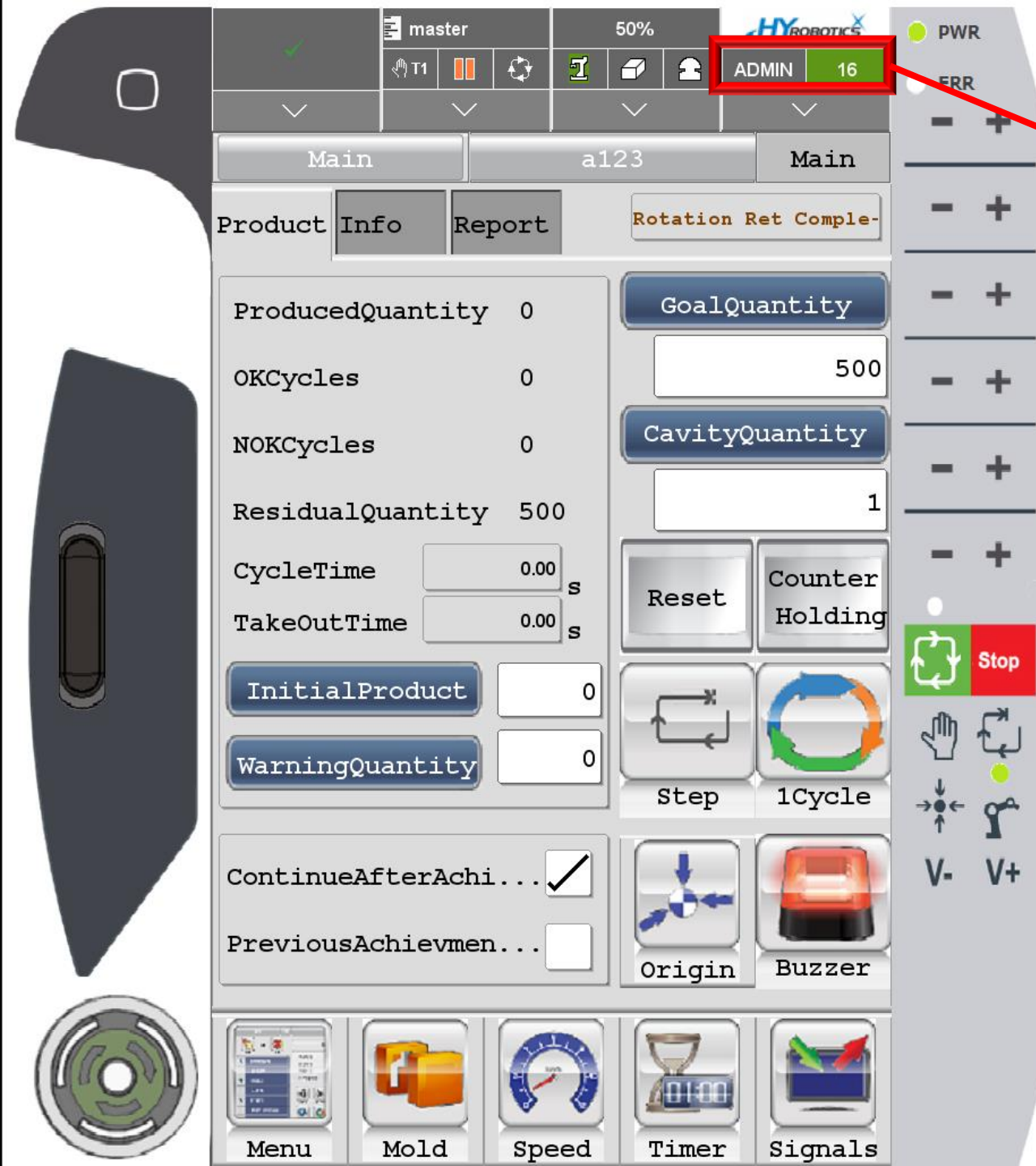
For the safety,
The program requires the Waiting position z-axis to be “0 mm”

However, you can lower the waiting position so that you can save taking-out time.

This modification may cause an accident. Do at your own risk.

DO NOT FORGET

BACK UP THE MEMORY DATA BEFORE MODIFYING THE FILES



Log in level 16 Admin
PW: pass



At first,
the mold safety area
need to be adjusted

Press menu button TWICE



Press here



Press
EUROMAP

master

50%

HY ROBOTICS

T1

ADMIN

16


EUROMAP

EUROMAP selection

SEM

active

Mold monitor state



☐ Rob in mold closure area


☐ Mold is over middle

☐ Zone-switch fb. 'mold free'

☐ Enable mold close

☒ Mold is open

Robot state



☐ Manual mode active


☒ All axes referenced

☐ Production without robot

☒ Robot switched on

☐ Autom. programm running

Machine signals



☐ Is in automatic mode

State

Signals

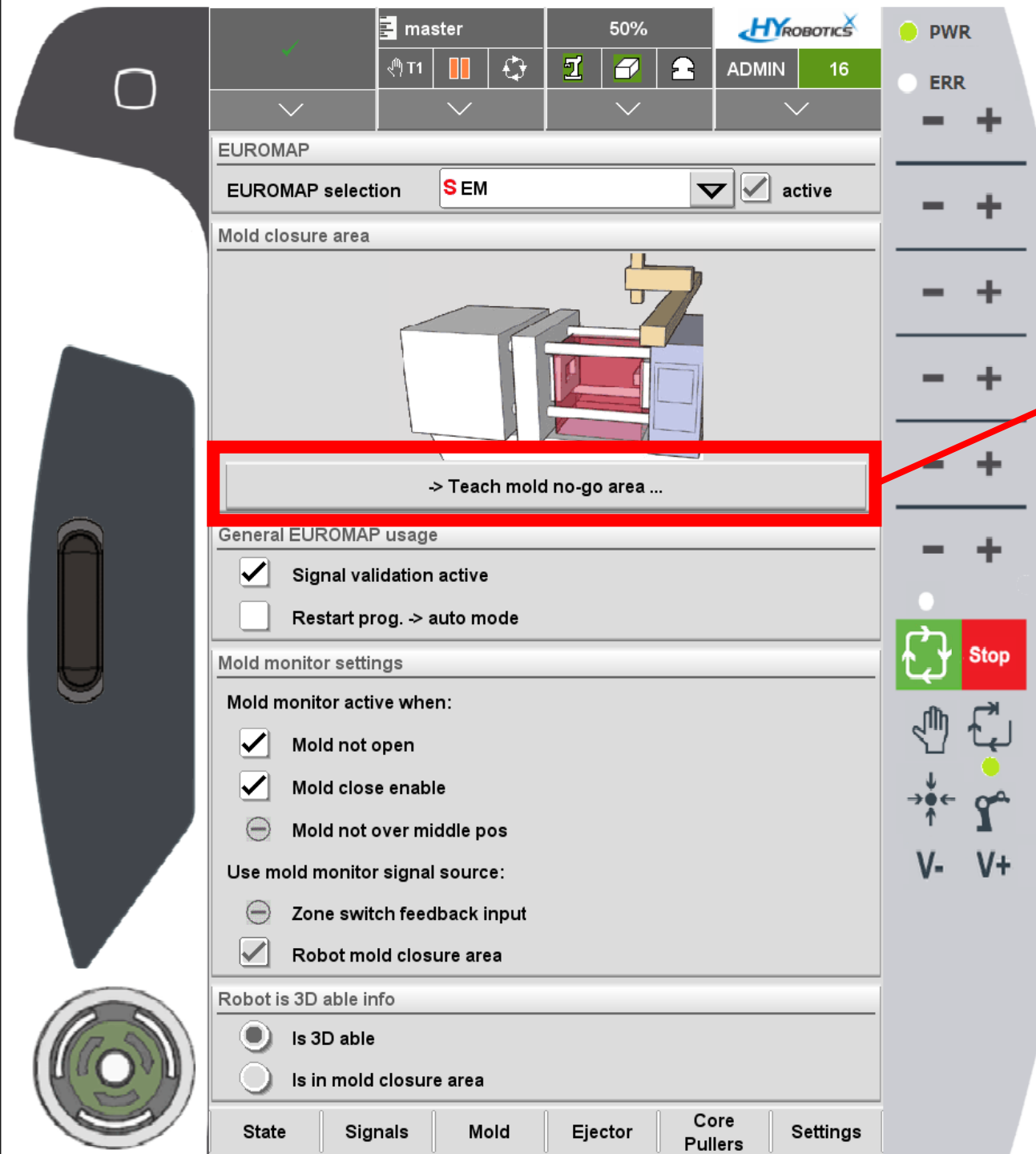
Mold

Ejector

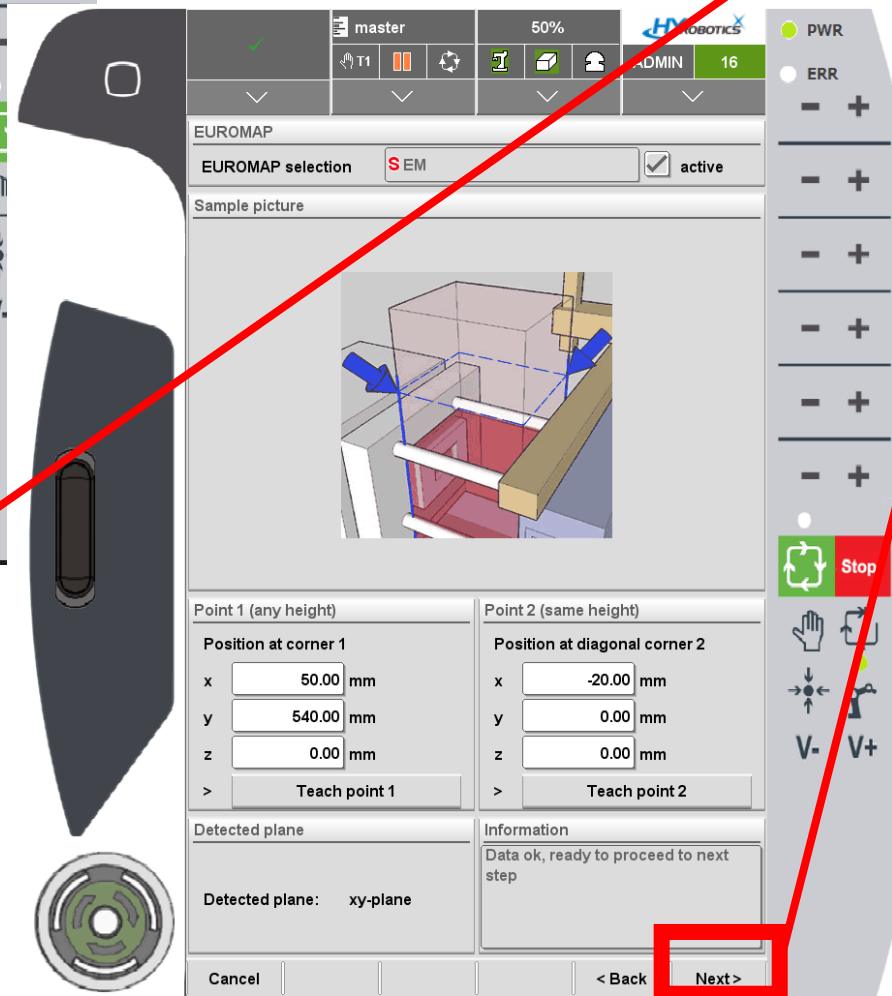
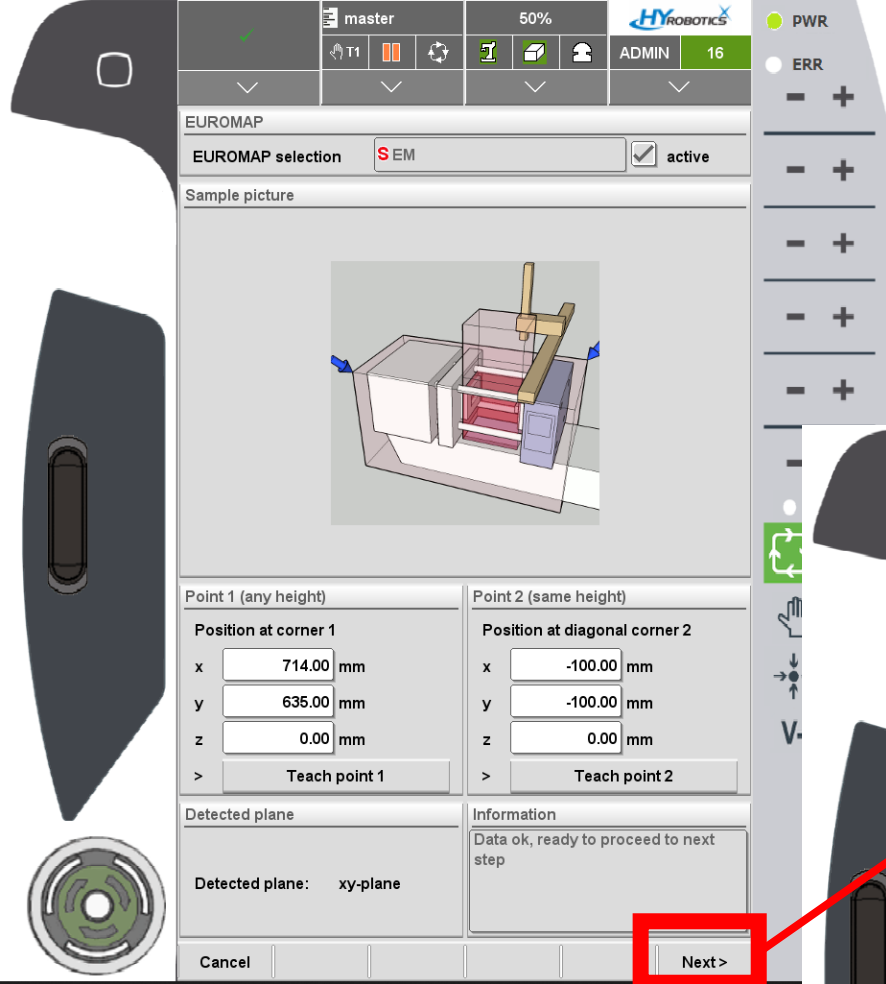
Core Pullers

Settings

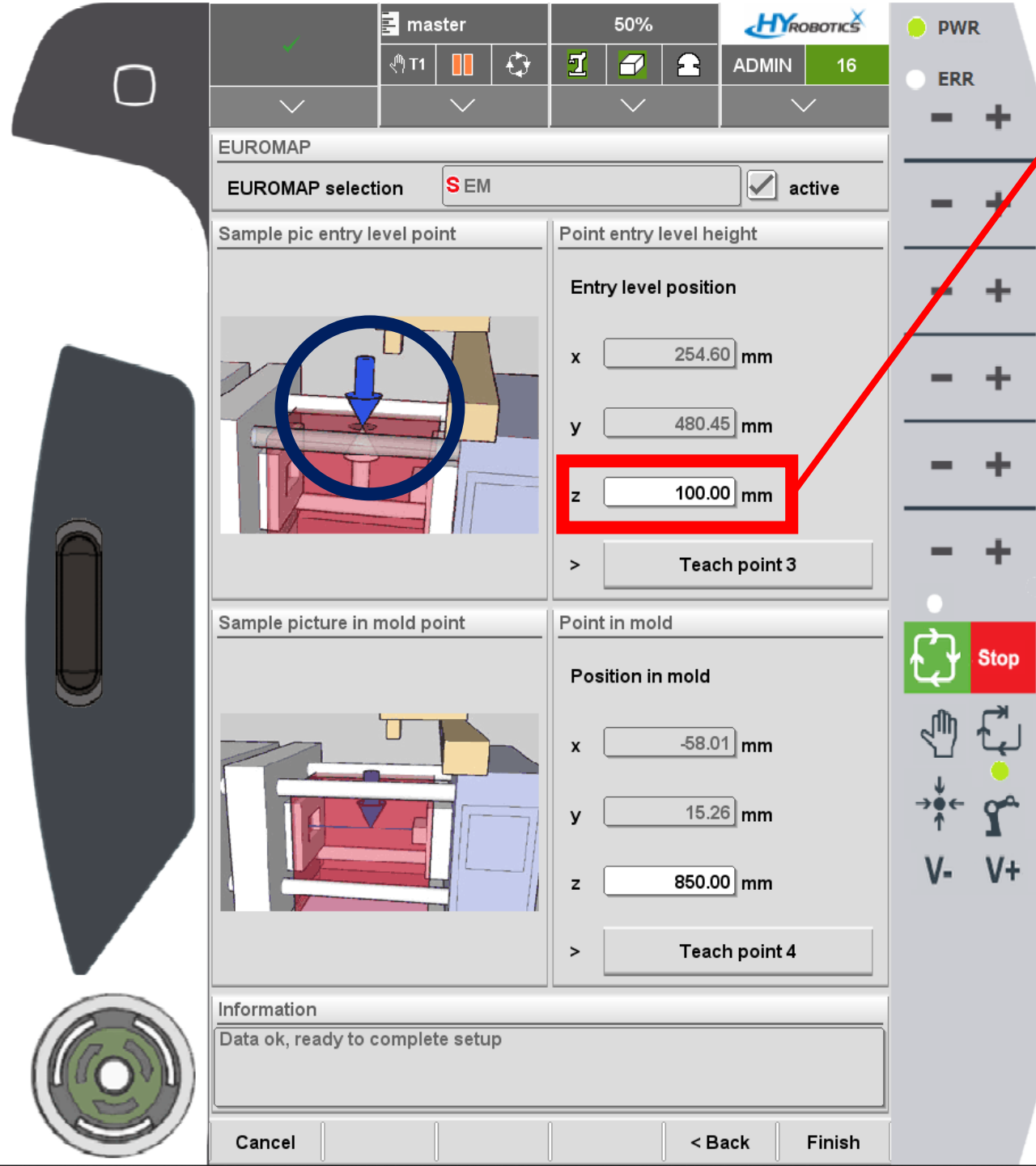
Go to Setting



Go to
Teach mold no-go area

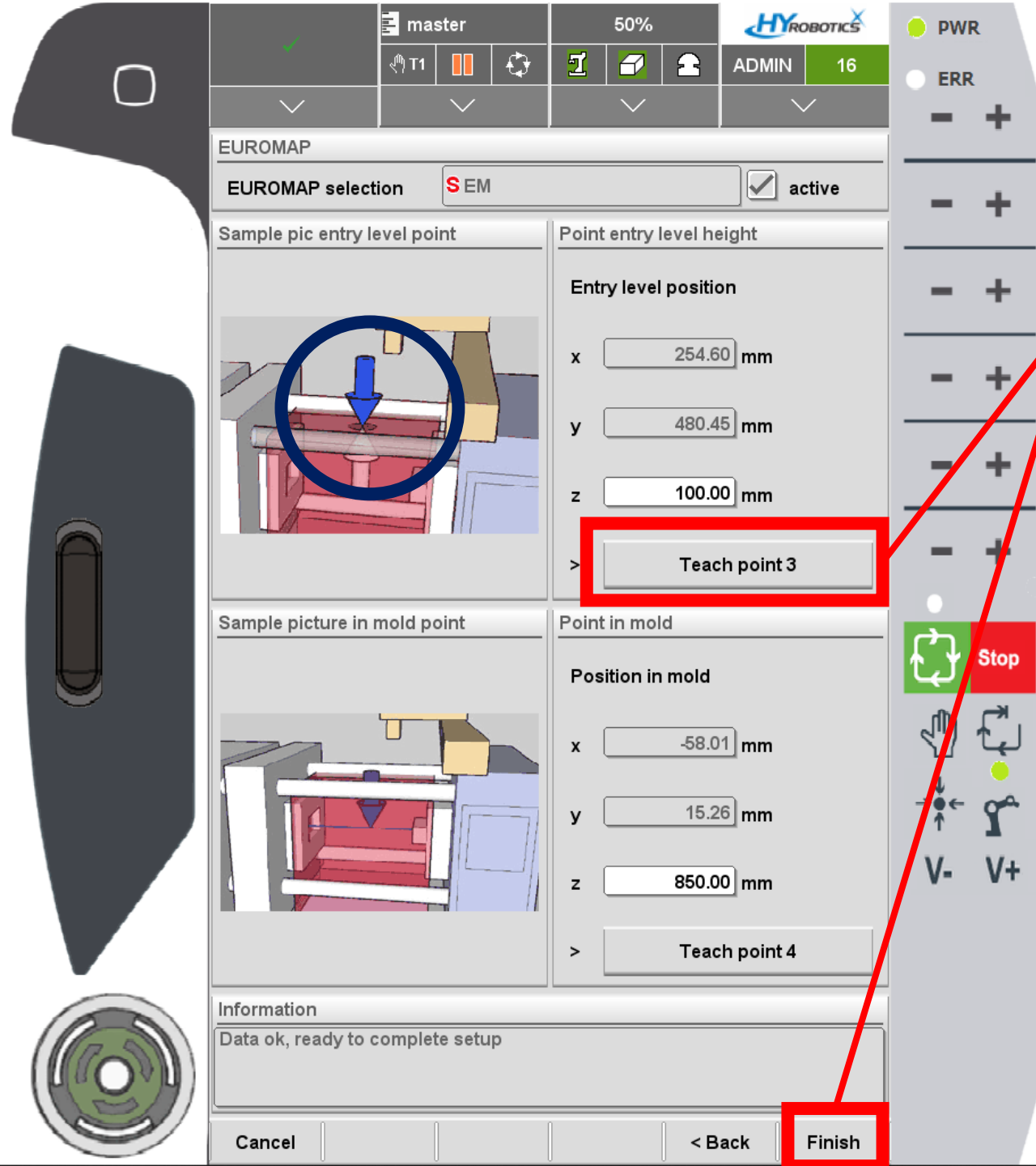


Go to
NEXT



Default is 100mm

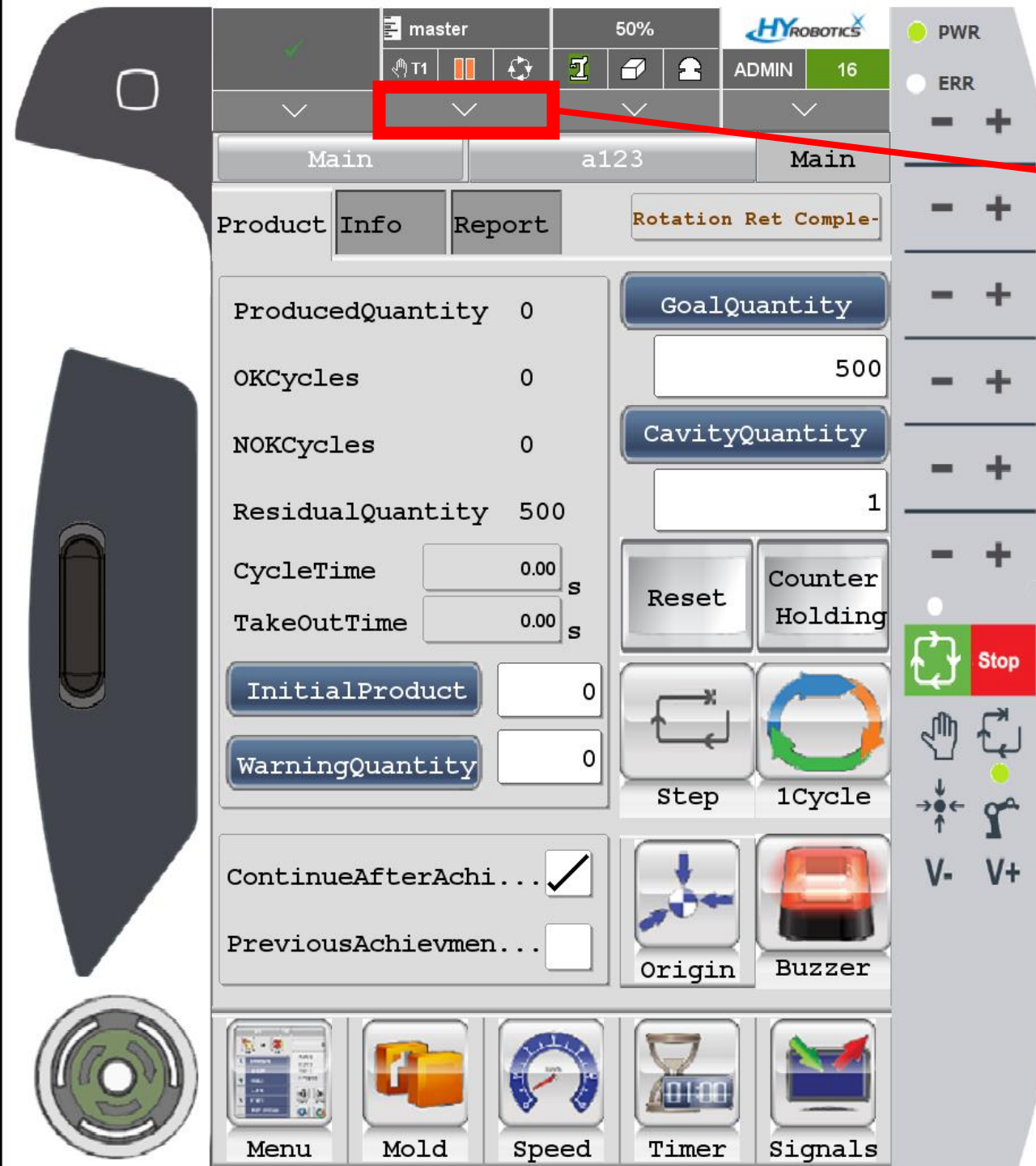
From waiting position,
Move the robot arm down
manually **WITH CAUTION**
Until the top of the mold
area. See sample pic.



Then teach
And Finish

Adjusting the mold safety
area is done.

The next step is modifying
the system file.



Press here



Press here



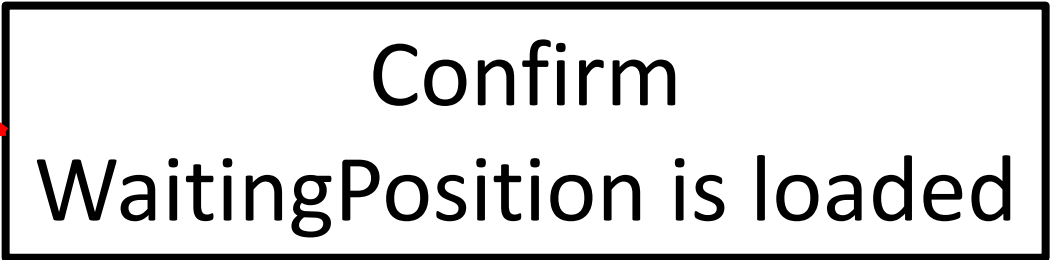
You will see
your mold
project files

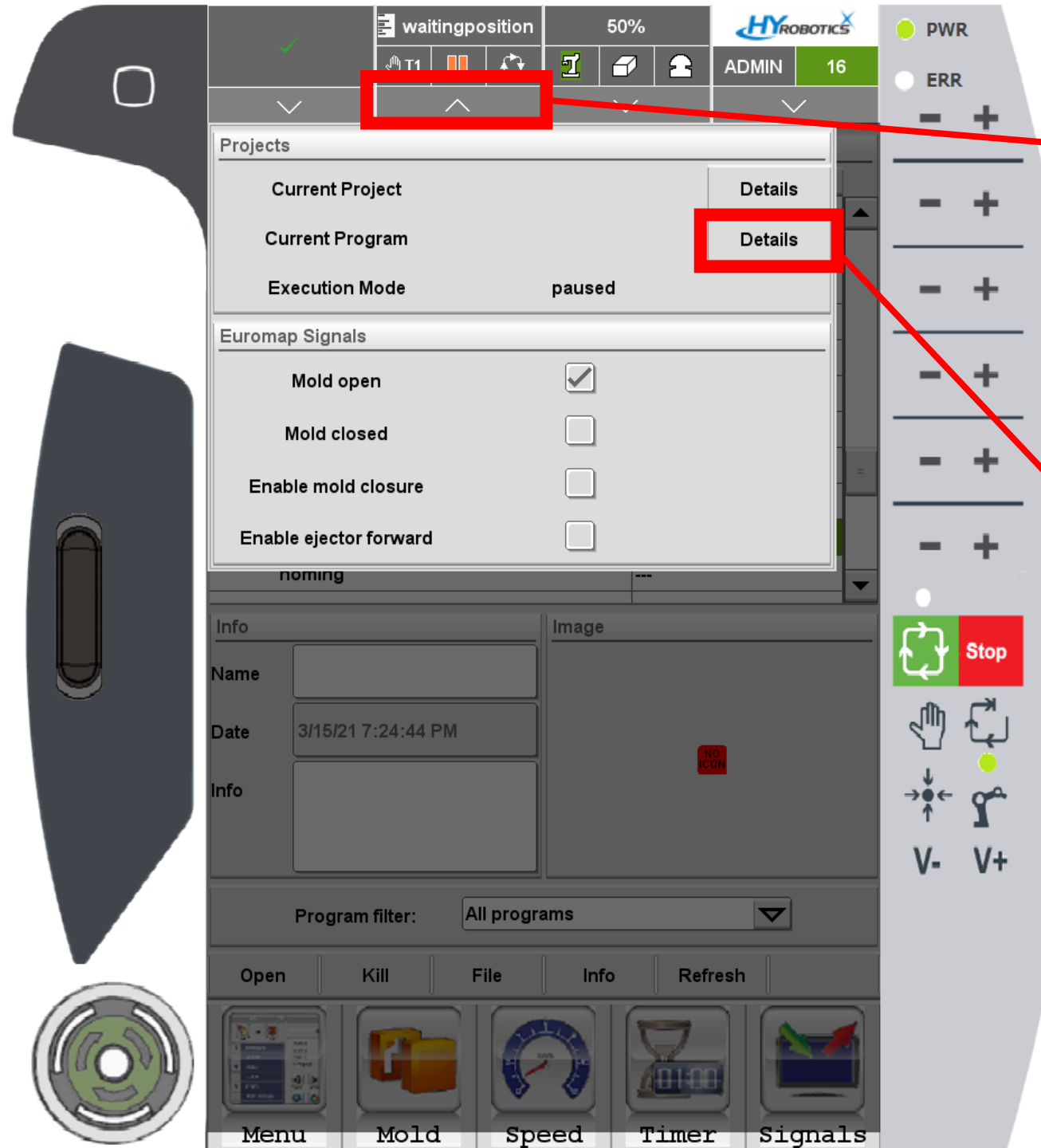


Press **+** button and
Expand **currently loaded**
mold project file



Find WaitingPosition
And
OPEN it





Click here

Click here

① Scroll down to bottom

② Select the line
JUST BEFORE
HYWaitMoveIsFinished()

The screenshot displays the HY Robotics software interface. At the top, a status bar shows 'waitingposition', '50%', and 'ADMIN 16'. Below this is a 'Program' editor window with the following code:

```
132 pMoveTemporaryPos.y := y-axis home position
133 Move(pMoveTemporaryPos, vpWaitingPos)
134 ELSIF MotionMode.i_M00 = 2 THEN
135 //Sub Arm
136 //Move to sub arm kick and traverse in waiting posit
137 pMoveTemporaryPos.x := x-axis home position
138 pMoveTemporaryPos.Aux1 := Aux1-axis home position
139 Move(pMoveTemporaryPos, vpWaitingPos)
140 END_IF
141 END_IF
142 HYWaitMoveIsFinished()
143 iWaitingID :=1000
144 // END_EDIT
145
```

A red box highlights the 'END_IF' line at line 141. A red arrow points from this box to the 'HYWaitMoveIsFinished()' line at line 142. Another red arrow points from the 'END_IF' line to the 'END_EDIT' line at line 144. To the right of the code editor is a vertical toolbar with various icons, including a 'Stop' button. At the bottom of the interface is a 'Movement' list with the following items:

Movement	Move
Homing	MoveOvl
Settings	MoveAxis
I/O-Control	MoveCirc
Flow Control	MoveUntil
Timing	StopRobot
HanYang	Palletize
	AfterPalletize

At the bottom of the interface is a 'Param' button and a 'Pos' button. The 'Param' button is highlighted with a red checkmark.

EDIT – Show Commands

The screenshot displays the HY Robotics software interface. At the top, a status bar shows 'waitingposition', '50%', and 'ADMIN 16'. The main area is a program editor with the following code:

```
124 pMoveTemporaryPos.y := y-axis home position
125 pMoveTemporaryPos.Aux1 := Aux1-axis home position
126 pMoveTemporaryPos.x := x-axis home position
127 Move(pMoveTemporaryPos, vpWaitingPos)
128 ELIF MotionMode.i_M00 = 1 THEN
129 //Main Arm
130 //Move to main arm kick and traverse in waiting position
131 pMoveTemporaryPos.x := x-axis home position
132 pMoveTemporaryPos.y := y-axis home position
133 Move(pMoveTemporaryPos, vpWaitingPos)
134 ELIF MotionMode.i_M00 = 2 THEN
135 //Sub Arm
136 //Move to sub arm kick and traverse in waiting position
137 pMoveTemporaryPos.x := x-axis home position
138 pMoveTemporaryPos.Aux1 := Aux1-axis home position
139 Move(pMoveTemporaryPos, vpWaitingPos)
```

A context menu is open over the code, with the following options: 'Hide editor', 'Show Commands' (highlighted in red), 'Graphical editor', 'Format', 'Deactivate', 'Set PC', and 'Edit' (highlighted in red). A red arrow points from the 'Show Commands' option to a callout box on the right. The bottom of the interface features a toolbar with icons for 'Param', 'Pos', 'Prog', 'Config', and 'Signals'.

Movement - MoveHY

The screenshot displays the HY Robotics software interface. At the top, a status bar shows 'waiting position', '50%', and 'ADMIN 16'. Below this is a 'Program' editor with the following code:

```
130 //Move to main arm kick and traverse in waiting position
131 pMoveTemporaryPos.x := x-axis home position
132 pMoveTemporaryPos.y := y-axis home position
133 Move(pMoveTemporaryPos, vpWaitingPos)
134 ELSIF MotionMode.i_M00 = 2 THEN
135 //Sub Arm
136 //Move to sub arm kick and traverse in waiting position
137 pMoveTemporaryPos.x := x-axis home position
138 pMoveTemporaryPos.Aux1 := Aux1-axis home position
139 Move(pMoveTemporaryPos, vpWaitingPos)
140 END_IF
141 END_IF
142 HYWaitMoveIsFinished()
143 iWaitingID := 1000
```

Below the code editor is a function menu. The 'Movement' category is highlighted with a red box. The 'MoveHY' function is also highlighted with a red box. Other functions listed include MoveAxis, MoveCirc, MoveUntil, StopRobot, Palletize, AfterPalletize, Homing, Settings, I/O-Control, Flow Control, Timing, and HanYang.

At the bottom of the interface is a toolbar with five icons: Param, Pos, Prog, Config, and Signals. The 'Prog' icon is highlighted with a red box.

On the right side of the interface is a vertical control panel with various buttons and indicators, including 'PWR', 'ERR', and a 'Stop' button.

waitingposition50%HY ROBOTICS

T1ADMIN16

Program

```
123 //Move to main, sub arm kick and traverse in waiting
124 pMoveTemporaryPos.y := y-axis home position
125 pMoveTemporaryPos.Aux1 := Aux1-axis home position
126 pMoveTemporaryPos.x := x-axis home position
127 Move(pMoveTemporaryPos, vpWaitingPos)
128 ELSIF MotionMode.i_M00 = 1 THEN
129 //Main Arm
130 //Move to main arm kick and traverse in waiting posi
131 pMoveTemporaryPos.x := x-axis home position
132 pMoveTemporaryPos.y := y-axis home position
133 Move(pMoveTemporaryPos, vpWaitingPos)
134 ELSIF MotionMode.i_M00 = 2 THEN
135 //Sub Arm
136 //Move to sub arm kick and traverse in waiting posit
137 pMoveTemporaryPos.x := x-axis home position
138 pMoveTemporaryPos.Aux1 := Aux1-axis home position
139 Move(pMoveTemporaryPos, vpWaitingPos)
140 END_IF
141 END_IF
142 HYWaitMoveIsFinished()
```

MoveHY(p0,100,,0.0)

ModifyKeyboardadd DOCancelOk

ParamPosProgConfigSignals

Press Modify

waitingposition50%HY ROBOTICSADMIN16

MoveHY

Position

p0

Axis	Actual	Set	Velocity (%)
x	13.02	13.02 mm	100
y	266.10	266.10 mm	Waiting time [s]
z	200.41	200.00 mm	0.00

Rotation

Return

turn/return

Rotation

Swivel

RotRETURN

SwiRETURN

use

Program

138 pMoveTemporaryPos.Aux1 := Aux1-axis home position

139 Move(pMoveTemporaryPos, vpWaitingPos)

140 END_IF

141 END_IF

142 HYWaitMoveIsFinished()

143 iWaitingID :=1000

Edit

Selection

Teach

Cancel

Ok

Param

Pos

Prog

Config

Signals

① from set waiting position

Move the robot arm
to the designated z-position

② Confirm Rotation

③ Teach and OK



Click here

Click here

waitingposition50%HY ROBOTICS

T1

ADMIN16

Programs

Projects	State
TakeOutSubJMotion	---
TakeOutSubNotJMotion	---
TempCheckHomePos	---
ToWaitingPos	---
UpPosMainGriperCheck	---
UpPosSubGriperCheck	---
UpPosVacummNChuckCheck	---
UpPosition	---
WaitingForImm	---
WaitingPosition	stopped
homing	---

Info

Name

Date3/15/21 7:24:44 PM

Info

Image

NO ICON

Program filter:

All programs

Open

Kill

File

Info

Refresh

Menu

Mold

Speed

Timer

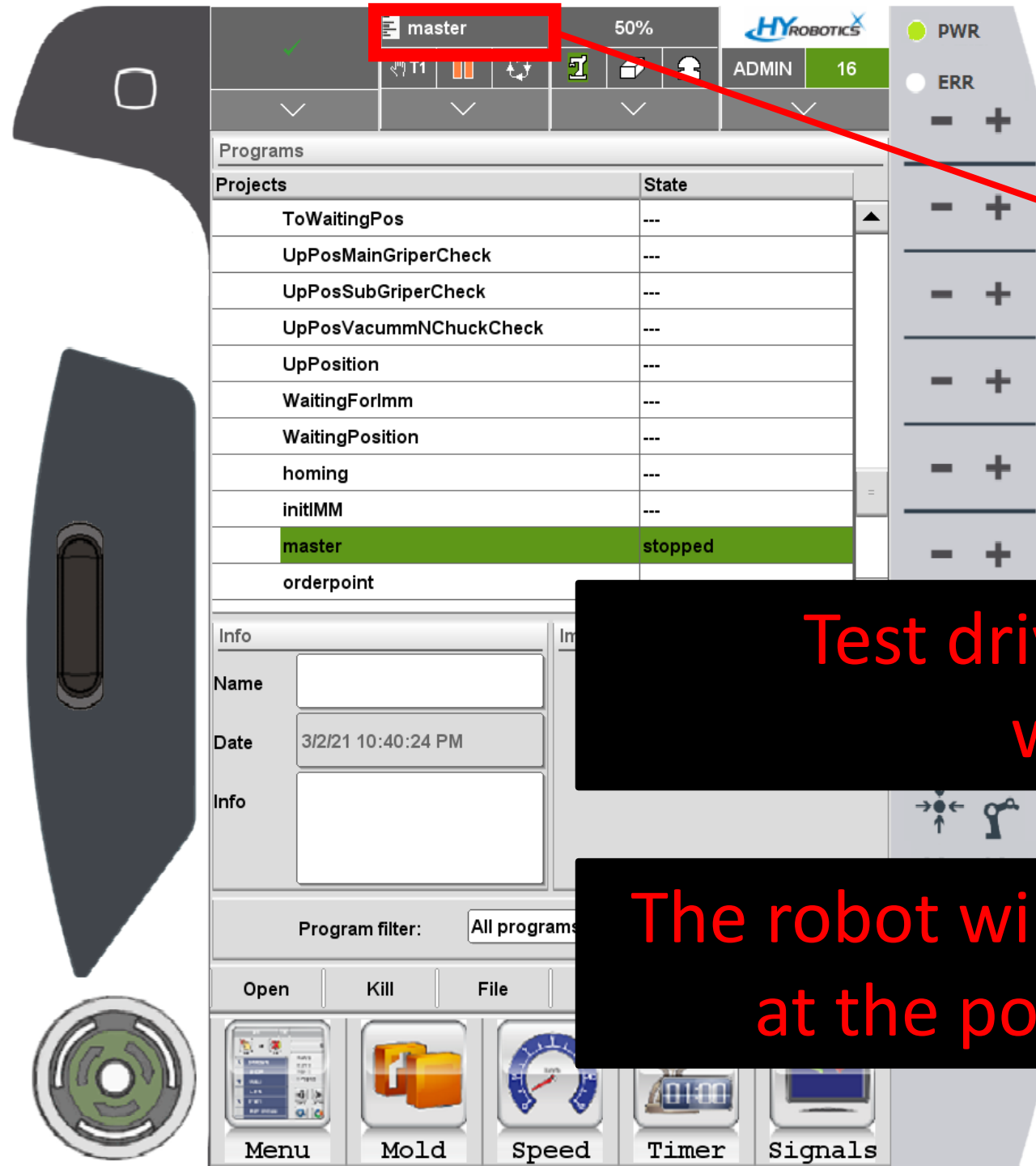
Signals

Kill currently opened
WaitingPosition



① Kill currently opened master

② Open master again



If you see master,
The robot is ready to be
tested.

Test drive first with low velocity
with mold opened

The robot will be waiting mold open signal
at the position you set on page 22.