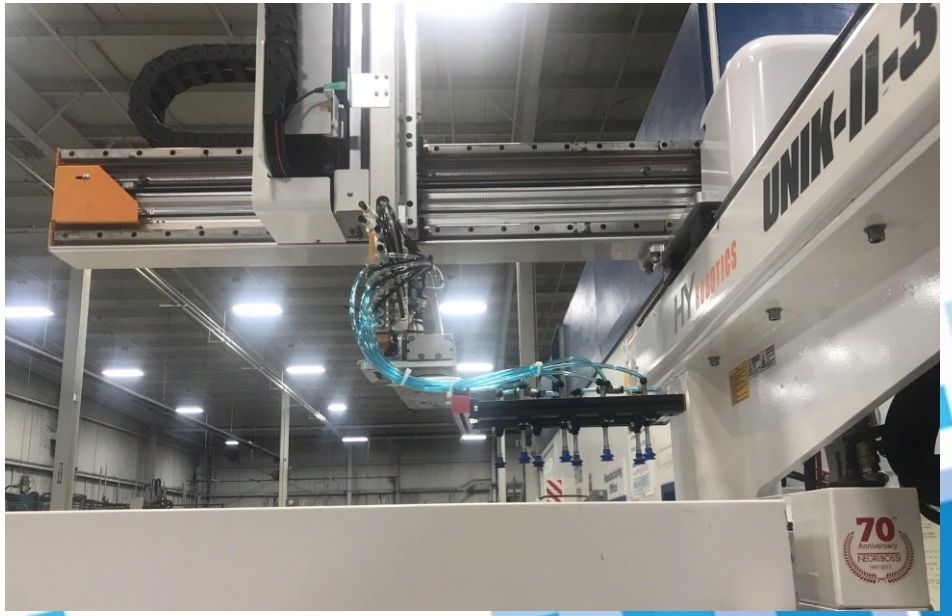
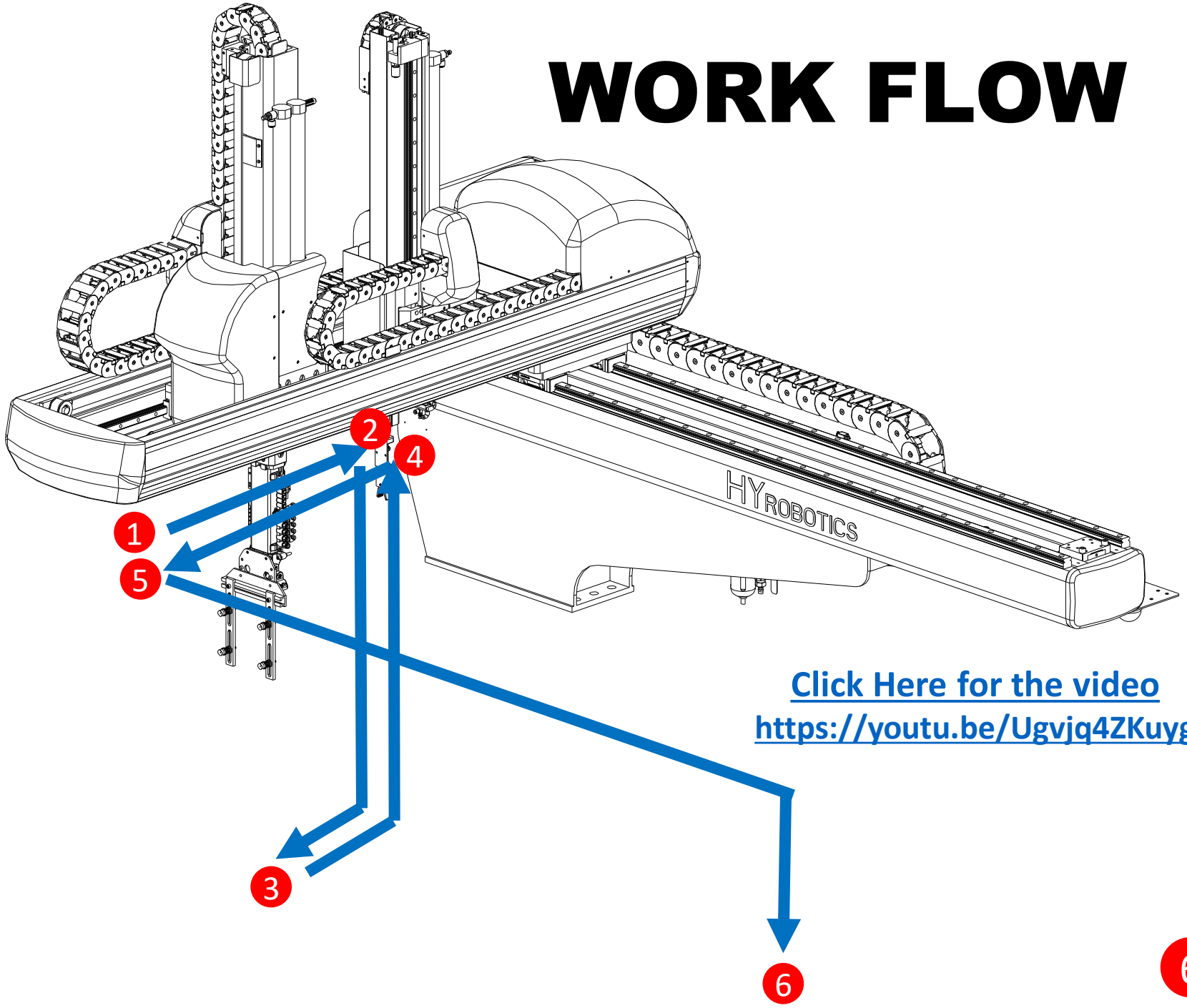
A CUSTOM PROGRAM FOR A LONG EOAT

EPIK / UNIK



HY ROBOTICS

WORK FLOW



[Click Here for the video](https://youtu.be/Ugvjq4ZKuyg)
https://youtu.be/Ugvjq4ZKuyg

1. Waiting EOAT
2. Rotate Return EOAT
3. P0 EOAT
4. Takeout EOAT
5. Up EOAT
6. P1 EOAT
7. Rotate EOAT
8. Main Release EOAT

STEP 1

MAKING A NEW MOLD FILE

Make a new mold file.

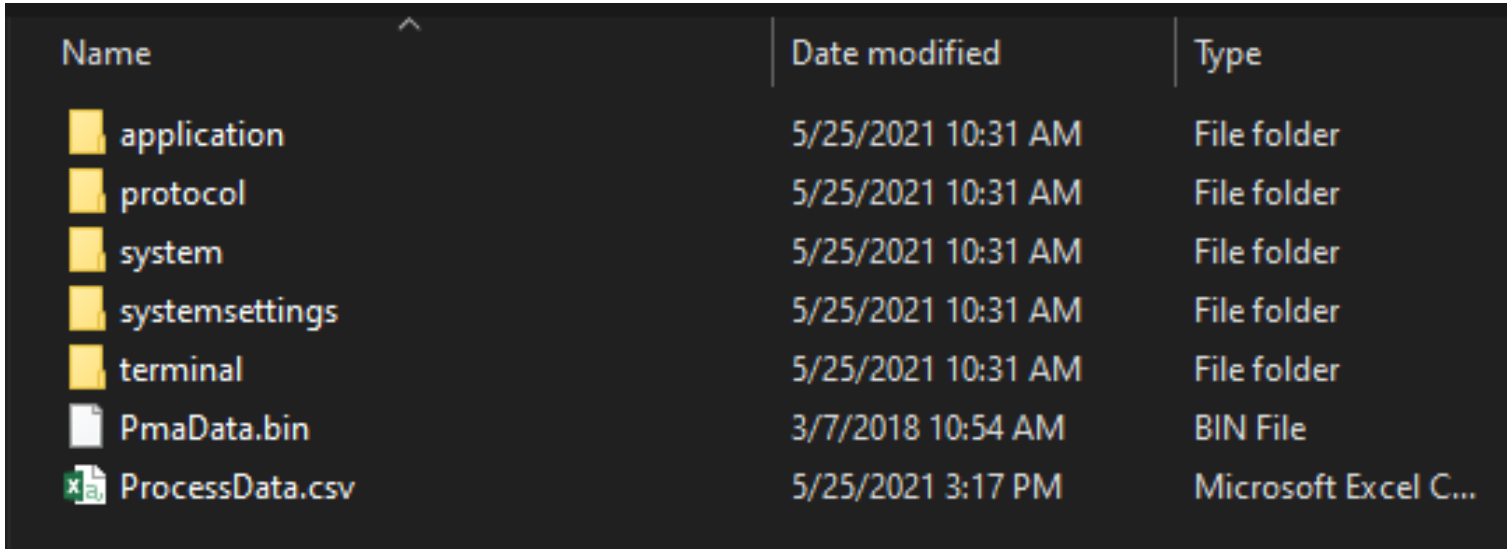
After the new mold file is created,
Power off the robot.

STEP 2

COPY & PASTE
CUSTOMIZED SUB-PROGRAMS

Power off the robot.
Take out SD card from the robot PLC in the control box

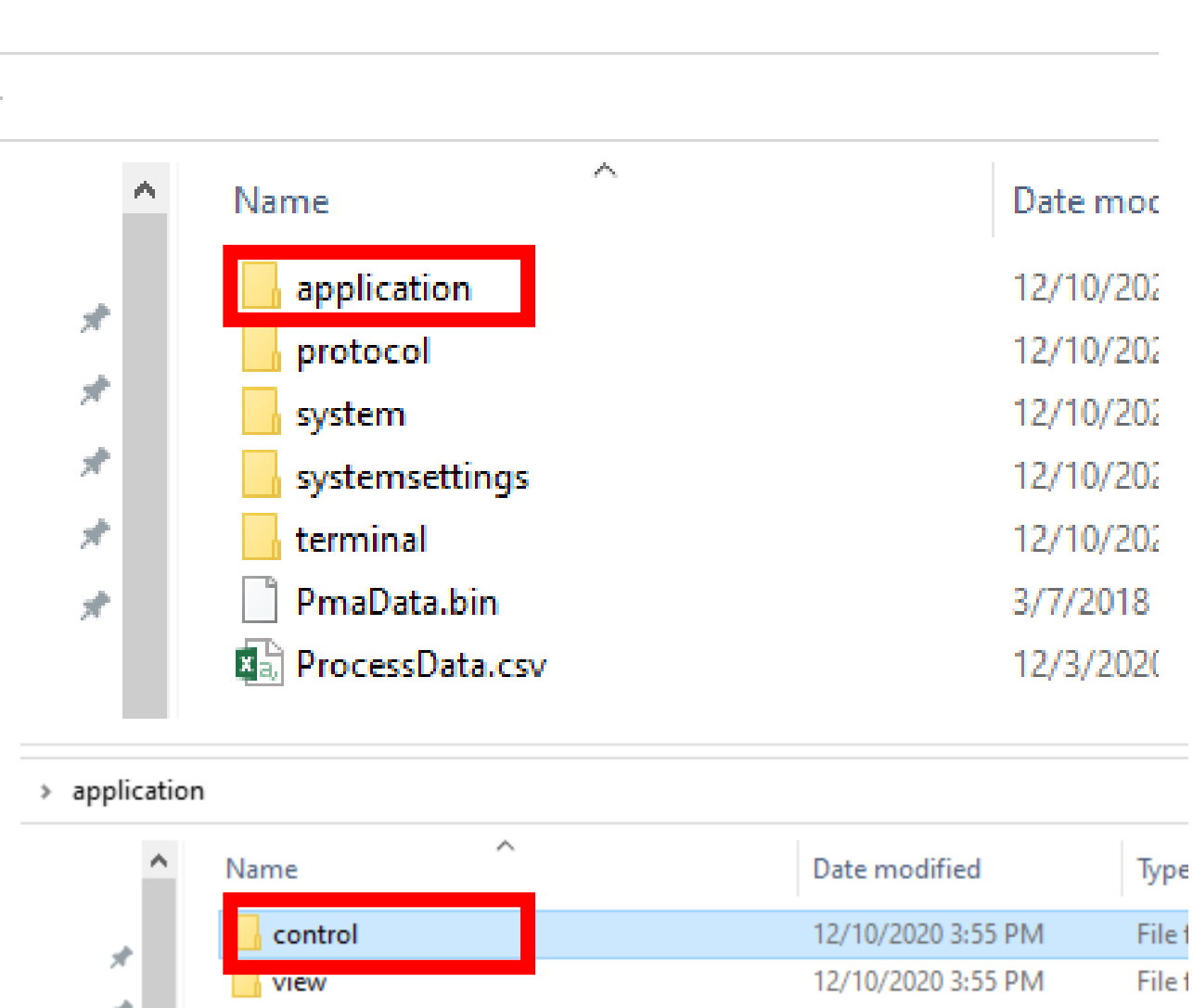
Connect it to the PC

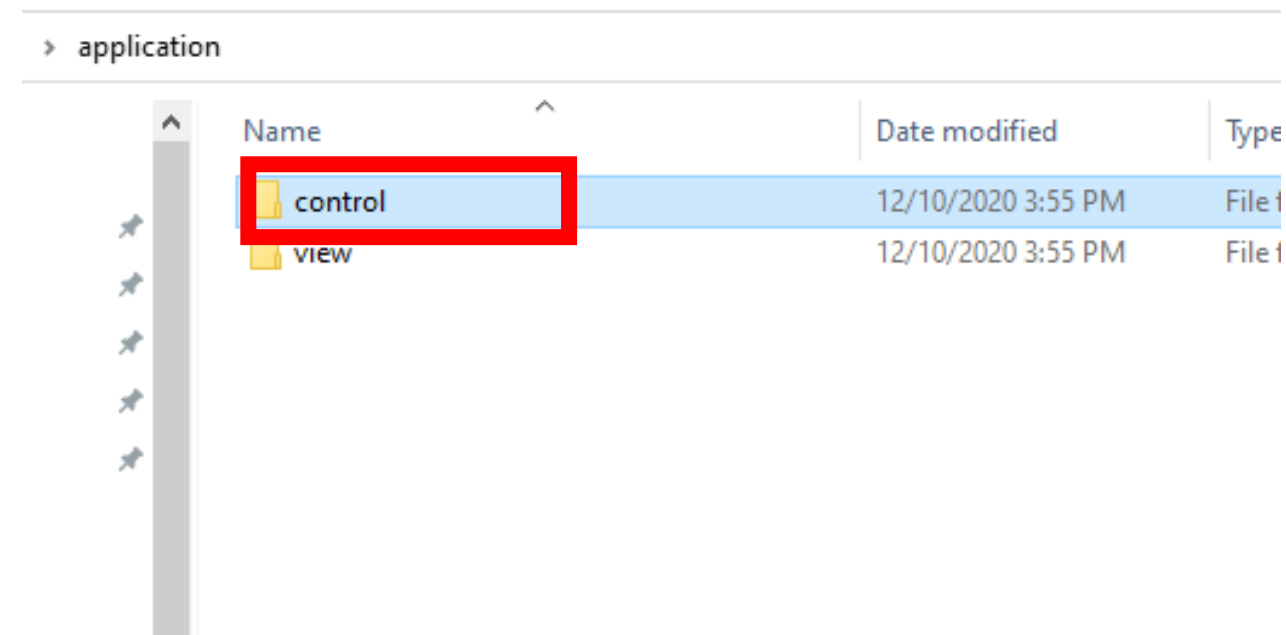


Before moving on to the next step,

PLEASE BACK UP these data

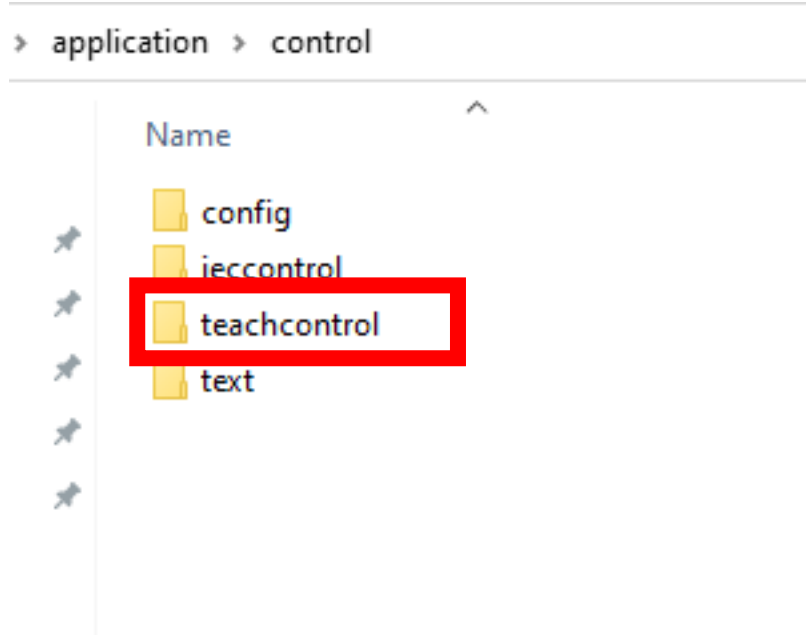
into your PC or another SD card.

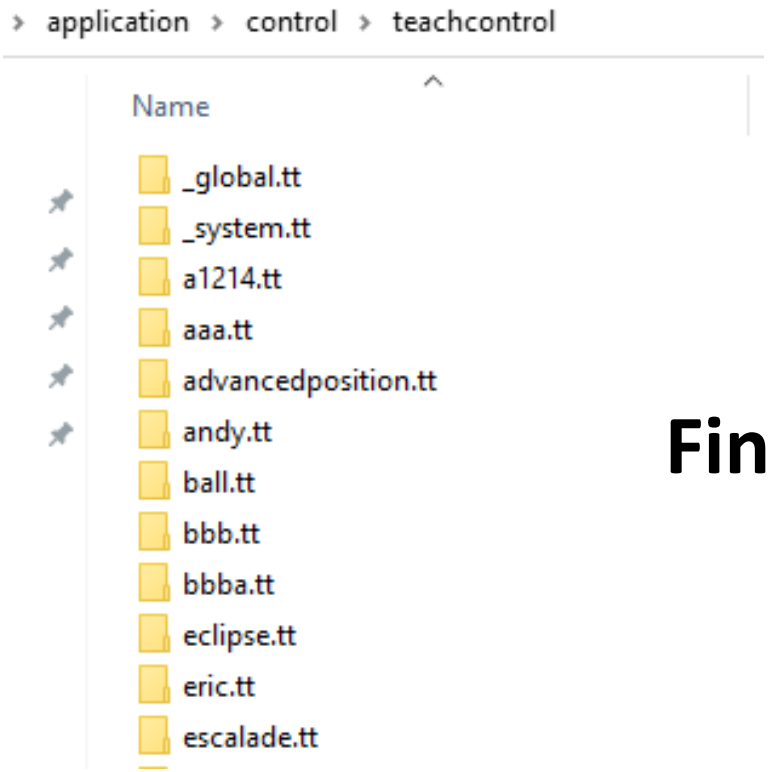




<Application>

<Control>

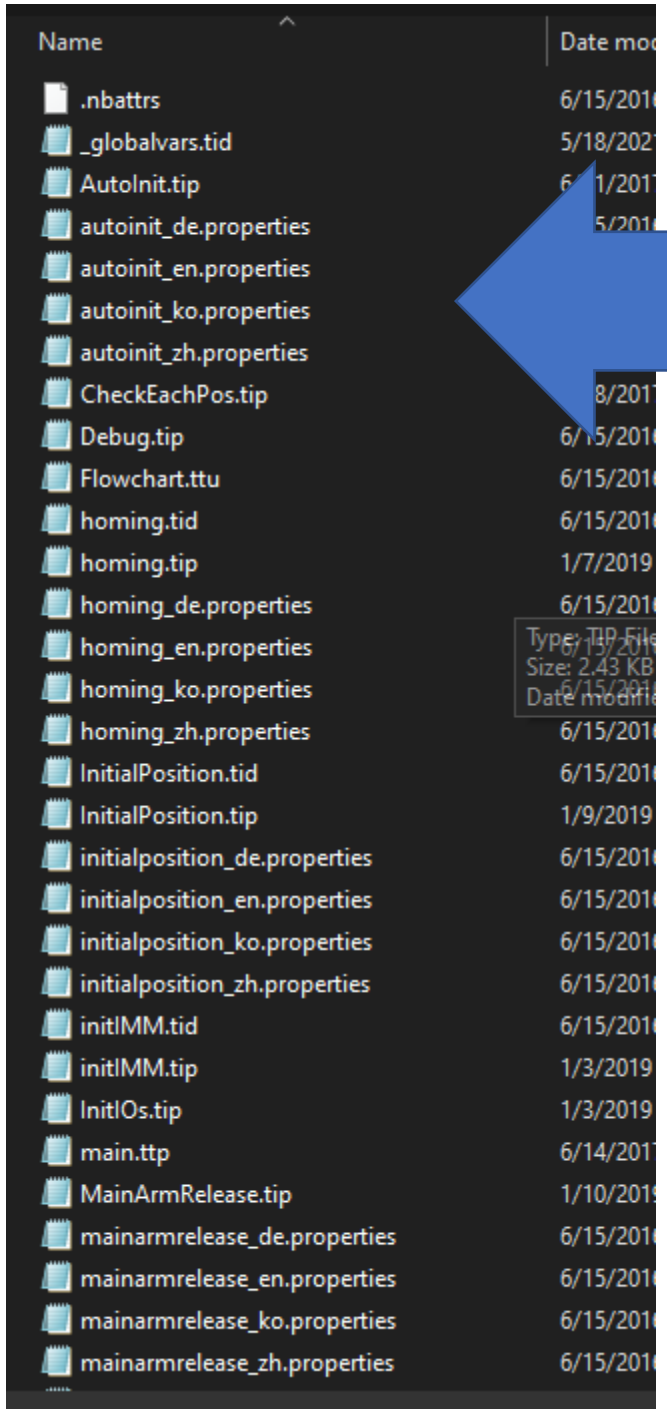




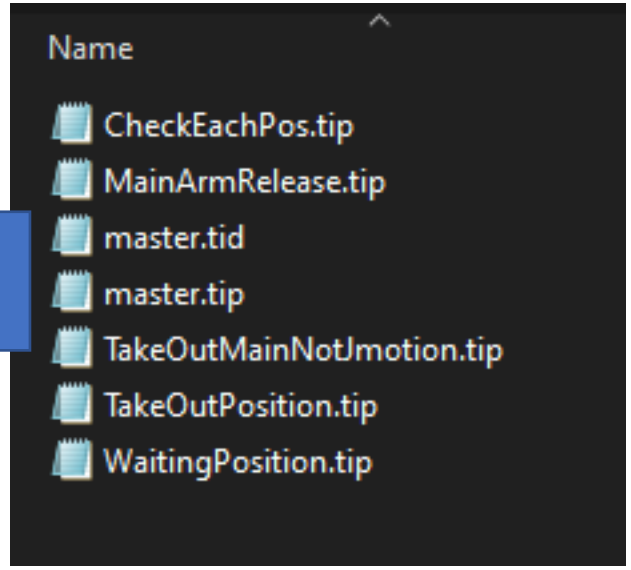
<teachcontrol>

You will see mold project file folders.

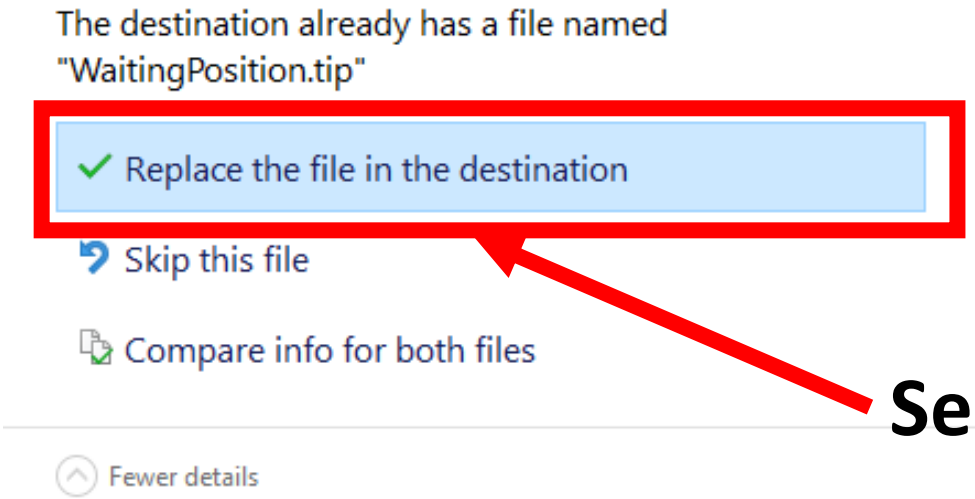
Find the mold file folder you created in step #1.



Copy & Paste



Copy and Paste provided 7 files into the mold file folder.

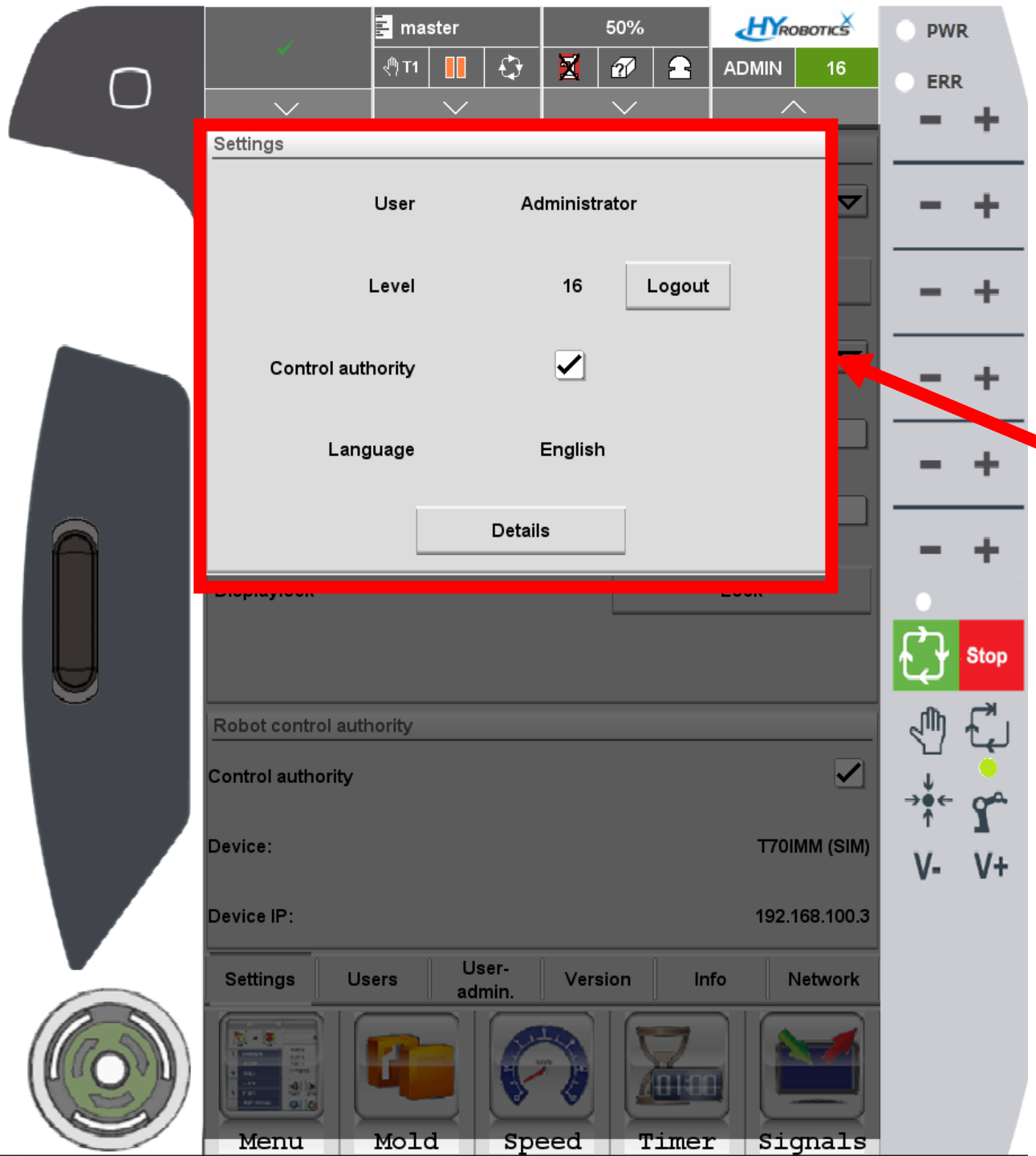


Select this

When replacing the files is done,
Put the SD card back to PLC, and power on the robot.

STEP 3

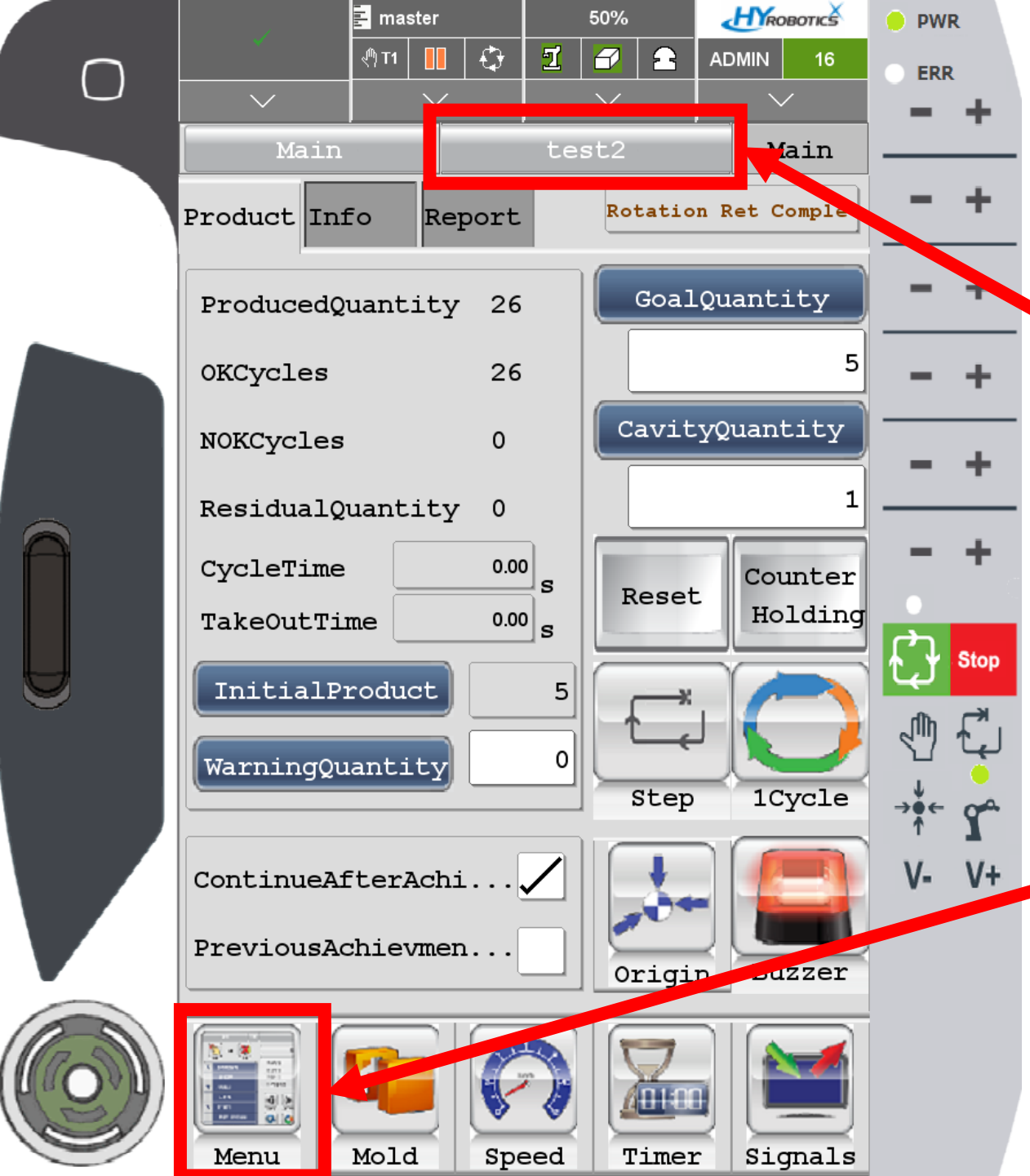
MODE SETTING



After referencing,

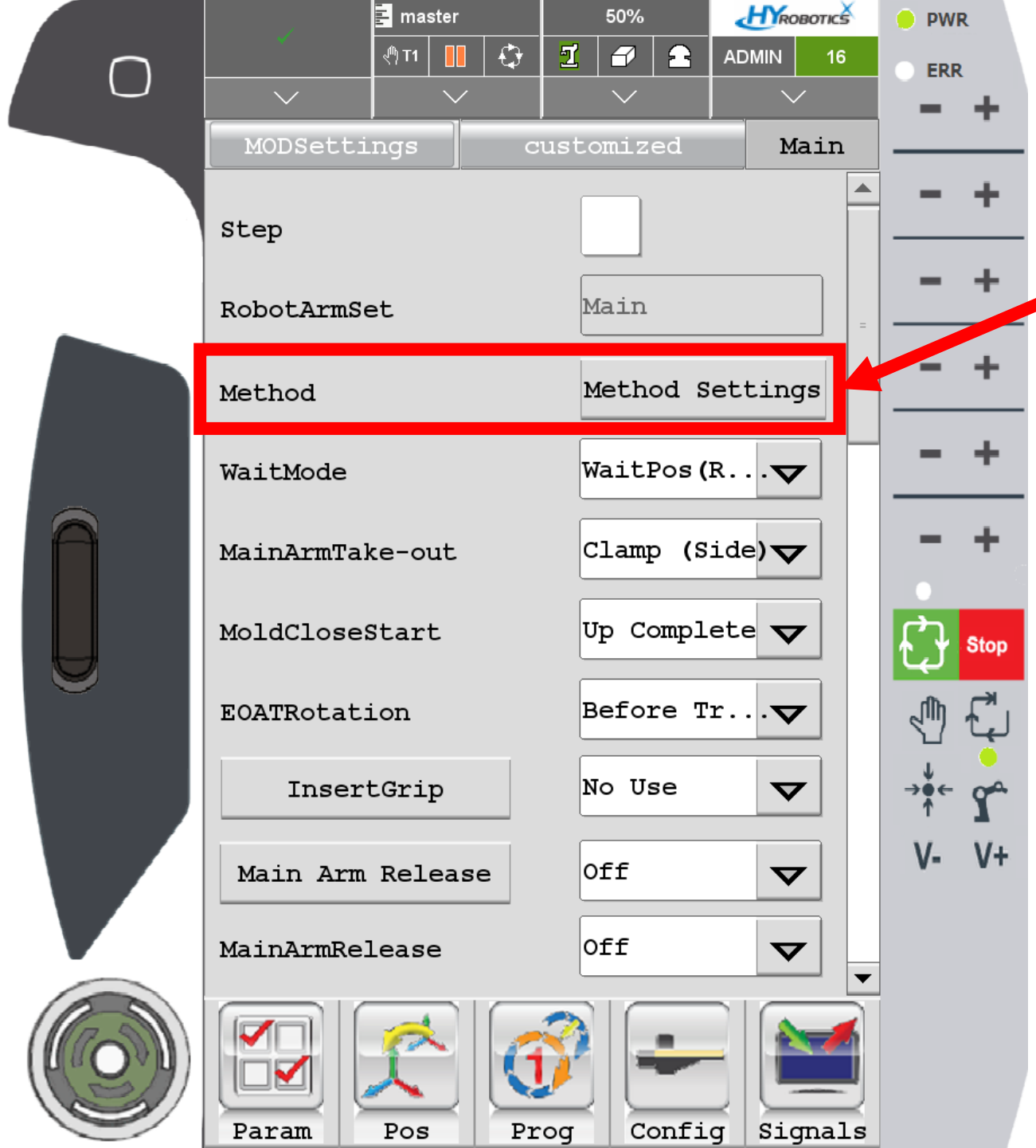
Log in as Level 16 Administrator

Load the mold file you created.

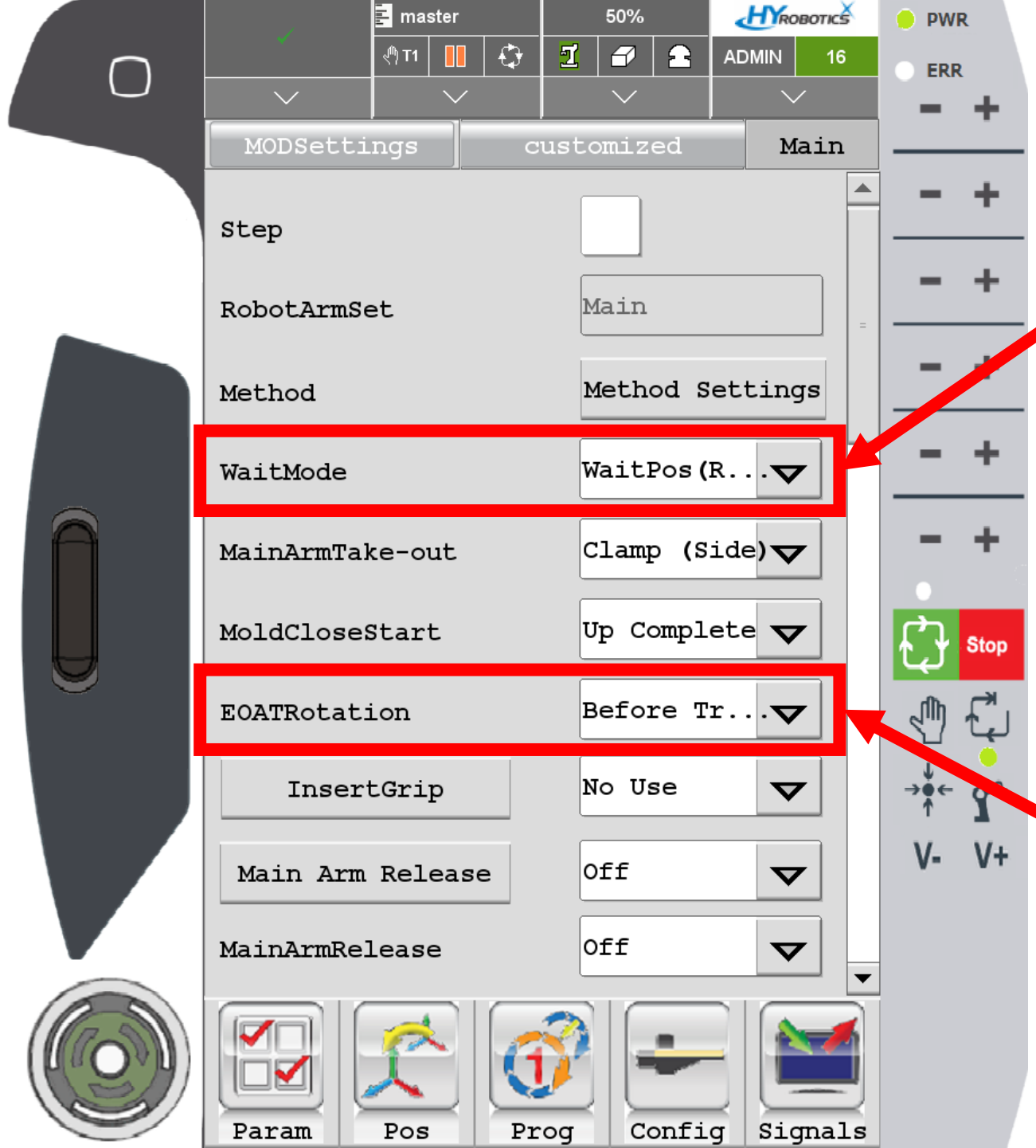


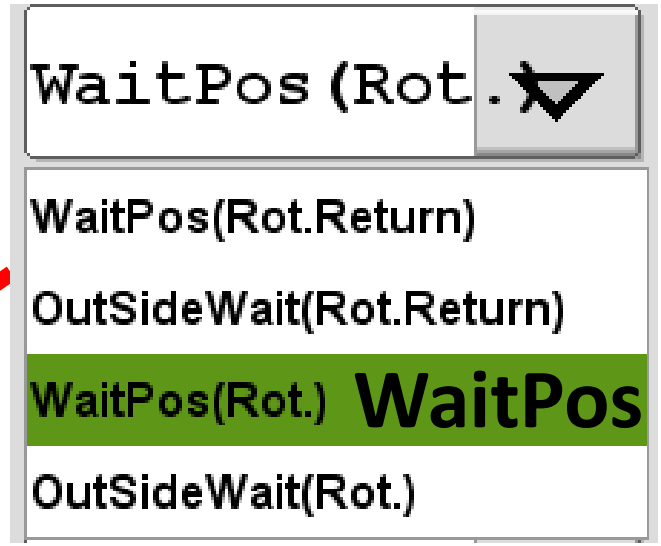
Check here if the right mold file is loaded.

Go to mode setting.

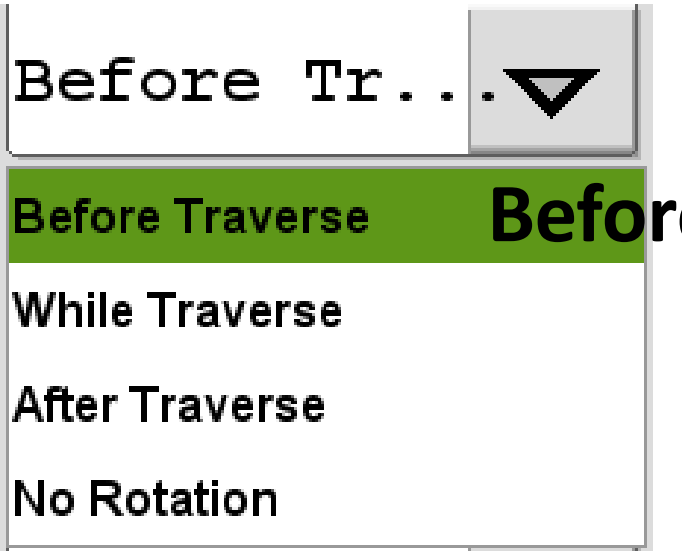


Select the method

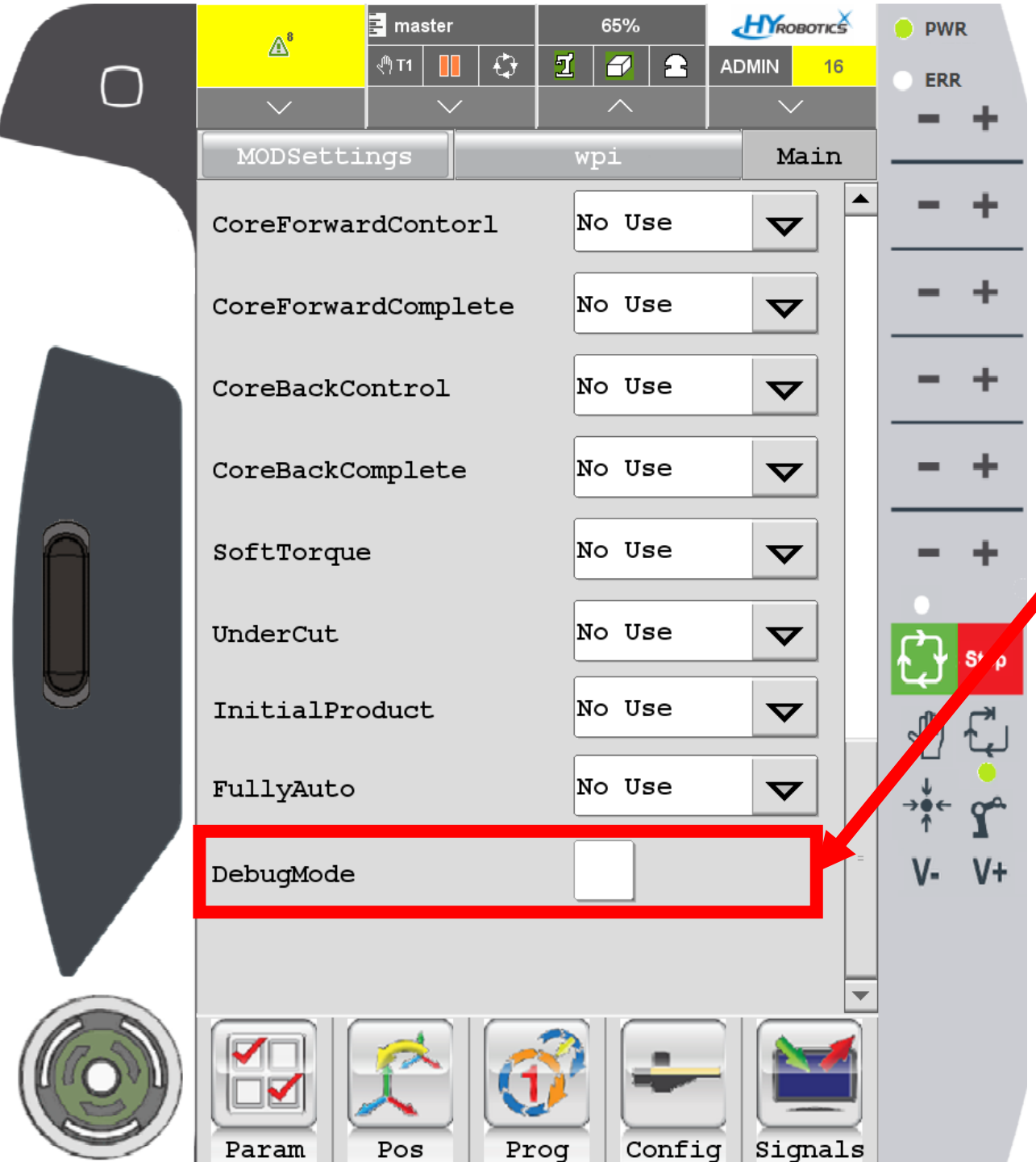




WaitPos (Rotation)



Before Traverse



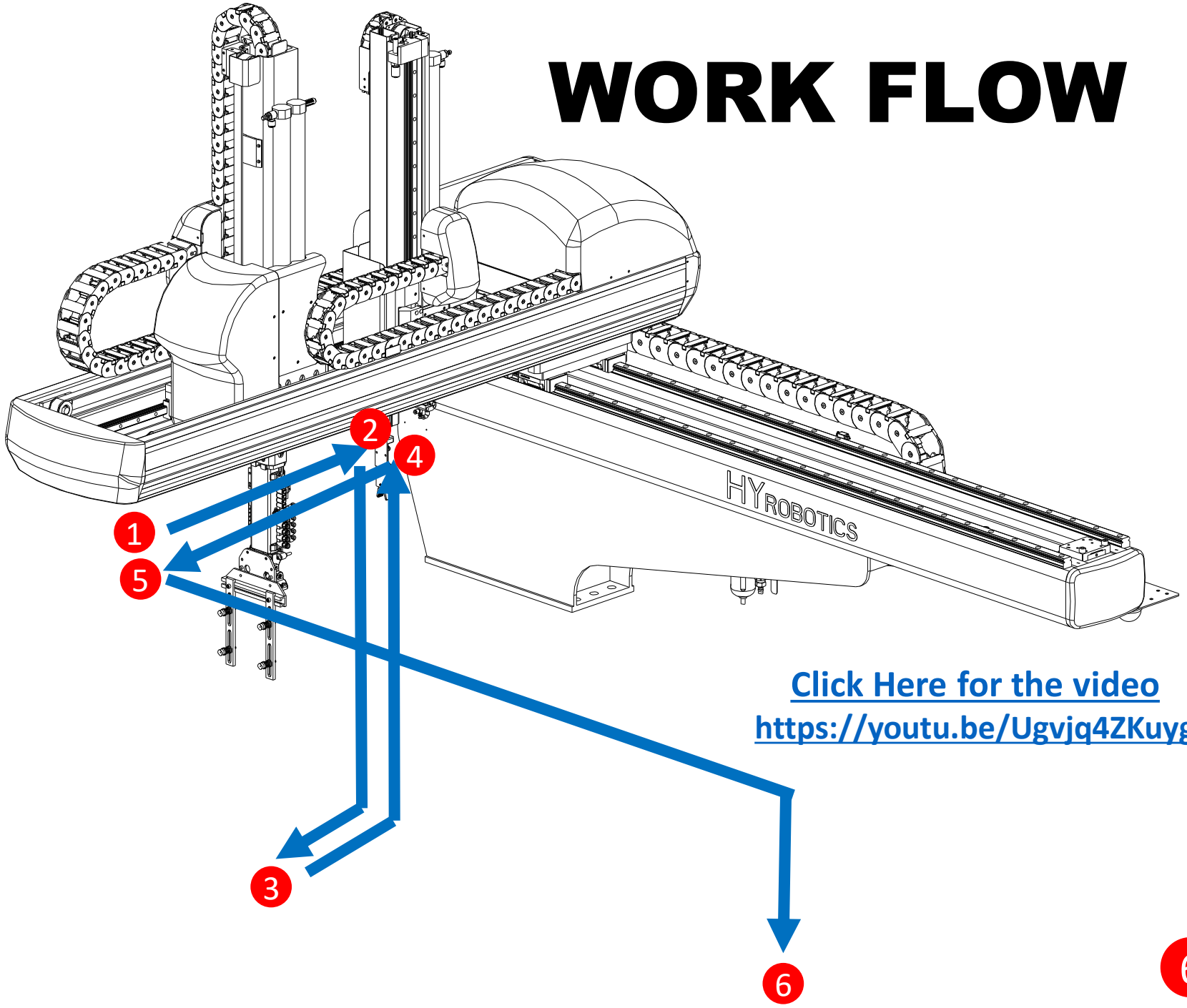
Debug Mode OFF

J-Motion No Use

STEP 4

TEACHING POSITIONS

WORK FLOW



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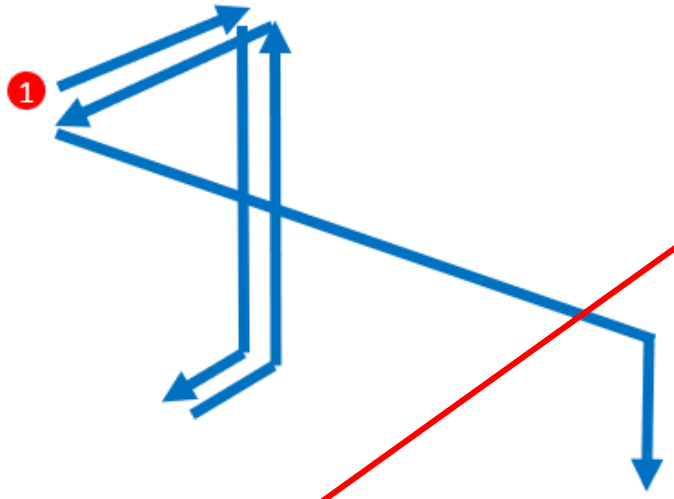
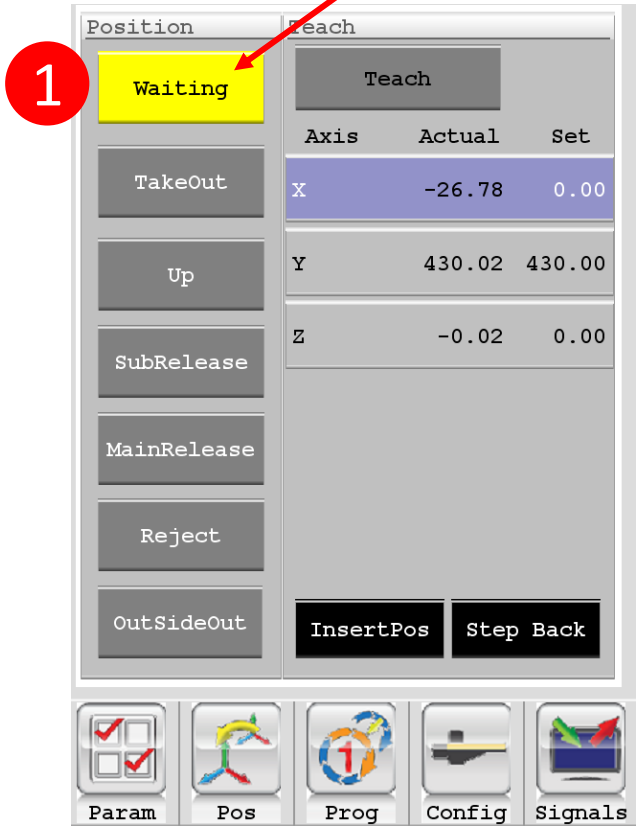


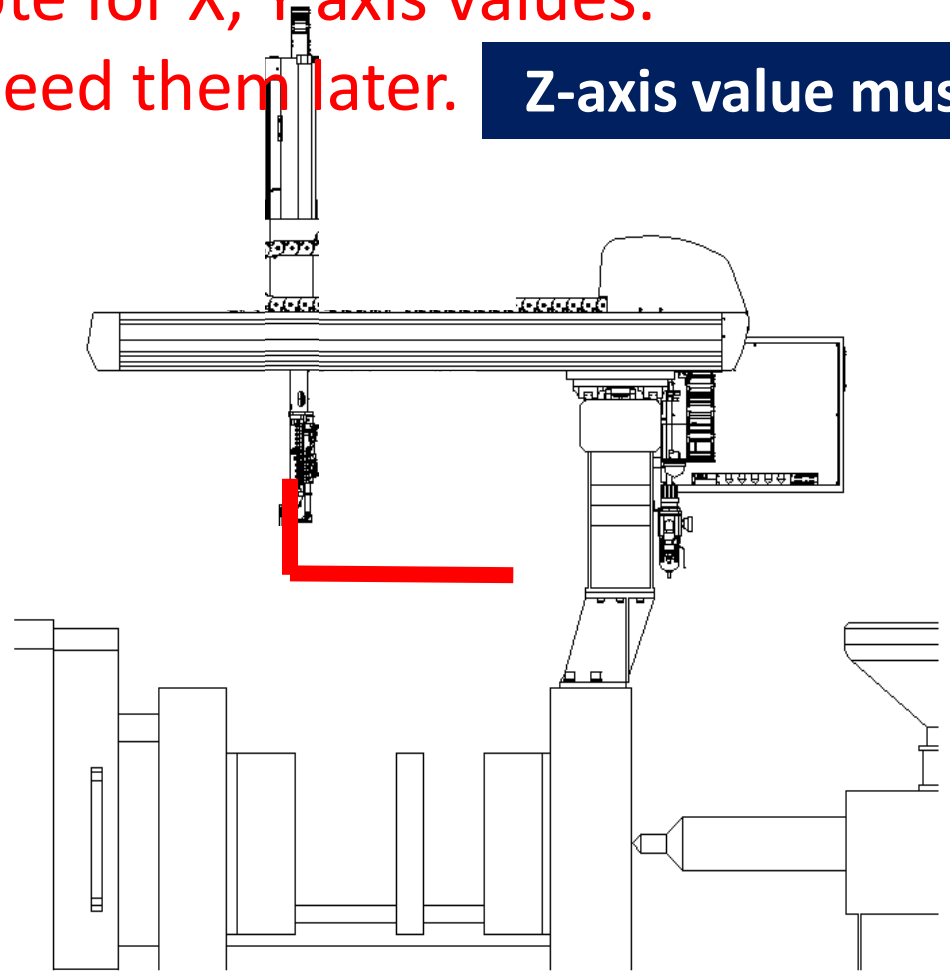


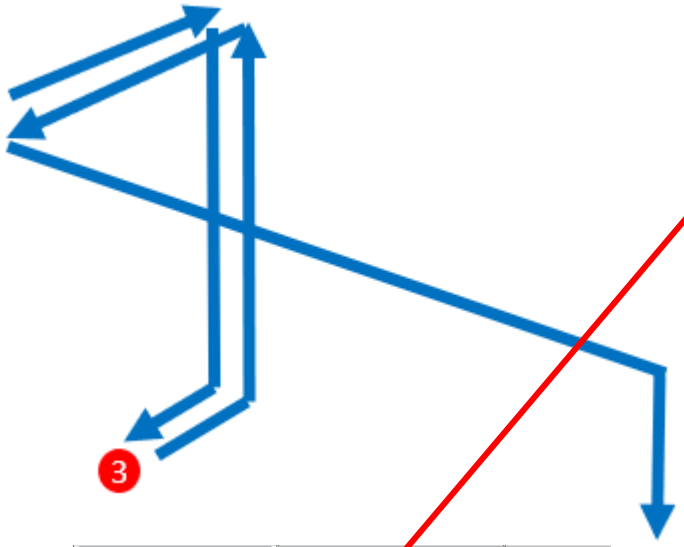
Select Waiting

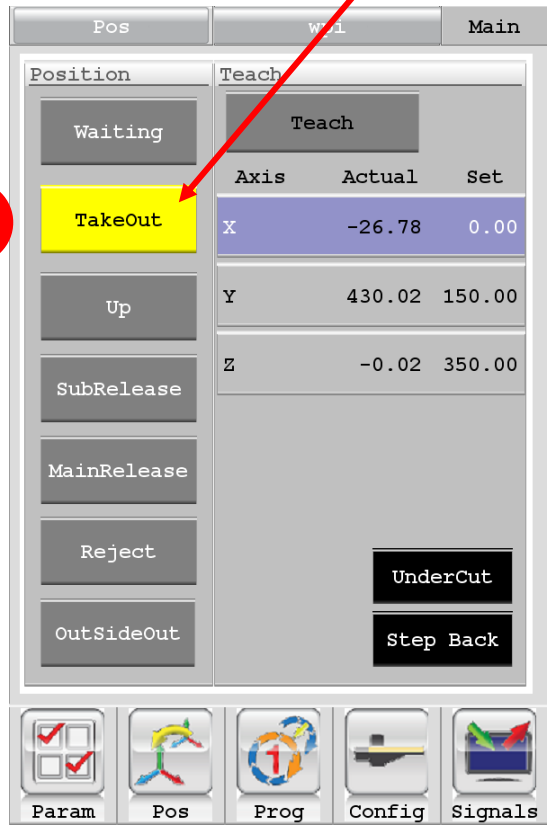
Rotate EOAT and move the robot manually to Waiting position. Press TEACH button.

Take a note for X, Y axis values.
We will need them later.

Z-axis value must be 0





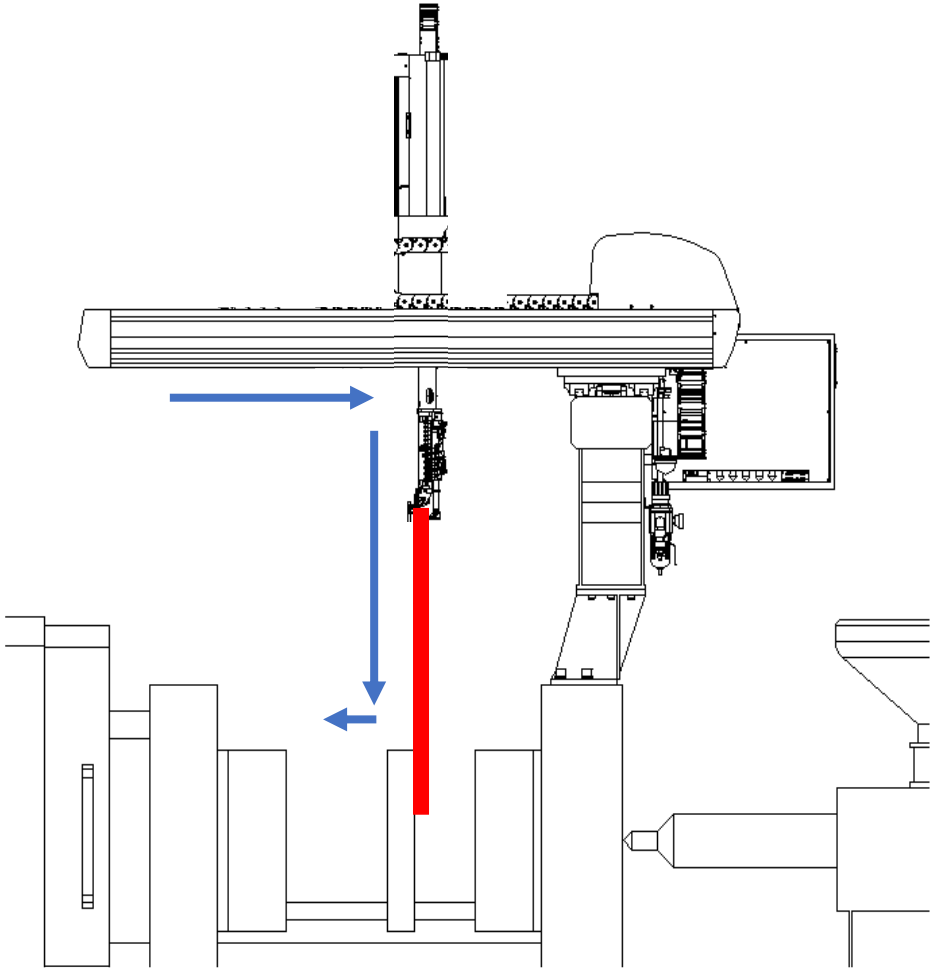


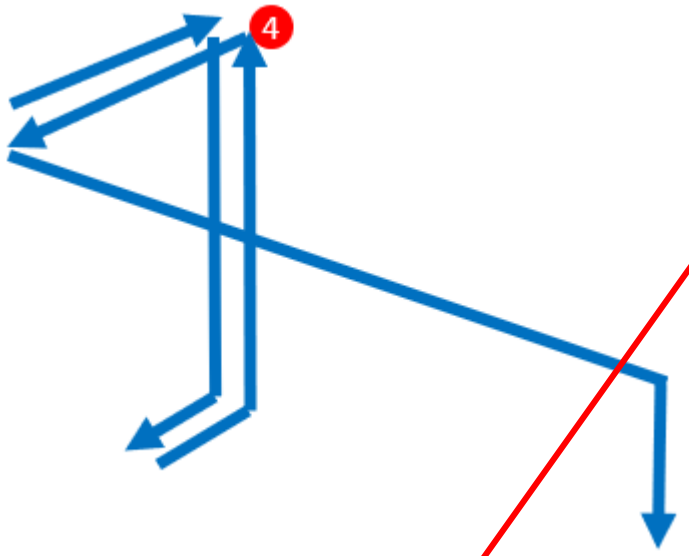
Select Takeout

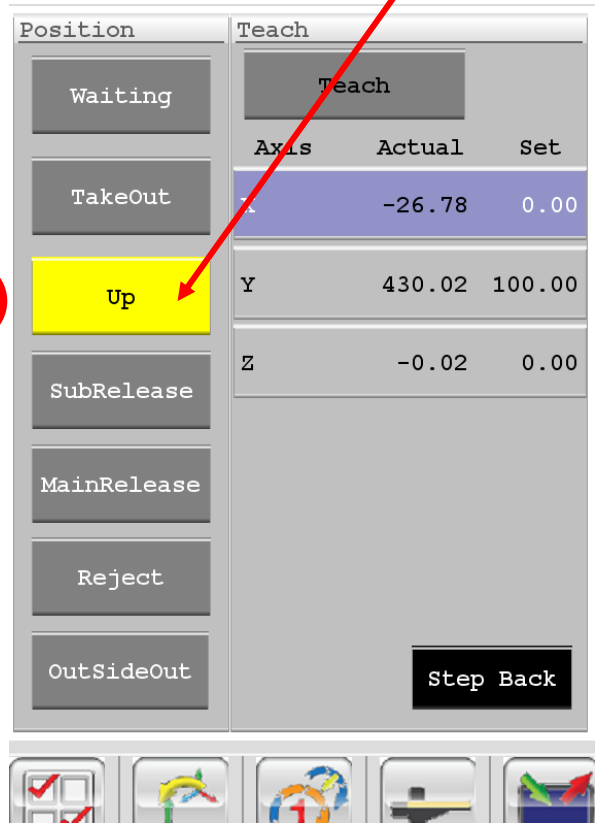
Rotate return.

Move the robot manually to Takeout position.

Press TEACH button.







Select Up

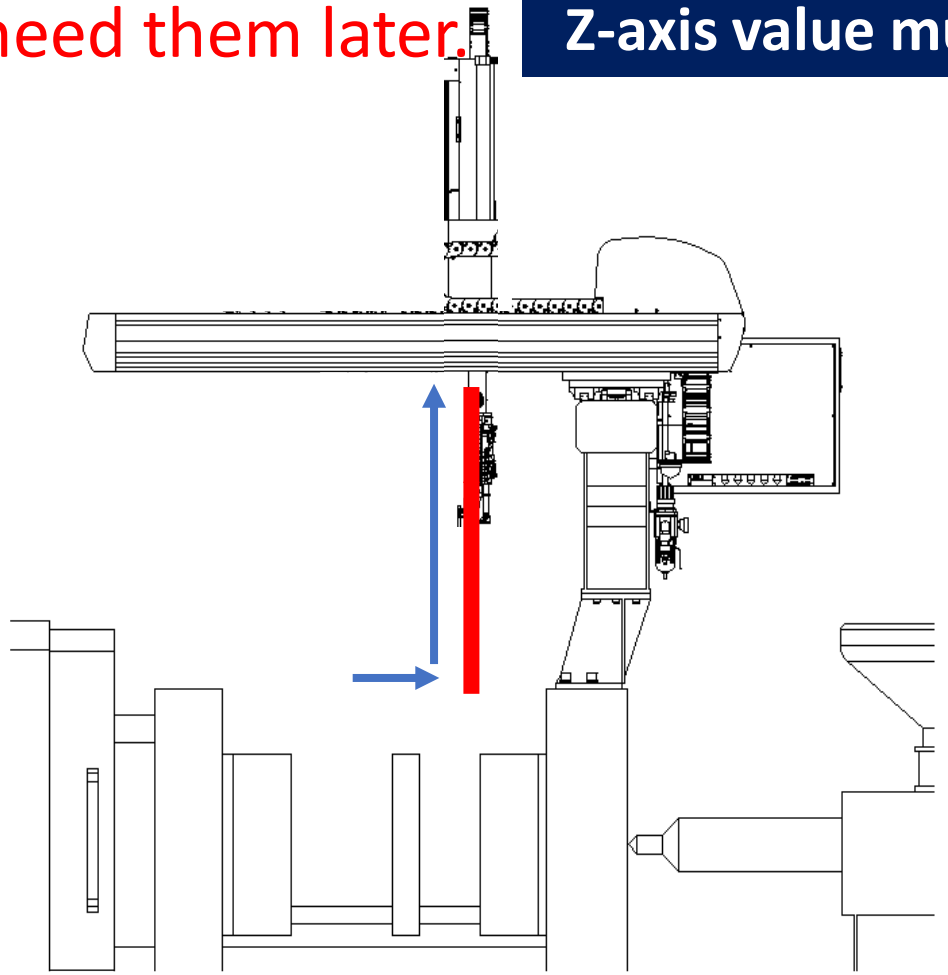
Move the robot manually to up position.

Press TEACH button.

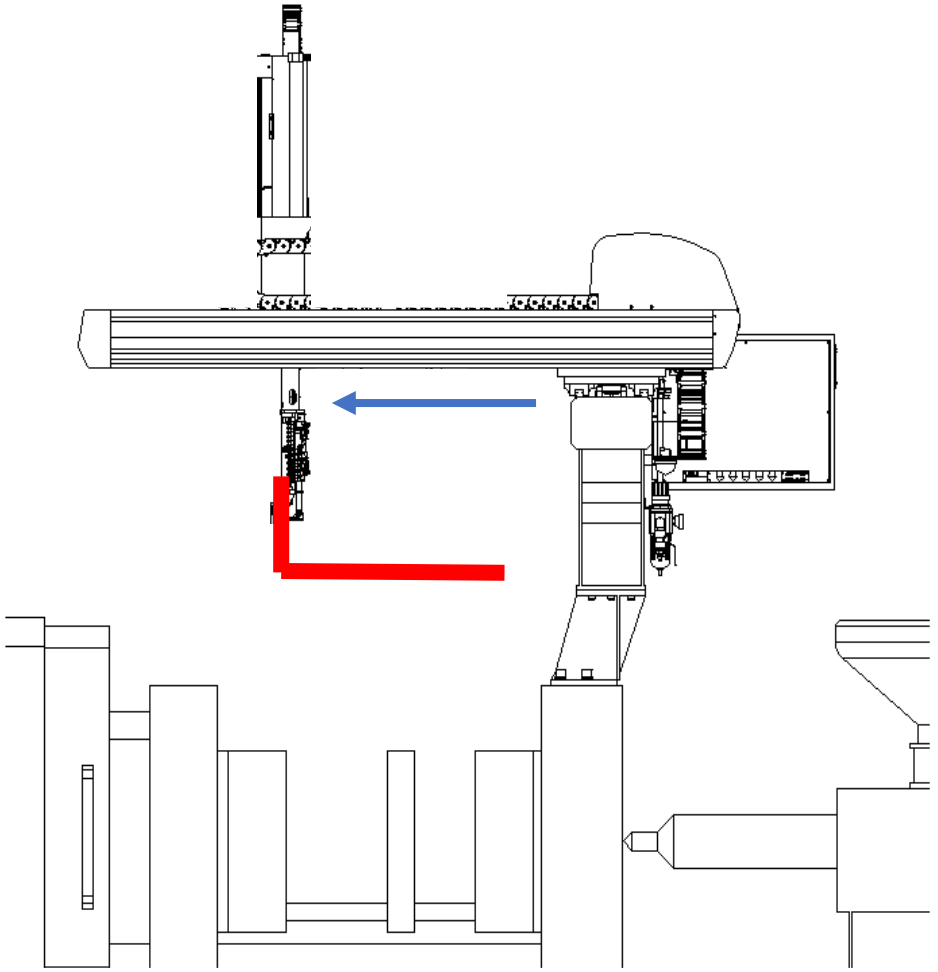
Take a note for X, Y axis values.

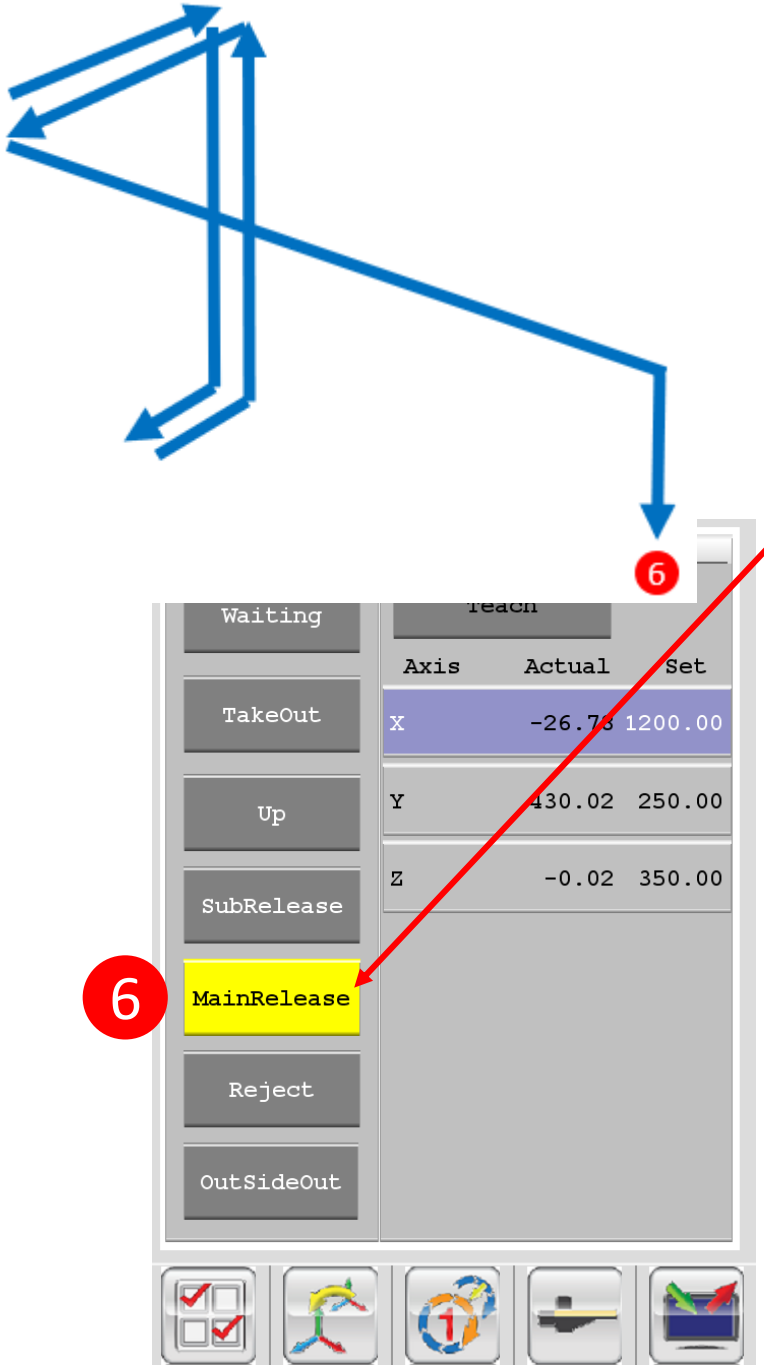
We will need them later.

Z-axis value must be 0



Move the robot forward,
And rotate EOAT





Select MainRelease

Traverse, down the robot to Release position.

Press TEACH button.

Be careful EOAT not to contact with the robot.

Double press

Press this button

Open
Position Monitor

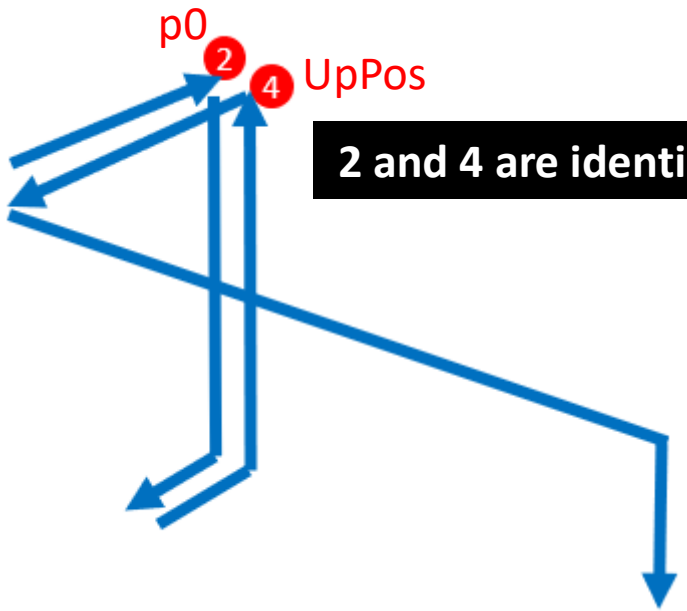
SETTING ❷p0 POSITION

Enter same X, Y values as ❹UP position.

Press here to modify each axis value

Z-axis value must be 0

Variables	x	y
p0 ❷	-26.80	112
p1	-26.80	430
OutSideWaitPos	830.61	499
home position	0.00	430
TakeOutPos	0.00	150
UpPos ❹	0.00	100
SubArmReleasePos	800.00	300
MainArmReleasePos	1,200.00	250
RejectPos	1,550.00	150
InsertGripWaitingPos	1,400.00	500
InsertGripPos	1,400.00	500
EOATPos	2,000.00	900



2 and 4 are identical positions.

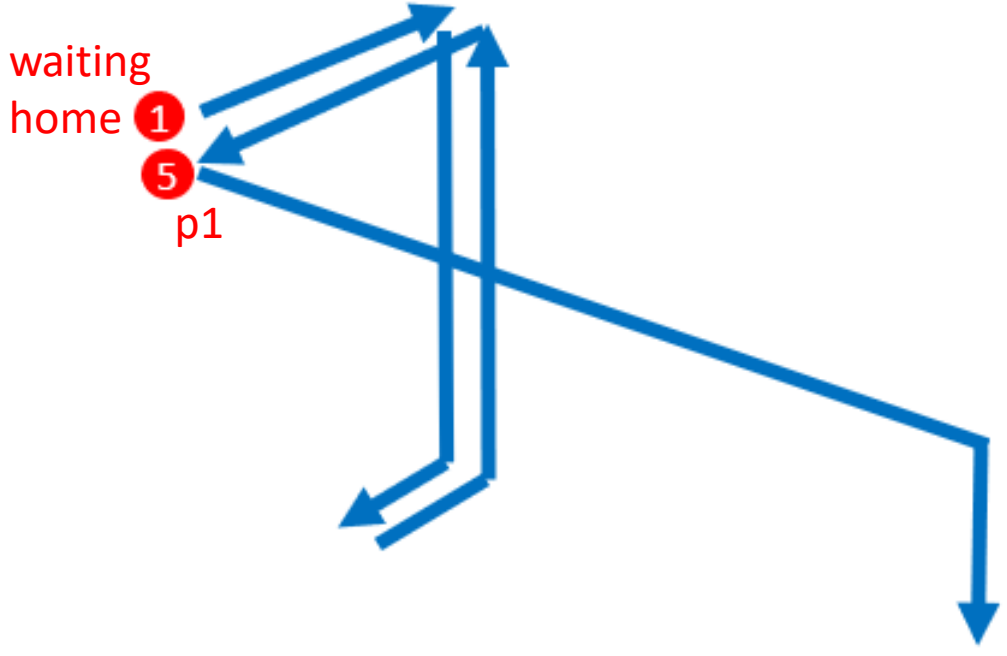
SETTING ❺p1 POSITION

Enter same X, Y values as ❶ Waiting position (=home position).

Z-axis value must be 0

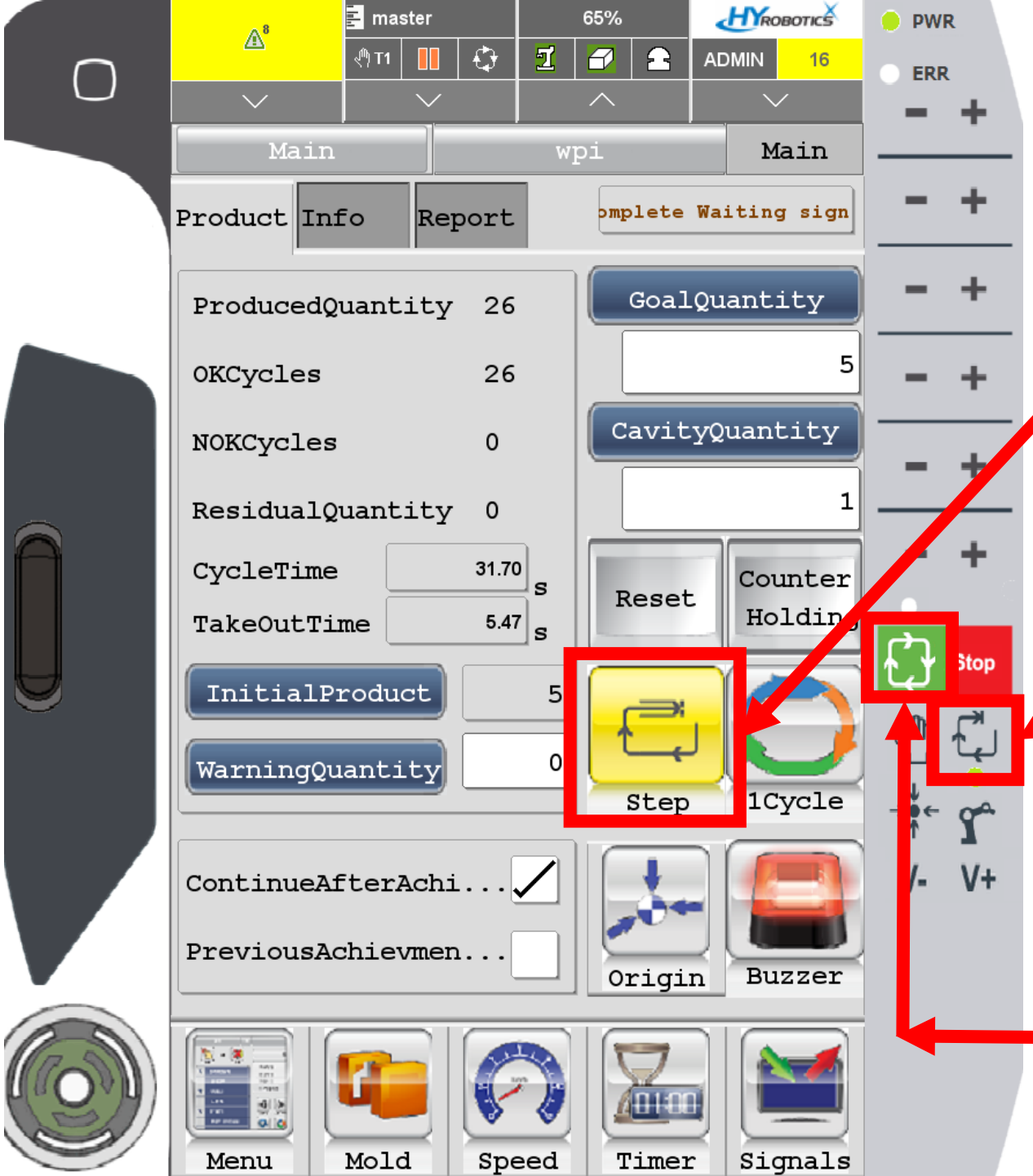
Variables	x	y
p0	-30.00	100
p1 ❺	5.00	430
OutSideWaitPos	830.61	499
home position ❶	-30.00	400
TakeOutPos	-30.00	183
UpPos	-30.00	100
SubArmReleasePos	1,250.00	600
MainArmReleasePos	995.72	387
RejectPos	1,550.00	150
InsertGripWaitingPos	1,400.00	500
InsertGripPos	1,400.00	500
EOATPos	2,000.00	900

1 and 5 are identical positions.



STEP 5

RUN DRY CYCLE
(TEST DRIVE)



Check the mold area is open

Turn on Step cycle

This function enables the robot runs automatic operation without mold signals with slower velocity

Step operation button to run the robot.

Press several times for the initial starting.

OR

Automatic operation button to run the robot.

Press twice for the initial starting.


HYROBOTICS