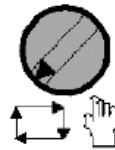
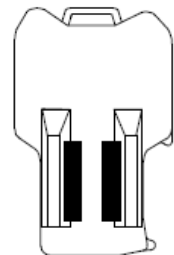


[Teach pendant enable switch]



This is used to switch between the teach mode and the playback mode in combination with the [Mode selector switch] on the operation panel or operation box.

[Enable switch] (Deadman switch)



This switch is provided on the rear panel, and it is used when the robot is to be manually operated in the teach mode.

Normally, it is provided on the left side only. There may be two buttons, one at the left and the other at the right as an option.

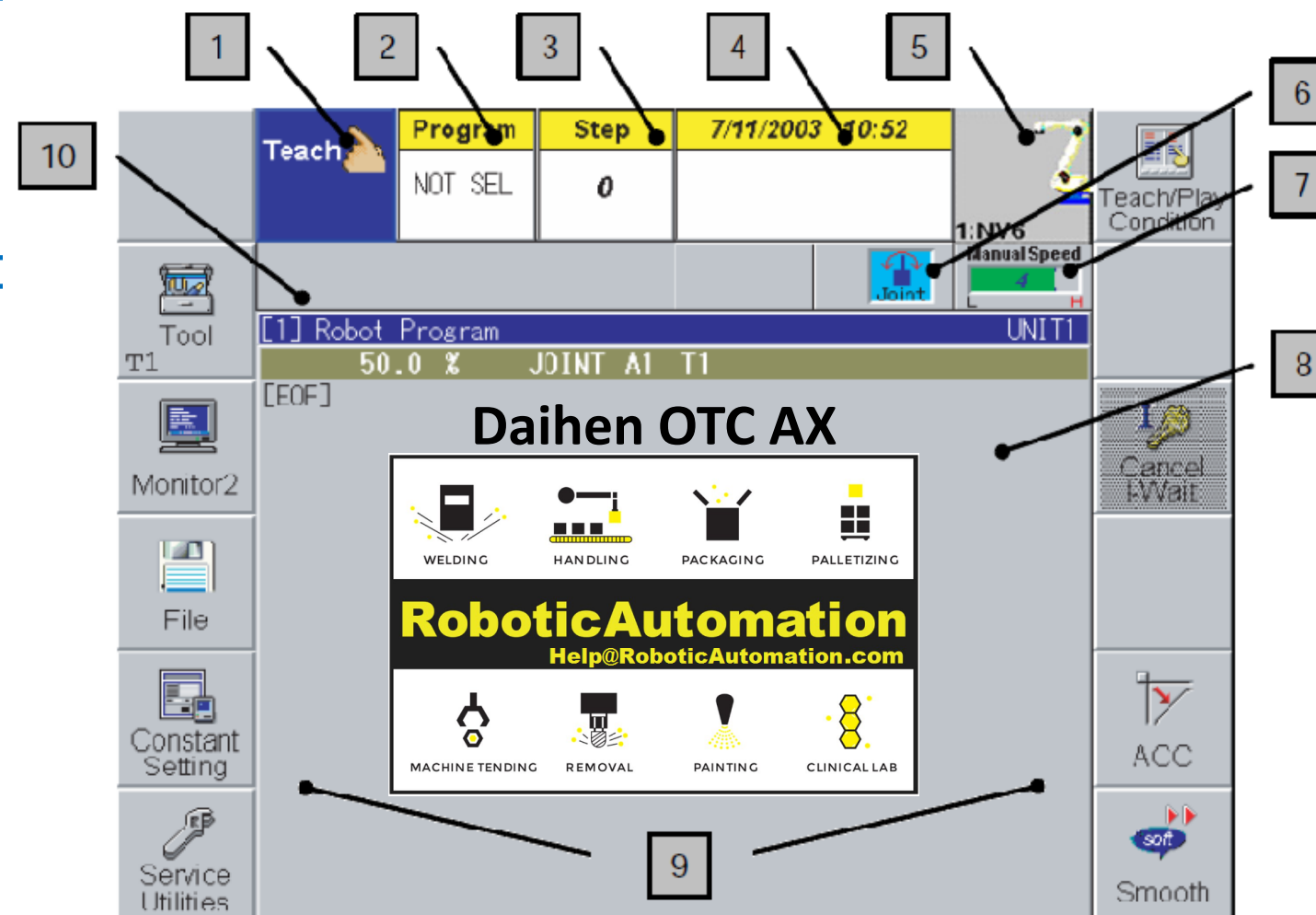
When the enable switch is grasped, power is supplied to the robot (the motor power is turned ON). The robot can be operated manually only while the switch is grasped.

If an impending danger is sensed, either release the enable switch or grasp it tightly until a clicking sound is heard.

1 Mode display area

The selected mode (teach, playback or high-speed teach) is displayed here. (The highspeed teach mode is optional.)
The motor power, operation underway and emergency stopped statuses are also displayed.

| Status | Teach mode | Playback mode |
|--|------------|---------------|
| Motor power OFF | | |
| Motor power ON, servo power OFF, now saving energy (playback mode) | | |
| Motor power ON, servo power ON | | |
| Motors energized, check GO/BACK operation underway (teach mode), now operating (playback mode) | | |
| Emergency stopped | | |



2 Program number display area

The number of the selected program is displayed.

3 Step number display area

The number of the step selected in the program is displayed here.

4 Date & time display area

The current date and time are displayed here.

5 Mechanism display area

The mechanism targeted for manual operation is displayed here. With a multi-unit specifications robot, the numbers of the units involved in the teaching are also displayed.

7 Speed display area

The manual operation speed is displayed here. When [ENABLE] is pressed, the check speed is displayed.

| Speed | Display | Speed | Display |
|--------------|---------|-------------|---------|
| Manual speed | | Check speed | |

8 Monitor display area

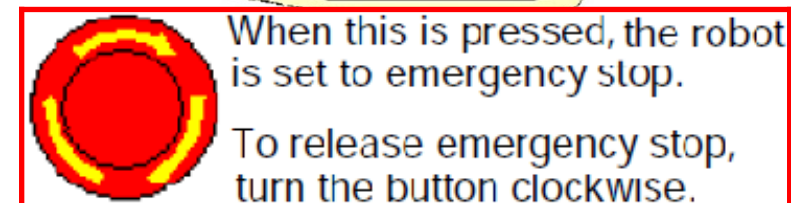
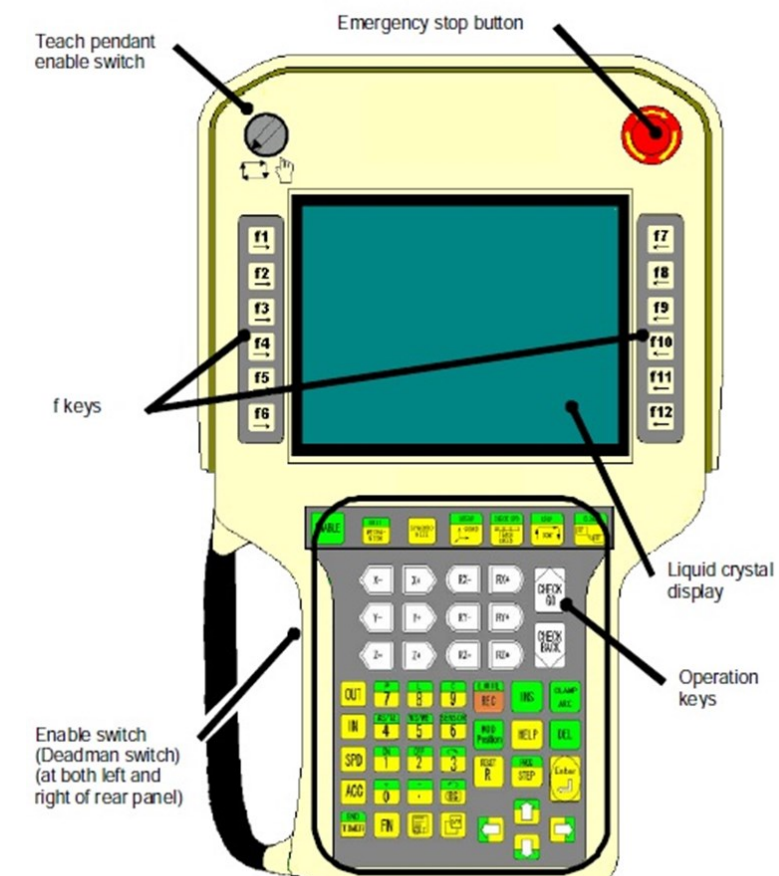
The contents of the program are displayed here (in the case of the initial settings).

9 f key display area

The functions that can be selected using the f keys are displayed here. The six keys on the left correspond to f1 to f6; the six keys on the right correspond to f7 to f12.

10 Variable status display area

The status displays including "input wait (I wait)" and "external start selected" appear as icons in this area. When this status ends, the icon is cleared.




6


Coordinate system display area

The selected coordinate is displayed here.

| Types of coordinate systems | Display |
|--|---------|
| Axis coordinate system | |
| Machine coordinate system | |
| Tool coordinate system (The number on the left of the icon is the tool number.) | |
| Work coordinate system | |
| Absolute coordinate system (world coordinate system) | |
| Cylindrical coordinate system | |
| User coordinate system (The number on the left of the icon is the coordinate number.) | |
| Welding line coordinate System | |

[ENABLE] 

The functions are executed by pressing this key together with other keys.


[UNIT/MECHANISM] 

- When this is pressed on its own, the mechanisms are selected.
When a multiple number of mechanisms are connected to the system, the mechanism to be operated manually is selected.
- When this is pressed together with [ENABLE], the unit is selected.
When a multiple number of units are defined in the system, the unit to be operated is selected.


[SYNCHRONIZE] 

This key is used by a system in which a multiple number of mechanisms are connected, and it has the following functions.

- When this is pressed on its own, it selects or releases coordinated manual operation.
- When this is pressed together with [ENABLE] during teaching, it selects or releases coordinated operations.
When cooperative operation is specified for a move command, "H" appears before the step number.

[INTERP/COORD] 

- When this is pressed on its own, one of the coordinates is selected.
During manual operation, the coordinate system that serves as the reference for operation is selected. Each time it is pressed, the axis independent, orthogonal coordinates (or user coordinates) or tool coordinates are selected and displayed on the LCD screen.
- When this is pressed together with [ENABLE], the interpolation type is selected.
This switches the interpolation type (joint interpolation, linear interpolation or circular interpolation) of the recording status.

[CHECK SPD /
TEACH SPEED] 

- When this is pressed on its own, the manual speed is changed.
The operating speed of the robot during manual operation is selected. Each time it is pressed, one of the 1 to 5 operating speeds is selected (the higher the number, the faster the speed).
Furthermore, the following function is provided as well.


NACHI The playback speed recorded in the steps is also determined by the manual speed which has been selected by this key.

DAIHEN The above setting is not established. Set the playback speed when teaching the movement commands.




This function is set by selecting [Constant Setting] → [5 Operation Constants] → [4 Record speed] → [Value of recording method — Decision method].

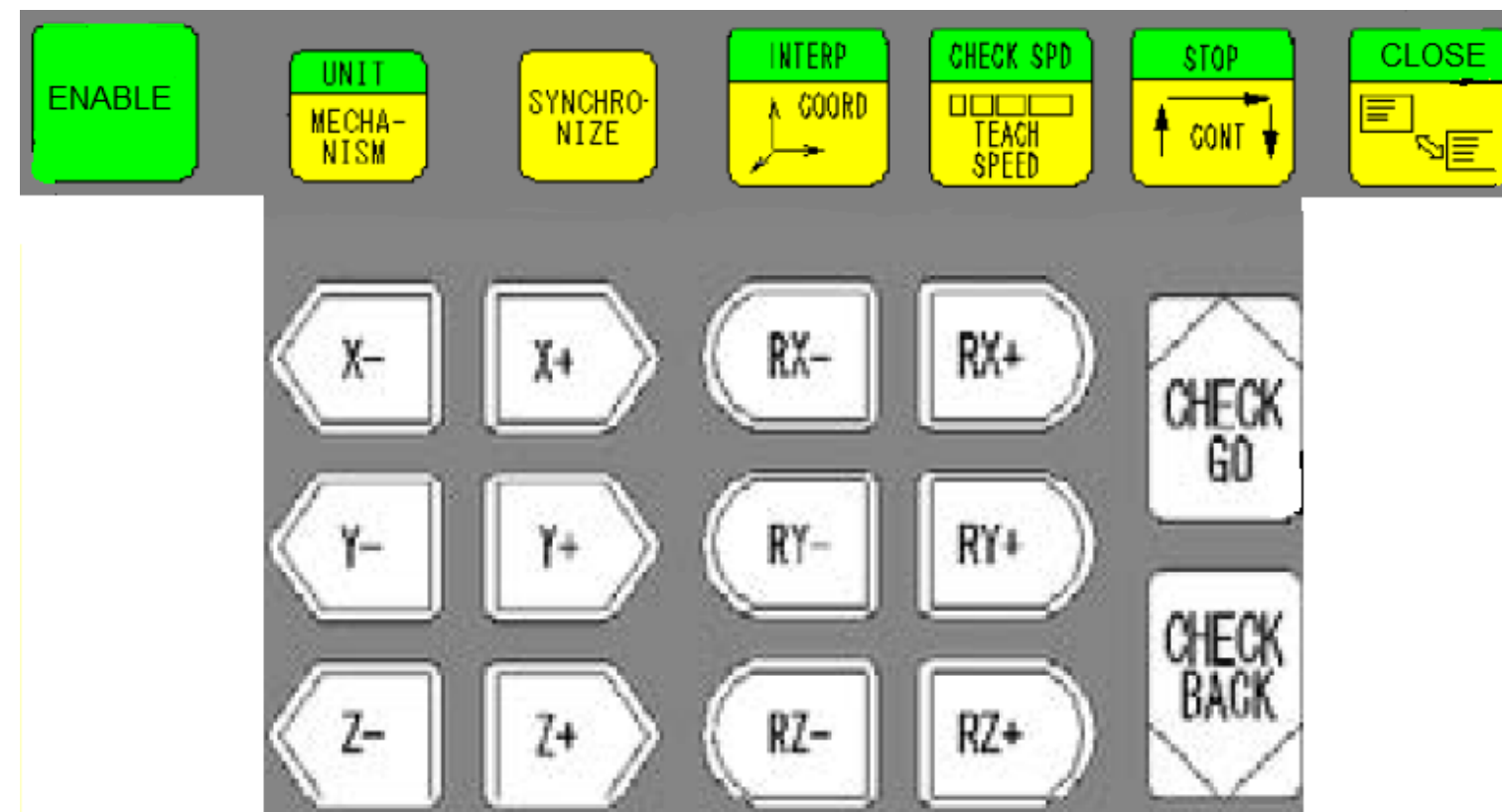
- When this is pressed together with [ENABLE], the check speed is changed.
The speed during a check go or check back operation is selected. Each time it is pressed, one of the 1 to 5 operating speeds is selected (the higher the number, the faster the speed).


[STOP/CONTINUOUS] 

- When this is pressed on its own, continuous or noncontinuous is selected.
Continuous or non-continuous during a check go or check back operation is selected.
When continuous operation is selected, the operation of the robot does not stop at each step.
- When this is pressed together with [ENABLE], playback is stopped.
The program being played back is stopped. (This has the same function as the stop button.)



[CLOSE/
SELECT SCREEN] 

- When this is pressed on its own, the screen is selected or moved.
If a multiple number of monitor screens are displayed, the screen targeted for operation is selected.
- When this is pressed together with [ENABLE], the screen is closed.
The selected monitor screen is closed.



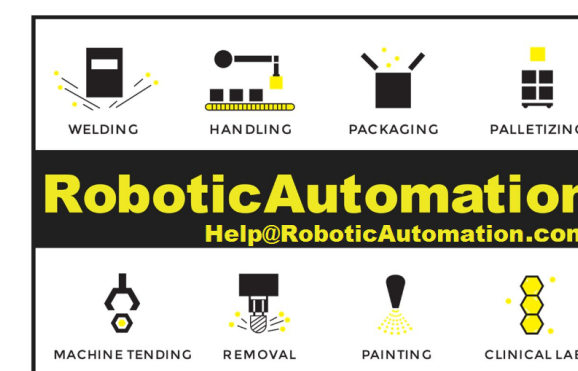
[Axis operating keys] 

- When these are pressed on their own, they have no function.
- When these are pressed together with the [Enable(Deadman) switch], the axes are operated.
The robot is moved manually. If an auxiliary axis to be moved, the operation target is selected ahead of time using [UNIT/MECHANISM].

[CHECK GO]  [CHECK BACK] 

- When these are pressed on their own, they have no function.
- When these are pressed together with the [Enable(Deadman) switch], the check go or check back operation is performed.
Normally, the robot is stopped at each recorded position (step) but it can also be operated continuously.
Use [STOP/CONTINUOUS] to select step or continuous.

Daihen OTC AX



[O.WRITE / REC]

- When this is pressed on its own, the movement command is recorded.
During teaching, the movement command is recorded.
This can be used only when the last step in the task program has been selected.
- When this is pressed together with [ENABLE], the movement command is overwritten.
The already recorded movement command is overwritten by the current recording statuses (position, speed, interpolation type, and accuracy). However, the command can be overwritten only when changes are made to what is recorded for the movement commands. A movement command cannot be overwritten by a function command; neither can a function command be overwritten by another function command.

NACHI The recording position, speed and accuracy of a recorded movement command can each be revised using [MOD Position], [SPD] and [ACC], respectively.

DAIHEN The recording position of a recorded movement command can be revised using [MOD Position].

HINT The [SPD] and [ACC] key functions are set by selecting [Constant Setting] → [5 Operation Constants] → [1 Operation condition] → [5 Usage of SPD key] or [6 Usage of ACC key].

[MOD Position]

- When this is pressed on its own, it has no function.
- When this is pressed together with [ENABLE], the position is modified.
The position stored in the movement command now selected is changed to the current robot position.

[RESET/R]

This clears the input or returns the setting screen to its original status. It also enables R codes (short-cut codes) to be input. The function that is to be used can be called immediately by inputting an R code.

[INS]

- When this is pressed on its own, it has no function.
- When this is pressed together with [ENABLE], a movement command is inserted.

NACHI The movement command is inserted "Before" the current step.

DAIHEN The movement command is inserted "After" the current step.

HINT "Before" can be changed to "After" or vice versa by selecting [Constant Setting] → [5 Operation Constants] → [1 Operation condition] → [7 Step insertion position].

[HELP]

Press this for help concerning an operation or function.
The built-in tutorial function (help function) is called.

[PROG/STEP]

- When this is pressed on its own, a step is specified.
This is used to call a step specified in the program.
- When this is pressed together with [ENABLE], a program is specified.
The specified program is called.

Arrow keys

- When these keys are pressed on their own, the cursor moves.
- When these are pressed together with [ENABLE], the page is moved or changed.
- On a screen where the settings are configured on a multiple number of pages, the page is moved.
- On a program editing screen, for instance, the cursor is moved by several lines at a time.
- On a service or constant setting screen, for instance, the selection items arranged horizontally (radio buttons) are selected.
- On a teach or playback mode screen, the number of the current step is changed.

[CLAMP ARC]

This key functions in a different way depending on the application concerned.

When the spot welding application is used

- When this is pressed on its own, the spot welding command is set.
It is used to set the spot welding commands.
Each time the key is pressed, the ON or OFF is selected for the recording status.
- When this is pressed together with [ENABLE], the spot welding gun is manually pressurized.

When the arc welding application is used

- When this is pressed on its own, commands are easily selected.
Selects "easy teach mode", which allows you to select move commands, welding start/stop commands and frequently used application commands with simple operations.
- When this is pressed together with [ENABLE], it has no function.

[DEL]

- When this is pressed on its own, it has no function.
- When this is pressed together with [ENABLE], a step is deleted.
The step now selected (movement command or function command) is deleted.

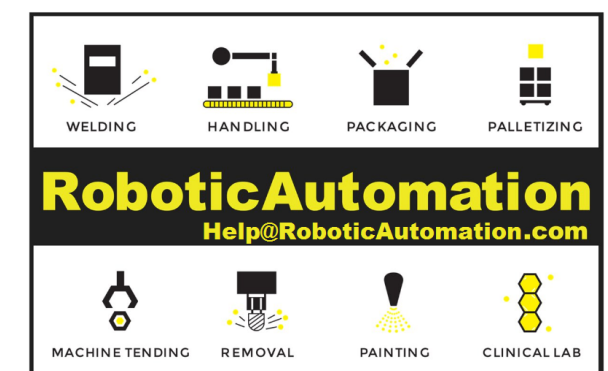
[Enter]


This enters the menu or numerical input contents.

HINT Determination operation of numerical input can also be performed with arrow keys by <Constant Setting> - [7F-key] - [7 Numerical input] and switching to "Cursor" under [Decision method of numerical input].




Daihen OTC AX




[OUT] 

- When this is pressed on its own, a short-cut to the SETM function command is provided.
During teaching, this short-cut calls the output signal command (SETM <FN105> function command).
- When this is pressed together with [ENABLE], the manual signals are output.
The external signals are set to ON or OFF manually.

[IN] 


During teaching, this short-cut calls the input signal wait "positive logic" command (WAITI <FN525> function command).

[SPD] 

NACHI This is used to revise the speed of recorded movement commands.

DAIHEN This is used to set the speed of movement commands.
(The setting is reflected in the recording status.)


HINT This function is set by selecting [Constant Setting] → [5 Operation Constants] → [1 Operation condition] → [5 Usage of SPD key].

[ACC] 

NACHI This is used to revise the accuracy of a recorded movement command.

DAIHEN This is used to set the accuracy of a movement command which is to be recorded. (What has been set is reflected in the recording status.)

HINT This function is set by selecting [Constant Setting] → [5 Operation Constants] → [1 Operation condition] → [6 Usage of ACC key].


[TIMER] 

During teaching, this short-cut records the timer command (DELAY <FN50> function command).

Numeric keys/
[0] to [9] / [.]

| | | |
|----|-----|------|
| 7 | 8 | 9 |
| 4 | 5 | 6 |
| ON | OFF | |
| 1 | 2 | 3 |
| 0 | . | [BS] |

- When these are pressed on their own, numbers (0 to 9, decimal point) are input.
- When [1] is pressed together with [ENABLE], ON is selected.
On a setting screen, for instance, a check mark is placed inside the check box.
- When [2] is pressed together with [ENABLE], OFF is selected.
On a setting screen, for instance, the check mark inside the check box is removed.
- When [3] is pressed together with [ENABLE], redo. This re-does the operation which was restored by clearing (undo) the operation immediately before. It is effective only while creating a new or editing an existing program.
- When [0] is pressed together with [ENABLE], "+" is input. Input "+".
- When [.] is pressed together with [ENABLE], "-" is input. Input "-".

[FN] (Function) 

This is used when selecting the function commands.

[EDIT] 

This opens the program editing screen.

On the program editing screen, principally the function commands are changed, added or deleted and the parameters of movement commands are changed.

[I/F] (Interface) 

When a teach pendant with touch panel specifications is used, the interface panel window is opened.

Numeric keys/
[4] to [9]

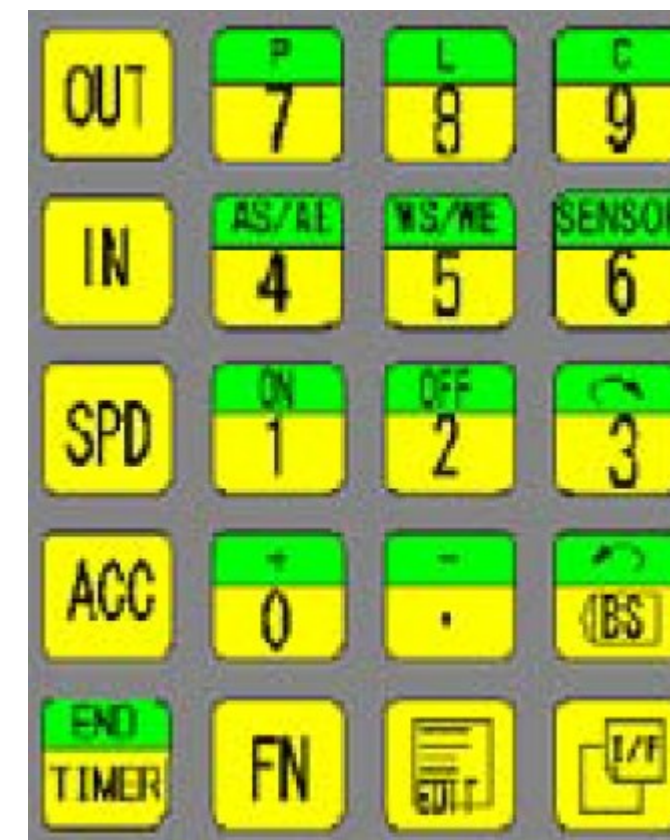
| | | |
|-------|-------|--------|
| P | L | C |
| 7 | 8 | 9 |
| AS/AE | WS/WE | SENSOR |
| 4 | 5 | 6 |


AX21 Capable of operating the following functions.

- When these are pressed on their own, numbers (4 to 9) are input.
- When [4] is pressed together with [ENABLE], AS/AE is selected.
During teaching, commands regarding arc welding will be displayed on the f key (f1 ~ f12).
- When [5] is pressed together with [ENABLE], WS/WE is selected.
During teaching, commands regarding weaving will be displayed on the f key (f1 ~ f12).
- When [6] is pressed together with [ENABLE], SENSOR is selected.
During teaching, commands regarding sensor will be displayed on the f key (f1 ~ f12).
- When [7] is pressed together with [ENABLE], P is selected.
This short-cut calls the movement command for the Joint Interpolation (JOINT).
- When [8] is pressed together with [ENABLE], L is selected.
This short-cut calls the movement command for the Line Interpolation (LIN)
- When [9] is pressed together with [ENABLE], C is selected.
This short-cut calls the movement command for the Circular Interpolation (CIR).

[BS] (Back space) 

- When this is pressed on its own, a number or character is deleted.
The number or character before the cursor position is deleted. The key is also used to release a selection during file operations.
- When this is pressed together with [ENABLE], undo the operation immediately before.
The operation performed immediately before is cleared, and the status prior to the change is restored.
It is effective only while creating a new or editing an existing program.

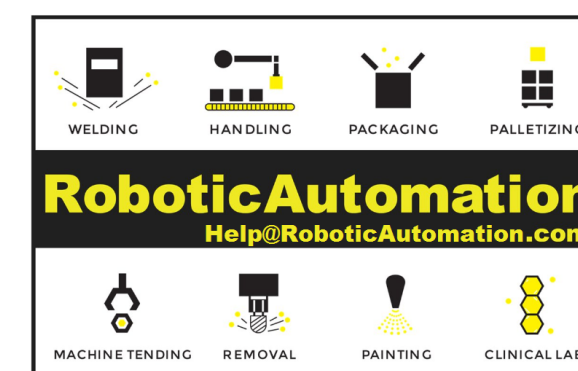


[END/TIMER] 













AX21 Capable of operating the following functions.

- When this is pressed on its own, it will lead to a short-cut to DELAY (function command)
During teaching, this short-cut records the timer command (DELAY <FN50> function command)
- When this is pressed together with [ENABLE], it will lead to a short-cut to END (function command)
During teaching, this short-cut records the end command (END <FN92> function command).











Daihen OTC AX



■ Teach mode (page 1: when the keys are simply pressed)

| | | | | | |
|----|---|-------------------------------|---------------------------------|---|-----|
| f1 |  | key switching | Arc start command selection |  | f7 |
| f2 |  | Welding ON/OFF | Weaving start command selection |  | f8 |
| f3 |  | Weaving ON/OFF | Allocates station startup |  | f9 |
| f4 |  | File operations | Wire inching (low-speed) |  | f10 |
| f5 |  | Arc constant setting | Wire retract (low-speed) |  | f11 |
| f6 |  | Arc welding Condition setting | Gas check |  | f12 |

■ Teach mode (page 1: when the keys are pressed together with [ENABLE])












| | | | | | |
|----|---|---------------------------------------|--|---|-----|
| f1 |  | f key switching | Arc end command selection |  | f7 |
| f2 |  | Welder select | Weaving end command selection |  | f8 |
| f3 |  | Weaving ON/OFF target robot switching | Forcibly initiates I release. (Input wait release) |  | f9 |
| f4 | | No function | Wire inching (high-speed) |  | f10 |
| f5 |  | Sets the constant. | Wire retract (high-speed) |  | f11 |
| f6 |  | Service menu | No function | | f12 |



Initial layout of f keys for arc welding (teach mode)







■ Teach mode (page 2: when the keys are simply pressed)

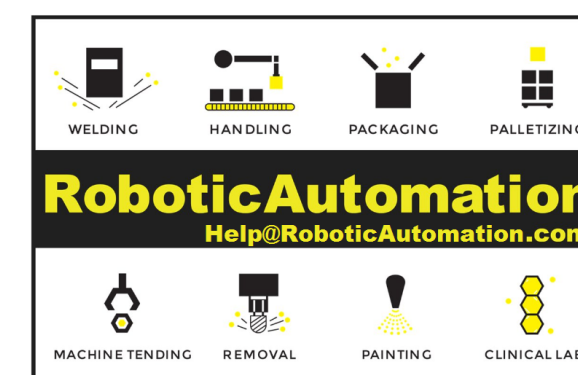
| | | | | | |
|----|---|-------------------------------------|---------------------------------------|---|-----|
| f1 |  | f key switching | Sets the teach or playback conditions |  | f7 |
| f2 |  | Sensor ON/OFF | Manual speed Switching (speed up) |  | f8 |
| f3 |  | Input/output ON/OFF | Manual speed switching (speed down) |  | f9 |
| f4 |  | Sets monitor 2 | No function | | f10 |
| f5 |  | Tool switching | Sets the accuracy. |  | f11 |
| f6 |  | Step Clear/ Change Specified Return | Performs the Smooth setting. |  | f12 |












■ Teach mode (page 2: when the keys are pressed together with [ENABLE])












| | | | | | |
|----|---|--|---------------------------|---|-----|
| f1 |  | f key switching | No function | | f7 |
| f2 | | No function | No function | | f8 |
| f3 | | No function | No function | | f9 |
| f4 | | No function | No function | | f10 |
| f5 | | No function | Pass/ positioning setting |  | f11 |
| f6 |  | Automatic operation pause status release (only during station startup) | Acceleration setting |  | f12 |

Daihen OTC AX



| ■ Playback mode (page 1: when the keys are simply pressed) | | | | |
|--|---|-----------------|---|-----|
| f1 |  | f key switching | Arc welding Condition setting  | f7 |
| f2 |  | Welding ON/OFF | No function | f8 |
| f3 |  | Weaving ON/OFF | No function | f9 |
| f4 |  | Arc monitor | Wire inching (low-speed)  | f10 |
| f5 | | No function | Wire retract (low-speed)  | f11 |
| f6 |  | Stop | Gas check  | f12 |










| ■ Playback mode (page 1: when the keys are pressed together with [ENABLE]) | | | | |
|--|---|--|--|-----|
| f1 |  | f key switching | Service Menu  | f7 |
| f2 |  | Welder select | Step feed  | f8 |
| f3 |  | Weaving ON/OFF target robot switching | Forcibly initiates I release. (Input wait release)  | f9 |
| f4 |  | Step continuous | No function | f10 |
| f5 |  | Switches between cycle, Continuous and step. | Speed override (10% up)  | f11 |
| f6 |  | Stop | Speed override (10% down)  | f12 |









Initial layout of f keys for arc welding (playback mode)


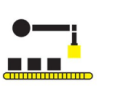




| ■ Playback mode (page 2: when the keys are simply pressed) | | | | |
|--|---|--|--|-----|
| f1 |  | f key switching | Sets the teach or playback conditions.  | f7 |
| f2 |  | Sensor ON/OFF | No function | f8 |
| f3 |  | Step Clear/ Change Specified Return | No function | f9 |
| f4 |  | Changing the method for returning to the stopped position for normal startup | No function | f10 |
| f5 |  | Changing the method for starting up after a step set. | No function | f11 |
| f6 |  | Stop | No function | f12 |








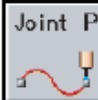

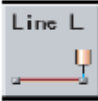

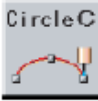






| ■ Playback mode (page 2: when the keys are pressed together with [ENABLE]) | | | | |
|--|---|-----------------|---|-----|
| f1 |  | f key switching | No function | f7 |
| f2 | | No function | No function | f8 |
| f3 | | No function | No function | f9 |
| f4 | | No function | Wire inching (high-speed)  | f10 |
| f5 | | No function | Wire retract (high-speed)  | f11 |
| f6 |  | Stop | Simultaneously switches the start select and program select or station monitor   | f12 |

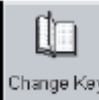
Daihen OTC AX











 WELDING
  HANDLING
  PACKAGING
  PALLETIZING

RoboticAutomation
 Help@RoboticAutomation.com

 MACHINE TENDING
  REMOVAL
  PAINTING
  CLINICAL LAB


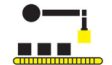


| | | | | | |
|----|---|---|--------------------------|---|-----|
| f1 |  | f key switching | Move command (JOINT) |  | f7 |
| f2 |  | Weld start command(AS) | Move command (LINE) |  | f8 |
| f3 |  | Weld end command (AE) | Move command (CIRCLE) |  | f9 |
| f4 |  | Fixed pattern Weaving start Command (WFP) | Wire inching (low-speed) |  | f10 |
| f5 |  | Weaving end Command (WE) | Wire retract (low-speed) |  | f11 |
| f6 |  | END instruction | Gas check |  | f12 |







| | | | | | |
|----|---|-----------------------------------|--------------------------|---|-----|
| f1 |  | f key switching | Start allocation |  | f7 |
| f2 |  | Step jump command(JMP) | SET command |  | f8 |
| f3 |  | Program call command (CALLP) | RESET command |  | f9 |
| f4 |  | Joint weaving Start command (WAX) | ON wait command (WAITI) |  | f10 |
| f5 | | No function | OFF wait command (WAITJ) |  | f11 |
| f6 |  | Timer command (DELAY) | No function | | f12 |

Initial layout of f keys for arc welding (when the CLAMP/ATRC key has been pressed)

Daihen OTC AX

WELDING
HANDLING
PACKAGING
PALLETIZING

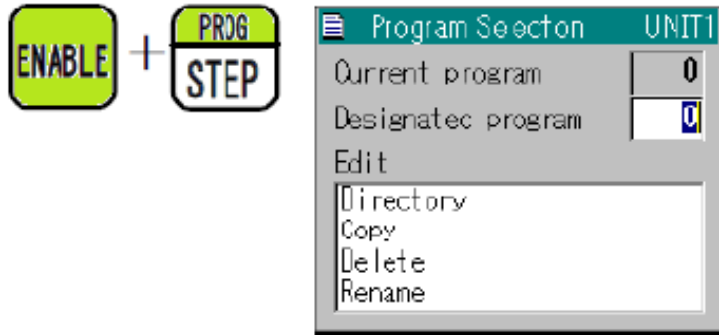





MACHINE TENDING
REMOVAL
PAINTING
CLINICAL LAB

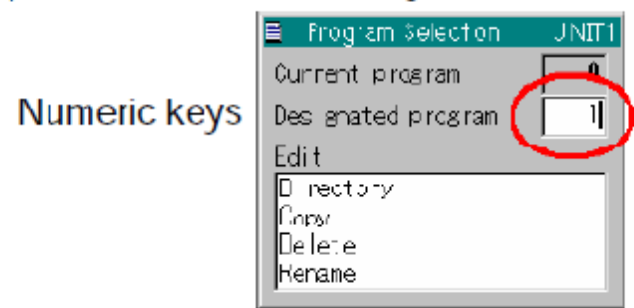
RoboticAutomation
Help@RoboticAutomation.com

Input the number of the program.

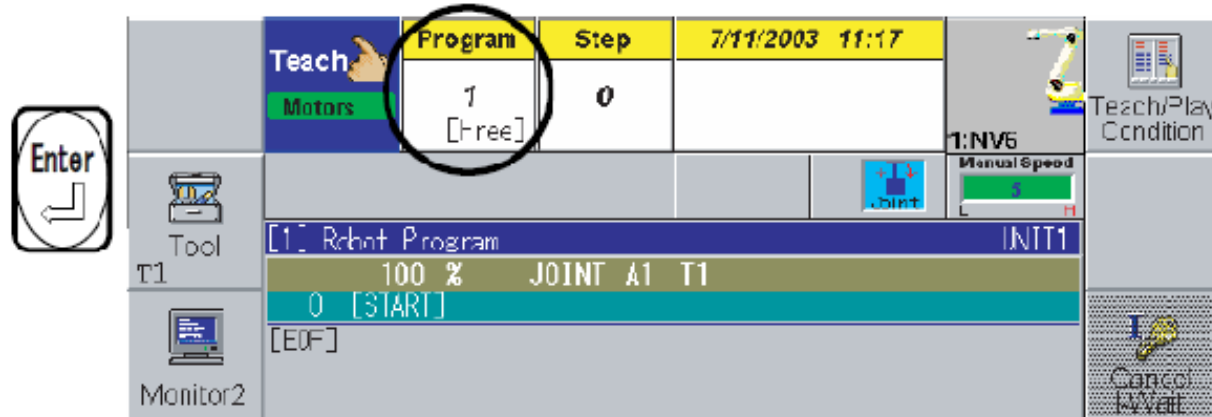
- 1 Select the teach mode.
- 2 While holding down [ENABLE], press [PROG/STEP].
>> The [Program Selection] window now opens.



- 3 Input the number of the program in the "Designated program" field, and press [Enter].
When "1" is to be specified as the program number, for instance, press the [1] numeric key.



- 4 Press [Enter].
>> Program "1", a new program, is now opened.

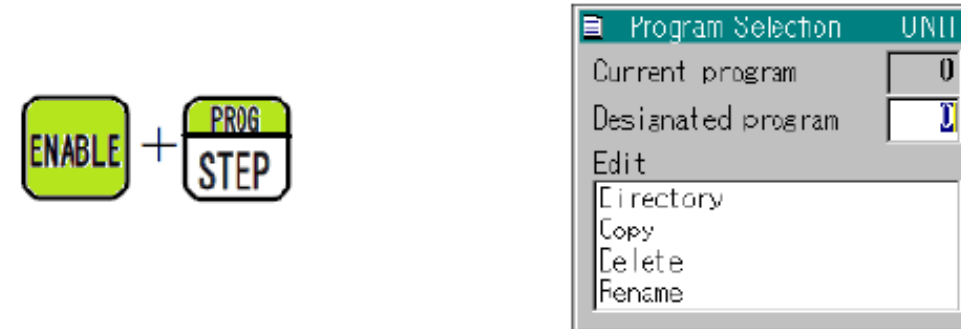


At this point, the teaching can now begin.

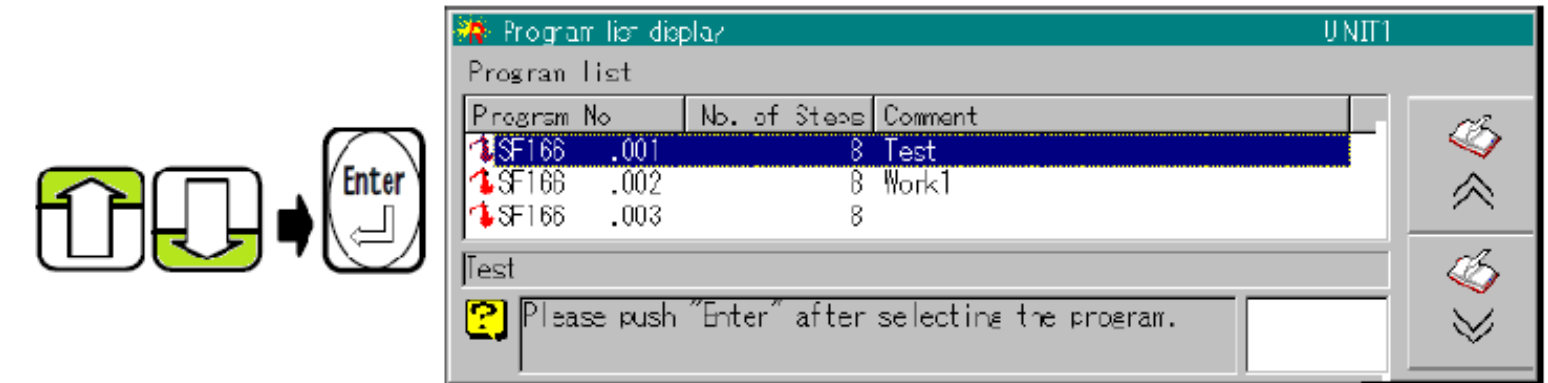


Listing the programs on the display

- 1 Select the teach mode.
- 2 While holding down [ENABLE], press [PROG/STEP].
>> The [Program Selection] window now opens.

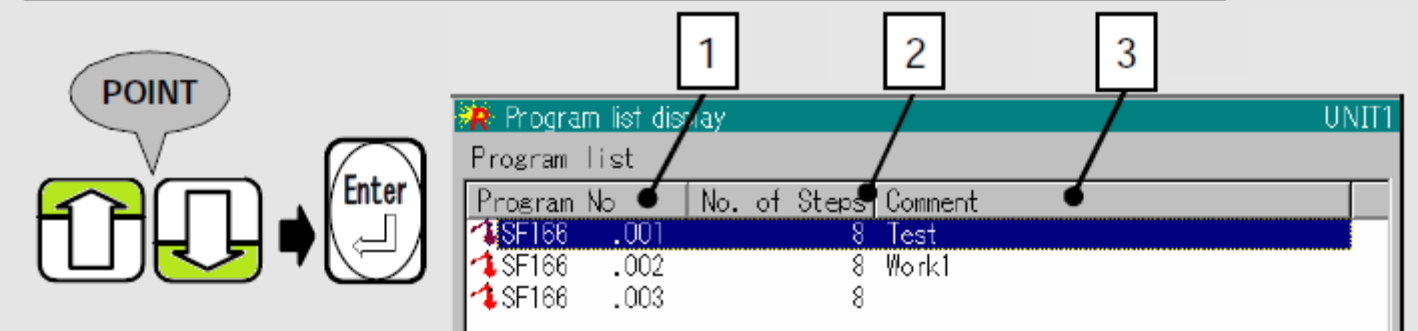


- 3 Align the cursor with "Directory", and press [Enter].
>> A list of the programs already created is now displayed.



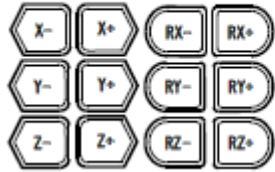
- 4 Align the cursor with the program to be opened, and press [Enter].
>> The selected program is now opened.

Concerning the contents displayed when programs are listed



- 1: The program filenames are displayed in this column.
The filenames are indicated using the "robot name.xxxx" format.
"xxxx" denotes the number of the program.
- 2: The number of recorded steps is displayed in this column.
- 3: If comments have been registered, they are displayed in this column.

1 Use the [Axis operation keys] to move the robot



2 In the recording status, movement commands have already been selected.

| [1] Robot Program | | | | UNIT1 |
|-------------------|----------|----|--|-------|
| 20.0 % | JOINT A1 | T1 | | |
| 0 | [START] | | | |
| [EOF] | | | | |

Recording status

3 While holding down [ENABLE], press [INTERP/COORD], and set the interpolation specification of the recording status to "JOINT." "JOINT" → "LIN" → "CIR" → "JOINT", etc. >> Each time this is pressed, the interpolation type of the recording status is switched in the following sequence:

| | | |
|-----------------------|--------------------|-------|
| ENABLE + INTERP/COORD | [1] Robot Program | UNIT1 |
| | 100 % JOINT A1 T1 | |
| | ↓ | |
| | [1] Robot Program | UNIT1 |
| | 200 cm/s LIN A1 T1 | |
| | ↓ | |
| | [1] Robot Program | UNIT1 |
| | 200 cm/s CIR A1 T1 | |
| | ↓ | |
| | [1] Robot Program | UNIT1 |
| | 100 % JOINT A1 T1 | |

4 Press [SPD].

>> The [Modify speed] screen now appears.

SPD

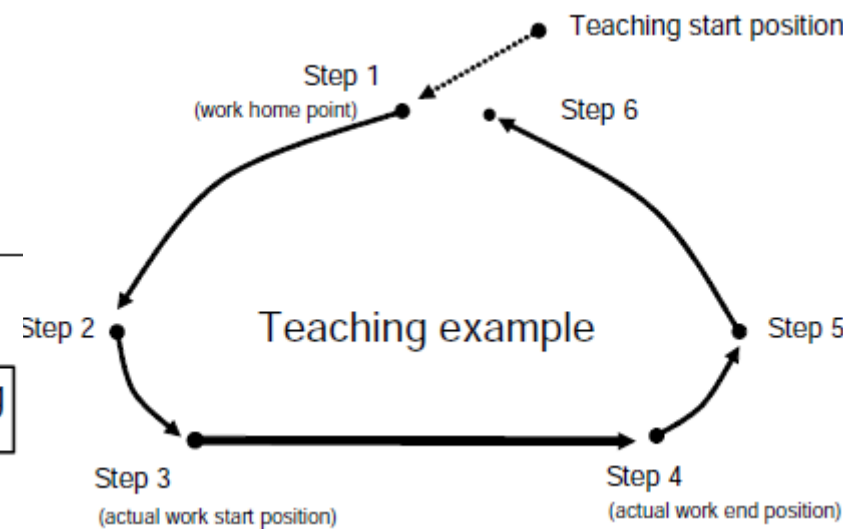
Modify speed

Input Power ratio(%).[1.0 - 100.0]

5 Input "100", and press [Enter].

>> "100%" is displayed as the recording status.

| | | | |
|-----|-------|-------------------|-------|
| 100 | Enter | [1] Robot Program | UNIT1 |
| | | 100 % JOINT A1 T1 | |
| | | 0 [START] | |



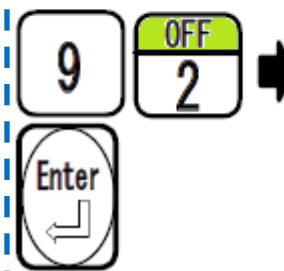
Press [FN].

>> The list of function commands is now displayed.



Press [9] → [2] → [Enter].

>> The end command is now recorded.



6 To specify the accuracy level, press [ACC].

>> Each time it is pressed, the accuracy changes in sequence by one level from A1 to A8.

| | | | | |
|-------------------|----------|----|--|-------|
| [1] Robot Program | | | | UNIT1 |
| 100 % | JOINT A1 | T1 | | |
| 0 | [START] | | | |
| [EOF] | | | | |

7 Press [O.WRITE/REC].

>> Step X is now recorded.

| | | | | |
|-------------------|----------|----------|----|-------|
| [1] Robot Program | | | | UNIT1 |
| 100 % | JOINT A1 | T1 | | |
| 0 | [START] | | | |
| 1 | 100 % | JOINT A1 | T1 | |
| [EOF] | | | | |

Step 1

Step 2

Step 3

Step 4

Step 5

Step 6

Step 7

| | | | | |
|-------------------|----------|----------|----|-------|
| [1] Robot Program | | | | UNIT1 |
| 100 % | JOINT A1 | T1 | | |
| 0 | [START] | | | |
| 1 | 100 % | JOINT A1 | T1 | |
| [EOF] | | | | |

| | | | | |
|-------------------|----------|----------|----|-------|
| [1] Robot Program | | | | UNIT1 |
| 100 % | JOINT A1 | T1 | | |
| 0 | [START] | | | |
| 1 | 100 % | JOINT A1 | T1 | |
| 2 | 100 % | JOINT A1 | T1 | |
| [EOF] | | | | |

| | | | | |
|-------------------|----------|----------|----|-------|
| [1] Robot Program | | | | UNIT1 |
| 100 % | JOINT A1 | T1 | | |
| 0 | [START] | | | |
| 1 | 100 % | JOINT A1 | T1 | |
| 2 | 100 % | JOINT A1 | T1 | |
| 3 | 100 % | JOINT A1 | T1 | |
| [EOF] | | | | |

| | | | | |
|-------------------|----------|----------|----|-------|
| [1] Robot Program | | | | UNIT1 |
| 200 cm/m | LIN | A1 | T1 | |
| 0 | [START] | | | |
| 1 | 100 % | JOINT A1 | T1 | |
| 2 | 100 % | JOINT A1 | T1 | |
| 3 | 100 % | JOINT A1 | T1 | |
| 4 | 200 cm/m | LIN | A1 | T1 |
| [EOF] | | | | |

| | | | | |
|-------------------|----------|----------|----|-------|
| [1] Robot Program | | | | UNIT1 |
| 100 % | JOINT A1 | T1 | | |
| 0 | [START] | | | |
| 1 | 100 % | JOINT A1 | T1 | |
| 2 | 100 % | JOINT A1 | T1 | |
| 3 | 100 % | JOINT A1 | T1 | |
| 4 | 500 mm/s | LIN | A1 | T1 |
| 5 | 100 % | JOINT A1 | T1 | |
| [EOF] | | | | |

| | | | | |
|-------------------|----------|----------|----|----------|
| [1] Robot Program | | | | UNIT1 |
| 100 % | JOINT A1 | T1 | | |
| 0 | [START] | | | |
| 1 | 100 % | JOINT A1 | T1 | |
| 2 | 100 % | JOINT A1 | T1 | |
| 3 | 100 % | JOINT A1 | T1 | |
| 4 | 200 cm/m | LIN | A1 | T1 |
| 5 | 100 % | JOINT A1 | T1 | |
| 6 | 100 % | JOINT A1 | T1 | |
| 7 | END | | | FN92;End |
| [EOF] | | | | |

Daihen OTC AX

