

DX200 OPTIONS INSTRUCTIONS

FOR T-AXIS ENDLESS FUNCTION

Upon receipt of the product and prior to initial operation, read these instructions thoroughly, and retain for future reference.

MOTOMAN INSTRUCTIONS

MOTOMAN-□□□ INSTRUCTIONS
DX200 INSTRUCTIONS
DX200 OPERATOR'S MANUAL
DX200 MAINTENANCE MANUAL

The DX200 operator's manuals above correspond to specific usage.
Be sure to use the appropriate manual.

Part Number: 165264-1CD
Revision: 0



MANDATORY

- This manual explains T-axis endless function of the DX200 system. Read this manual carefully and be sure to understand its contents before handling the DX200.
- General items related to safety are listed in Chapter 1: Safety of the DX200 Instructions. To ensure correct and safe operation, carefully read the DX200 Instructions before reading this manual.



CAUTION

- Some drawings in this manual are shown with the protective covers or shields removed for clarity. Be sure all covers and shields are replaced before operating this product.
- The drawings and photos in this manual are representative examples and differences may exist between them and the delivered product.
- YASKAWA may modify this model without notice when necessary due to product improvements, modifications, or changes in specifications. If such modification is made, the manual number will also be revised.
- If your copy of the manual is damaged or lost, contact a YASKAWA representative to order a new copy. The representatives are listed on the back cover. Be sure to tell the representative the manual number listed on the front cover.
- YASKAWA is not responsible for incidents arising from unauthorized modification of its products. Unauthorized modification voids your product's warranty.

NOTES FOR SAFE OPERATION

Read this manual carefully before installation, operation, maintenance, or inspection of the DX200.

In this manual, the Notes for Safe Operation are classified as “WARNING”, “CAUTION”, “MANDATORY”, or “PROHIBITED”.



WARNING

Indicates a potentially hazardous situation which, if not avoided, could result in death or serious injury to personnel.



CAUTION

Indicates a potentially hazardous situation which, if not avoided, could result in minor or moderate injury to personnel and damage to equipment. It may also be used to alert against unsafe practices.



MANDATORY

Always be sure to follow explicitly the items listed under this heading.



PROHIBITED

Must never be performed.

Even items described as “CAUTION” may result in a serious accident in some situations. At any rate, be sure to follow these important items



To ensure safe and efficient operation at all times, be sure to follow all instructions, even if not designated as “CAUTION” and “WARNING”.



WARNING

- Before operating the manipulator, check that servo power is turned OFF when the emergency stop buttons on the front door of the DX200 and programming pendant are pressed. When the servo power is turned OFF, the SERVO ON LED on the programming pendant is turned OFF.

Injury or damage to machinery may result if the emergency stop circuit cannot stop the manipulator during an emergency. The manipulator should not be used if the emergency stop buttons do not function.

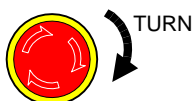
Figure 1: Emergency Stop Button



- Once the emergency stop button is released, clear the cell of all items which could interfere with the operation of the manipulator. Then turn the servo power ON

Injury may result from unintentional or unexpected manipulator motion.

Figure 2: Release of Emergency Stop



- Observe the following precautions when performing teaching operations within the P-point maximum envelope of the manipulator:
 - View the manipulator from the front whenever possible.
 - Always follow the predetermined operating procedure.
 - Keep in mind the emergency response measures against the manipulator's unexpected motion toward you.
 - Ensure that you have a safe place to retreat in case of emergency.

Improper or unintended manipulator operation may result in injury.

- Confirm that no person is present in the P-point maximum envelope of the manipulator and that you are in a safe location before:
 - Turning ON the DX200 power
 - Moving the manipulator with the programming pendant
 - Running the system in the check mode
 - Performing automatic operations

Injury may result if anyone enters the P-point maximum envelope of the manipulator during operation. Always press an emergency stop button immediately if there is a problem. The emergency stop buttons are located on the right of the front door of the DX200 and the programming pendant.



CAUTION

- Perform the following inspection procedures prior to conducting manipulator teaching. If problems are found, repair them immediately, and be sure that all other necessary processing has been performed.
 - Check for problems in manipulator movement.
 - Check for damage to insulation and sheathing of external wires.
- Always return the programming pendant to the hook on the DX200 cabinet after use.

The programming pendant can be damaged if it is left in the manipulator's work area, on the floor, or near fixtures.

- Read and understand the Explanation of the Warning Labels in the DX200 Instructions before operating the manipulator.

Definition of Terms Used Often in This Manual

The MOTOMAN is the YASKAWA industrial robot product.

The MOTOMAN usually consists of the manipulator, the controller, the programming pendant, and supply cables.

In this manual, the equipment is designated as follows:

Equipment	Manual Designation
DX200 Controller	DX200
DX200 Programming Pendant	Programming Pendant
Cable between the manipulator and the controller	Manipulator Cable

DX200 T-Axis Endless Function

Descriptions of the programming pendant keys, buttons, and displays are shown as follows:

Equipment		Manual Designation
Programming Pendant	Character Keys /Symbol Keys	The keys which have characters or its symbol printed on them are denoted with []. ex. [ENTER]
	Axis Keys /Numeric Keys	[Axis Key] and [Numeric Key] are generic names for the keys for axis operation and number input.
	Keys pressed simultaneously	When two keys are to be pressed simultaneously, the keys are shown with a "+" sign between them, ex. [SHIFT]+[COORD]
	Displays	The menu displayed in the programming pendant is denoted with { }. ex. {JOB}

Description of the Operation Procedure

In the explanation of the operation procedure, the expression "Select ●●●" means that the cursor is moved to the object item and the SELECT key is pressed.

Registered Trademark

In this manual, names of companies, corporations, or products are trademarks, registered trademarks, or brand names for each company or corporation. The indications of (R) and TM are omitted.

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1 T-Axis Endless Function

This function is used for endless rotation of an T-axis. In order to prevent T-axis from rotating in the reversed direction for the endless rotating amount when the manipulator moves to the next step after the endless rotation has been performed, a function to reset the endless axis position to a position within one revolution is also available.

The following outlines the function.

1.1 Endless Rotation

By specifying “How many times T-axis is to be rotated” for a move instruction (MOVJ), T-axis rotates for “the specified rotating amount + the taught position pulses” while moving to the target position.

“How many times T-axis is to be rotated” is specified with “MT” tag.

For the rotating amount, from -32768 to 32767 revolutions can be specified for one move instruction.

1.1.1 Relative Motion and Absolute Motion

Endless rotation has two types of motion; relative motion and absolute motion.

Relative motion enables T-axis to move to a target position from a taught position by rotating for the sum of T-axis rotating amount and the rotating amount of start position.

Target Position = Taught Position

+ (T-axis rotating amount + start position rotating amount)

To rotate the axis continuously, move instruction (same position) is to be registered consecutively.

When emergency stop is executed, and then restart is executed, the target position will be changed, and T-axis moves to the position from taught position by rotating from the sum of T-axis rotating amount and the rotating amount of restart position.

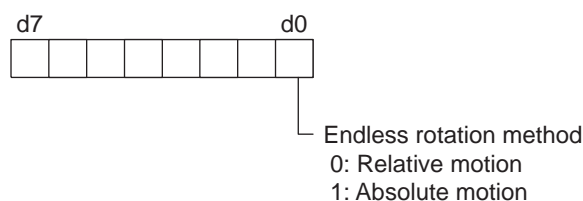
Absolute motion enables T-axis to move to target position from taught position by rotating for T-axis rotating amount.

target position = taught position + T-axis rotating amount

Even in case that the emergency stop is executed during endless rotation, and then the restart is executed, the target position is not changed.

■ S2C710 T-axis endless motion instruction

Motion method for T-axis endless function is to be set with this parameter



1.2 Resetting the Rotating Amount

To perform an interpolation after completion of endless rotation, re-create T-axis current value pulse and the motor feedback pulse at a position within one revolution in one of the following operations.

- Execution of MRESET instruction
- Operation from the programming pendant

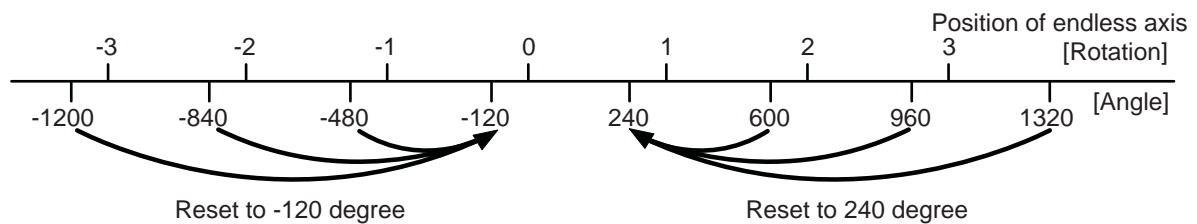
The position of the endless axis after resetting the rotation angle is one of the following two areas depending on the position before reset.

When the position before reset is 0 degree or higher: 0 to 360 [degree]

When the position before reset is 0 degree or lower: -360 to 0 [degree]

<Example>

The position after reset when the endless axis is reset at a position of -120 degree between -3 to 3 revolutions.



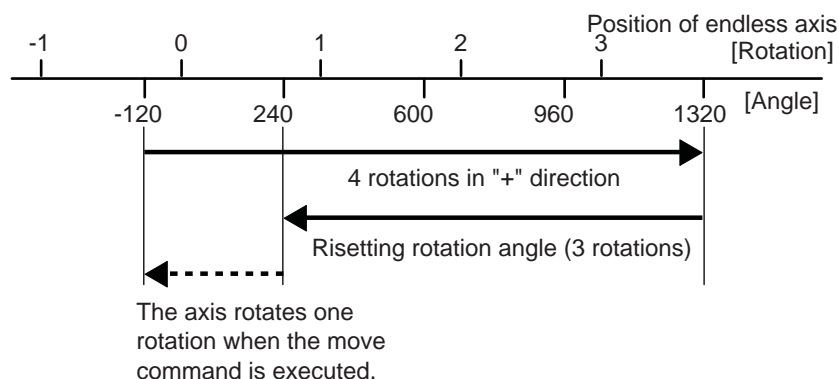
Perform teaching so that the rotation starts at a position between 0 to 360 degree when you want to rotate the axis in “+” direction or so that the rotation starts at a position between -360 to 0 degree when you want to rotate the axis in “-” direction.

When the axis is rotated in “+” direction from a position between -360 to 0 degree or when the axis is rotated in “-” direction from a position between 0 to 360 degree, the rotation angle and the reset rotation angle differs one rotation.

Therefore, note that the endless axis rotates one rotation when it is moved to the position before rotation or around it.

<Example>

When the rotation angle is reset after it is rotated 4 rotations in “+” direction from the position at -120 degree:



1.3 Job Example

The examples of making jogs are as follows.

Line	Instruction	Contents
0000	NOP	
0001	MOVJ VJ=25.00	Normal move instruction
0002	MOVL V=500.0	Normal move instruction
0003	MOVJ VJ=25.00	Normal move instruction
0004	MOVJ VJ=25.00 MT=100	T-axis rotates 100 times until reaching the step 4.
0005	MOVJ VJ=25.00 MT=100	T-axis rotates 100 times until reaching the step 5. (If endless rotation method is set for absolute motion, it does not rotate.)
0006	MRESET	MRESET instruction is executed to reset T-axis position to a position within one revolution.
0007	MOVL V=500.0	Linear interpolation motion
0008	MOVJ VJ=25.00	Normal move instruction
0009	END	End of the job

2 Instructions for T-Axis Endless Function

2.1 Tag to Specify T-Axis Rotation Angle (MT=)

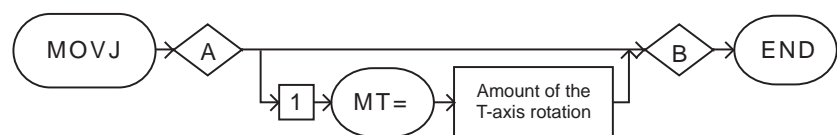
2.1.1 Function

The endless rotation action of T-axis rotation angle is performed when the specified move command is executed.

It is set as an additional item to the move instruction.

- MOVJ

2.1.2 Construction



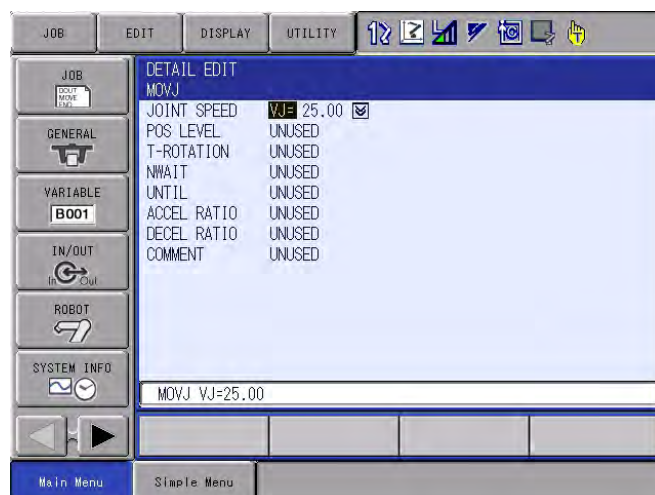
* Two or more tags can be set in portions $\diamond A$ and $\diamond B$, though the description is omitted here.

2.1.3 Explanation

No	Tag	Explanation	Note
1	MT= Amount of T-axis rotation	Specifies the amount of T-axis rotation. The operation of T-axis can be specified by the number of rotations.	Amount of rotation:-32768 to 32767 Can be added or omitted.

2.1.4 Setting of MT

1. Move the cursor to the instruction area.
2. Select the move command to which the MT tag is to be added.
 - The detailed edit window appears.



3. Set T-axis rotation angle.

- (1) Move the cursor to “T-axis rotation angle” and press “Select”.



- (2) Move the cursor to “MT=” and press “Select”.



- (3) Move the cursor to the right, press “Select”, enter the value using the numeric keys, and press “Enter”.



4. Press [ENTER] key two times.

- The set contents are registered in the job.

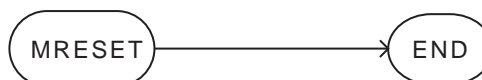


2.2 MRESET Instruction

2.2.1 Function

MRESET instruction is used to reset the endless axis position to a position within one revolution.

2.2.2 Construction



2.2.3 Registration of MRESET Instruction

Register MRESET instruction to reset the rotating amount in the following manner.

1. Move the cursor to the address area.
2. Press [INFORM LIST] key.



3. Select "MRESET".

- (1) Move the cursor to {OTHER} and press [Select] key.



-
- (2) Move the cursor to {MRESET} and press [Select] key.
 4. Press [ENTER] key.
 5. The set contents are registered in the job.

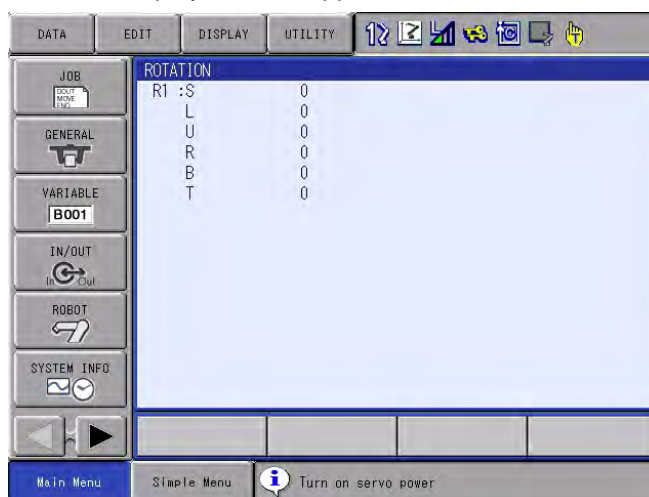
3 Display of Rotation Amount

The rotation angle of the endless axis will be displayed.

The rotation angle of the endless axis can also be reset.

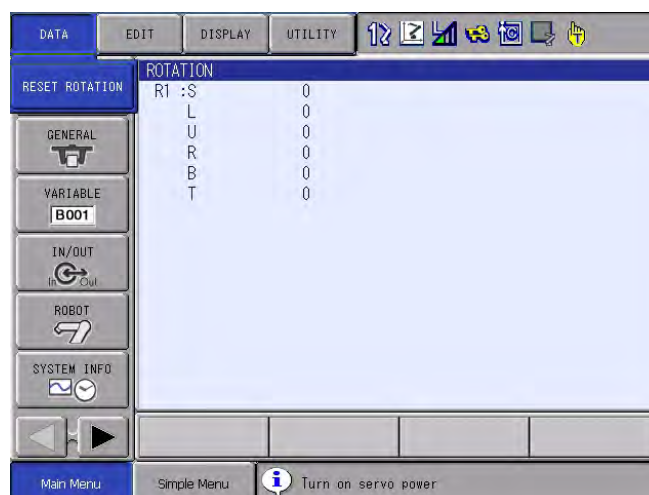
3.1 Display of the Rotation Angle Window

1. Select {ROBOT} under the main menu.
2. Select "ROTATION".
 - The rotation display window appears.



3.2 Resetting the Axis Rotation Amount

1. Select {ROBOT} under the main menu.
2. Select "ROTATION".
3. Select {DATA} of the menu.
 - A pull-down menu appears.



4. Select {RESET ROTATION}
 - The external rotation amount is reset to "0".

4 Restrictions

The restrictions for T-axis endless function are as follows.

4.1 FWD and BACK Operations

During FWD and BACK operations, T-axis does not perform a continuous rotation motion.

Also when a playback is executed after having executed the FWD operation till 1 to 3 steps before the step where the endless operation is specified, T-axis does not perform a continuous rotation motion. This is because the status of FWD operation and BACK operation remains.

In this case, after having executed the FWD and BACK operation, move the cursor and start the job in play mode. Thus, T-axis performs a continuous rotation motion.

Normally, when the manipulator's current value coincides with the reference position value after having reached the target step by FWD or BACK operation, the cursor stops blinking. In FWD or BACK operation after T-axis continuous rotation by using playback operation, T-axis does not have the manipulator current position coincident with the reference position even after having reached the target position. Therefore, the cursor does not stop blinking. In this case, execute MRESET instruction before FWD or BACK operation so that the cursor stops blinking when the manipulator reaches the target position.

4.2 When NWAIT is Specified

Normally, when a move instruction where NWAIT is added is executed, the instructions that are registered before the next move instruction, are executed sequentially. However, for MRESET instruction, NWAIT specification is not applied and MRESET instruction is executed after completion of the move instruction.

4.3 Maximum Endless Rotating Amount

The maximum endless rotating amount can be obtained by the following equation. The amount differs depending on the endless axis resolution.

Maximum endless rotating amount = ± 536870911 (pulse) / Resolution (pulse/revolution)

4.4 Execution of MRESET Instruction

Since the execution of MRESET instruction is processed for the manipulator feedback pulse, it is executed in the status that the manipulator is completely stopped.

Accordingly, it takes a several seconds to execute MRESET instruction.

In the meantime, the manipulator does not stop and the start lamp is not unlit even by hold or changing mode operation.

4.5 T-Axis Position at Teaching

In a position where T-axis has rotated more than one time, the teaching is disabled. If teaching is executed in this state, the following error occurs.

Error 2110 : Over softlimit

When the above error occurs, reset the axis rotating amount manually.

4.6 Display of Rotating Amount

When the sign of the taught position of the MOVJ instruction where a rotating amount is specified and the sign of the rotating amount specification are different, the display value of rotating amount may be one revolution less than the specified rotating amount.

For example, when the taught position is at -1000 pulses and the rotating amount is specified to be 100 revolutions, the displayed value of rotating amount is 99 revolutions.

5 Alarm Message List

Alarm No.	Message		Cause	
4490	DEFECTIVE TAUGHT POINT (ENDLESS)	1	One of the interpolation instructions (MOVL, MOVC, etc.) is executed after the endless rotation is completed and before MRESET is executed.	(1)Confirm the settings below. · Execute MRESET if you want to perform one of the interpolation actions (MOVL, MOVC, etc.) after the endless rotation.
		4	The pulse number of the endless axis exceeds the max. pulse value (± 536870911).	(1)Confirm the settings below. · Set the rotation angle so that the pulse value does not exceed the max. pulse number.

DX200 OPTIONS INSTRUCTIONS

FOR T-AXIS ENDLESS FUNCTION

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