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

MOTOMAN INSTRUCTIONS
MOTOMAN-□□□ INSTRUCTIONS
DX200 INSTRUCTIONS
DX200 OPERATOR’S MANUAL (for each purpose)
DX200 MAINTENANCE MANUAL

The DX200 operator’s manual above corresponds to specific usage. Be sure to use the appropriate manual.
### MANDATORY

- This manual explains the macro command 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”.

**DANGER**

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

**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:

- **NOTE**
  
  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 pressing the emergency stop buttons on the front door of the DX200 and the programming pendant. 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:
  – Be sure to use a lockout device to the safeguarding when going inside. Also, display the sign that the operation is being performed inside the safeguarding and make sure no one closes the safeguarding.
  – 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 power for the DX200.
  – 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.
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:

<table>
<thead>
<tr>
<th>Equipment</th>
<th>Manual Designation</th>
</tr>
</thead>
<tbody>
<tr>
<td>DX200 controller</td>
<td>DX200</td>
</tr>
<tr>
<td>DX200 programming pendant</td>
<td>Programming pendant</td>
</tr>
<tr>
<td>Cable between the manipulator and DX200</td>
<td>Manipulator Cable</td>
</tr>
</tbody>
</table>

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

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

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, or that the item is directly selected by touching the screen.

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 ™ are omitted.
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      2.2.1 GETARG Instruction ........................................................................................................ 2-3
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1 Outline

The macro command function registers a prepared job as a macro command and then carries out the job by the macro command.

With the macro command function, system integrators who apply various MOTOMAN robot systems can freely create INFORM (a robot programming language used in DX200) that corresponds to each system.

The macro command function enables an easier robot system with use of the key customize function. (Refer to section 8.15 “Numeric Key Customize Function” in the “DX200 INSTRUCTIONS” for details.)

1.1 Features

• A job prepared with the macro command function by user is registered as a macro command.

• The contents of macro command can be prepared with INFORM, which is the same manner as the normal job data.

• An argument tag can be added to a macro command like a normal instruction. Macro commands and their argument tags can be easily programmed at will in the job data display.

< Example > Macro command for sealing

SEALON WIDTH=8

Argument tag to specify the sealing width

Macro command to start sealing

• The macro commands can be used in the same way as the other instructions. Unlike the CALL instruction, end users do not have to consider the restarting method in case of a job interruption.

• The macro command function enables settings for post-processing of the job interruption, such as the cancellation of current work instruction, etc.

• If a macro command is interrupted during the execution, the interrupted macro command is re-executed from the beginning when the operation is restarted.

• The macro command function is enabled only when the security mode is in the management mode.

• The character strings and the character type variable of the argument for macro command are available for DN1.60-00 and later versions.
2 Preparation of Macro Commands

The execution sequence of a macro command is registered as a macro job.

### 2.1 Preparing a Macro Job

Depending on the applications, there are three types of macro jobs as follows:

- **Robot macro job with a designated control group**
  A move instruction can be registered in a macro command. A macro command prepared as a robot macro job can be used only in the jobs configured for the same control groups. For example, the macro command prepared as a robot macro job for R1 cannot be used in a job for R2.

- **Robot macro job without a control group**
  Can be used for all robot jobs. Since the control group is not designated, no move instruction can be registered.

- **Concurrent macro job**
  Can be used in a concurrent job. Since the control group is not designated, no move instruction can be registered.

1. Select “Management Mode” for the security mode.
2. Select {JOB} from the top menu.
3. Select {NEW JOB CREATE}.
4. Enter the job name.

**NOTE**
The macro command function is enabled only when the security mode is in the management mode.
5. Point the cursor to "JOB TYPE", and press [SELECT].
   – A selection list appears.

   - Select "ROBOT MACRO" or "CONCURRENT MACRO".

   - A macro job is prepared, and the JOB CONTENT window appears.

6. Select “EXECUTE”.
   – A macro job is prepared, and the JOB CONTENT window appears.
2.2 Teaching a Macro Job

Teach a macro job which is prepared as a macro command in the same manner as normal jobs.

A maximum of sixteen argument tags can be added to a macro command. Since the data of the argument tag is stored in a local variable to be used, the required number of local variables must be set in a “JOB HEADER” before teaching the macro job.

**NOTE**

In a macro job, job execution instructions such as JUMP, CALL, and PSTART cannot be registered.

### 2.2.1 GETARG Instruction

**2.2.1.1 Function**

The GETARG instruction is an instruction to receive an argument for macro command. When a macro command is executed, the GETARG instruction gets the data of the argument tag which is added to the macro command, and stores it in a local variable to be used in the macro job.

**2.2.1.2 Format**

\[ \text{GETARG \ LB000 IARG#(1)} \]

Stores the data of the first argument in the local variable LB000.

① Designation of the local variable as the storage destination of the argument data.

The following types of local variables can be used for storage destination:

- Byte-type
- Integer-type
- Double-precision integer type
- Real-number type
- Character type
- Robot-axis-position type
- Base-axis-position type
- Station-axis-position type

② Designation of argument data.

Specifies the number of the argument data to be taken.

For the setting procedure of the local variables, refer to section 3.9.11 “Editing Local Variables” described in the “DX200 OPERATOR'S MANUAL”.

**SUPPLEMENT**

In a macro job, job execution instructions such as JUMP, CALL, and PSTART cannot be registered.
2.2.1.3 Job Example

Robot Job

- NOP
- MOVJ VJ=100.00
- WAIT IN#(1)=ON
- MOVJ VJ=50.00
- SEALON WIDTH=8
- MOVL V=125
- MOVL V=95

Macro Job: SEALON

- NOP
- GETARG LI000 IARG#(1)
- DOUT OT#(10) ON
- MUL LI000 10
- WAIT IN#(10)=ON
- AOUT AO#(1) LI000
- END

Stores the first argument data "8" in the local variable LI000.

Outputs the analog voltage according to the first argument data.
3 Registration of Macro Commands

To register the macro job prepared in section 2.1 “Preparing a Macro Job” on page 2-1 as a macro command, display the MACRO (ROBOT) window or MACRO (CONCURRENT) window following the procedure below.

The macro command function is enabled only when the security mode is in the management mode.

1. Select “Management Mode” for the security mode.
2. Select {SETUP} from the top menu.
3. Select {MACRO INST.}.
   - The macro command setting window appears.
   - Press [PAGE] to alternately display the MACRO (ROBOT) window and the MACRO (CONCURRENT) window.
3.1 Setting an Execution Macro Job

The execution macro jobs are macro jobs in which the operations to be carried out by a macro command are programmed. Note that the JOB CONTENT window of a macro command displays the names of the jobs which are specified as execution macro jobs.

1. Point the cursor to the “EXECUTE JOB” to be set in the macro command setting display, and press [SELECT].
   - A list box appears.

2. Select “SETTING MACRO JOB”.
   - The MACRO JOB NAME window appears.
3. Select the desired macro job.
   
   – The selected macro job is registered as an execution macro job.

Even if the macro job registration is canceled, the argument setting of the macro command still remains. Confirm the content of the argument setting of the macro command before registering the macro job to the same macro number which is already canceled.
3.2 Setting the Contents of Argument Tag Added to the Macro Command

Set the contents of argument tag to be added to the registered macro command.

This setting is not necessary for the macro command with no argument.

1. Point the cursor to the macro number to which the argument is to be set.

2. Press [SELECT].

(Continued on the next page.)

- The macro ARGUMENT DEFINITION window appears. There are two windows to define the macro argument. Press [PAGE] to switch the windows.

① Argument number (ARG. 1 to 16)

Point the cursor to the desired argument number, and press [SELECT]. Select “USE” or “NOT USE” from the list box. For the unused argument numbers, the window displays “------”.
3.2 Setting the Contents of Argument Tag Added to the Macro Command

① **COMMENT 1 (Up to 16 characters)**
Point the cursor to COMMENT 1 and press [SELECT]. A character input window appears.
Enter the contents of the argument tag added to the macro command in the “COMMENT 1” column. These contents are displayed as the comment for the argument tag in the detail editing window of the macro command.

② **TYPE**
Point the cursor to TYPE and press [SELECT]. A dropdown list appears.
Select the data type of the argument tag. The following types of data are available for the setting:

- <Constants or variables>
  - Byte-type
  - Integer-type
  - Double-precision integer type
  - Real-number type
  - Character type
- <Variables or teaching points>
  - Robot-axis-position type
  - Base-axis-position type
  - Station-axis-position type

③ **COMMENT 2 (Up to 8 characters)**
Point the cursor to COMMENT 2 and press [SELECT]. A character input window appears.
Enter the unit for inputting data in the argument tag to be added to the macro command in “COMMENT 2”. The units are displayed as the comment for the argument tag data input units in the detail editing window of the macro command.
3.2 Setting the Contents of Argument Tag Added to the Macro Command

３ DISPLAY
Select whether to display the expression in the EXPRES’N column. Pressing [SELECT] displays “ON” and “OFF” alternately: “ON” displays the expression; “OFF” hides the expression. When the teaching point for the robot position, base position, or station position is set in “TYPE”, the screen does not display the tag set for the teaching point even if “ON” is selected.

６ EXPRES’N (Up to 8 characters)
Point the cursor to EXPRES’N and press [SELECT]. The character input box appears. Enter the expression for the argument tag.

3. Perform the settings for each item.
3.3 Setting an Interruption Macro Job

If a post-processing is required when a macro command is interrupted, add an interruption macro job (SUSPEND JOB) to the program.

The interruption macro job is carried out when a macro command that includes an interruption macro job (SUSPEND JOB) is interrupted by being put on a status such as hold, emergency stop, or mode switching.

**NOTE**

Only a robot job without a designated control group can be added to the interruption macro job of the robot macro command.

1. Point the cursor to the “SUSPEND JOB” column of the macro job for which an interruption macro job is to be added, and press [SELECT].
   - A list box appears.

2. Select “SETTING MACRO JOB”.
   - The MACRO JOB NAME window appears.
3. Select the desired macro job.
   - The selected macro job is registered as the interruption macro job.

If the following infinite loop is programmed in the interruption macro job, the start lamp stays lit but no operation is carried out. Do not add such a job to the program. Also note that the TIMER and WAIT instructions are not carried out in the interruption macro job.

**JOB example**

```
NOP
*LOOP
DOUT OT#(1) OFF
AOUT AO#(1) 10.00
JUMP *LOOP IF IN#(1)=ON
END
```
Specifications are subject to change without notice
for ongoing product modifications and improvements.