YRC1000 OPTIONS INSTRUCTIONS
FOR MACRO COMMAND FUNCTION

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

MOTOMAN INSTRUCTIONS

MOTOMAN-□□□□ INSTRUCTIONS
YRC1000 INSTRUCTIONS
YRC1000 OPERATOR’S MANUAL (GENERAL) (SUBJECT SPECIFIC)
YRC1000 MAINTENANCE MANUAL
YRC1000 ALARM CODES (MAJOR ALARMS) (MINOR ALARMS)

The YRC1000 operator’s manual above corresponds to specific usage. Be sure to use the appropriate manual. The YRC1000 operator’s manual above consists of “GENERAL” and “SUBJECT SPECIFIC”. The YRC1000 alarm codes above consists of “MAJOR ALARMS” and “MINOR ALARMS”.

Please have the following information available when contacting Yaskawa Customer Support:

- System
- Primary Application
- Software Version (Located on Programming Pendant by selecting: [Main Menu] - [System Info] - {Version})
- Robot Serial Number (Located on robot data plate)
- Robot Sales Order Number (Located on controller data plate)

Part Number: 178673-1CD
Revision: 0
DANGER

• This manual explains the macro command function of the YRC1000 system. Read this manual carefully and be sure to understand its contents before handling the YRC1000. Any matter not described in this manual must be regarded as "prohibited" or "improper".

• General information related to safety are described in “Chapter 1. Safety” of the YRC1000 INSTRUCTIONS. To ensure correct and safe operation, carefully read “Chapter 1. Safety” of the YRC1000 INSTRUCTIONS.

CAUTION

• In some drawings in this manual, the protective covers or shields are removed to show details. Make sure to install all the covers and shields in place before operating this product.

• YASKAWA is not responsible for incidents arising from unauthorized modification of its products. Unauthorized modification voids the product warranty.

NOTICE

• 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.
Notes for Safe Operation

Read this manual carefully before installation, operation, maintenance, or inspection of the YRC1000.

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

**DANGER**
Indicates an imminently hazardous situation which, if not avoided, will result in death or serious injury. Safety Signs identified by the signal word DANGER should be used sparingly and only for those situations presenting the most serious hazards.

**WARNING**
Indicates a potentially hazardous situation which, if not avoided, will result in death or serious injury. Hazards identified by the signal word WARNING present a lesser degree of risk of injury or death than those identified by the signal word DANGER.

**CAUTION**
Indicates a hazardous situation, which if not avoided, could result in minor or moderate injury. It may also be used without the safety alert symbol as an alternative to “NOTICE”.

**NOTICE**
NOTICE is the preferred signal word to address practices not related to personal injury. The safety alert symbol should not be used with this signal word. As an alternative to “NOTICE”, the word “CAUTION” without the safety alert symbol may be used to indicate a message not related to personal injury.

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 “DANGER”, “WARNING” and “CAUTION”.
DANGER

Before operating the manipulator, make sure the servo power is turned OFF by performing the following operations. When the servo power is turned OFF, the SERVO ON LED on the programming pendant is turned OFF.

- Press the emergency stop buttons on the front door of the YRC1000, on the programming pendant, on the external control device, etc.
- Disconnect the safety plug of the safety fence.
  (when in the play mode or in the remote mode).

If operation of the manipulator cannot be stopped in an emergency, personal injury and/or equipment damage may result.

Fig. : Emergency Stop Button

Before releasing the emergency stop, make sure to remove the obstacle or error caused the emergency stop, if any, and then turn the servo power ON.

Failure to observe this instruction may cause unintended movement of the manipulator, which may result in personal injury.

Fig. : Release of Emergency Stop

Observe the following precautions when performing a teaching operation within the manipulator's operating range:

- Be sure to perform lockout by putting a lockout device on the safety fence when going into the area enclosed by the safety fence. In addition, the operator of the teaching operation must display the sign that the operation is being performed so that no other person closes the safety fence.
- View the manipulator from the front whenever possible.
- Always follow the predetermined operating procedure.
- Always keep in mind emergency response measures against the manipulator's unexpected movement toward a person.
- Ensure a safe place to retreat in case of emergency.

Failure to observe this instruction may cause improper or unintended movement of the manipulator, which may result in personal injury.

Confirm that no person is present in the manipulator's operating range and that the operator is in a safe location before:

- Turning ON the YRC1000 power
- Moving the manipulator by using the programming pendant
- Running the system in the check mode
- Performing automatic operations

Personal injury may result if a person enters the manipulator's operating range during operation. Immediately press an emergency stop button whenever there is a problem. The emergency stop buttons are located on the front panel of the YRC1000 and on the right of the programming pendant.

Read and understand the Explanations of the Warning Labels 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 manipulator 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>YRC1000 Controller</td>
<td>YRC1000</td>
</tr>
<tr>
<td>YRC1000 Programming Pendant</td>
<td>Programming Pendant</td>
</tr>
<tr>
<td>Cable between the manipulator and the controller</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 [.].</td>
</tr>
<tr>
<td></td>
<td>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</td>
</tr>
<tr>
<td></td>
<td>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</td>
</tr>
<tr>
<td></td>
<td>“+” 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>

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 [SELECT] 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 TM are omitted.
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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 YRC1000) that corresponds to each system.

The macro command function enables an easier robot system with use of the key customize function. (Refer to "8.15 Numeric Key Customize Function" in "YRC1000 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 reexecuted from the beginning when the operation is restarted.

**NOTE**

- The macro command function is enabled only when the security mode is in the management mode.
2 Preparation of Macro Commands

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

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

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.

4. Enter the job name.
5. Point the cursor to "JOB TYPE", and press [SELECT].
   – A selection list appears.
   – Select "ROBOT MACRO" or "CONCURRENT MACRO".

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.

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

GETARG LB000 IARG#(1)  
\[1\] 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.

NOTE

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

SUPPLEMENT

For the setting procedure of the local variables, refer to "3.9.5 Editing Local Variables" described in "YRC1000 OPERATOR'S MANUAL".

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 chapter 2.1 “Preparing a Macro Job” as a macro command, display the MACRO (ROBOT) window or MACRO (CONCURRENT) window following the procedure below.

NOTE
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.

### NOTE
Even if the macro job registration is cancelled, 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 cancelled.
3 Registration of Macro Commands

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 Registration of Macro Commands

3.2 Setting the Contents of Argument Tag Added to the Macro Command

② 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.

③ 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

④ 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 Registration of Macro Commands
3.2 Setting the Contents of Argument Tag Added to the Macro Command

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.

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 putting 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.

NOTE
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
YRC1000 OPTIONS
INSTRUCTIONS
FOR MACRO COMMAND FUNCTION

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Specifications are subject to change without notice for ongoing product modifications and improvements.

YASKAWA

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