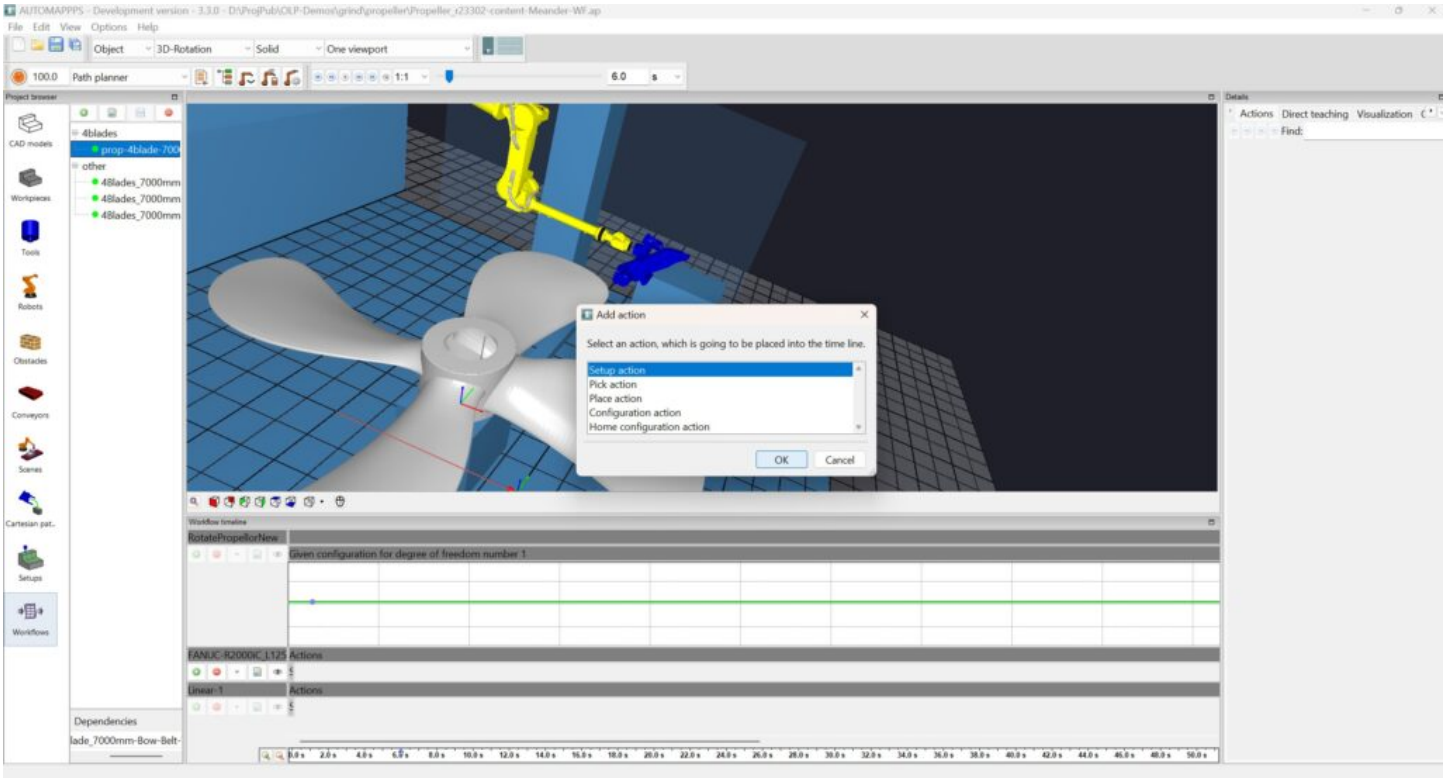
Assign actions to robots

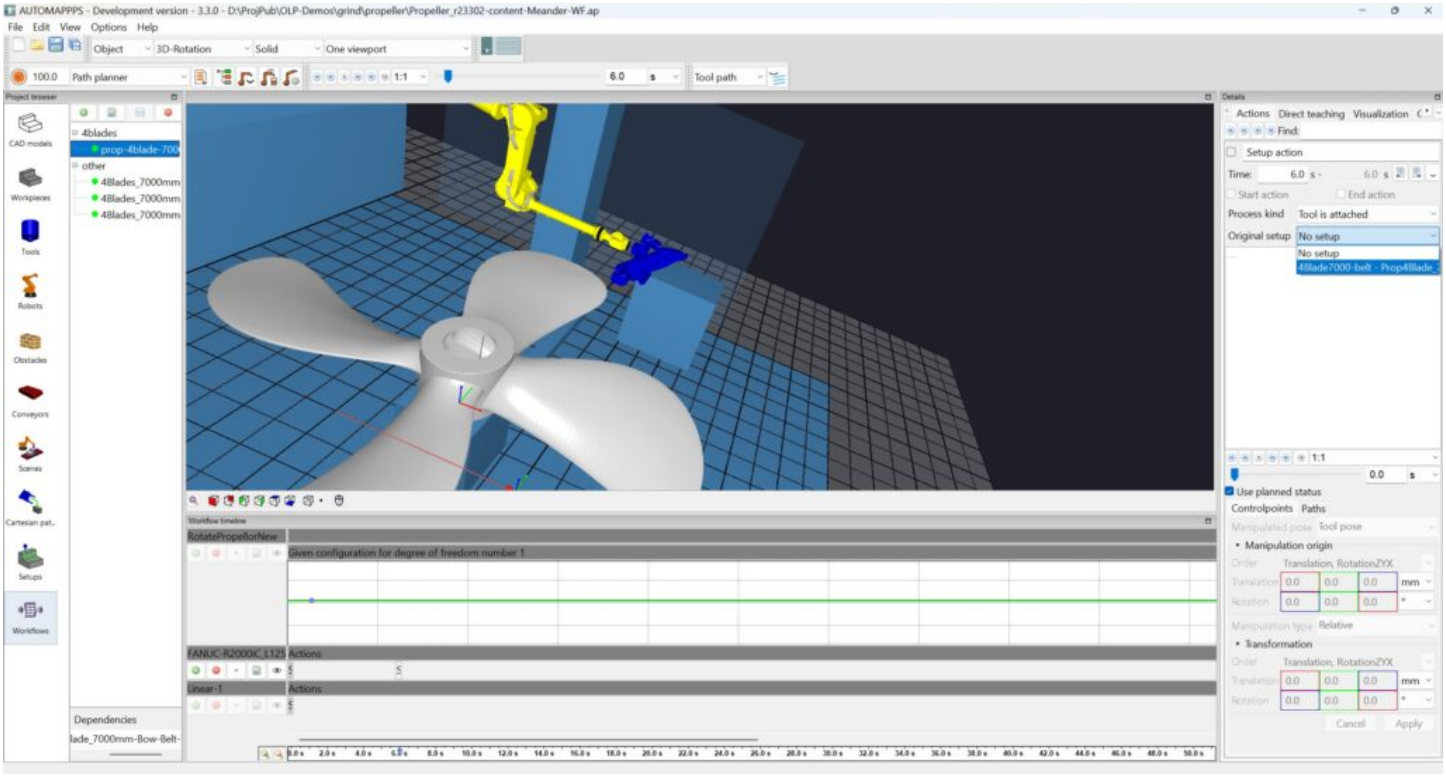
Robot motions & programming - Robot Offline Programming · https://convergent-it.com/tutorial/robot-motions-and-programming/assign-actions-to-robots/

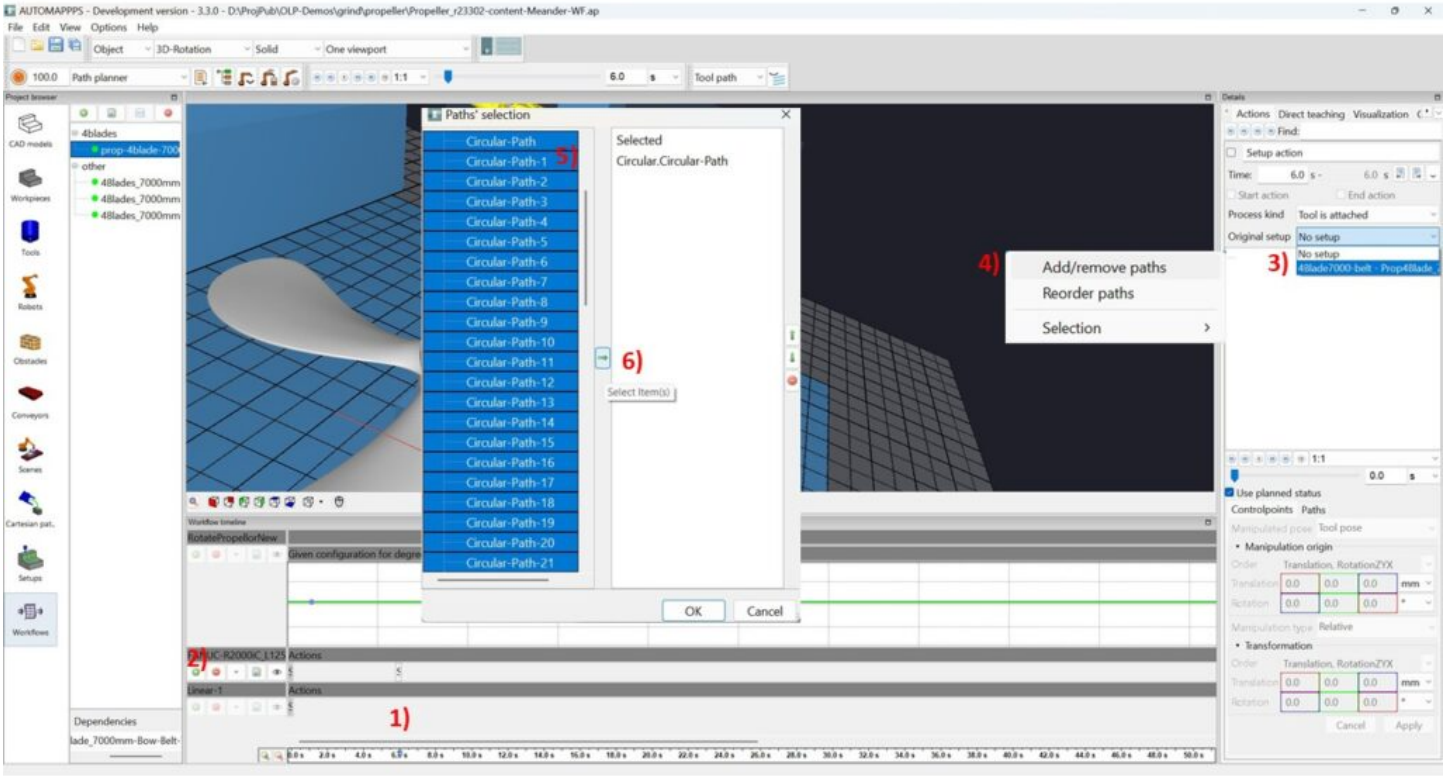
The video describes (in 2 different examples with 1 and 2 robots and external axes) how to assign one or several tool paths (including meanders etc.), which has been created in the setup, to a robot in a workflow. This specifies (initally) which robots are executing which tool-paths at which time. Assignment, order and timing can be changed later easily.

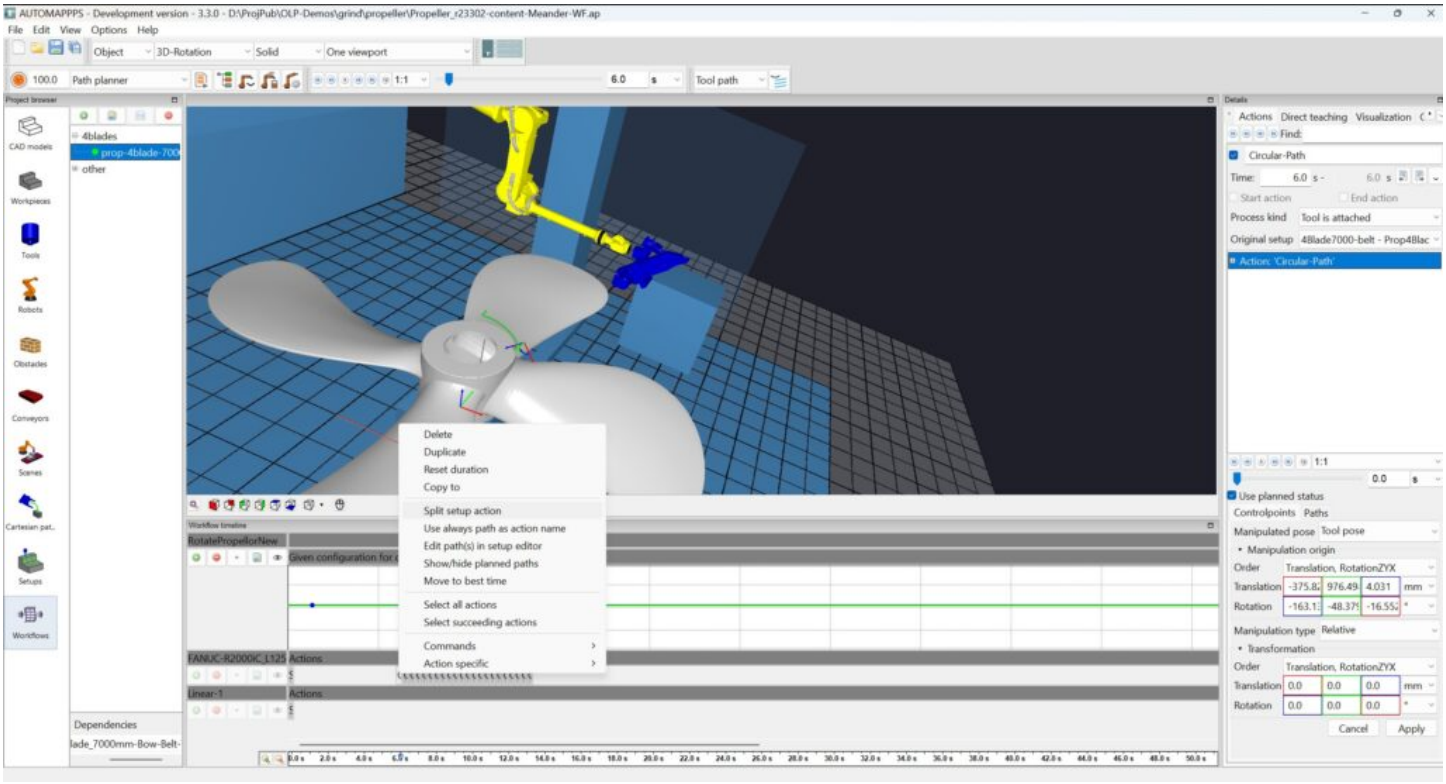
The video is embedded by YouTube and only loaded and played from there when you click on the play button. From then on, the privacy policy of Google applies.

Add and select actions






Paths' selection
Circular-Path
Circular-Path-1
Circular-Path-2
Circular-Path-3
Circular-Path-4
Circular-Path-5
Circular-Path-6
Circular-Path-7
Circular-Path-8
Circular-Path-9
Circular-Path-10
Circular-Path-11
Circular-Path-12
Circular-Path-13
Circular-Path-14
Circular-Path-15
Circular-Path-16
Circular-Path-17
Circular-Path-18
Circular-Path-19
Circular-Path-20
Circular-Path-21
Selected
Circular.Circular-Path
OK
Cancel
Add/remove paths
Reorder paths
Selection
1)
2)
3)
4)
5)
6)


AUTOMAPPPS - Development version - 3.3.0 - D:\ProjPub\OLP-Demos\grind\propeller\Propeller_r23302-content-Meander-WF.ap
File Edit View Options Help
Object
3D-Rotation
Solid
One viewport
Path planner
Tool path
Project browser
CAD models
Workpieces
Tools
Robots
Obstacles
Conveyors
Scenes
Cartesian pat..
Setups
Workflows
4blades
prop-4blade-700
other
Dependencies
lade_7000mm-Bow-Belt-
Delete
Duplicate
Reset duration
Copy to
Split setup action
Use always path as action name
Edit path(s) in setup editor
Show/hide planned paths
Move to best time
Select all actions
Select succeeding actions
Commands
Action specific
RotatePropellorNew
Given configuration for
FANUC-R2000iC_125
Actions
Linear-1
Actions
Details
Actions Direct teaching Visualization
Find:
Circular-Path
Time: 6.0 s - 6.0 s
Start action End action
Process kind Tool is attached
Original setup 48lade7000-belt - Prop4Blac
Action: 'Circular-Path'
Use planned status
Controlpoints Paths
Manipulated pose Tool pose
Manipulation origin
Order Translation, RotationZYX
Translation -375.8 976.49 4.031 mm
Rotation -163.1 -48.37 -16.55
Manipulation type Relative
Transformation
Order Translation, RotationZYX
Translation 0.0 0.0 0.0 mm
Rotation 0.0 0.0 0.0
Cancel
Apply