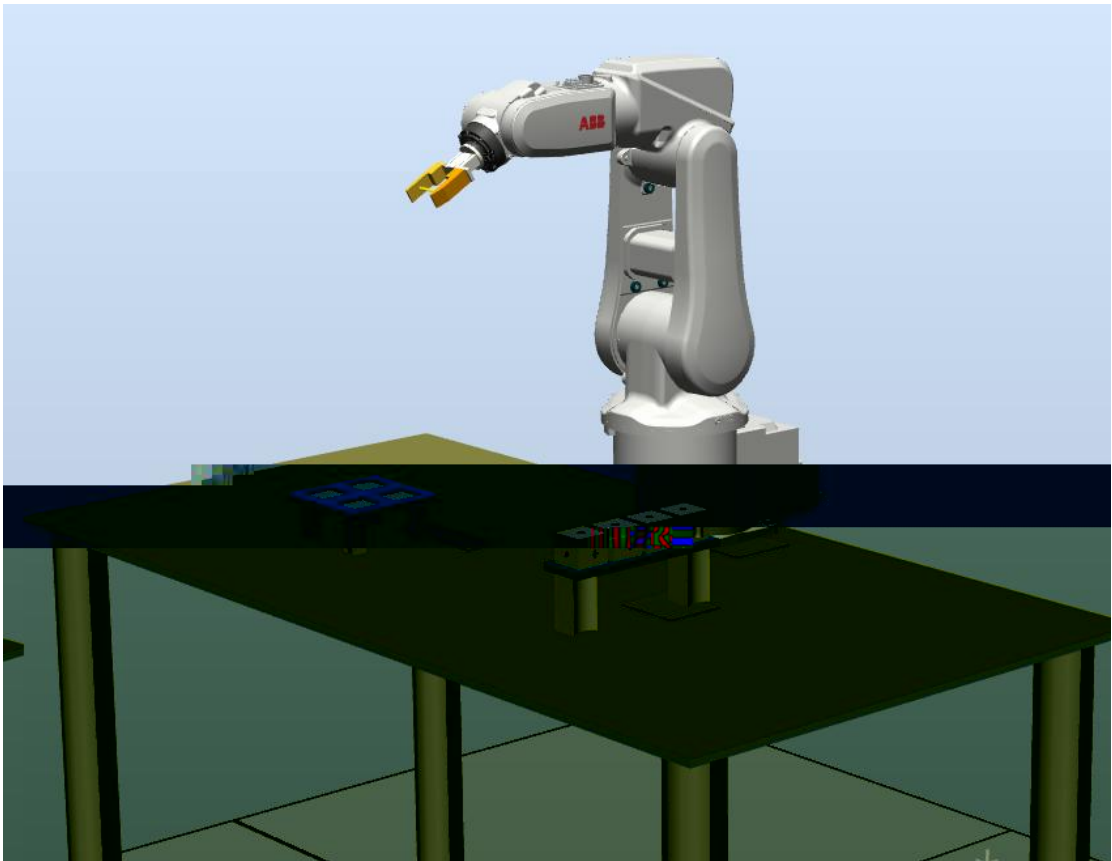
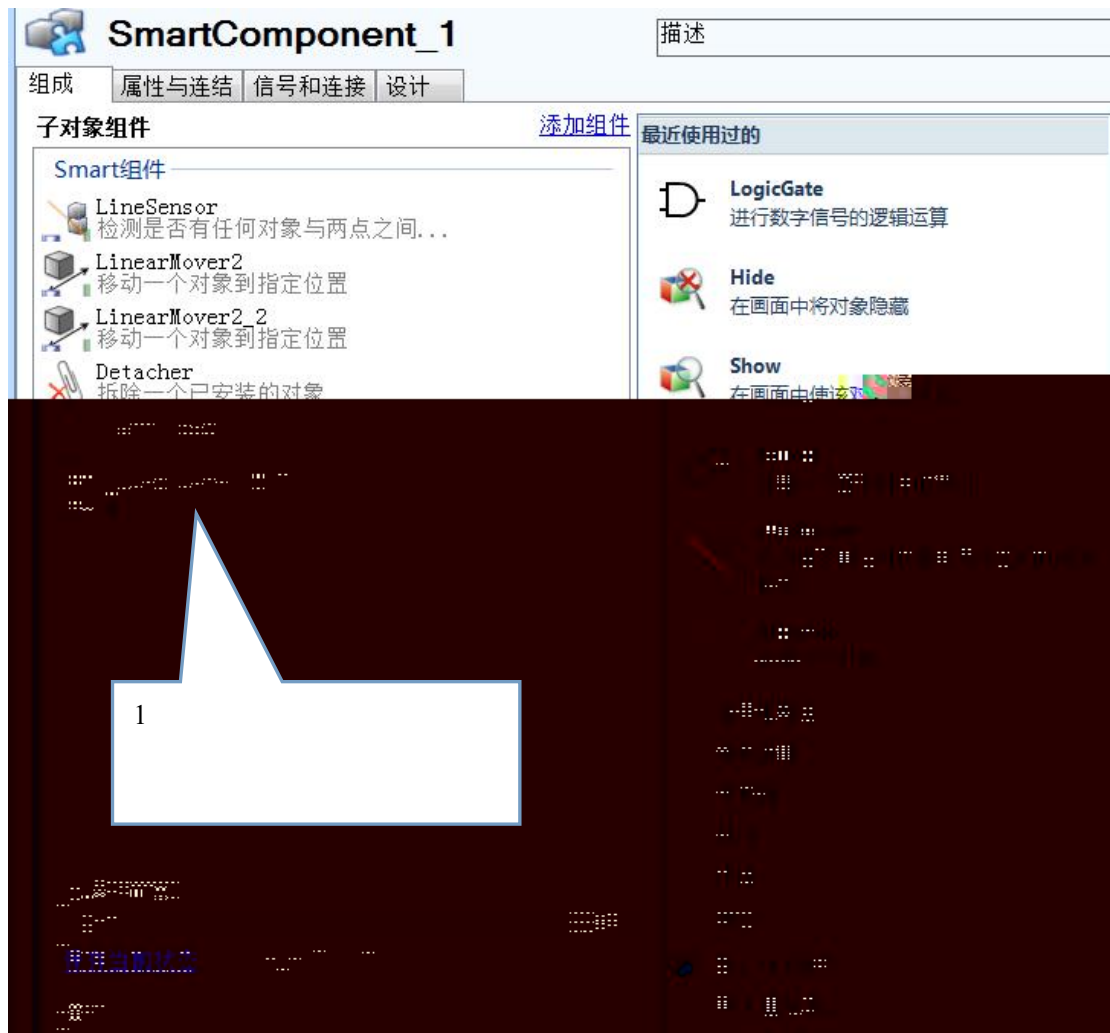


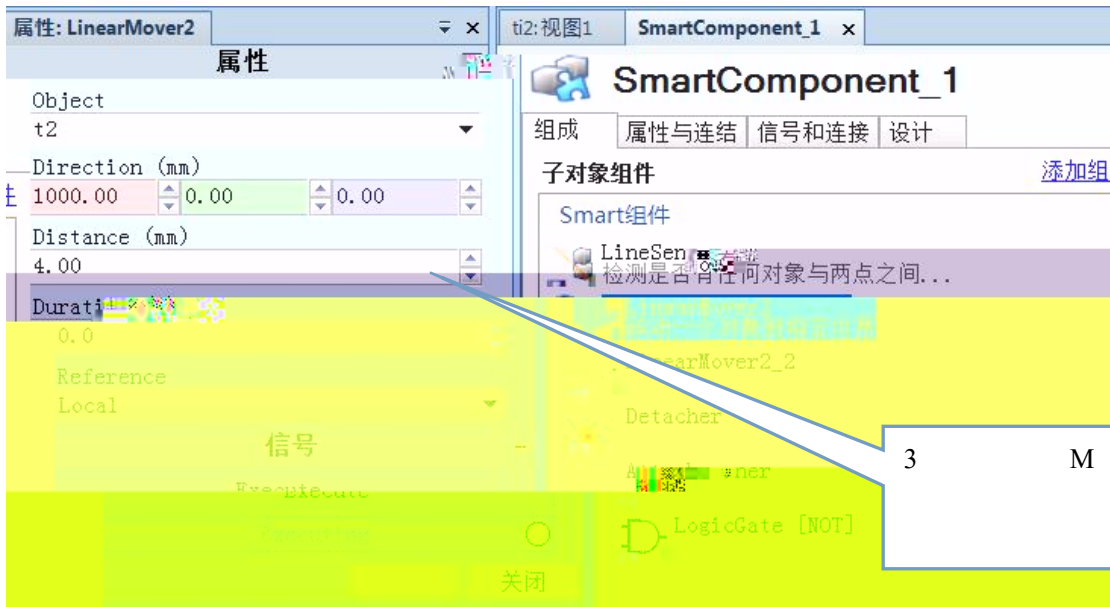
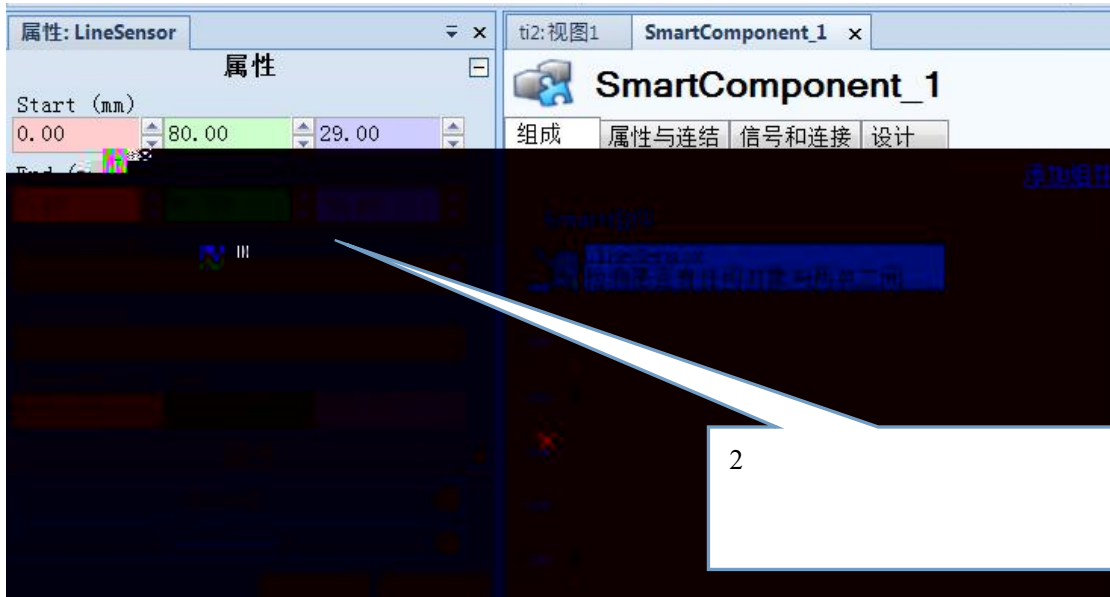
- 1 ROBOTSTUDIO
- 2 IO
- 3 S a
- 4
- 5

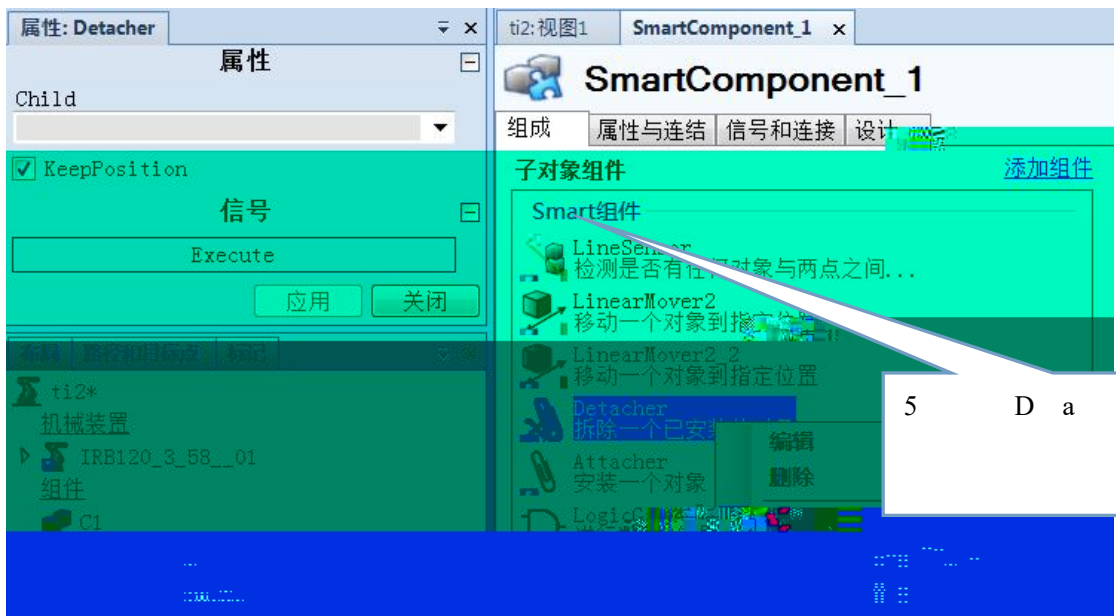
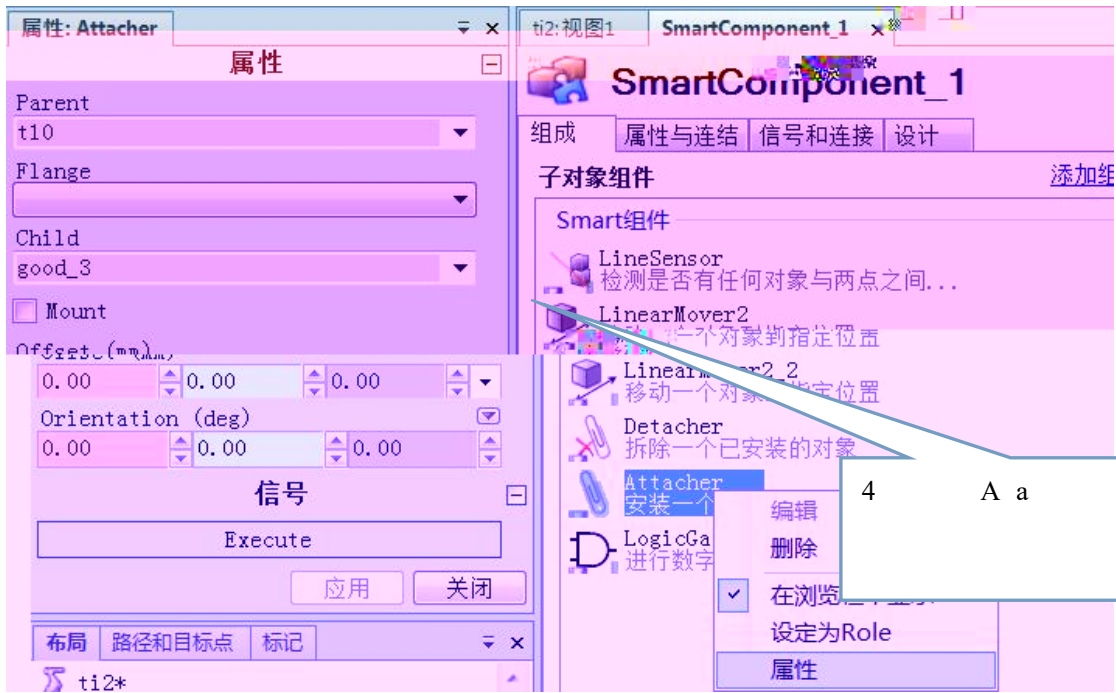


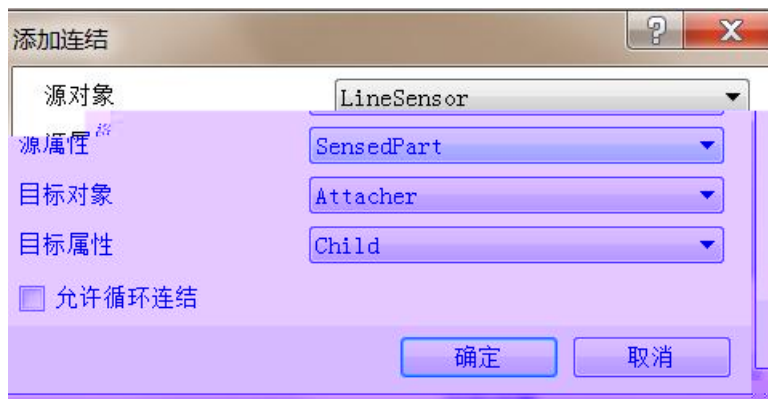
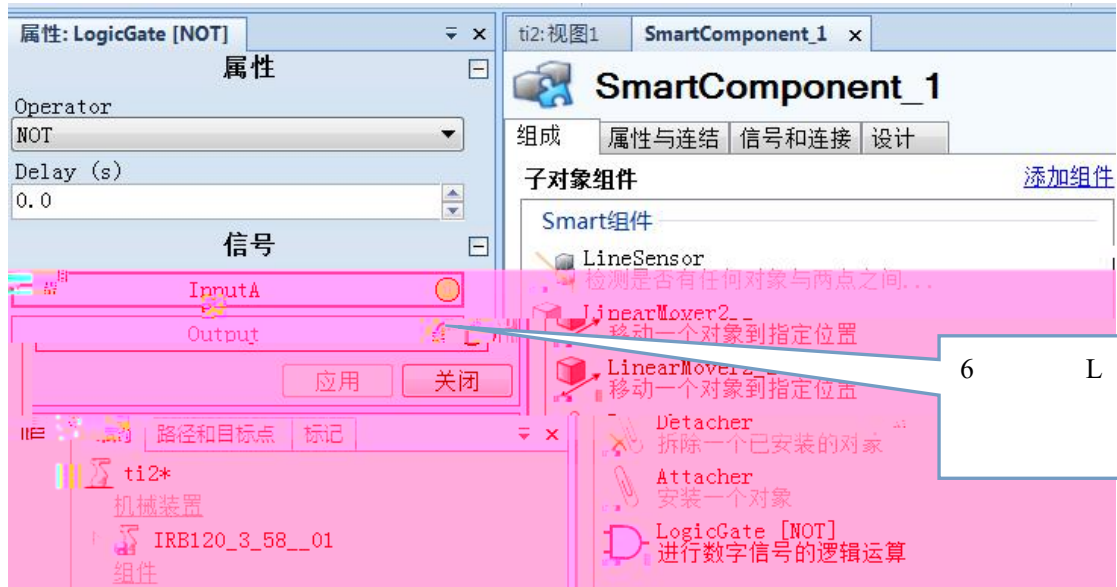
### Smart

a --- a ---

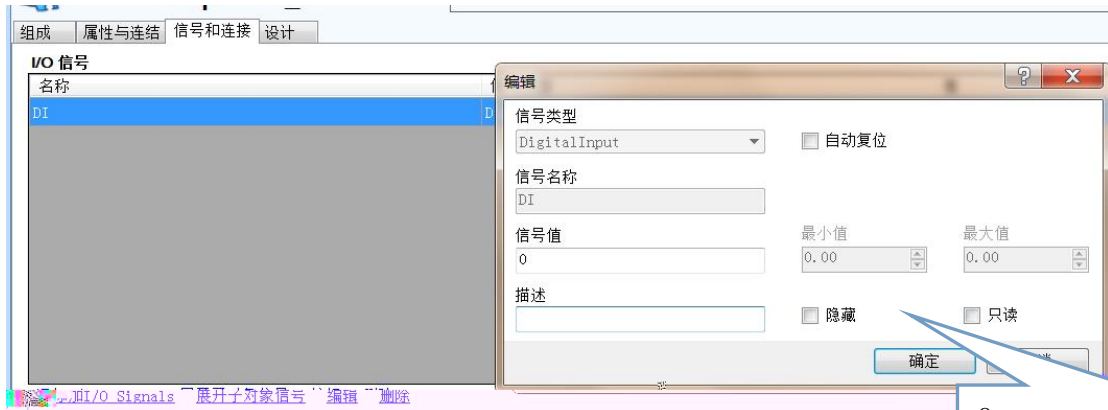








源对象	源属性	目标对象	目标属性
LineSensor	SensedPart	Attacher	Child
Attacher	Child	Detacher	Child



8 a



9

I/O连接

源对象	源信号	目标对象	目标对象
SmartComponent_1	DI	LineSensor	Active
LineSensor	SensorOut	Attacher	Execute
SmartComponent_1	DI	LinearMover2	Execute
SmartComponent_1	DI	LogicGate [NOT]	InputA
LogicGate [NOT]	Output	LinearMover2_2	Execute
LogicGate [NOT]	Output	Detacher	Execute

10

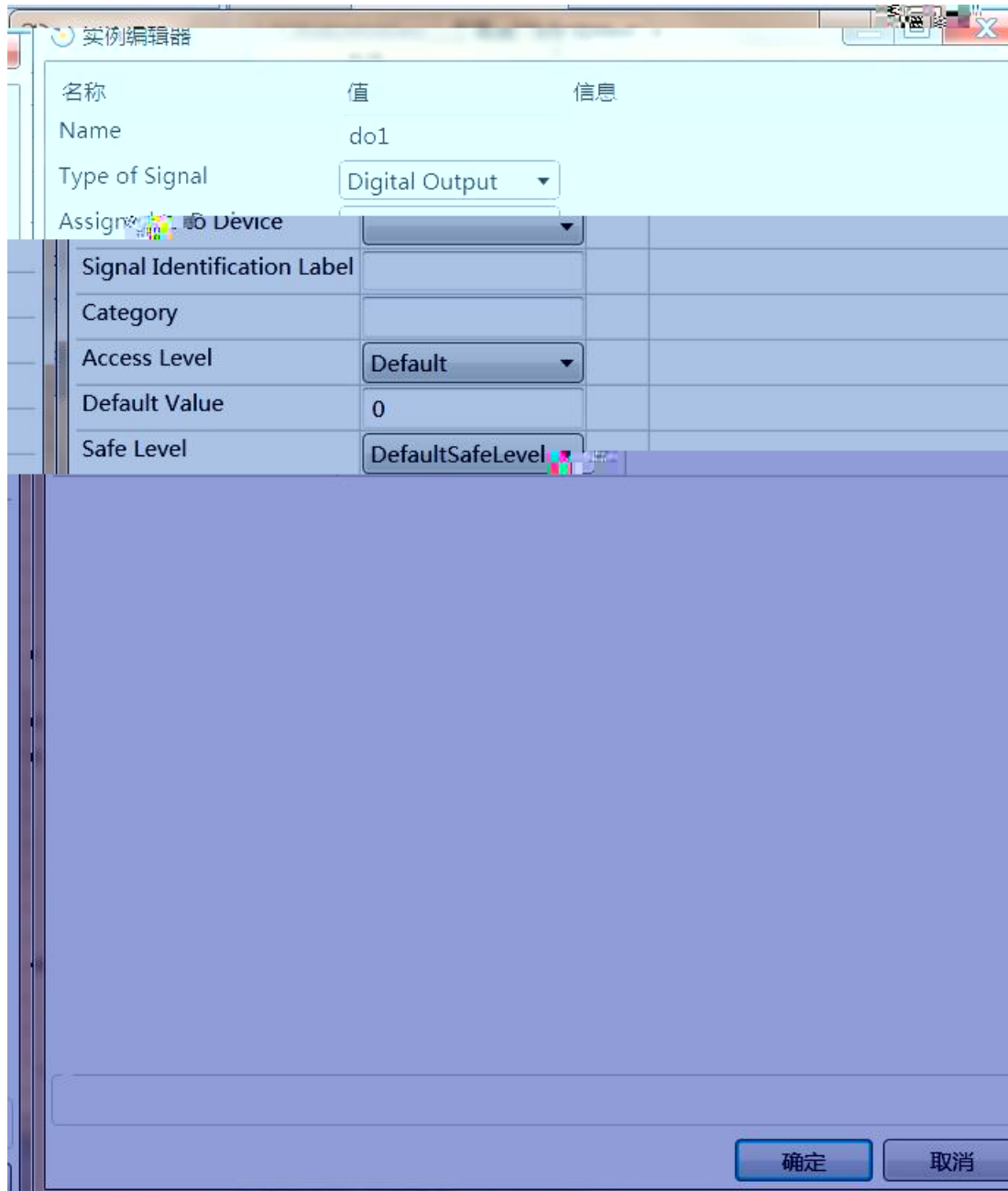
IO

/

IO

--- ---IO SYSTEM---SIGNAL

1



1



2

MoveJ \* v1000 z100 Tooldata\_1 \WObj=Workobject\_1 选择方式 捕捉模式 UCS : 工作站 0.00 0.00 0.00 控制器状态: 1/1

3

MODULE M 1

CONST a

Ta \_70:=[[-224.011205552,135.527108744,487.704338612],[0.353553313,-0.61237248,0.61237248,0.353553313],[-1,0,-1,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a

11:=[[37.869880471,44.814983349,115.908038328],[0.001652216,0.707104385,-0.707105313,0.00165409],[-1,-1,-1,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a

a1:=[[37.8700052,44.815136086,39.490813564],[0.001651816,0.70710452,-0.707105178,0.001654058],[-1,-1,-1,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a

11:=[[-489.951104876,140.965986471,162.762733411],[0.001652044,0.7071057,-0.707103996,0.001655228],[0,0,0,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a

1:=[[-489.951183238,140.966082149,59.407584776],[0.001651979,0.707105621,-0.707104075,0.00165472],[0,0,0,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a

a22:=[[37.869942427,116.557143713,155.39126366],[0.001651852,0.707104876,-0.707104822,0.001654266],[-1,-1,-1,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a

a2:=[[37.869940738,116.557190745,39.490847993],[0.001651699,0.707104729,-0.707104969,0.001654142],[-1,-1,-1,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a

22:=[[-489.951259604,80.653337944,156.122050005],[0.001652015,0.707105581,-0.707104116,0.001654666],[0,0,0,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a

2:=[[-489.951173225,80.653256714,59.407299329],[0.001651987,0.707105682,-0.707104014,0.001654959],[0,0,0,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a

a33:=[[115.738761397,44.409702788,133.350771359],[0.001651405,0.707105229,-0.707104447,0.001654215],[-1,-1,-1,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a

a3:=[[115.738591832,44.409570256,39.490752672],[0.00165187,0.707105066,-0.707104632,0.001654128],[-1,-1,-1,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a

33:=[[-489.951153989,20.789766822,176.305175859],[0.00165229,0.707105496,-0.707104197,0.001655658],[0,0,0,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a

3:=[[-489.951229613,20.789932408,59.407225593],[0.00165209,0.707105525,-0.70710417,0.001655202],[0,0,0,0],[9E9,9E9,9E9,9E9,9E9,9E9]];

CONST a



```
a44:=[[115.738762369,116.557191188,146.072597057],[0.00165153,0.707104774,
-0.707104925,0.001654045],[-1,-1,-1,0],[9E9,9E9,9E9,9E9,9E9,9E9]];
```

```
CONST a
```

```
a4:=[[115.738726819,116.557121339,39.490732226],[0.00165192,0.707104783,-0.
707104915,0.001654139],[-1,-1,-1,0],[9E9,9E9,9E9,9E9,9E9,9E9]];
```

```
CONST a
```

```
44:=[[ -489.951097873,-38.971314643,204.450846504],[0.001651847,0.707105696,
-0.707103999,0.001655135],[0,0,0,0],[9E9,9E9,9E9,9E9,9E9,9E9]];
```

```
CONST a
```

```
4:=[[ -489.951092308,-38.971402841,59.407056847],[0.00165204,0.707105435,-0.
70710426,0.001655285],[0,0,0,0],[9E9,9E9,9E9,9E9,9E9,9E9]];
```

```
PROC Pa _10()
```

```
ENDPROC
```

```
PROC Pa _20()
```

```
M J Ta _70, 1000, 100,T a a_1\WO :=W _1;
```

```
M J 11, 1000, 100,T a a_1\WO :=W _1;
```

```
M L a1, 1000, ,T a a_1\WO :=W _1;
```

```
S 1;
```

```
Wa T 0.3;
```

```
M J 11, 1000, 100,T a a_1\WO :=W _1;
```

```
M J 11, 1000, 100,T a a_1\WO :=W _1;
```

```
M L 1, 1000, ,T a a_1\WO :=W _1;
```

```
R 1;
```

```
Wa T 0.3;
```

```
M J 11, 1000, 100,T a a_1\WO :=W _1;
```

```
M J a22, 1000, 100,T a a_1\WO :=W _1;
```

```
M L a2, 1000, ,T a a_1\WO :=W _1;
```

```
S 1;
```

```
Wa T 0.3;
```

```
M J a22, 1000, 100,T a a_1\WO :=W _1;
```

```
M J 22, 1000, 100,T a a_1\WO :=W _1;
```

```
M L 2, 1000, ,T a a_1\WO :=W _1;
```

```
R 1;
```

```
Wa T 0.3;
```

```
M J 22, 1000, 100,T a a_1\WO :=W _1;
```

```
M J a33, 1000, 100,T a a_1\WO :=W _1;
```

```
M L a3, 1000, ,T a a_1\WO :=W _1;
```

```
S 1;
```

```
Wa T 0.3;
```

```
M J a33, 1000, 100,T a a_1\WO :=W _1;
```

```
M J 33, 1000, 100,T a a_1\WO :=W _1;
```

```
M L 3, 1000, ,T a a_1\WO :=W _1;
```

```
R 1;
```

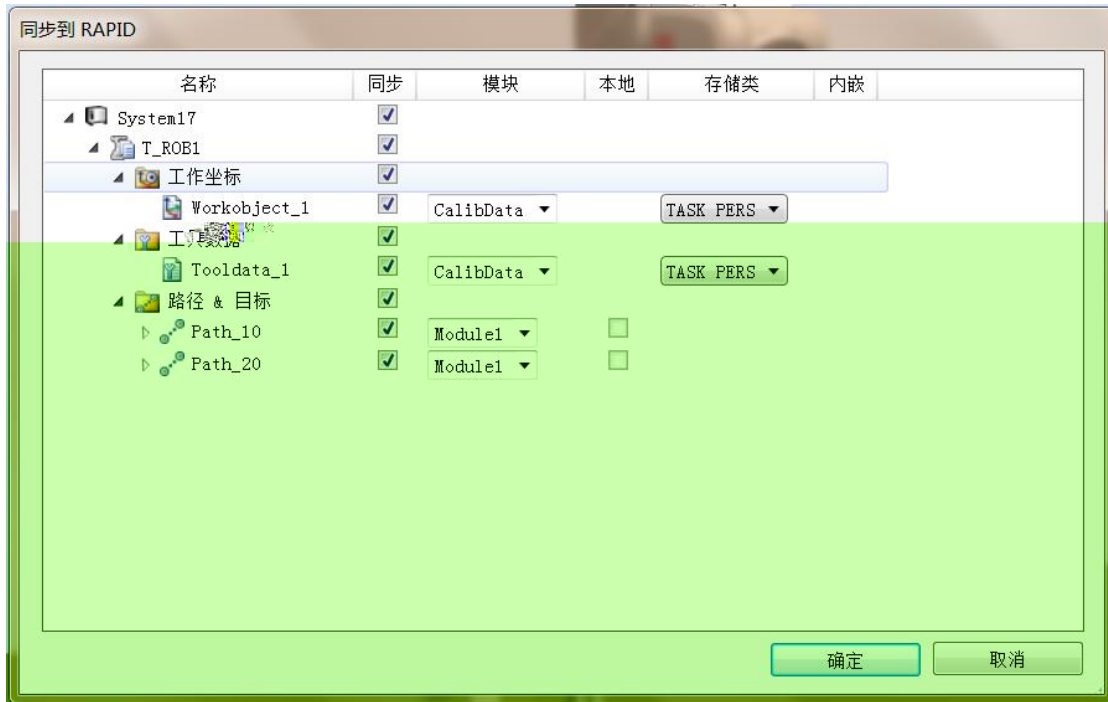
```

Wa T 0.3;
M J 33, 1000, 100,T a a_1\WO :=W _1;
M J a44, 1000, 100,T a a_1\WO :=W _1;
M L a4, 1000, ,T a a_1\WO :=W _1;
S 1;
Wa T 0.3;
M J a44, 1000, 100,T a a_1\WO :=W _1;
M J 44, 1000, 100,T a a_1\WO :=W _1;
M L 4, 1000, ,T a a_1\WO :=W _1;
R 1;
Wa T 0.3;
M J 44, 1000, 100,T a a_1\WO :=W _1;
M J Ta _70, 1000, 100,T a a_1\WO :=W _1;

```

ENDPROC  
ENDMODULE

RAPID --- --- RAPID



1 RAPID PATH20 ---  
--- PATH20

活动仿真场景: (SimulationConfiguration) - ti 添加... 删除 重命名

场景设置

初始状态: 1 [管理状态](#)

仿真对象:

物体	仿真
ti2	
Controllers	
System17	<input checked="" type="checkbox"/>
T_ROB1	<input checked="" type="checkbox"/>
Smart Components	
SmartComponent_1	<input checked="" type="checkbox"/>

System17 的设置

当仿真开始时自动开

运行模式

单个周期

连续

初始状态:

**State Name:** 1  
**Description:**  
**Date:** 2015/11/6 0:49:20

**Controller States**

**System17:**

**Variable values:**

/RAPID/T\_  
/RAPID/T\_  
/RAPID/T\_  
/RAPID/T\_  
/RAPID/T\_  
/RAPID/T\_  
**I/O Signal values**  
do1 = 1

2