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| | Updated by: Anders Jahnberg | | Approved by: Göran Holmqvist | Version 2.0 |
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| Software Support, Industrial Software Products | | Type of doc: Trouble Shooting Guideline (TSG) | | |

TSG_RS 37 : How to create a coordinated Workobject on a positioner

Product: RobotStudio

Version: 4.0

Problem: How do I create a coordinated workobject on a positioner?

Solution: This guideline aims to show how to create a coordinated workobject on a positioner (see below)

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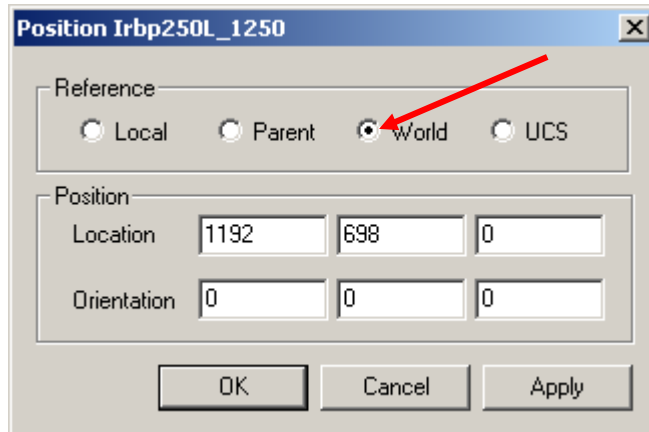
1. Create a station with a robot and a positioner

Please follow the example below:

1. Start RobotStudio.
2. Import a robot.
On the **File** menu select **Import** then click **Library**, select **c:\program files\abb robotics\library\robots\IRB2400L_M98A-M2000.rlb** and click **Open**
3. Import a welding tool.
On the **File** menu select **Import** then click **Library**, select **c:\program files\abb robotics\library\tools\AW_Gun_PKI_500_22.rlb** and click **Open**

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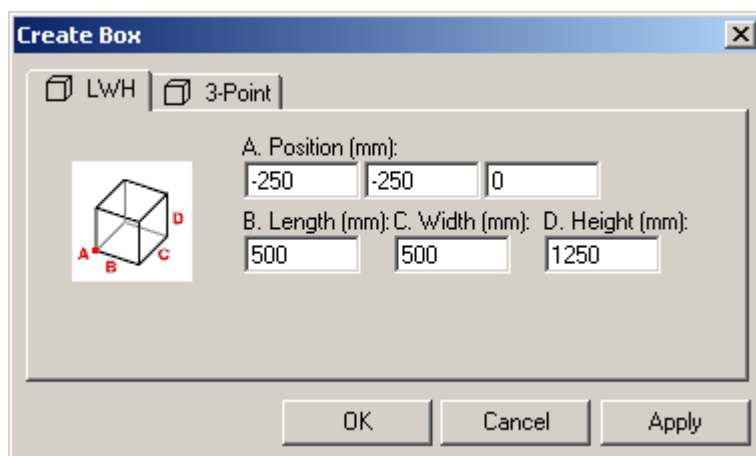
4. Attach the tool to the robot.
In the **Object browser** select the tool **AWGunPKI500_22** and drag it to the robot **IRB2400L_xxxx**, answer **YES** to the question “Do you also want to reposition AWWGunPKI500_22?”
5. Import a positioner.
On the **File** menu select **Import** then click **Library**, select **c:\program files\abb robotics\library\Positioners\IRBP250L_1250.rlb** and click **Open**
6. Modify the position of the positioner.
In the **Object browser** right click on the positioner **irbp250L_1250**, point to **Modify** in the context menu and click on **Position**
7. Input the new position.
In the **Reference** group select the radio button **World** and input the values **1192**, **698** and **0** for **Location** then input the values **0**, **0** and **0** for **Orientation** (see picture below)



8. Click **OK**

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9. Create a box.
On the **Create** menu select **3D Components** then click **Box**, input the values **-250**, **-250** and **0** for **Position** then input the values **500** for **Length**, **500** for **With** and **1250** for **Height** (see picture below)

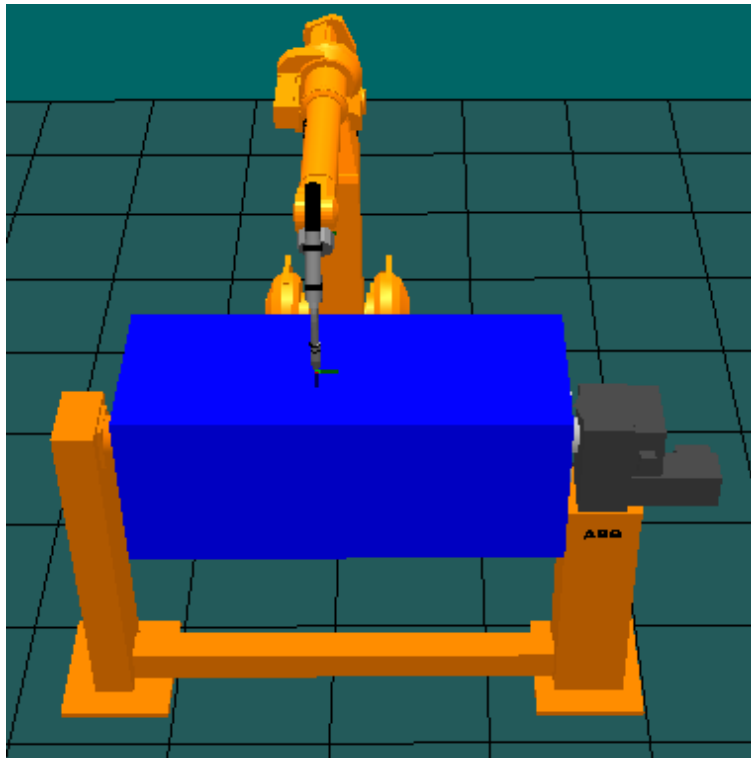


10. Rename Part1 to Box1.
Click **OK**, in the **Object browser** right click on the Part **Part1** and select **Rename** in the context menu, input the name **Box1** and press **Enter**
11. Attach the box to the positioner.
In the **Object browser** select the box **Box1** and drag it to the positioner **irbp250L_1250**, answer **YES** to the question "Do you also want to reposition Box1?"

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12. Save the station.

On the **File** menu select **Save As**, input the name **Coordinated_workobject** and click **Save** (below you can see how the station is supposed to look)

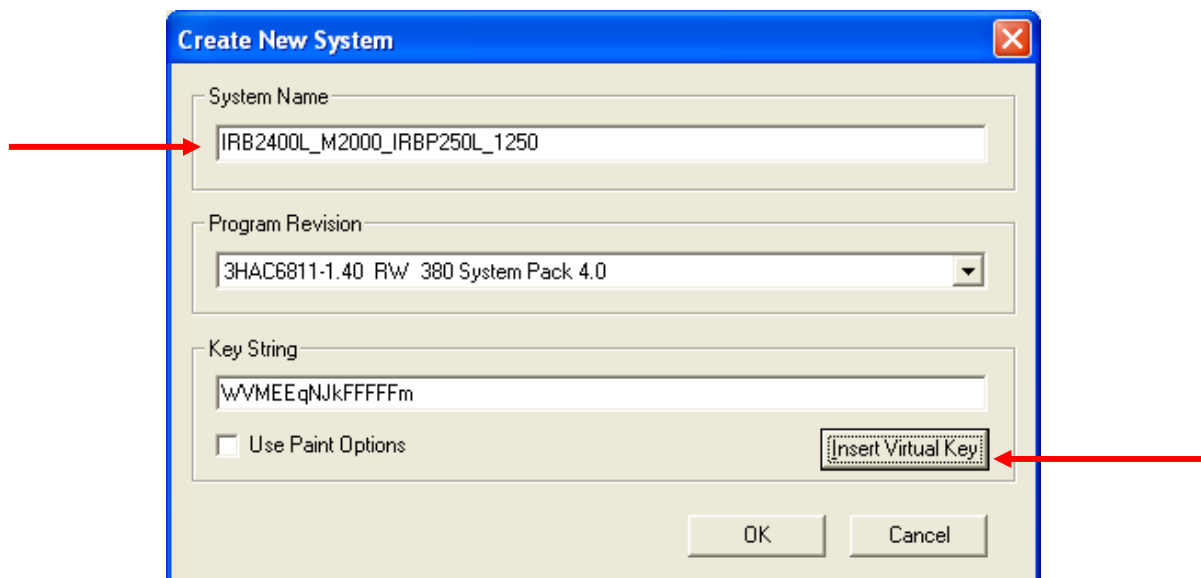


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2. Create and setup a controller with a positioner

Please follow the example below:

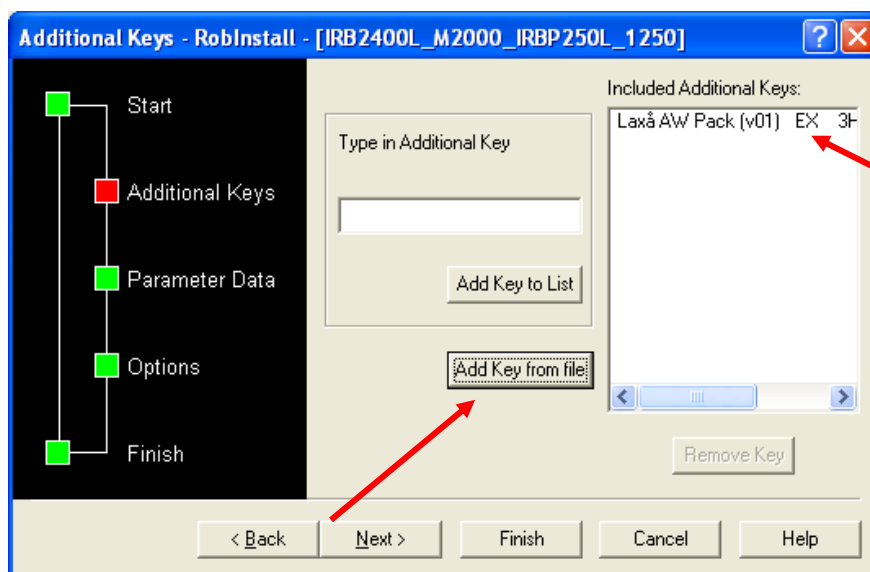
1. Create a new controller.
In the **Object** browser right click on the robot **IRB2400L_xxxx** and select **Setup Controller** in the context menu, click **Change Controller** and the Virtual Robot Browser will be displayed, click **Create**, input the name **IRB2400L_M2000_IRBP250L_1250** and click **Insert Virtual Key** (see picture below)



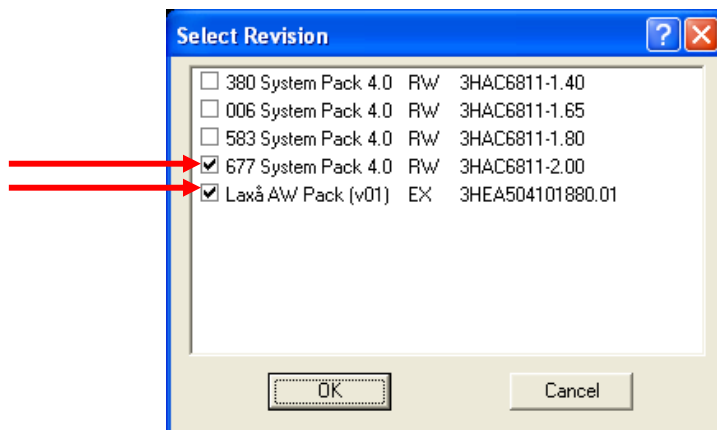
2. Start RobInstall.
Click **OK**

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3. Insert Additional Key.
Click **Next** and click **Add Key from file**, select **c:\program files\common files\abb automation\mediapool\3HEA504101880.01\virtual.kxt** and click **Open** (see picture below)

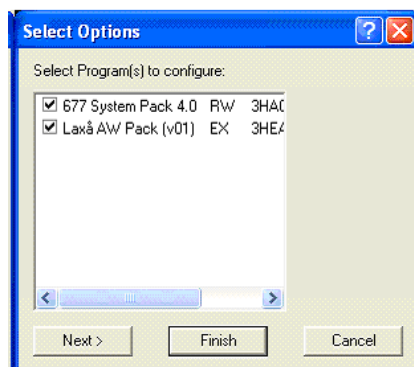


4. Select Program Revision.
Click **Next** and click **Next**, uncheck the box **Use latest Program Revision** and click on **Rev. Select**, **if you are using RobotStudio 3.0** then check the box **583 System Pack 4.0 RW 3HAC6811-1.80** and the box **Laxå AW Pack (v01) EX 3HEA504101880.01**, **if you are using RobotStudio 3.1** then check the box **677 System Pack 4.0 RW 3HAC6811-2.00** and the box **Laxå AW Pack (v01) EX 3HEA504101880.01** (see picture below)

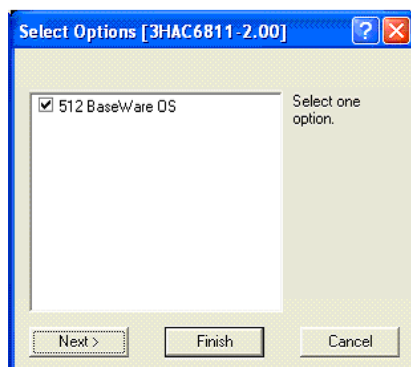


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5. Select options.
Click **OK** and click **Options**, select options according to step 4 (see picture below)



6. Click **Next** and select options according to the picture below

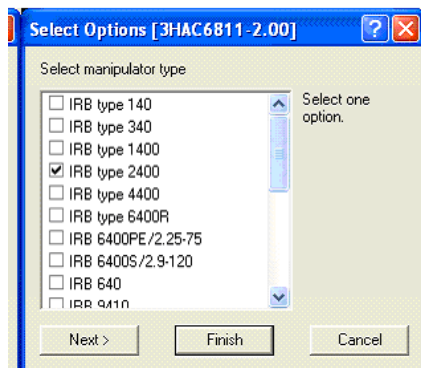


7. Click **Next** and select options according to the picture below

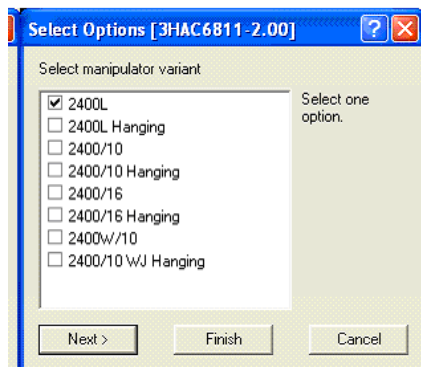


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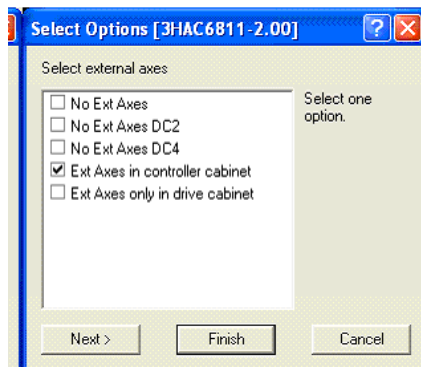
8. Click **Next** and select options according to the picture below



9. Click **Next** and select options according to the picture below

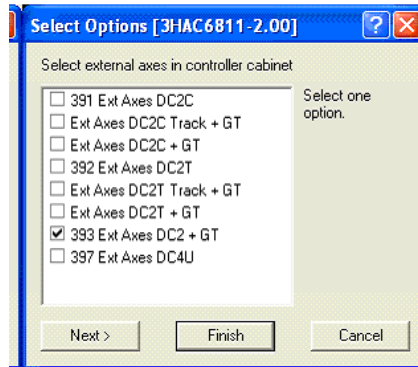


10. Click **Next** and select options according to the picture below

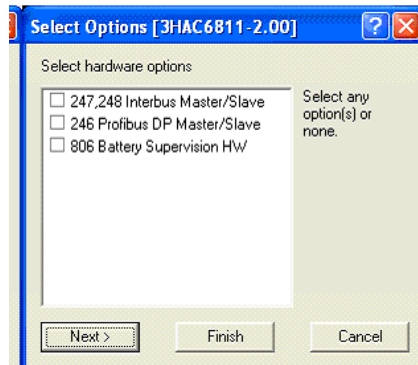


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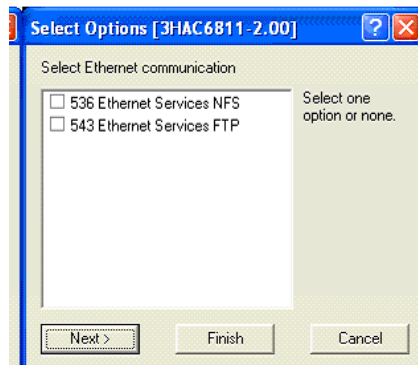
11. Click **Next** and select options according to the picture below



12. Click **Next** and select options according to the picture below

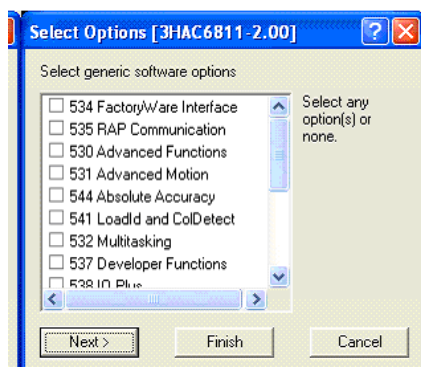


13. Click **Next** and select options according to the picture below

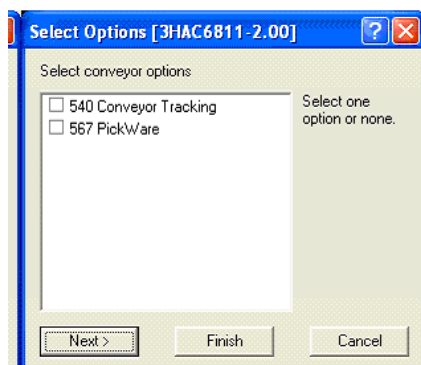


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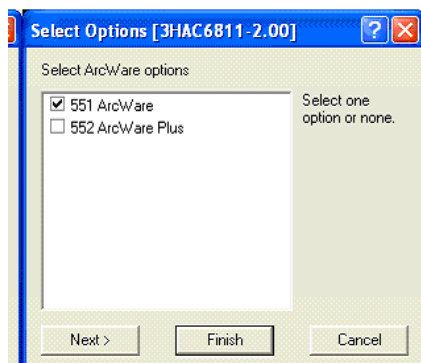
14. Click **Next** and select options according to the picture below



15. Click **Next** and select options according to the picture below

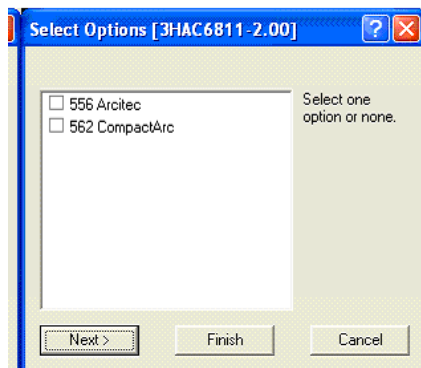


16. Click **Next** and select options according to the picture below

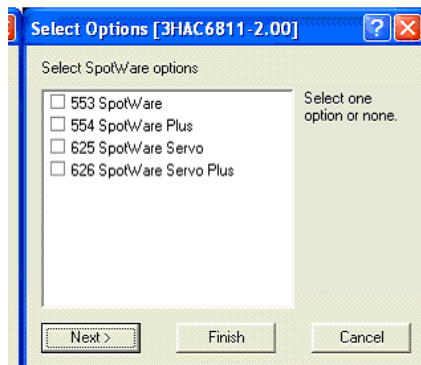


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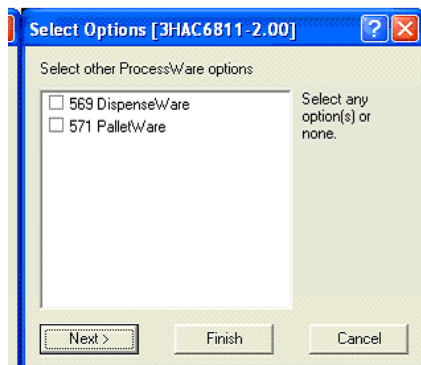
17. Click **Next** and select options according to the picture below



18. Click **Next** and select options according to the picture below

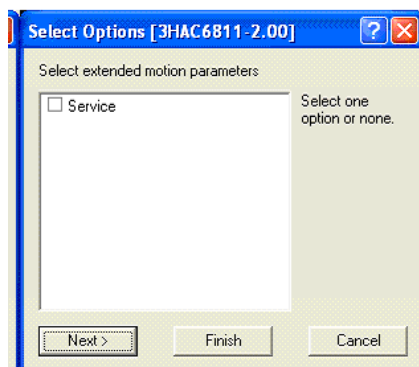


19. Click **Next** and select options according to the picture below

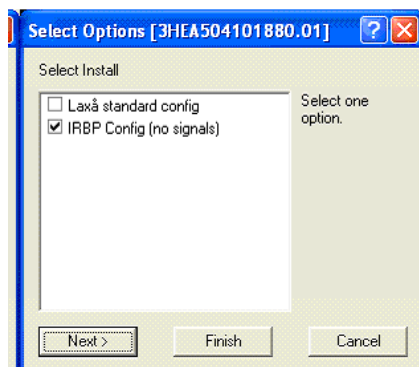


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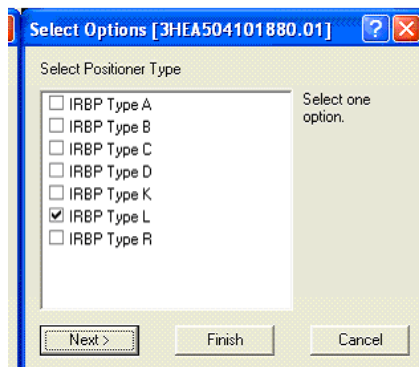
20. Click **Next** and select options according to the picture below



21. Click **Next** and select options according to the picture below

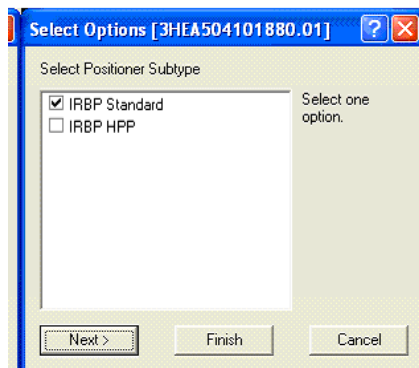


22. Click **Next** and select options according to the picture below

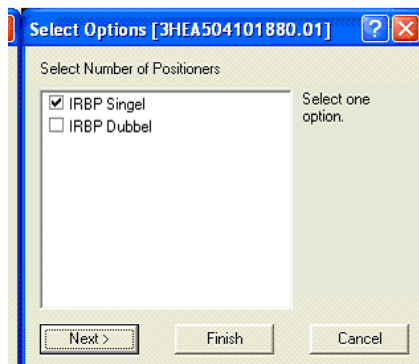


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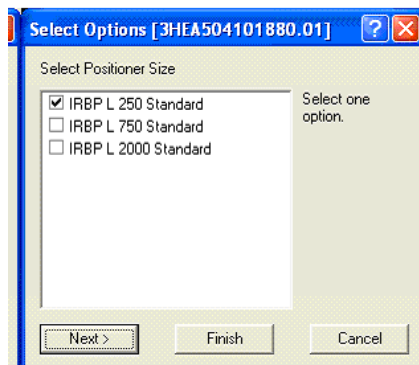
23. Click **Next** and select options according to the picture below



24. Click **Next** and select options according to the picture below

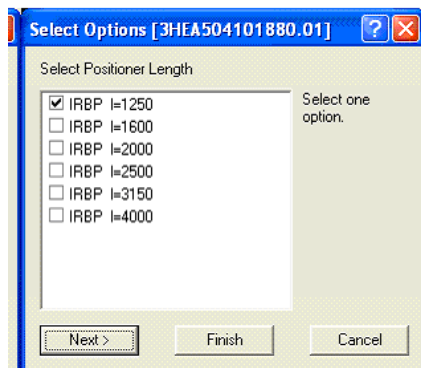


25. Click **Next** and select options according to the picture below

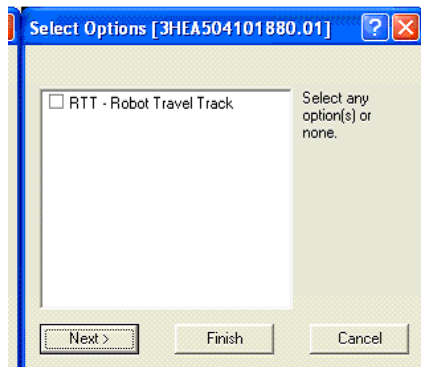


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26. Click **Next** and select options according to the picture below



27. Click **Next** and select options according to the picture below



28. Click **Next** and click **Finish**

29. Close RobInstall.
Click **Finish**

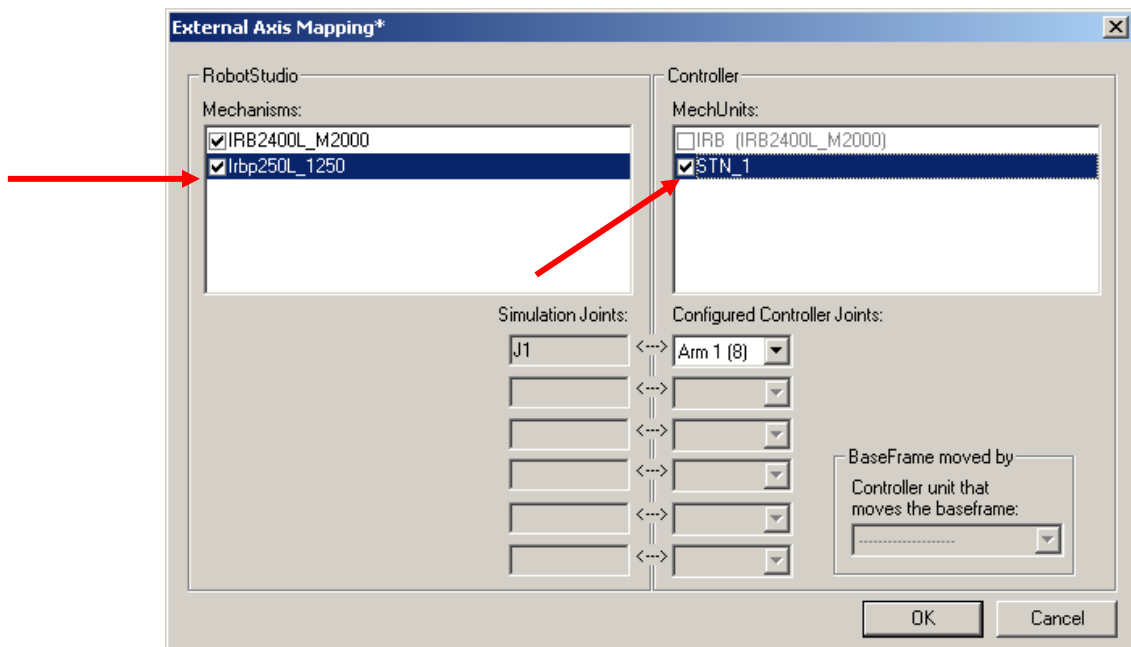
30. Activate the new controller.
Click **Set Current Robot**

31. Close the Virtual Robot Browser.
Click **Close**

32. Close the setup menu.
Click **OK**

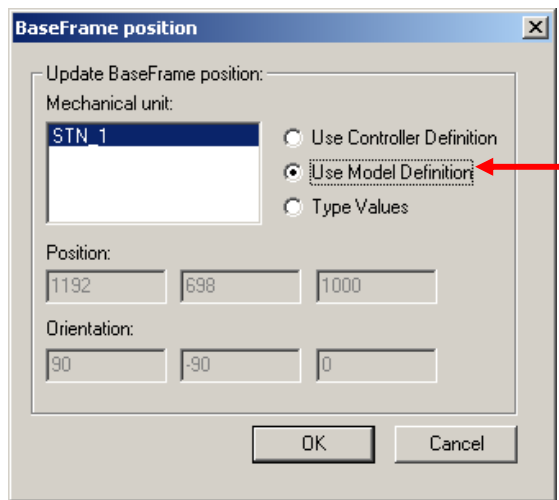
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33. Start the new controller.
In the **Object** browser right click on the robot **IRB2400L_xxxx** and select **Start Controller** in the context menu, wait for the controller to start
34. In the **Object** browser right click on the robot **IRB2400L_xxxx** and select **Setup Controller** in the context menu, select the **Ext. Axis** tab, click **Set Up**, in the Mechanisms window select the box **irbp250L_1250**, in the MechUnits window check the box **STN_1** (see picture below)

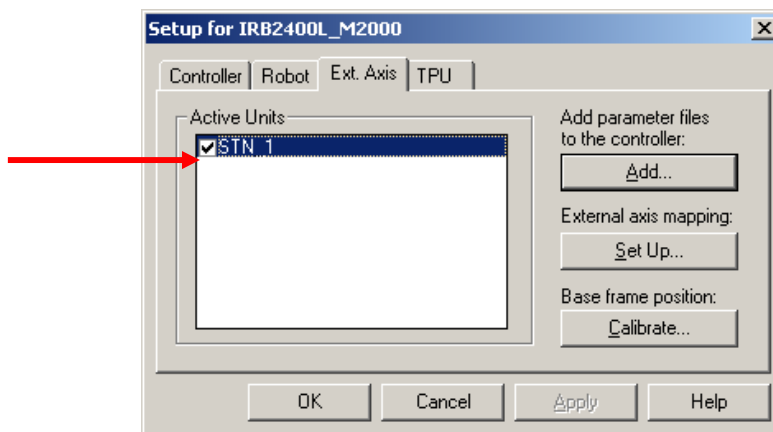


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35. Update the BaseFrame position.
Click **OK** and click **Yes**, click **Calibrate** and click on the radio button **Use Model Definition** (see picture below)

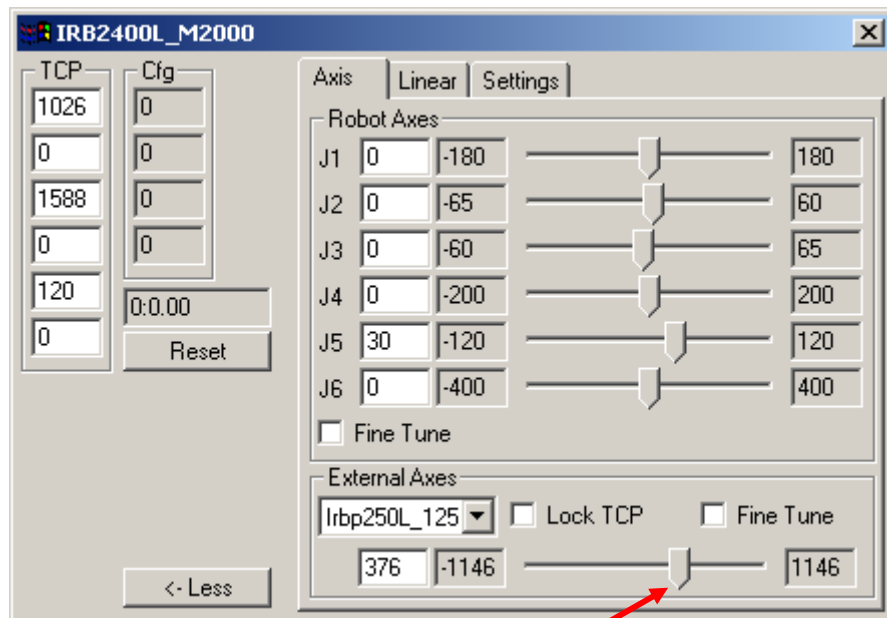


36. Restart the Virtual Controller.
Click **OK** and wait for the controller to start
37. Close the setup menu.
Click **OK**
38. Activate the positioner.
In the **Object** browser right click on the robot **IRB2400L_xxxx** and select **Setup Controller** in the context menu, select the **Ext. Axis** tab and check the box **STN_1**, this is the same as turning on the power for the controller in reality (see picture below)



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39. Close the setup menu.
Click **OK**
40. You can now test the positioner with the Mech Status Window.
In the **Object browser** select the robot **IRB2400L_xxxx**, on the **Mechanism** menu select **Show Mech Status Window** (see picture below)



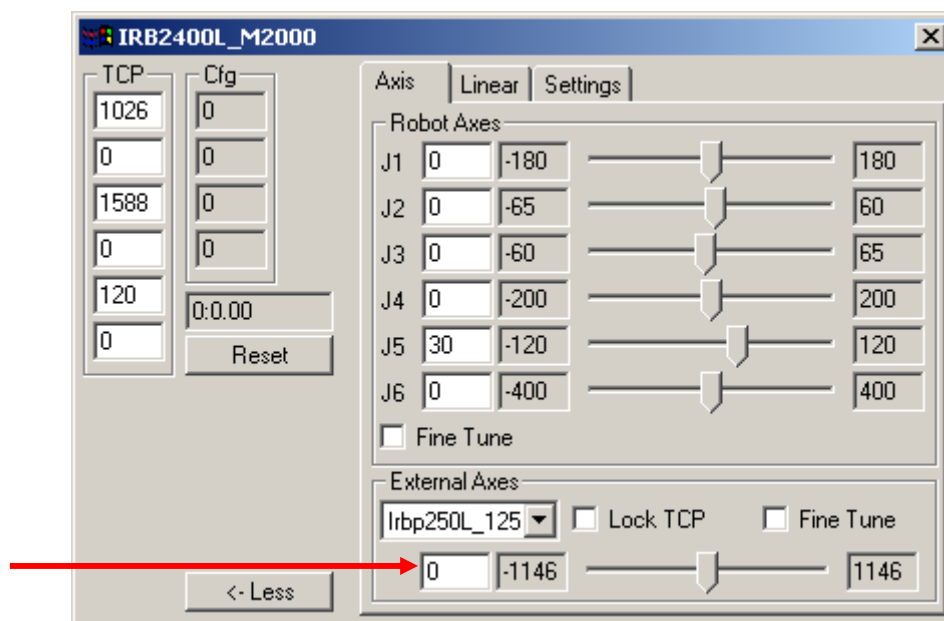
3. Create a coordinated workobject on the positioner

Please follow the example below:

1. Create a workobject.
On the **Create** menu select **Workobject**, input the name **Coordinated** and click **OK**
2. Attach the workobject to the positioner.
In the **Object browser** select the workobject **Coordinated** and drag it to the positioner **irbp250L_1250**, answer **YES** to the question "Do you also want to reposition Coordinated?", answer **YES** to the question "Do you want Wobj: Coordinated to be moved by Irbp250L_1250?"

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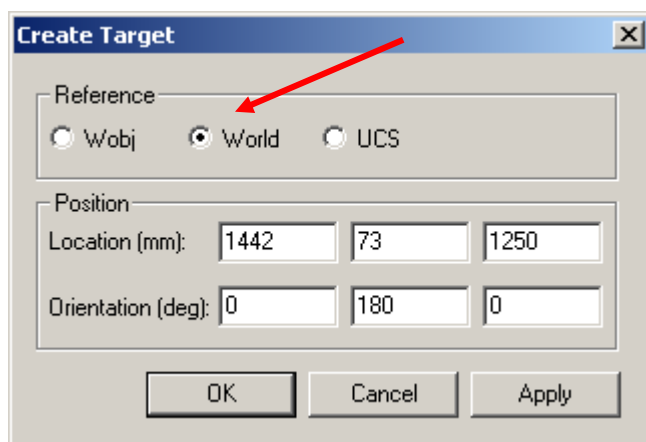
3. Move the robot to the home position.
In the **Object browser** select the robot **IRB2400L_xxxx**, on the **Mechanism** menu select **Move** then click **Move to Home**
4. Move the positioner to position 0.
In the **Object browser** select the robot **IRB2400L_xxxx**, on the **Mechanism** menu select **Show Mech Status Window**, input the value 0 for the External Axes and press **Enter** (see picture below)



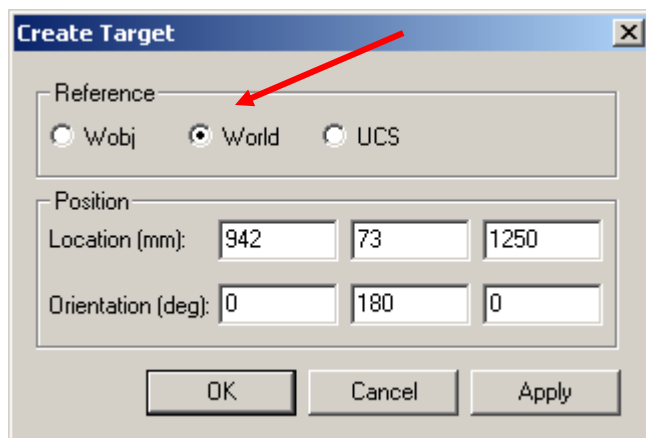
5. Close the Mech Status Window.
Click on **X** in the upper right corner of the Mech Status Window
6. Teach target Home in workobject wobj0.
On the **Create** menu select **Teach Target**
7. Rename the target to Home.
In the **Object browser** right click on the target and select **Rename** in the context menu, input the name **Home** and press **Enter**

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8. Create a target at the middle front of the box.
On the **Create** menu select **Target**, in the **Reference** group select the radio button **World** and input the values **1442, 73** and **1250** for **Location** then input the values **0, 180** and **0** for **Orientation** (see picture below)

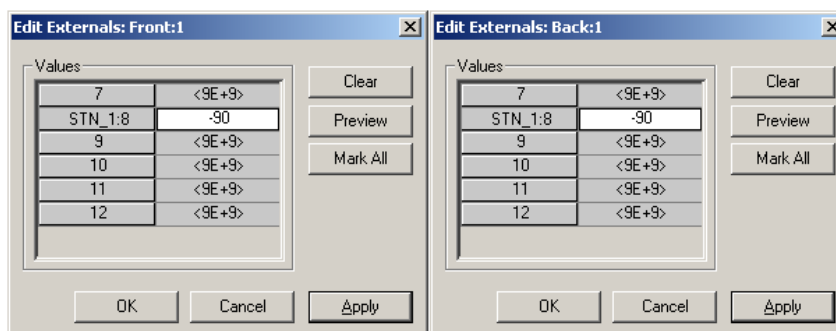


9. Rename the target to Front.
Click **OK**, in the **Object browser** right click on the target and select **Rename** in the context menu, input the name **Front** and press **Enter**
10. Create a target at the middle back of the box.
On the **Create** menu select **Target**, in the **Reference** group select the radio button **World** and input the values **942, 73** and **1250** for **Location** then input the values **0, 180** and **0** for **Orientation** (see picture below)



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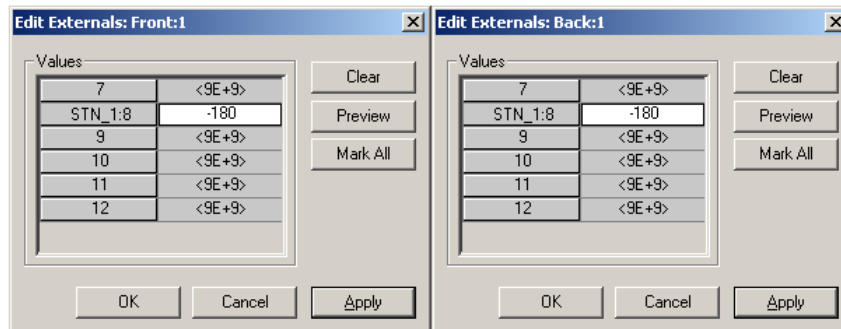
11. Rename the target to Back.
Click **OK**, in the **Object browser** right click on the target and select **Rename** in the context menu, input the name **Back** and press **Enter**
Since the targets Home, Front and Back was created under wobj0 they will not change positions with the coordinated motion.
We can therefore use them as default positions while rotating the box on the positioner.
12. Change the active workobject to Coordinated.
In the **Object browser** right click on workobject **Coordinated** and select **Set As Active Wobj** in the context menu
13. Teach target Side1A in workobject Coordinated.
In the **Object browser** right click on target **Front** and select **Jump to Target** in the context menu, on the **Create** menu select **Teach Target**, in the **Object browser** right click on the target and select **Rename** in the context menu, input the name **Side1A** and press **Enter**
14. Teach target Side1B in workobject Coordinated.
In the **Object browser** right click on target **Back** and select **Jump to Target** in the context menu, on the **Create** menu select **Teach Target**, in the **Object browser** right click on the target and select **Rename** in the context menu, input the name **Side1B** and press **Enter**
15. Edit the external axis value for targets Front and Back.
In the **Object browser** right click on target **Front** and select **Edit Externals** in the context menu, input the value **-90** for **STN_1:8** and click **OK**, repeat step 15 for target **Back** (see picture below)



16. Teach target Side2A in workobject Coordinated.
In the **Object browser** right click on target **Front** and select **Jump to Target** in the context menu, on the **Create** menu select **Teach Target**, in the **Object browser** right click on the target and select **Rename** in the context menu, input the name **Side2A** and press **Enter**

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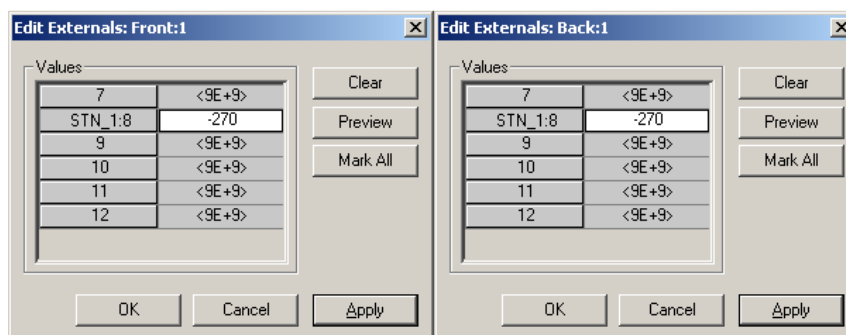
17. Teach target Side2B in workobject Coordinated.
In the **Object browser** right click on target **Back** and select **Jump to Target** in the context menu, on the **Create** menu select **Teach Target**, in the **Object browser** right click on the target and select **Rename** in the context menu, input the name **Side2B** and press **Enter**
18. Edit the external axis value for targets Front and Back.
In the **Object browser** right click on target **Front** and select **Edit Externals** in the context menu, input the value **-180** for **STN_1:8** and click **OK**, repeat step 18 for target **Back** (see picture below)



19. Teach target Side3A in workobject Coordinated.
In the **Object browser** right click on target **Front** and select **Jump to Target** in the context menu, on the **Create** menu select **Teach Target**, in the **Object browser** right click on the target and select **Rename** in the context menu, input the name **Side3A** and press **Enter**
20. Teach target Side3B in workobject Coordinated.
In the **Object browser** right click on target **Back** and select **Jump to Target** in the context menu, on the **Create** menu select **Teach Target**, in the **Object browser** right click on the target and select **Rename** in the context menu, input the name **Side3B** and press **Enter**

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21. Edit the external axis value for targets Front and Back.
In the **Object browser** right click on target **Front** and select **Edit Externals** in the context menu, input the value **-270** for **STN_1:8** and click **OK**, repeat step 21 for target **Back** (see picture below)



22. Teach target Side4A in workobject Coordinated.
In the **Object browser** right click on target **Front** and select **Jump to Target** in the context menu, on the **Create** menu select **Teach Target**, in the **Object browser** right click on the target and select **Rename** in the context menu, input the name **Side4A** and press **Enter**
23. Teach target Side4B in workobject Coordinated.
In the **Object browser** right click on target **Back** and select **Jump to Target** in the context menu, on the **Create** menu select **Teach Target**, in the **Object browser** right click on the target and select **Rename** in the context menu, input the name **Side4B** and press **Enter**
24. Create path pthHome.
In the **Elements Toolbar** select **MoveJoint** (see picture below), on the **Create** menu select **Path**, in the **Object browser** right click on the path and select **Rename** in the context menu, input the name **pthHome** and press **Enter**

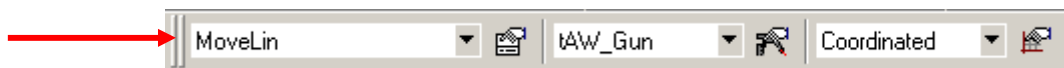


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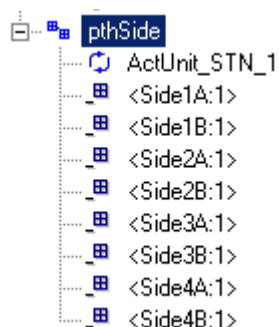
25. Copy target Home to path pthHome.
Delete **ConfJ_Off** and **ConfL_Off** from path **pthHome**, In the **Object browser** select the target **Home** and drag it to the path **pthHome** (see picture below)



26. Create path pthSide.
In the **Elements Toolbar** select **MoveLin** (see picture below), on the **Create** menu select **Path**, in the **Object browser** right click on the path and select **Rename** in the context menu, input the name **pthSide** and press **Enter**

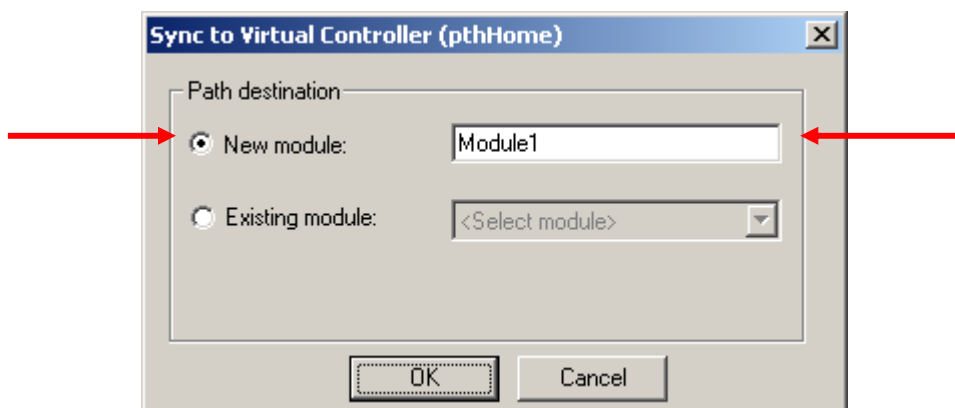


27. Copy all the "Side" target to path pthSide.
Delete **ConfJ_Off** and **ConfL_Off** from path **pthSide**, In the **Object browser** select all the "Side" targets and drag them to the path **pthSide** (see picture below)

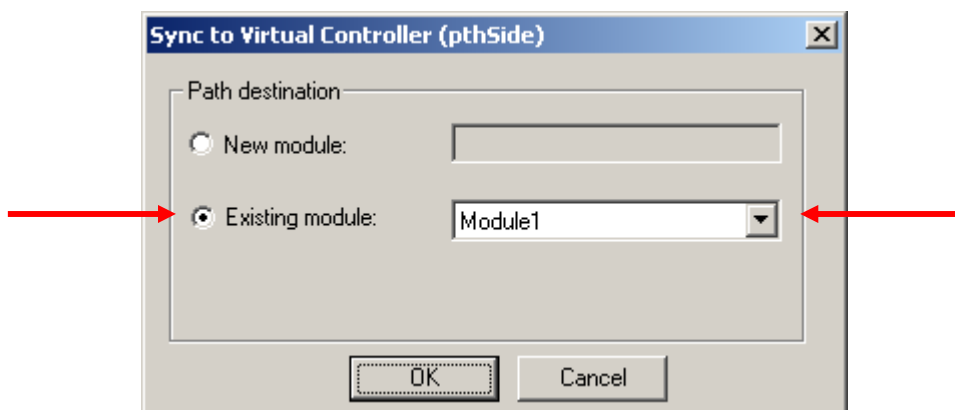


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28. Sync pthHome to the controller.
In the **Object browser** right click on the path **pthHome** and select **Sync to VirtualController** in the context menu, select the radio button **New module** input the name **Module1** (see picture below)



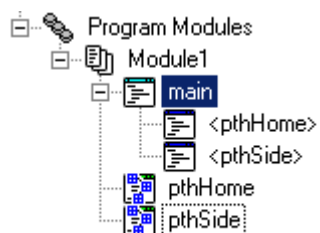
29. Sync pthSide to the controller.
Click **OK**, in the **Object browser** right click on the path **pthSide** and select **Sync to VirtualController** in the context menu, select the radio button **Existing module** and select **Module1** (see picture below)



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30. Insert Main module.

Click **OK**, in the **Program browser** right click on **Module1** and select **Insert main procedure** in the context menu, select **pthHome** and **pthSide** and drag the to **Main** (see picture below)



31. Save the station.

On the **File** menu select **Save**

32. Play the simulation.

in the **Program browser** right click on **main** and select **Execute Procedure** in the context menu

If you have any further questions, please contact your local ABB Support Center.