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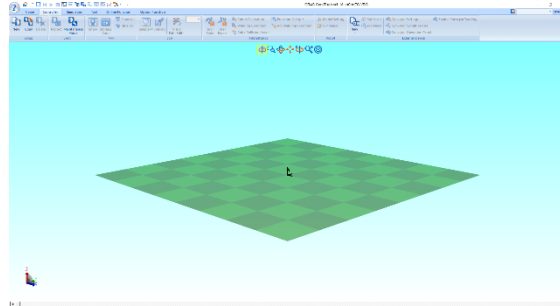
MotoSim EG-VRC – Setting Up Multiple Robots

Introduction

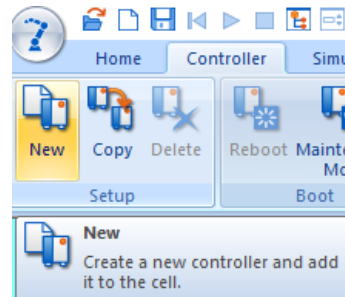
This document describes the setup of multiple robots using the same controller in MotoSim EG-VRC

Procedure

1. Create a New Cell

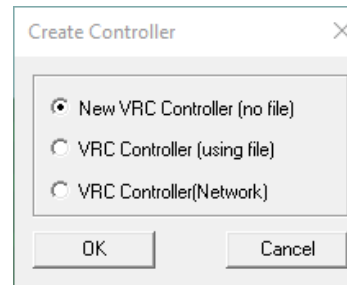


2. On the Controller tab, select New in the Setup section

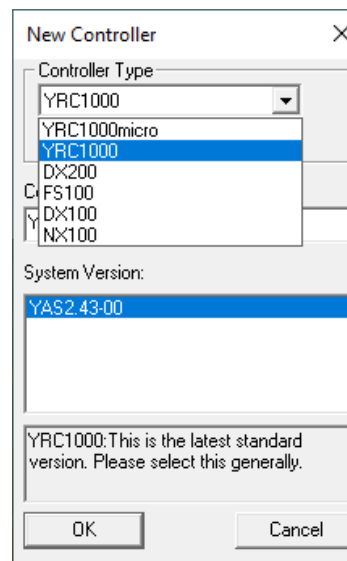


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3. Select New VRC Controller (no file). Click OK

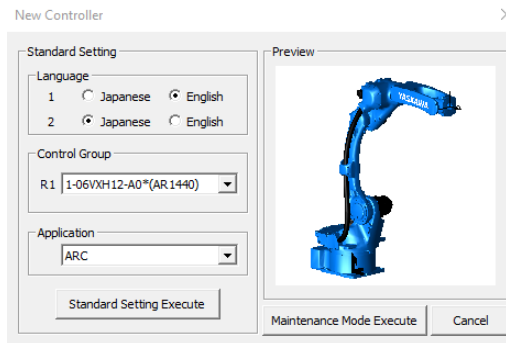


4. Select Controller Type. Click OK

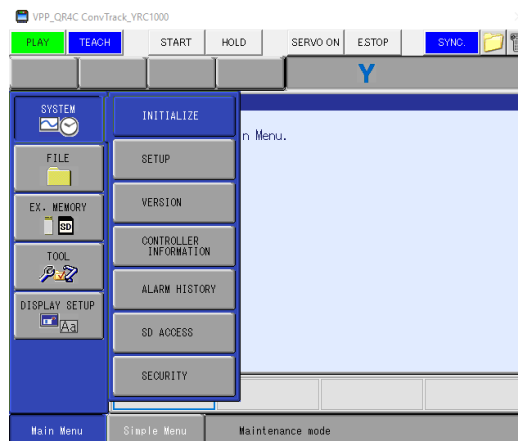


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5. Select Maintenance Mode Execute

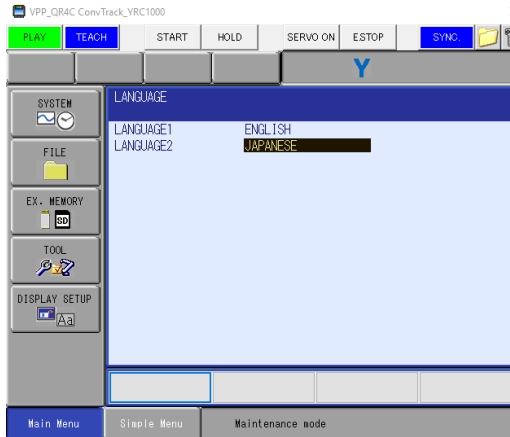


6. On virtual pendant, select SYSTEM – INITIALIZE.

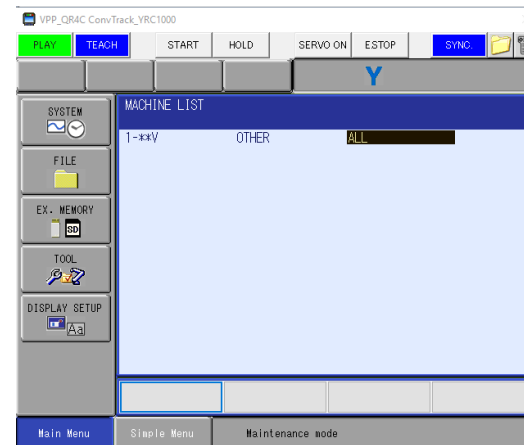
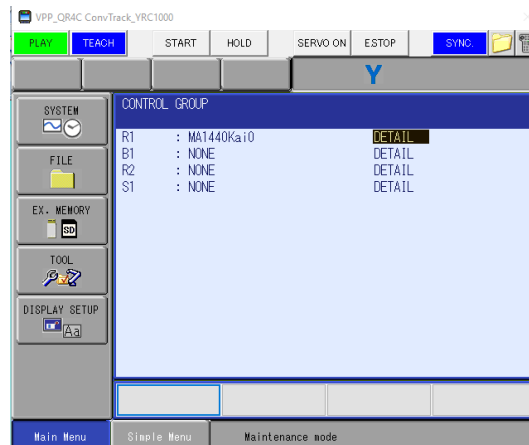


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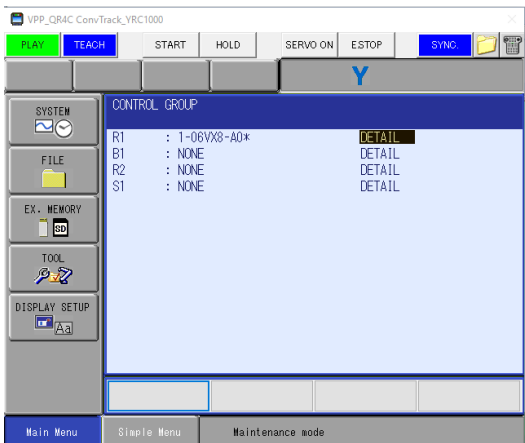
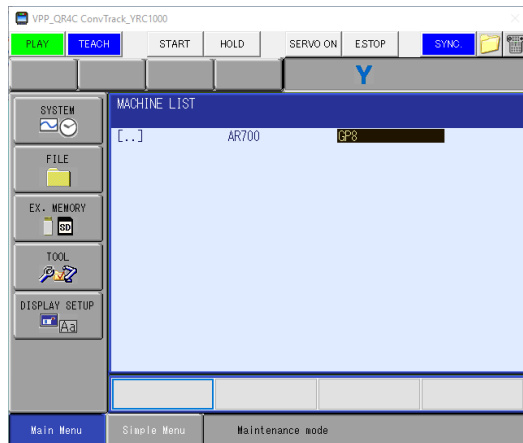
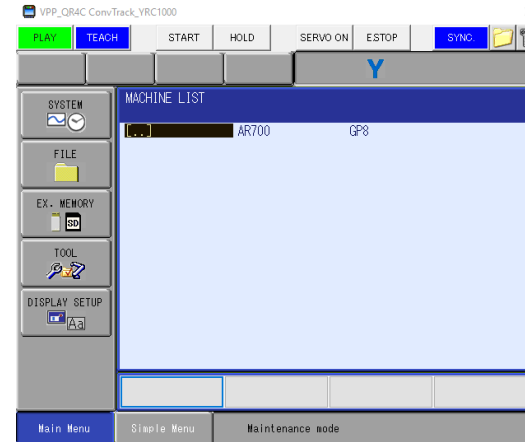
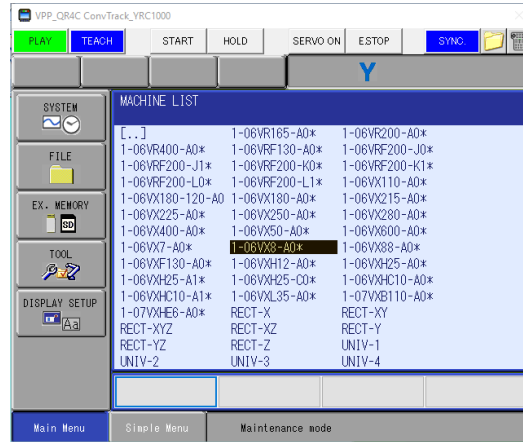
7. Set Language. Press ENTER



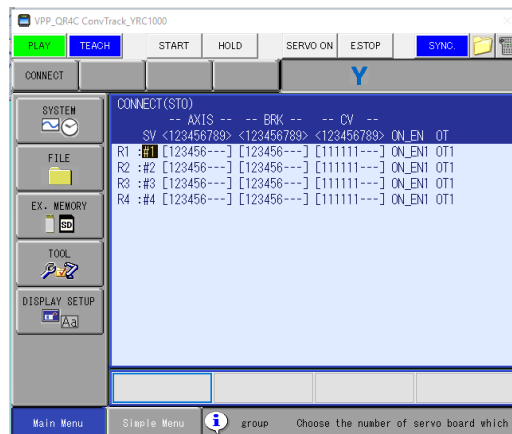
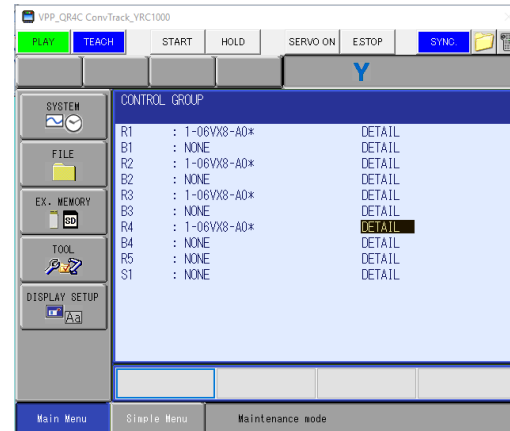
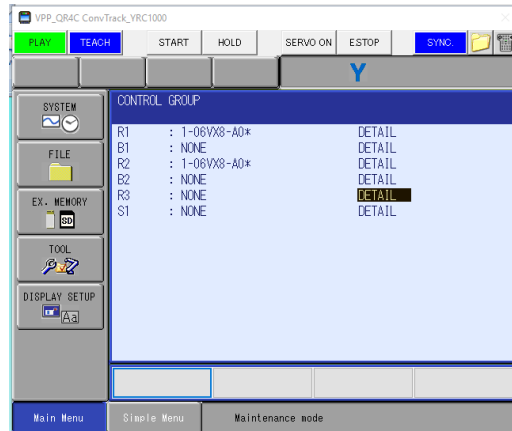
8. Set R1, R2, etc. as needed in DETAIL of each line using SELECT (refer to MotoSim EG-VRC manual sec. 15.9 for robot list). Press ENTER until you are past the CONNECT (STO) screen



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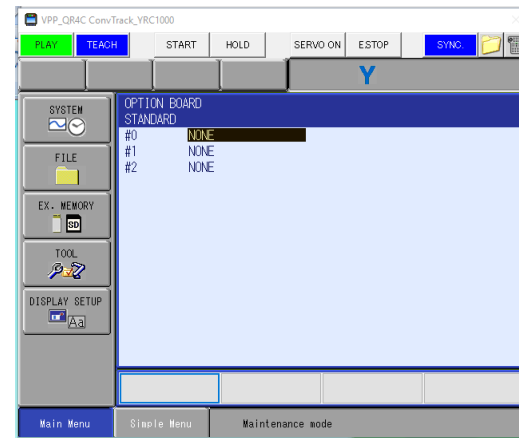
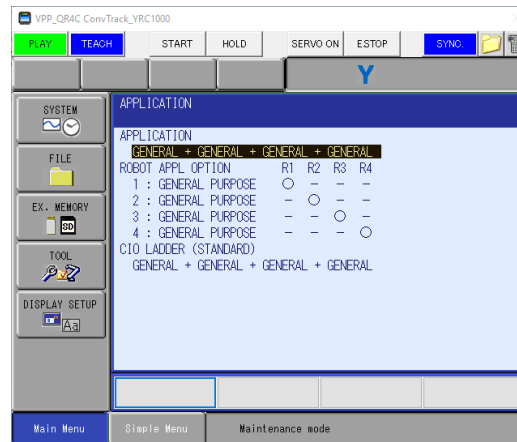
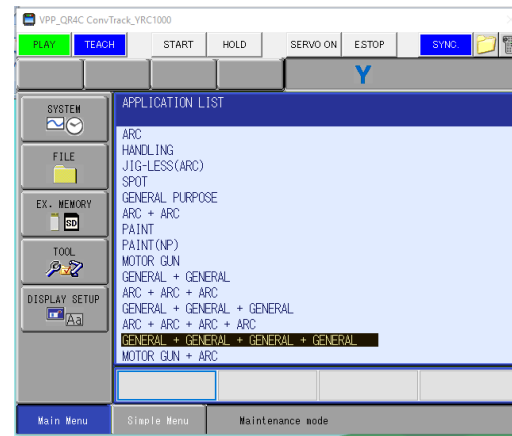
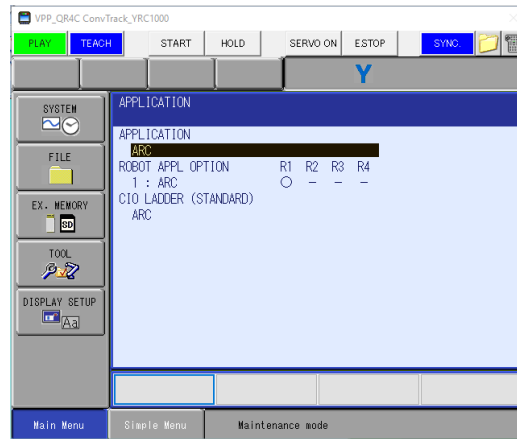


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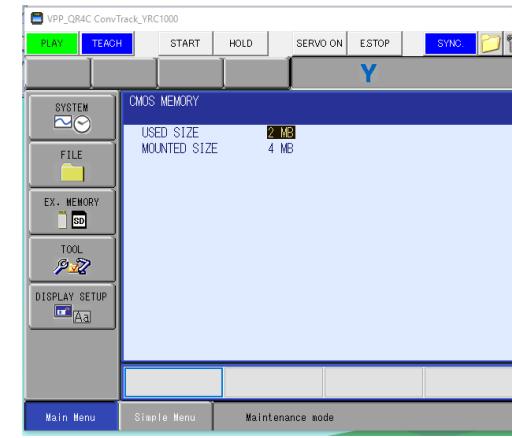
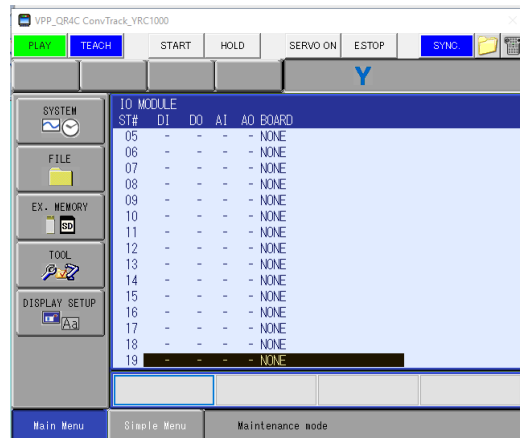
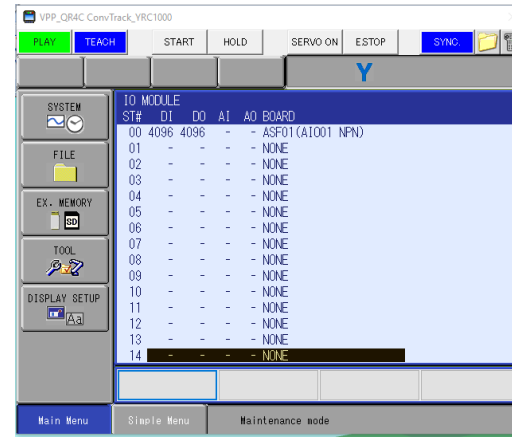
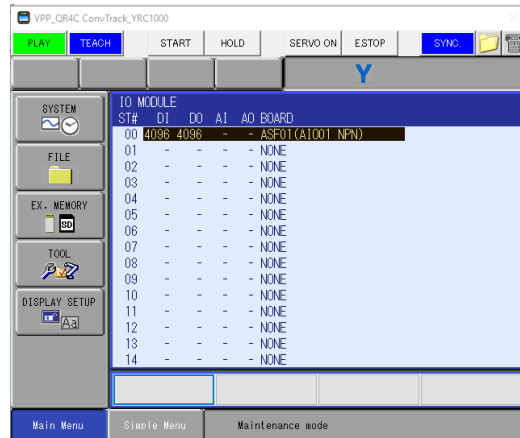


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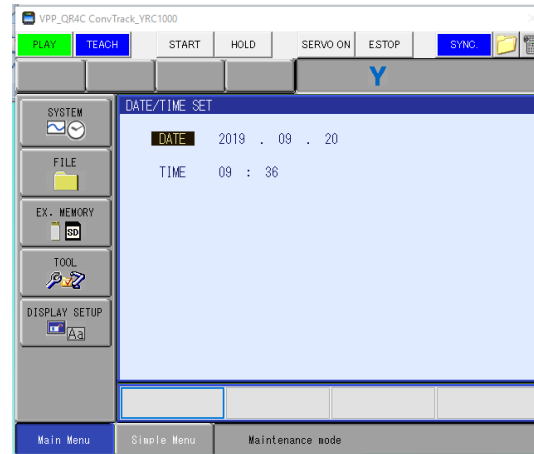
9. Select APPLICATION (Application + must match robot count. If using 3 robots, application and ladder should be GENERAL + GENERAL + GENERAL. More than 4 read GENERAL * 5,6,7,8.) Press ENTER to confirm.



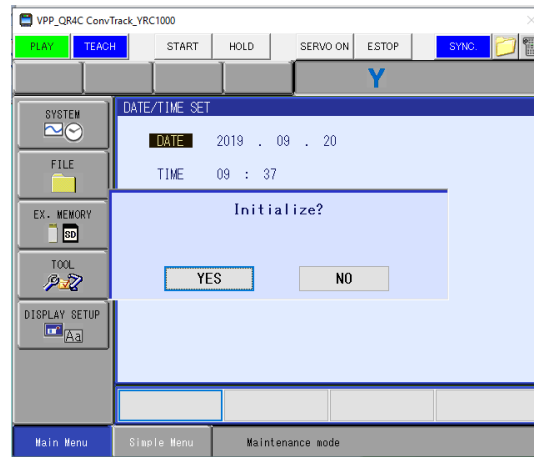
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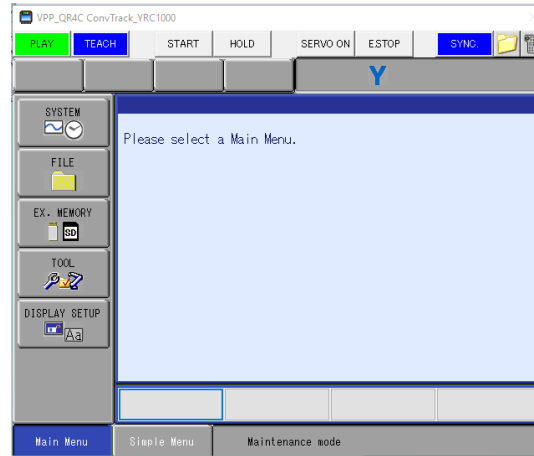


10. Press ENTER until Initialize? Confirmation. Select YES.



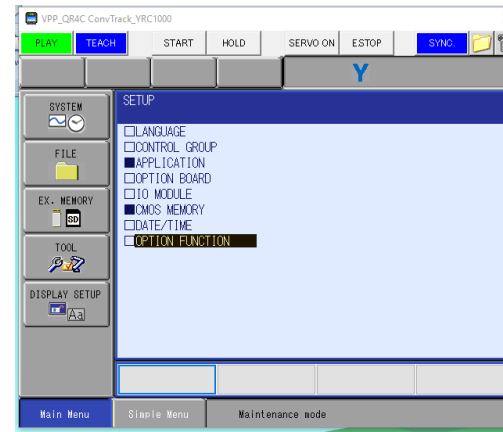
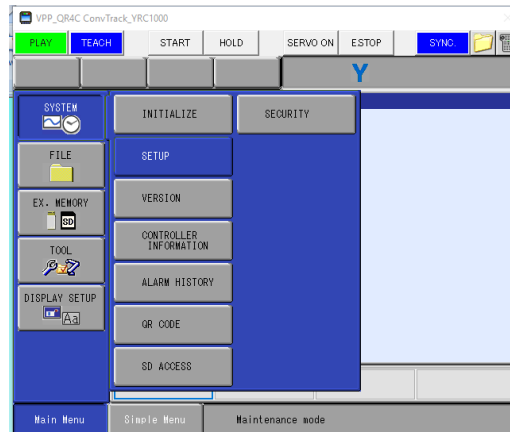
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11. Wait for Please select a Main Menu screen

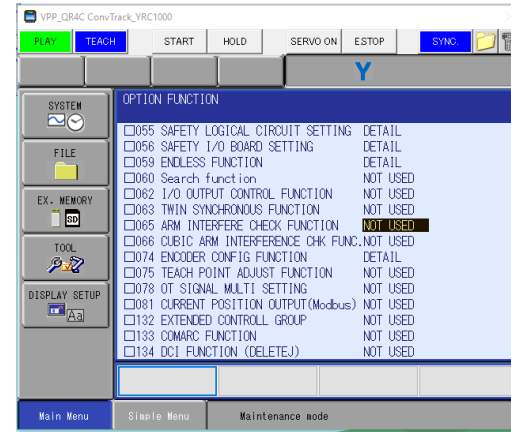
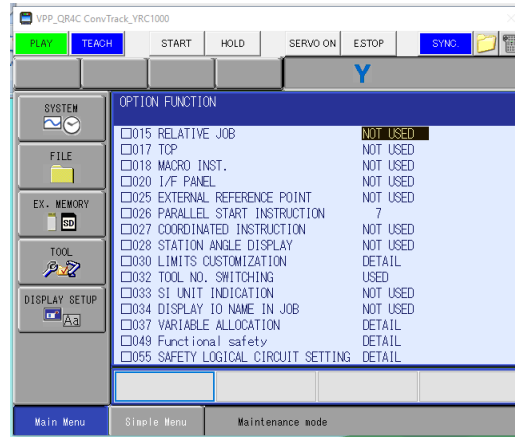


12. Select SYSTEM- SETUP - OPTION FUNCTION to select robot options (such as Arm Interference, Relative Job, Coordinated Instruction, FSU, etc.).

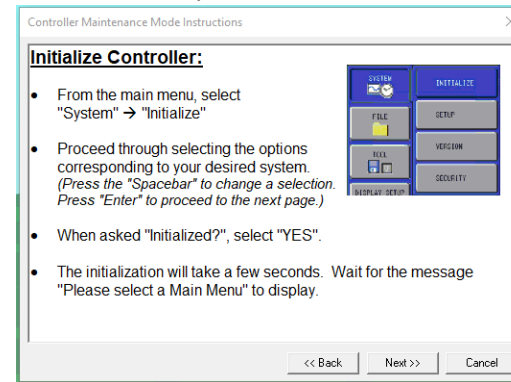
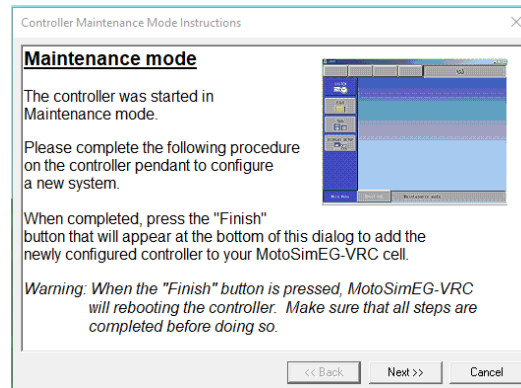
* Robots in proximity should have Arm Interference enabled and complete robot calibration(s)



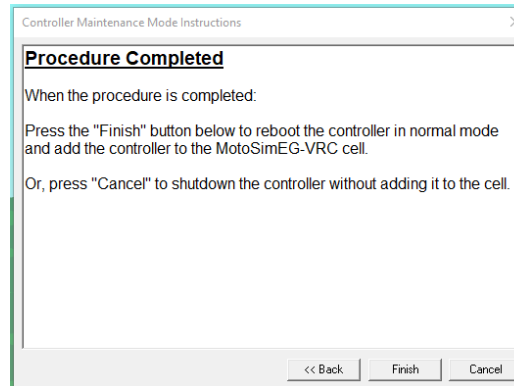
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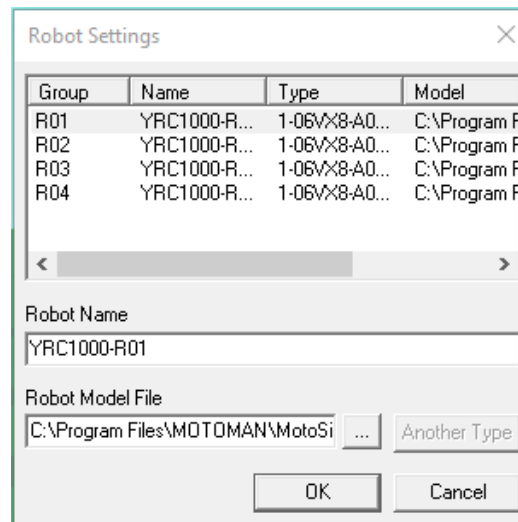
13. Click Next on Controller Maintenance Mode Instructions window until the Procedure Completed window. Click Finish



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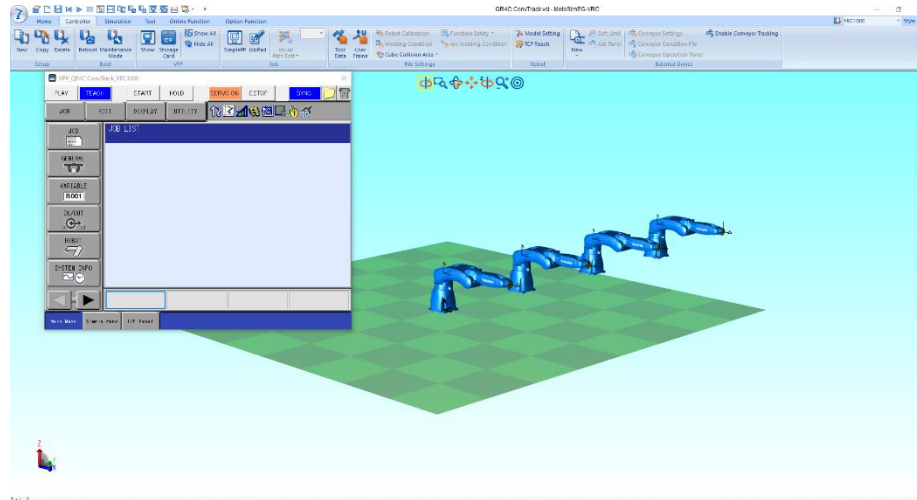


14. Click OK on Robot Settings window



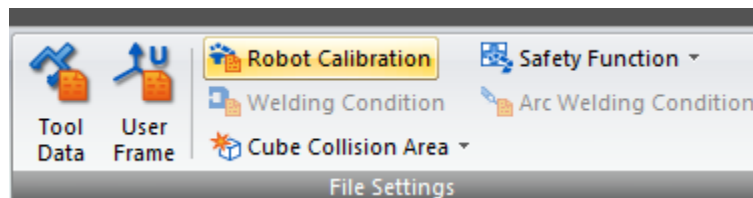
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15. Robots will automatically space 1M. Position robot(s) as needed with CAD Tree.



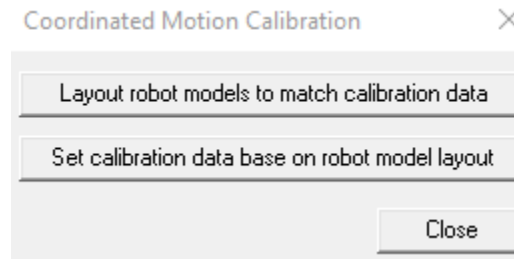
16. Locate robots as required for cell.

17. Click Robot Calibration in Controller tab.



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18. Coordinated Motion Calibration window will appear. Select “Set calibration data base upon robot model layout” & Close window.



- a. “Layout robot models to match calibration data” selection will be invalid for new setup unless robot calibration file has been loaded into virtual controller.

19. Process complete. Save progress.