

ROBOTICS

Application manual

Wizard



Trace back information:
Workspace Main version a472
Checked in 2022-09-20
Skribenta version 5.5.019

Application manual

Wizard

RobotWare 7.7

Document ID: 3HAC073766-001

Revision: E

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Overview of this manual

About this manual

This manual introduces the user interface and instructions contained in the blocky programming application Wizard on the FlexPendent.

Usage

This manual should be read during programming of IRB 14050, IRB 1100, IRB 1300, CRB 1100 and CRB 15000.

Who should read this manual?

This manual is intended for robot programmers, especially the beginners.

Prerequisites

The reader should:

- Be trained in robot operation.

References

Documentation referred to in the manual, is listed in the table below.

Document name	Document ID
<i>Operating manual - Emergency safety information</i>	3HAC027098-001
<i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i>	3HAC031045-001
<i>Operating manual - OmniCore</i>	3HAC065036-001
<i>Product manual - OmniCore C30</i>	3HAC060860-001
<i>Product manual - IRB 14050</i>	3HAC064625-001
<i>Product manual - Grippers for IRB 14050</i>	3HAC064626-001
<i>Product manual - IRB 1100</i>	3HAC064992-001
<i>Product manual - IRB 1300</i>	3HAC070390-001
<i>Product manual - CRB 1100</i>	3HAC078007-001
<i>Product manual - CRB 15000</i>	3HAC077389-001

Revisions

Revision	Description
A	First edition.
B	Released with RobotWare 7.1. The following updates are made in this revision: <ul style="list-style-type: none"> • Supported programming on IRB 1100. • Updated description about trigger conditions for the if block and while loop block. • Added description about the Variables blocks. • Added description about Skill Creator.

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Revision	Description
C	Released with RobotWare 7.4. The following updates are made in this revision: <ul style="list-style-type: none">• Supported programming on CRB 1100, CRB 15000 and IRB 1300.• Added network security disclaimer.• Added Message blocks and Stop & Wait blocks• Updated descriptions of buttons in the user interface.• Updated values of predefined motion speed parameter in Move blocks.• Updated procedures about location modification.• Added Play from this block and Update Location to shortcut commands.• Updated description about Skill Creator.
D	Released with RobotWare 7.6.1. The following updates are made in this revision: <ul style="list-style-type: none">• Added Gripper blocks and Force blocks.• Added parameters used in Gripper blocks and Force blocks.• Added Gripper operations.• Added procedure about defining a hole.
E	Released with RobotWare 7.7. The following updates are made in this revision: <ul style="list-style-type: none">• Supported to work with lead-through device for SWIFTI™ robots.• Added figures to show the user interface.

Network security

Network security

This product is designed to be connected to and to communicate information and data via a network interface. It is your sole responsibility to provide, and continuously ensure, a secure connection between the product and to your network or any other network (as the case may be).

You shall establish and maintain any appropriate measures (such as, but not limited to, the installation of firewalls, application of authentication measures, encryption of data, installation of anti-virus programs, etc) to protect the product, the network, its system and the interface against any kind of security breaches, unauthorized access, interference, intrusion, leakage and/or theft of data or information. ABB Ltd and its entities are not liable for damage and/or loss related to such security breaches, any unauthorized access, interference, intrusion, leakage and/or theft of data or information.

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1 Introduction

Overview

Wizard is a programming application available on the FlexPendant. It provides an easy and interactive programming means, enabling users to program by simply combining visible instruction blocks and setting pre-defined parameters.

Supported robot type

The following robot families are supported by Wizard:

- IRB 14050 (supported from RobotWare 7.0)
 - IRB 1100 (supported from RobotWare 7.1)
 - CRB 1100 (supported from RobotWare 7.2)
 - CRB 15000 (supported from RobotWare 7.2)
 - IRB 1300 (supported from RobotWare 7.4)
-

Safety information

Before using Wizard to program, make sure that all safety information included in but not restricted to the following manuals are acknowledged and necessary safety measures are conducted:

- *Operating manual - Emergency safety information*
 - *Safety manual for robot - Manipulator and IRC5 or OmniCore controller*
 - *Operating manual - OmniCore*
 - *Product manual - OmniCore C30*
 - *Product manual - IRB 1100*
 - *Product manual - IRB 14050*
 - *Product manual - Grippers for IRB 14050*
 - *Product manual - CRB 1100*
 - *Product manual - CRB 15000*
 - *Product manual - IRB 1300*
-

Prerequisites

To work with Wizard, the followings are required:

- OmniCore controller operating in RobotWare 7.0 or later
- Installed Wizard add-in



Note

The Wizard add-in version is backward compatible with RobotWare versions. However, an older version of the Wizard add-in cannot work with a newer RobotWare version.

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1 Introduction

Continued

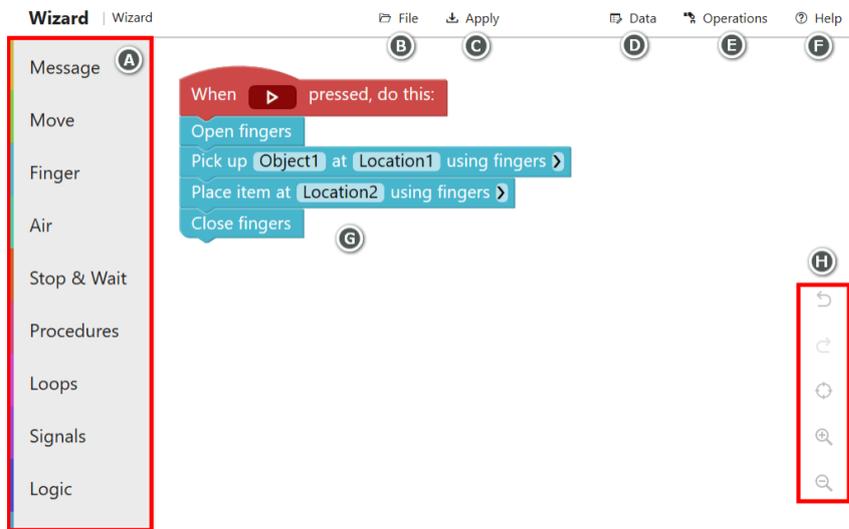


Note

For IRB 14050 working with controller in RobotWare 7.0, Smart Gripper, Collision Detection [3107-1] and Multitasking [3114-1] must be selected during setup of the robot system.

For IRB 14050 working with controller in other RobotWare versions, the Smart Gripper add-in is optional. However, if Smart Gripper is selected, Collision Detection [3107-1] and Multitasking [3114-1] must be selected together.

The user interface



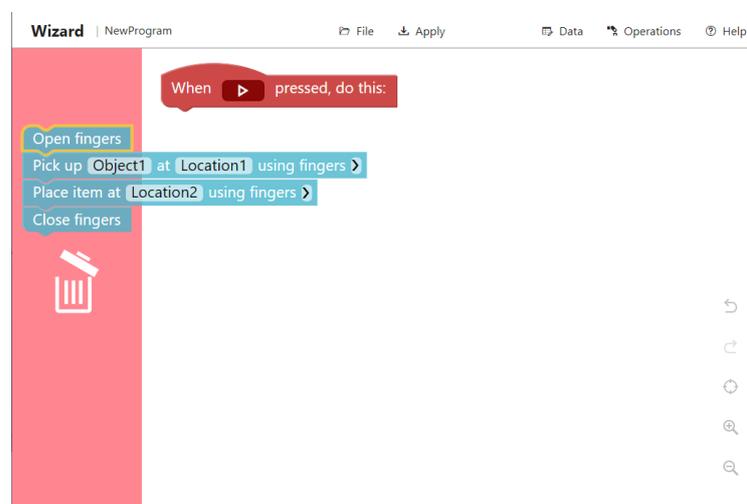
xx1900002111

Label	Buttons/Section	Description	
A	Block category	Tapping each block category button displays a list of available blocks in this category. During programming, tap the required block and drag it to the editing area. You can sort and set visibility of the categories in the category manager by tapping the Help button in the right corner of the window and then tap Category Manager .	
B	File	New	Clears the blocks in the editing area and creates a new program. If there is a program under editing, a dialog displays, prompting to discard or save the program.
		Save	Saves the current program to the default directory \$HOME/Programs/.
		Save as	Saves the current program under a new name in the default directory \$HOME/Programs/.
		Load	Loads a program from the default program saving directory \$HOME/Programs/.
		Rename	Renames the current program.
C	Apply	Tapping the Apply button, the edited program will be saved to controller hard disk. When the program is saved, the Applied button replaces the Apply button.	

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Label	Buttons/Section	Description
D	Data	Tapping the Data button displays the quickset window for setting data and variables.
E	Operations	Tapping the Operation button allows a quick access to basic gripper-related operations.
F	Help	Tapping the Help button to access the help contents, such as tutorial, user manual and Wizard version information. You can click Feedback to give comments or suggestions.
G	Editing area	The main programming window of the Wizard. Users can easily sequence and edit the blocks in this area.
H	View settings	 Removes more than one action until the program returns to what you previously had.
		 Redoes more than one action.
		 Aligns the blocks/program to the left corner.
		 Zooms in the window view.
		 Zooms out the window view. Double-tapping the icon will directly zoom out the display to fit to window.

To delete unnecessary block(s), tap and press the block(s) and drag them to the left pane of the window. Release the tapping when a trash can icon displays. Note that deletion cannot be undone.



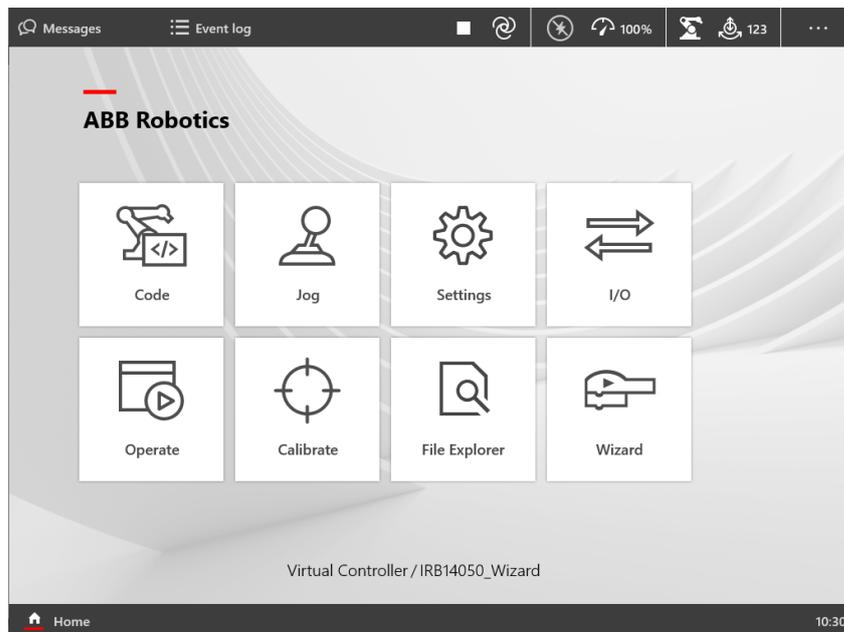
xx200000202

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2 Getting started

General

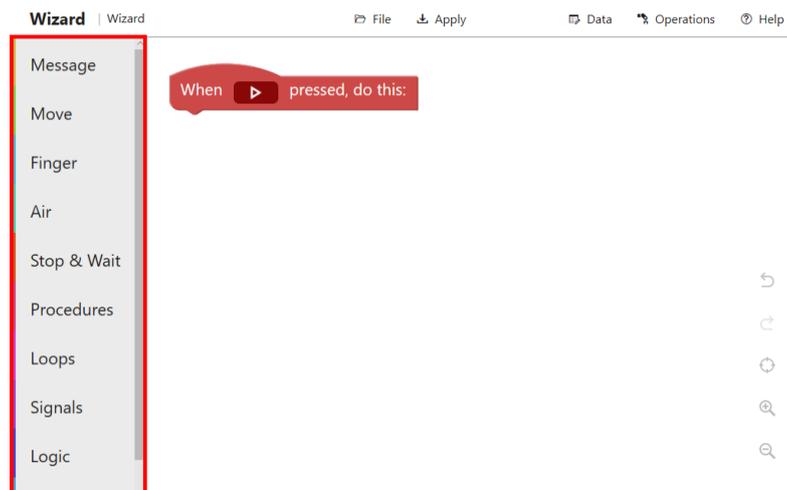
Wizard is a default application on the FlexPendant for IRB 14050, IRB 1100, IRB 1300, CRB 1100 and CRB 15000. You can access the main window of Wizard directly by tapping the following application icon on the FlexPendant touch screen.



xx200000258

Procedure

- 1 Tap the required block category icon to display the list.



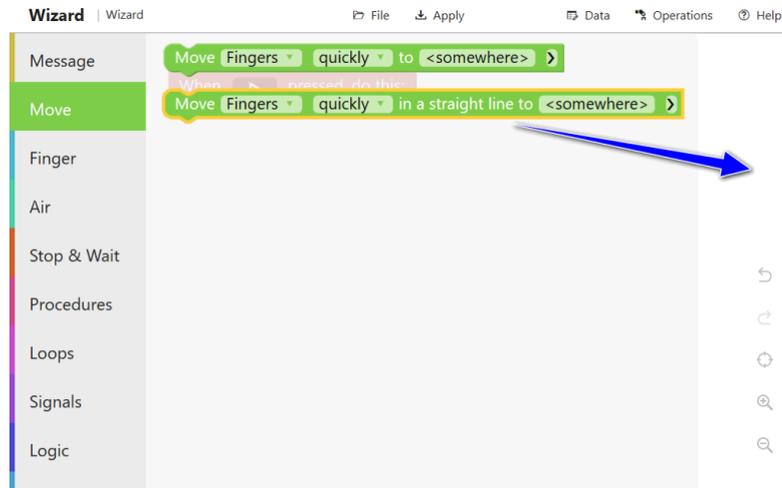
xx1900002112

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2 Getting started

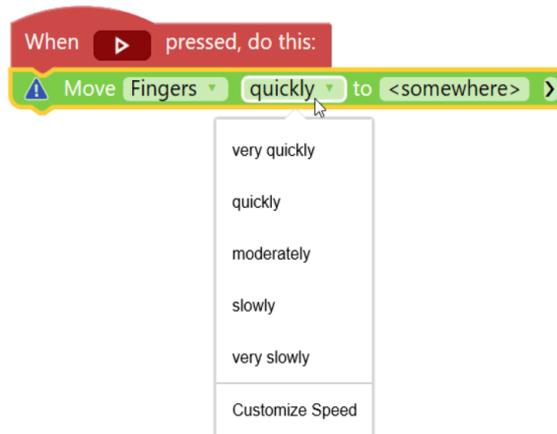
Continued

2 Tap or drag the required block to the editing area.



xx1900002113

3 Set necessary parameters by choosing from the predefined list or a customized list.



xx1900002114

4 Repeat steps 2 and 3 until the program is created or modified as required.



Tip

You can drag the blocks to adjust their sequences.

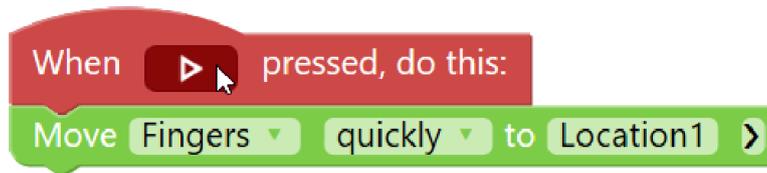
5 Tap Apply to save the program.



xx1900002115

Continues on next page

- 6 Tap the **Play** button to run the program and apply the codes to the controller.



xx1900002116



Note

To view the corresponding RAPID data of the program edited in the Wizard,

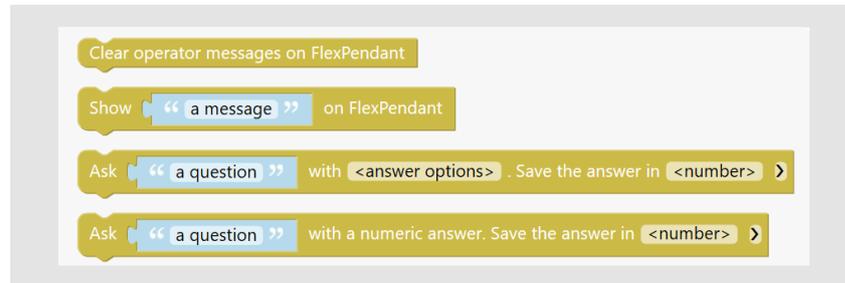
- 1 Tap **Applications** in the status bar of the FlexPendant.
- 2 Tap **Code** on the start screen.
- 3 Tap **Wizard** in the displayed **Modules** page.

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3 Programming with Wizard

3.1 Communicating with the FlexPendant

Block illustration



xx220001333

Descriptions

Users can define the texts written on the FlexPendant display, which could be displayed as messages to show information, as questions to ask users to operate or as answers read from the FlexPendant. Available message blocks are listed as follows:

- Clear operator messages on FlexPendant
- Show a message on FlexPendant
- Ask a question with <answer options>. Save the answer in <number>.: label the function keys and to read which key is pressed. This block allows to set optional parameters.
- Ask a question with a numeric answer. Save the answer in <number>.: read a numeric value from the FlexPendant. This block allows to set optional parameters.

For details about the numeric variable in the blocks and optional parameters, see [Parameters on page 35](#).

3 Programming with Wizard

3.2 Moving the fingers and suction cups

3.2 Moving the fingers and suction cups

Block illustration



xx2200001334

Descriptions



Note

The Finger and Air blocks are available only for IRB 14050 configured with ABB Smart Gripper.

Use the **Move** blocks to move the robot gripper fingers or suction cups to the destination location along a non-linear path or linearly.

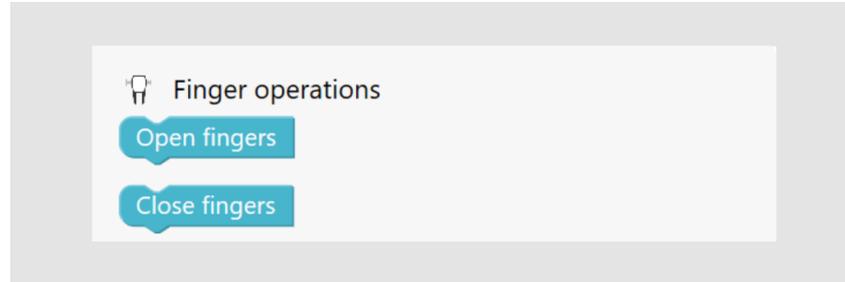
- Move *Finger quickly* to *<somewhere>*
- Move *Finger quickly* in a straight line to *<somewhere>*

The movement speed is set to **quickly** by default. It can be reset to another value by users.

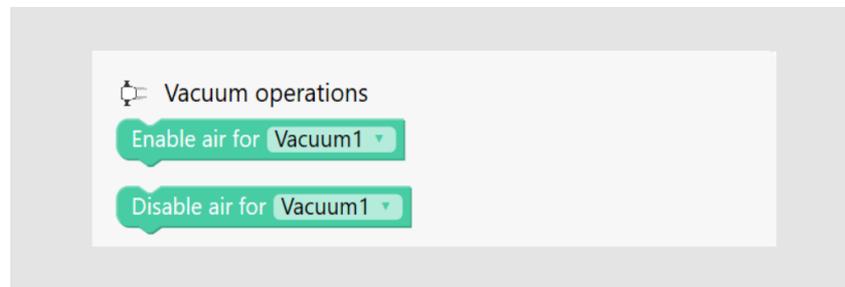
The **Move** blocks also allow to set optional parameters. For details about the parameters, including optional parameters, in the blocks, see [Parameters on page 35](#).

3.3 Controlling the fingers and suction cups

Block illustration



xx2200001335



xx2200001336

Descriptions



Note

The Finger and Air blocks are available only for IRB 14050 configured with ABB Smart Gripper.

To open and close the gripper fingers, use the `Open finger` and `Close finger` blocks in the **Finger** block group.

The gripper can also be configured with one or two vacuum modules. To enable and disable air supply to a suction cup, use the `Enable air for VacuumX` and `Disable air for VacuumX` blocks in the **Air** block group.

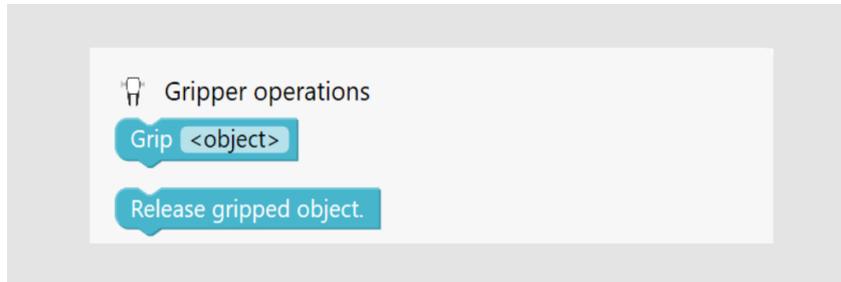
For details about the parameters in the blocks, see [Parameters on page 35](#).

3 Programming with Wizard

3.4 Operating the gripper

3.4 Operating the gripper

Block illustration



xx2200001337

Descriptions



Note

The Gripper blocks are available for robots (except IRB 14050) configured with a gripper (other than ABB Smart Gripper) and its corresponding application add-in.

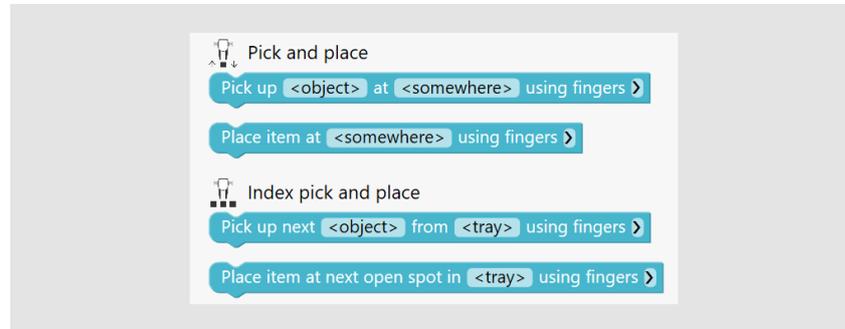
To grip an object using a configured gripper or release the object gripped by the gripper, use the `Grip <object>` and `Release gripped object` blocks in the **Gripper** block group.

If the gripper is configured with fingers and suction cups, and both of them have objects gripped, the `Release gripped object` block will release the object gripped by fingers first.

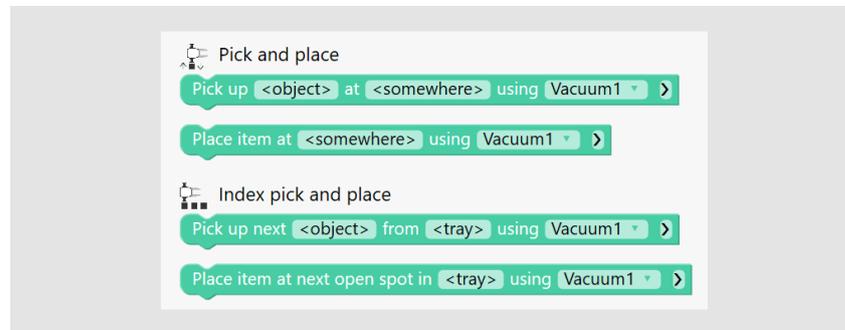
For details about the parameters in the blocks, see [Parameters on page 35](#).

3.5 Picking up and placing with fingers and suction cups

Block illustration



xx2200001339



xx2200001338

Descriptions



Note

Finger- and air-related blocks are available only for IRB 14050 with gripper(s).

Grippers can pick up and place objects using fingers or suction cups if configured. Available blocks are listed as follows.

Use...	To...	Single object	Objects in a tray
Fingers	Pick	Pick up <object> at <somewhere> using finger	Pick up next <object> from <tray> using finger
	Place	Place item at <somewhere> using finger	Place item at next open spot in <tray> using finger
Suction cups	Pick	Pick up <object> at <somewhere> using VacuumX	Pick up next <object> from <tray> using VacuumX
	Place	Place item at <somewhere> using VacuumX	Place item at next open spot in <tray> using VacuumX

The picking and placing blocks must be used in pair. If the gripper uses suction cups to pick up and place, the suction cup selected in a pair of picking and placing blocks must be the same one.

Continues on next page

3 Programming with Wizard

3.5 Picking up and placing with fingers and suction cups

Continued

In scenarios where the gripper needs to pick up same objects that are orderly arranged in a tray and then place them to another tray for several times, use the **Index pick and place** blocks in which a tray is defined.

For details about the parameters in the blocks, see [Parameters on page 35](#).

Failure handling

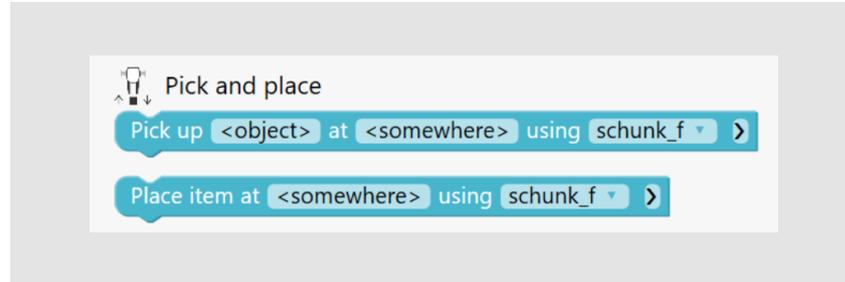
For picking and placing blocks, it is possible to define the gripper behavior if the operation experiences a failure. Tapping the > button after a picking/placing block displays the **on failure** parameter.

When a failure occurs,

- if **pause** is set, the gripper stops until users restore it manually;
- if **wait and retry** is set, the gripper will stop for a short period and then retry the operation until it succeeds.

3.6 Picking up and placing with the gripper

Block illustration



xx2200001340

Descriptions



Note

Gripper-related blocks are available for robots (except IRB 14050) configured with a gripper (other than ABB Smart Gripper) and its corresponding application add-in.

Grippers can pick up and place objects using any available configured tools.

- Pick up *<object>* at *<somewhere>* using *<tool>*
- Place item at *<somewhere>* using *<tool>*

The picking and placing blocks must be used in pair, and the tool selected in a pair of picking and placing blocks must be the same one.

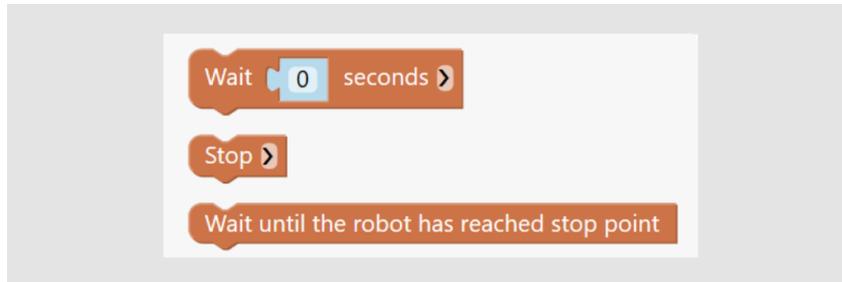
The blocks also allow to set optional parameters. For details about the parameters, including optional parameters, in the blocks, see [Parameters on page 35](#).

3 Programming with Wizard

3.7 Stopping and waiting

3.7 Stopping and waiting

Block illustration



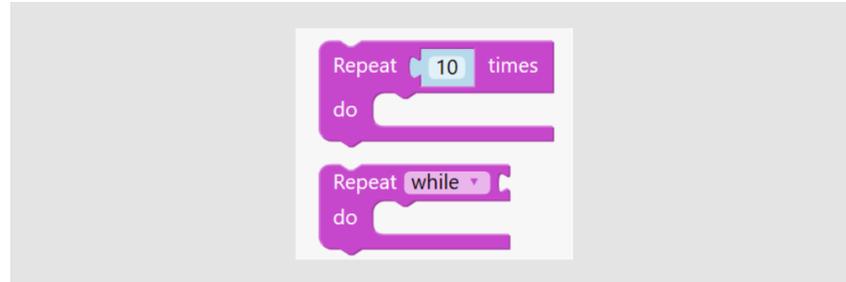
Descriptions

Use the **Stop & Wait** blocks to control the robot motion, stop or wait until a defined condition is met.

- Wait X seconds
- Stop
- Wait until the robot has reached stop point

3.8 Operation repetitions

Block illustration



xx2200001342

Descriptions

Operations can repeat for several times with a loop block is set. It can be a loop with defined repeated time or a while/until loop.

- `repeat X times`: defines the number that the blocks are to be repeated. The *X* parameter in the block must be set to a value equal to or larger than 1. The default repeated time is 10.
- `repeat while <condition> do <something>`: used when the blocks need to repeat under a condition. The judgement parameter can be set to `while` or `until`.

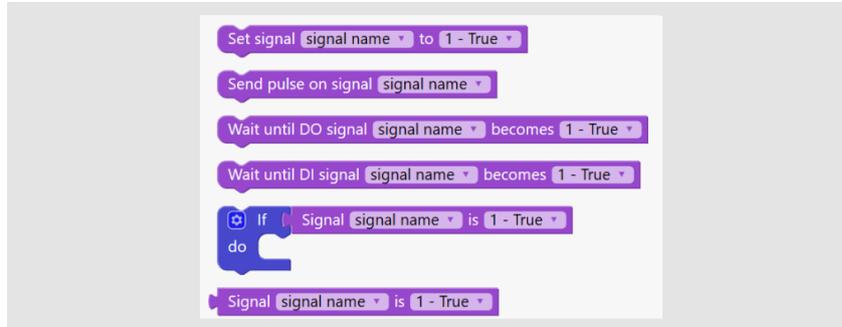
For details about the conditions, see [Trigger conditions on page 29](#).

3 Programming with Wizard

3.9 Working with I/O signals

3.9 Working with I/O signals

Block illustration



xx2200001343

Descriptions

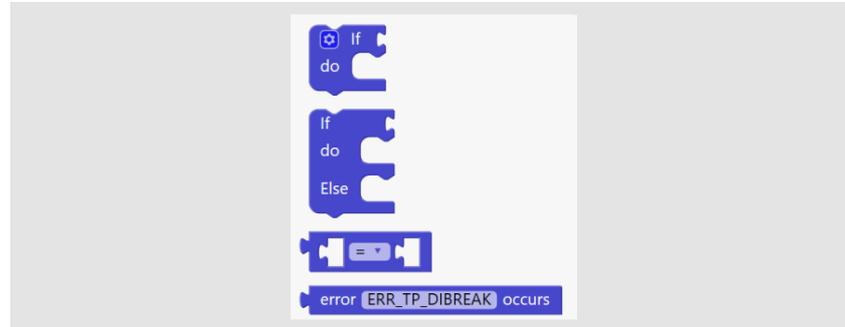
The signal blocks control the responses of the gripper with the I/O signal values **1-True** and **0-False**. Available signal blocks are listed as follows:

- set signal `<signal name>` to `1-True`
- send pulse on signal `<signal name>`
- wait until DO signal `<signal name>` become `1-True`
- wait until DI signal `<signal name>` become `1-True`
- if signal `<signal name>` is `1-True` do
- signal `<signal name>` is `1-True`

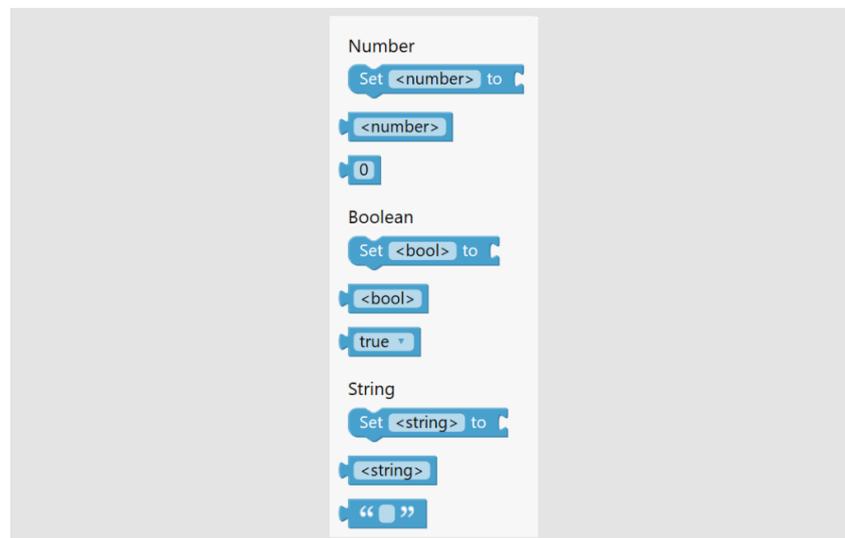
For details about the parameters in the blocks, see [Parameters on page 35](#).

3.10 Logical executions

Block illustration



xx2200001344



xx2200001345

Descriptions

To execute an operation under a specified condition, the **if** and **if else** blocks in the **Logic** block group are used. It is also possible to expand the **if** block to the **else** and **else if** blocks with more conditions by tapping the button at the left corner.

Trigger conditions

Both the **if** block and **while** loop block require a condition to take effect. The condition can be a signal, a variable, a logical expression or an error.

- The signal *<signal name>* is **1-True** block is used as the signal condition.
- A variable can be in number type, boolean type or string type. Both the variable name and variable value can be used as a condition.
- A logical expression can be used as a condition, in which the relationship between two variables are defined. The variables on the right and left sides of the relations operator must be the same type.
- The error *<error name>* **occurs** block is used as the error condition.

Continues on next page

3 Programming with Wizard

3.10 Logical executions

Continued

For details about the parameters in the blocks, see [Parameters on page 35](#).

Variable blocks

In the **Variable** block group, three types of variables are available, number, boolean and string.

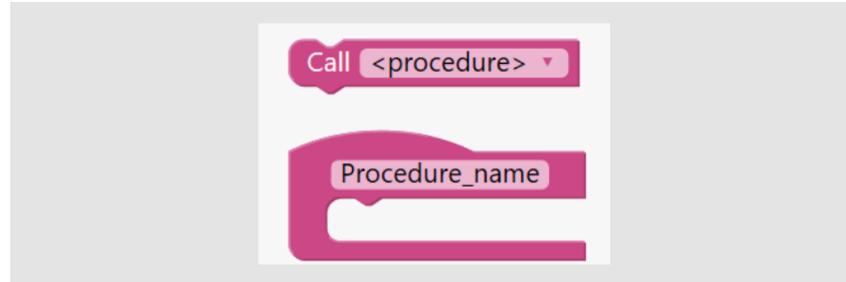
Both variable name and variable value can be user-defined. The `Set <variable name> to` block is used to assign a value to a specific variable. The default values of the numeric, boolean and string variables are **0**, **true** and **default**, respectively.

All the defined variables are listed in corresponding tab in **Data** window.

For details about the parameters in the blocks, see [Parameters on page 35](#).

3.11 Programming a subroutine

Block illustration



xx2200001346

Descriptions

Defining a subroutine

The *Procedure_name* block in the **Procedures** block group defines a subroutine. Users can edit the subroutine as they do in the main routine. All defined subroutines will be listed in the **Procedures** block group and available for use later as a normal instruction block. This facilitates the user in programming a number of blocks which need to be reused for several times.

It is possible to name every subroutine. Tapping *Procedure_name* displays a keyboard for entering the name.

Calling procedure

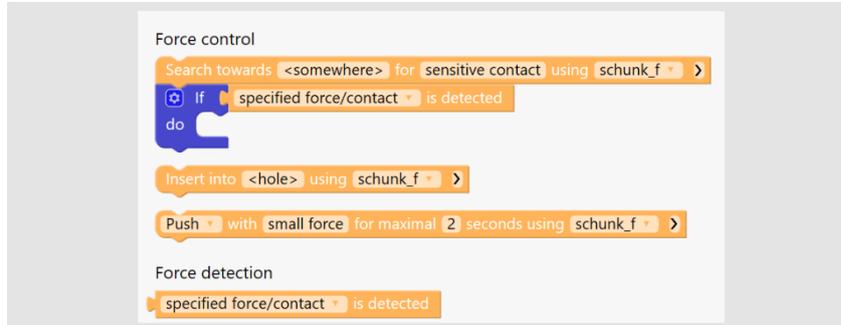
The *call <procedure>* block in the **Procedures** block group is used to call a defined and parameterless procedure from other modules in the active program in the controller.

3 Programming with Wizard

3.12 Searching and operating with force control

3.12 Searching and operating with force control

Block illustration



Descriptions



Note

The Force blocks are available only for robots configured with ABB force sensors. Please note that if force control is enabled, any defined force will have an impact on the robot movement speed.

Robots with Force Control are sensitive to contact forces. Use the Force blocks to control the robot to "feel" the surroundings and perform specified actions with force. Available force blocks are listed as follows:

- Search towards *<somewhere>* for *<sensitive contact>* using *<tool0>*: find whether a contact can be detected in the searching direction. Used together with a Logic block to define the following operations if a specified detection result is met. This block allows to set optional parameters.
- Insert into *<hole>* using *<tool0>*: insert an object. This block allows to set optional parameters.
- Push with *small force* for maximal *2* seconds using *<tool0>*: push or pull with force. This block allows to set optional parameters.
- *Specified force/contact* is detected: trigger condition used together with the searching for contact block.

For details about the parameters, including optional parameters, in the blocks, see [Parameters on page 35](#).

3.13 Working with ASI

Description



Note

Arm-side interface (ASI) is located on GoFa™ CRB 15000. Blocks added using ASI and ASI settings are available only on real controller.

The down button on the ASI is, by default, configured to add a Move block. It allows to change the block type by tapping **Help > ASI Setting**.

Pressing the button will add a Move block or a block containing only one location parameter, depending on the setting, with the current location of the cobot.

Buttons on the ASI could also be configured to other functions, such as gripper to control the opening and closing of the fingers on the gripper. For details about ASI, see *Product manual - CRB 15000*.

3 Programming with Wizard

3.14 Working with lead-through device

3.14 Working with lead-through device

Description



Note

The lead-through device is installed on SWIFTI™ robots. Blocks added using the buttons on the device and lead-through device settings are available only on real controller.

The flat button on the lead-through device is, by default, configured to add a Move block. It allows to change the block type by tapping **Help > Lead-through Device Setting**.

Pressing the button will add a Move block or a block containing only one location parameter, depending on the setting, with the current location of the cobot.

Buttons on the lead-through device could also be configured to other function, such as locking the movement along a specified direction. See the product manual of the manipulator for lead-through device button configuration details.

4 Defining parameters and data

4.1 Parameters

Predefined parameters

The following table lists the parameters whose values are predefined. Users can only choose a value from the parameter list during programming.

Parameter	In blocks...	Value
Motion speed	Move	The robot movement speed can be set to very quickly, quickly, moderately, slowly and very slowly , which corresponding to the movement speed v1000, v500, v200, v50 and v20 respectively.
Suction	Air	<p>The gripper can be configured with one or two vacuum modules. Vacuum2 is available only for the gripper with two vacuum modules.</p> <p>Vacuum1 and Vacuum2 are defined as follows.</p>  <p>xx1900002120</p>
Tool name	Gripper	All the configured tools are listed by tooldata name.
Signal name	Signals	All the configured I/O signals in the controller are listed.
Signal value	Signals	The values can be set to 1-True or 0-False for signal blocks.
Error name	Logic	Common errors are listed.
Contact type	Force	<p>Type of the contact to be searched for can be set.</p> <ul style="list-style-type: none"> • Sensitive(5N) is recommended for soft contact, such as foam board and sponge. The contact force is 5N. • Hard(10N) is recommended for hard contact, such as metal. The contact force is 10N. • For other contact types, user can customize a contact force that is suitable to be applied to the contact.
Push/pull	Force	It allows to set the robot behavior to push or pull an object.

Continues on next page

4 Defining parameters and data

4.1 Parameters

Continued

Parameter	In blocks...	Value
Pushing/pulling force	Force	The force that the robot uses to push or pull can be set to Small(10N) , Medium(14N) or a customized force.
Pushing/pulling duration	Force	It allows to set the duration that the robots pushes or pulls the object. The unit is seconds. The default value is 2s.

Customized parameters

The following table lists the parameters whose values can be customized.

Parameter	In blocks...	Value
somewhere	Move Finger Air Gripper Force	<p>Defines a destination location. Users can choose an existing location defined before or define a new location.</p> <ul style="list-style-type: none"> • If specified in Move blocks, it refers to the location where the gripper fingers or suction cups moves to. • If specified in Finger blocks, it refers to the location where the gripper fingers moves to. • If specified in Air blocks, it refers to the location where the gripper suction cups moves to. • If specified in Gripper blocks, it refers to the location where the gripper moves to. • If specified in Force blocks, it refers to the location towards which the robot will search along a defined direction (Tool Z direction by default). <p>For details about how to define a location, see Defining a location on page 39.</p>
object	Finger Air Gripper	<p>Defines the object that requires the gripper to pick up or place using fingers, suction cups or specified tools. The object defined in a pair of picking and placing blocks must be the same.</p> <p>It also defines the object to be released in Release <object> block in Gripper category. For details about how to define an object, see Defining an object on page 41.</p>
tray	Finger Air	<p>Defines the tray where the object to be picked up from or to be placed to. Users can specify the tray orientation and dimensionality. For details about how to define a tray, see Defining a tray on page 45.</p>
number/bool/string	Variables	<p>Defines a variable name or a variable value. It is also possible to assign a variable value to a specific variable using the Set <variable name> to block. For details about how to define a variable, see Defining a variable on page 47.</p>

Continues on next page

Parameter	In blocks...	Value
hole	Force	Defines the hole into which the object is insert. Users can choose an existing hole defined before or define a new hole. For details about how to define a hole, see Defining a hole on page 43 .

Optional parameters

Optional parameters are available in some blocks for user to extend settings.

Tapping the > button after the block displays the available optional parameters.

Parameter	Definition
\MaxTime	Defines the maximum amount of time in seconds that program execution waits. If no function key is pressed within this time then the program continues to execute in the error handler.
\DIBreak	Defines the digital signal that may interrupt the operator dialog. If no function key is pressed when the defined signal is set to 1 (or is already 1) then the program continues to execute in the error handler.
\WorkObject	Define the work object (coordinate system) to which the specified location in the block is related.
\Speed	<p>Defines the movement speed. Can be set to very quickly, quickly, moderately, slowly and very slowly, which corresponding to the movement speed v1000, v500, v200, v50 and v20 respectively by default.</p> <p> Note</p> <p>The movement speed to which each value corresponds can be modified by clicking Customize Speed. The modified speeds will be applied to all the blocks with a speed parameter of all the Wizard programs. The blocks customized in Skill Creator are not affected.</p>
Direction	<p>Defines the direction along which the tool moves.</p> <p>If no direction is defined, the tools moves along the Z- direction of TCP coordination system.</p>
InsertDuration	<p>Define the inserting duration from the insertion starting position to the desired inserted position when the robot inserts an object into a hole. The default duration is 10s.</p> <p>When force control is enabled, the actual robot movement speed depends on all of the defined force, moving distance and specified moving duration. If the duration is set to an extremely small value, the robot stops when the duration elapses, no matter it reaches the desired final position or not. If the duration is set to an extremely large value, the robot may reach the desired final position earlier than the defined duration to ensure the defined force could be achieved. In this case, always take the force and distance into consideration when setting the duration.</p>

Continues on next page

4 Defining parameters and data

4.1 Parameters

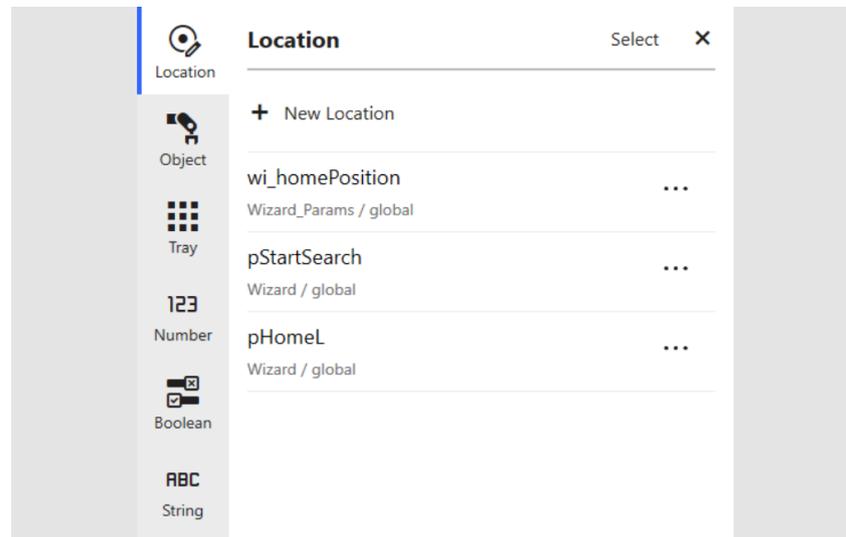
Continued

Parameter	Definition
SearchDuration	<p>Defines the searching duration from the starting position to the position of the object to be pushed/pulled when the robot pushes or pulls an object.</p> <p>When force control is enabled, the actual robot movement speed depends on all of the defined force, moving distance and specified moving duration. If the duration is set to an extremely small value, the robot stops when the duration elapses, no matter it reaches the desired final position or not. If the duration is set to an extremely large value, the robot may reach the desired final position earlier than the defined duration to ensure the defined force could be achieved. In this case, always take the force and distance into consideration when setting the duration.</p>

4.2 Data definition

4.2.1 Defining a location

Operation panel - Location



xx2200001348

Adding a location

- 1 Click **<somewhere>** in a block and then click **New Location** in the displayed **Location** tab page, or tap **Data > Location > New Location**.
- 2 In the displayed **Add new location wizard**, follow the instructions to add a new location.
The added locations are listed in the **Location** tab page.

Deleting a location

To delete a specific location,

- 1 Tap **Data > Location**.
- 2 In the displayed **Location** tab page, tap **More options** button next to the location you want to delete.
- 3 Tap **Delete**.
- 4 Tap **Delete** in the confirmation dialog box.
The location is now removed from the list.

To delete multiple locations,

- 1 Tap **Data > Location**.
- 2 In the displayed **Location** tab page, click **Select**.
- 3 In the displayed list, select the check boxes of all locations you want to delete.
- 4 Tap **Delete**.
- 5 Tap **Delete** in the confirmation dialog box.
The locations are now removed from the list.

Continues on next page

4 Defining parameters and data

4.2.1 Defining a location

Continued

Modifying a location

- 1 Tap **Data > Location**.
- 2 In the displayed **Location** tab page, tap **More options** button next to the location you want to modify.
- 3 In the displayed list,
 - to modify name,
 - a tap **Rename**.
 - b edit the new name in the text box.
 - c tap **Save**.
 - to modify location coordinates,
 - a tap **Update Location**.
 - b follow the instructions in the displayed **Update location wizard**.

Checking the location



Note

This function is valid only in manual mode and when the motor is on.

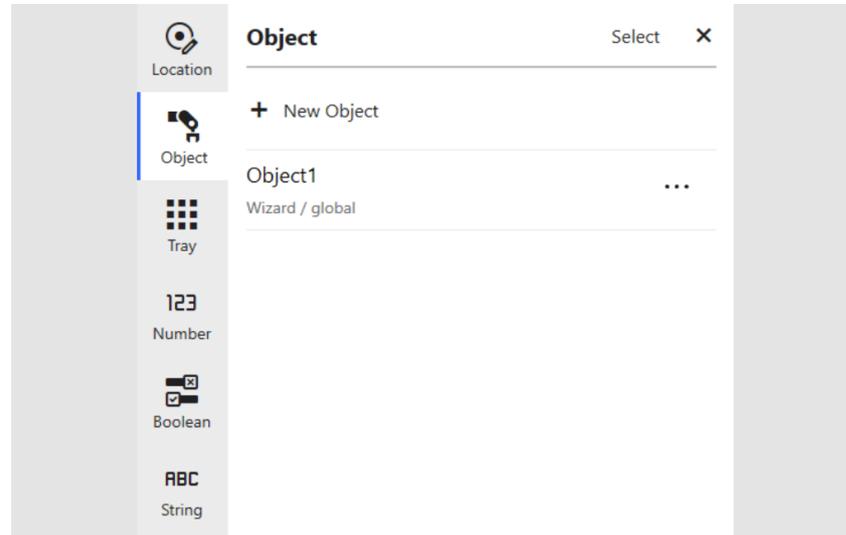
- 1 Tap **Data > Location**.
- 2 In the displayed **Location** tab page, tap **More options** button next to the location you want to check.
- 3 Tap **Go to**.
- 4 Choose the tool in use from the list.
- 5 Tap and hold **Press to Go to**.

About home location

A home position **wi_homePosition** is predefined for use. This position cannot be deleted but is allowed to be modified.

4.2.2 Defining an object

Operation panel - Object



xx2200001349

Adding an object

- 1 Click **<object>** in a block and then click **New Object** in the displayed **Object** tab page, or tap **Data > Object > New Object**.
- 2 In the displayed **Add new object** wizard, follow the instructions to add a new object.
The added objects are listed in the **Object** tab page.

Deleting an object

- 1 Tap **Data > Object**.
- 2 In the displayed **Object** tab page, tap **More options** button next to the object you want to delete.
- 3 Tap **Delete**.
- 4 Tap **Delete** in the confirmation dialog box.
The object is now removed from the list.

Modifying an object

- 1 Tap **Data > Object**.
- 2 In the displayed **Objects** tab page, tap **More options** button next to the object you want to modify.
- 3 Tap **Edit**.
- 4 In the displayed **Edit object** window, modify the required data:
 - object name
 - tool used for picking
 - grasping way of the fingers

Continues on next page

4 Defining parameters and data

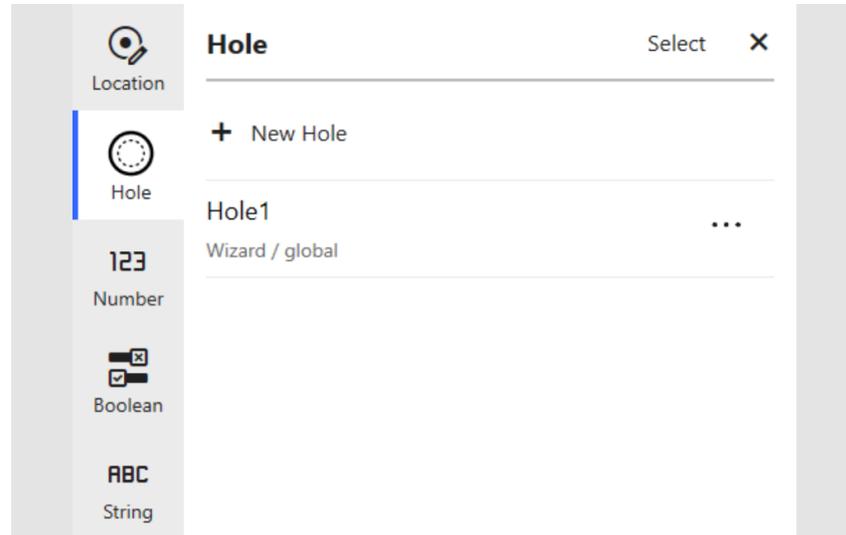
4.2.2 Defining an object

Continued

- finger position and holding force
- air pressure of the suction cup

4.2.3 Defining a hole

Operation panel - Hole



xx2200001357

Adding a hole

- 1 Click <hole> in a block and then click **New Hole** in the displayed **Hole** tab page, or tap **Data > Hole > New Hole**.
- 2 In the displayed **Add new hole wizard**,
 - a Jog the robot to the desired inserted position where the sensor pin is properly inserted into the hole, and click **Update position**.
 - b Click **Search starting position** to activate it.
 - c Jog the robot a position from where the search starts, and click **Update position**.
 - d If required, click **Lock tool direction** to open the **Lead-through** window (for collaborative robots) or **Joystick Jog** window (for industrial robots) in the **Jog** app and lock required direction.
 - e Enter a name for the hole in the **Hole name** text box, or keep the default provided name.
 - f Set the force used for searching the hole.
 - g Click **Test inserting** to verify the settings.
 - h If required, click **Advanced** to set the searching diameter.
The tool searches towards the hole in a spiral pattern. The searching diameter defines the circle that forms the spiral.
 - i Click **Save**.

The added holes are listed in the **Hole** tab page.

Deleting a hole

To delete a specific hole,

- 1 Tap **Data > Hole**.

Continues on next page

4 Defining parameters and data

4.2.3 Defining a hole

Continued

2 In the displayed **Hole** tab page, tap **More options** button next to the hole you want to delete.

3 Tap **Delete**.

4 Tap **Delete** in the confirmation dialog box.

The hole is now removed from the list.

To delete multiple holes,

1 Tap **Data > Hole**.

2 In the displayed **Hole** tab page, click **Select**.

3 In the displayed list, select the check boxes of all holes you want to delete.

4 Tap **Delete**.

5 Tap **Delete** in the confirmation dialog box.

The holes are now removed from the list.

Modifying a hole

1 Tap **Data > Hole**.

2 In the displayed **Hole** tab page, tap **More options** button next to the hole you want to modify.

3 Tap **Edit**.

4 In the displayed **Edit hole** window, modify the required data:

- inserted position and search starting position

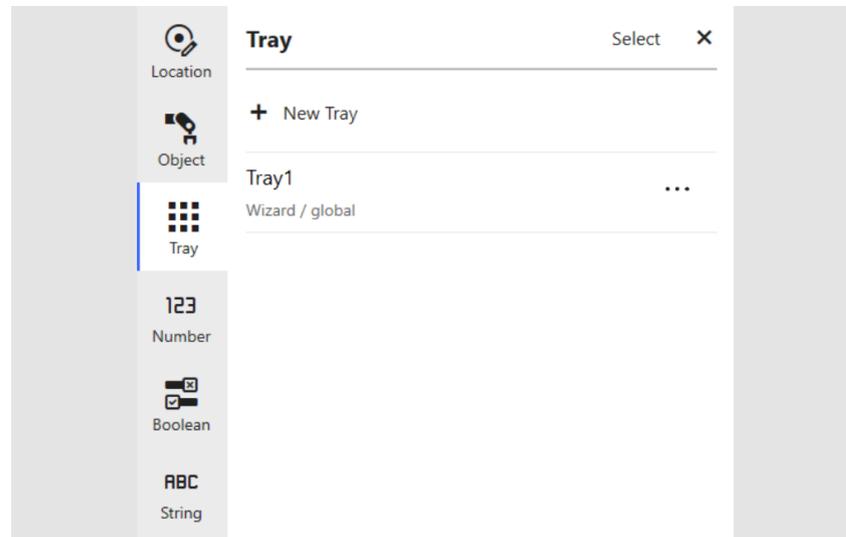
- hole name

- searching force

- searching diameter

4.2.4 Defining a tray

Operation panel - Tray



xx2200001350

Adding a tray

- 1 Choose **New Tray** from the <tray> drop-down list in a block, or tap **Data > Tray > New Tray**.
- 2 In the displayed **Add new tray wizard**, follow the instructions to add a new tray.
The added trays are listed in the **Tray** tab page.

Deleting a tray

To delete a specific tray,

- 1 Tap **Data > Tray**.
- 2 In the displayed **Tray** tab page, tap **More options** button next to the tray you want to delete.
- 3 Tap **Delete**.
- 4 Tap **Delete** in the confirmation dialog box.
The tray is now removed from the list.

To delete multiple trays,

- 1 Tap **Data > Tray**.
- 2 In the displayed **Tray** tab page, click **Select**.
- 3 In the displayed list, select the check boxes of all trays you want to delete.
- 4 Tap **Delete**.
- 5 Tap **Delete** in the confirmation dialog box.
The trays are now removed from the list.

Continues on next page

4 Defining parameters and data

4.2.4 Defining a tray

Continued

Modifying a tray

- 1 Tap **Data > Tray**.
- 2 In the displayed **Tray** tab page, tap **More options** button next to the tray you want to modify.
- 3 Tap **Edit**.
- 4 In the displayed **Edit tray** window,
- to modify the tray name, edit the new name in the text box and click **Save**.



Note

The information of the object arrangement in each tray dimension is shown for reference.

4.2.5 Defining a variable

**Note**

Following procedures are valid for all number, boolean and string variables. The number variable is used as an example.

Operation panel - Variable

Number variables

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Boolean variables

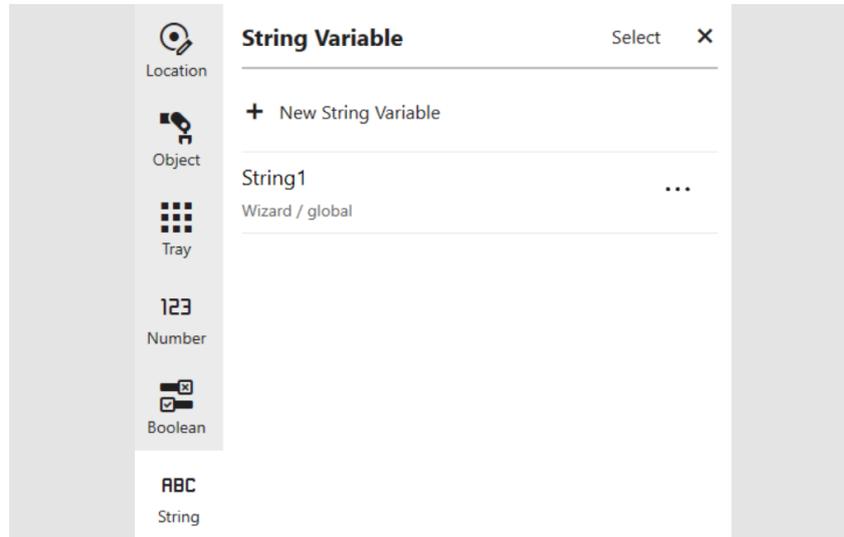
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4 Defining parameters and data

4.2.5 Defining a variable

Continued

String variables



Adding a variable

- 1 Click **<number>** in a variable name block or the **Set <number> to** block, or tap **Data > Number > New Number Variable**.
- 2 In the displayed **Add new number** window, edit the name in the **Variable name** text box.
- 3 Click **Save**.

Deleting a variable

To delete a specific variable,

- 1 Tap **Data > Number**.
- 2 In the displayed **Number Variable** tab page, tap **More options** button next to the variable you want to delete.
- 3 Tap **Delete**.
- 4 Tap **Delete** in the confirmation dialog box.
The variable is now removed from the list.

To delete multiple variables,

- 1 Tap **Data > Number**.
- 2 In the displayed **Number Variable** tab page, click **Select**.
- 3 In the displayed list, select the check boxes of all variables you want to delete.
- 4 Tap **Delete**.
- 5 Tap **Delete** in the confirmation dialog box.
The variables are now removed from the list.

Renaming a variable

- 1 Tap **Data > Number**.
- 2 In the displayed **Number Variable** tab page, tap **More options** button next to the variable whose name you want to modify.

Continues on next page

3 Tap **Rename**.

4 In the displayed window, edit the new name in the text box and click **Save**.

Data scope

The scope of data denotes the area in which the data is visible. The optional local directive of a data declaration classifies data as local (within the module), otherwise it is global. Note that the local directive may only be used at module level, not inside a routine.

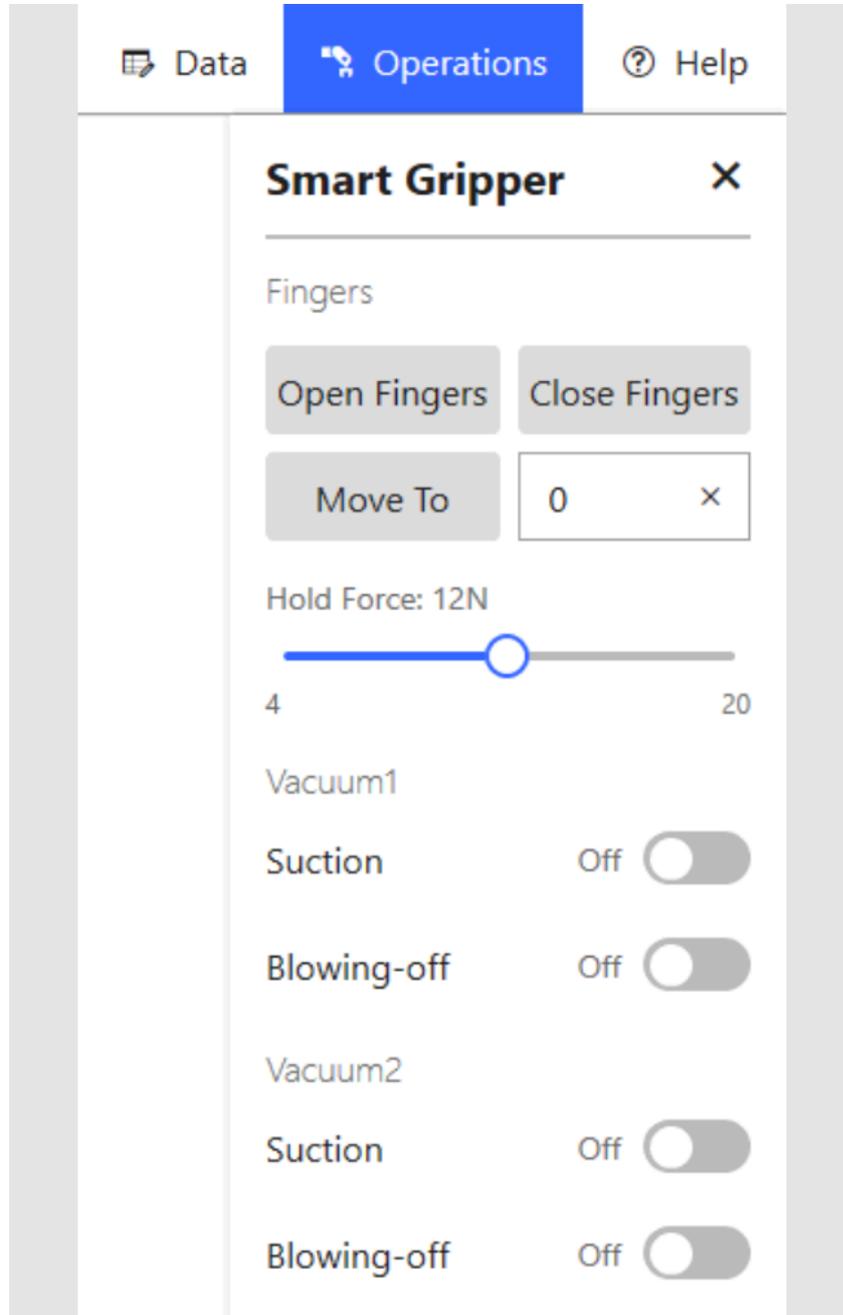
For more details about data scope, see *Technical reference manual - RAPID overview (3HAC050947-001)*.

4 Defining parameters and data

4.3 Operations

4.3 Operations

Smart Gripper



xx2200001354

Fingers



Note

The Finger tab page is available only for IRB 14050 having ABB Smart Gripper configured with fingers.

Continues on next page

Finger status is available for set. It can be opened, closed or moved to a specific distance. Specify the finger distance (unit: mm) in the text box and tap **Move to**. When the specified distance is reached, the finger movement stops. You can also tap **Stop** to manually stop its movement.

Hold force can also be set.

Vacuum modules



Note

The **Vacuum** tab page is available only for IRB 14050 having ABB Smart Gripper configured with one or two vacuum modules.

Air supply can be enabled for gripping objects using vacuum modules and disabled to remove suction and release object.

Two vacuum modules **Vacuum1** and **Vacuum2** are defined as follows.



xx1900002120

Gripper



Note

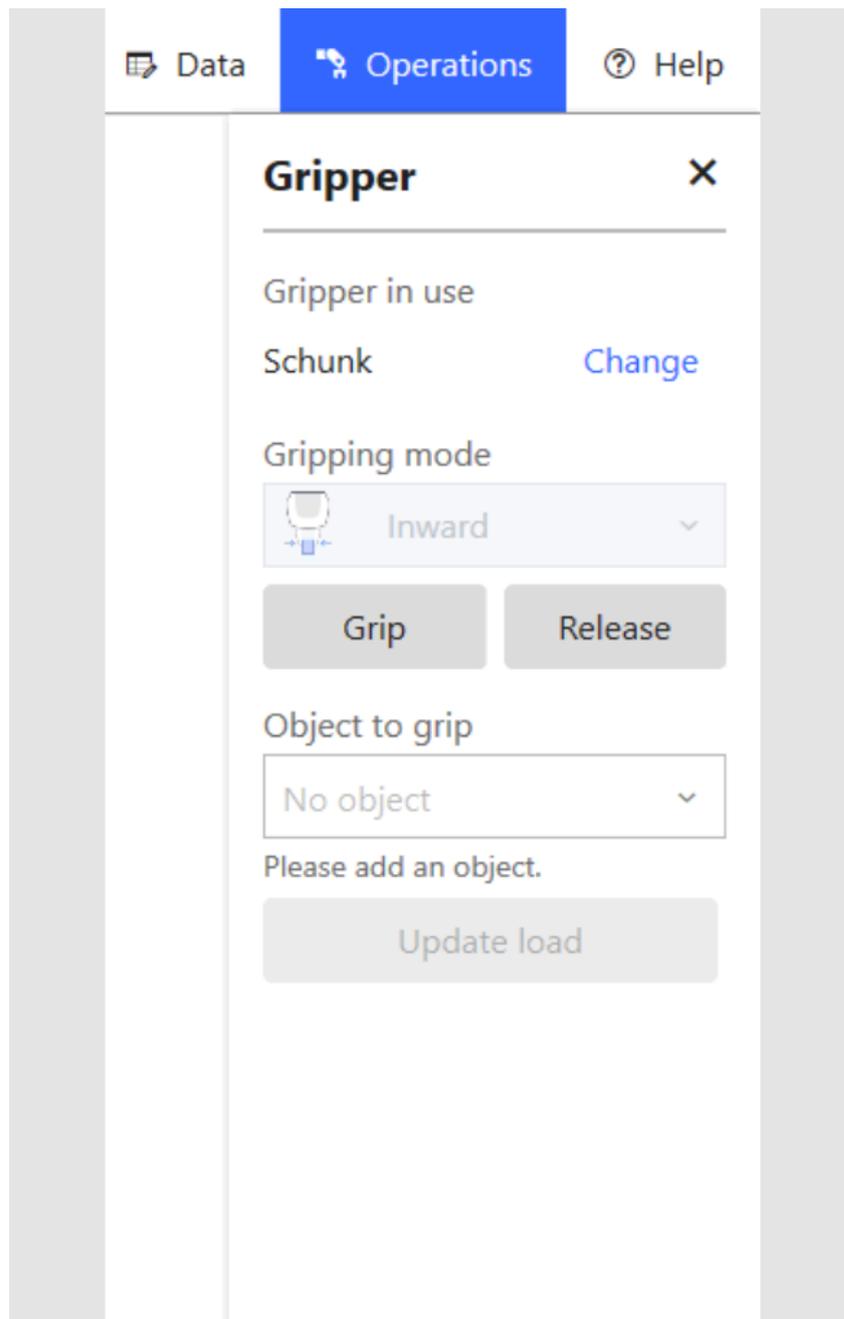
The **Gripper** tab page is available only robots (except IRB 14050) configured with a gripper and its corresponding application add-in.

Continues on next page

4 Defining parameters and data

4.3 Operations

Continued



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If it is detected that the robot is configured with a gripper, a dialog box is displayed when you enter the Wizard program for the first time, asking selecting the gripper in use. You can also change the gripper in the **Gripper** tab page.

The **Grip** or **Release** buttons are available to have quick gripping operations. For grippers with tools such as fingers, gripper modes **Inward** and **Outward** are available to choose; for grippers with tools such as suction cups, gripping mode **Vacuum** is available.

Existing objects are listed for a quick and easy selection for the gripper to grip or release. You could also click **New** and following the instructions in the displayed dialog box to create a new object.

Continues on next page

The object mass is displayed under the object list for a reference. Click **Update load** if it needs an update. For CRB 15000, the mass could be calculated automatically but is also allowed to enter manually. For other robots, you should always enter a mass value.

Other configurable parameters, such as hold force, can also be set if the gripper supports such functions.

4 Defining parameters and data

4.4 Shortcut menu

4.4 Shortcut menu

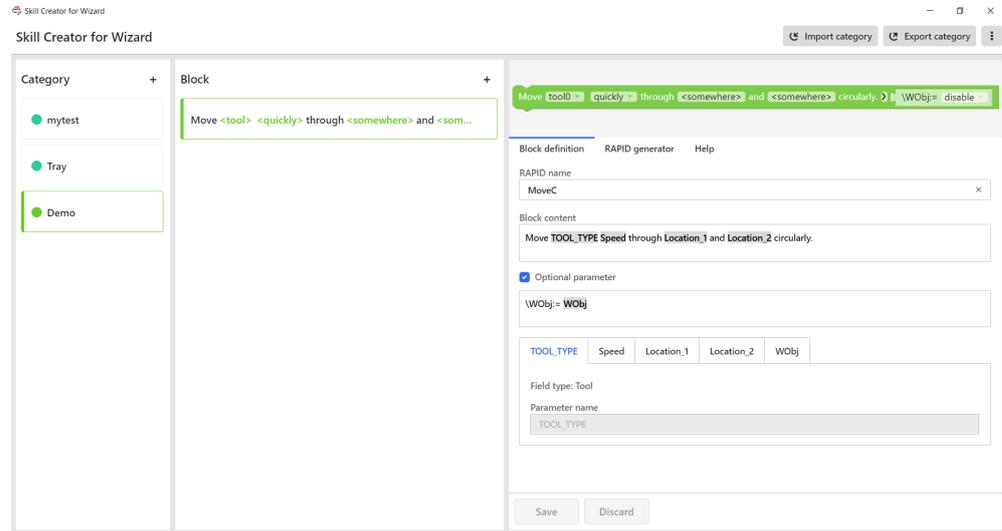
Shortcut commands

Tapping and holding a block or the blank area of the editing area displays the shortcut command list.

Command	Description
Play from this block	Executes the program from the selected block.
Update Location	Modifies the location coordinates in the Update location wizard. Valid only for the blocks having a location parameter.
Collapse Block(s)	Folds block(s) to display only a concise information of the block(s).
Expand Block(s)	Expands block(s) to show all information.
Delete Block/Delete X Blocks	Tapping a specific block and choosing Delete Block deletes only the selected block. Tapping the blank area and choosing Delete X Blocks deletes all the blocks under programming.
Duplicate	Creates a same block under the selected one.
Disable Block(s)	Disables the block(s) so that they will not be saved and functional in the program.
Highlight function definition	Goes to and highlights the Procedure block in the editing area.

4.5 Skill creator

Create your own blocks



xx2200001358

Skill Creator provides an open interface with which you can easily define your own blocks and related parameters. By exporting or importing categories, a group of blocks, to or from the real/virtual controller, you can expand the applications in Wizard.

If no controller is connected, it is also possible to manually load the categories to Wizard by placing the *CategoryName.coblox* file from Skill Creator folder to directory \$HOME/BlockLibrary/. The user-defined categories will display under Skill Creator group after restarting the FlexPendant. If a category created in Skill Creator already exists as default category in Wizard, the blocks created in this category will be merged in the Wizard-default category other than the Skill Creator group.

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