

secondpositio... 50% HY ROBOTICS ADMIN 16

Program

```
12 Move(pMoveTemporaryPos, vpUpCompletePos)
13 HYWaitMoveIsFinished()
14
15 IF MotionMode.i_M14 > 0 THEN
16 //Vertical Swivel - after traverse or in mold + trave
17 CALL SwivelReturn()
18 END_IF
19
20 IF bSimpleFlowChart = FALSE THEN
21 // Operating Mode -> Auto
22 IF (MotionMode.i_M06 = 2) OR (MotionMode.i_M06 = 4) T
23 //Main Arm Release - Multi Point Off or Multi + Orde
24 SetDO(douStackingComplete, ON)
25 IF palletcount = pallet1.numberofParts[0] * pallet
ountN1 < 0) OR (iWeightCountN2 < 0) c
onveyorOff,ON, rConvOnTime, FALSE)
ouConveyorOn, ON, rConvOnTime, FALSE)
:= 0
```

Keep editor in front

Show Commands

Graphical editor

Format

Deactivate

Set PC

Edit Selection Undo Remove

Param Pos Prog Config Signals

PWR

ERR

- +

- +

- +

- +

- +

- +

- +

Stop

Hand

Light

V- V+

Edit – Show Commands

Program

```
17 HYWaitForIMM()  
18 // START_EDIT  
19 // 2.00a.12  
20 HYTakeOutPosition(TakeOutPos, vpTakeOutPos, rKickRetu  
21 HYUpPosition(UpPos, vpUpPos, rUpDelay)  
22 HYRunnerRelease(SubArmReleasePos, vpSubArmReleasePos,  
23 HYMainRelease(MainArmReleasePos, vpMainArmReleasePos,  
24 HYRunnerReturnRelease(SubArmReleasePos, vpSubArmRelea  
25 HYInsertGripWaiting(InsertGripWaitingPos, vpInsertGri  
26 HYInsertGrip(InsertGripPos, vpInsertGripPos, rInsertG  
27 HYToWaitingPos(home position, vpWaitingPos, rDownDela  
28 // END_EDIT  
29 IF bOnlyOneAutoRun THEN  
30 BREAK
```

Movement	IMMIOActionAddToQueue
Homing	IMMIOActionQueueSet
Settings	IMMIOActionQueueClear
I/O-Control	IMMStartup
Flow Control	SetDO
Timing	PulseDO
HanYang	SetIMM

Edit Selection Remove

I/O Control – Pulse DO

secondpositio... 50% HY ROBOTICS

ADMIN 16

Program

```
11 pMoveTemporaryPos.Aux2 := Aux2-axis home position
12 Move(pMoveTemporaryPos, vpUpCompletePos)
13 HYWaitMoveIsFinished()
14
15 IF MotionMode.i_M14 > 0 THEN
16 //Vertical Swivel - after traverse or in mold + trave
17 CALL SwivelReturn()
18 END_IF
19
20 IF bSimpleFlowChart = FALSE THEN
21 // Operating Mode -> Auto
22 IF (MotionMode.i_M06 = 2) OR (MotionMode.i_M06 = 4) T
23 //Main Arm Release - Multi Point Off or Multi + Orde
24 SetDO(douStackingComplete, ON)
25 IF palletcount = pallet1.numberofParts[0] * pallet
26 IF (iWeightCountN1 <> 0) OR (iWeightCountN2 <> 0) C
27 PulseDO(douConveyorOff, ON, rConvOnTime, FALSE)
28 ELSE
29 PulseDO(douConveyorOn, ON, rConvOnTime, FALSE)
30 END_IF
```

PulseDO(douUserOutput1, 0.0)

Modify keyboard add DO Cancel Ok

Param Pos Prog Config Signals

PWR

ERR

- +

- +

- +

- +

- +

- +

- +

Stop

Hand

Light

V- V+

Modify

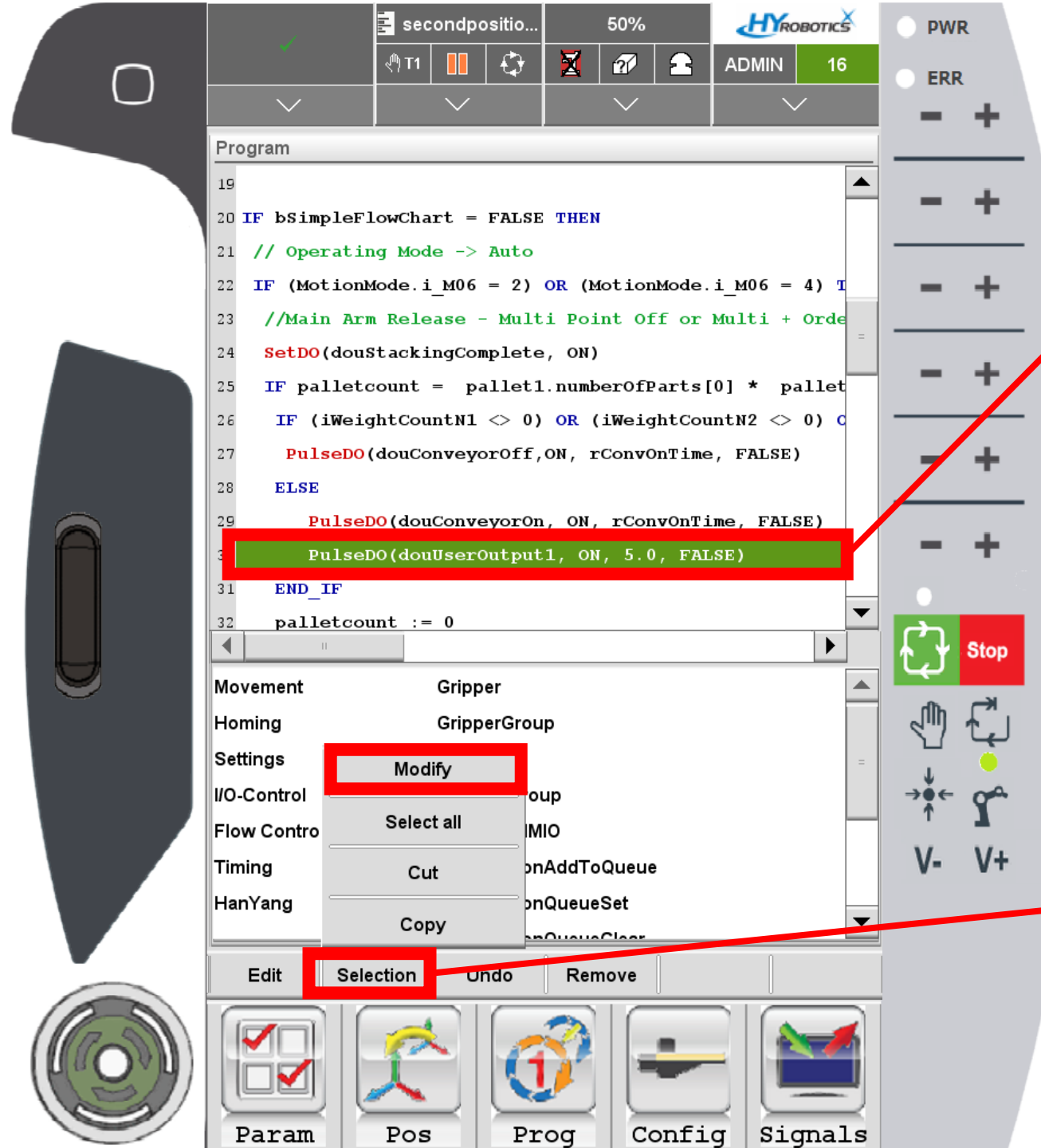
The screenshot shows a control interface for a robot. At the top, there's a status bar with 'secondpositio...', '50%', and 'HY ROBOTICS'. Below that, a 'PulseDO' configuration panel has three dropdown menus: 'Output (DOUT)' set to 'S douUserOutput1', 'State' set to 'ON', and 'Pulse length [s]' set to '0.0'. A 'Program' editor window shows code with the line 'PulseDO(douConveyorOn, ON, rConvOnTime, FALSE)' highlighted. At the bottom, a toolbar has an 'Ok' button highlighted in red.

You can select which User output to use.

ON

Type pulse length.
It is seconds.

Hit OK



DO command added.
Robot will turn on DO1
for 5 seconds.

If you want to modify
the command,
Selection - Modify