

PICK UP THE INSERTS USING MOVE UNTIL COMMAND

EPIK / UNIK



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STEP 1

ADD “VACUUM ON” COMMAND

**WE NEED TO TURN ON VACUUM FIRST
BEFORE MOVE UNTIL COMMAND**

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 Undo Remove

Go to Program Editor

I/O Control

Set DO

SetDO(douChuck)

Modify Keyboard add DO Cancel Ok

Press Modify

SetDO

Output (DOUT)	S douVacuum	▼
State	ON	▼
<input type="checkbox"/> Set output while robot is moving		
Feedback (DIN)	∅ < no Value >	▼
Feedback timeout [s]	∅ < no Value >	▼
<input type="checkbox"/> Halt program until feedback signal is set		

Select **Vacuum 1**
State **ON**

Press



You may add vacuum 2 ~ 4 if applicable.



STEP 2

**ADD MOVE UNTIL COMMAND
&
A POSITION**



```
Program
9
10 IF bSimpleFlowChart = TRUE THEN //181219_move_WJM
11   Dynamic(10, 10, 10)
12 ELSE
13   Dynamic(100, 100, 100)
14 END_IF
15
16 WHILE bAutoRun AND NOT ((bContinueToProduce = FALSE) A
17   HYWaitForIMM()
18   // START_EDIT
19   // 2.00a.12
20   SetDO(douVacuum, ON, FALSE, , , FALSE)
21   HYTakeOutPosition(TakeOutPos, vpTakeOutPos, rKickRetd
22   HYUpPosition(UpPos, vpUpPos, rUpDelay)
```

Movement	Move
Homing	MoveOvl
Settings	MoveAxis
I/O-Control	MoveCirc
Flow Control	MoveUntil
Timing	StopRobot
HanYang	Palletize
	AfterPalletize

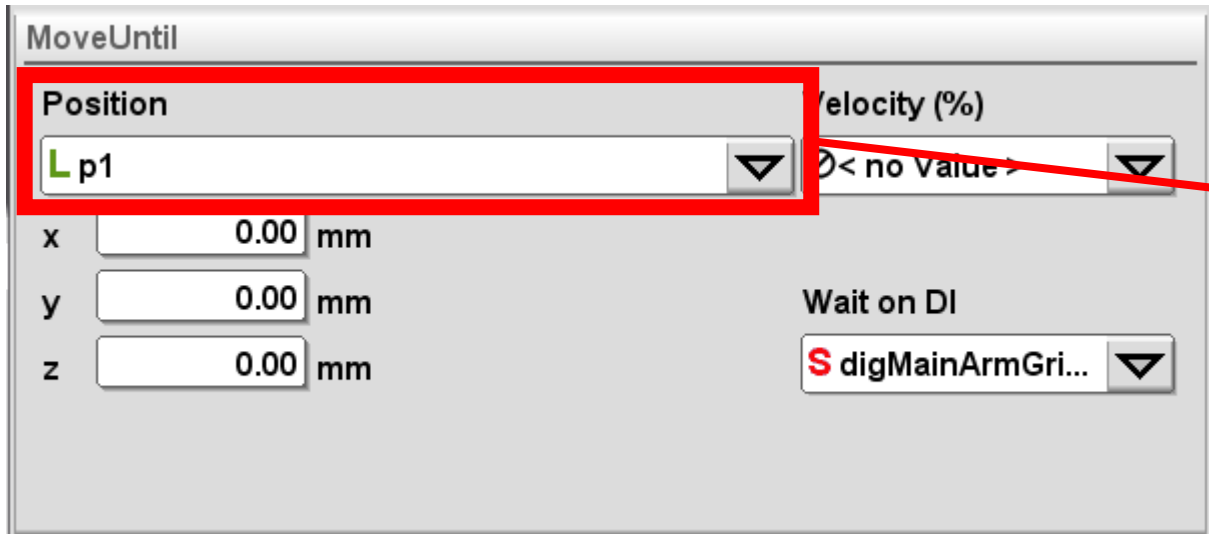
Edit | Selection | Undo | Remove

Movement
↓
Move Until

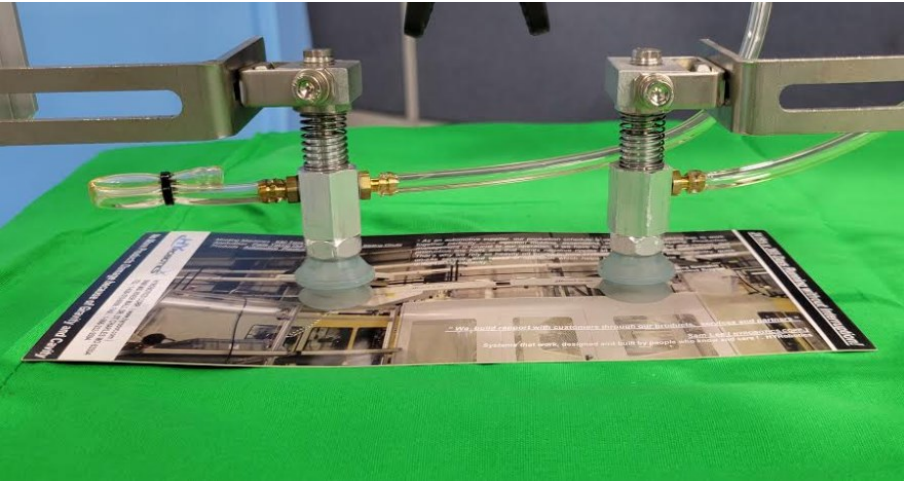
← MoveUntil(p1, , digMainArmGripConfirm) →


Modify | Keyboard | add DO | Cancel | Ok

Press Modify

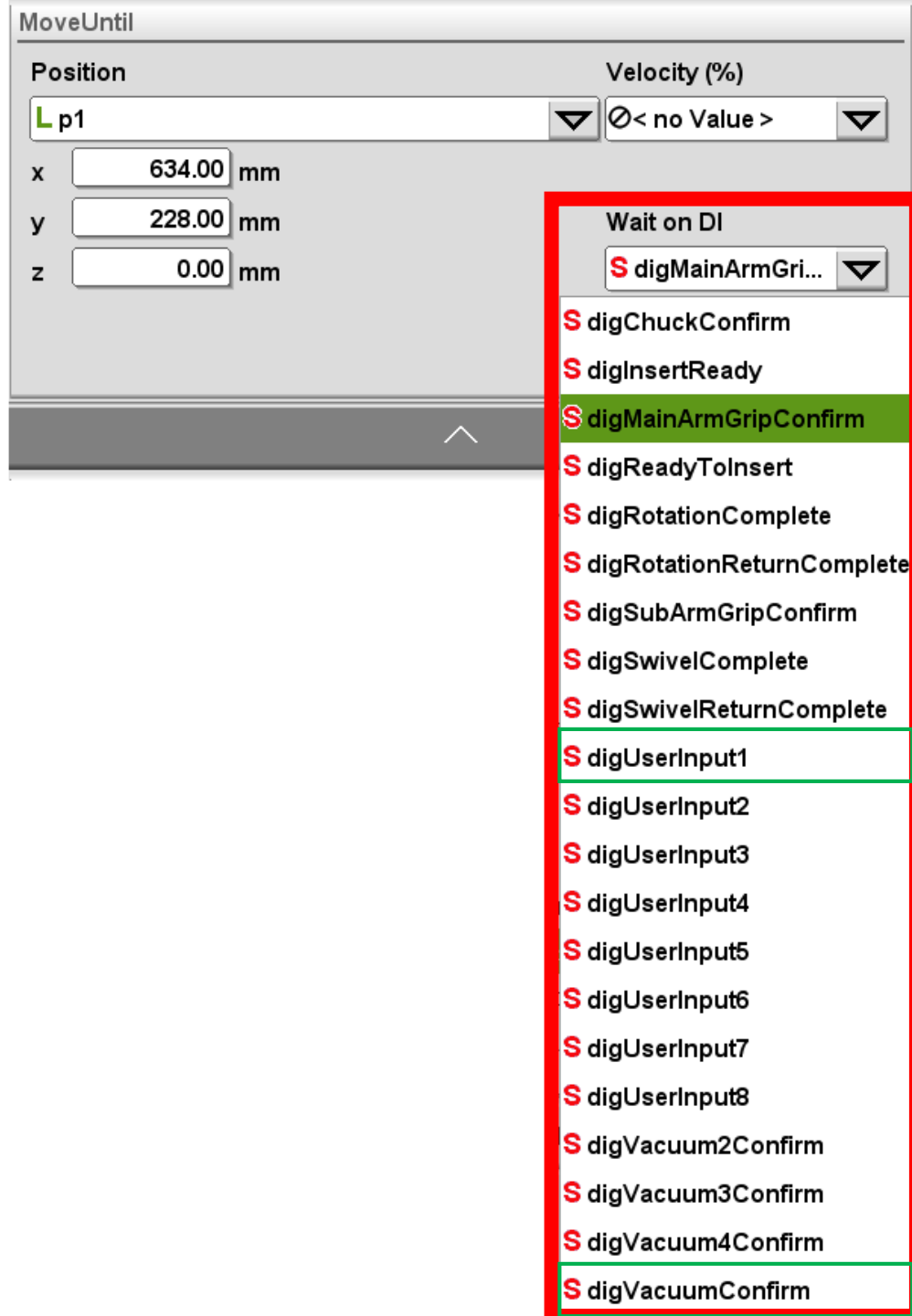


This is the position the robot moves to.



Move the robot to the position,
And press  .

Automatically new position(p1~pn) will be added.
(Or you can select an existing position.)



Select the input signal.

The robot will move until p1.

If it gets the signal, it will stop immediately and move on to the next command line.

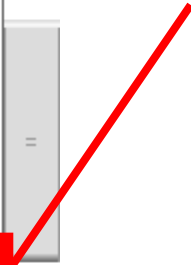
Most of the time,

Vacuum confirm, or User Input signals are used.

Press OK to add the command

```
Program
13   Dynamic(100, 100, 100)
14 END_IF
15
16 WHILE bAutoRun AND NOT ((bContinueToProduce = FALSE) A
17   HYWaitForIMM()
18   // START_EDIT
19   // 2.00a.12
20   SetDO(douVacuum, ON, FALSE, , , FALSE)
21   MoveUntil(p1, , digVacuumConfirm)
22   HYTakeOutPosition(TakeOutPos, vpTakeOutPos, rKickRetu
23   HYUpPosition(UpPos, vpUpPos, rUpDelay)
24   HYRunnerRelease(SubArmReleasePos, vpSubArmReleasePos,
25   HYMainRelease(MainArmReleasePos, vpMainArmReleasePos,
26   HYRunnerReturnRelease(SubArmReleasePos, vpSubArmRelea
```

Move Until command is added



ATTENTION!

1. Must understand that the robot moves **the shortest distance to the added positions.**
You will need to add several positions.

For example, If you are picking up parts at an added position, there should be another position at right angles from the picking up position above.

2. If you use Move Until command with Vacuum check sensor, the robot speed **must not to be too fast.**

I recommend you to add a position right before pick up the parts so that you can lower the speed at certain point.

Sample video
(Move Until Vacuum check)

<https://youtu.be/kAdBuHG7NI4>

