



CORE CONTROL MANUAL

EPIK / UNIK



HY ROBOTICS

24%

TEACH 7

Settings

User	teacher	
Level	7	Logout
Control authority	<input checked="" type="checkbox"/>	
Language	English	

Details

Displaylock

Robot control authority

Control authority

Device: T70IMM (SIM)

Device IP: 192.168.100.3

Settings Users Version Info Network

Menu Mold Speed Timer Signals

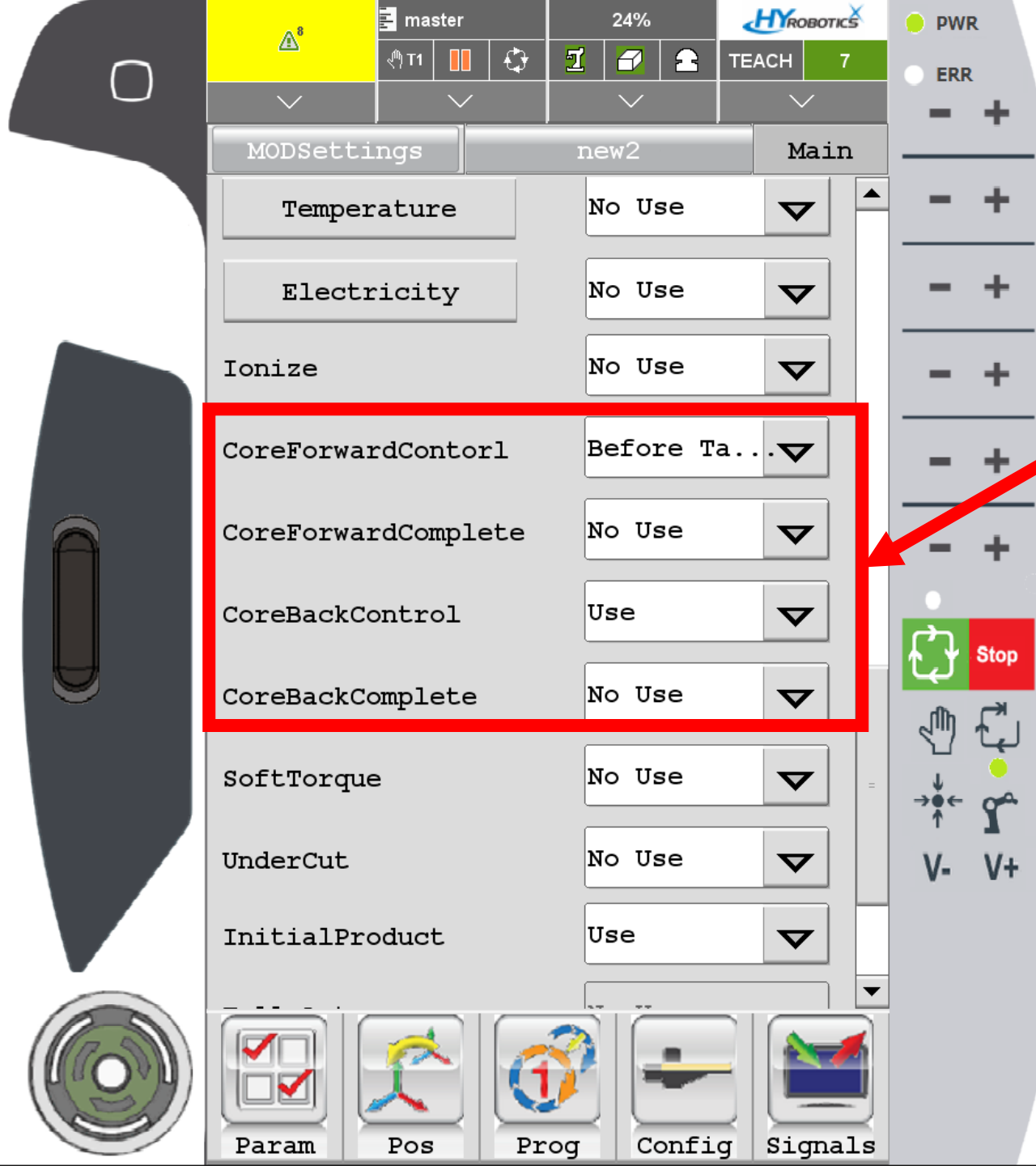
**Log in as
Level 7 or above.**



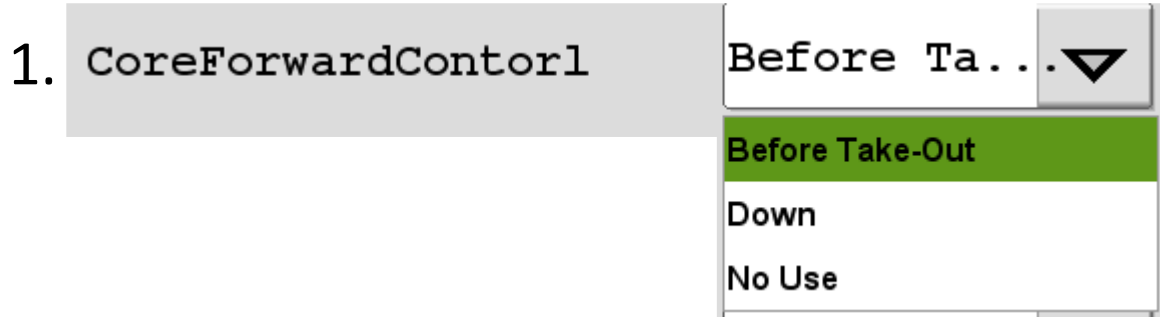
Go to MENU

The image shows a screenshot of a robotic control interface. At the top, there is a status bar with 'master', '24%', and 'HY ROBOTICS' logo. Below this is a navigation bar with 'Main', 'new2', and 'Main' tabs. The main area is divided into 'Product Info' and 'Report' sections. The 'Product Info' section contains fields for 'ProducedQuantity' (34), 'OKCycles' (28), 'NOKCycles' (6), 'ResidualQuantity' (0), 'CycleTime' (66.34 s), and 'TakeOutTime' (12.60 s). The 'Report' section contains 'GoalQuantity' (23), 'CavityQuantity', 'Reset', 'Counter Holding', 'Step', '1Cycle', 'Origin', and 'Buzzer'. At the bottom, there is a row of buttons: 'Menu', 'Mold', 'Speed', 'Timer', and 'Signals'. A red arrow points from the text 'Go to MENU' to the 'Menu' button. The 'Menu' button is highlighted with a red box.

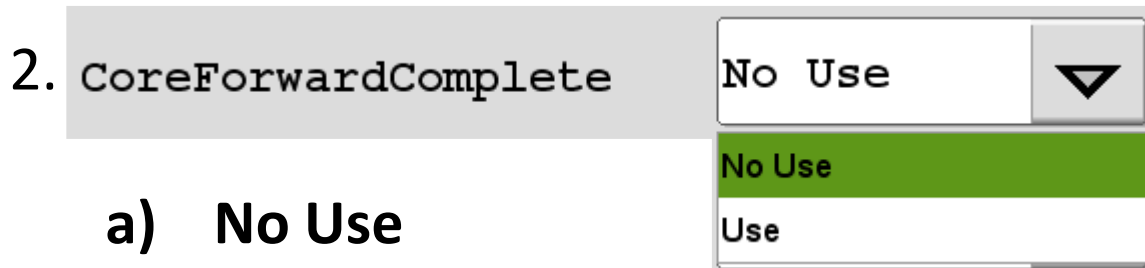
Field	Value
ProducedQuantity	34
OKCycles	28
NOKCycles	6
ResidualQuantity	0
CycleTime	66.34 s
TakeOutTime	12.60 s
GoalQuantity	23
CavityQuantity	
InitialProduct	0
WarningQuantity	0



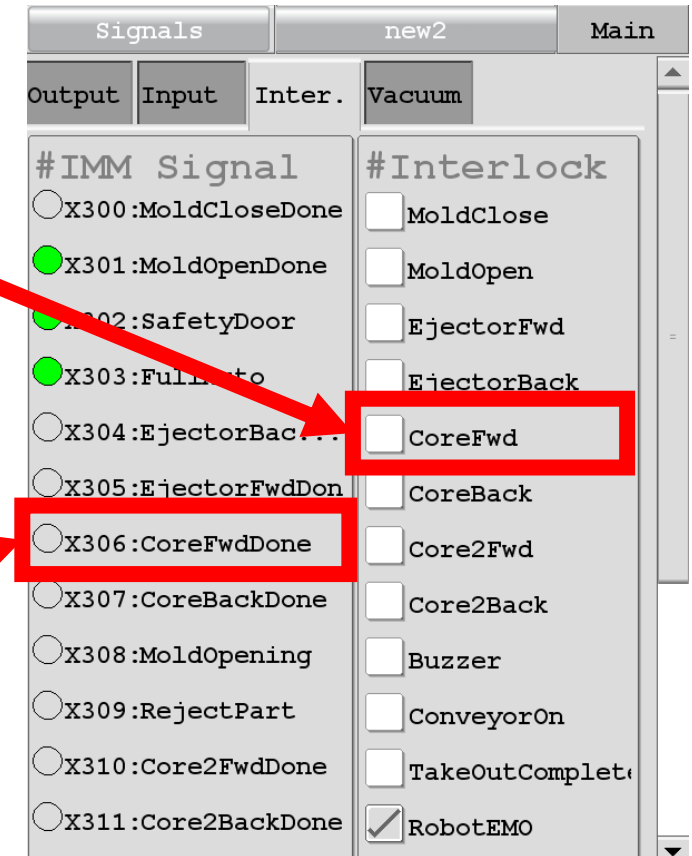
Find Core Control setting



- a) **Before Take Out:** Turn on Core Forward Interlock signal right before taking out.
- b) **Down:** Turn on Core Forward Interlock signal while the robot arm goes down.
- c) **No Use**



- a) **No Use**
- b) **Use:** The robot waits for Core Forward Completion signal after going down to takeout position.



3. CoreBackControl

Use	▼
No Use	
Use	

a) **Use:** Turn on Core Back Interlock signal after the parts are taken out.

b) **No Use**

4. CoreBackComplete

No Use	▼
No Use	
Use	

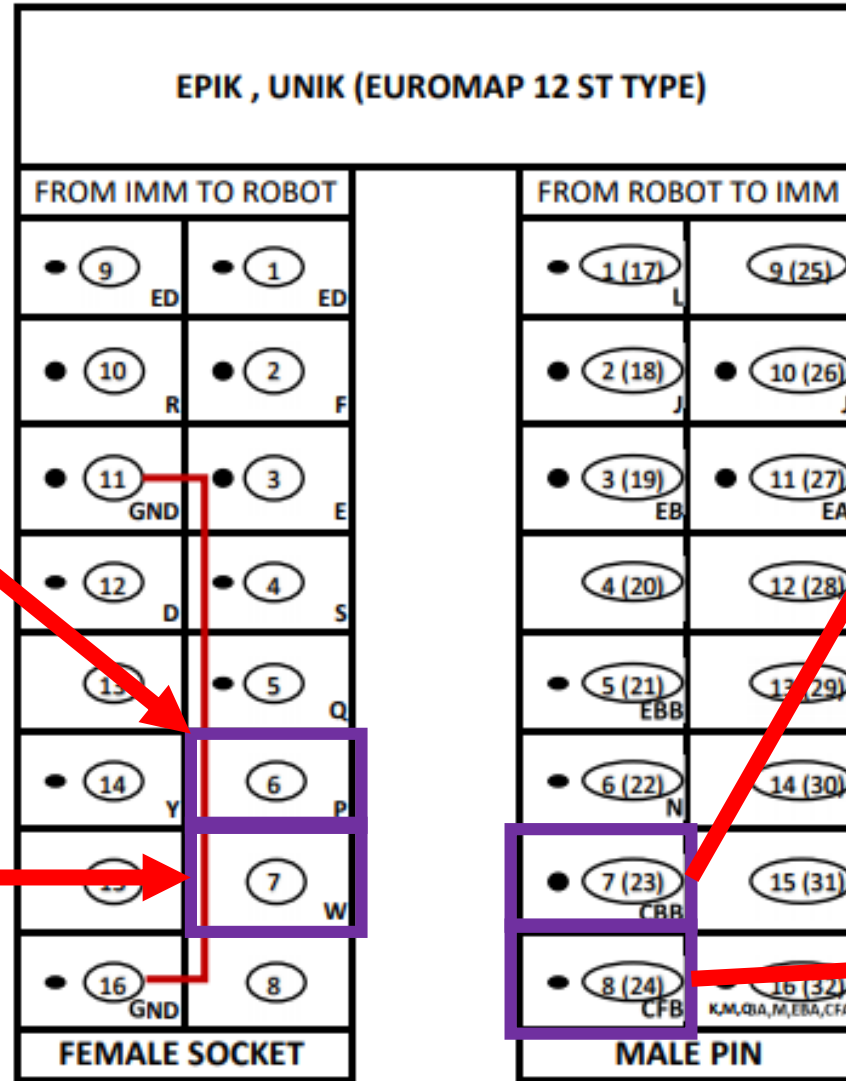
a) **No Use**

b) **Use:** The robot waits for Core Back Completion signal after taking out.

Signals		new2	Main
Output	Input	Inter.	Vacuum
#IMM Signal		#Interlock	
<input type="radio"/> X300:MoldCloseDone		<input type="checkbox"/> MoldClose	
<input checked="" type="radio"/> X301:MoldOpenDone		<input type="checkbox"/> MoldOpen	
<input checked="" type="radio"/> X302:SafetyDoor		<input type="checkbox"/> EjectorFwd	
<input checked="" type="radio"/> X303:FullAuto		<input type="checkbox"/> EjectorBack	
<input type="radio"/> X304:EjectorBackDone		<input type="checkbox"/> CoreFwd	
<input type="radio"/> X305:EjectorFwdDone		<input type="checkbox"/> CoreBack	
<input type="radio"/> X306:CoreFwdDone		<input type="checkbox"/> Core2Fwd	
<input type="radio"/> X307:CoreBackDone		<input type="checkbox"/> Core2Back	
<input type="radio"/> X308:MoldOpening		<input type="checkbox"/> Buzzer	
<input type="radio"/> X309:RejectPart		<input type="checkbox"/> ConveyorOn	
<input type="radio"/> X310:Core2FwdDone		<input type="checkbox"/> TakeOutComplete	
<input type="radio"/> X311:Core2BackDone		<input checked="" type="checkbox"/> RobotEMO	

WIRING: EUROMAP 12

*WIRING CHANGE MAY BE REQUIRED



6

Core 1 Forward Complete signal from IMM.

X306:CoreFwdDone

7

Core 1 Back Complete signal from IMM

X307:CoreBackDone

23

Enable interlock signal for movement of Core 1 to forward

CoreFwd

24

Enable interlock signal for movement of Core 1 to back

CoreBack

WIRING: EUROMAP 67

*WIRING CHANGE MAY BE REQUIRED

ZB5

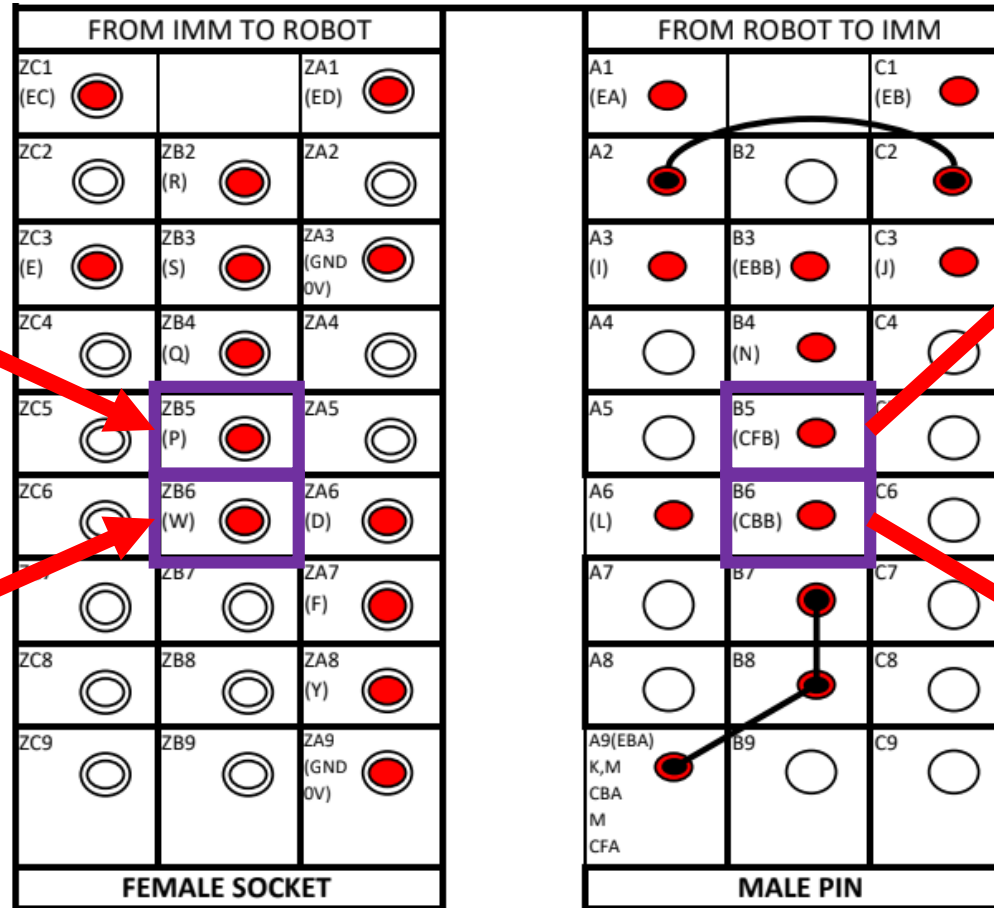
Core 1 Forward Complete signal from IMM.

X306:CoreFwdDone

ZB6

Core 1 Back Complete signal from IMM

X307:CoreBackDone



B5

Enable interlock signal for movement of Core 1 to forward

CoreFwd

B6

Enable interlock signal for movement of Core 1 to back

CoreBack

