

Gantry-Application Tutorial

Course: TMKU01

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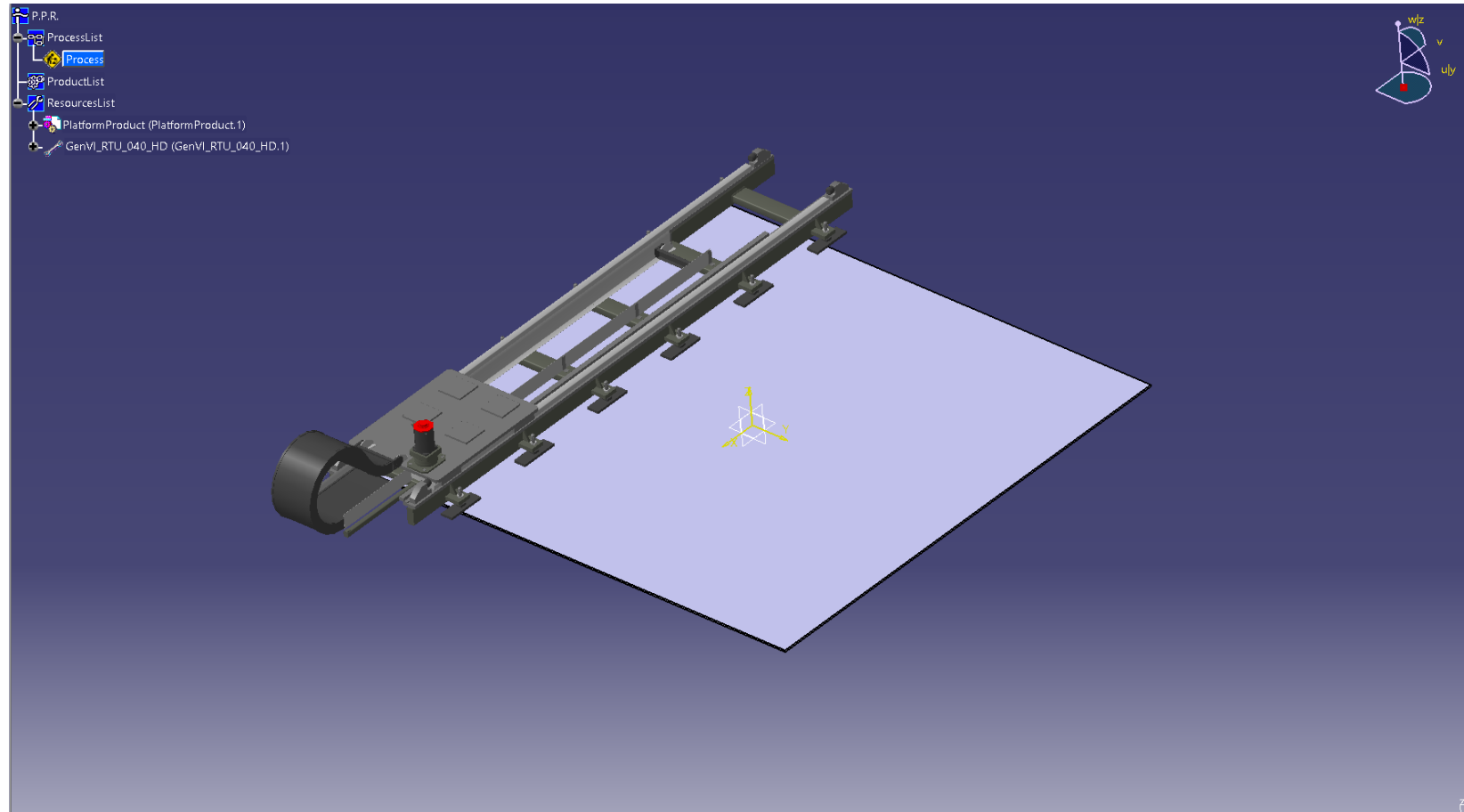
Nikhil Bhargav

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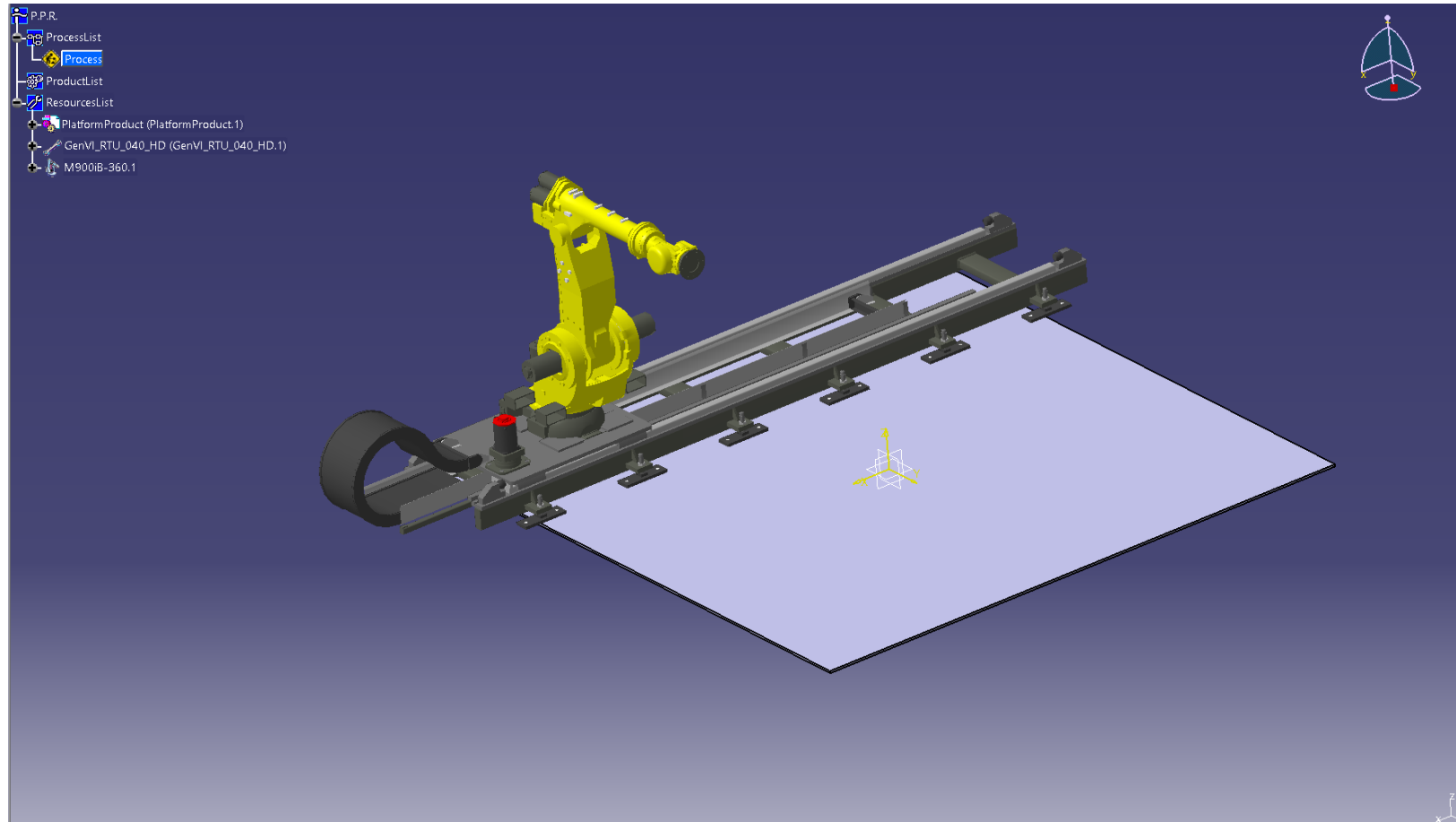
Start with Inserting any Gantry

For this Example: FANUC: GenVI_RTU_040_HD.1



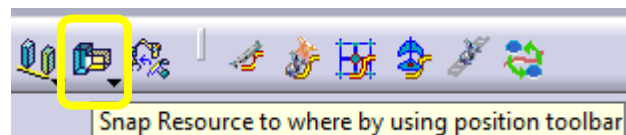
Import the required robot

For this Example: FANUC: M900iB-360.1



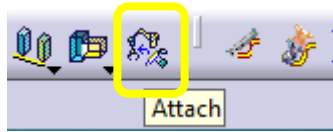
Note: The object (Robot) can be placed at desired location using the snap option ("Snap Automatically to Selected Object")

Or
Using this option

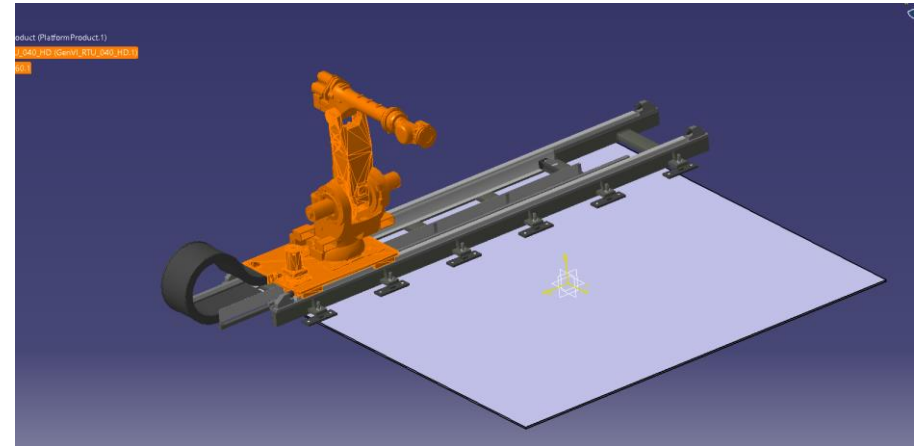
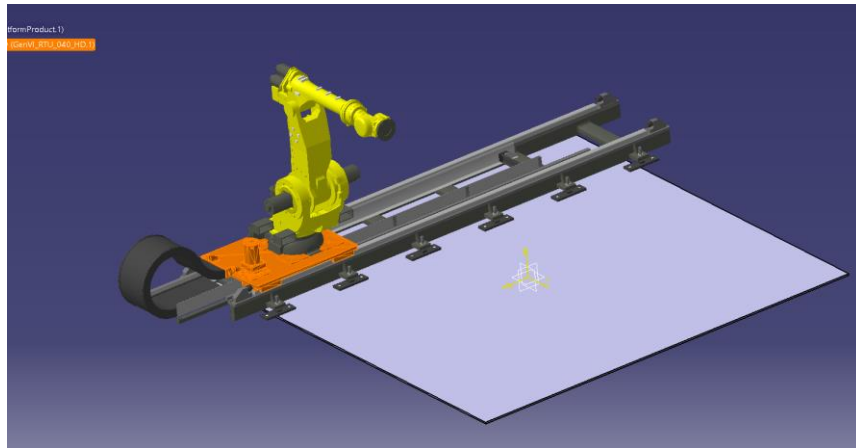


Use the Attach the robot to Gantry

- Click on



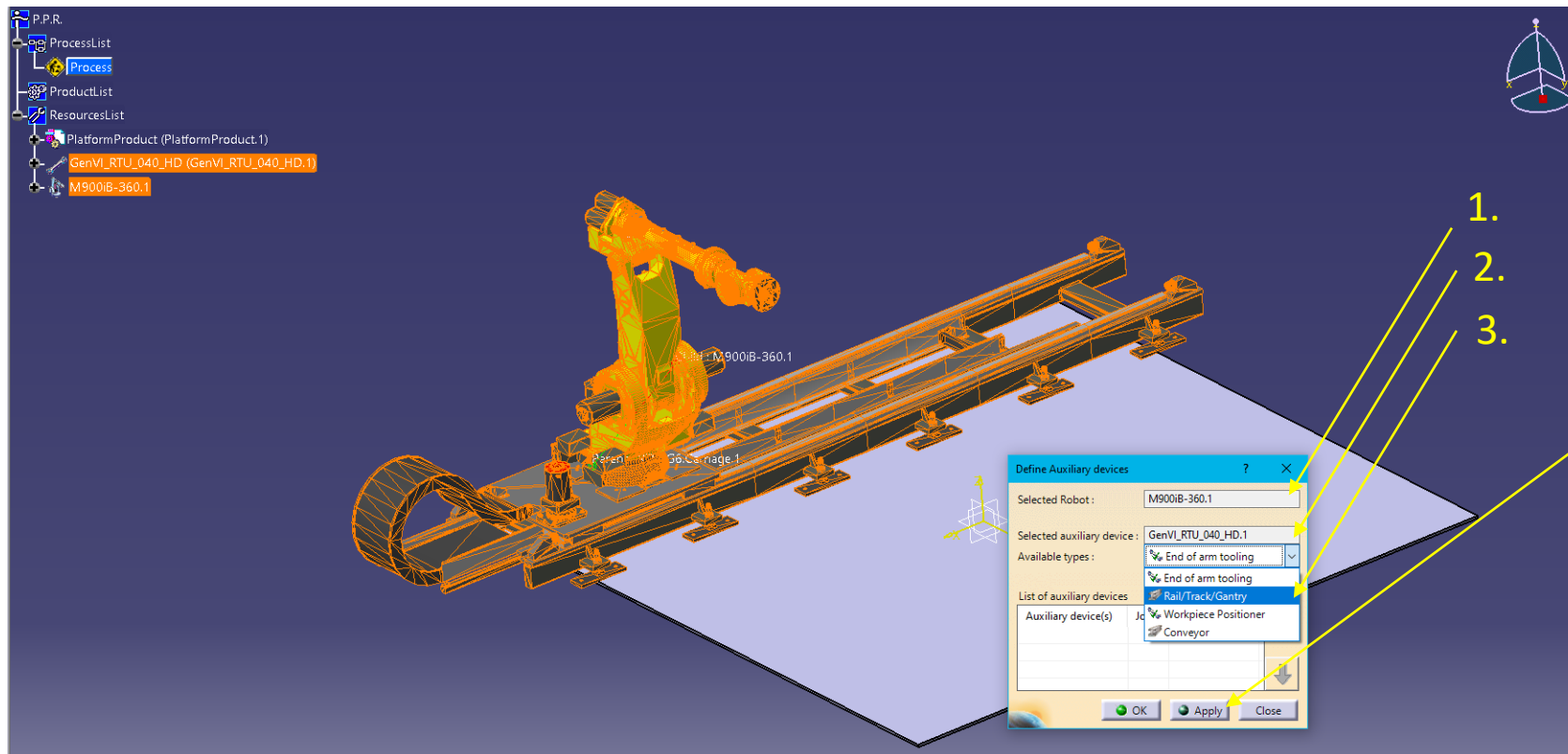
- Click on the gantry rest table (Parent) and then on the robot (Child) to attach it



- Click OK

Now we define the Auxiliary device

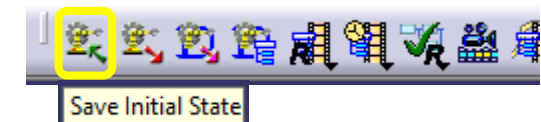
- Click on



1. Select the Robot
2. Select the Gantry
3. Select the "Rail/Track/Gantry"

Then Click on Apply

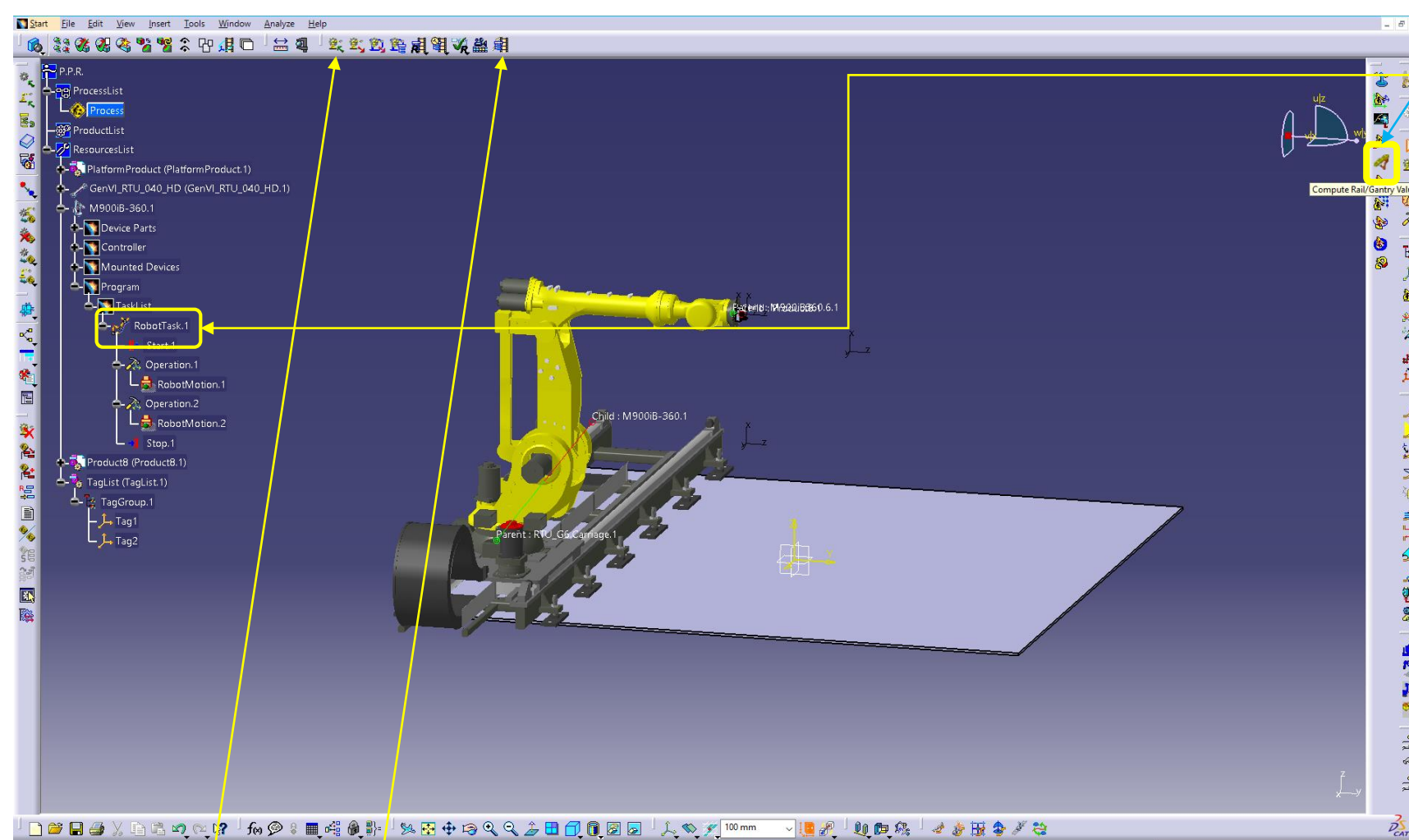
- From the previous tutorials add the end effector/tool for the robot
- Then Click on "Save initial state"



Defining of Tag and Robot motion

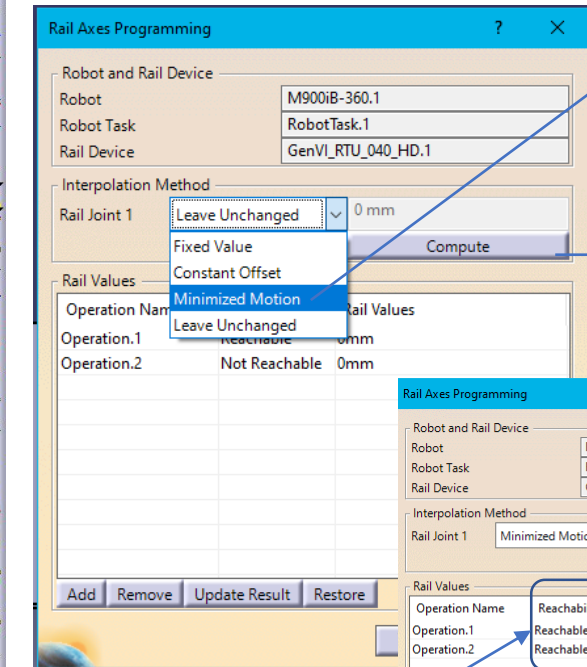
- This step would be the same as you have done for the previous tutorials
- Just neglect/ignore all the warning message on non-rechability of the robot, the next slides will give a fix for these...

- Once the Tags and robot motion is given it should look something like this



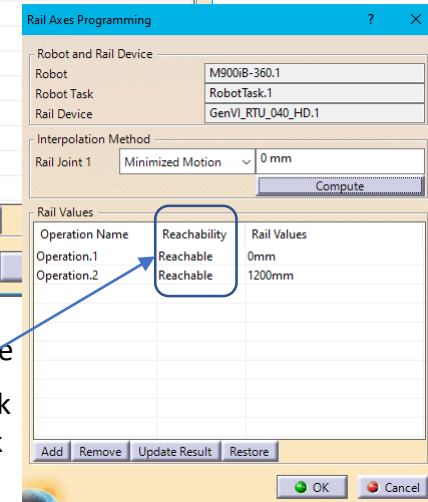
- Click on this option, this is done to check the robot and the gantry reach
- Then select the Robot Task which you have created

3. This should pop-up



4. Select Minimized Motion

5. Then Click on compute



6. Note the changes it Becomes reachable

Note: It will show "Not Reachable" for pick and drop operation, thats fine, it will work

7. Click on "Save Initial State"

8. Run the Robot Using "Robot Task Simulation"