

Sysmac Library for NJ/NX/NY Controller

SYSMAC-XR009

Adept Robot Control Library



Install and manage robots easily.

Issue 1 There is no time to learn a new robot programming language.

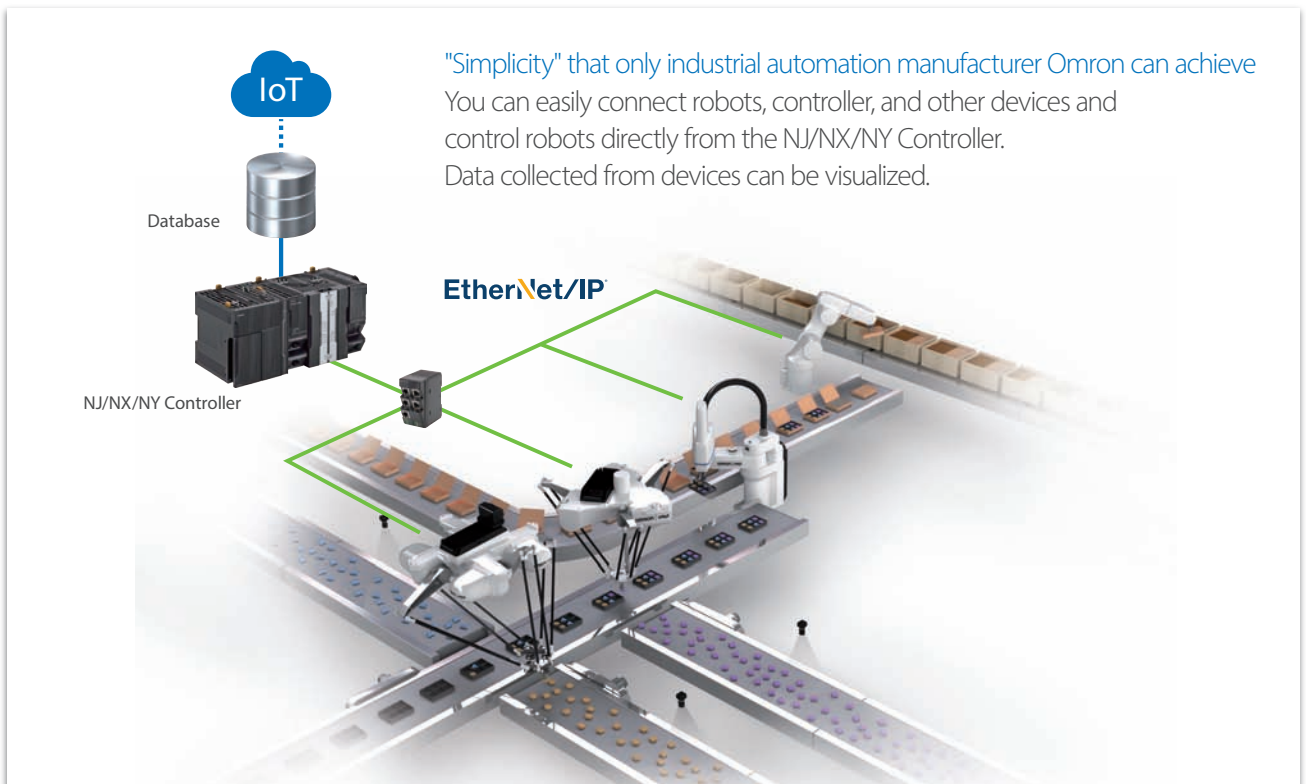
Issue 2 Controller data and robot data are backed up and managed separately.

Adept Robot Control Library offers solution!

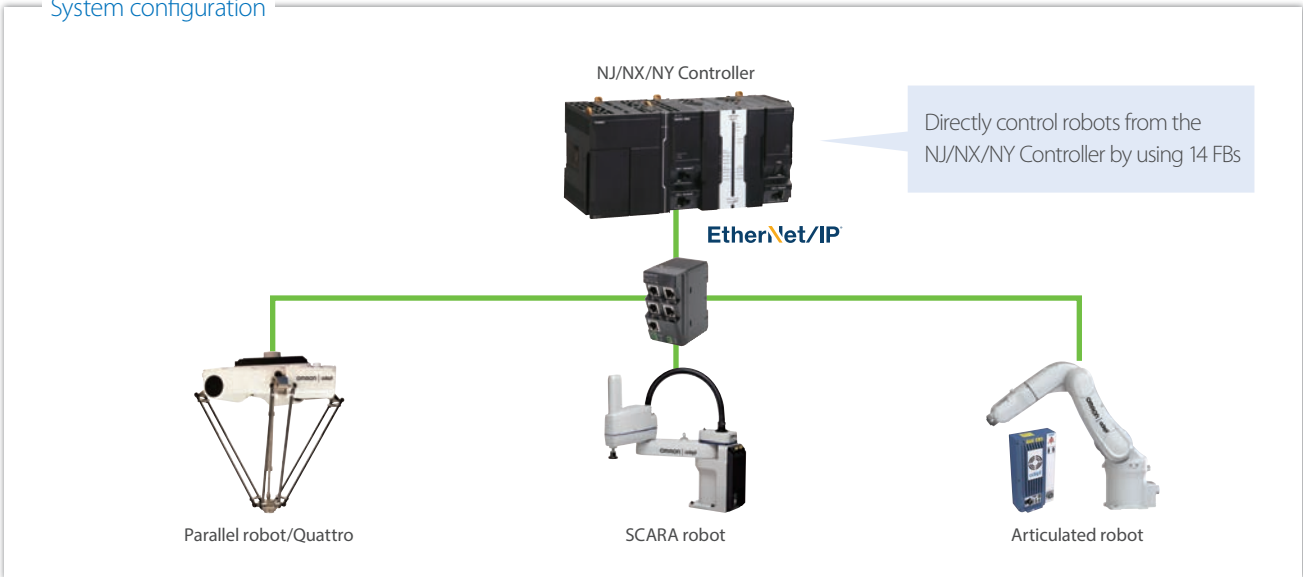
The Adept Robot Control Library allows parallel, SCARA, and articulated robots manufactured by Omron Adept Technologies Inc. to be controlled directly from the NJ/NX/NY Controller by using the same instructions and programming method as the controller.

Function Blocks in this library enable robot control using Ladder and ST that are the programming languages used for the NJ/NX CPU Unit and the NY Industrial PC Platform, eliminating the need to learn a new robot programming language.

The NJ/NX CPU Unit and the NY Industrial PC Platform integrates robot system control and data management.



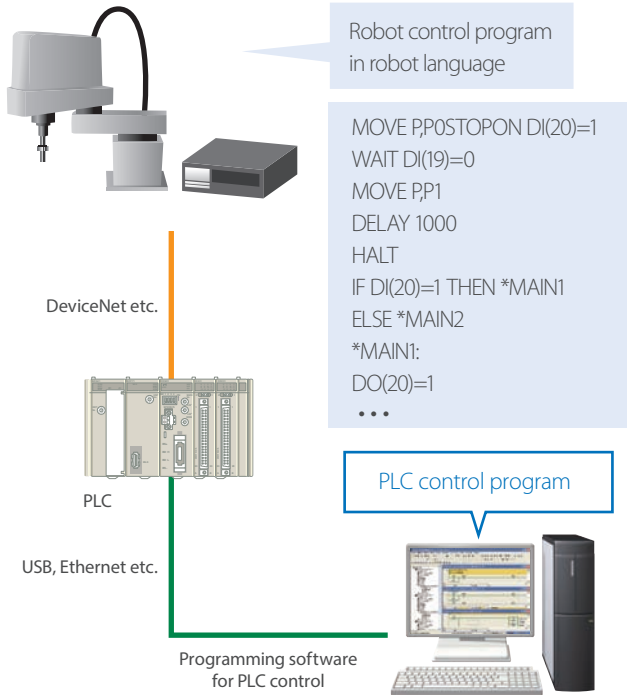
System configuration



Example of combination of controller and robot

From

Programming requires knowledge of controller and robot.



- Knowledge of both controller and robot
- I/O connection to network used for robot controller
- Separate programming and data backup

To

The same programming language is used for controller and robot control.



- Programming only for NJ/NX/NY Controller
- Integrated programming and data management for easy troubleshooting



Compatible Models

Name		Model	Version
Machine Automation Controller NJ/NX CPU Unit		NX701-1□□□/NJ101-□□□□	Version 1.10 or later
		NJ501-□□□□/NJ301-□□□□	Version 1.01 or later
		NX1P2-□□□□□□(1)	Version 1.13 or later
		NX102-□□□□	Version 1.30 or later
		NX502-□□□□	Version 1.60 or later
Industrial PC Platform NY IPC Machine Controller		NY5□□-1	Version 1.12 or later
		NY5□□-5	Version 1.18 or later
Automation Software Sysmac Studio		SYSMAC-SE2□□□	Version 1.15 or higher
Parallel Robot	Hornet 565	1720□-4560□	Version 2.3.C or later
	Quattro 650H/HS, 800H	1720□-26□□□	Version 2.3.C or later
SCARA Robot	eCobra 600/800	17□□□-1□□□00	Version 2.3.C or later
	Cobra 450/500/650	1720□-1□□□00	-
Articulated Robot	Viper 650/850	1720□-36□□000	Version 2.3.C or later

Function Block (FB) Specifications

Name	FB name	Description
Set Tool Trans	ARB_SetToolTransform	Sets a tool system transformation to the robot.
Reset Tool Transform	ARB_ResetToolTransform	Resets the robot tool which is set to the robot.
Define Location	ARB_DefineLocation	Defines a position in the robot.
Define Pallet	ARB_DefinePallet	Defines all pallet information in the robot.
Reset Error	ARB_ResetRobotError	Resets any existing error in the robot.
Robot Control	ARB_RobotControl	Controls the main robot settings and monitors the robot status.
Teach Position	ARB_TeachPosition	Teaches the current robot position and configuration.
Input Output Signals	ARB_InputOutputSignals	Communicates with the robot through its digital inputs and outputs.
Teach Pendant Control	ARB_TeachPendantControl	Sends and receives information from the manual control pendant attached to the robot.
Read Latch	ARB_ReadLatch	Outputs the current robot position when an external trigger is input.
Move	ARB_MoveCommand	Moves the robot to a target position using a linear interpolation or PTP operation.
Pick And Place	ARB_PickAndPlaceCommand	Moves the robot to a target position in a three-part motion.
Jog	ARB_Jog	Moves the specified joint or axis of the robot.
Align Tool Command*	ARB_AlignToolCommand	Rotates the tool to be aligned with the world coordinate system.
Move Arc Command*	ARB_MoveArcCommand	Moves the robot to the specified target position along arc trajectory.
Move Circular Command*	ARB_MoveCircularCommand	Moves the robot along a circular trajectory, passing specified two positions.
Define Belt*	ARB_DefineBelt	Defines a conveyor belt.
Belt Read Latch*	ARB_BeltReadLatch	Outputs the belt encoder value of the conveyor when an external trigger is input.
Track Belt*	ARB_TrackBelt	Enables tracking a workpiece.

* Supported only by the Adept Robot Control Library version 2.00 or higher.

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Note: Do not use this document to operate the Unit.

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