Move to Contact

User Guide

The Move to contact app can be used to move along a defined trajectory until the robot detects an object. If the contact occurs in the defined contact area, the robot will stop and jump to the next app in the process. If a collision is detected outside the allowed area, an error will occur.

Tab: Motion

Define a trajectory to follow, as well as the speed and acceleration to use.

Option: Define Trajectory

Teach the trajectory that the robot will follow. This can be up to 100 poses. In the next tab you can define an expected contact area. The contact area will be in relation to the LAST pose defined in the trajectory.

Option: Speed

Set the default speed that will be used when moving between the poses defined in the trajectory. This will be affected by the task speed. The default speed can be overwritten for individual poses in the trajectory by selecting the *Advanced Options* for that pose.

Option: Acceleration

Set the default acceleration that will be used when moving between the poses defined in the trajectory. The default speed can be overwritten for individual poses in the trajectory by selecting the *Advanced Options* for that pose.

Tab: Contact Area

Define an area in which contact can be expected, relative to the last pose in the defined trajectory. If a collision is detected in the expected area, no error will occur and the process will proceed to the next app. A collision outside the expected contact are will result in an error.

Option: Collision Area X

The offset along the X Axis on both sides of the final pose (in mm) in which a collision is to be expected.

Option: Collision Area Y

The offset along the Y Axis on both sides of the final pose (in mm) in which a collision is to be expected.

Option: Collision Area Z

The offset along the Z Axis on both sides of the final pose (in mm) in which a collision is to be expected.