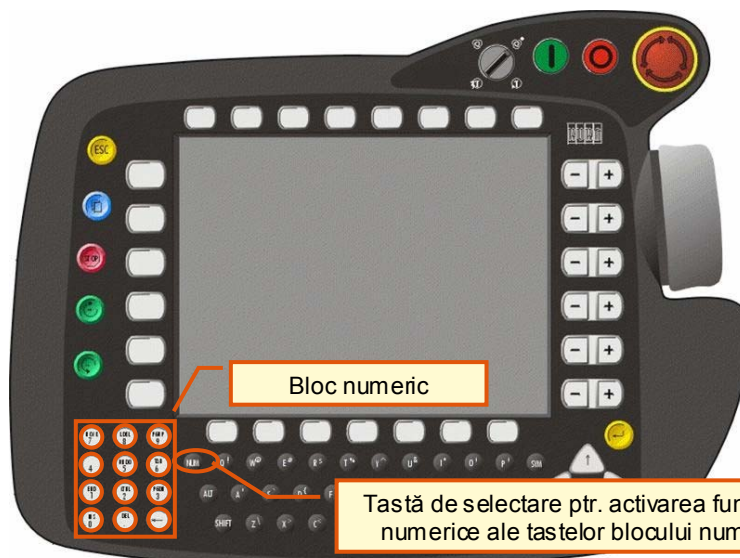


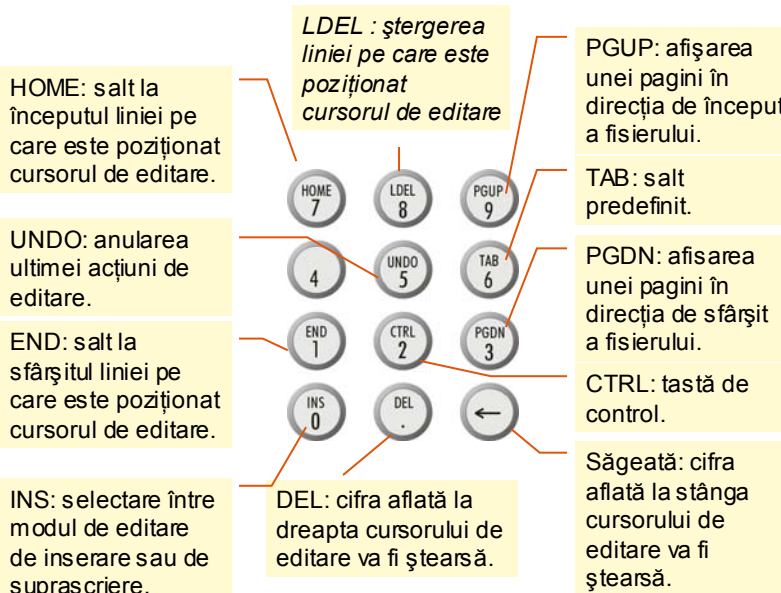


Elemente de comandă pentru utilizarea comunicării CAN-Bus



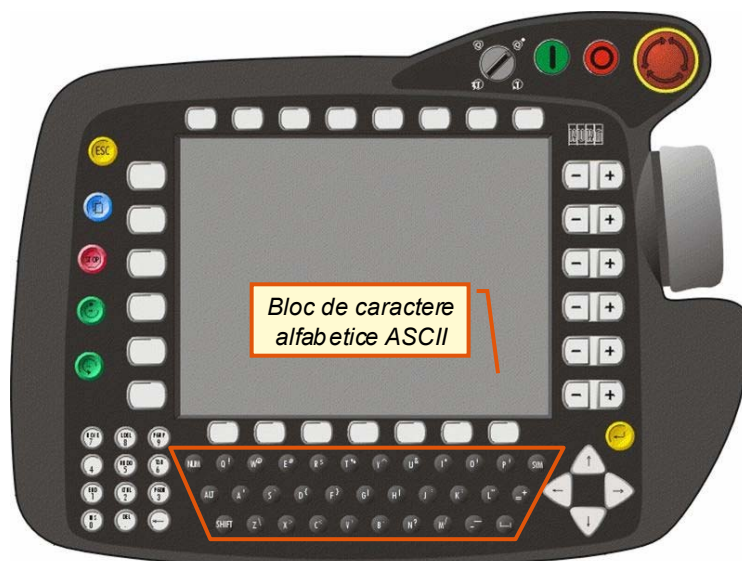
KUKARoboter GmbH, Hery Park 3000, D-86368 Gersthofen, Tel.: +49 (0) 8 21 45 33-1906, Fax: +49 (0) 8 21 45 33-2340, <http://www.kuka-roboter.de>
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Blocul numeric



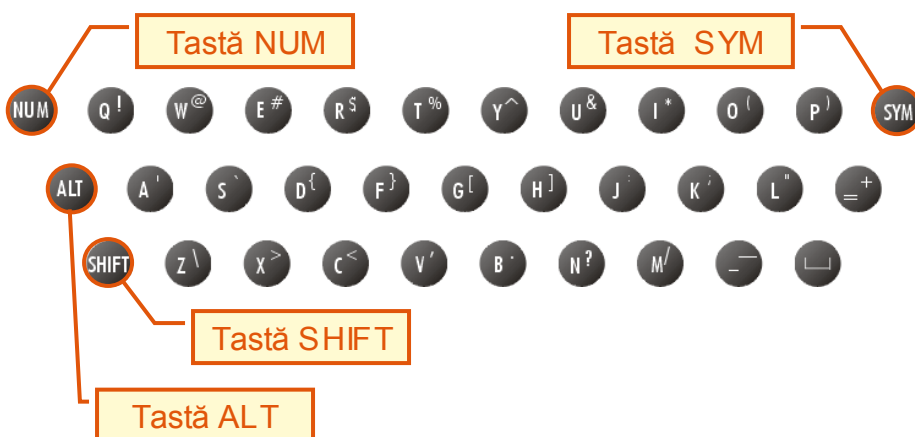
KUKARoboter GmbH, Hery Park 3000, D-86368 Gersthofen, Tel.: +49 (0) 8 21 45 33-1906, Fax: +49 (0) 8 21 45 33-2340, <http://www.kuka-roboter.de>
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Elemente de execuție pentru utilizarea comunicării CAN-Bus



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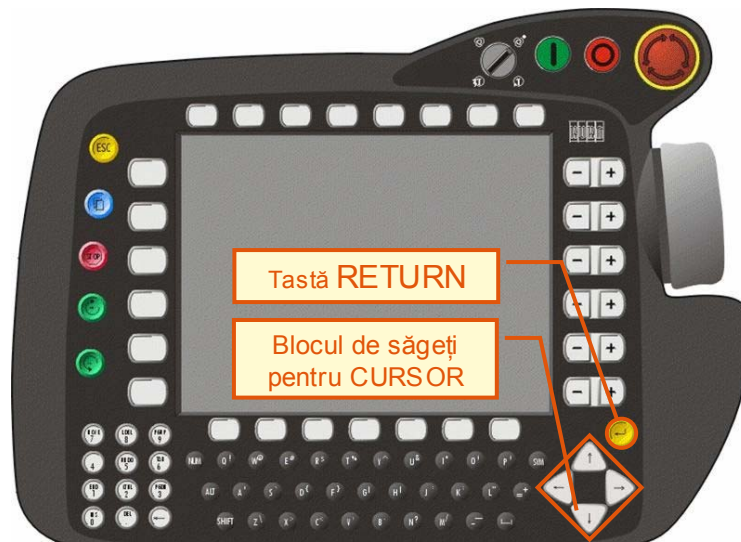
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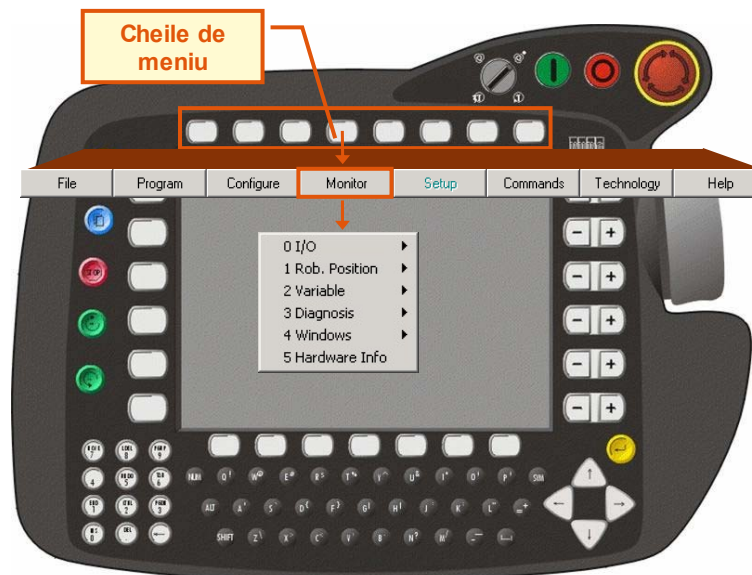


Elemente de execuție pentru utilizarea comunicării CAN-Bus



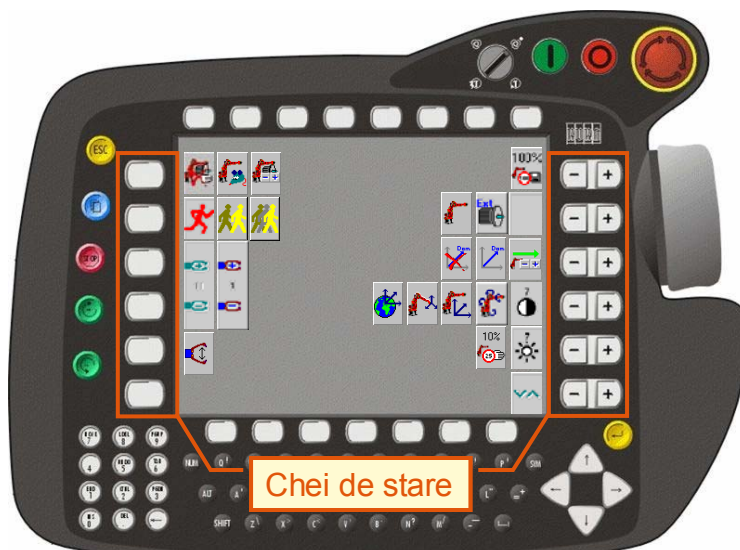
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Cheile de meniu



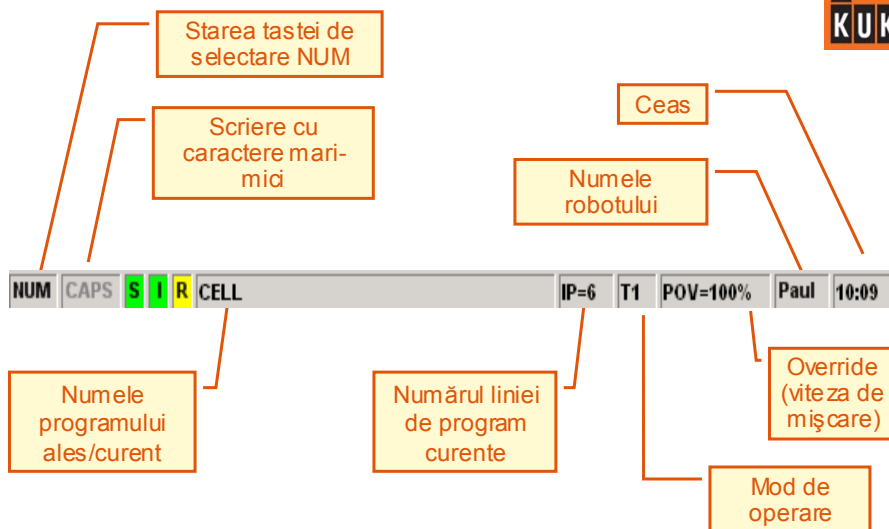
KUKARoboter GmbH, Hery Park 3000, D-86368 Gersthofen, Tel.: +49 (0) 8 21 45 33-1906, Fax: +49 (0) 8 21 45 33-2340, <http://www.kuka-roboter.de>
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Cheile de selectare a modului de funcționare a robotului



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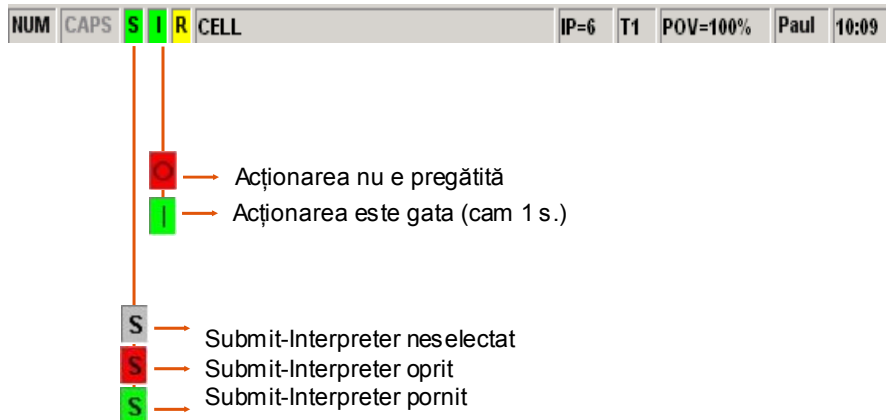
Vizualizarea stării selecțiilor curente



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3. Sistemele de coordonate ale robotului

Sistemele de coordonate ale robotului



- Sistemul de coordonate propriu al robotului:



Fiecare axă comandată a robotului poate fi deplasată în sens pozitiv sau negativ.

- Sistemul de coordonate atașat bazei robotului:



Sistem de coordonate fix, tri-ortogonal drept, cu originea la baza robotului.

- Sistemul de coordonate atașat sculei:



Sistem de coordonate triortogonal, cu originea în punctul caracteristic al sculei

- Sistemul de coordonate atașat bazei (piesei):



Sistem de coordonate triortogonal, cu originea în punctul caracteristic al piesei de prelucrat.

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