

I'm not robot  reCAPTCHA

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Jesper May 9th 2019 Theme marked as Resolved. I have a fanuc M-430iA with a Fanuc R-30iA controller and a Sony XC-56. I'm trying to create a vision system where the robot lifts wooden blocks (with different letters on it) out of the conveyor belt and places them in a certain order to form a name. To check out some basic things, I thought I'd check the belt-free moving process to make sure the camera can find the blocks and that the robot gets the right seats and can pick them up. I found the iRvision manual, and these are the steps I've made: Setting up the camera (on the internet explorer) Setting the line (on the internet explorer) Performed visual calibration of the tracking grid (on the internet explorer) Attached pointer to the pointer end capture and adjust the tool frame (on the controller) 4 Points Grid calibration to install the user frame (on the controller) --gt; 'LETTERS' when I click snap find the block is detected at all times. - Created a program, Set a reference point (on an internet explorer) and then moved the robot to this position for P '2' Program looks like this: UTOOL_NUM '1 UFRAME_NUM '6J P' '3 100% FINE zlt; - random points home position CALL GRIP_OPEN LBL 99 VISION_RUN_FIND 'LETTERS' VISION_GET_OFFSET 'LETTERS' VR'2 JMP LBL .99' P'1' 30% FINE VOFFSET, VR -2' qlt; -dot above P'2' 40mm/FINE SEC VOFFSET, - Grip position CALL GRIP_CLOSE What occurs: When I don't move the wooden block, the robot will run the trough program and perfectly go to the same point and pick up the block. Thus, the letter is being recognized etc. however, when I rotate the block the robot will go into a completely different position, or even can not reach the position (error). And sometimes when I move a linear block (for example, in x-direction) the robot will move in a different direction (off-direction) without logic. Does anyone have a clue what the problem might be, or that there is a proper guide other than the iRvision guide? Thank you in advance! Just curious, when you did a calibration tracking frame you put direction X to the conveyor belt move? Usually I take the following steps: instruct the robot (create a conveyor belt, fixture / etc.) to go to the conveyor tab, Create a Tracking Frame (place of grid calibration from X to conveyor move, calibrate the camera, then move the conveyor belt and create a robot frame) go to the conveyor tab, create upstream and downstream beamslater depends on what your placement (conveyor/tray/ etc.) do the rest when you're done with the vision tracking camera program, after creating a link to move the robot to move the position. Depends on what type of tracking you use you need to choose the right program. In my case I go PK_CV_PICK11, and make a touch-up on PR-57: Cv Ref Pos. Ask you: You want to exclude VR, click F5. I usually run the original pipeline tracking program that comes with a tracking pipeline to check that my conveyor tracking calibration and settings work the way that I want. Seeing as you don't use the conveyor yet you can have the calibration settings wrong. Make sure you use the correct value for the grid calibration sheet used to adjust the camera calibration. Example: Using a 30mm grid with a 5 mm calibration will result in the robot attempting to move at the wrong distance than necessary. Just curious, when you did a calibration tracking frame you put direction X to the conveyor belt move? Usually I take the following steps: to set up the robot (creating a conveyor belt, fixture / etc.) go to the conveyor tab, Create a Tracking Frame (place of grid calibration from X to conveyor move, calibrate the camera, then move the conveyor belt and create a robot frame) go to the conveyor tab, create upstream and downstream beamslater depends on what your placement (conveyor/tray/ etc.) do the rest when you're done with the vision tracking camera program, after creating a link to move the robot to move the position. Depends on what type of tracking you use you need to choose the right program. In my case I go PK_CV_PICK11, and make a touch-up on PR-57: Cv Ref Pos. It will ask you: You want to exclude VR, click F5. I usually run the original pipeline tracking program that comes with a conveyor tracking package to check that my conveyor tracking calibration and settings work the way I want. Display More Since I didn't use the pipeline for testing purposes, I used a line that had already been introduced to the (previous) owner of the robot. The block does not move, but the robot lifts the block from under the camera. So for this reason I didn't install frame tracking, up/down streams, etc., but used one that was already installed. My thought was that if the pipeline didn't move, the coder wouldn't change, and the robot had to pick up the part. For normal calibration, I put the X-direction to a positive x-direction robot that is perpendicular to the conveyor line. Could this be a problem? And where did you get all the information you needed? Do you, by chance, have proper guidance? Thank you for your response! Seeing as you don't use the conveyor yet you can have the calibration settings wrong. Make sure you use the correct value for the grid calibration sheet used to adjust the camera calibration. Example: Using a 30mm grid with a 5 mm calibration will result in the robot attempting to move at the wrong distance than necessary. I used 22mm mesh and this is also what I used in the installation. Thank you for your response! Oh, and when I rotate a 90-degree block: What do I mean with a completely different direction, the robot move more than half a meter the other way. Hello, so some thoughts about your problem:1. If you don't use tracking, take it out (do a normal calibration - Grid Pattern Calib.) 2. After calibrating I would like to make a 2D single 2D single The vision process is to test the system. Teach the circle on the grid and do tests. 3. What type of vision process do you use? If you're not using tracking, use a simple 2D vision process with one view. Make sure the frame shift is correct. It could be your uframe gauge grid, for example. Check if a proper tool is being used. Hello, so some thoughts about your problem:1. If you don't use tracking, take it out (do a normal calibration - Grid Pattern Calib.) 2. After calibrating I would like to do a 2D single view vision process to test the system. Teach the circle on the grid and do tests. 3. What type of vision process do you use? If you're not using tracking, use a simple 2D vision process with one view. Make sure the frame shift is correct. It could be your uframe gauge grid, for example. Check if a proper tool is being used. Display More I tried to calibrate the grid pattern, however the only tool I can choose is: the caliber of the camera. For in relation to the trackingSame counts on the process of vision, the only one I can choose: One-shaped visual tracking. Am I missing the settings somewhere? Thank you for the answer! I've been trying to calibrate the grid pattern, but the only tool I can choose is the caliber of the camera. For in relation to the trackingSame counts on the process of vision, the only one I can choose: One-shaped visual tracking. Am I missing the settings somewhere? Thank you for the answer! You won't miss the se-up. If you have a conveyor tracking system, you can't use regular one-way visual tracking. If you don't have a camera setup as a regular iRvision 2D. Send me PM with you via email, I'll send you a conveyor belt tracking guides. Personally I have had that issue many times using GET_OFFSET, I prefer to use POS_FOUND and just move there. I also make sure my userframe and my calibration camera is exactly the same. I think the problem is that it compensates for the frame of the tool, not the userframe. You won't miss the se-up. If you have a conveyor tracking system, you can't use regular one-way visual tracking. If you don't have a camera setup as a regular iRvision 2D. Send me PM with you via email, I'll send you a conveyor belt tracking guides. That explains a lot, and that would be great! I send you my email in pm. Personally I have had that issue many times using GET_OFFSET, I prefer to use POS_FOUND and just move there. I also make sure my userframe and my calibration camera is exactly the same. I think the problem is that it compensates for the frame of the tool, not the userframe. You won't miss the se-up. If you have a conveyor tracking system, you can't use regular one-way visual tracking. If you don't have a camera setup as a regular iRvision 2D. Send me PM with you via email, I'll send you a conveyor belt tracking guides. That explains a lot, and that would be great! I send you my email in pm. Personally I have had that issue many times using GET_OFFSET, I prefer to use POS_FOUND and just move there. I also make sure my userframe and my calibration camera is exactly the same. I think the problem is that it compensates for the frame of the tool, not the userframe. I haven't got it to work, how can I use POS_FOUND? I've cleared the found positions in VR1 This is what I thought:VISION_RUN_FIND 'EXAMPLEVISIONEXAMPLEVISION EXAMPLE VR1 JMP LBL.99 PR7VR. FOUND_POS 50% FINEI is the right way to go? because I can't make it work. You must be a member to leave a comment

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