

## Tutorial 1: Collaborative Robot Basics and Jogging

Name: \_\_\_\_\_

### Questions

1. Which movement type did you find the easiest to use? Why?
2. Which movement type did you find the most difficult to operate? Why?
3. Manual Guide Teaching Weight: Describe the movement feeling when the robot is set to heavy versus light
4. Manual Guide: Try and get the robot to fault by applying more than 150N of force in a direction. NOTE: The robot will fault out > Operator will need to clear the fault before movement can continue. Describe the movement you performed (i.e. Free, Transition, Rotation, Custom w/enabled or disabled joints, heavy or light teaching weight).
5. Jog Mode: Describe how the robot moved between Joint versus Cartesian
6. Jog Mode: Set Frame Tool > Describe the movement of the robot as compared to Cartesian or Joint Movement
7. Jog Mode Override Percentage: Describe the movement and accuracy has the operator adjusts from 0 to 100%

8. Motion Pulse Generator (MPG): Describe the use of the dial in jogging the robot, along with adjusting the scaling factor and/or Override.
  
  
  
  
  
  
  
  
  
  
9. Faults: Were the faults easy to clear? If no what type of fault was the most difficult to fix.
  
  
  
  
  
  
  
  
  
  
10. Did you have to power cycle the robot because you put the robot into a position it could not get out of? (I.E Singularity) If Yes describe the robots position.
  
  
  
  
  
  
  
  
  
  
11. Axis Polarity: Describe your experience with the +/- polarity of the different joints.
  
  
  
  
  
  
  
  
  
  
12. Did you explore any other menus while working experimenting with movements? If so which menus did you navigate through?