ControlTech

Authorised Distributor

A ROCKWELL AUTOMATION PARTNER

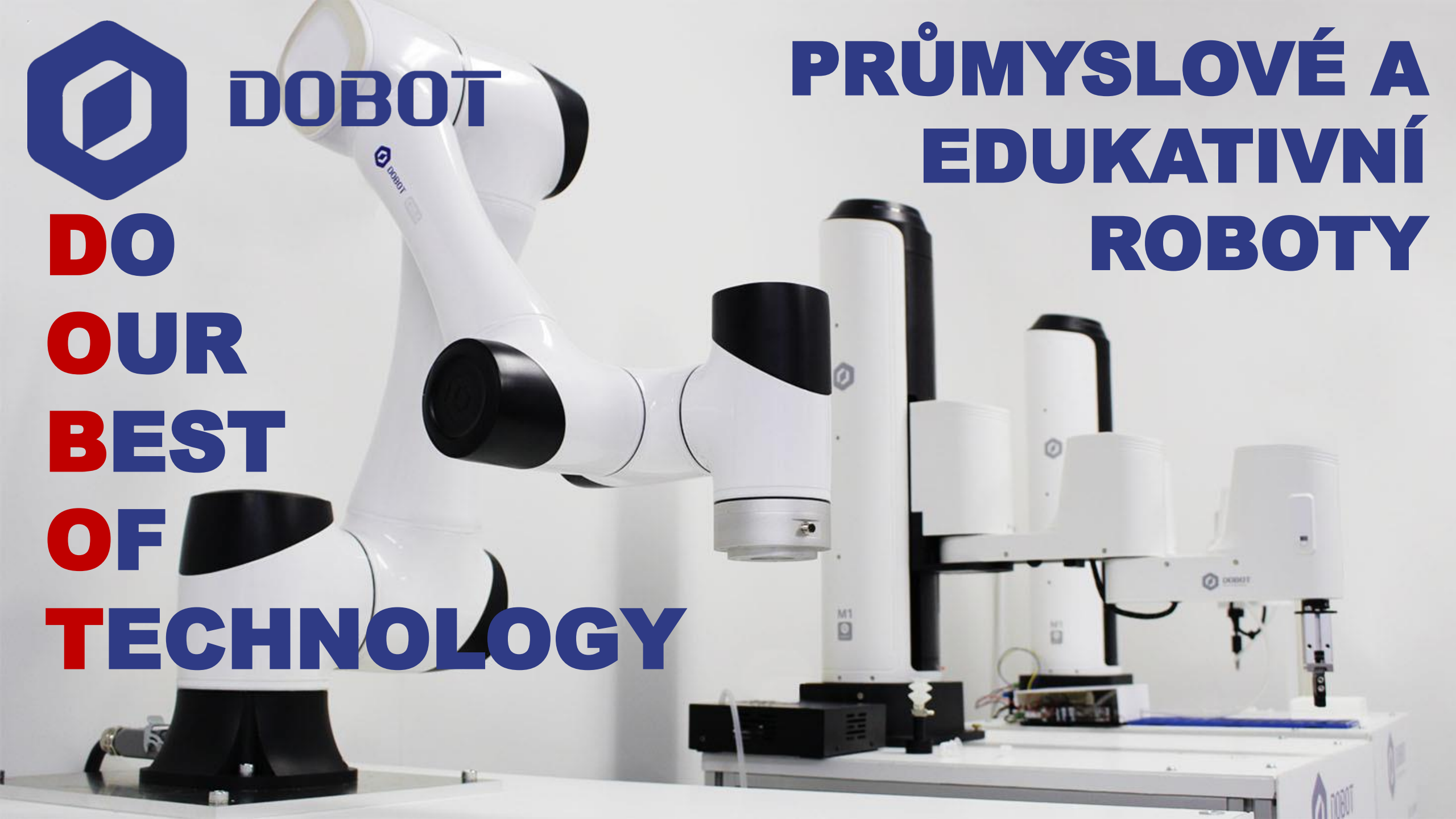
PRŮMYSLOVÉ A EDUKATIVNÍ ROBOTY

VLADYKA PAVEL

DOBOT

PRŮMYSLOVÉ A EDUKATIVNÍ ROBOTY

DO OUR BEST OF TECHNOLOGY



DOBOT

CR6-5

ROBOTA PRACOVAT NAUČTE
jednoduše a bez programování

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DOBOT


DOBOT
Secondly, press the upper button - start to record the trajectory
Firstly, press the middle Enter button - switch to the Manual Mode

DOBOT

Opakovatelnost
0,03 mm

Rychlost
3m/s – 180°/s

Modbus

TCP/IP

Nosnost
5 kg

Dosah
900 mm

Wi Fi

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Hmotnost (kg)	23kg	
Užitečné zatížení (kg)	5kg	
Dosah (mm)	900mm	
Maximální rychlost	3m/s	
Rozsah (°)	**J1**	±180
	J2	±180
	J3	±160
	J4	±180
	J5	±180
	J6	±360
Rychlost (°/s)	**J1**	180°/s
	J2	180°/s
	J3	180°/s
	J4	180°/s
	J5	180°/s
	J6	180°/s

I/O porty robota	**DI**	2
	DO	2
	AI	2
	AO	0
	Kom.	RS485
I/O porty řídicí jednotky	**DI**	16
	DO	16
	AI	2
	AO	2
Opakovatelnost	±0.03mm	
Napájení	100~240VAC, 50~60Hz	
Komunikace	TCP/IP, Modbus, Wi-Fi	
IP klasifikace	IP54	
Teplotní rozsah	0~45°	
Zdroj	Okolo 200W	
Materiál	Aluminum, ABS	

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DOBOT

NEUTRÁCEJTE ZA TEACH PENDANT

vyberte si tablet, kterým budete robota ovládat

android iOS

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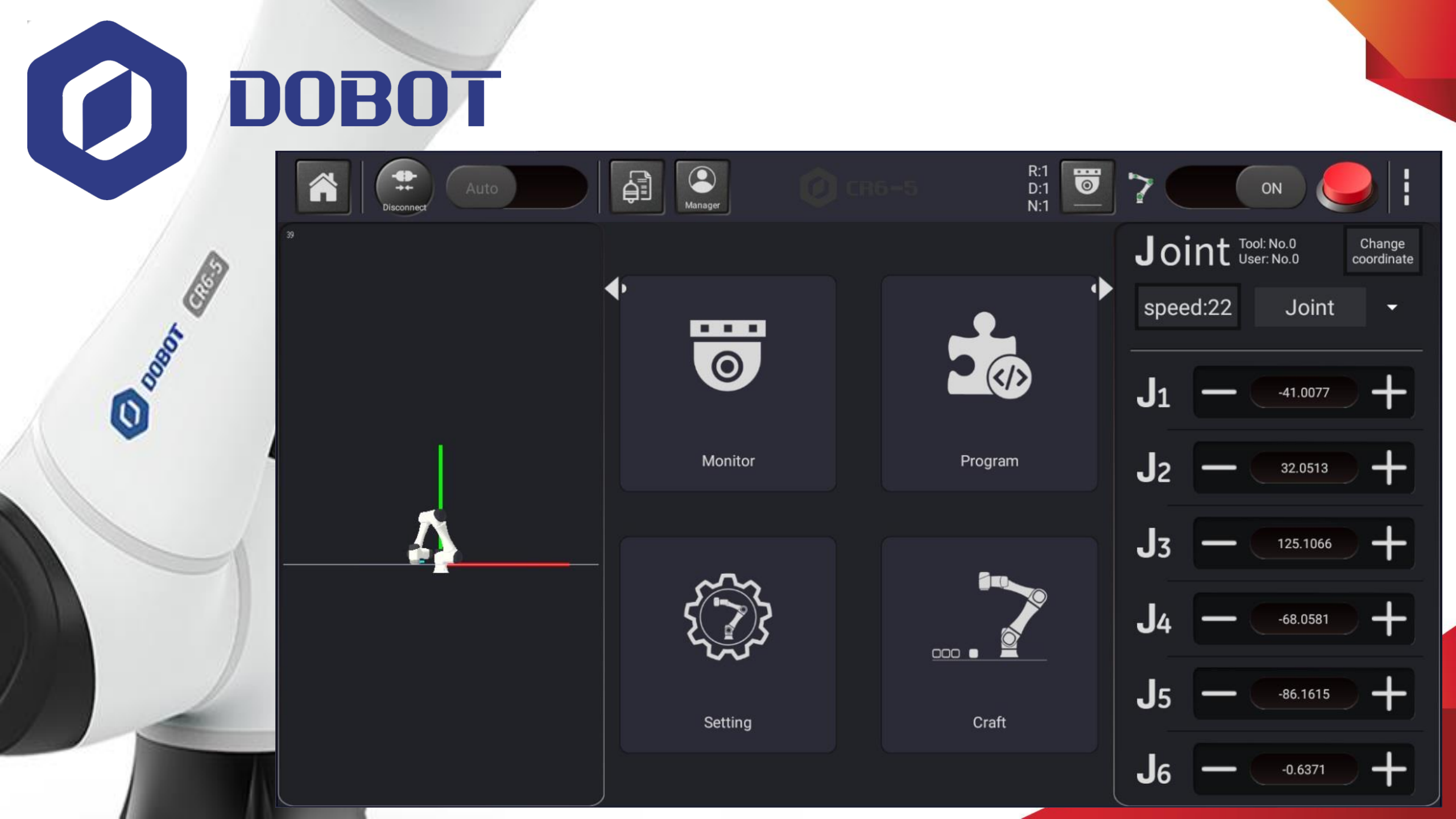
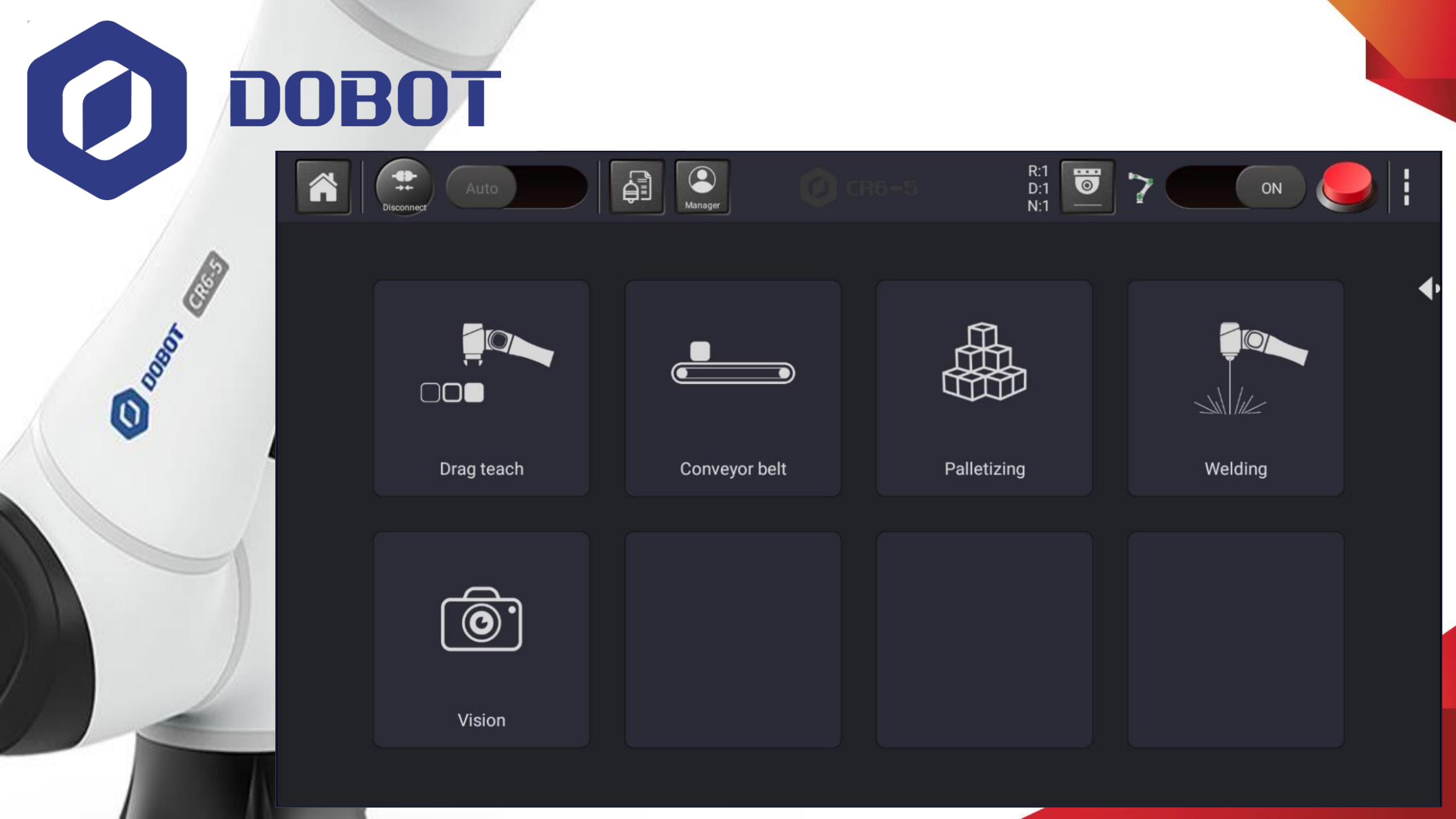
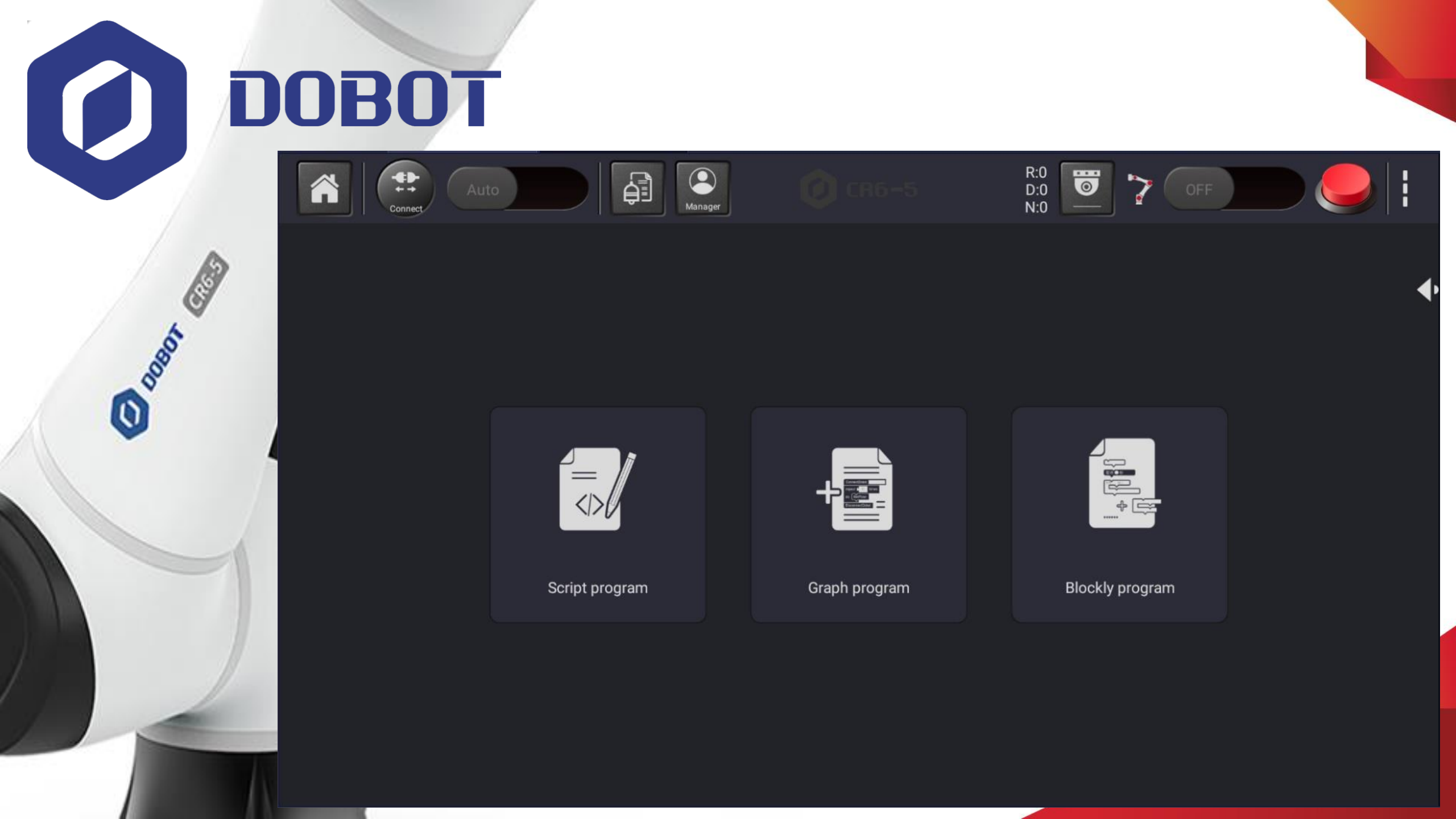
DOBOT


Disconnect
Auto
Manager
CR6-5
R:1
D:1
N:1
ON
Joint
Tool: No.0
User: No.0
Change coordinate
speed:22
Joint
Monitor
Program
Setting
Craft
J1
-41.0077
J2
32.0513
J3
125.1066
J4
-68.0581
J5
-86.1615
J6
-0.6371

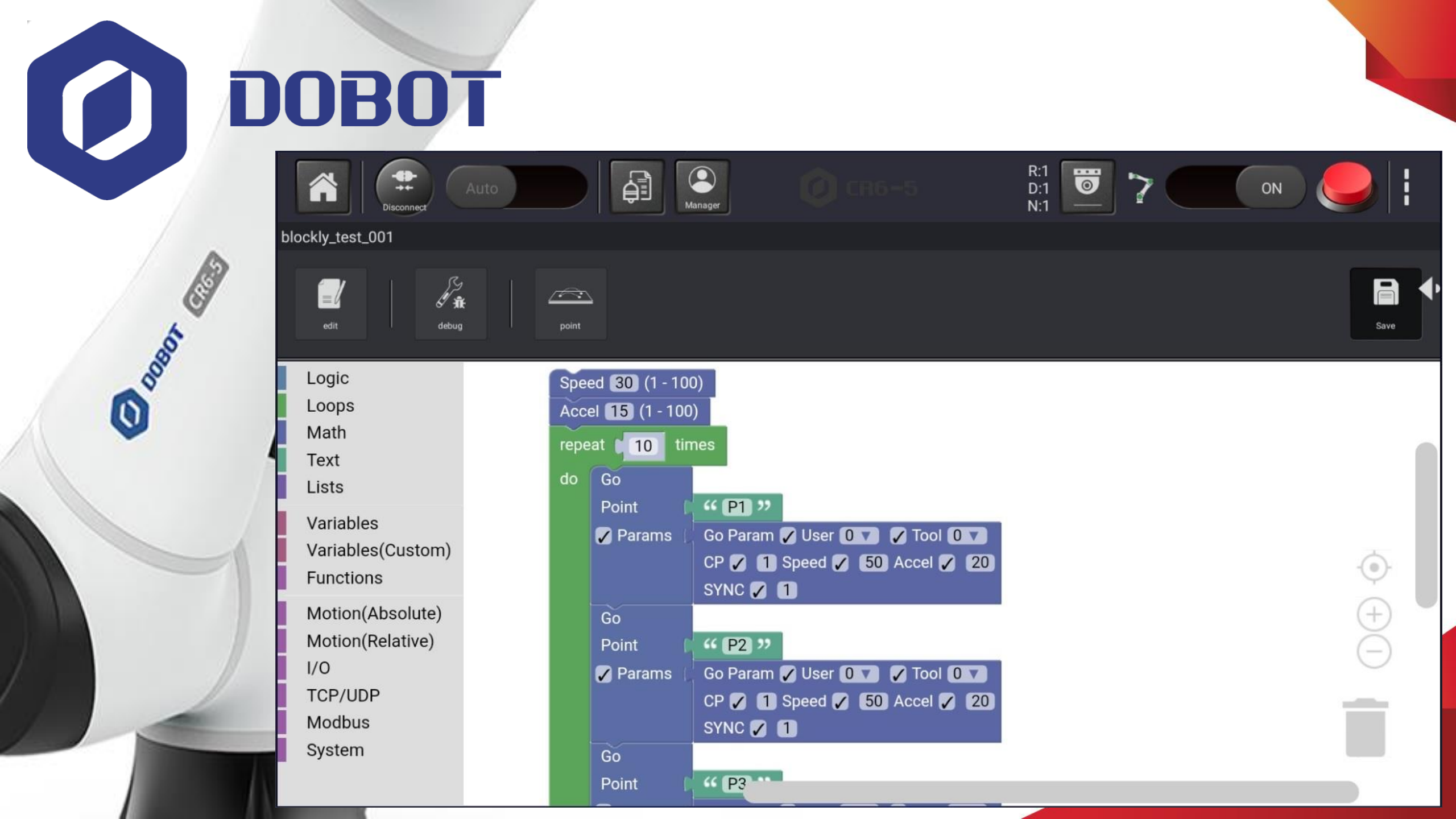
DOBOT


Disconnect
Auto
Manager
CR6-5
R:1
D:1
N:1
ON
Drag teach
Conveyor belt
Palletizing
Welding
Vision
DOBOT
CR6-5

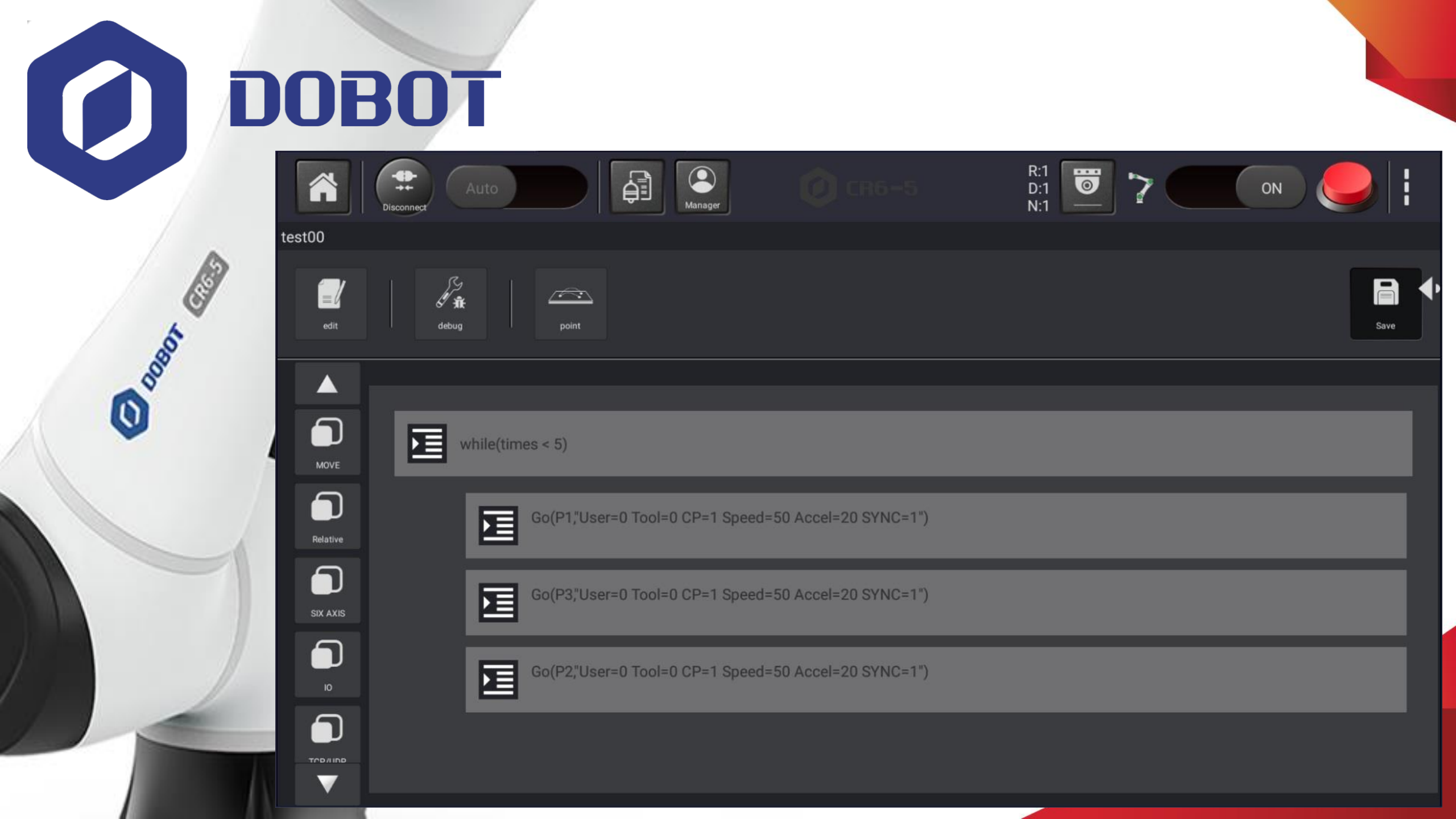
DOBOT


Connect
Auto
Manager
CR6-5
R:0
D:0
N:0
OFF
Script program
Graph program
Blockly program
DOBOT
CR6-5

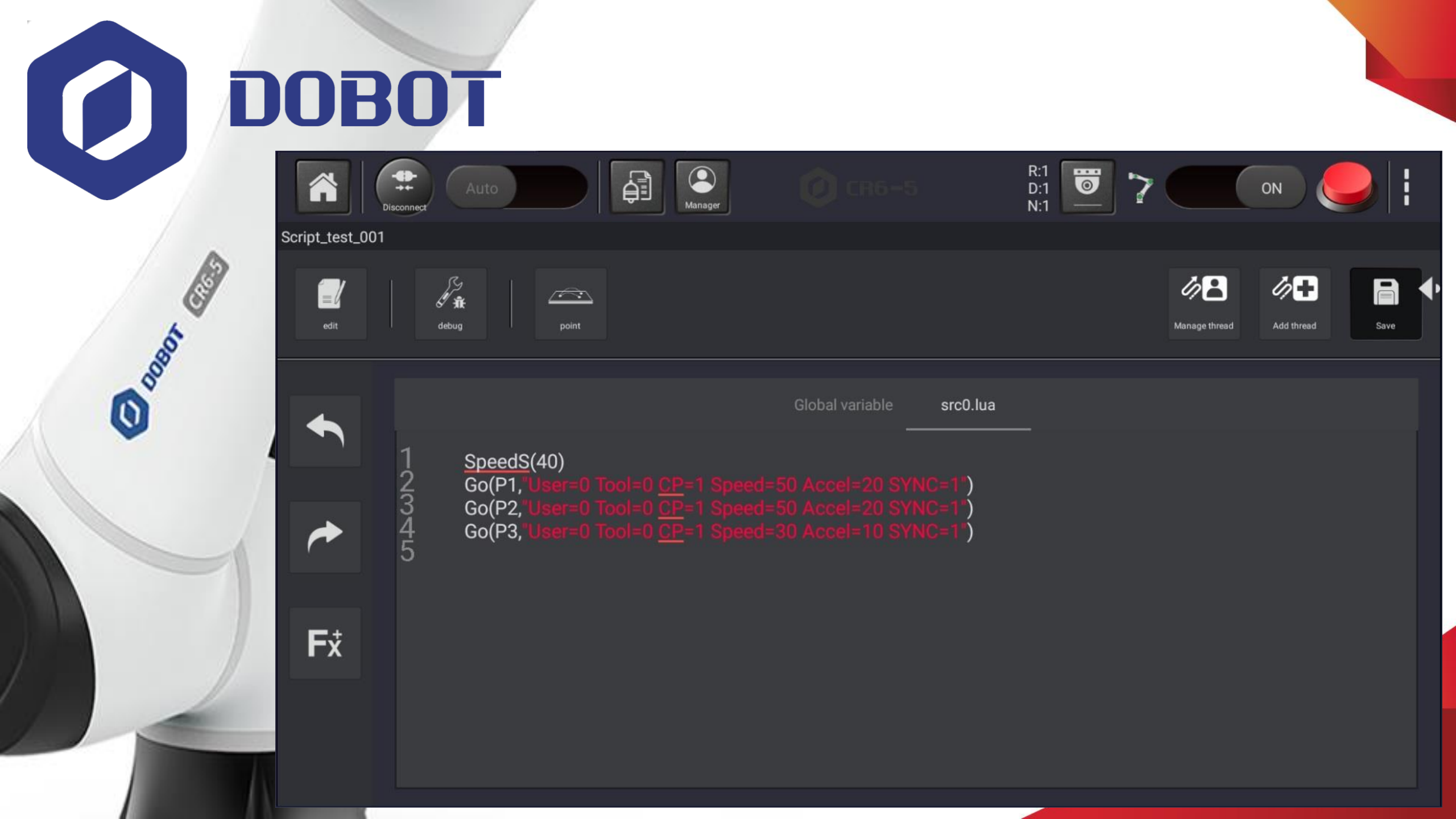
DOBOT


Disconnect
Auto
Manager
CR6-5
R:1
D:1
N:1
ON
blockly_test_001
edit
debug
point
Save
Logic
Loops
Math
Text
Lists
Variables
Variables(Custom)
Functions
Motion(Absolute)
Motion(Relative)
I/O
TCP/UDP
Modbus
System
Speed 30 (1 - 100)
Accel 15 (1 - 100)
repeat 10 times
do
Go
Point "P1"
Params Go Param User 0 Tool 0
CP 1 Speed 50 Accel 20
SYNC 1
Go
Point "P2"
Params Go Param User 0 Tool 0
CP 1 Speed 50 Accel 20
SYNC 1
Go
Point "P3"

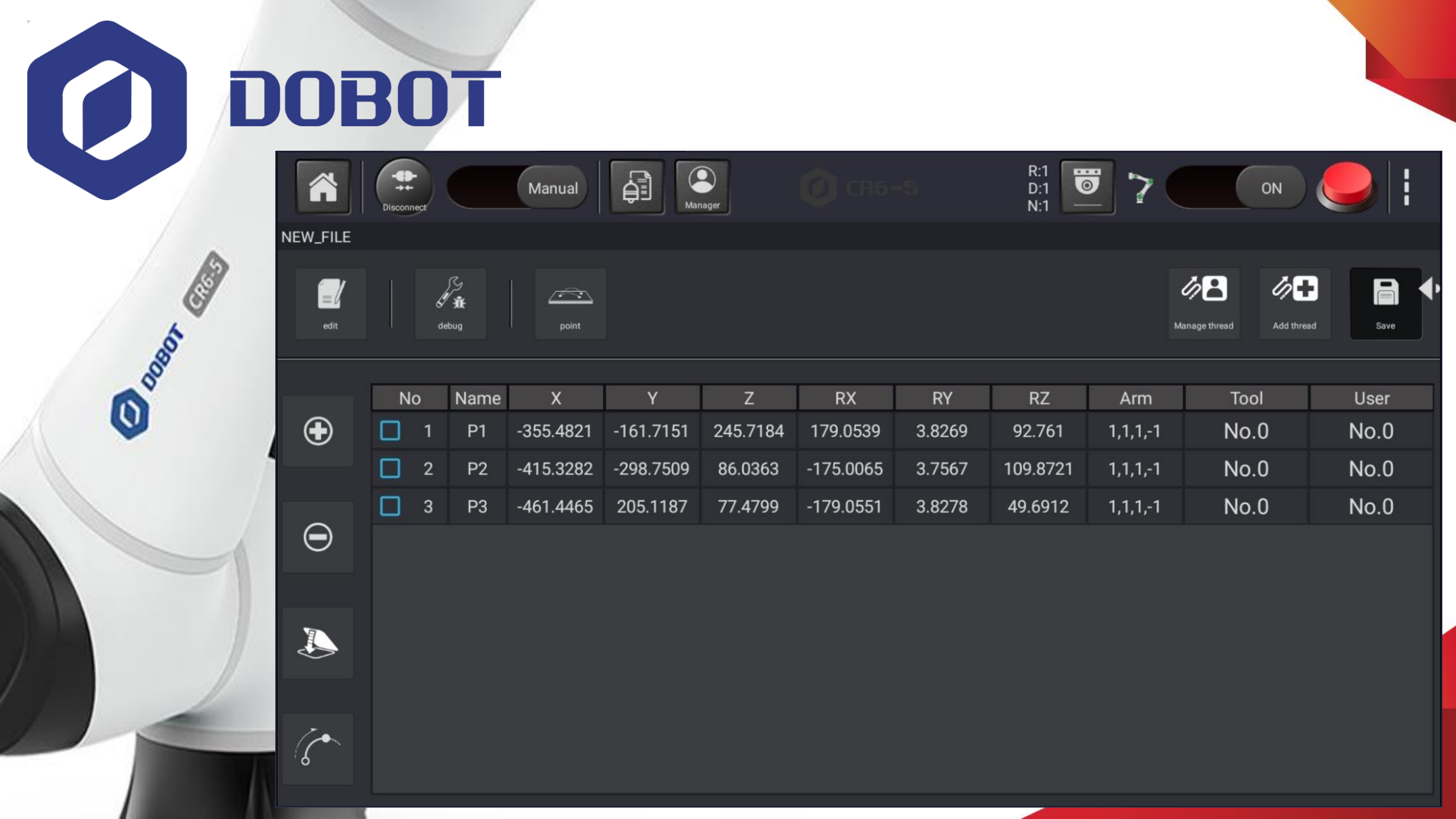
DOBOT


Disconnect
Auto
Manager
CR6-5
R:1
D:1
N:1
ON
test00
edit
debug
point
Save
MOVE
Relative
SIX AXIS
IO
while(times < 5)
Go(P1,"User=0 Tool=0 CP=1 Speed=50 Accel=20 SYNC=1")
Go(P3,"User=0 Tool=0 CP=1 Speed=50 Accel=20 SYNC=1")
Go(P2,"User=0 Tool=0 CP=1 Speed=50 Accel=20 SYNC=1")
DOBOT
CR6-5

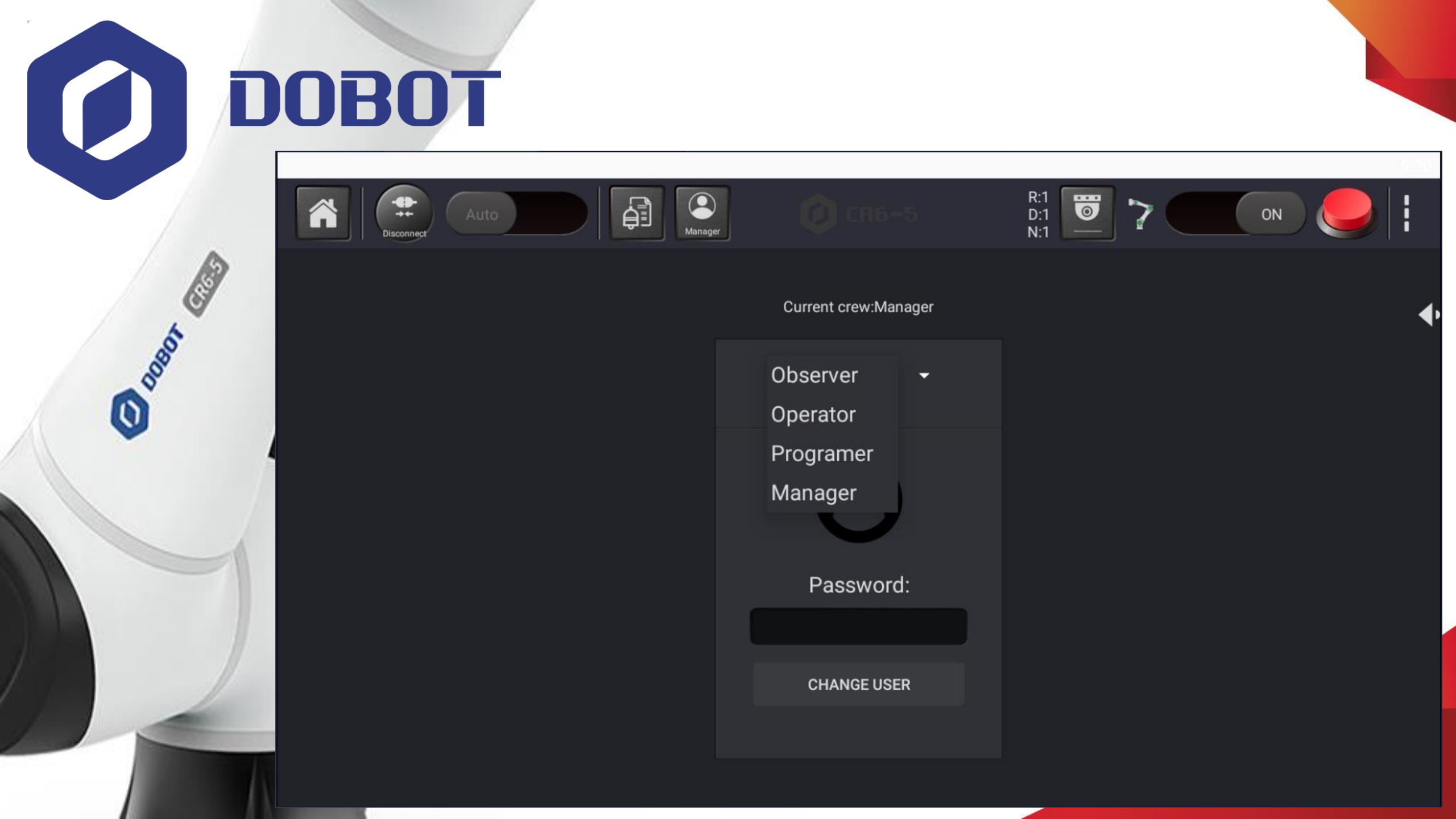
DOBOT


Disconnect
Auto
Manager
CR6-5
R:1
D:1
N:1
ON
Script_test_001
edit
debug
point
Manage thread
Add thread
Save
Global variable
src0.lua
SpeedS(40)
Go(P1,"User=0 Tool=0 CP=1 Speed=50 Accel=20 SYNC=1")
Go(P2,"User=0 Tool=0 CP=1 Speed=50 Accel=20 SYNC=1")
Go(P3,"User=0 Tool=0 CP=1 Speed=30 Accel=10 SYNC=1")
DOBOT
CR6-5

DOBOT


Disconnect
Manual
Manager
CR6-5
R:1
D:1
N:1
ON
NEW_FILE
edit
debug
point
Manage thread
Add thread
Save
No
Name
X
Y
Z
RX
RY
RZ
Arm
Tool
User
1 P1 -355.4821 -161.7151 245.7184 179.0539 3.8269 92.761 1,1,1,-1 No.0 No.0
2 P2 -415.3282 -298.7509 86.0363 -175.0065 3.7567 109.8721 1,1,1,-1 No.0 No.0
3 P3 -461.4465 205.1187 77.4799 -179.0551 3.8278 49.6912 1,1,1,-1 No.0 No.0
DOBOT
CR6-5

DOBOT


Disconnect
Auto
Manager
CR6-5
R:1
D:1
N:1
ON
Current crew:Manager
Observer
Operator
Programer
Manager
Password:
CHANGE USER
DOBOT
CR6-5

DOBOT SCARA M-1

Opakovatelnost
0,02 mm

Rychlost
200°/s

Nosnost
1,5 kg

Dosah
400 mm

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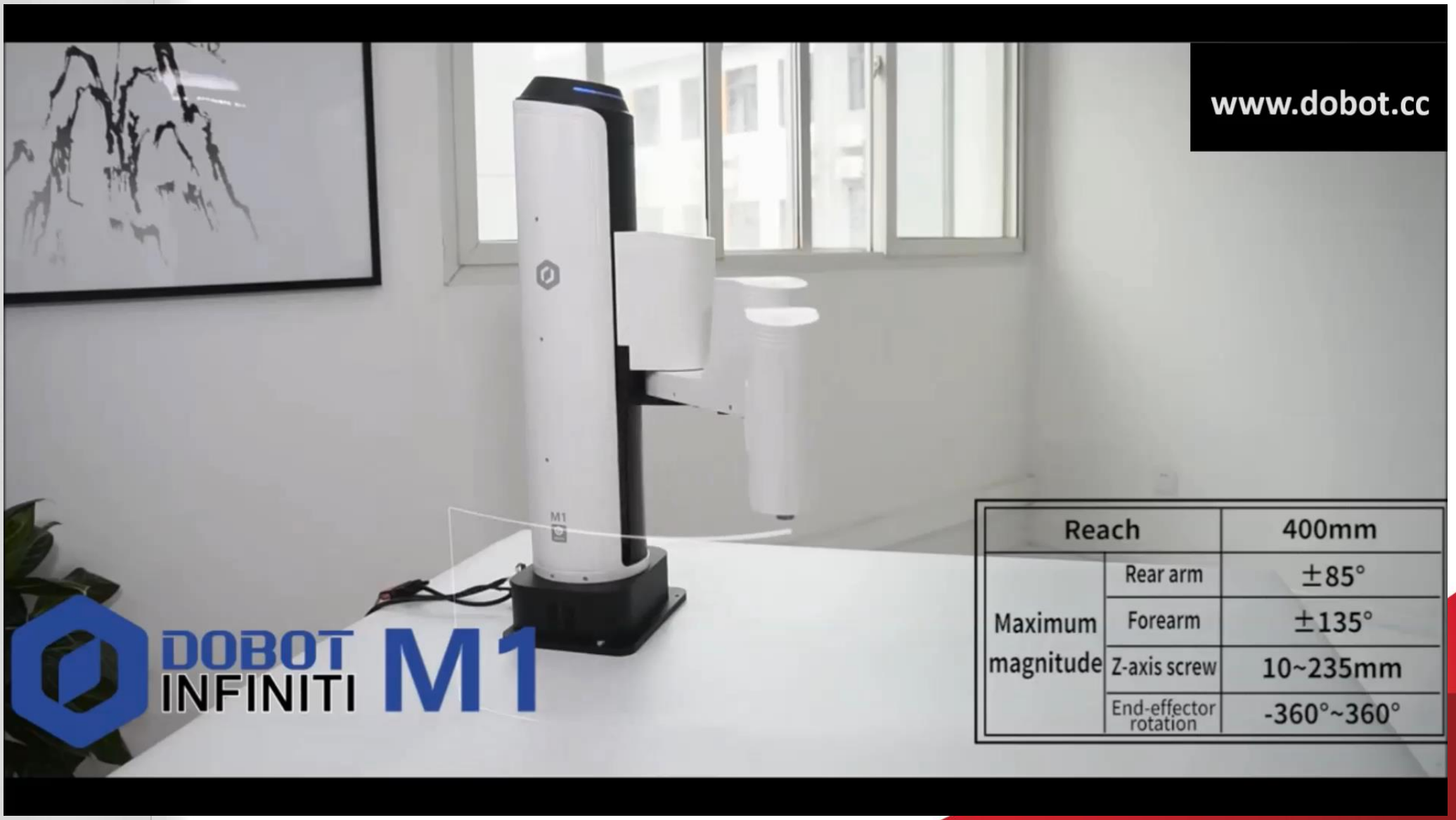

Reach		400mm
Maximum magnitude	Rear arm	±85°
	Forearm	±135°
	Z-axis screw	10~235mm
	End-effector rotation	-360°~360°

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M1Studio-V1.0.4 >> C:/Program Files/M1Studio/config/pbstore/Playback_Test_PV_01.playback

Settings Tools Help

Connect

DOBOT

Emergency Stop

Playback Script

New Open Save Save As Start Stop

Infinite Loop

Loop 5

DynRatio 100 %

1% 200%

Option

Index	Name	Type	Content
0		OUTPUT	OUT18=0V
1		MOVJ	To(154.0141, 298.2269, 96.0000, 22.6511), Vel/Jerk(20%, 50%), ArmOrientation(Right)
2		MOVJ	To(154.0141, 298.2269, 69.0000, 22.6511), Vel/Jerk(20%, 50%), ArmOrientation(Right)
3		OUTPUT	OUT17=0V
4		MOVJ	To(154.0141, 298.2269, 96.0000, 22.6511), Vel/Jerk(20%, 50%), ArmOrientation(Right)
5		MOVJ	To(78.1350, -386.5726, 96.0000, -161.1687), Vel/Jerk(50%, 50%), ArmOrientation(Left)
6		MOVJ	To(78.1350, -386.5726, 69.0000, -161.1687), Vel/Jerk(20%, 50%), ArmOrientation(Left)
7		OUTPUT	OUT17=24V
8		MOVJ	To(78.1350, -386.5726, 96.0000, -161.1687), Vel/Jerk(20%, 50%), ArmOrientation(Left)
9		WAIT	Pause 1.00 S
10		MOVJ	To(78.1350, -386.5726, 69.0000, -161.1687), Vel/Jerk(20%, 50%), ArmOrientation(Left)
11		OUTPUT	OUT17=0V
12		MOVJ	To(78.1350, -386.5726, 96.0000, -161.1687), Vel/Jerk(20%, 50%), ArmOrientation(Left)
13		MOVJ	To(154.0141, 298.2269, 96.0000, 22.6511), Vel/Jerk(50%, 50%), ArmOrientation(Right)
14		MOVJ	To(154.0141, 298.2269, 69.0000, 22.6511), Vel/Jerk(20%, 50%), ArmOrientation(Right)
15		OUTPUT	OUT17=24V
16		MOVJ	To(154.0141, 298.2269, 96.0000, 22.6511), Vel/Jerk(20%, 50%), ArmOrientation(Right)
17		WAIT	Pause 1.00 S

Add At Last

Insert Before Selected Row

OverWrite Selected Row

Enable Hand Hold Teach

Add Motion Command

PTP MOVJ

Vel 50 %

Jerk 50 %

Add Wait Command

1.00 s

Add I/O Command

Output Trigger

Apply DynRatio

Operation Panel

X	0,0000	Joint1	0,0000
Y	0,0000	Joint2	0,0000
Z	0,0000	Joint3	0,0000
R	0,0000	Joint4	0,0000

Joint

J1+ J2+ J3+ J4+

Vel 35 %

Acc 52 %

Motor: Power:

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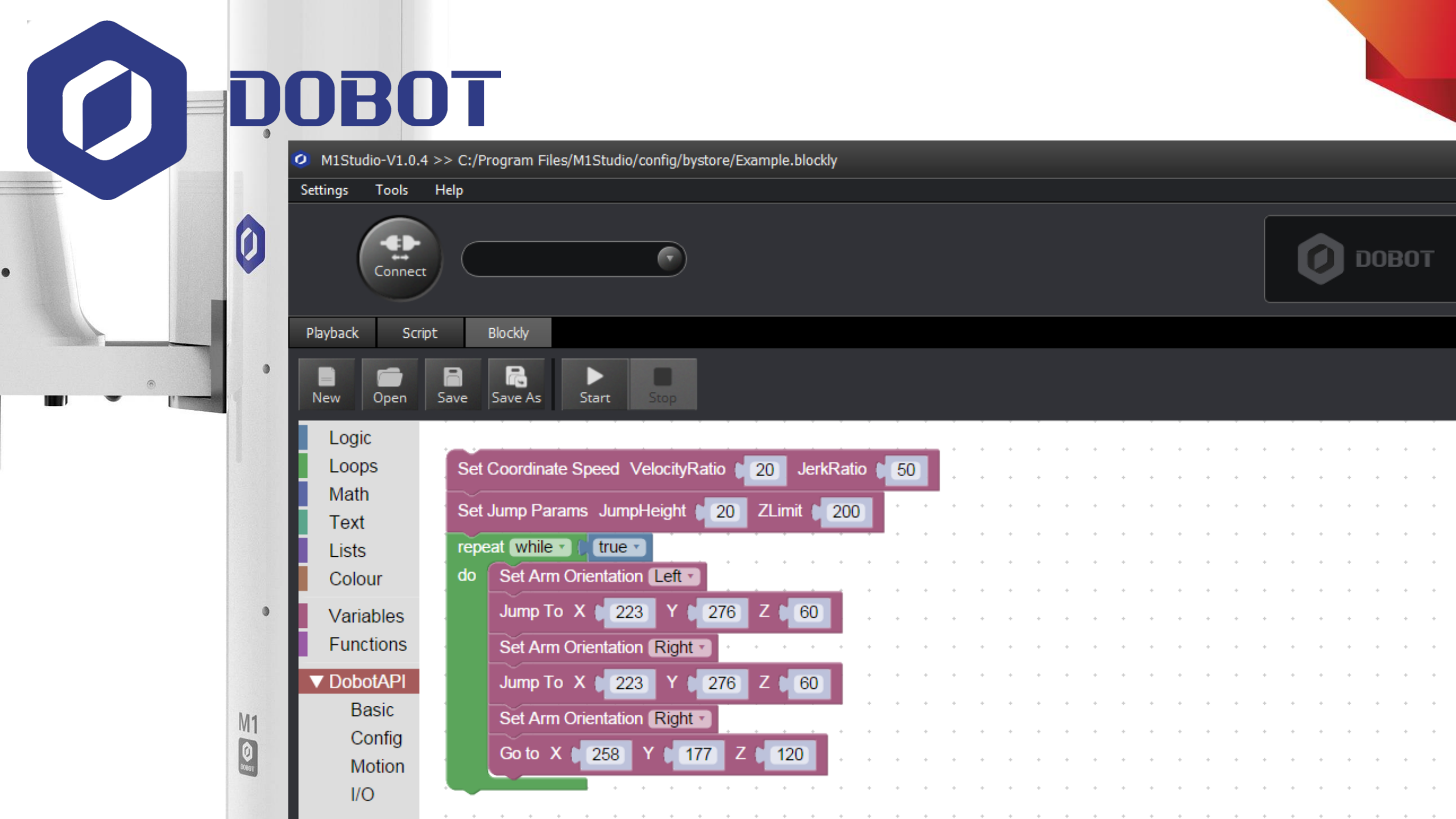
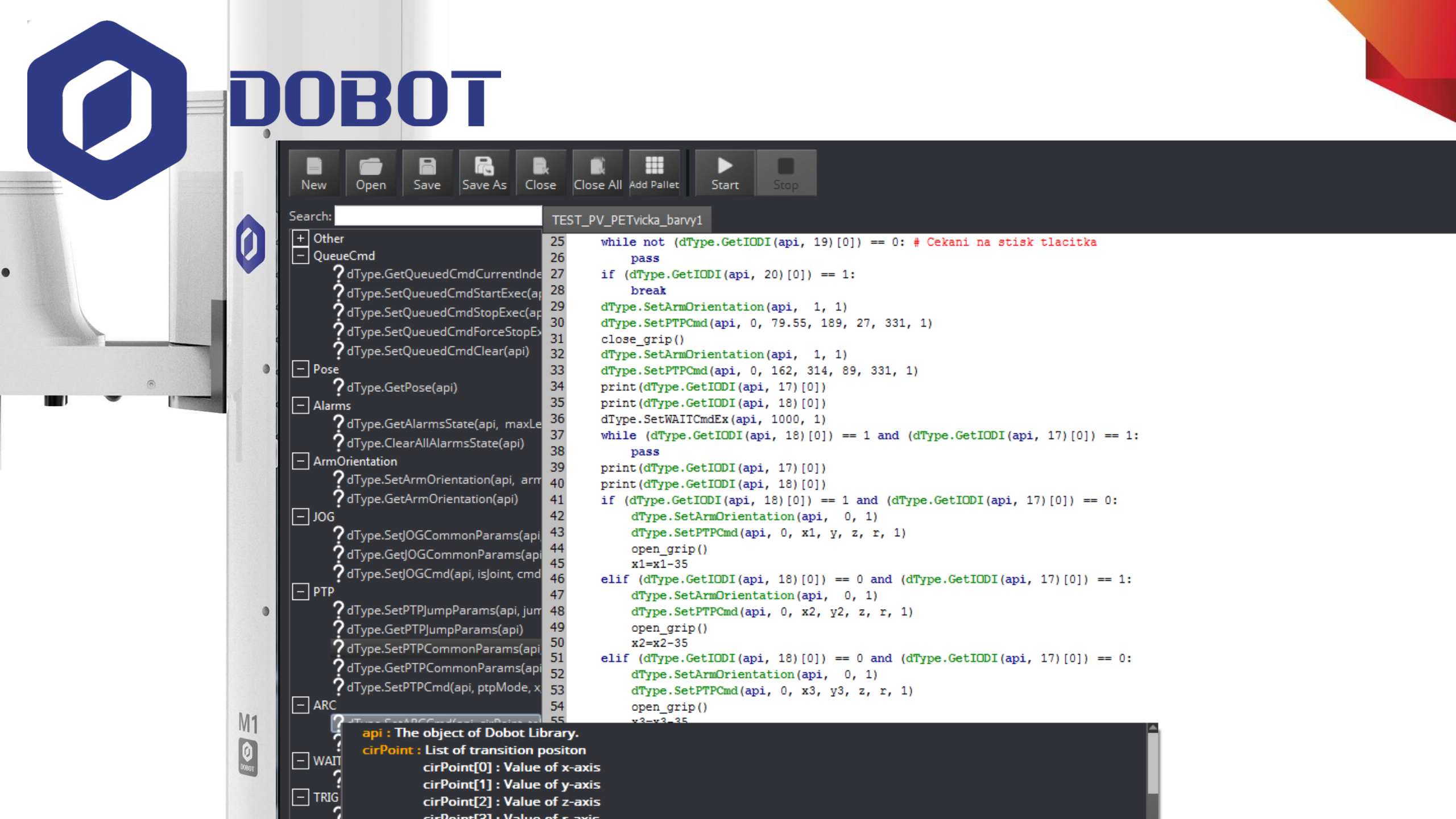

M1Studio-V1.0.4 >> C:/Program Files/M1Studio/config/bystore/Example.blockly
Settings
Tools
Help
Connect
DOBOT
Playback
Script
Blockly
New
Open
Save
Save As
Start
Stop
Logic
Loops
Math
Text
Lists
Colour
Variables
Functions
DobotAPI
Basic
Config
Motion
I/O
Set Coordinate Speed VelocityRatio 20 JerkRatio 50
Set Jump Params JumpHeight 20 ZLimit 200
repeat while true
do
Set Arm Orientation Left
Jump To X 223 Y 276 Z 60
Set Arm Orientation Right
Jump To X 223 Y 276 Z 60
Set Arm Orientation Right
Go to X 258 Y 177 Z 120
M1


DOBOT
New
Open
Save
Save As
Close
Close All
Add Pallet
Start
Stop
Search:
TEST_PV_PETvicka_barvy1
Other
QueueCmd
dType.GetQueuedCmdCurrentInde
dType.SetQueuedCmdStartExec(ap
dType.SetQueuedCmdStopExec(ap
dType.SetQueuedCmdForceStopEx
dType.SetQueuedCmdClear(api)
Pose
dType.GetPose(api)
Alarms
dType.GetAlarmsState(api, maxLe
dType.ClearAllAlarmsState(api)
ArmOrientation
dType.SetArmOrientation(api, arm
dType.GetArmOrientation(api)
JOG
dType.SetJOGCommonParams(api
dType.GetJOGCommonParams(api
dType.SetJOGCmd(api, isJoint, cmd
PTP
dType.SetPTPJumpParams(api, jum
dType.GetPTPJumpParams(api)
dType.SetPTPCommonParams(api
dType.GetPTPCommonParams(api
dType.SetPTPCmd(api, ptpMode, x
ARC
WAIT
TRIG
25 while not (dType.GetIODI(api, 19)[0]) == 0: # Cekani na stisk tlacitka
26 pass
27 if (dType.GetIODI(api, 20)[0]) == 1:
28 break
29 dType.SetArmOrientation(api, 1, 1)
30 dType.SetPTPCmd(api, 0, 79.55, 189, 27, 331, 1)
31 close_grip()
32 dType.SetArmOrientation(api, 1, 1)
33 dType.SetPTPCmd(api, 0, 162, 314, 89, 331, 1)
34 print(dType.GetIODI(api, 17)[0])
35 print(dType.GetIODI(api, 18)[0])
36 dType.SetWAITCmdEx(api, 1000, 1)
37 while (dType.GetIODI(api, 18)[0]) == 1 and (dType.GetIODI(api, 17)[0]) == 1:
38 pass
39 print(dType.GetIODI(api, 17)[0])
40 print(dType.GetIODI(api, 18)[0])
41 if (dType.GetIODI(api, 18)[0]) == 1 and (dType.GetIODI(api, 17)[0]) == 0:
42 dType.SetArmOrientation(api, 0, 1)
43 dType.SetPTPCmd(api, 0, x1, y, z, r, 1)
44 open_grip()
45 x1=x1-35
46 elif (dType.GetIODI(api, 18)[0]) == 0 and (dType.GetIODI(api, 17)[0]) == 1:
47 dType.SetArmOrientation(api, 0, 1)
48 dType.SetPTPCmd(api, 0, x2, y2, z, r, 1)
49 open_grip()
50 x2=x2-35
51 elif (dType.GetIODI(api, 18)[0]) == 0 and (dType.GetIODI(api, 17)[0]) == 0:
52 dType.SetArmOrientation(api, 0, 1)
53 dType.SetPTPCmd(api, 0, x3, y3, z, r, 1)
54 open_grip()
api : The object of Dobot Library.
cirPoint : List of transition positon
cirPoint[0] : Value of x-axis
cirPoint[1] : Value of y-axis
cirPoint[2] : Value of z-axis
M1

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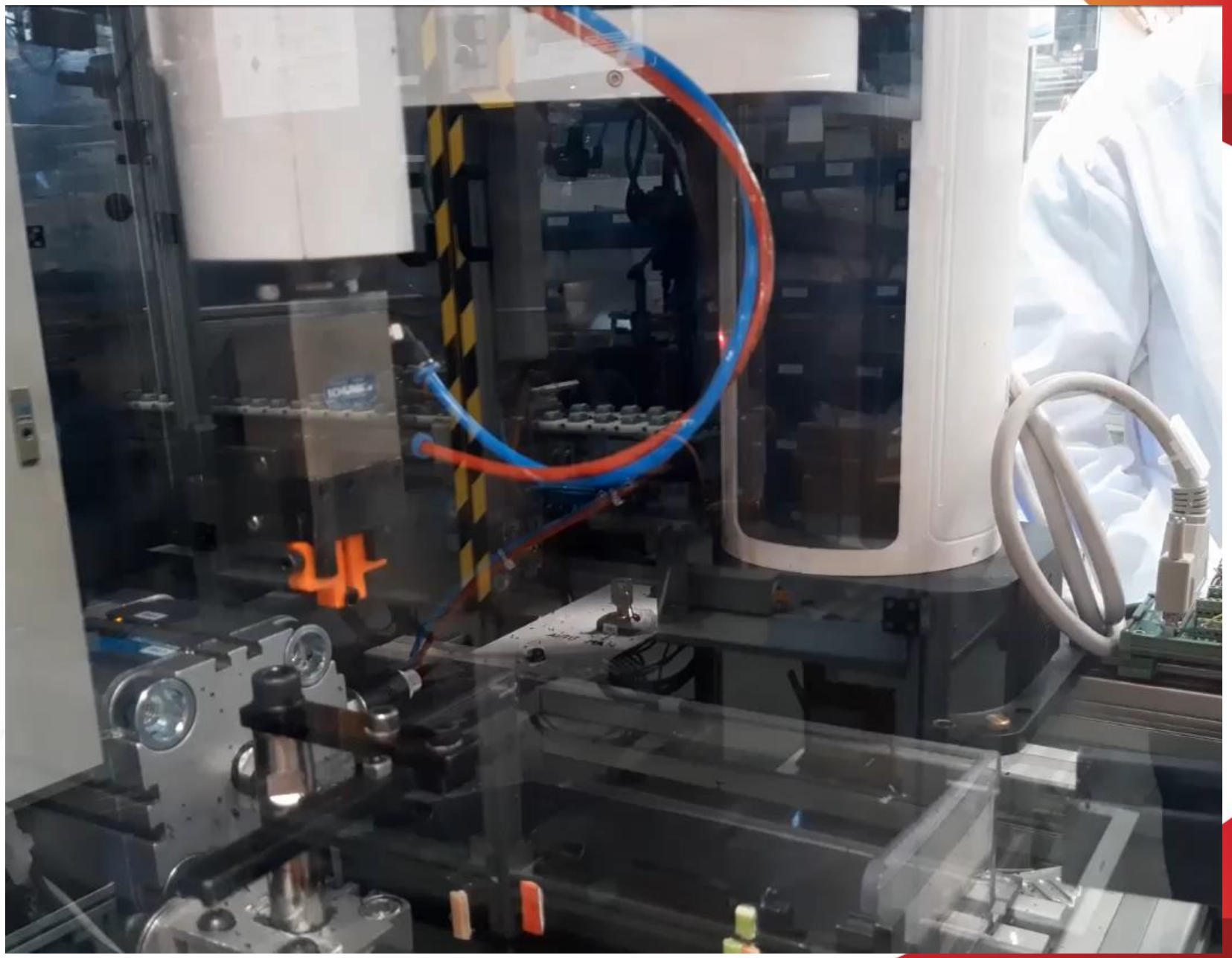

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DOBOT Magician

All-in-One Robot for Education

DESIGN AWARD 2018

reddot award 2018 winner

CES 2018

红星奖 Red Star Design Award

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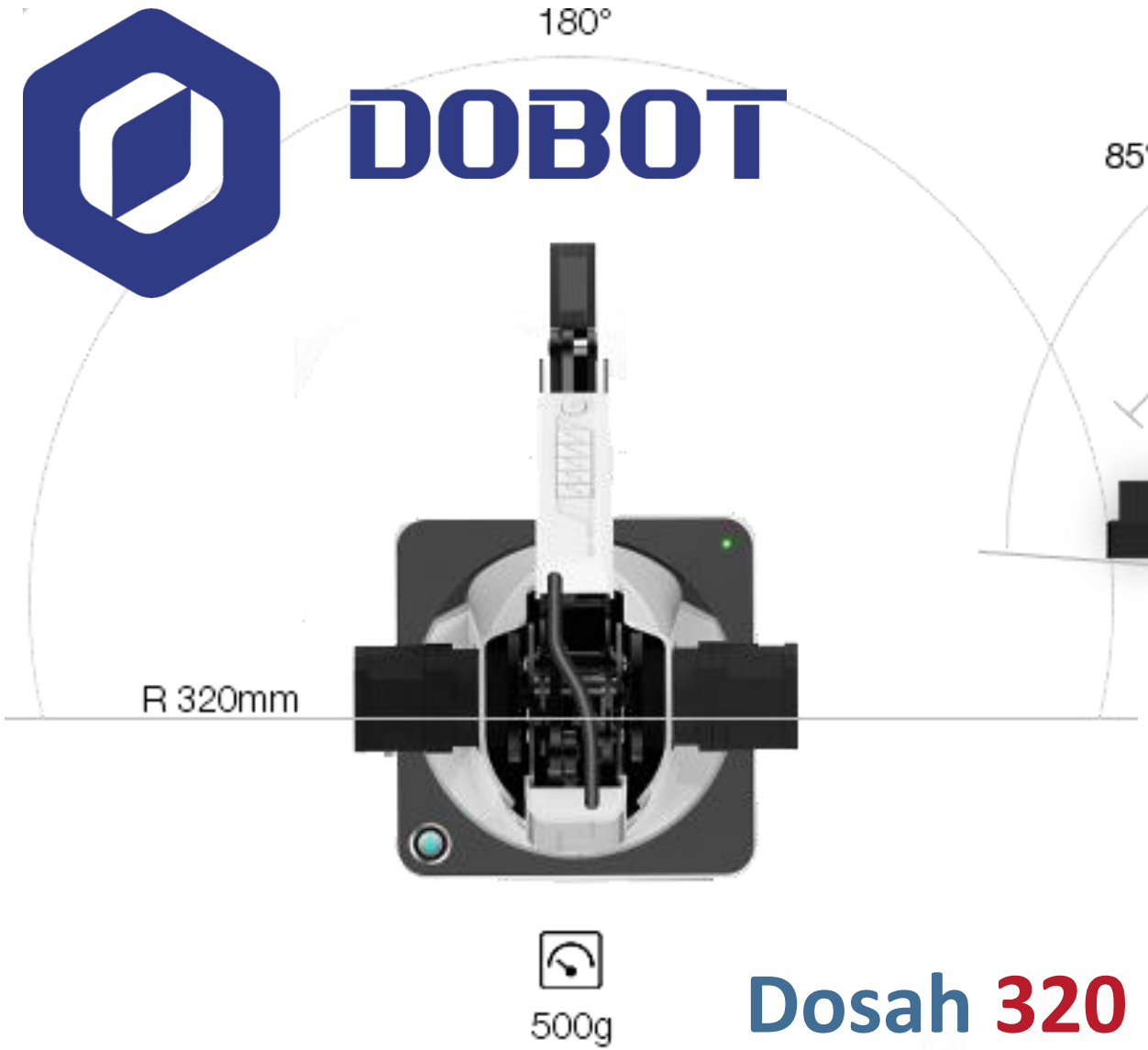

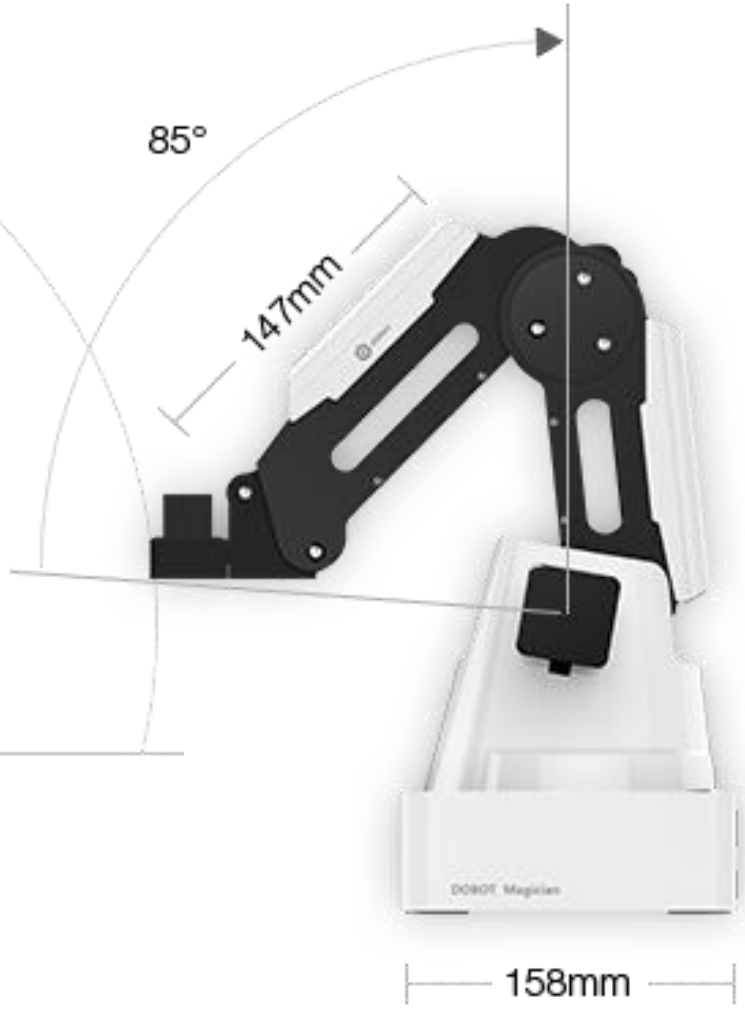

500g

Dosah 320 mm

opakovatelnost 0.2 mm

nosnost 500 g

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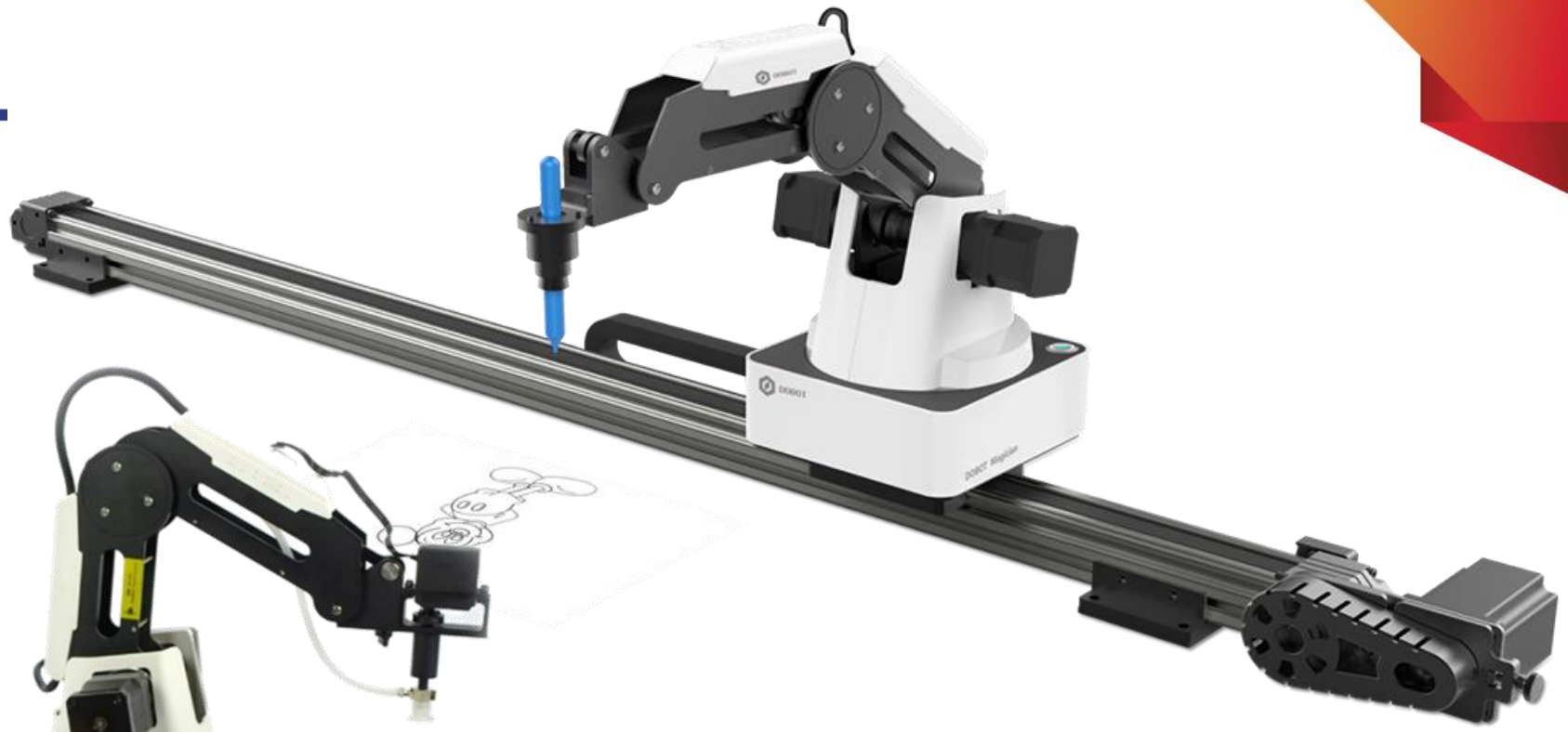
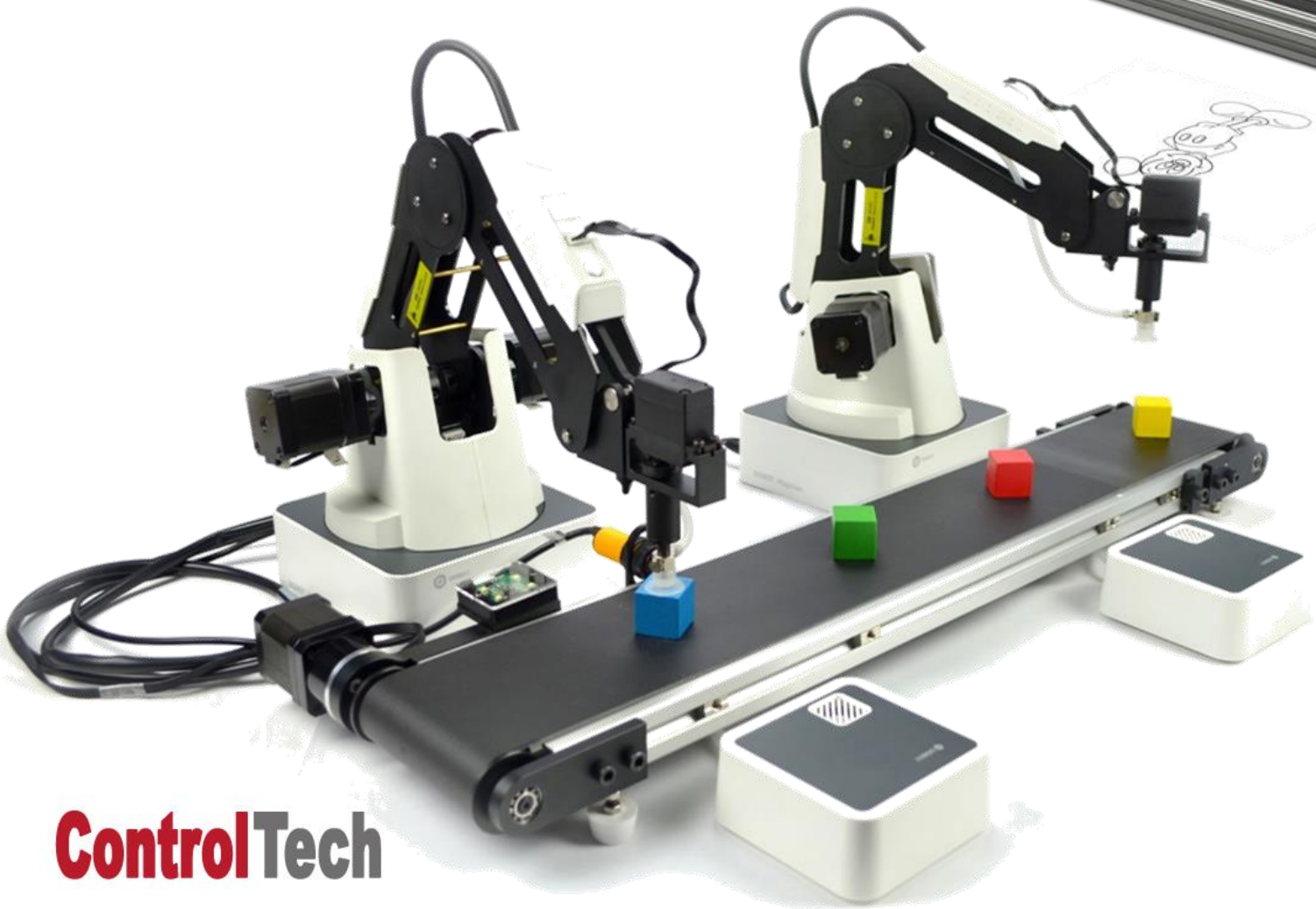
DOBOT

DOBOT





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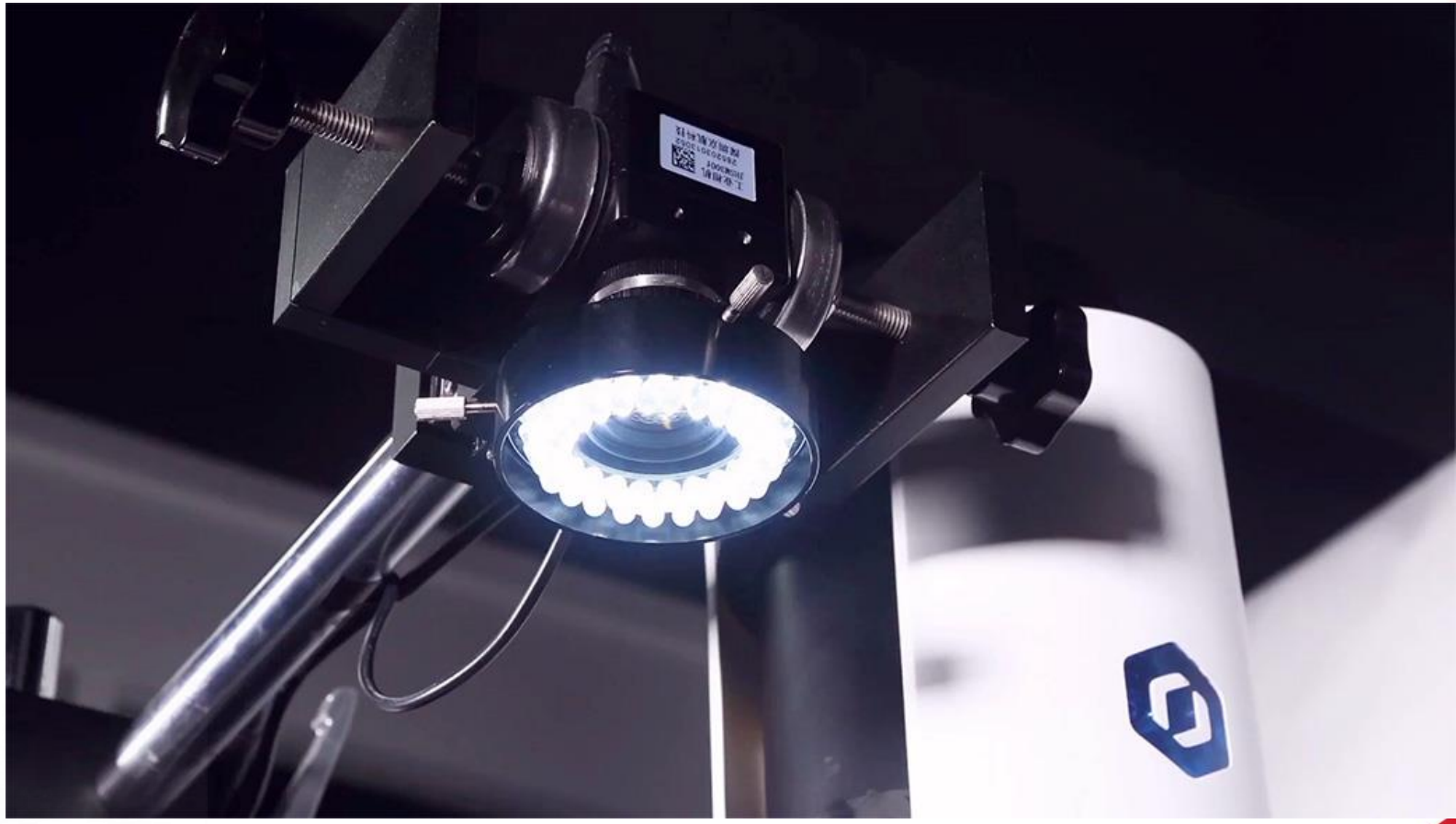
DOBOT



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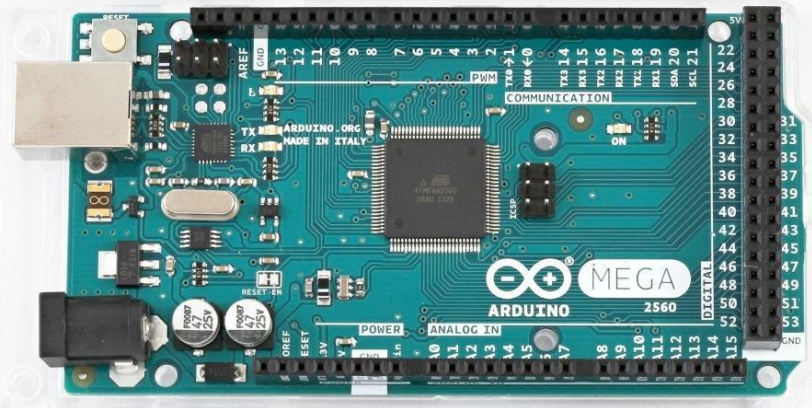
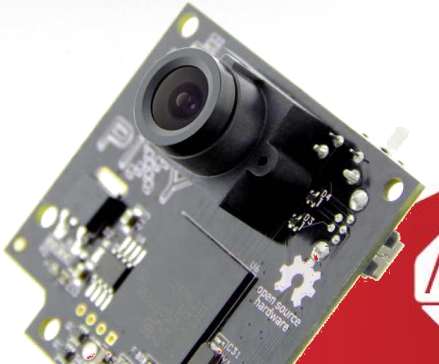
ARDUINO

EDUCATION





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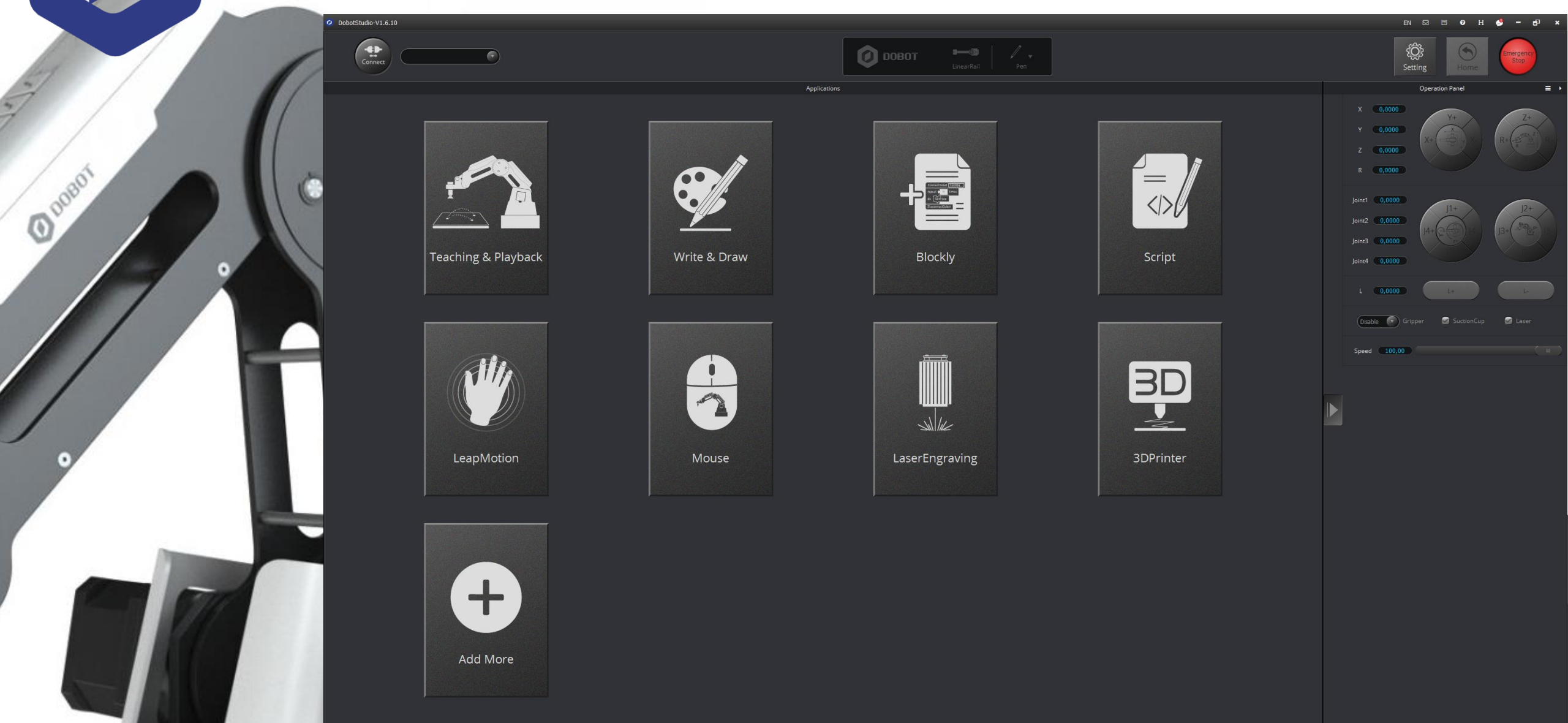
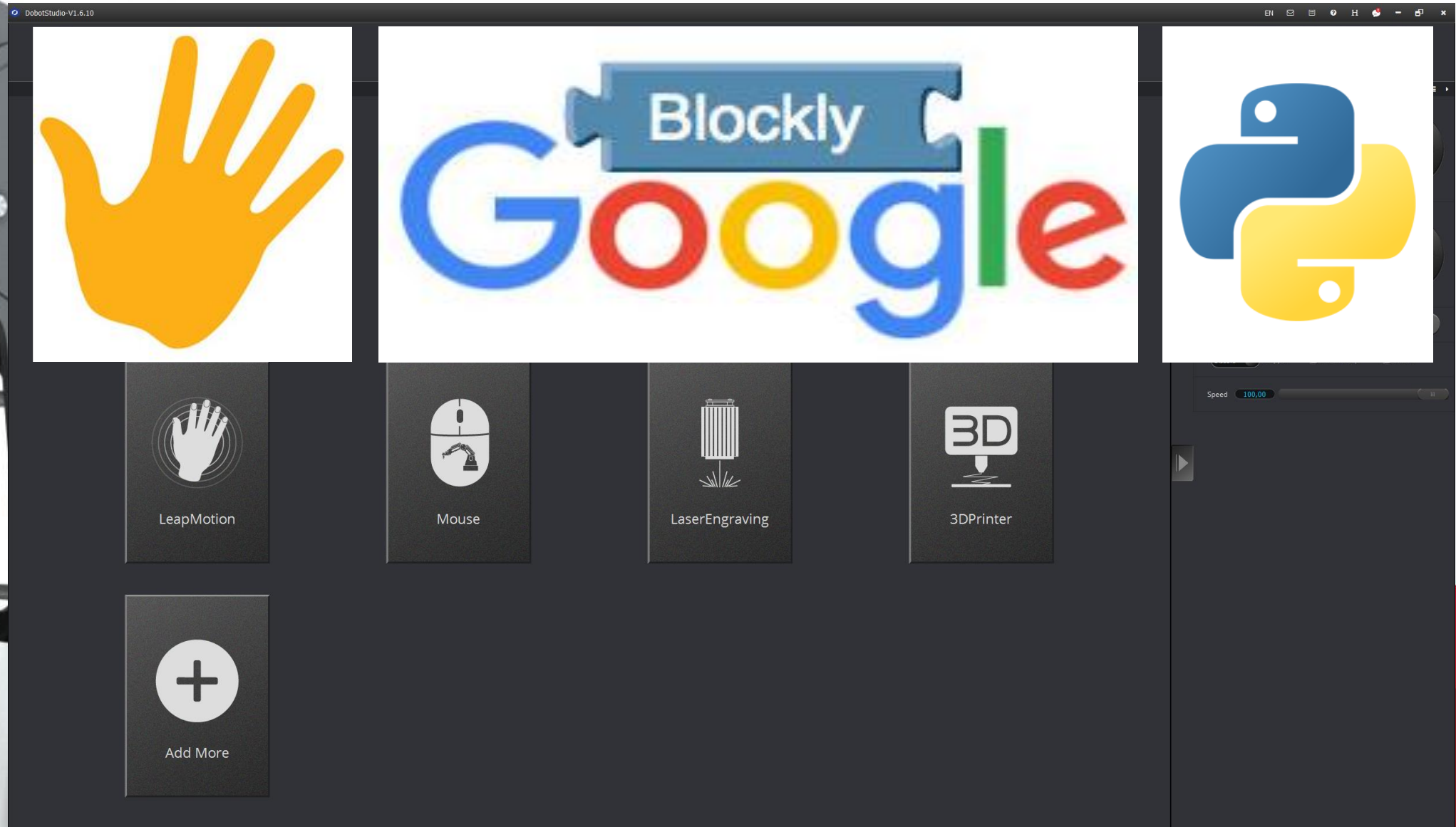

DobotStudio-V1.6.10
Connect
DOBOT
LinearRail
Pen
Setting
Home
Emergency Stop
Applications
Teaching & Playback
Write & Draw
Blockly
Script
LeapMotion
Mouse
LaserEngraving
3DPrinter
Add More
Operation Panel
X
Y
Z
R
Joint1
Joint2
Joint3
Joint4
L
Disable
Gripper
SuctionCup
Laser
Speed
100,00

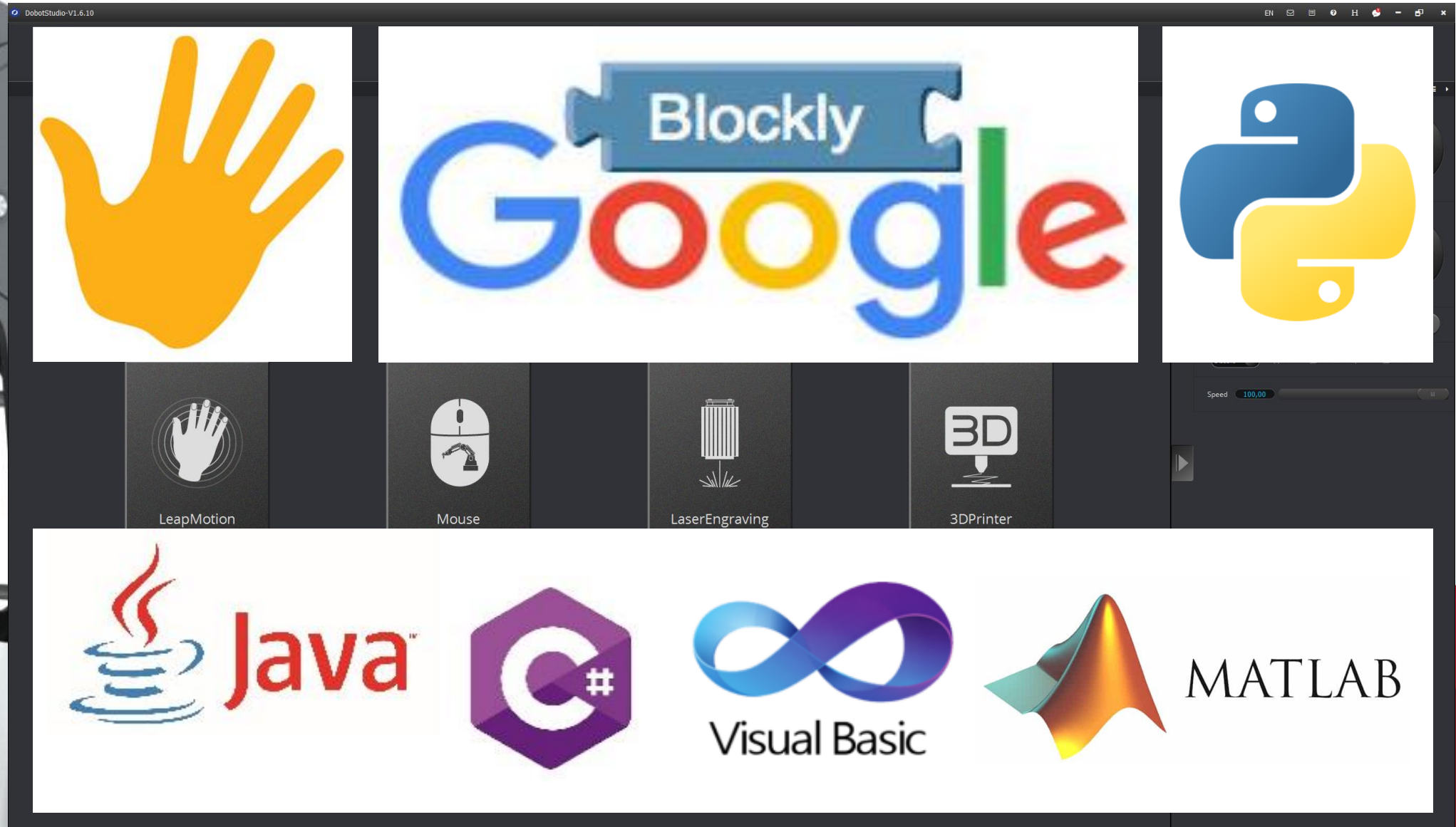
DOBOT


DOBOT


DobotStudio-V1.6.10
Blockly
Google
LeapMotion
Mouse
LaserEngraving
3DPrinter
Add More
Speed
100,00

DOBOT


DOBOT


DobotStudio-V1.6.10
Blockly
Google
Speed
100,00
LeapMotion
Mouse
LaserEngraving
3DPrinter
Java
Visual Basic
MATLAB

DobotStudio-untitled.playback

EN

Disconnect

COM11

DOBOT

LinearRail

SuctionCup

Setting

Home

Emergency Stop

Teaching & Playback

New Open Save SaveAs Start Stop

Easy Pro

Loop 100

Speed 50

Acc 50

Exit

Option

	MotionStyle	Name	X	Y	Z	R	PauseTime	SuctionCup
1	MOVJ	KROK 001	122.976	180.7739	-38.4769	55.7735	0	SuctionCupOff
2	MOVJ		188.7793	-25.09	13.9731	-7.5706	0.0	SuctionCupOff
3	MOVJ		75.3481	-200.8049	-38.256	-69.4324	0.0	SuctionCupOff
4	MOVJ		191.1944	-37.3886	135.9339	-11.0647	0.0	SuctionCupOff
5	MOVJ		157.2817	-187.2849	31.057	-49.9765	0.0	SuctionCupOff
6	MOVJ		199.4411	31.8717	-20.4231	9.0794	0.0	SuctionCupOff
7	MOVJ		222.1407	116.9612	79.019	27.7676	0.0	SuctionCupOff
8	MOVJ		184.9539	-43.591	-0.7109	-13.2618	0.0	SuctionCupOff
9	MOVJ		164.1302	-185.4772	75.2225	-48.4941	0.0	SuctionCupOff
10	MOVJ		206.341	-128.4213	116.31	-31.8971	0.0	SuctionCupOff
11	MOVJ		169.3341	-152.5164	63.9103	-42.0088	0.0	SuctionCupOff
12	MOVJ		136.5666	-150.5033	28.1913	-47.7794	0.0	SuctionCupOff
13	MOVJ		204.8583	-120.8976	11.1428	-30.5471	0.0	SuctionCupOff
14	MOVJ		208.0085	-27.4501	64.8908	-7.5177	0.0	SuctionCupOff
15	MOVJ		223.9895	38.4529	126.0804	9.7412	0.0	SuctionCupOff
16	MOVJ		174.4121	86.445	24.1449	26.3647	0.0	SuctionCupOff
17	MOVJ		130.9011	182.9993	69.5842	54.4235	0.0	SuctionCupOff
18	MOVJ		152.4365	152.7184	-4.5646	45.0529	0.0	SuctionCupOff
19	MOVJ		209.0913	55.3361	-10.2153	14.8235	0.0	SuctionCupOff

+Point

PTP Point

Move Mode

MOVJ

MOVL

JUMP

ARC Point

Point Type

cirPoint

toPoint

PauseTime

0,00 s

Operation Panel

X 222,1406

Y 116,9612

Z 79,0190

R 27,7676

Y+ X+ X- Y-

Z+ R+ R- Z-

Joint1 27,7676

Joint2 22,4895

Joint3 18,1184

Joint4 0,0000

J1+ J4+ J4- J1-

J2+ J3+ J3- J2-

L 0,0000

L+ L-

Disable Gripper SuctionCup Laser

Speed 42,00

DOBOT

DobotStudio-untitled.playback

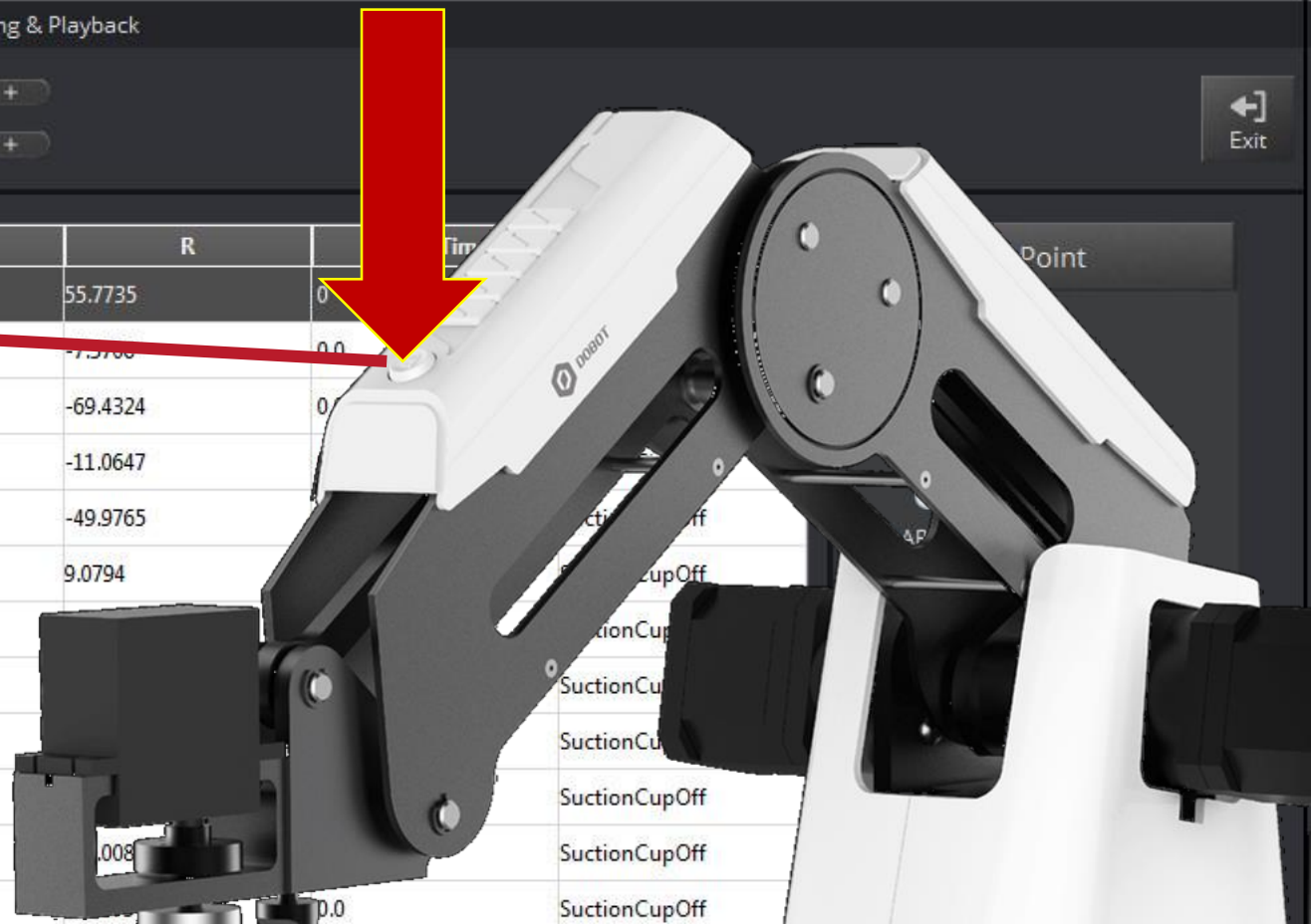
Disconnect | COM11 | DOBOT | LinearRail | SuctionCup

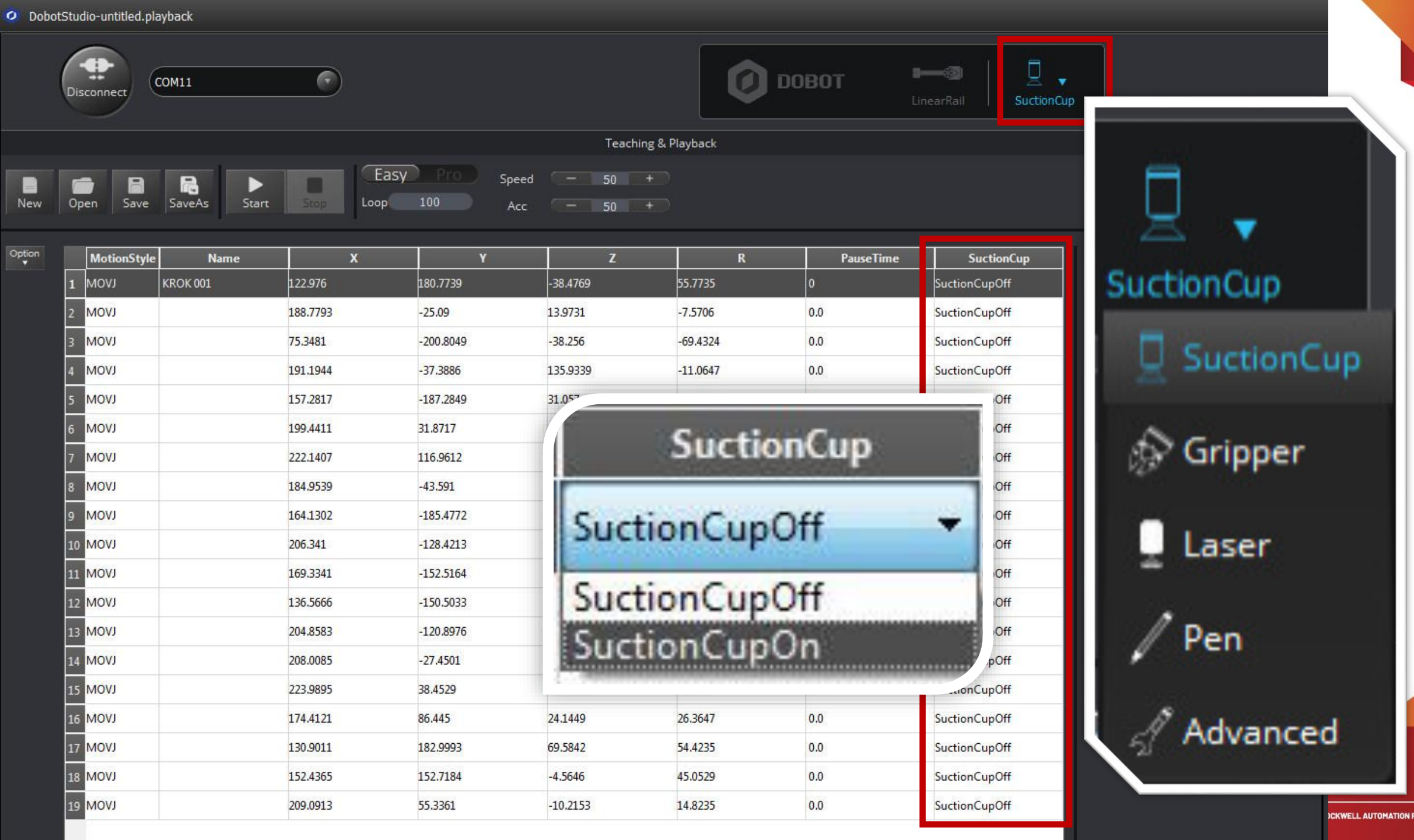
Teaching & Playback

New | Open | Save | SaveAs | Start | Stop | Easy | Pro | Loop 100 | Speed 50 | Acc 50 | Exit

Option

	MotionStyle	Name	X	Y	Z	R	Point
1	MOVJ	KROK 001	122.976	180.7739	-38.4769	55.7735	0
2	MOVJ		188.7793	-25.09	13.9731		0.0
3	MOVJ		75.3481	-200.8049	-38.256	-69.4324	0
4	MOVJ		191.1944	-37.3886	135.9339	-11.0647	
5	MOVJ		157.2817	-187.2849	31.057	-49.9765	
6	MOVJ		199.4411	31.8717	-20.4231	9.0794	
7	MOVJ		222.1407	116.9612	79.019		
8	MOVJ		184.9539	-43.591	-0.7109		
9	MOVJ		164.1302	-185.4772	75.2225		
10	MOVJ		206.341	-128.4213	116.31		SuctionCupOff
11	MOVJ		169.3341	-152.5164	63.9103		SuctionCupOff
12	MOVJ		136.5666	-150.5033	28.1913	0.0	SuctionCupOff




DobotStudio-untitled.playback
Disconnect
COM11
DOBOT
LinearRail
SuctionCup
Teaching & Playback
New
Open
Save
SaveAs
Start
Stop
Easy
Pro
Loop
100
Speed
50
Acc
50
Option
MotionStyle
Name
X
Y
Z
R
PauseTime
SuctionCup
1 MOVJ KROK 001 122.976 180.7739 -38.4769 55.7735 0 SuctionCupOff
2 MOVJ 188.7793 -25.09 13.9731 -7.5706 0.0 SuctionCupOff
3 MOVJ 75.3481 -200.8049 -38.256 -69.4324 0.0 SuctionCupOff
4 MOVJ 191.1944 -37.3886 135.9339 -11.0647 0.0 SuctionCupOff
5 MOVJ 157.2817 -187.2849
6 MOVJ 199.4411 31.8717
7 MOVJ 222.1407 116.9612
8 MOVJ 184.9539 -43.591
9 MOVJ 164.1302 -185.4772
10 MOVJ 206.341 -128.4213
11 MOVJ 169.3341 -152.5164
12 MOVJ 136.5666 -150.5033
13 MOVJ 204.8583 -120.8976
14 MOVJ 208.0085 -27.4501
15 MOVJ 223.9895 38.4529
16 MOVJ 174.4121 86.445 24.1449 26.3647 0.0 SuctionCupOff
17 MOVJ 130.9011 182.9993 69.5842 54.4235 0.0 SuctionCupOff
18 MOVJ 152.4365 152.7184 -4.5646 45.0529 0.0 SuctionCupOff
19 MOVJ 209.0913 55.3361 -10.2153 14.8235 0.0 SuctionCupOff
SuctionCup
SuctionCupOff
SuctionCupOff
SuctionCupOn
SuctionCup
SuctionCup
Gripper
Laser
Pen
Advanced

DobotStudio-untitled.blockly

Connect

DOBOT

LinearRail

Blockly

New | Open | Save | SaveAs | Start | Stop

- Logic
- Loops
- Math
- Text
- Lists
- Colour
- Variables
- Functions
- ▼ DobotAPI
  - Basic
  - Config
  - Motion
  - I/O
  - Additional

```
Home
ChooseEndTools Gripper
SetCoordinateSpeed Velocity 20 Acceleration 50
SetJumpHeight Height 20
JumpTo X 200 Y 0 Z 0
Delaytime 0 s
MoveTo X 200 Y 0 Z 0
Set5VOutput EIO EIO10 IsEnabled ON

Laser ON Power 50
MoveLinearRailTo 0
SetConveyor Motor STEPPER1 Speed 50 mm/s
SetPhotoelectricSensor OFF Version V1 Port GP1
```

```
if GetLevelInput EIO EIO01 = 0
do Gripper Release

set Osa X to 200

repeat 10 times
do MoveTo X Osa X + 10 Y 75 Z 100

to seznam
in list Osa X insert at first as 200

seznam
```

DobotStudio-untitled.blockly

Disconnect

COM11

DOBOT

LinearRail

SuctionCup

Blockly

New Open Save SaveAs Start Stop

- Logic
- Loops
- Math
- Text
- Lists
- Colour
- Variables
- Functions
- ▼ DobotAPI
  - Basic
  - Config
  - Motion
  - I/O
  - Additional

JumpTo X 200 Y 0 Z 0

MoveTo X 200 Y 0 Z 0

MoveDistance ΔX 0 ΔY 0 ΔZ 0

SetR 0

Check Lost Step

SetJointAngle Joint1 0 Joint2 45 Joint3 45

GetCurrentCoordinate x

GetJointAngle Joint1

SuctionCup ON

Gripper Gripper

- Logic
- Loops
- Math
- Text
- Lists
- Colour
- Variables
- Functions
- ▼ DobotAPI
  - Basic
  - Config
  - Motion
  - I/O
  - Additional

Laser ON Power 50

SetPhotoelectricSensor OFF Version V1 Port GP1

GetPhotoelectricSensor GP1

SetColorSensor OFF Version V1 Port GP1

IdentifyColor r

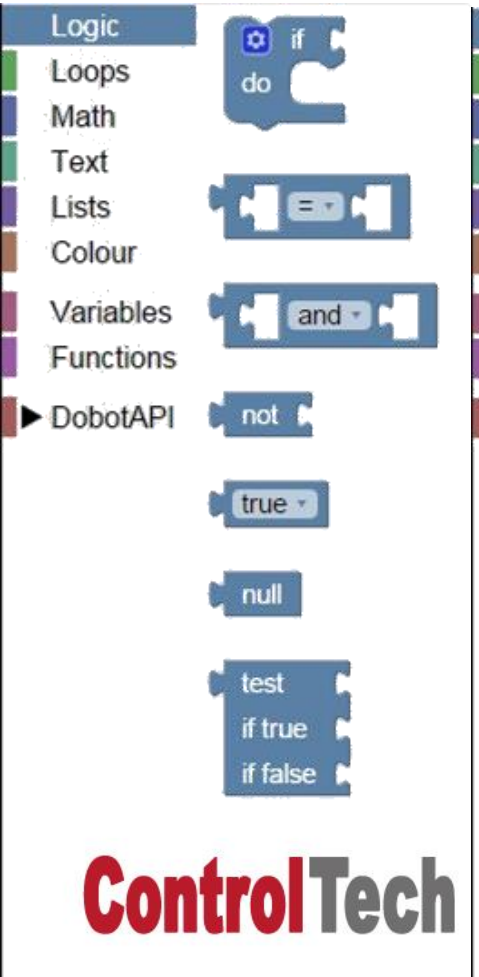
SetConveyor Motor STEPPER1 Speed 50 mm/s

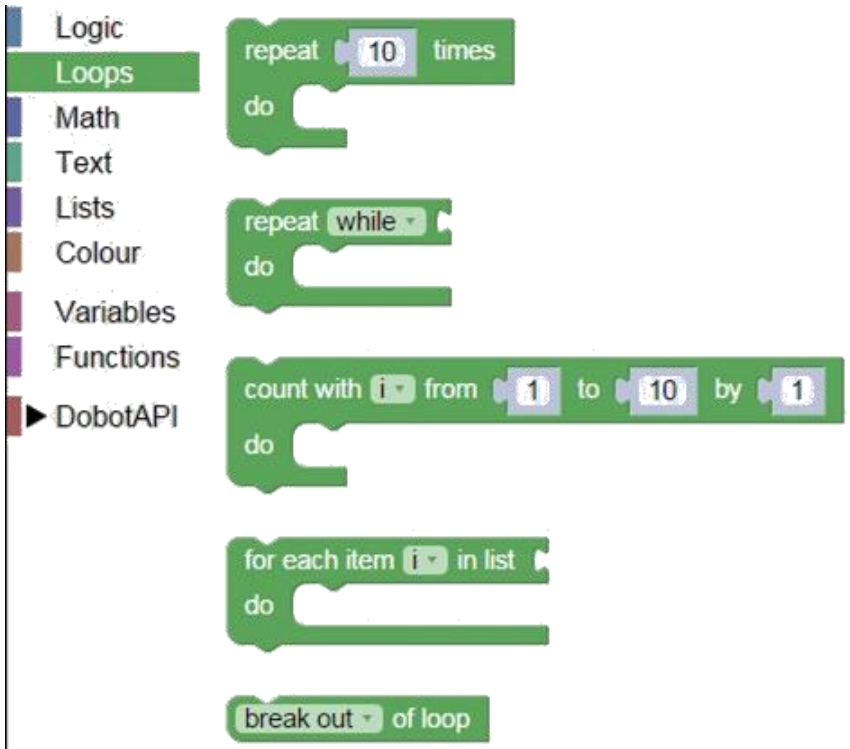
SetLinearRail IsEnabled OFF Version V1

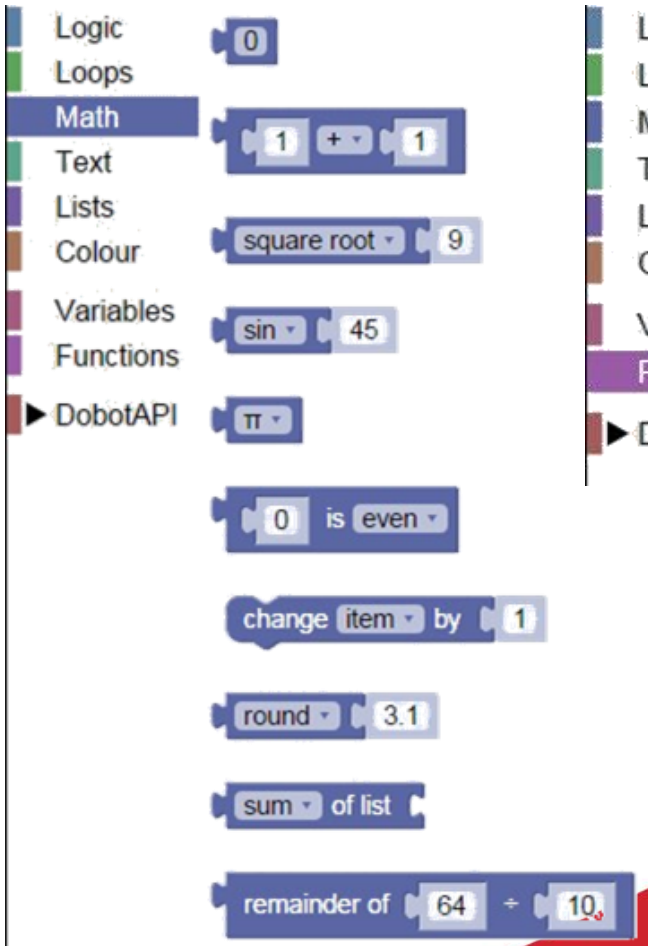
MoveLinearRailTo 0

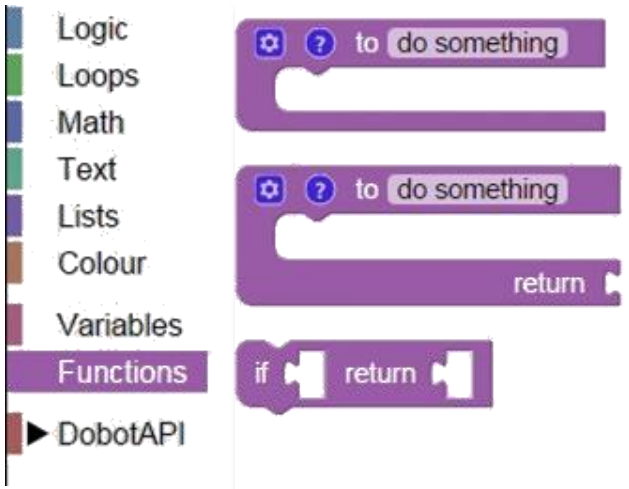
DOBOT

Blockly Google









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Gripper Release

count with Pozice from 1 to 4 by 1

do

JumpTo X in list in list Leva get # 1 get # Pozice Y in list in list

Gripper Gripper

Delaytime 1 s

JumpTo X in list in list Prava get # 1 get # Pozice Y in list in list

Gripper Release

Delaytime 0.5 s

count with Pozice from 1 to 4 by 1

do

JumpTo X in list in list Prava get # 1 get # Pozice Y in list in list

Gripper Gripper

Delaytime 1 s

JumpTo X in list in list Leva get # 1 get # Pozice Y in list in list

Returns the value of this variable.

Gripper Release

Delaytime 0.5 s

MoveTo X 180 Y 0 Z 25

Leva = [[225.5, 235.6279, 245.4217, 255.5538, 265.4469, 274.8148], [43, 42.999, 42.5677, 42.2319, 42.28, 41.8972]]
Prava = [[223.6901, 233.7885, 243.7215, 253.4057, 263.3534, 273.2444], [-42.9919, -43.1828, -43.5424, -43.5426, -43.8326, -44.0512]]
dType.SetEndEffectorParamsEx(api, 59.7, 0, 0, 1)
dType.SetPTPJumpParamsEx(api,40,100,1)
dType.SetPTPLParamsEx(api,20,50,1)
dType.SetHOMECmdEx(api, 0, 1)
print('HOME FINISHED')
current_pose = dType.GetPose(api)
dType.SetPTPCmdEx(api, 2, 180, 0, 25, current_pose[3], 1)
current_pose = dType.GetPose(api)
dType.SetPTPCmdEx(api, 4, current_pose[4], current_pose[5], current_pose[6], 8.4, 1)
Z = -20.5
dType.SetEndEffectorGripperEx(api, 1, 0)
for Pozice in range(1, 5):
  dType.SetPTPCmdEx(api, 0, ((Leva[0])[int(Pozice - 1)]), ((Leva[1])[int(Pozice - 1)]), Z, 0, 1)
  dType.SetEndEffectorGripperEx(api, 1, 1)
  dType.SetWAITCmdEx(api, 1, 1)
  dType.SetPTPCmdEx(api, 0, ((Prava[0])[int(Pozice - 1)]), ((Prava[1])[int(Pozice - 1)]), Z, 0, 1)
  dType.SetEndEffectorGripperEx(api, 1, 0)
  dType.SetWAITCmdEx(api, 0.5, 1)
for Pozice in range(1, 5):
  dType.SetPTPCmdEx(api, 0, ((Prava[0])[int(Pozice - 1)]), ((Prava[1])[int(Pozice - 1)]), Z, 0, 1)
  dType.SetEndEffectorGripperEx(api, 1, 1)
  dType.SetWAITCmdEx(api, 1, 1)
  dType.SetPTPCmdEx(api, 0, ((Leva[0])[int(Pozice - 1)]), ((Leva[1])[int(Pozice - 1)]), Z, 0, 1)
  dType.SetEndEffectorGripperEx(api, 1, 0)
  dType.SetWAITCmdEx(api, 0.5, 1)

DOBOT

New Open Save SaveAs Close CloseAll Add Pallet Start Stop

Search:

Example_JOG Example_PTP

- Other
- QueueCmd
- Pose
- Alarms
- HOME
- HandTeach
- EndEffector
- LinearRail
- JOG
- PTP
- CP
- ARC
- WAIT
- TRIG
- EIO
- AngleSensor
- ColorSensor
- WIFI
- LostStep
  - dType.SetLostStepParams(api, thre
  - dType.SetLostStepCmd(api, isQue

```
15 dType.SetWAITCmdEx(api, 0, 1)
16 current_pose = dType.GetPose(api)
17 dType.SetPTPCmdEx(api, 2, 200,  0,  0, current_pose[3], 1)
18 dType.SetIODOEx(api, 10, 1, 1)
19
20 if (dType.GetIODI(api, 1)[0]) == 0:
21   dType.SetEndEffectorGripperEx(api, 1, 0)
22
23 Osa_X = 200
24
25 for count in range(10):
26   current_pose = dType.GetPose(api)
27   dType.SetPTPCmdEx(api, 2, (Osa_X + 10),  75,  100, current_pose[3], 1)
28
29 dType.SetEndEffectorLaserEx(api, 1, 50, 1)
30 current_pose = dType.GetPose(api)
31 dType.SetPTPWithLCmdEx(api, 1, current_pose[0], current_pose[1], current_pose[2], current_pose[3], 0, 1)
32 STEP_PER_CRICLE = 360.0 / 1.8 * 10.0 * 16.0
33 MM_PER_CRICLE = 3.1415926535898 * 36.0
34 vel = float(50) * STEP_PER_CRICLE / MM_PER_CRICLE
35 dType.SetEMotorEx(api, 0, 1, int(vel), 1)
36 dType.SetInfraredSensor(api, 0 ,0, 0)
```

Params:

#Warning# Don't change the "api" Variable.

api : The object of Dobot Library.

#Warning# You must use queue mode for current firmware.

isQueued : The switch state of using queue mode

1 : use queue mode

0 : don't use queue mode

DOBOT

python SOFTWARE FOUNDATION

Open source

Podpora běžných platforem

Linux, Unix

Windows

macOS

Android

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DOBOT

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Instagram

YouTube

Walt Disney

Bitbucket

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NASA

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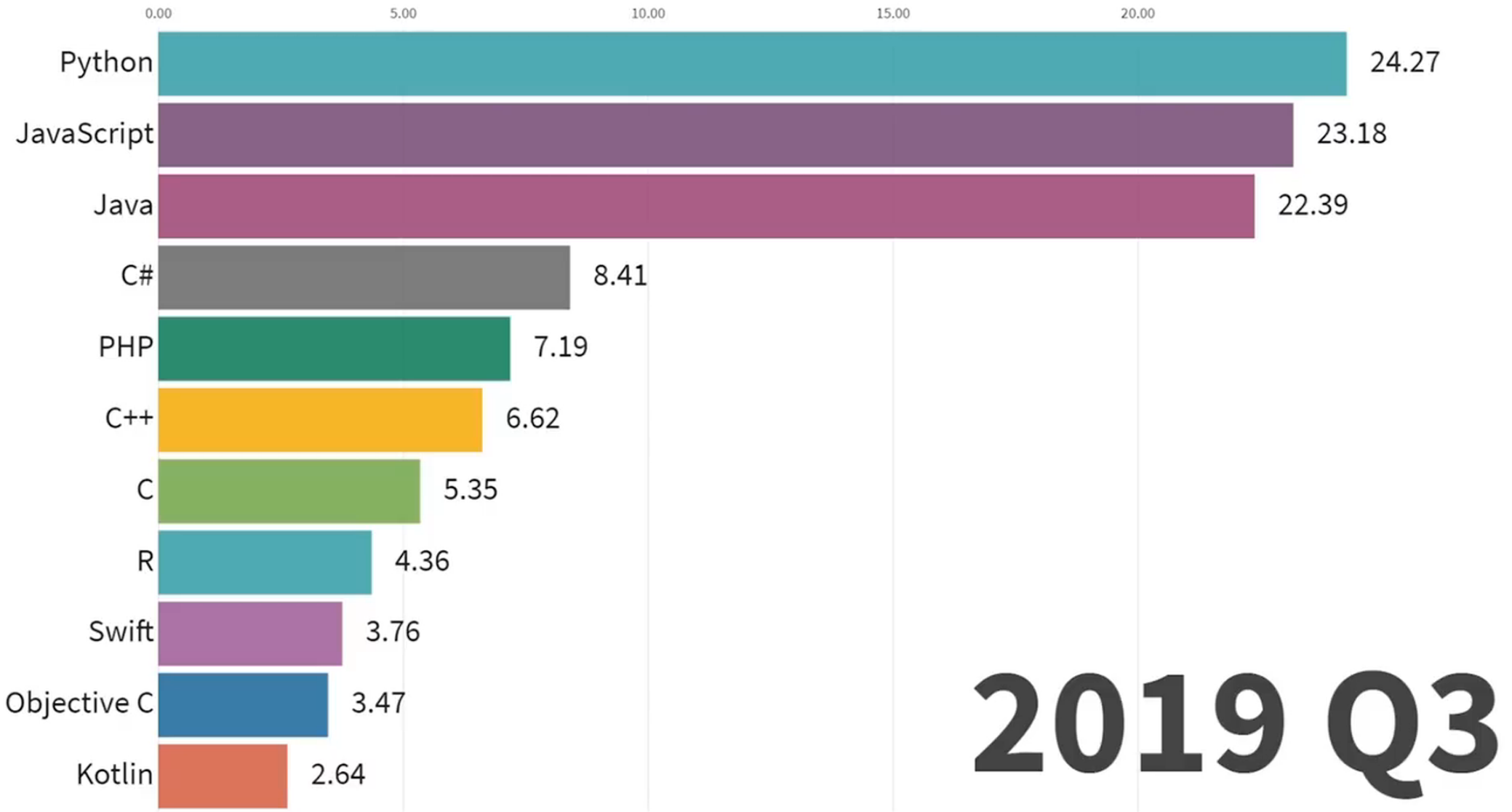

2019 Q3

DOBOT

python SOFTWARE FOUNDATION

Java

```java
import java.util.ArrayList;

public class Main {
    public static void main(String[] args) {
        ArrayList al = new ArrayList();
        al.add("a");
        al.add("b");
        al.add("c");
        System.out.println(al);
    }
}
```

Python

```python
aList = []

aList.append("a")
aList.append("b")
aList.append("c")

print(aList)
```

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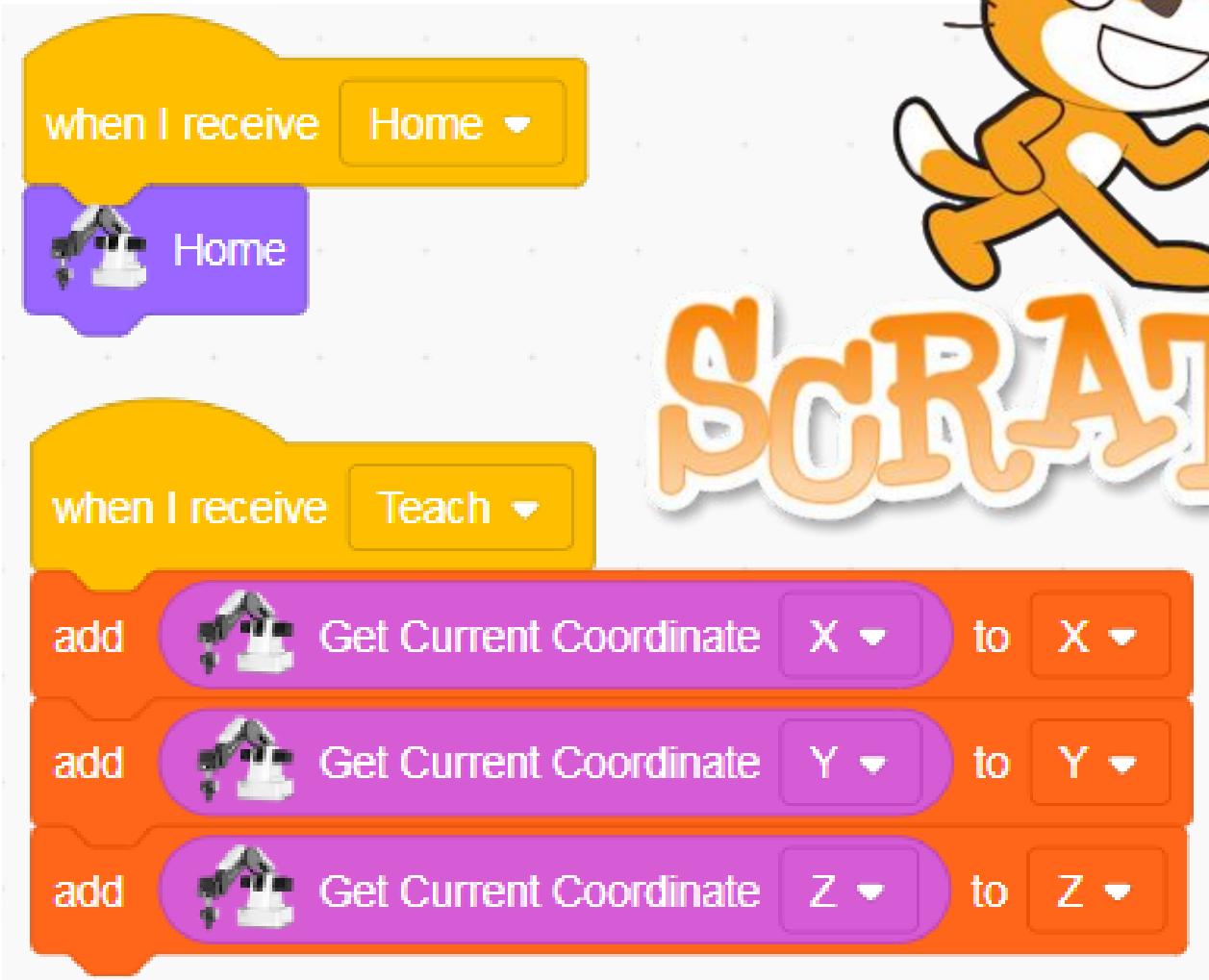

SCRATCH

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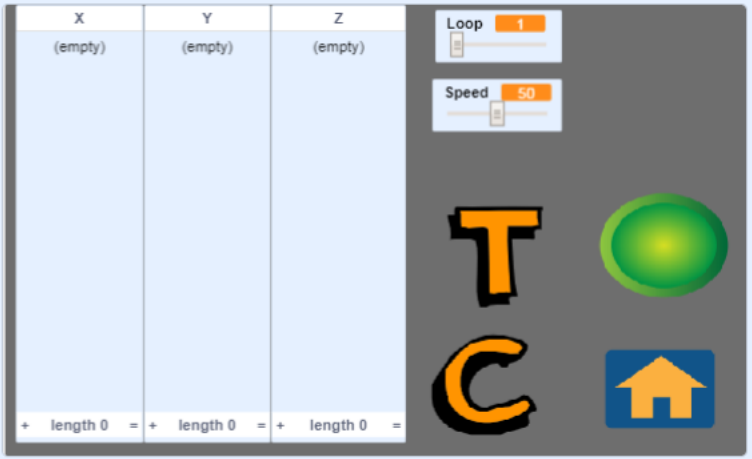
DobotScratch 1.3.1

DOBOT | File | Edit | Help | Playback



Device | Sprite

Magician

Coordiate | Velocity

X 0
Y 0
Z 0
R 0

Y+ X- Z+ X+ Z- Y-

R- R+

LinearRail L- L+

ON OFF

SuctionCup

Code

Control
Operators
Variables
Sensing
Events
Setting
Motion
Status
I/O
My Blocks

Motion

Home
Jump To X 0 Y 0 Z 0 R
Goto X 0 Y 0 Z 0 R 0
Relative Move ΔX 0 mm ΔY 0
Move Joints to Joint1 0 ° Joint2 0
Set R 0 °
Gripper Grip
Suction Cup ON

Status

Check Lost Step
Get Current Coordinate X
Get Current Joint Angle Joint1
Clear Alarm

I/O

Set Pin EIO1 Mode IOFunctionDu
Set PWM Output Port EIO1 Freque
Set digital Output Port EIO1 Value

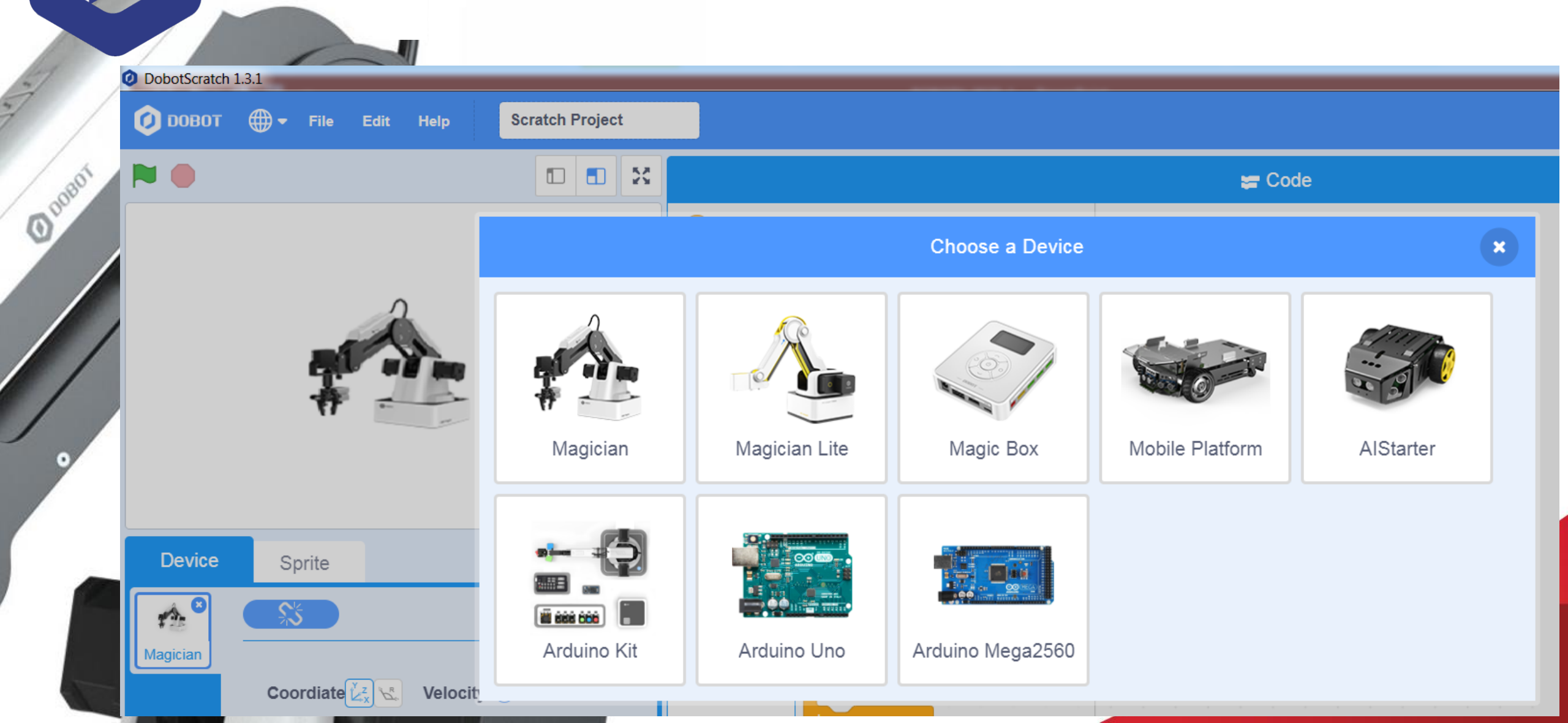
when I receive Home
Home

when I receive Teach
add Get Current Coordinate X to X
add Get Current Coordinate Y to Y
add Get Current Coordinate Z to Z

when I receive Clear
delete all of X
delete all of Y
delete all of Z

when I receive Play
set Stop to 0
set Index to 0
Set Motion Ratio Velocity Speed % Accelerati
repeat Loop
repeat length of X
if not Stop = 1 then
change Index by 1
Goto X item Index of X Y
set Index to 0
if not Stop = 1 then
broadcast Done and wait

DOBOT


DobotScratch 1.3.1
DOBOT
File
Edit
Help
Scratch Project
Code
Choose a Device
Magician
Magician Lite
Magic Box
Mobile Platform
AIStarter
Arduino Kit
Arduino Uno
Arduino Mega2560
Device
Sprite
Magician
Coordiate
Velocity

DOBOT

Sliding Rail Kit

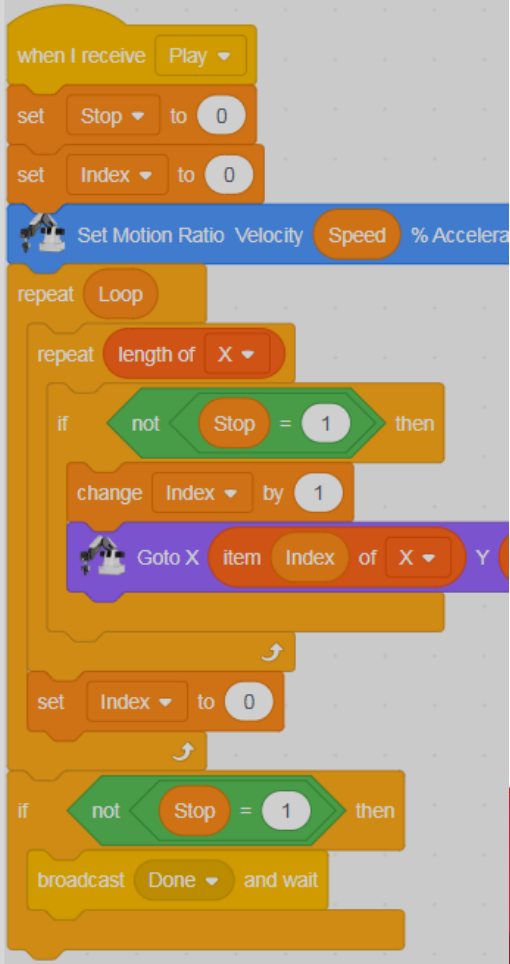
This is a Sliding Rail Kit for Controller & Magician

Photoelectric & Color Sensor

This is a Photoelectric & Color Sensor for Controller & Magician

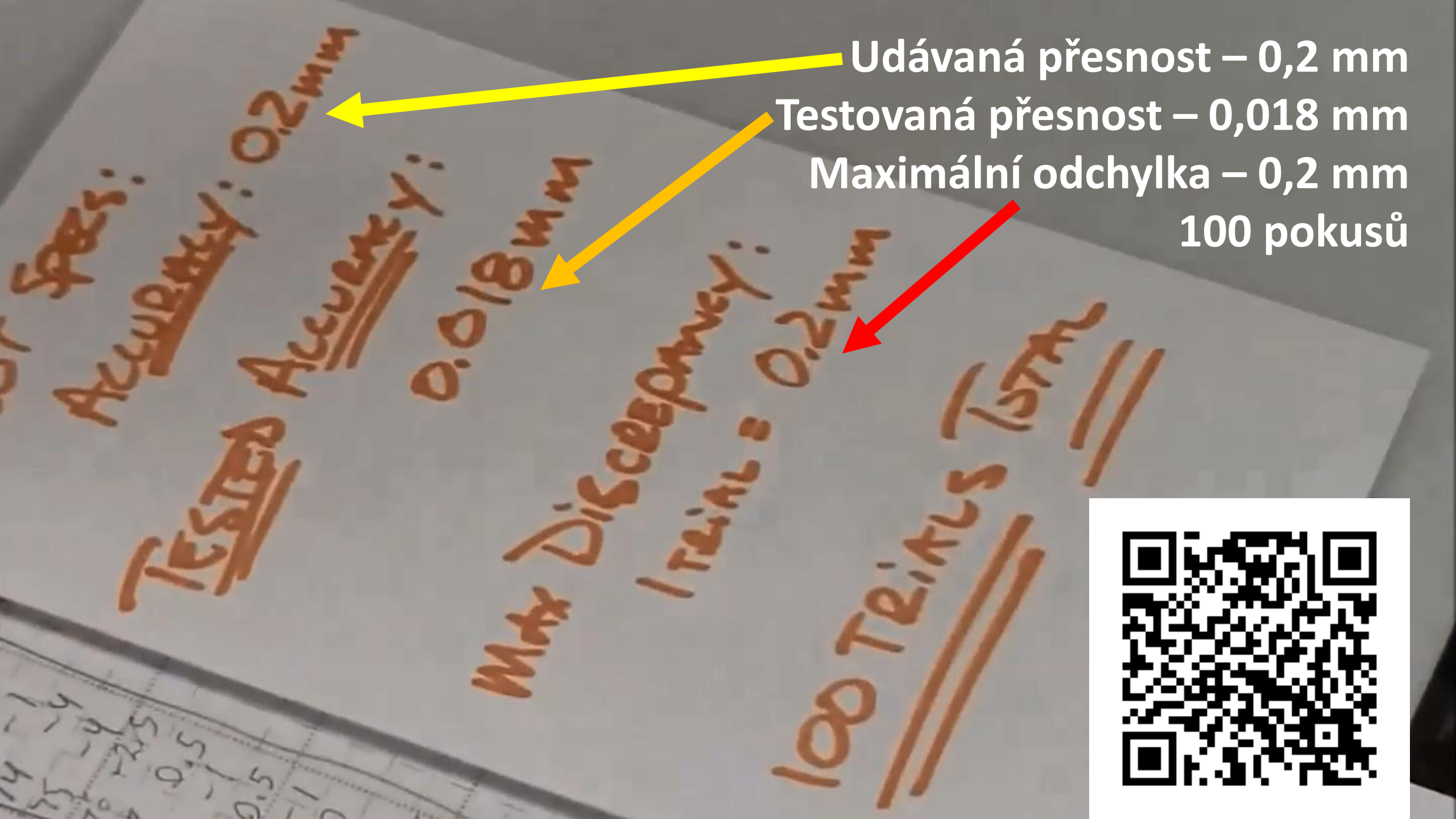
Magic Box AI Extension

This is the extension of Magician Lite and Magic Box



DOBOT

https://youtu.be/O03D-oNUwbg?list=PLJuwb3xnlvckCf5nZE3UdFngSsVYELV4G


Udávaná přesnost – 0,2 mm
Testovaná přesnost – 0,018 mm
Maximální odchylka – 0,2 mm
100 pokusů
Accuracy: 0.2mm
Tested Accuracy:
0.018mm
Max Discrepancy:
Trial = 0.2mm
100 Trials Test

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Technická Univerzita v Košiciach
Slovenská technická univerzita v Bratislave
Žilinská univerzita v Žiline
Vyšší odborná škola a Střední průmyslová škola Děčín
VOŠ, SPŠ a JŠ Kutná Hora
Stredná odborná škola Dubnica nad Váhom
Stredná odborná škola polytechnická
Střední průmyslová škola Ostrov
Střední průmyslová škola Otrokovice
Střední průmyslová škola, Klatovy
Střední průmyslová škola automobilní, České Budějovice
Smíchovská střední průmyslová škola, Praha
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- www.DOBOTMAGICIAN.cz

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