

Adapt kinematic settings

For the commissioning of a real machine, some important information is still missing in the data layer of the ctrlX. As a workaround, this data is saved in the PLC and can be edited in the WebIQ HMI. See **Commissioning> Kinematics**.

When the PLC program is started, the saved setting is compared with the existing kinematics to determine changes. If a deviation is detected, an administrator must adapt the configuration.

Kinematic settings

Label	Meaning
KIN_X Min. Pos []	Min. position of kinematic axis X
KIN_Y Min. Pos []	Min. position of kinematic axis Y
KIN_Z Min. Pos []	Min. position of kinematic axis Z
* Max. Pos []	Max. position of other kinematic axes
Jog. Rel.	Enables relative Jog in widget cx-jog
Max. Jog Vel. []	Max. jog velocity for kinematic

MoldEjectorCore pullersInputs/OutputsSystem InformationSystem StatusJogAxisKinematics

Save

#	Kin Project	==	Kin Cfg
1	Robot	==	Robot
2	Robot2	==	Robot2
3	AxGroup Rot	==	AxGroup Rot
4		==	
5		==	

Robot

ID	Variable name	Value
1	Kin Name	Robot
2		
3	KIN_X min.Pos [mm]	0.0
4	max.Pos [mm]	0.0
5	KIN_Y min.Pos [mm]	0.0
6	max.Pos [mm]	0.0
7	KIN_Z min.Pos [mm]	0.0
8	max.Pos [mm]	0.0
9		
10	Jog Rel.	✓
11	max. Jog Vel. [mm/s]	0.0

Copy name

Copy free axes limits

To set other application specific settings, see **FB_Machine_Customer/00_Init/mUserCfg**.