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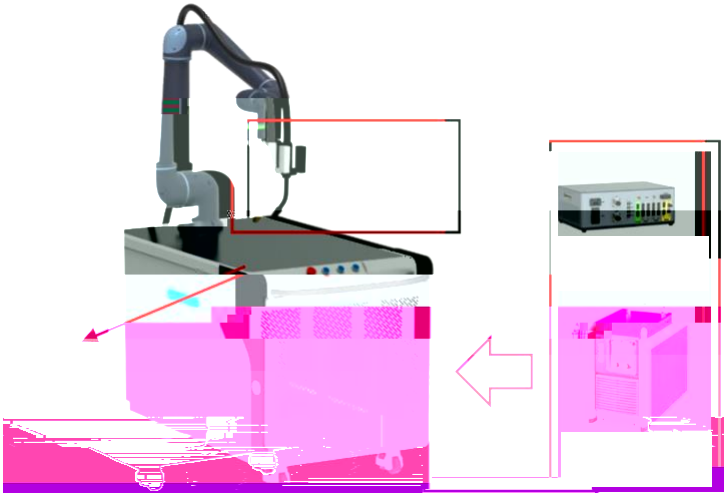
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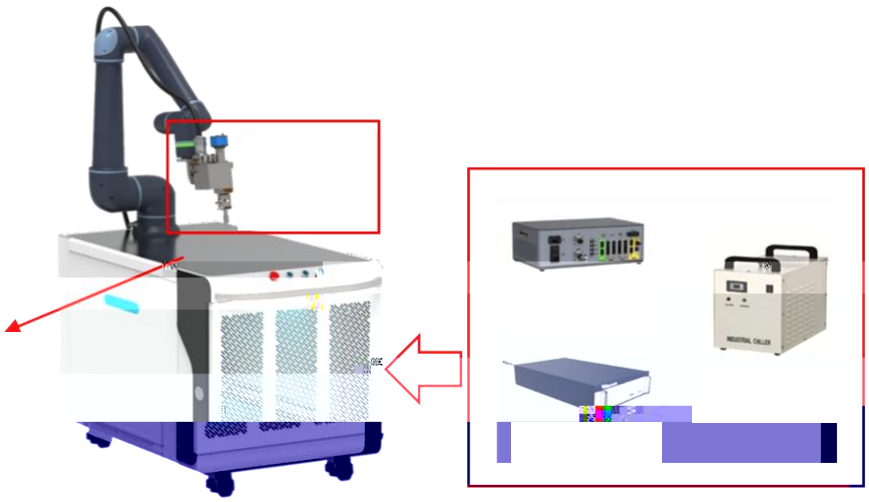
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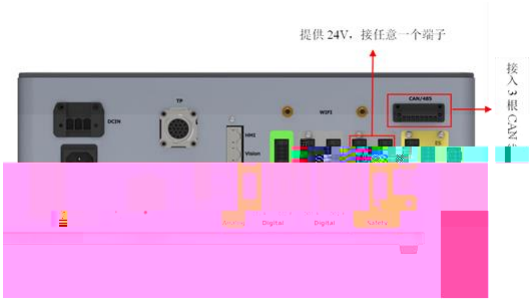
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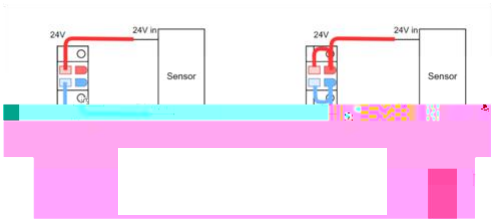
	
	
	
	
	

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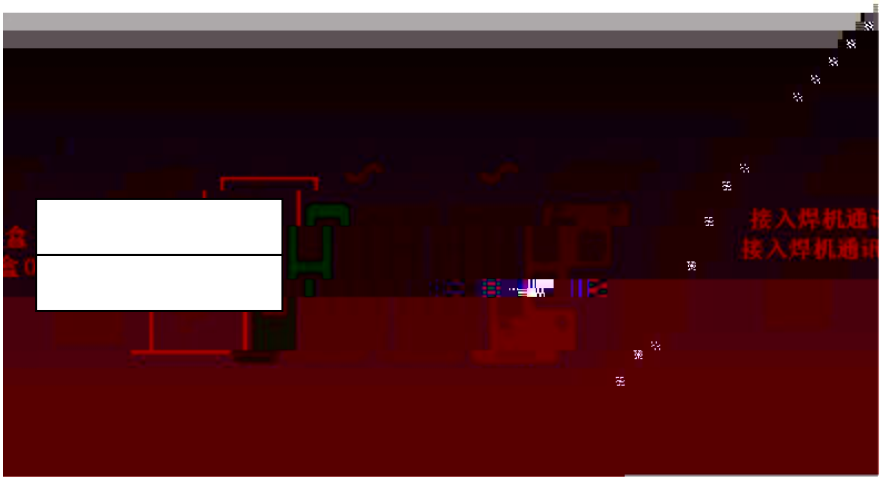





提供24V，接任意一个端子
接入3根CAN

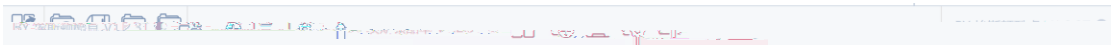

24V
24V in
Sensor
24V
24V in
Sensor


CAN/485


接入焊机通讯
接入焊机通讯









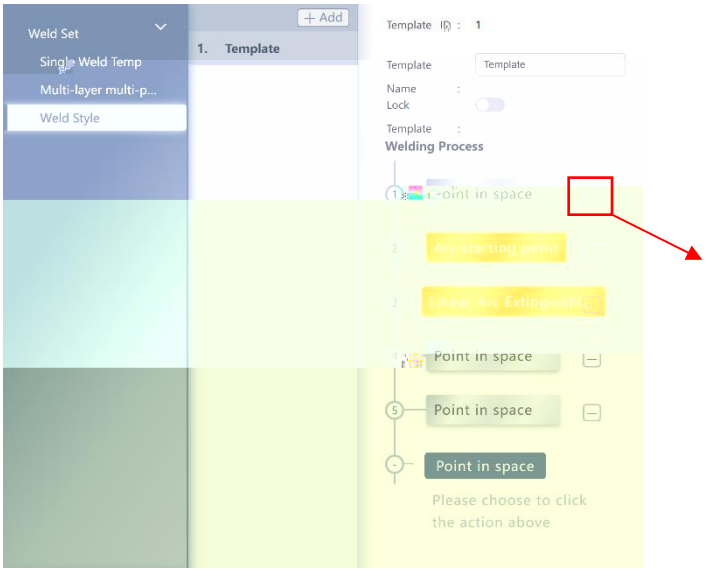








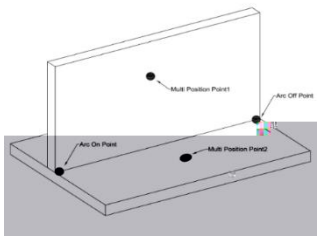
“ ”


Weld Set
Single Weld Temp
Multi-layer multi-p...
Weld Style
Add
1. Template
Template : 1
Template
Template
Name :
Lock
Template :
Welding Process
Point in space
Point in space
Point in space
Point in space
Please choose to click
the action above

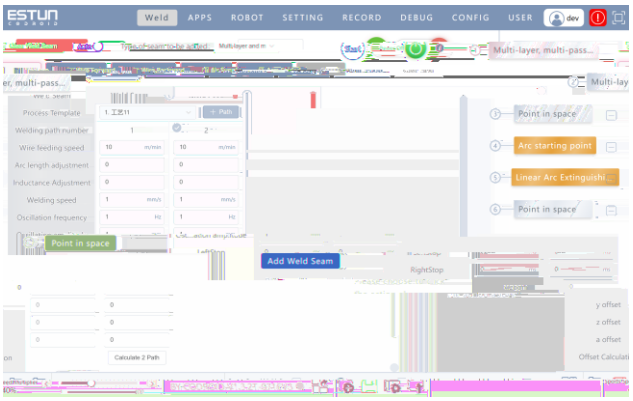

Project Vars
Search
system
global
project
task
ACC
ACC100
REAL
rate
V100
SPEED
Add variable
Save


Global
Type
TOOL


默 认 工 具
NOTOOL
默 认 负 载
NOPAYLOAD


Multi Position Point1
Arc Off Point
Arc On Point
Multi Position Point2


Z
Y
X


ESTUN
Weld
APPS
ROBOT
SETTING
RECORD
DEBUG
CONFIG
USER
dev
Multi-layer, multi-pass...
Point in space
Arc starting point
Linear Arc Extinguishi...
Point in space
Add Weld Seam
Process Template
Welding path number
Wire feeding speed
Arc length adjustment
Inductance Adjustment
Welding speed
Oscillation frequency
Point in space
RightStop
y offset
z offset
a offset
Calculate 2 Path

√



Laser welding head with weaving function, the robot does not need to weaving.

The program includes a section of weld teaching, if you need to add transition points during the welding process, add "MovL" command to the required position, and select "RELATIVE" transition type, the transition value depends on the situation.

When teaching the circular trajectory, replace "MovL" to MovC and add two points.

When teaching the full circle track, replace "MovL" to MovCircle and add two points.

Note:

1. Laser welding is non-contact welding, that is, there is no need to arc after the welding wire and the workpiece, and do not open the laser signal in the non-welding area when teaching the robot or writing the laser program.

2. Before welding, it is necessary to confirm whether the protective gas is sufficient, and do not weld in the case of insufficient protective gas.