

This procedure will help you recover the calibration of the robot. You cannot quick master a robot unless the quick master reference position has been previously recorded. You must clear any servo faults that prevent you from jogging the robot. All axis must be at less than 1 motor turn from the reference position recorded. This procedure must be done with controller selector key to T1 and teach pendant to ON.

ENABLING MASTERING

- 1 PRESS --> [MENU]
- 2 SELECT --> [0] 0 NEXT
- 3 SELECT --> [6] 6 SYSTEM
- 4 PRESS --> [2] Variables
- 5 Using Arrow --> Scroll down the variables list until you get to **\$MASTER_ENB**.
- 6 PRESS --> [1]
- 7 PRESS --> [ENTER]

QUICK MASTERING

Jog each joint of the robot until the reference marks used are align (most of the time they are the 0° marks of each joint)..

- 1 PRESS --> [MENU]
- 2 SELECT --> [0] 0 NEXT

- 3** SELECT --> **[6]** 6 SYSTEM
- 4** SELECT --> **[2]** Variables
- 5** Using Arrow --> Scroll down to **\$DMR_GRP.**
- 6** PRESS --> **[F2]** DETAIL
- 7** PRESS --> **[F2]** DETAIL
- 8** Using Arrow --> Scroll down to **\$REF_POS.**
- 9** PRESS --> **[F2]** DETAIL
- 10** Put each data from line 1 to 9 to --> **0**
- 11** PRESS --> **[PREV]**
- 12** Using Arrow --> Scroll down to **\$MASTER_COUN.**
- 13** PRESS --> **[F2]** DETAIL
- 14** Note each value written on line 1 to 6.
- 15** PRESS --> **[PREV]**

- 16 Using Arrow --> Scroll down to **\$REF_COUNT**.
- 17 PRESS --> **[F2]** DETAIL
- 18 ENTER --> Each value of the **\$MASTER_COUN** to the corresponding lines (1 to 6).
PRESS--> **[ENTER]** after each line to enter the number.
- 19 PRESS --> **[PREV]**
- 20 Using arrow --> Scroll up to **\$MASTER_DONE**
- 21 PRESS --> **[F4]** TRUE
- 22 Using Arrow --> Scroll down to **\$REF_DONE**
- 23 PRESS --> **[F4]** TRUE
- 24 PRESS --> **[MENU]**
- 25 SELECT --> **[0]** 0 NEXT
- 26 SELECT --> **[6]** 6 SYSTEM
- 27 SELECT --> **[3]** 3 Master/Cal
- 28 Using Arrow --> Scroll down to line **3 QUICK MASTER**.

- 29 PRESS --> [ENTER]
- 30 PRESS --> [F4] YES
- 31 Using Arrow --> Scroll down to line **7 CALIBRATE.**
- 32 PRESS --> [ENTER]
- 33 PRESS --> [F4] YES
- 34 PRESS --> [F5] DONE

IF A DCS IS IN FUNCTION

- 1 PRESS --> [MENU]
- 2 SELECT --> [0] 0 NEXT
- 3 SELECT --> [6] 6 SYSTEM
- 4 SELECT --> [8] DCS
- 5 Using Arrow --> Scroll down to line **11 MASTERING PARAMETERS.**
- 6 PRESS --> [F2] APPLY
- 7 ENTER --> **Code Number (master) xxxxx** (this code is provided by the integrator.)
- 8 PRESS --> [F4] OK

- 9 PRESS --> **[FCTN]**
- 10 PRESS --> **[F4]** OK
- 11 SELECT --> **[0]** 0 NEXT
- 12 SELECT --> **[8]** CYCLE POWER
- 13 PRESS --> **[YES]**

CHECKING CALIBRATION

- 1 PRESS --> **[SELECT]**
- 2 Using Arrow --> Scroll down the program list until **ZERO**.
- 3 PRESS --> **[ENTER]**
- 4 PRESS --> **[SHIFT + COORD]**
- 5 At TOOL line, ENTER --> **[1]**
- 6 PRESS --> **[SHIFT + COORD]**
- 7 At USER line, ENTER --> **[0]**

- 8** Place cursor to **line 1**.
- 9** PRESS --> [**SHIFT + FWD**] Press and hold the SHIFT key until the robot is at this position.
- 10** Check **0°** marks on each joint of the robot to see if they perfectly match.
- 11** PRESS --> [**POSN**]
- 12** PRESS --> [**F2**] JOINT
- 13** Each joint should be at **0**.