

*This procedure is use to change tool frame number to a section or all of a program points maintaining robot joints positions. If old and new tool frame are the same, TCP position along the robot path won't change.*

- 1** PRESS --> [ **SELECT** ]
- 2** Choose the program you want to make tool frame reference changes.
- 3** PRESS --> [ **ENTER** ]
- 4** PRESS --> [ **MENU** ]
- 5** SELECT --> [ **1** ] 1 UTILITIES
- 6** SELECT --> [ **8** ] 8 Tool Offset
- 7** PRESS --> [ **F4** ] [CHOICE]
- 8** Select the program in which the changes have to be made.
- 9** PRESS --> [ **ENTER** ]
- 10** Using Arrow --> Scroll down to the **2nd line**.
- 11** PRESS --> [ **F4** ] [PART]
- 12** Using Arrow --> Scroll down to the **3rd line**.
- 13** ENTER --> The **number** where the changes should start.

**14** PRESS --> [ ENTER ]

**15** Using arrow, SCROLL DOWN TO --> The **3rd line**

**16** Enter the line number where changes should end.

**17** Using Arrow --> Scroll down to the **5th line.**

**18** ENTER --> A **new program name** (or keep the same one.)

**19** PRESS --> [ ENTER ]

**20** Using Arrow --> Scroll down to the **6th line.**

**21** If you kept the same program name, enter a program line number where the lines with the switched tool frames will be copied. If you have changed the program name the step before, no “insert line” will be asked.

**22** PRESS --> [ ENTER ] (if you have entered an “insert line” number)

**23** Using Arrow --> Scroll down until the **next page appear.**

**24** ENTER -- > Old tool frame number (*the frame number on which the points where reference to*)

**25** PRESS --> [ ENTER ]

- 26** Using Arrow --> Scroll down to the **2nd line**.
- 27** ENTER --> **New tool frame number** (*the tool frame number on which the points on which you want to reference them to*).
- 28** PRESS --> **[ ENTER ]**
- 29** Using Arrow --> Scroll down to the **3rd line**.
- 30** PRESS --> **[ F4 ] [ CHOICE ]**
- 31** SELECT --> **[ 2 ] 2 Robot Fixed** (*This convert type will keep the position of the face plate of joint 6 of the robot where it is for each of the targeted points. It will change the tool frame number. If both old and new frames are identical, then the TCP positions along the taught path won't change.*)
- 32** PRESS --> **[ F2 ] EXECUTE**
- 33** PRESS --> **[ F4 ] YES**
- 34** You can also delete **line 4 to 8** and change **UTOOL\_NUM from 1 to 5**.