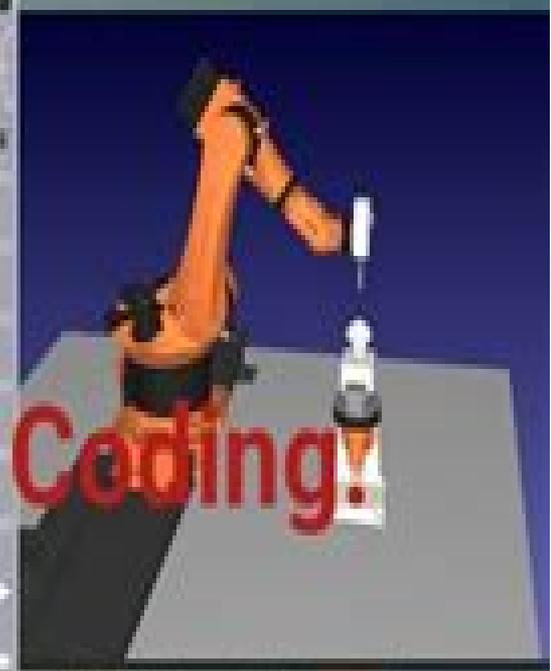


Kuka Robot programming By Coding!

```
1 DEF BallPy()
2 .....
3 ; Demonstration of Graphtops Ballforms
4 .....
5 ;
6 ; Effort_PIP/LIN creates a effort moment to a
7 ; given Position
8 ;
9 ;
10 .....
11 .....
12 .....
13 END
14
15 PIP WIRE Set= 100 % DETAIL
16
17 PIP P1 Set=100 % P001 Tool[1] Base[0]
18
19 Effort_PIP_P1 , Set=100 % , P001, Tool[1] Base[0],
20 ;Acceleration, 0.100, 1.0, 2.0, 0.0, 0.0, 0.0
21
22 [PIP] [P1] [Set= 100 (%)] [P001] [Base[0]]
23 [Effort_PIP] [P1] [Set= 100 (%)] [P001] [Tool[1]] [Base[0]]
24
25 ToolUse_Activate Axis 1, ToolUse = 10 %
26
27 [Activate] [Axis 1] [ToolUse = 10 (%)]
28
29 ToolUse_Activate Axis 1
30
31 PIP P2 Set=100 % P002 Tool[1] Base[0]
32
33 PIP WIRE Set= 100 % DETAIL
34
35 END
```

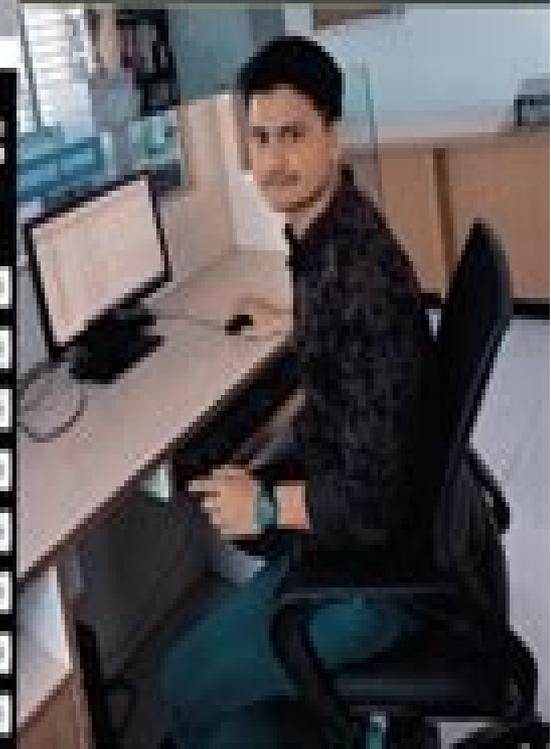
```
DEF BallPy()
.....
; Demonstration of Graphtops Ballforms
.....
;
; Effort_PIP/LIN creates a effort moment to a
; given Position
;
;
.....
.....
.....
END

```



```
DEF BallPy()
.....
; Demonstration of Graphtops Ballforms
.....
;
; Effort_PIP/LIN creates a effort moment to a
; given Position
;
;
.....
.....
.....
END

```



Manualing For Kuka Robot Programming

Annelies Wilder-Smith



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