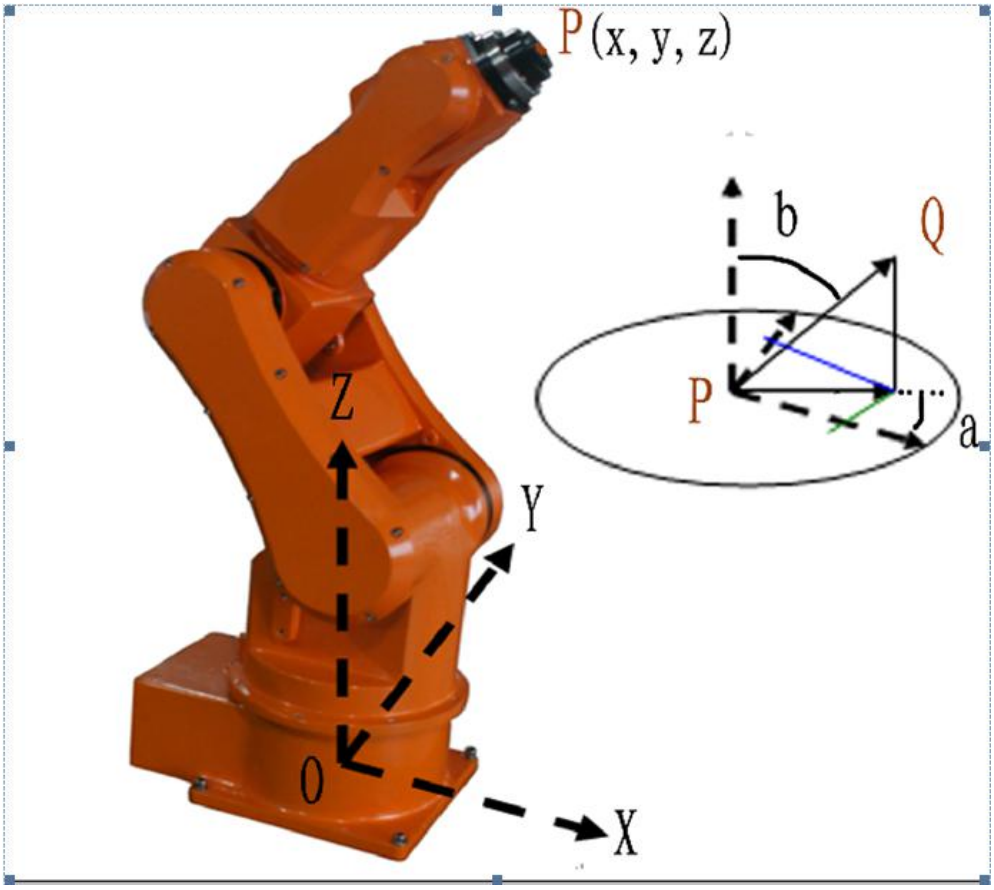

========= Six-axis robot Cartesian coordinate system ========

P (x, y, z, a, b, c, d)

x: X-axis distance (P-point X-axis component);

y: Y-axis distance (P-point Y-axis component);

z: Z-axis distance (P-point Z-axis component);

a: attitude plane angle;

The angle is the angle between the vector mapped by the attitude vector PQ in the XOY plane and the OX axis;

Angle range: (-180, 180);

b: attitude line face angle;

The angle b is the angle between the attitude vector PQ and the OZ axis;

Angle range: (0, 180);

c: attitude rotation angle;

The angle c is the angle between the vector mapped by the tool vector in the XOY plane and the OX axis;

Angle range: (-360, 360);

d: angle state of each joint in the model;

D is an integer, and no value defaults to 0;

Provisions:

0: The end is mapped to the positive direction, the same direction as D1 of the DH parameter, the third axis angle (-) sign, and the fifth axis angle (-) sign;

1: The end map is in the positive direction, the same direction as D1 of the DH parameter, the

third axis angle (-) sign, and the fifth axis angle (+) sign;
2.The end is mapped in the positive direction, the same direction as D1 of the DH parameter, the third axis angle (+) sign, and the fifth axis angle (-) sign;
3: The end map is in the positive direction, the same direction as D1 of the DH parameter, the third axis angle (+) sign, and the fifth axis angle (+) sign;
4: The end is mapped in the negative direction, inverse to D1 of the DH parameter, the third axis angle (-) sign, and the fifth axis angle (-) sign;
5: The end is mapped in the negative direction, inverse to D1 of the DH parameter, the third axis angle (-) sign, and the fifth axis angle (+) sign;
6: The end is mapped in the negative direction, inverse to D1 of the DH parameter, the third axis angle (+) sign, and the fifth axis angle (-) sign;
7: The end is mapped to the negative direction, inverse to D1 of the DH parameter, the third axis angle (+) sign, and the fifth axis angle (+) sign;

Progaram case Description

FILE=ST
AM.ST
1719 //Sequence number of the program
code:
G07 VP=20 //Speed set to 20%
G00 J1=0 J2=0 J3=-90 J4=0 J5=-90 J6=0 //Run to door position
G20 X=300 Y=131 Z=55 A=0 B=180 C=0 D=0 //Run to a location
G06 O=P0.1 //Turn on output 00
G20 X=300 Y=131 Z=20 A=0 B=180 C=0 D=0 //Run to a location
G06 O=P0.0 //Turn off output 00
G06 T=500 //Delay 500 ms
G00 J1=0 J2=0 J3=-90 J4=0 J5=-90 J6=0 //Back door position
G08 EXIT //Exit the loop,Program ends