 www.retisoft.ca

ThermoFisher A255

Manufacturer: ThermoFisher
Model Number: A255
Web Address: www.thermofisher.com

The A255 five axis articulated arm is ideally suited for laboratory automation, educational and industrial users. Typical industrial applications include machine tending, adhesive dispensing and light material handling as well as general pick and place operations.

Robotic Arm: Commands

ash(destination) - Invokes the ash command prompt and changes to the destination directory.

destination	String	Name of the destination directory.

gc( ) - Closes the gripper fingers using the pressure sensing sensor.

exit( ) - Exits from the ash command prompt.

grip_close(servoForce) - Closes the gripper fingers.

servoForce	Integer	The percentage of the force applied. Range of values: **1** to **100**.

grip_open(servoForce) - Opens the gripper fingers.

servoForce	Integer	The percentage of the force applied. Range of values: **1** to **100**.

grip(distance) - Opens the gripper fingers by the specified distance in millimeters.

distance	Integer	The specified distance in millimeters.

finish( ) - Wait until the queued robotic arm movements complete.

move(location) - Move the robotic arm in non-linear motion to the specified location. This command is asynchronous, i.e. it returns as soon as the command is sent to the robotic arm.

location	String	Specified location for the move.

moves(location) - Move the robotic arm in linear motion to the specified location. This command is asynchronous, i.e. it returns as soon as the command is sent to the robotic arm.

location	String	Specified location for the move.

speed(speed) - Set the robotic arm speed as percentage.

speed	Integer	Percentage value for the arm speed. Range of values: **1** to **100**.

wzs(zDistance) - Move the robotic arm up and down on the Z axis by the specified distance.

zDistance	Integer	Move the robotic arm the specified amount of millimeters. Range of values: **-1000** to **1000**.

park( ) - Returns the arm to a parked position inside the homing bracket.

unpark( ) - Moves the arm from the homing bracket into a safe position and then homes the arm.

run(name, action, location, speed) - Runs the specified move program.

name	String	Specifies the name of the move program.
action	Boolean	False signifies the pick (i.e. fetch) action. True signifies the place (i.e. deposit) action.
location	Integer	Specifies the location index for the run command.
speed	Integer	Specifies the speed for the run command. Range of values: **1** to **100**.

output(outputNumber, outputValue) - Turns on the specified output on the CRS robotic PLC controller.

outputNumber	Integer	Specifies the PCL output number. Range of values: **1** to **16**.
outputValue	Boolean	Specifies the ouput boolean value.

input(inputNumber) - Reads the specified input from the CRS PLC controller.

inputNumber	Integer	Specifies the PCL input number. Range of values: **1** to **16**.

Robotic Arm: Errors

Error(description) - Error occurred during command execution.

description	String	Error description.

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