

Mitsubishi RV-6S



Manufacturer: Mitsubishi
Model Number: RV-6S
Web Address: www.rixan.com

RV-6S series robots are the fastest, most affordable and most precise 6-axis robots ever built by Mitsubishi. With a standard pick and place cycle time of up to 0.37 seconds, the RV-S series runs faster than most SCARA robots. It is literally a productivity marvel.

Run - Robotic Arm: Commands

▶ **Open(robot)** - Opens the connection with the remote robotic arm.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
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▶ **SetControl(robot, controlOn)** - Enables/disables control of the robotic arm.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
controlOn	Boolean	True: enables the control. False: disables the control.

▶ **SetServo(robot, servoOn)** - Turns on/off the servo power to the robotic arm.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
servoOn	Boolean	True: turns on the servo power. False: turns off the servo power.

▶ **SetIntVariable(robot, variable, value)** - Sets the value for the specified integer variable in the loaded program.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
variable	String	Variable name.
value	Integer	Value for the variable.

▶ **SetFloatVariable(robot, variable, value)** - Sets the value for the specified float variable in the loaded program.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
variable	String	Variable name.
value	Float	Value for the variable.

▶ **SetBooleanVariable(robot, variable, value)** - Sets the value for the specified boolean variable in the loaded program.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
variable	String	Variable name.
value	Boolean	Value for the variable.

▶ **SetStringVariable(robot, variable, value)** - Sets the value for the specified string variable in the loaded program.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
variable	String	Variable name.
value	String	Value for the variable.

▶ **LoadProgram(robot, programName)** - Load the specified program.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
programName	String	Program name which specifies which program to load.

▶ **RunProgram(robot, programName)** - Run the specified program.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
programName	String	Program name which specifies which program to run.

▶ **MoveSafePosition(robot)** - Moves the robotic arm to the safe position.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
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▶ **MoveJointPosition(robot, position)** - Moves the robotic arm to the specified position using joint interpolation.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
position	String	Specifies the position name for the move.

▶ **MoveLinearPosition(robot, position)** - Moves the robotic arm to the specified position using linear interpolation.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
position	String	Specifies the position name for the move.

▶ **SetRelativeSpeed(robot, speed)** - Sets the speed for the arm movements as a percentage value.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
speed	Integer	Specifies the speed for the arm movements as a percentage value (1% unit). Range of values: 1 to 100 .

▶ **SetRelativeAcceleration(robot, acceleration, deceleration)** - Sets the acceleration/ deceleration as a percentage value with respect to the predetermined maximum value.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
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acceleration	Integer	Specifies the acceleration for the arm movements as a percentage value (1% unit). Range of values: 1 to 100 .
deceleration	Integer	Specifies the deceleration for the arm movements as a percentage value (1% unit). Range of values: 1 to 100 .

▶ **OpenHand(robot, handNumber)** - Open the specified robotic arm hand.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
handNumber	Integer	Specifies which robotic hand to open. Range of values: 1 to 8 .

▶ **CloseHand(robot, handNumber)** - Close the specified robotic arm hand.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
handNumber	Integer	Specifies which robotic hand to close. Range of values: 1 to 8 .

▶ **ReadInputSignal(robot, inputNumber)** - Reads the specified input signal.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
inputNumber	String	Input signal number represented as hex value ranging from 0 to 7FFF.

▶ **WriteOutputSignal(robot, outputNumber, outputValue)** - Writes the specified output signal.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
outputNumber	String	Output signal number represented as hex value ranging from 0 to 7FFF.
outputValue	String	Output signal value represented as hex value.

▶ **Reset(robot)** - Resets the robotic arm and the slot.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
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▶ **ResetError(robot)** - Reset the error code on the robotic arm.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
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Run - Robotic Arm: Errors

🔥 **ArmError(errorCode)** - Error occurred during command execution.


errorCode	Integer	Error code number.
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Abort - Robotic Arm: Commands

▶ **Stop(robot)** - Stop the robotic arm and the current program.

robot	Integer	Robot mechanism. Range of values: 1 to 8 .
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Abort - Robotic Arm: Errors

 **ArmError(errorCode)** - Error occurred during command execution.

errorCode	Integer	Error code number.
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