

Staubli TX40



Manufacturer: Staubli
 Model Number: Staubli-TX40
 Web Address: www.staubli.com

The TX40 robot features an articulated arm with 6 degrees of freedom for high flexibility. The spherical work envelope allows maximum utilization of cell workspace. Additional benefits are the floor, wall and ceiling mount options. The fully enclosed structure of the robot arm (IP65) is ideal for applications in harsh environments.

Robotic Arm: Commands

▶ **setVelocity(velocity)** - Sets the velocity of the robotic arm.

velocity	Integer	Velocity of the robotic arm. Range of values: 1 to 100.
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▶ **setAccel(accel)** - Sets the acceleration of the robotic arm.

accel	Integer	Acceleration of the robotic arm. Range of values: 1 to 100.
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▶ **setDecel(decel)** - Sets the deceleration of the robotic arm.

decel	Integer	Deceleration of the robotic arm. Range of values: 1 to 100.
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▶ **moveLinear(Path)** - Moves the robot arm between the specified points, in a linear motion (no blending of movements).

Path	String	Set of points to use.
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▶ **moveCircular(Path)** - Moves the robot arm between the specified points, in a circular motion (using blending).

Path	String	Set of points to use.
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▶ **moveAbsolute(x, y, z, rz)** - Moves the robotic arm to an absolute location on the workspace.

x	Float	The absolute x-coordinate
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y	Float	The absolute y-coordinate
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z	Float	The absolute z-coordinate
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rz	Float	The absolute angle along the z-axis
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▶ **moveRelative(x, y, z, rz)** - Moves the robotic arm relative to the current location.

x	Float	The relative x-coordinate
y	Float	The relative y-coordinate
z	Float	The relative z-coordinate
rz	Float	The relative angle along the z-axis

▶ **openGripper()** - Opens the robotic arm gripper.

▶ **closeGripper()** - Closes the robotic arm gripper.

▶ **getPoint()** - Returns the current position of the arm in cartesian coordinates.

▶ **setIO(channel, state)** - Sets the state of the specified IO channel on the controller.

channel	Integer	IO channel on the controller
state	Boolean	State for the IO channel

▶ **getIO(channel)** - Retrieves the state of the specified IO channel on the controller.

channel	Integer	IO channel on the controller.
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Robotic Arm: Errors

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

errorCode	Integer	Determines what kind of error occurred.
description	String	Description of the error

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