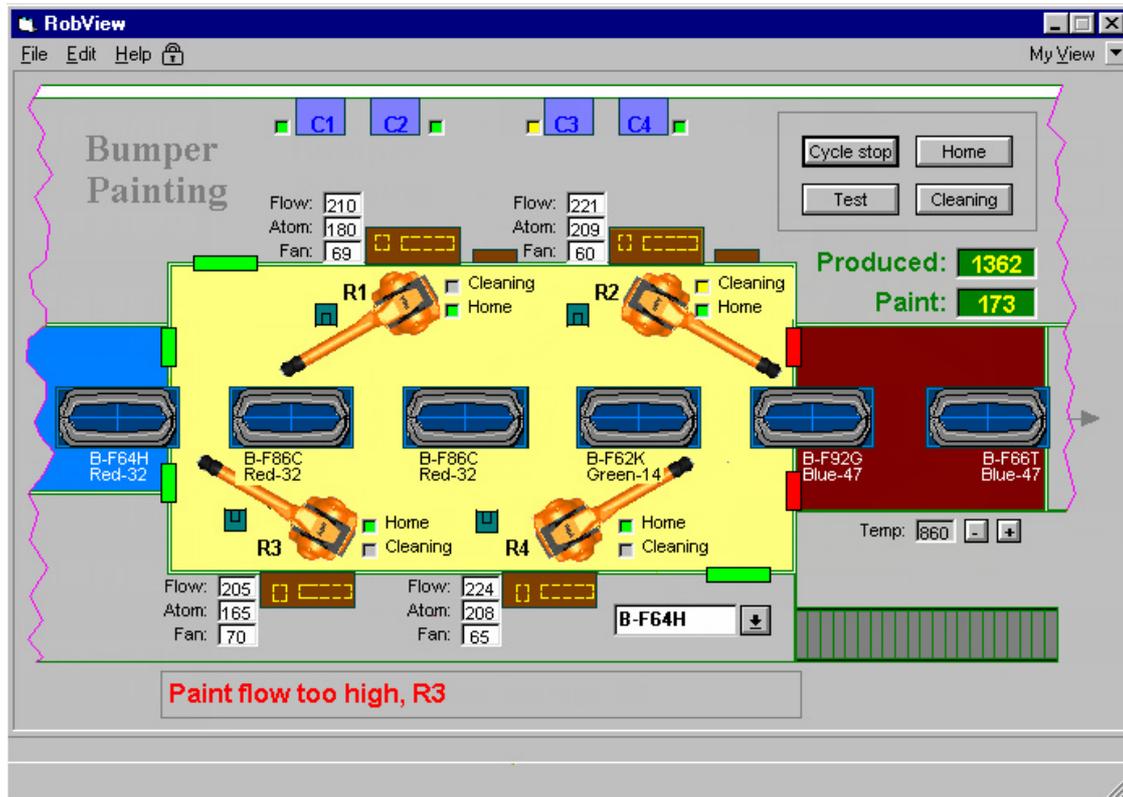


RobView

Robot Status Monitoring



Customized System Overview and Remote Control

RobView lets you operate and monitor your robots from a PC.

It also provides convenient access to the robot controller for easy file transfer and program backup.

Design your own views and screens in RobView to make it fit perfectly to your specific needs - without programming.

Robot status monitoring

RobView gives you full overview of, and control over, all the robots in your work cell.

With its user-friendly graphical interface and ready built robot boxes, you can monitor the robot status, inspect I/O, display the robot position, view robot RAPID variables and list robot messages.

Remote robot operation

RobView offers remote control of your robots, including power on/off, program loading and execution, setting of I/O's, RAPID variables, etc.

Project customisation

You can customize the RobView screens to reflect your specific robot cell. All the tools you need are included in RobView.

Define your own command buttons signal lamps and "connect" them to RAPID variables in the robots. The objects will display the value or change colour as the variable changes in the robot.

Robot file operations

RobView allows you to manipulate robot files and up- and download them for off-line editing or back-up purposes.

You see all the robots connected on the network and can easily navigate to view all files and directories in each robot.

Central storage

CAP is your central point for storage and back-up of all robot programs from all robots in your work cell.

TECHNICAL DATA, ROBVIEW

ROBVIEW FEATURES

Projects	Unlimited number of projects
Customer views	Up to 99 screens (views) in each project
Robot communication	InterLink - Interface for connecting up to 32 robots
User security	Optional Log In functionality with user-id and user-password. Four user categories: View, Safe, Expert and "Programmer".
File Manager	Using familiar "drag-and-drop" interface

PREDEFINED CONTROLS

Robot monitoring	Motor state Controller state I/O monitoring Robot position Controller information
Robot operation	Motor on/off Run/continue program execution Halt program execution Load program Start program from top



USER DEFINED CONTROLS

Screen

For each screen (view) you can define the following:

- The name of the view
- A picture used as a background in the view
- The fill-colour (background) colour of the view
- Specify if this view is to be the start-up screen
- A 'Go to Page' link to make variables in the robot automatically select a screen based on the value of a persistent robot variable or an I/O

Shape

Used to display robot variable status by changing colours. For a Shape you can define the following properties:

- The form of the shape: Rectangle, Square, Oval, Circle, Rounded rectangle or Rounded square
- If the shape is to be filled or transparent
- The fill colour of the shape
- If the shape is to have a border or not
- The colour and thickness of the border
- Link your shape to variables in the robot. The shape can change colour or become invisible, depending on the value of a persistent robot variable or an I/O
- If the shape is to move on the screen dependent on a value of a variable in the robot

Label

A label can be anything from a simple text on the screen to a dynamically updated data field displaying the value of a robot variable, including the ability to edit the value and send it back to the robot. For a label you can define the following properties:

- The name of the variable in the robot that you want to display the value of, and the format (text, number, etc) of the value
- The text of the label, if any
- The font, size, alignment and colour of the label text
- If the value can be edited by the operator and sent to the robot
- Whether the label is to be protected or not
- If the label is to be filled or transparent, and the fill colour
- If the label is to have a (3D) border
- Link your label to variables in the robot. The label can change its fill colour, text colour or become invisible, dependent on the value of a persistent robot variable or an I/O. Note that the variable can be a different variable than the one displaying its value
- A log-text to be logged when the label is changed by the operator

Array

An array can be connected to both complex variables or arrays. It will dynamically update the data fields displaying the value of a robot variable, including the ability to edit the value and send it back to the robot. For an array you can define the following properties:

- The name of the variable in the robot that you want to display the values of, and the format (text, number, etc) of the values
- The font, size and alignment (left, centred, right) of the array text
- The number of columns and rows to display in the array

- The width of the columns
- The text to be displayed in the header of columns and rows
- If the operator is allowed to edit the values and send them to the robot
- Whether the array is to be protected or not

Command button

A command button is used to send commands to the robot. It can be used to set I/O's, clear a variable, load a program, start it, etc. For an array you can define the following properties:

- The text on the button, if any
- The font, size and colour of the button text
- The size of the 3D appearance of the button
- A picture-file (.bmp or .ico) to display on the button
- The action you want to perform when the button is operated
- Link your button to variables in the robot that can change the appearance of the button. The button can change its text colour, picture, user input or become invisible, dependent on the value of a persistent robot variable or an I/O. The variables can be different from those used to execute an action.
- A log-text that is written to a log file when the button is operated

Image

An Image is used to draw a picture on the screen. For an image you can define the following properties:

- The name of the picture-file (.bmp or .ico) that you want displayed
- Link your image to variables in the robot. The image can change picture or become invisible, dependent on the value of a persistent robot variable or an I/O.

Hotspot

A hotspot is any area you define in a screen (view) to make RobView change to another view when you click on the hotspot. The property you can define for a hotspot is:

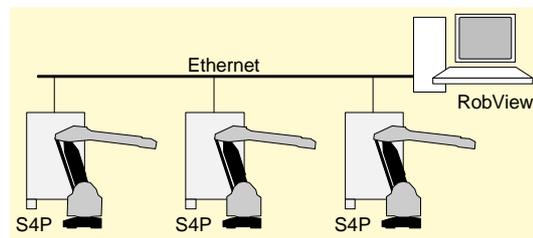
- The name of the screen (view) you want to move to

SYSTEM REQUIREMENTS

PC	Windows NT 4.0 with Service Pack 3 or higher, Windows 95 to Windows 2000
Robot Controller	FactoryWare Interface 3.1 or RAP Communication 3.1 installed Ethernet interface hardware

RECOMMENDED PC HARDWARE REQUIREMENTS

CPU	Pentium III 450 MHz
Memory	256 MB RAM
Free disc-space	50 MB
Graphics card	Graphics card with 2,5 MB Video RAM 16 Mio colours
Screen resolution	800x600 pixels or better
Communication	Ethernet board
Media	CD-ROM reader



Data and dimensions may be changed without notice.