Release Notes
RobotStudio
6.00.01

Revision: -
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1 Release Information

1.1 General

Release Name
The release name is RobotStudio 6.00.01 and the build number is 6.00.6270.1211.

Release Date
The release date is January 23rd, 2015.

Demo stations
The following demo stations are included in this version.
- Demo AW Station
- Demo Solar Simulation
- Demo Exhaust Pipe
- Demo FlexLoader

They are stored in the Pack & Go format (.rspag) and can be opened with the command Unpack & Work on the Share section of the RobotStudio menu.

ScreenMaker Demo Station and Project
There is a demo station and associated ScreenMaker project available.
- SCM_ExampleProject (ScreenMaker Project)
- SCM_ExampleStation (RobotStudio station)

These files are found in the ‘Addins/ScreenMaker/Samples’ folder under the RobotStudio installation folder.

Tutorials
Tutorials are available at the RobotStudio product pages at http://www.abb.com/roboticssoftware

Documentation
User documentation for RobotStudio is available from the Help button (帮助) in the upper-right corner of RobotStudio.

The complete documentation in PDF for RobotWare including RobotStudio is available on DVD and can be ordered separately from ABB.

1.2 System recommendation

Recommended Software

<table>
<thead>
<tr>
<th>Operating System</th>
<th>Edition</th>
</tr>
</thead>
<tbody>
<tr>
<td>Microsoft Windows 7 SP1</td>
<td>32-bit edition</td>
</tr>
<tr>
<td>Microsoft Windows 7 SP1 (recommended)</td>
<td>64-bit edition</td>
</tr>
<tr>
<td>Microsoft Windows 8.1 (recommended)</td>
<td>64-bit edition</td>
</tr>
</tbody>
</table>
Note

The Windows Firewall will try to block features necessary to run RobotStudio. Make sure to unblock these features when asked (Industrial Robot Discovery Server, RobotStudio StudioAppFramework module, Virtual RobotController (all published by ABB)). The blocking state of a certain program can be viewed and changed at Start/Control Panel/Windows Security Center/Windows Firewall. Read more on http://www.microsoft.com.

Recommended hardware

<table>
<thead>
<tr>
<th>Item</th>
<th>Requirement</th>
</tr>
</thead>
<tbody>
<tr>
<td>CPU</td>
<td>2.0 GHz or faster processor, multiple cores recommended</td>
</tr>
<tr>
<td>Memory</td>
<td>3 GB if running Windows 32 bit</td>
</tr>
<tr>
<td></td>
<td>8 GB if running Windows 64-bit</td>
</tr>
<tr>
<td>Disk</td>
<td>10+ GB free space, solid state drive (SSD)</td>
</tr>
<tr>
<td>Graphics card</td>
<td>High-performance, DirectX 11 compatible, gaming graphics card from any of the leading vendors. For the Advanced lightning mode Direct3D feature level 10_1 or higher is required.</td>
</tr>
<tr>
<td>Screen resolution</td>
<td>1920 x 1080 pixels or higher is recommended</td>
</tr>
<tr>
<td>DPI</td>
<td>Normal size (100% / 96 dpi) up to Large size (150% / 144 dpi) Only Normal size supported for Integrated Vision.</td>
</tr>
<tr>
<td>Mouse</td>
<td>Three-button mouse</td>
</tr>
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1.3 Simulation Models

Robot Libraries

<table>
<thead>
<tr>
<th>IRB Variant</th>
<th>IRB Variant</th>
<th>IRB Variant</th>
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</thead>
<tbody>
<tr>
<td>120 3kg/0.58m</td>
<td>360 3kg/1130 Std No axis 4</td>
<td>6650 125kg/3.2m</td>
</tr>
<tr>
<td>120T 3kg/0.58m</td>
<td>360 3kg/1130 Wash-down No axis 4</td>
<td>6650 200kg/2.75m</td>
</tr>
<tr>
<td>1200 5kg/0.9m BTM</td>
<td>360 3kg/1130 Standard</td>
<td>6650D 170kg/2.75m</td>
</tr>
<tr>
<td>1200 5kg/0.9m STD</td>
<td>360 3kg/1130 Wash-down</td>
<td>6650S 125kg/3.5m</td>
</tr>
<tr>
<td>1200 7kg/0.7m BTM</td>
<td>360 3kg/1130 Stainless</td>
<td>6650S 200kg/3.0m</td>
</tr>
<tr>
<td>1200 7kg/0.7m STD</td>
<td>360 1kg/1600 Standard</td>
<td>6650S 90kg/3.9m</td>
</tr>
<tr>
<td>140 5kg/0.8m Type A/B</td>
<td>360 6kg/1600 Standard</td>
<td>6600 100kg/3.35m</td>
</tr>
<tr>
<td>140 6kg/0.8m Type C</td>
<td>360 8kg/1130 Standard</td>
<td>6660 130kg/3.1m</td>
</tr>
<tr>
<td>140T 5kg/0.8m Type C</td>
<td>4400 45kg</td>
<td>6660 205kg/1.9m</td>
</tr>
<tr>
<td>1400 Type A/B</td>
<td>4400 60kg</td>
<td>6700 145 kg/3.2m MH</td>
</tr>
<tr>
<td>1400H Type A/B</td>
<td>4400L 10kg</td>
<td>6700 145 kg/3.2m SW</td>
</tr>
<tr>
<td>1410</td>
<td>4400L 30kg</td>
<td>6700 150 kg/3.2m MH3</td>
</tr>
<tr>
<td>1520ID</td>
<td>4400S 30kg</td>
<td>6700 150 kg/3.2m</td>
</tr>
<tr>
<td>1600 5kg/1.2m</td>
<td>4400R 200kg/2.5m</td>
<td>6700 155 kg/3.05m MH</td>
</tr>
<tr>
<td>1600 5kg/1.2m Type A</td>
<td>4400R 120kg/2.5m</td>
<td>6700 175 kg/3.05m MH3</td>
</tr>
<tr>
<td>1600 5kg/1.45m</td>
<td>4400R 150kg/2.8m</td>
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<td>6700 200 kg/2.8m MH</td>
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<tr>
<td>1600 6kg/1.45m</td>
<td>4600 40kg/2.55m</td>
<td>6700 200 kg/2.8m SW</td>
</tr>
<tr>
<td>1600 7kg/1.2m</td>
<td>4600 40kg/2.55m Type C</td>
<td>6700 205 kg/2.8m MH3</td>
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<tr>
<td>1600 8kg/1.2m</td>
<td>6400R 200kg/2.5m</td>
<td>6700 220 kg/2.5m MH3</td>
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<tr>
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<td>6700 220 kg/2.65m</td>
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<td>6700 220 kg/2.65m SW</td>
</tr>
<tr>
<td>1600ID 4kg/1.5m</td>
<td>6400R 150kg/2.8m</td>
<td>6700 235 kg/2.65m MH3</td>
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<td>2400 10kg</td>
<td>6400R 100kg/2.5m</td>
<td>6700 235 kg/2.65m</td>
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<td>2400 16kg</td>
<td>660 180kg/3.15m</td>
<td>6700 175 kg/2.65m MH</td>
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<td>2400L</td>
<td>660 250kg/3.15m</td>
<td>6700 175 kg/2.65m SW</td>
</tr>
<tr>
<td>2600 12kg/1.65m</td>
<td>660 175kg/2.55</td>
<td>6700 200 kg/2.65 MH3</td>
</tr>
<tr>
<td>2600 20kg/1.65</td>
<td>660 175kg/2.80m</td>
<td>6700 200 kg/2.6</td>
</tr>
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<td>2600 12kg/1.85</td>
<td>660 225kg/2.55</td>
<td>6700 220kg/3.0m MH</td>
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<td>2600ID 8kg/2.0m</td>
<td>660 185kg/2.55m</td>
<td>6700 220kg/3.0m SW</td>
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<td>2600ID 15kg/1.85m</td>
<td>660 150kg/2.2m</td>
<td>6700 245kg/3.0m MH3</td>
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<tr>
<td>260ID 8kg/2.0m</td>
<td>660 150kg/2.5m</td>
<td>6700 245kg/3.0m</td>
</tr>
<tr>
<td>260ID 15kg/1.85m</td>
<td>6520LX 130kg1.9m</td>
<td>6702 270kg/2.7m MH</td>
</tr>
<tr>
<td>260ID 15kg/1.85m</td>
<td>6640 130kg/3.2m</td>
<td>6702 270kg/2.7m SW</td>
</tr>
<tr>
<td>340</td>
<td>6640 180kg/2.55</td>
<td>6700 300kg/2.7m MH3</td>
</tr>
<tr>
<td>360 1kg/1130 Std No axis 4</td>
<td>6640 185kg/2.8</td>
<td>6700 300kg/2.7m</td>
</tr>
<tr>
<td>360 1kg/1130 Wash-down No axis 4</td>
<td>6640 205kg/2.75</td>
<td>7600 150kg/3.5</td>
</tr>
<tr>
<td>360 1kg/1130 Standard</td>
<td>6640 235kg/2.55</td>
<td>7600 325kg/3.1m</td>
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<tr>
<td>360 1kg/1130 Wash-down</td>
<td>6640 170kg/2.75m</td>
<td>7600 340kg/2.8</td>
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<tr>
<td>360 1kg/1130 Stainless</td>
<td>6640D 200kg/2.55m</td>
<td>7600 400kg/2.55</td>
</tr>
<tr>
<td>360 1kg/800 Std No axis 4</td>
<td>6640 150kg/2.55m DP6</td>
<td>7600 500kg/2.3</td>
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<tr>
<td>360 1kg/800 Wash-down</td>
<td>6640 165kg/2.6m DP6</td>
<td>7600 500kg/2.55</td>
</tr>
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</table>
| 360 1kg/800 Std | 6640 205kg/2.55m DP6 | **940**
| 360 1kg/800 Wash-down | **940** | |

** requires the StandAlone Controller mediapool that is available for download from Add-Ins tab / RobotApps / RobotWare Add-Ins

Note

All simulation models in the table are installed with RobotStudio, but only the robots in the current product range are displayed in the ABB Library gallery. To import any other robot you need to browse to the file on disk.
Robot Libraries

<table>
<thead>
<tr>
<th>Variant</th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>52 short vertical arm</td>
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</tr>
<tr>
<td>52 std vertical arm</td>
<td></td>
</tr>
<tr>
<td>540-12 std arm</td>
<td></td>
</tr>
<tr>
<td>580-12 std arm</td>
<td></td>
</tr>
<tr>
<td>580-12 short arm</td>
<td></td>
</tr>
<tr>
<td>5300-12 left</td>
<td></td>
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<tr>
<td>5300-12 right</td>
<td></td>
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<tr>
<td>5320-1500</td>
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<tr>
<td>5320-2000</td>
<td></td>
</tr>
<tr>
<td>5350/01 Type Left</td>
<td></td>
</tr>
<tr>
<td>5350/01 Type Right</td>
<td></td>
</tr>
<tr>
<td>5350/02 Type Left Side Left</td>
<td></td>
</tr>
<tr>
<td>5350/02 Type Left Side Right</td>
<td></td>
</tr>
<tr>
<td>5350/02 Type Right Side Left</td>
<td></td>
</tr>
<tr>
<td>5350/02 Type Right Side Right</td>
<td></td>
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<tr>
<td>5400-12 std arm</td>
<td></td>
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<td>5400-13 std arm</td>
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<td>5400-22 process arm</td>
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<tr>
<td>5400-23 process arm</td>
<td></td>
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<tr>
<td>5400-24 process arm</td>
<td></td>
</tr>
<tr>
<td>5400-12 std arm axis 2 +60 deg</td>
<td></td>
</tr>
<tr>
<td>5400-13 std arm axis 2 +60 deg</td>
<td></td>
</tr>
<tr>
<td>5400-14 std arm axis 2 +60 deg</td>
<td></td>
</tr>
<tr>
<td>5500 35A b_00 / b_80</td>
<td></td>
</tr>
<tr>
<td>5500 35B b_00 / b_80</td>
<td></td>
</tr>
<tr>
<td>5500 ProArm 35A b_00 / b_80</td>
<td></td>
</tr>
<tr>
<td>5500 ProArm 35B b_00 / b_80</td>
<td></td>
</tr>
</tbody>
</table>

Track Libraries

RobotStudio is distributed with the following track types that are available in the Track folder of the ABB Library.

<table>
<thead>
<tr>
<th>Track family</th>
<th>Length</th>
</tr>
</thead>
<tbody>
<tr>
<td>IRBT4003</td>
<td>1.7 m to 10.7 m</td>
</tr>
<tr>
<td>IRBT4004</td>
<td>1.9 m to 19.9 m</td>
</tr>
<tr>
<td>IRBT6003</td>
<td>1.7 m to 10.7 m</td>
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<td>IRBT6004</td>
<td>1.7 m to 19.7 m</td>
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<td>IRBT7003</td>
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<tr>
<td>IRBT7004</td>
<td>1.7 m to 19.7 m</td>
</tr>
<tr>
<td>RTT_Bobin</td>
<td>1.7 m to 11.7 m</td>
</tr>
<tr>
<td>RTT_Marathon</td>
<td>1.7 m to 11.7 m</td>
</tr>
<tr>
<td>Paint Rails</td>
<td>2 m to 20 m</td>
</tr>
<tr>
<td>left and right versions</td>
<td></td>
</tr>
<tr>
<td>IRBS350 Rail</td>
<td>3 m to 10 m</td>
</tr>
<tr>
<td>left and right versions</td>
<td></td>
</tr>
</tbody>
</table>
2 What’s new in RobotStudio 6.00.01

Overview

This section describes the news of RobotStudio 6.00.01

2.1 Serial number in Jobs

In RobotStudio 6.00.01 you can name the backups retrieved by the Jobs function according to the serial number of the robot. RobotStudio reads the serial number from the controller configuration database (same as the serial number of the SMB).

2.2 CAD kernel and CAD converter upgraded to ACIS R25SP1

The ProE CAD-converter reads ProE / Creo files up to version 3.0 in RobotStudio 6.00.01

2.3 Updated version of the migration guide

The instruction that describes how to upgrade from RobotWare 5.6x to RobotWare 6.x is replaced by a new version (Revision A) in RobotStudio 6.00.01.
3 What’s new in RobotStudio 6.0

Overview

This section describes the news of RobotStudio 6.0

3.1 Changes related to RobotWare 6

Migration tools

A number of migration tools are provided to support upgrade from RobotWare 5.60 and 5.61 to RobotWare 6.0. See the Migration Checklist available from the Installation Manager menu for details.

Installation Manager and System From Layout

Installation Manager is the tool for building real and virtual controller systems based on RobotWare 6. Offline users can use the function System From Layout to build their virtual RobotWare 6 systems from the manipulators of the station.

Changes to I/O System

Signal setup has been simplified in RobotWare 6. For instance, simulated signals to be used for offline programming does not need to be connected to a unit and no unit mapping needs to be specified.
RobotWare installed with RobotStudio

RobotWare is automatically installed for the ‘Complete’ installation option.

New terminology: Distribution packages, products and RobotWare Add-Ins

RobotWare is a product and part of a distribution package that also contains the RobotWare Add-Ins for TrackMotion and IRBP.

A product consists of two parts, first, one or more robot packages (file suffix .rpk) and, second, a manifest (file suffix .rmf).

A distribution package may consist of one or more products. When distributed as one file the file suffix is .rspak.

RobotWare installed from RobotStudio

Other versions of RobotWare apart from the version installed by RobotStudio, can be downloaded and installed from the RobotApps page of the Add-Ins tab. An Internet connection is required.

3.2 Online features

Jobs

The new Jobs functions lets you do certain actions for a large number of robots concurrently. You can take backups, update UAS, and set time

Load and save RAPID and configuration on the controller

You can now load and save modules and controller configuration files by accessing the controller disk directly. This will save you time since you no longer need to use the File Transfer tool to move files between your PC and the controller.
3.3 Offline features

Solution

The new Solution concept helps you structure your station data, the solution structure will keep it all in one place.

2D export in DXF and SVG

With the 2D export function you can export 2D drawings from RobotStudio and use in your 2D CAD program. In addition to DXF you can use the SVG format that can be viewed in e.g. Internet Explorer. The DXF and SVG formats are available as options for the Export Geometry command on the Station level.

Visualization and adjustment of zone data

You can view and adjust the RAPID zone data in the 3D graphics view. RobotStudio can reduce the size of your zone data to avoid having overlapping zones. The controller will reduce any overlapping zones during program execution, but now RobotStudio can help you understand and adjust your zone during program creation.
Collison indication

To make it easier to find the point of collision a markup can optionally be created at the point of first collision. You can choose to highlight the colliding body or surface in to part which was available before.

3.4 Other features

Keyboard shortcuts

You can export and import your customized keyboard shortcuts. This is useful when you exchange your PC or want to share a pre-defined set of shortcuts with your colleagues.
Automatic transparency

When zooming in on objects in the 3D view, you can enable automatic transparency to make the closest part become gradually invisible.

Defining your main procedure and add procedure calls in the browser

You can define the main procedure directly in the Paths&Targets browser and add procedure calls to your paths by Drag’n Drop. The main procedure will be synchronized to the VC along with your paths. This means you no longer need to use the Simulation Setup window for the standard case.
Setup Simulation

The Setup Simulation tool has been re-made and has become a document window. To the left you see a tree view and to the right you see a property window that changes with the selected tree item. The virtual time mode selection has been moved from RobotStudio Options to Simulation Setup. The simulation entry point (i.e. by default the main procedure) can be defined as a property of the task node.

Screen Recorder: Record cursor

The Screen Recorder options Record Graphics and Record Application now includes the mouse cursor which also illustrates mouse clicks. The cursor recording is enabled through RobotStudio Options.
4 Late Breaking Information

Overview
This section contains information about late changes that were done after the RobotStudio 6.0 Operating Manual was finalized.

4.1 RobotWare Packages

Overview
This section describes how RobotWare 6 packages are handled in RobotStudio 6.

4.1.1 Concepts

Overview
This section describes a couple of fundamental concepts related to RobotStudio.

Virtual and real controller
RobotStudio is installed by an installer, similar to many other Windows applications. RobotStudio contains the tool to install RobotWare onto the real, physical robot controller, hereafter denoted as real controller (RC). For the purpose of offline programming and simulation there is also a virtual controller (VC) which is a virtual replica of the real controller. RobotStudio connects to both real and virtual controllers.

Systems
The specific configuration of RobotWare for use by a particular robot is denoted as a controller system, or simply system in this context. The tool used to create RobotWare 5 systems is called System Builder and the similar tool for RobotWare 6 is called Installation Manager. Both of these tools are part of RobotStudio. In addition, RobotStudio can create VC systems for either RobotWare 5 of 6 using the functions System From Layout and New System.

4.1.2 Package Installation

Overview
This section describes the installation of RobotWare packages on the PC.

RobotWare installation
A pre-requisite for creating systems is that RobotWare is available on the PC. RobotWare 5 is installed into the PC’s Program Files folder using a standard PC installer. RobotWare 6 is on the PC by RobotStudio for Complete installation option. Alternatively, RobotWare 6 can be installed using the RobotApps page in RobotStudio’s Add-Ins tab.

Distribution Packages
RobotWare 6 comes with a Distribution Package that also contains RobotWare Add-Ins for Positioners and TrackMotion. The RobotWare Add-In for the Stand Alone Controller (SAC) is a separate Package available from the RobotWare Add-Ins section of RobotApps, see item 2 of Figure 1.

If you have a Package file (.rspak) you can install it using the Browse command, see item 3. You can install RobotWare Add-Ins by browsing to a RobotWare Add-In manifest (.rmf file).

The Add-Ins browser will show the installed packages, see item 4.
GoOffline and Pack&Go

The functions GoOffline and Pack&Go requires any RobotWare Add-Ins used by the systems to be installed on the PC.

**Note**

You can create a system in Installation Manager and add it to a RobotStudio station, but not create a Pack&Go file unless the RobotWare Add-ins are installed and available as Installed Packages in the Add-Ins browser.
4.1.3 Package Locations

Overview

This section describes where to find the packages.

RobotWare is Application Data

In RobotStudio 6, RobotWare and related packages are considered to be application data and as such they are treated according to the Microsoft Certification requirements for Windows desktop apps. In particular the following two rules apply:

10.3 Your app data, which must be shared among users on the computer, should be stored within ProgramData

10.4 Your app’s data that is exclusive to a specific user and that is not to be shared with other users of the computer, must be stored in Users\<username>\AppData

Thus, Packages can be available in two locations.

Location 1 (ProgramData)

The first location is

%ProgramData%\ABB Industrial IT\Robotics IT\DistributionPackages\n
that is used if RobotWare is installed with RobotStudio. On a PC with a default installation of Windows 7 the path is

C:\ProgramData\ABB Industrial IT\Robotics IT\DistributionPackages.

In this case, rule 10.3 applies as the person installing RobotStudio is typically an IT technician and may not be same person as the one actually using the software. For this reason RobotWare must be placed in a location accessible for all users.

Location 2 (LocalAppData)

The second location is used if a Package or Manifest is installed by a particular user. Then the location is

%LocalAppData%\Local\ABB Industrial IT\Robotics IT\DistributionPackages.

On a PC with a default installation of Windows 7 the path is

C:\Users\<username>\AppData\Local\ABB Industrial IT\Robotics IT\DistributionPackages

This location is only visible to the particular user who installs the Package, see rule 10.4.
[Optional] Location 3: (Customized location)

Optionally, the Packages can be placed in a customized location, see RobotStudio Options. This is typically done in a shared environment, where several users want to share a Package repository.

Tooltip with location information

The location for a specific package is shown in the tooltip of the Add-Ins browser if you let the mouse pointer hover over a Package node.

Open Package Folder in Windows Explorer

If you select the option Open Package Folder from the context menu of an Installed Package Windows Explorer will be opened showing the location of the selected Package Folder.
Unpacked data

When used by a virtual controller, the Packages are unpacked into a cached location which always resides in a LocalAppData sub-folder, namely

%LocalAppData%\Local\ABB Industrial IT\Robotics IT\RobotWare.

On a PC with a default installation of Windows 7 the path is

C:\Users\<user name>\AppData\Local\ABB Industrial IT\Robotics IT\RobotWare

(Users familiar with RobotWare 5 will recognize the content of this folder to be similar to the previous Mediapool folder.)

4.1.4 Uninstall Packages

Overview

This section describes how to uninstall Packages

Uninstall Package

The context menu option Uninstall Package will remove the selected Package and related, unpacked, data.
5 Corrections

Overview

This section describes the defects solved in RobotStudio.

5.1 Corrections in RobotStudio 6.00.01

Overview

This section describes the corrections made in 6.00.01

5.1.1 Product Defect Documents (PDD)

<table>
<thead>
<tr>
<th>ID</th>
<th>Title</th>
</tr>
</thead>
<tbody>
<tr>
<td>4115</td>
<td>Loosing view center when rotating the view</td>
</tr>
<tr>
<td>4390</td>
<td>Visual SafeMove &amp; SafeMove Report: Some German translations need to be revised.</td>
</tr>
<tr>
<td>4456</td>
<td>Error in path interpolation function</td>
</tr>
<tr>
<td>4464</td>
<td>Not possible to export more than one geometry</td>
</tr>
<tr>
<td>4547</td>
<td>Solution name with quotation mark causes exception</td>
</tr>
</tbody>
</table>

5.1.2 Other corrections

RAPID Editor: File based syntax check not correct

When the RAPID Editor was used with a file placed in a backup, the syntax check was not correct. This is fixed in RobotStudio 6.00.01

5.2 Corrections in RobotStudio 6.0

Overview

This section describes the corrections made in 6.0

Product Defect Documents (PDD)

<table>
<thead>
<tr>
<th>ID</th>
<th>Title</th>
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</thead>
<tbody>
<tr>
<td>330</td>
<td>SafeMove/RS: Messages, that a restart of the controller failed, are not translated to German language.</td>
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<td>1986</td>
<td>Controller Shutdown button is grayed and not documented</td>
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<tr>
<td>2023</td>
<td>OnlineMonitor does not show supervised ToolPoints</td>
</tr>
<tr>
<td>2062</td>
<td>System builder drop down box too small</td>
</tr>
<tr>
<td>2461</td>
<td>RobotStudio cut plane</td>
</tr>
<tr>
<td>2484</td>
<td>Update problem in RobotStudio when creating a new system based on a former RobotWare</td>
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<tr>
<td>2522</td>
<td>Bad rendering of a STEP and SAT files</td>
</tr>
<tr>
<td>2568</td>
<td>Method to prevent loading of 5.15 system to 5.60 RAC computer works but is confusing</td>
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<tr>
<td>2678</td>
<td>Additional Resources button under Help disappears when RS window is not maximized</td>
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<tr>
<td>2746</td>
<td>RW 5.60RC3 and Integrated Vision: Toggle Mode button in ribbon bar must be clicked twice very often</td>
</tr>
<tr>
<td>2757</td>
<td>Visualizing Safety Zones in RobotStudio Online Monitor does not show tool configured in SafeMove</td>
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<tr>
<td>3155</td>
<td>Problem with Mechanism Modeler (numerical problem in 32-bit)</td>
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<tr>
<td>3210</td>
<td>RobotStudioReport 2014_0221</td>
</tr>
<tr>
<td>ID</td>
<td>Description</td>
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<tr>
<td>-----</td>
<td>-------------------------------------------------------------------------------------------------------</td>
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<td>3212</td>
<td>Incorrect messages in RS, Rapid output window - identifiers starting with</td>
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<tr>
<td>3222</td>
<td>RobotStudioReport 2014-0305</td>
</tr>
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<td>3271</td>
<td>RS threw TaskException</td>
</tr>
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<td>3299</td>
<td>Libraries of IRB 5350_01 versions missing</td>
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<tr>
<td>3307</td>
<td>UAS Groups deletes entry even if user selects Not to</td>
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<td>Help for CAD ACIS export and VRML import not correct</td>
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<td>3326</td>
<td>Validation Integrated vision ribbon menu test Network Digits (check for dpi settings)</td>
</tr>
<tr>
<td>3329</td>
<td>Validation Integrated vision ribbon menu test</td>
</tr>
<tr>
<td>3336</td>
<td>Validation RC RobotStudio Manual</td>
</tr>
<tr>
<td>3337</td>
<td>RS 5.61 RC Validation RS manual UI</td>
</tr>
<tr>
<td>3340</td>
<td>Problems with work envelope display</td>
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<tr>
<td>3341</td>
<td>Double camera node</td>
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<tr>
<td>3367</td>
<td>System from layout does not use mediapool for track type A, but older type</td>
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<tr>
<td>3371</td>
<td>IV - Truncated Localized Texts</td>
</tr>
<tr>
<td>3391</td>
<td>Validation RC Rotate window</td>
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<td>3407</td>
<td>missing german translation</td>
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<td>3444</td>
<td>RS Online Jog: wrong mech unit moved in multimove system</td>
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<td>3520</td>
<td>Compile Mechanism button in RS</td>
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<tr>
<td>3535</td>
<td>Spanish Translation use Arista instead of Borde for Edge</td>
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<tr>
<td>3553</td>
<td>Go Offline failing to work</td>
</tr>
<tr>
<td>3560</td>
<td>markups can't be tagged</td>
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<tr>
<td>3565</td>
<td>Positioner not updating position</td>
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<td>3571</td>
<td>EIO.cfg template shows 5.60 header</td>
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<tr>
<td>3572</td>
<td>IRB1200 arm type does not show in available arms</td>
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<tr>
<td>3597</td>
<td>System from Layout throws exception</td>
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<tr>
<td>3646</td>
<td>Crash from selecting mech unit</td>
</tr>
<tr>
<td>3651</td>
<td>crashes when conveyor created in Picking PowerPac is clicked</td>
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<tr>
<td>3659</td>
<td>sync problem in RS 5.61</td>
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<tr>
<td>3672</td>
<td>Create System from layout wizard select add task page problem</td>
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<tr>
<td>3688</td>
<td>Custom Instructions Won't Sync to Station</td>
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<tr>
<td>3689</td>
<td>Error when closing floating I/O-windows</td>
</tr>
<tr>
<td>3706</td>
<td>Exception in RobotStudio when loading system module</td>
</tr>
<tr>
<td>3717</td>
<td>shows syntax error when using explicit syntax for mandatory arguments</td>
</tr>
<tr>
<td>3723</td>
<td>RobotStudio 5.61 Release version bug with station extracting</td>
</tr>
<tr>
<td>3727</td>
<td>Geometries lost while saving the station</td>
</tr>
<tr>
<td>3735</td>
<td>All graphics disappears</td>
</tr>
<tr>
<td>3747</td>
<td>External Mechanical Unit in RS [Gantry problem]</td>
</tr>
<tr>
<td>3773</td>
<td>mechanism joint jog misbehaving IRBP K</td>
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<tr>
<td>3778</td>
<td>Mirrored Path</td>
</tr>
<tr>
<td>3870</td>
<td>Importing Catia Files that Have not been showed into RS</td>
</tr>
<tr>
<td>4071</td>
<td>Signal Analyzer Disabled</td>
</tr>
<tr>
<td>4194</td>
<td>Problems to use RobotWare 5.12.04</td>
</tr>
</tbody>
</table>
6 Known Limitations

Overview

This section describes known limitations in RobotStudio.

6.1 General

Compatibility of RobotStudio Library and Stations with older RobotStudio versions

RobotStudio is generally not forwards compatible, i.e. it is not possible to load stations or libraries created in RobotStudio 6.00.01 into an earlier version of RobotStudio such as e.g. RobotStudio 5.15.02, 5.61.02, 6.0 or earlier. However, RobotStudio is backwards compatible, which means stations and libraries created in versions 5.15.02, 5.61.02, 6.0 or earlier can be opened in RobotStudio 6.00.01.

6.2 Online

Visual SafeMove windows can be re-opened from the Quick Access Toolbar menu

Any windows that are closed can be re-opened using the Quick Access Toolbar menu, as the command Default Layout does not recover these windows.

Individual RAPID tasks cannot be stopped for RobotWare 5.60 and later

When running multitasking systems, it is not possible to start and stop individual tasks with the dropdown menu of the task node in the Controller browser. This is due a restriction introduced with RobotWare 5.60 and later.

Signal Analyzer Online not available for RobotWare 5.60, RobotWare 5.15.02 and earlier

The feature Signal Analyzer Online is not available for controllers running RobotWare 5.60, RobotWare 5.15.02 and earlier. The reason is a vulnerability in Robotware that may cause interruptions in the robot operation.

Signal Analyzer Online is supported by Robotware 5.15.03 and later, and RobotWare 5.61 and later, where the problem has been corrected.

It is not recommended to use Signal Analyzer Online of RobotStudio 5.15.01 or 5.15.02 with RobotWare versions prior to 5.15.03 or 5.61.

SafeMove Tool Zone visualization in Online Monitor for robots with external axes

Only TCP robots and track mounted robots will be visualized in the Online Monitor, no other external axes or positioners.

As a consequence, the Online Monitor may show the robot in a non-violating position, even though the safety controller has detected a safety violation and stopped the robot.

FlexPendant Viewer running with automatic reloading

When having FlexPendant Viewer running with automatic reloading of the screens and at the same time jogging the robot with the joystick the robot jogging might halt when the FlexPendant Viewer reloads.

6.2.1 Online - Paint

Backup for Paint systems does not create backup of the PIB board

The Backup function of RobotStudio does not create a backup of the PIB board of the IRC5P system.
**Workaround:** Create the backup of the PIB board with the FlexPaint Pendant using an USB-stick.

**Go Offline does not work for Paint systems**

The Go offline function will not create a working Virtual controller system for Paint system unless the Paint package I/O option is set to Simulated.

**6.2.2 Online – Integrated Vision**

**Information – Integrated Vision only works on 32-bit installations**

It is not possible to use Integrated Vision in the 64-bit version of RobotStudio.

**Information – Camera firmware version and update**

The minimum firmware version to be used with Integrated Vision is 4.08. If this version is not available for a specific camera model, then the newest version available shall be used.

There are two important things to know before upgrading a sensor

- The user must make sure to first backup the files on the camera. This can be done using the Rapid snippets for camera backup/restore, or the FlexPendant Explorer.
- The latest available firmware version may vary across sensor types. However, when the firmware update utility presents the latest available version it shows the firmware with the highest version number which may not apply to the sensor to be updated. However, the appropriate firmware will be applied.

**Information – The spreadsheet view**

The spreadsheet view is not enabled when editing in the in the following modes “Add part location tool”, “Add part inspection tool”. Before entering the spreadsheet mode click for example “Setup Image” or Output to Rapid.

**Information – Calibration board without fiducial**

When using the calibration boards, checkerboard or board with dots, the user must select the preferred origin by clicking and accepting (press enter) three points on the board. Only after these three points have been selected is it possible to click “calibrate” to execute the calibration.

**Information - Use default camera settings**

If the camera is not using default communication settings the result may be that RAPID instructions return error code “Communication Error”. The safest method to get default settings is to go to Connect->Add Sensor Right click and select “Show all sensors”. Select the device to reset and click “Apply factory settings” in the lower right corner. The most important settings are:

- Telnet port: 23
- User: “admin”
- Password: “”

**Information – User Credentials**

It is now possible to create user profiles with different access levels on the camera. For detailed information about this, please refer to the Integrated Vision User Manual.
Remaining error – Save image on camera

It is not possible to save an image on the camera using “Save Image”. This is by design, but the dialog still allows the user to try to do this. The result is that the image is not saved and no error message is given.

Remaining error - Connect button greyed out for no reason

It may sometimes happen that the “Connect” button is greyed out, with the tooltip saying the camera is not on the correct subnet although the IP settings are OK.

Workaround: Restart the Integrated Vision Add-In.

Remaining error – VC started from Controller->Add controller does not detect cameras

A VC that is started from Controller->Add controller does not detect cameras on the network, even if the VC_network_definition.xml is correctly configured and the firewall is turned off. The reason is that the controller is not able to detect new cameras on the network when it is in “Motors On” state. When the VC is started stand-alone in RobotStudio it is automatically set to “Motors On” when started.

Workaround: To allow it to discover cameras, turn the control panel key to manual mode or launch the VC as part of a station.

User tip - Removing cameras from configuration

To remove a configured camera from the list of configured cameras, use the configuration editor. Enter Configuration->Communication->Application Protocols and remove the desired camera. Perform a warm start to complete the operation.

User tip – Viewing all cameras present on the network

Connect->Add Sensor is normally used for setting the IP addresses of sensors that are not currently on the correct subnet (192.168.125.X). Since the dialog shows all cameras “seen” by the PC, this dialog is useful when error tracing camera network problems.

If a camera does not appear on the network using the “Add sensor” dialog as suggested above, it is advisable to cycle the power of the camera. If the camera receives power from the controller, then cycle power by turning the mains switch.

User tip – Warm start the controller after changing network settings

Whenever changing the network settings of the camera, either from Connect->Add Sensor or Connect->Network settings, it is important to warm start the controller. If this is not done, RAPID instructions will give the error “Communication Error” and the FTP-mounted camera disk is not accessible. If DHCP addres is used and persits, please try a static address instead.

6.3 Offline

6.3.1 General

The 2D work envelope fails for certain robot models

As a result, the generated work envelop may appear distorted.

Update of current selection in the 3D graphics window may be delayed

A problem related to the graphics driver has been observed on certain PCs. The problem is that the update of the current selection in the 3D graphics is delayed until the next redraw.

Workaround: Add or uncomment the following line in the file RobotStudio.exe.config

```xml
<add key="DoublePresentWorkaround" value="true" />
```
Failure to open Pack&Go file to same folder the second time

RobotStudio will prevent Pack&Go files to be opened to the same folder a second time if the station contains VC systems with the EPS or SafeMove option. This is by design to prevent the safety controller configuration file to be accidentally overwritten.

**Workaround:** Remove the write protection manually using Windows Explorer.

Updates of instruction template and code snippets

RobotStudio will not automatically update the user files for instruction templates and code snippets files in the folders:

```
...\My Documents\RobotStudio\Instruction Templates
...\My Documents\RobotStudio\Code snippets
```

**Workaround:** The user has to manually copy the latest files from

```
%ProgramFiles%\ABB Industrial IT\Robotics IT\RobotStudio 5.xx\Instruction Templates,
and
%ProgramFiles%\ABB Industrial IT\Robotics IT\RobotStudio 5.xx\Code Snippets
```
to the data folder.

IO signals configured with access level ‘DEFAULT’

When IO signals are configured with access level ‘DEFAULT’, only input signals are possible to set/reset from the I/O Simulator and I/O Window. To be able to affect also output signals, set the access level to ‘ALL’ for them in the Configuration Editor.

VC does not start with RRI option and GSI folder structure missing.

The VC will hang when started with a system containing the RobotWare option RRI (Robot Reference Interface) if the GSI folder structure is missing.

**Workaround:** create GSI Folder before starting the VC inside the HOME directory of the system. See the Application Manual for Robot Reference interface for more information.

System in Guard Stop state in Automatic mode after run-time error

Certain run-time errors may cause the controller system to enter Guard Stop state in Automatic mode. This is the same behavior as in a physical robot controller system. This typically happens when a run-time error related to Conveyor Tracking occurs. A simulation cannot be started when the controller is in this state.

**Workaround:** To reset the controller state, open the Control Panel window and first switch to Manual mode, and then back to Automatic mode.

Information message starting system with IRB260/460/660/760

Starting a system with IRB260/660 gives you an error message: ‘The number of joints is different between the library model and the controller configurations’. The reason is that the IRBx60 is modeled with six joints in RobotStudio of which two are locked, but has four joints in the VC.

Path handling of instructions with multiple joint targets

The path functions Rotate, Translate, and Mirror do not work as expected with instructions containing via points as joint targets. The functions will leave the joint targets as is. Interpolate Path gives an Unknown Error and Tool Compensation reports an error message.
Event Manager: Simulation cannot be triggered by analog system signals

The event manager only supports analog station signals, not analog system signals

6.3.2 Station Viewer

Memory problem when doing Save As Viewer or Record to Viewer with large stations

RobotStudio may run out of memory (OutOfMemory exception) when doing Save As Viewer or Record To Viewer if the station is very large.

*Workaround:* Use the 64-bit version of RobotStudio and create a 64-bit viewer by ticking the checkbox in the Save As Viewer file dialog.

6.3.3 MultiMove

MultiMove error: ‘Object reference not set to an instance of an object’

When the Test Play button is pressed in the MultiMove tool, the following error message may be displayed: ‘Object reference not set to an instance of an object’, but the robot moves and the Status ‘Calculation OK’ is displayed. In addition, when ‘Create Paths’ is pressed the following message is displayed: ‘Can’t create paths : Value cannot be null’, and no paths are created. In the ‘Create Paths Settings’, is the WP TCP drop down empty.

*Reason:* wobj is not set for the current task

6.3.4 External Axis

Error 50091: ‘Restart not possible’ after warm start of a system with external axis

When restarting a system with activated mechanical units the activation state is lost. Then the program can no longer be started from the Virtual FlexPendant, the RAPID Editor or the RAPID Tasks window.

*Workaround:* Reset the program pointer (‘Program Pointer to Main’) before starting the program from the Virtual FlexPendant, the RAPID Editor or the RAPID Tasks window, or, start the program from the Simulation Play button.

6.3.5 Network Drives and UNC Paths

RobotStudio on computers with roaming user profiles

RobotStudio may fail on PC configurations with roaming user profiles, i.e. when the users’ documents folder resides on a server and not on the local disk.

*Workaround:* Redefine the ‘User Project Folder’ to a folder on the local disk (File → Options → General → Files&Folders → User Project Folder).

Virtual Controller does not support UNC paths

UNC paths cannot be used to locate Virtual Controller systems. Using UNC paths for VC systems will cause the log message ‘Failed to initialize FW upgrade framework’ to appear when the system starts. Subsequent attempts to work with the VC such as synchronizing RAPID data will fail.

Creating and starting systems located on a network drive

When using a network drive to store RobotStudio data such as RobotWare systems or the RobotWare mediapool, the following problems may occur

- Virtual controller does not start
- Not possible to open VirtualFlexpendant
Cause: By default, the .NET Framework does not allow execution of code from a remote file system. This means the application may behave unexpectedly if the media used by the system or the system itself resides on a network share.

Workaround: To resolve this, the user must explicitly grant the required permissions:

1. Open the file Virtual FlexPendant.exe.config located in
C:\Program Files (x86)\ABB Industrial IT\Robotics IT\RobotStudio 5.61\Bin
2. Add the following lines

```xml
<?xml version="1.0" encoding="utf-8"?>
<configuration>
  <startup useLegacyV2RuntimeActivationPolicy="true">
    <supportedRuntime version="v4.0" sku=".NETFramework,Version=v4.0"/>
  </startup>
  <runtime>
    <loadFromRemoteSources enabled="true"/>
  </runtime>
</configuration>
```

The Virtual FlexPendant must be restarted for the changes to take effect.

For further information, see

Note

Windows security settings may prevent the file from being directly edited in the default location. Copy the file to your local Documents folder to edit it. Upon completion, you need to manually copy the file back to its original location.

6.3.6 RAPID

Robtarget names must be unique in RAPID even if they are LOCAL

RobotStudio requires that robtarget names are unique for the RAPID synchronization to work properly, i.e. you cannot have a global robtarget named MyTarget1 in module A and a local robtarget with the same name in Module B.

Global robtargets cannot be made local through Synchronization to VC

Global robtargets cannot be changed to local through Synchronization to VC, the option is disabled (PDD 3140).

Workaround: Change the robtargets to module local in the RAPID Editor and Synchronize to station.

Error Message: Sync. to Station completed with errors

Error Message: Sync to Station completed with errors: New data <name> <type> has same name as existing object in same block <routine>.

When this error message appears, there is a storage type mixup between data already stored in RS and in the VC. Because of this, and per design, the data is not considered the same data.

Workaround: 1. Ensure all data declarations have the same definition in RS as in RAPID (there is no user interface for this).
2. Sync to station should now work.
3. Sync back to controller, and remember to change the data declarations back to what you want.
6.3.7 Paint

Lack of Virtual Controller support for the Paint systems

Paint systems that are configured using the Paint package I/O option Discrete, Compact or Fieldbus, will result in a SysFail state.

Workaround: Re-create the system with the simulated I/O option.

Compiling a Conveyor Mechanism does not disable the Compile button

After compiling a conveyor mechanism, using the Create Mechanism tool, the Compile Mechanism button is not disabled. If the user presses the Compile button again, without changing anything, another identical conveyor mechanism will be created.

6.3.8 Graphics and Geometry

Enforce selected graphics device for PCs with multiple graphics cards

For best performance when running RobotStudio on a PC with multiple graphics cards, RobotStudio can be configured to use a specified device. By this option you can ensure maximum performance. This is useful for e.g. Lenovo W540 that has both an integrated Intel graphics device and a discrete NVIDIA card.

Open the file RobotStudio.exe.config that is located in the folders:

\C:\Program Files (x86)\ABB Industrial IT\Robotics IT\RobotStudio 6.0\Bin64

and

\C:\Program Files (x86)\ABB Industrial IT\Robotics IT\RobotStudio 6.0\Bin

and uncomment the line:

<add key="GraphicsDeviceType" value="Discrete"/>

Valid values are 'Discrete', 'Integrated' and 'Warp' (software renderer).

Note that there are two different files, one for the 32-bit version, and another for the 64-bit version.

Problems when undoing Boolean operations on Geometry

Undoing a Boolean operation might not succeed. To recover from these problems, you need to delete the items that caused the problem.

Out of memory

The application might fail when out of memory due to the import of very large ACIS files or load of very large stations.

Workaround: Use the 64-bit version that can handle more memory. Ensure that you have enough memory installed on the PC, see System Requirements.

6.4 ScreenMaker Limitations

File changes to FlexPendant applications does not load the changes until a FlexPendant reset

With RobotWare 6.0x the controller's restart will no longer reset the FlexPendant memory. This was part of an effort to improve the restart time of the controller.

This means that after placing a new FlexPendant application file(s) on the FlexPendant unit, you need to manually reset the FlexPendant for it to reload its assets.

To manually reset the FlexPendant you need to use the reset button on the FlexPendant's backside. (See Operating Manual – IRC5 with FlexPendant, 3HAC16590)
Dynamic update of Rapid Data

The switch from Manual Mode to Auto Mode causes the RAPID boolean data bound to the enabled property of control change to value TRUE. This behaviour is noticed when the mode is changed from a different screen and not on the screen where the control is bound to RAPID boolean data. An additional side effect is that the enabled property of RunRoutine button has been disabled as similar behavior was seen.

Running Routine with Movement

RunRoutine Button control does not always work correct when a routine with movements is called.

As a workaround use instructions like StopMove, StorePath, RestorePath and StartMove to control the movements of the robot.

A Trap routine could be called with a normal button control and in the Trap the above instructions can be used to control the movements of the robot.

PictureBox control as a Widget

If a Picture Box control is created as a widget from a Windows 8 operating system, the control is not shown on the FlexPendant. The behavior is fine with any other operating system like Windows 7.
7 RobotWare Compatibility

7.1 General

Supported RobotWare versions
RobotStudio 6.00.01 is distributed with RobotWare 6.00.01 and works with RobotWare 5.07 and later. Please check details below.

7.2 RobotWare 5.05 and 5.06 Compatibility
RobotWare 5.05 and 5.06 including revisions thereof are not supported by RobotStudio 5.15 and later versions. Please use the corresponding version of RobotStudio for managing robot controllers with any of these RobotWare versions.

7.3 RobotWare 5.07 Compatibility
RobotWare 5.07 and its revisions of are supported with the following limitations:

General
The location of the program pointer is not updated in the RAPID Editor during program execution.

Offline
A limitation in the versions 5.07.02, 5.07.03, and 5.07.04 of RobotWare may cause the Virtual Controller to System Failure state during I-start on certain computers. The problem is due to the ctrl.bin-file not being correctly created.

Workaround: Create an empty ctrl.bin file in the INTERNAL folder of the controller system, and then perform a warm start.

Note
The problem will reappear if the system is I-started.

The virtual controller does not support RobotWare 5.07.08 and RobotWare 5.07.07.

Online

FlexPendant Viewer does not work RobotWare 5.07

7.4 RobotWare 5.08 Compatibility
RobotWare 5.08 and its revisions of are supported with the following limitations:

Offline
RobotWare 5.08 is not supported.

Workaround: Use RobotWare 5.08.01 or later.

7.5 RobotWare 5.10 Compatibility
RobotWare 5.10 and its revisions of are supported with the following limitations:

Offline
Starting a controller will generate internal UAS error in controller error log.

7.6 RobotWare 5.11 Compatibility
RobotWare 5.11 and its revisions of are supported with the following limitations:
Offline

Linear jogging of a robot across joint values that will cause a change of confdata may fail. For example, if the robot is jogged linearly when joint values is passing 90 degrees for axis 1 may cause the robot to stop or to change configuration.

7.7 RobotWare 5.12 Compatibility

RobotWare 5.12 and its revisions of are supported with the following limitations:

Paint backups from RW 5.12.01 not compatible with RW 5.12.02 or later

Restoring a paint system backup from RobotWare 5.12.01 will cause SysFail for RobotWare 5.12.02 or later

Workaround: Add the following parameters to the configuration files

**EIO.CFG:**

```xml
EIO_SIGNAL:
   -Name "doMainInMC" -SignalType "DO" -Unit "SysComm" -UnitMap "44"
   -Name "A1HVEnSt" -SignalType "GO" -Unit "SysComm" -UnitMap "150-151"
   -Access "ALL"
   -Name "A1HVEnr" -SignalType "DC" -Unit "SysComm" -UnitMap "154"
   -Access "ALL"

EIO_CROSS:
   -Res "A1HVEn" -Act1 "HVEnabled"

SYS.CFG:

```xml
CAB_TASK_MODULES:
   -File "INTERNAL:/pntrapid/T_ROB1/cycinfo.sys" -ModName "cycinfo"
   -Task "T_ROB1"
   -File "INTERNAL:/pntrapid/csvlkup.sys" -ModName "csvlkup" -AllTask
   -Hidden
```

7.8 RobotWare 5.13 Compatibility

RobotWare 5.13 and its revisions of are supported with the following limitations:

Paint backups from RW 5.12.02, 5.12.03 or RW 5.13 or 5.13.01 not compatible with RW 5.13.02 or RW 5.13.03

There are several changes in the configuration database for I/O (EIO.CFG) and Controller (SYS.CFG) that will cause System Failure if an old backup is loaded. There are also changed in installed RAPID modules. To create a compatible configuration, proceed as follows:

1. Create and start a VC with a RobotWare 5.13.03 system containing the same options as your original backup, but do not load the backup.
2. Save the EIO.CFG and SYS.CFG to file.
3. Compare the saved files with the corresponding files of your backup. (You can use a text file comparison tool for simplification.)
4. Add your system-specific configuration to the general configuration files saved from the 5.13.01-system using a text editor.
5. Replace the files of the original backup with the corresponding modified configuration files.
6. Go through the RAPID modules of the backup and remove the default modules (i.e. those that are not changed by the user).
7. Load the backup and restart the system. You are done.
7.9 RobotWare 5.15 Compatibility

*Signal Analyzer Online

The feature Signal Analyzer Online requires RobotWare 5.15.03 or later.

7.10 General Compatibility Limitations

**RAPID Profiler**

The profiler will be able to create a log file for the profiler automatically for RobotWare 5.14 or later. For RobotWare 5.13 or earlier, the log file must be created manually using the RAPID Spy command (SpyStart/SpyStop).

**Safety Configuration**

Safety configuration of a track motion IRC5 system equipped with a safety controller of type EPS or SafeMove can be done without the need to read track motion parameters manually when using RobotWare 5.11.01 or later. Encrypted parameters needed by the safety controller will be automatically read by EPS Wizard and SafeMove Configurator, respectively.

**Signal Analyzer Online**

Signal Analyzer Online requires RobotWare 5.15.01 or later.

**Signal Analyzer.**

The error message Failed to subscribe on signal may sometimes appear during signal recording for RobotWare 5.15 or earlier. **Workaround:** Restart the VC or upgrade to RobotWare 5.15.01 or later.

**Configurations**

The feature Configurations for selecting the robot arm configuration (confdata) may fail, or not present all solutions, in some specific circumstances even when the target is reachable if RobotWare 5.14 or earlier is used. **Workaround:** Upgrade to RW5.14.01 or later.

7.11 ScreenMaker Compatibility

**RobotWare**

It is possible to use previous RobotWare versions, but with some limitations.

- ActionTrigger will work only on RobotWare 5.12.02 or later.
- The controls Button, TpsLabel and PictureBox controls was modified in RobotStudio 5.13. The property 'Allow MultipleStates' of these controls can be accessed from RobotWare 5.13 and later.
- Variant Button will work only on RobotWare 5.14.01 or later
- Conditional Trigger will work only on RobotWare 5.14.01 or later
- Widgets will work only on RobotWare 5.60 or later.

**FlexPendant SDK**

ScreenMaker should be used with FlexPendant SDK 5.12.02 or later. ScreenMaker allows selection of FlexPendant SDK version when it is launched. If only one version of FlexPendant SDK is available in the system, it is loaded by default.
7.12 Support for future RobotWare versions

RobotStudio 6.00.01 supports all future minor revisions of RobotWare 6.00.01, but no future major releases. For example, RobotStudio 6.00.01 will support RobotWare 6.00.02 (if, and when available) but not RobotWare 6.01, or 6.02.