



RELEASE NOTES

RobotStudio 2024.1

Contents

Release Notes for RobotStudio 2024.1	3
General	3
User documentation	3
Tutorials	3
System Requirements	3
New Functionality	5
Activate new cloud subscription when a cloud license exists	5
Always add virtual controllers when opening a project	6
Install required virtual controller software when opening a project	6
Jobs functionality to distribute software updates to OmniCore controllers	6
Local package installation sources in Add-Ins Gallery	6
New custom collision geometry dialog	7
OmniCore external axis support	7
Restrictions when modifying installation on a real robot controller	8
Support Offs and RelTool	8
Visualize World Zones	8
Information	9
Problem with safety configuration recovery	9
Safety network number configuring	9
Corrections	10
Known Limitations	14
IO Configurator 6	14
Online	14
Online – Paint	14
Online – Integrated Vision	15
Offline	17
Conveyor Tracking	20
MultiMove	20
External Axis	20
Network Drives and UNC Paths	21
RAPID	21
Paint	22
Graphics and Geometry	22
ScreenMaker	23
RobotWare Compatibility	26
Supported RobotWare versions	26
RobotWare 5.05 and 5.06 Compatibility	26
RobotWare 5.07 Compatibility	26
RobotWare 5.08 Compatibility	26
RobotWare 5.10 Compatibility	26
RobotWare 5.11 Compatibility	26
RobotWare 5.12 Compatibility	27
RobotWare 5.13 Compatibility	27
RobotWare 5.15 Compatibility	27
RobotWare 6 Compatibility	28
General Compatibility Limitations	28

Release Notes for RobotStudio 2024.1

General

The release name is RobotStudio 2024.1 and the build number is 24.1.10693.0. The build date is March 4, 2024.

User documentation

The RobotStudio Operating Manual is available in all languages supported by RobotStudio except Czech, i.e. English, German, French, Italian, Chinese, Japanese, Spanish. RobotWare manuals for IRC5 and OmniCore can be installed from the Add-Ins Gallery.

Tutorials

Tutorials are available at the RobotStudio product pages at <https://new.abb.com/products/robotics/robotstudio>.

System Requirements

Required Software

Microsoft Windows 10 Anniversary Edition or later, 64-bit edition, is required.

The Windows App Installer is a pre-requisite for the virtual OmniCore FlexPendant software, see <https://www.microsoft.com/en-us/p/App-Installer/9NBLGGH4NNS1>. The App Installer is a default built-in app in Windows 10 and later, but may have been removed on some PCs.

Sideloaded apps must be enabled on Windows to install the virtual OmniCore FlexPendant.

To enable sideloading follow these steps:

1. Open **Settings**.
2. Click **Update & Security** (Windows 10) or **Privacy & security** (Windows 11) > **For developers**.
3. Ensure **Developer Mode** is set to **On**.

Recommended Hardware

ITEM	REQUIREMENT
CPU	2.0 GHz or faster processor, multiple cores recommended
Memory	8 GB minimum 16 GB or more if working with large CAD models
Disk	10+ GB free space, solid state drive (SSD)
Graphics Card ¹	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.
Screen Resolution	1920 x 1080 pixels or higher is recommended
Mouse	Three-button mouse
3D Mouse	Any 3D mouse from 3DConnexion, see http://www.3dconnexion.com .

ITEM	REQUIREMENT
Virtual Reality Headset	Meta Quest 2, HTC Vive or any Windows Mixed Reality Headset. Note that special PC hardware requirements apply when using RobotStudio with VR, see https://www.oculus.com/oculus-ready-pcs/ , https://www.vive.com/us/vive-ready/ , or, https://www.microsoft.com/en-us/mixed-reality/windows-mixed-reality , respectively.

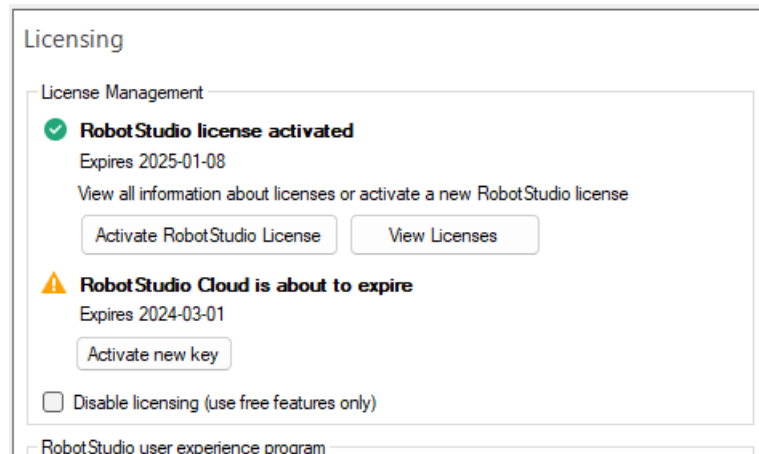
¹ RobotStudio will not benefit from the additional features of so-called 'Professional' or 'Workstation' graphics cards. The price level of these are at a much higher range than gaming graphics cards with comparable performance. High-end gaming PCs are very suitable for offline programming with RobotStudio. Such a PC will provide good performance for a limited budget.

New Functionality

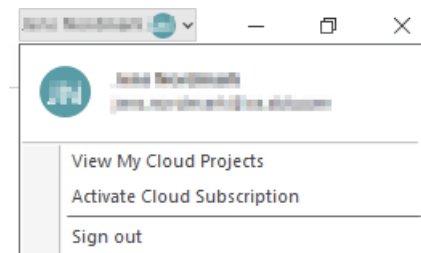
- [Activate new cloud subscription when a cloud license exists](#)
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- [Jobs functionality to distribute software updates to OmniCore controllers](#)
- [Local package installation sources in Add-Ins Gallery](#)
- [New custom collision geometry dialog](#)
- [OmniCore external axis support](#)
- [Restrictions when modifying installation on a real robot controller](#)
- [Support Offs and RelTool](#)
- [Visualize World Zones](#)

Activate new cloud subscription when a cloud license exists

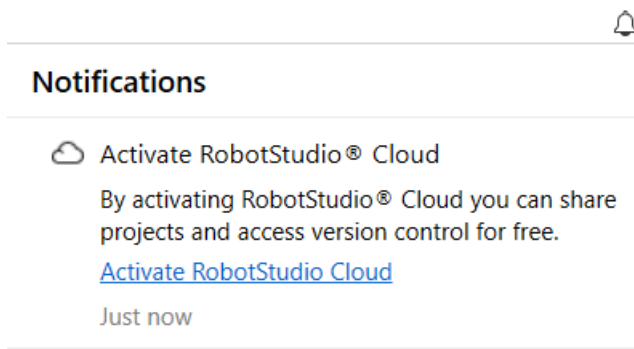
A new cloud subscription may now be activated before the expiration of the current one.



Activation is also accessible from the sign-in dropdown.



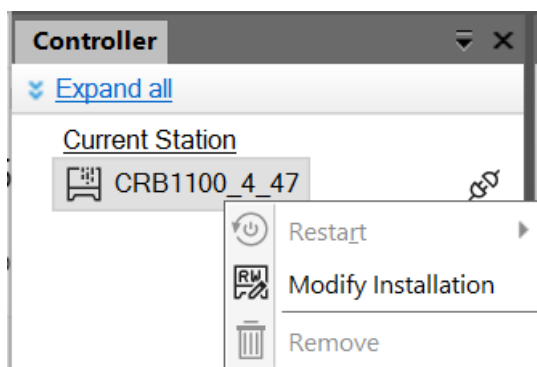
A notification will appear if its possible to activate Cloud using the current license key.



Always add virtual controllers when opening a project

When opening a project, all virtual controllers are now added to the Controller browser even if they cannot be started because of missing software components (RobotWare or add-ins).

After a virtual controller has been repaired or the missing components installed, it can be started with the Restart command.



Install required virtual controller software when opening a project

When opening a project, RobotStudio will verify that the software components (RobotWare and add-ins) required by each virtual controller are installed on the PC. If there are missing components that are available in the Gallery, the user will now have the choice to automatically download and install them.

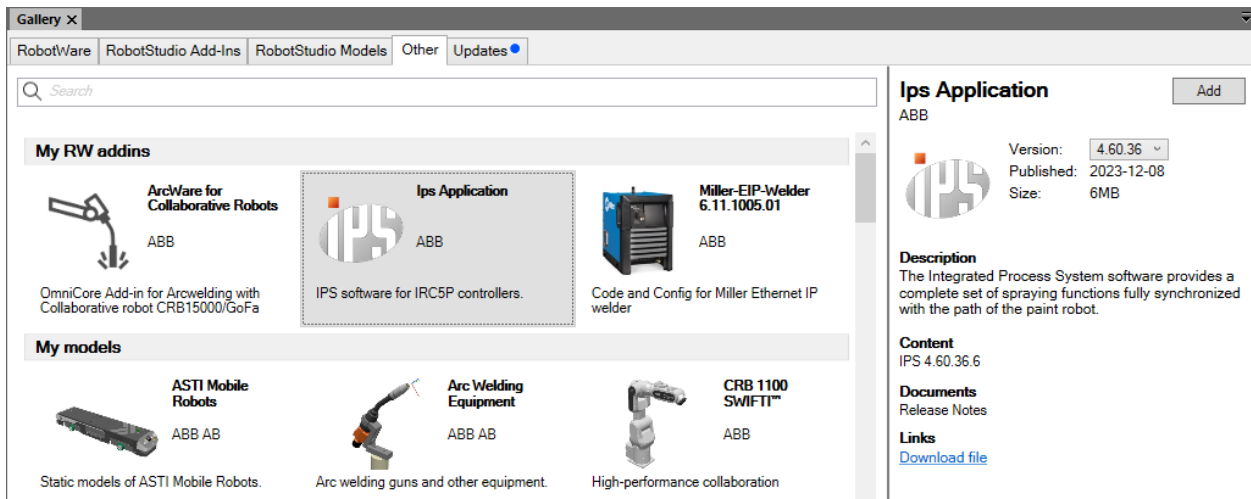
Jobs functionality to distribute software updates to OmniCore controllers

Starting from version 2024.1, RobotStudio jobs supports action "Distribute Update Package" to OmniCore controllers with RobotWare version 7.13 or newer.

Local package installation sources in Add-Ins Gallery

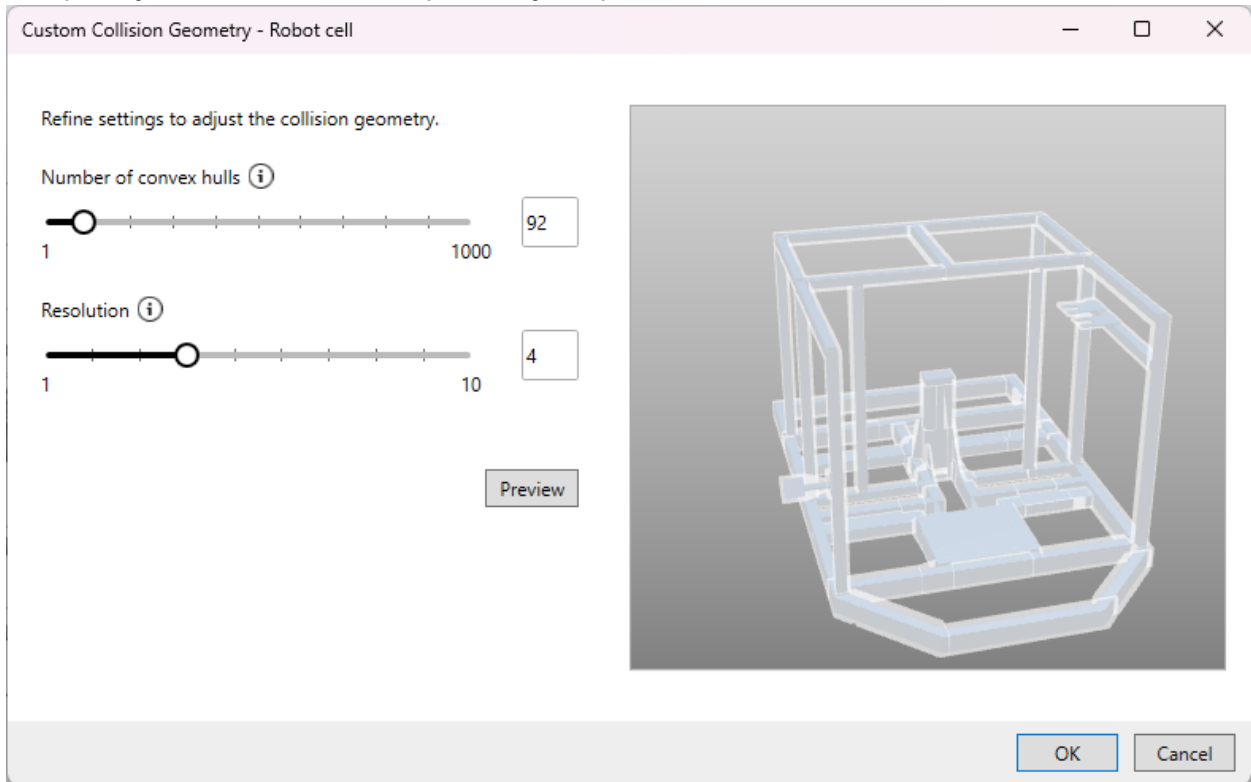
Distribution packages in locations marked as "Package installation source" in Options - Files & Folders - Document Locations are now shown under a separate tab in the Add-Ins Gallery.

The appropriate metadata is extracted so the appearance of the gallery items is comparable to official distribution packages.

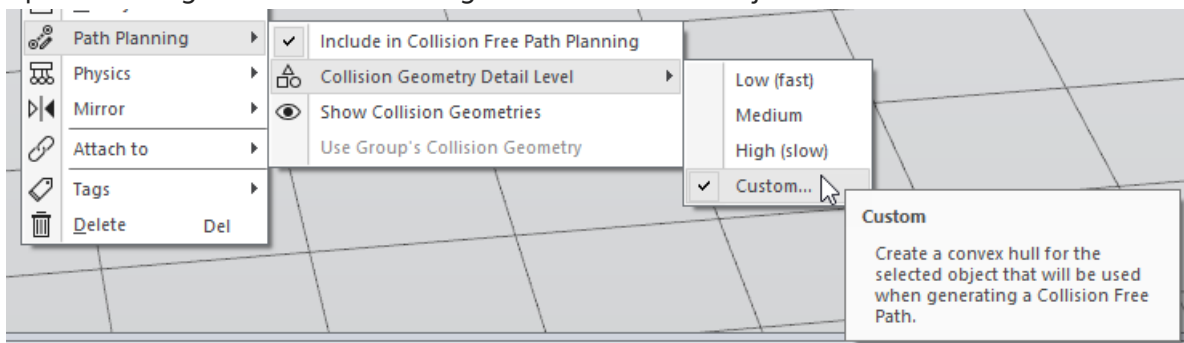


New custom collision geometry dialog

The dialog for creating a collision geometry with custom detail level, for use in collision free path planning, has been updated to be easier to use. It is now also possible to apply the custom detail level to multiple object at once, which was previously not possible.



Open the dialog from the Path Planning context menu of an object.



OmniCore external axis support

It is now possible to create an OmniCore Virtual Controller from Layout with external equipment, for example track motion IRT 510.

The selected controller variant must support the number of drive units required by the equipment.

Restrictions when modifying installation on a real robot controller

Starting from RobotStudio 2024.1, Modify Installation dialog does not allow changing options that define controller hardware configuration when working with a real robot controller. These options are read-only and grayed out.

Support Offs and RelTool

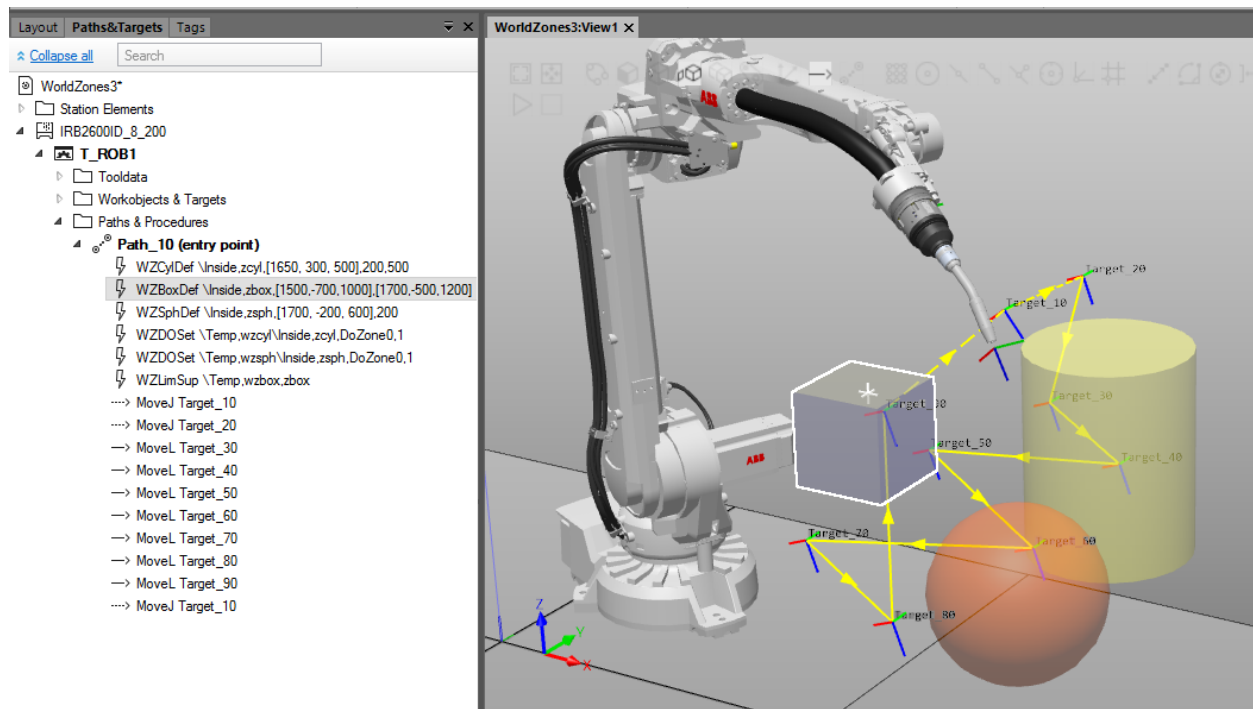
Move instructions that use Offs and RelTool in the target argument can now be synchronized and visualized in the station environment.

- When synchronizing between RAPID and the station environment, the target that is referenced by Offs or RelTool will also be synchronized.
- The path visualization is adjusted according to the offset and an extra frame will be displayed at the offset position.
This requires that only numeric literals are used in the function arguments.
- The "Jump To Move Instruction" command will move the robot to the offset position.
- "View Robot at Target" will jump to the offset position when a move instruction is selected.
- Automatic reach check for move instructions will use the offset position.

Visualize World Zones

World Zone instructions can now be visualized and synchronized between the Station and Virtual Controller.

The instructions for defining World Zone volumes (WZBoxDef, WZCylDef and WZSphDef) are visualized as semi-transparent shapes in the Station environment. It is possible to set the color of the shapes or hide them. The instructions can be selected in the 3D graphics when using the Instruction selection level.



Visualization requires the instructions to use numeric literals in the volume definition.

World Zones defined in joint coordinates (WZLimJointDef and WZHomeJointDef) are not yet supported.

Information

Problem with safety configuration recovery

There is a problem with safety configuration recovery.

Given a safe Scalable device has been configured and is running, when resetting the safety configuration, it is no longer possible to recover the device as Configured using Configure Device/Update.

Work around: Remove device configuration and make a re-configuration of the device.

Safety network number configuring

If two systems using Safe Scalable IOs is incidentally interconnected (or by purpose) there is a risk, if the systems share the same IP address of their respective Safe Scalable IO devices, then the controller may be controlling the wrong IO.

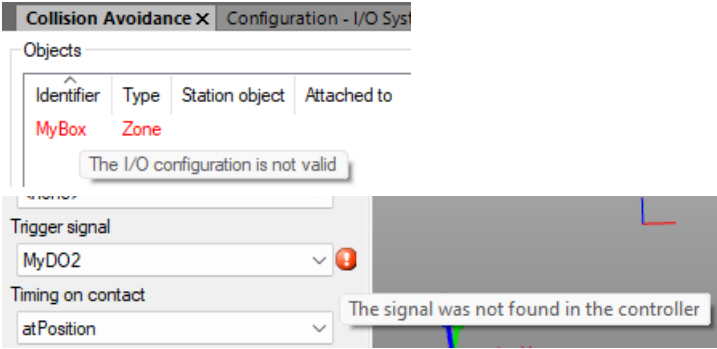
In RobotStudio 2023.4.1 and earlier it is not possible to create unique UNIDs (safety network numbers).

Recommendation: Update to RobotStudio 2024.1, do a factory reset, and a re-configure the Safe Scalable IO.

With RobotStudio 2024.1 it is possible to create uniqueness across Safe Scalable IO Devices in a system wide perspective by setting Safety Network Number in device configurator while configuring first Safe Scalable IO Device.

Corrections

PDD	
14697	<p>ENDPROC incorrectly suggested for IF/WHILE/FOR/TEST</p> <p>RAPID Editor statement completion will now correctly suggest the corresponding ENDxxx for the preceding IF/WHILE/FOR/TEST.</p>
14723	<p>RobotStudio TriggL/J templates do not work</p> <p>Fixed an issue where two mutually exclusive arguments could both be defined when a RAPID instruction was created or edited in the station environment.</p>
14753	<p>RAPID dnum error</p> <p>Fixed an issue in the RAPID editor where math operations within a conditional statement, between a number and a dnum variable would be flagged as a syntax error.</p>
15038	<p>Reduce Zones Not Documented in RS Help File</p> <p>Tooltips for reduce zones functionality have been improved.</p>
15207	<p>PhysicsControl Smart Component behavior</p> <p>The PhysicsControl Smart Component was difficult to use because the physics properties were updated whenever the Object property was set. This has been improved by adding a new input signal "GetProperties". If the signal is set to low (0), the component will not retrieve physics properties from the object.</p>
15240	<p>Jobs: Update UAS template error</p> <p>Fixed an issue in Jobs where a template file that contained the "Update UAS" action could not be loaded.</p> <p>It is now also possible to add or override template parameters when using the command line tool. This can be used to define the UAS file password which is not saved in the template file:</p> <pre data-bbox="304 1373 1398 1458">RunJob.exe C:\Temp\UpdateUASJob.xml /defaultCredentials /param:Secure_UasFilePassword=xyz123</pre>
	<p>No auto complete for ENDPROC</p> <p>RAPID Editor statement completion now works as expected for procedures/functions/traps that do not have a corresponding ENDPROC/ENDFUNC/ENDTRAP.</p>
	<p>File Transfer error</p> <p>Fixed an error that could occur when using File Transfer to copy or move a file on an OmniCore controller.</p>
	<p>Upload to RobotStudio Cloud failed for large project</p> <p>Improved the reliability and error handling when uploading a large project to RobotStudio Cloud. The upload no longer times out after 100 seconds, and it is possible to cancel the operation.</p>

PDD	
	<p>Jobs: Failing for Save Assessment Data for multiple controllers</p> <p>Save Assessment Data in Jobs will now report an appropriate error message if "{SerialNumber}" is used for the folder name, and the serial number of a controller is not valid.</p>
	<p>Help page is not opening while clicking on the button on Unpack Pack&Go</p> <p>Previously the Help button in the unpack Pack&Go wizard did not work. Now it opens help.</p>
	<p>VrSession Smart Component fatal error</p> <p>Fixed an crash that could occur when using the VrSession Smart Component to add commands in VR.</p>
	<p>Collision Avoidance action text incorrect</p> <p>The "Action" text in the Collision Avoidance configurator has been corrected. For objects with a Trigger signal configured it now shows the signal instead of "StopProgram".</p>
	<p>RobotStudio 2022 possible bug with compare folders</p> <p>Compare folders sometimes failed to mark directories as changed when containing changed files. This is now fixed.</p>
	<p>Wrong scale factor when importing DXF/DWG file</p> <p>AutoCAD files without unit information are now treated as using metric units (millimeters) instead of imperial units (inches).</p>
	<p>DNS settings not readable without Write Access</p> <p>In the Public Network configuration for a controller, the DNS settings can now be viewed without acquiring Write Access.</p>
	<p>Collision Avoidance I/O configuration error</p> <p>The handling of invalid I/O configuration in Collision Avoidance has been improved. The error is now indicated in the Collision Avoidance window and the Object Properties window.</p> 
	<p>SmartComponent - Graphic Switch + Highlighter not working together</p> <p>Graphic Switch and Highlighter interacted in the wrong way before. Graphic Switch will no longer toggle a part to become invisible if it's already visible because it is highlighted.</p>

PDD	
	<p>Too high sample rate in Online Monitor</p> <p>The update rate in Online Monitor has been adjusted to reduce CPU and network load.</p>
	<p>RoboStudio is limiting password to only 16 characters</p> <p>Controller password length limit has increased from 16 to 128 characters for RobotWare 7.13 and above.</p>
	<p>Signal Analyzer: Stress index support</p> <p>Stress index is now only supported for Lima robots IRB 5710, 5720, 6710, 6720, 6730, 6740, 7710 or 7720.</p>
	<p>RobotStudio does not support latest version of .SLDPRT CAD file (SolidWorks version 2023 SP5)</p> <p>It is now possible to import .sldprt files from SolidWorks 2023.</p>
	<p>Device List filters not scrollable</p> <p>The filters for Group and Sub-Group in "Connect to Controller" - "Device List" are now scrollable and sorted alphabetically.</p>
	<p>Remove button for built-in package is enabled</p> <p>An error would occur if trying to uninstall distribution packages that are included in the RobotStudio installation, such as I/O Engineering. The "Remove" button for such packages in the Add-Ins Gallery is now disabled since they cannot be uninstalled. Also, they are now visible under "Installed Packages" in the Add-Ins browser.</p>
	<p>Missing MovePnP in station</p> <p>The RAPID instruction MovePnP can now be used in a station and synchronized to and from the Virtual Controller.</p>
	<p>Exception when opening context menu</p> <p>An issue caused an error when opening the context menu for an item in the layout browser for the first time, while using RobotStudio with a freemium license. This problem has now been resolved.</p>
	<p>Undo Markup does not restore image</p> <p>Fixed an issue with undo support for markup images. Previously, changes to markup images could not be undone. Now, undoing a change will correctly restore the markup image to its previous state.</p>
	<p>Cap and Disp instructions not loaded for OmniCore VC</p> <p>RAPID instructions from DispenseWare and Continuous Application Platform can now be used in a station with an OmniCore virtual controller.</p>
	<p>Collision free path fails in singularity</p> <p>Fixed an issue that could make the collision free path planning fail if the robot was in a singularity in one of the targets.</p>

PDD	
	Online Monitor: Incorrect robot orientation Previously, robots with a Gravity Beta value greater than 90° would be oriented incorrectly. This issue has now been resolved.
	Integrated Vision manual missing The application manual for Integrated Vision can now be found under Help - Add-Ins Documentation.

Known Limitations

IO Configurator 6

***Safety configuration problem with PROFIsafe Controller or CIP-Safety scanner**

Changing safety settings in Visual SafeMove or IO Configurator 6 does not always work in conjunction with the "PROFIsafe controller" or "CIP-Safety Scanner" option. Connection with robot controller can be lost during any IO-configuration, sometimes resulting in that the Flex Pendant reboots. Again this is only applicable when the PROFIsafe controller or CIP-Safety scanner option is present in the system. Problem is dependent on how many devices are configured on respective industrial network. I.e. EtherNet/IP or ProfiNet.

Online

Signal Analyzer Online recordings not saved

When recording signals from a real controller with RobotWare 6.13.03 and later, or RobotWare 7.6.1 and later, there is a sporadic issue which causes the signal changes to not be recorded.

Routine variables can't be displayed in RAPID Watch with RobotWare 6.12

A limitation in RobotWare 6.12 prevents variables declared in a routine from being displayed in the RAPID Watch window.

Port speed cannot be set at the same time as 'Obtain IP address automatically'

In the Public Network settings dialog the Port speed drop down menu is disabled when 'Obtain IP address automatically' is selected.

Workaround:

1. Select 'Use the following IP address' and specify any valid IP address.
2. Select the desired port speed and press OK.
3. Select 'Obtain IP address automatically' and press OK.

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. However, from RobotWare 6.03 onwards, then RAPID tasks to execute or to stop can be selected from RobotStudio RAPID tab.

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.

Cable harness not visible in Online Monitor

Physics-based dynamic cables that are part of a robot model are not visible in Online Monitor.

Online – Paint

Backup for Paint systems does not create backup of the PIB for IRC5P with RobotWare 5.xx

The Backup function of RobotStudio does not create a backup of the PIB board of the IRC5P system when running RobotWare 5.xx. 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.

Online – Integrated Vision

Installation error when having previous versions of RobotStudio or Insight Explorer

If you have a previous version of RobotStudio or Cognex In-Sight software installed, installing a new version of RobotStudio may result in the following error message

Module C:\Program Files (x86)\Common Files\Cognex\InSight\5.7.1674.0\CvsInSightDisplay.ocx failed to register. HRESULT -2147220472. Contact your support personnel.

Workaround: To correct the issue, open Windows Settings -> Apps -> Apps & features, select the current ABB RobotStudio 2019.x, select Modify, and step through the installation wizard and select Repair. Alternatively, uninstall and reinstall RobotStudio.

Note: Only one version of the In-Sight Display Control can be registered at a time, and this is always the latest version installed. Although older versions of RobotStudio or In-Sight may seem to function with this version installed, their compatibility with this version is not guaranteed.

RobotStudio may hang for up to 60 seconds when configuring jobs with PatMax 1-50

The user interface of RobotStudio may freeze for up to 60 seconds when configuration Integrated Vision jobs with the tool PatMax 1-50.

Workaround: Use PatMax 1-10 instead

Remaining error – New Emulators

New camera models have been added to the camera emulator option in RobotStudio 6.04.01. Some of these new models are not yet fully compatible. Our recommendation is to choose a camera model from the 7000 series which is fully compatible with Firmware version 4.10.2.

Emulated cameras not discovered when controller in Motors On

For RobotWare 5.61 onwards, the camera discovery mechanism is disabled when the controller is in Motors On. As a consequence, the camera nodes will not appear in the controller browser.

Workaround: Switch to Manual Reduced Speed and use the Refresh command on the Integrated Vision node in the browser to make the cameras appear.

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 it is 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:

```
TeInet 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 address is used and persist, please try a static address instead.

Offline

Point cloud data in JT files can't be imported

Point cloud data in JT files is not imported by RobotStudio.

Issue with collision avoidance for palletizer robots

When configuring collision avoidance for a palletizer robot using RobotWare 6.11, attaching an object to a mechanism link can result in an error and the configuration will not be loaded.

The YuMi library revision 1 cannot be successfully updated to YuMi revision 2

When opening a Pack&Go file with a station that has a reference to `IRB14000_0.5_0.5__01.rslib` you get the option to update it to the newer `IRB14000_0.5_0.5__02.rslib`.

The following issues occurs if you select ‘Yes’ and update the model:

- The attached parts, for example Smart Grippers, are detached.
- The new YuMi robot is not connected to the virtual Controller.
- The old YuMi mechanism is converted to a component.

Answer ‘No’ to this question to keep the original revision 1 model and avoid the problems mentioned above.

RobotStudio needs to be restarted to update a modified library instance

When editing a library file (.rslib) that is used in a currently open station, then RobotStudio needs to be restarted to update the library. Simply re-opening the station is not enough to update the content of the station. Unless RobotStudio is restarted, the old library instance will remain in memory and be loaded even though the underlying file has been updated. This is a known limitation and is expensive to fix. There is a workaround to the problem, which is to restart RobotStudio.

The robot IRB 1600ID 1.55 m / 6kg replaced by IRB 1660ID1.55 m / 6 kg in RobotWare 6.04

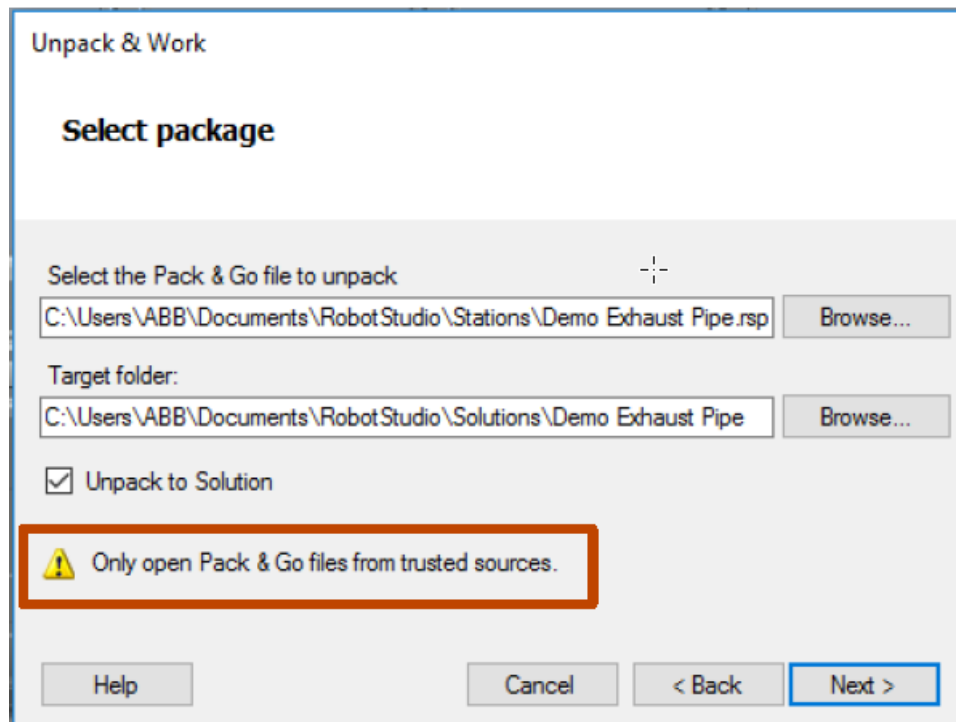
The robot IRB 1600ID 1.55 m / 6 kg is not available in RobotWare 6.04 and later. It has been renamed to IRB 1660ID 1.55 m / 6 kg. Virtual controller systems for IRB 1600ID 1.55 m / 6 kg based on RobotWare 6.03 cannot be upgraded to RobotWare 6.04 and later. This means that Pack&Go files for this robot based on RobotWare 6.03 cannot be upgraded to RobotWare 6.04 automatically.

Workaround: Re-build or modify the virtual controller system to use IRB 1660ID 1.55 m / 6 kg instead when using RobotWare 6.04 or later.

FlexPendant and RAPID applications run with logged in user rights

A FlexPendant or RAPID application running on the virtual controller runs with the rights of the logged-in Windows user. RAPID applications running in a background task will start to execute when the Pack&Go

file is opened and FlexPendant applications will start to execute when the user starts the Virtual FlexPendant. A warning message has been added to the Unpack&Work wizard to make the user aware that only Pack&Go files (.rspg) from trusted sources shall be opened.



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 6.04 into an earlier version of RobotStudio such as e.g. RobotStudio 5.x, 6.03.02 or earlier. However, RobotStudio is backwards compatible, which means stations and libraries created in versions 5.x, 6.03.02 or earlier can be opened in RobotStudio 6.04

TrueMove path visualization fails for customized zone data

The TrueMove path visualization function only supports predefined zonedata. It will not work for user defined zonedata.

Backup fails for RobotStudio solutions with SafeMove or Electronic Position Switches

Backups are automatically created for virtual controller systems that are part of a RobotStudio solution when saving the station. For virtual controller systems with the RobotWare options SafeMove or Electronic Positioning Switches the backup will fail since these systems contain files that are read-only. As a result, an error message is presented in the output window: `<System name>: Backup failed`. The station will be successfully saved but there will be no backup created. Workaround: Ignore the error message `<System name>: Backup failed` and create a manual backup whenever needed. The RobotStudio Option "Enable automatic backup of controllers in solution" that is available in "RobotStudio Options -> Robotics -> Virtual Controller" can be de-selected to disable the backup function.

IRB 14000 cannot be combined with any other robot

The function system from layout fails if trying to create a MultiMove system where one robot is an IRB 14000. The reason is that the IRB 14000 cannot be combined with any other robot.

Workaround: Create a separate system for the IRB 14000.

The Work Envelope function does not support IRB 14000

The function is disabled for the IRB 14000 and cannot be activated.

The 2D work envelope fails for certain robot models

As a result, the generated work envelope 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

```
<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.

I/O 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.

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 jointtargets. The functions will leave the jointtargets 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.

Conveyor Tracking

*Conveyor objects must be re-added for stations created prior to RS 6.05

When opening stations with conveyor tracking created prior to RobotStudio 6.05, conveyor objects must be re-added.

Incorrect default values for c1Position and c1Speed for RobotWare 5 with the PaintWare option

The default values for the parameters c1Position and c1Speed may become incorrect for a virtual controller system. The symptom is that its attribute values are all zero, see snapshot below.

Workaround: Save the following lines to a CFG file named 'TEMP.CFG' or similar and load in the virtual controller followed by a restart.

```
EIO:CFG_1.0:5:0::  
#  
EIO_SIGNAL:  
-Name "c1Position" -SignalType "AI" -Unit "CnvIf"\  
-SignalLabel "ctPosition" -UnitMap "0-31" -Access "ALL"\  
-MaxLog 21474.8 -MaxPhys 1 -MaxPhysLimit 1\  
-MaxBitVal 2147483647 -MinLog -21474.8 -MinPhys -1 -MinPhysLimit -1\  
-MinBitVal -2147483647  
-Name "c1Speed" -SignalType "AI" -Unit "CnvIf" -SignalLabel "ctSpeed"\  
-UnitMap "32-63" -Access "ALL"\  
-MaxLog 21474.8 -MaxPhys 1 -MaxPhysLimit 1\  
-MaxBitVal 2147483647 -MinLog -21474.8 -MinPhys -1 -MinPhysLimit -1\  
-MinBitVal -2147483647
```

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: Workobject is not set for the current task.

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.

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 Virtual FlexPendant

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 version="1.0"?>
<configuration>
  <startup useLegacyV2RuntimeActivationPolicy="true">
    <supportedRuntime version="v4.0" sku=".NETFramework,Version=v4.0"/>
  </startup>
  <runtime> <!-- THIS IS ONE OF THE NEW LINES!!! -->
    <loadFromRemoteSources enabled="true"/> <!-- THIS IS ONE OF THE NEW LINES!!! -->
  </runtime> <!-- THIS IS ONE OF THE NEW LINES!!! -->
</configuration>
```

The Virtual FlexPendant must be restarted for the changes to take effect. For further information, see [http://msdn.microsoft.com/en-us/library/dd409252\(v=vs.100\).aspx](http://msdn.microsoft.com/en-us/library/dd409252(v=vs.100).aspx)

RAPID

Robtargets that are LOCAL to a PROCEDURE cannot be synchronized with RobotStudio

The RobotStudio synchronization engine that translates 3D data of the station to RAPID code and vice

versa does not support robtargets that are declared locally to a procedure.

Workaround: Declare the robtargets as global or local to a module instead.

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

RobotStudio requires that robtargets names are unique for the RAPID synchronization to work properly, i.e. you cannot have a global robtargets named pMyTarget1 in module A and a local robtargets 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 mix-up 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.

Paint

The new conveyor tracking module DSQC2000 is not supported for paint robots.

The new conveyor tracking module DSQC2000 is not supported for paint robots.

Lack of Virtual Controller support for the Paint systems

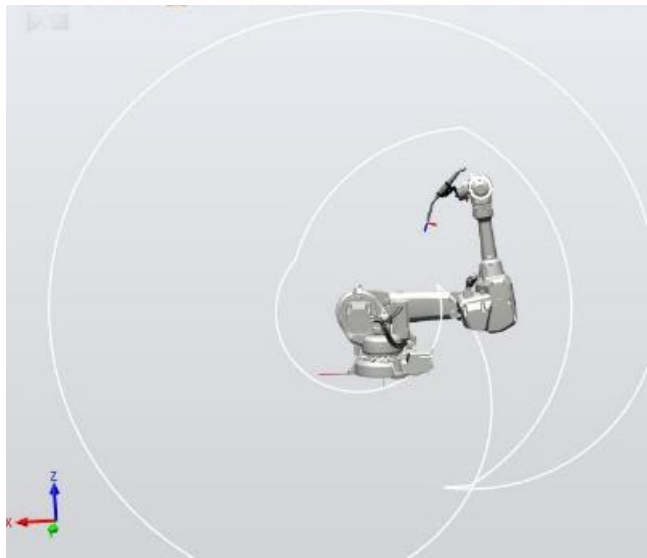
Paint systems that are configured using the Paint package I/O option Discrete, Compact or Fieldbus, will result in a SysFail state.

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

Graphics and Geometry

***Display of working range optimized for furthest reach**

The current algorithm uses a fixed value for joint five which gives the furthest reach for a given tool. The sweep is not optimized to get the shortest reach on the "inside" of the working area.



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 x.y\Bin64
```

and

```
C:\Program Files (x86)\ABB Industrial IT\Robotics IT\RobotStudio x.y\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.

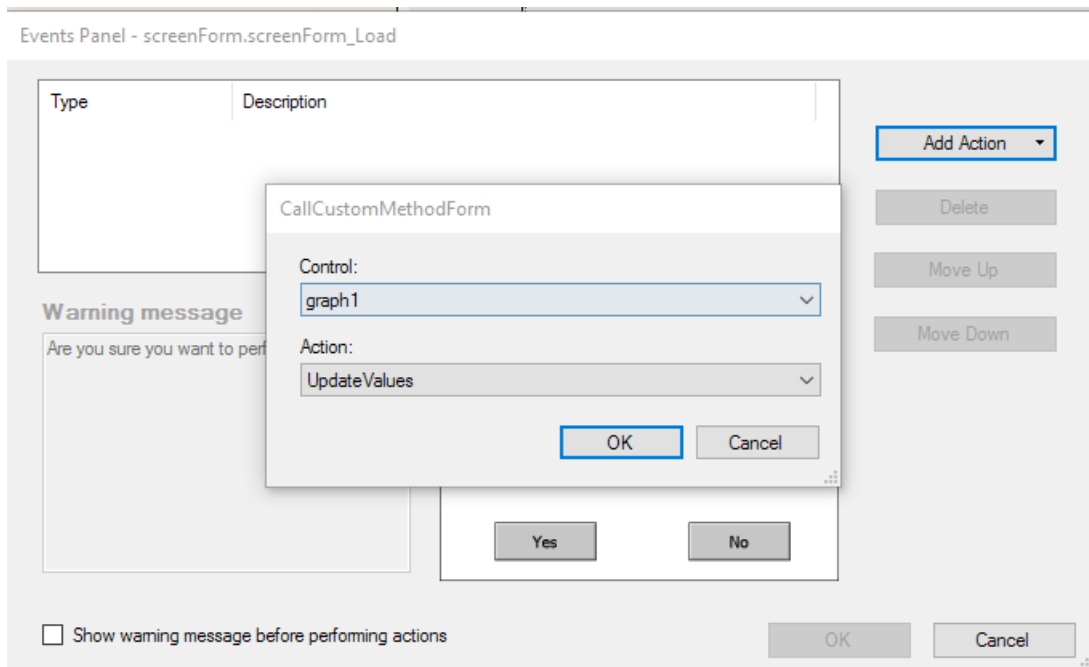
ScreenMaker

Numeric controls and decimal separators

To use numeric controls in ScreenMaker on the PC set the decimal symbol to a single period ('.'). Other decimal symbols are not supported and binding values will not work in the Virtual FlexPendant. The behavior on the real FlexPendant is not affected by this PC setting.

Graphs on secondary screens

To use a Graph on a secondary screen (not the main screen) a custom action is needed. Otherwise, the Graph will not be updated properly. In the ScreenForm that contains the Graph add a Load event. In this event add an action using Add Action->Advanced->Call Custom Action. Select the Graph control and the UpdateValues action.



Binding to the Enabled property

Connecting the *Enabled* property of any control to a BOOL variable or IO signal may not work as expected. The variable or signal may be inadvertently changed leading to unexpected behavior. Instead, bind to a digital output where the *Access Level* is set to *ReadOnly*

A ScreenMaker cannot be deployed a controller with disabled Default User

Workaround: Enable the Default User.

NumEditor in ScreenMaker disables the controls in a group box or panel

If you are using the NumEditor control in a group box or a panel, and that box or panel is enabled by an input signal, then all other controls of that group or panel will become disabled if the editor is opened and closed.

Button with multiple states in ScreenMaker app do not update the images if button is disabled

For an app which uses Buttons with multiple states connected to images that change depending on the value of a RAPID variable, then if the button is disabled, the button shows the greyed image of the state which was active when the disabled state was shown the first time.

ScreenMaker fails for RobotWare 5.12

ScreenMaker fails to build applications for RobotWare 5.12.

Workaround: Update to a later RobotWare version.

A ScreenMaker application may fail to build if the DPI setting is not set to 100%

Certain UI controls in ScreenMaker may fail to build correctly if the DPI setting is not set to 'Smaller – 100%'.

Symptom: The error message caused by this problem will read 'System.Drawing.Font' does not contain a constructor that takes 2 arguments.

Workaround: Set DPI to 100% on your PC.

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)

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.

RobotWare Compatibility

Supported RobotWare versions

RobotStudio works with RobotWare 5.07 and later. Please check details below. The latest supported RobotWare version for IRC5 and OmniCore controllers is stated under Help/About in RobotStudio. RobotWare packages can be added to RobotStudio from the Add-Ins Gallery window.

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.

RobotWare 5.07 Compatibility

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.

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.

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.

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.

RobotWare 5.12 Compatibility

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

Paint

Paint backups from RW 5.12.01 are 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

```
EIO_SIGNAL :
-Name "doMainInMC" -SignalType "D0" -Unit "SysComm" -UnitMap "44"
-Name "A1HVErrNo" -SignalType "G0" -Unit "SysComm" -UnitMap "150-151"\
-Access "ALL"
-Name "A1HVEEn" -SignalType "D0" -Unit "SysComm" -UnitMap "155"\
-Access "ALL"

EIO_CROSS:
-Res "A1HVEEn" -Act1 "HVEEnabled"
```

SYS.CFG:

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

RobotWare 5.13 Compatibility

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

Paint

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.

RobotWare 5.15 Compatibility

Signal Analyzer Online

The feature Signal Analyzer Online requires RobotWare 5.15.03 or later.

RobotWare 6 Compatibility

Overview

RobotWare 6.00 and 6.00.01 systems cannot be directly upgraded to RobotWare 6.01. To upgrade a system, you need to create backup and migrate it using the tool 'Migrate Backup or Folder', then recreate the system and finally, restore the backup. For this reason, the functions 'Unpack&Work', 'Go Offline' and 'New Solution with Station and Robot Controller – From backup' are blocked to prevent upgrade from RobotWare 6.00 or 6.00.01 to RobotWare 6.01. RobotStudio, however, is compatible with both RobotWare 6.00 / 6.00.01 and 6.01.

General Compatibility Limitations

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.

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