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General

**Machine Tending PowerPac**

This is a PowerPac to program Robotic handling applications using RobotWare Machine Tending which is an Additional option to RobotWare.

**Release Information**

The information should be considered as last minutes information and most up-to-date.

**Release Name**

The release name is Machine Tending PowerPac 5.60

The release contains following:

- Machine Tending PowerPac 5.60 build 138

**Release Data**

Release date 2013-12-20

**Language Support**

Machine Tending PowerPac 5.60 is available in English language

**Documentation**

The following documents are available in English language

- Operating Manual
  - MTPP_OM_3HAC044396-en

**System Specification**

**Recommended HardWare**

High-performance desktop or laptop workstation:
- CPU: 2.0 GHz or faster processor. Recommended is multicore processor
- Memory: 1 GB RAM or more (More is recommended)
- Available disk space: 5+ GB on the system disk
- Graphics card: High performance OpenGL-compatible graphics card with the corresponding up-to-date drivers installed
- Screen resolution: 1280 x 1024 pixels (Recommended)
- Colors: 256 or higher
- DPI: Normal size (96 dpi)
- Mouse: Three-button mouse

**Supported Operating Systems**
- Microsoft Windows 7 32-bit & 64-bit edition

**Installation**

**Prerequisites**
The following software must be installed:
- RobotStudio 5.60
- RobotWare 5.60
- RobotWare Machine Tending 5.60

**Installation Steps**
Execute the setup.exe file and follow through the installation steps.

Machine Tending PowerPac 5.xx should be installed under the ‘\Robotics IT\’ folder present at the same level as the Base application i.e. RobotStudio 5.XX

The default installation path for the Machine Tending PowerPac 5.60 is “…\ABBIndustrial IT\Robotics IT\”.

**New Functionality MTPP 5.60**
- The datatype **PosName** is configured from MTPP with information about the station position number and descriptions. This datatype is synchronized to the MT_Main module.
- MTPP support on 64 bit version of RobotStudio

**Changes in MTPP 5.60**
- Gripper handling
  - Updated the GripData arguments for the pre-defined tools installed by MTPP
Flexible to configure number of pre-defined GripData’s associated with a tool
- The tool SC’s signals are mapped with the corresponding controller signals after Synchronize to VC. This enables simulation of the gripper functions.

The Define Cycles functionality has slight modifications to simplify the process
- The Part –Cycle editor is moved to the Advanced section
- The user interface is updated with fewer options

**Known limitations in MTPP 5.60**

- It is possible to configure Project for single Robot Task
- Limited support for Undo and Redo operations when using MTPP
- The Part is not shown during simulation

**Known issues in MTPP 5.60**

- While Configuring HomeRun sequence when there are multiple movement modules, strategy for configured positions which are unique to a module will be deleted when shifting between the modules.

  **Workaround:** Ensure that the HomeRun is configured for the module with the most number of movement routines and avoid changing the views.

- While executing simulation of Stations such as Injection Moulding Machine and Die Casting Machines, it is necessary to start the machine operations by manually selecting the station smart component signals.

- Sometimes when Synchronizing to VC, there can be some error messages displayed in the output window of RobotStudio, as a result of this some of the RAPID modules might not open in the Controller tab.

  **Workaround:** First Synchronize to VC. If the error is seen again, then WarmStart the controller and try again. Else save the RobotStudio Station and close and re-open RobotStudio and try to Synchronize again.

**Corrections in MTPP 5.60**

PDD 2950   RS5.60- Exceptions when starting RWMT PowerPac 5.60