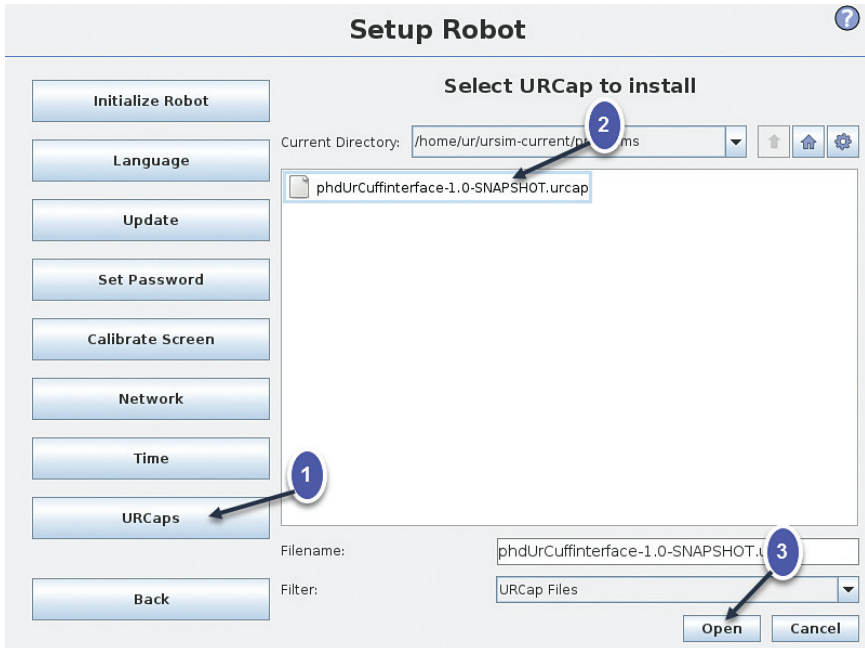


phd[®] URCAP SETUP INFORMATION



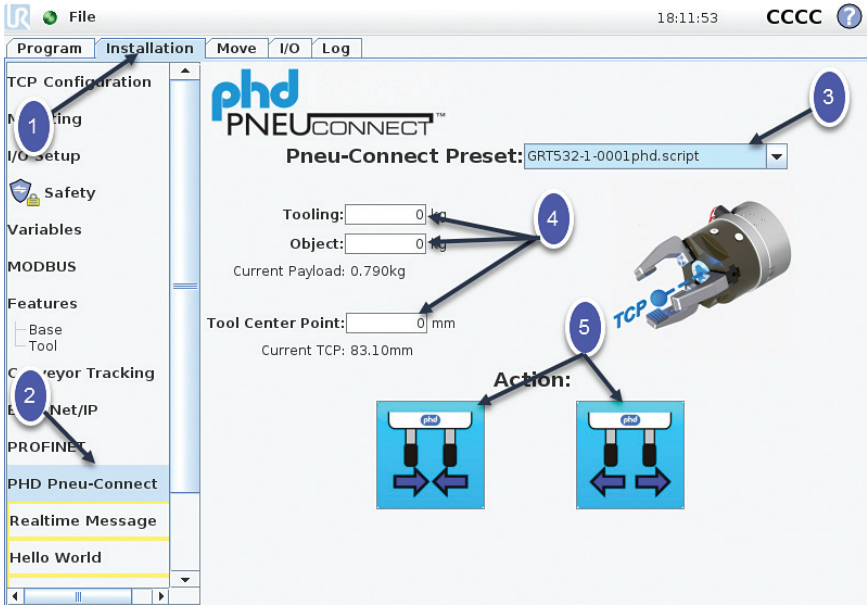
- 1) Power on robot and press **not now** when prompted to initialize.
- 2) Insert USB flash drive into Teach Pendant.
- 3) Navigate to **Setup Robot** tab on main menu and select **URCaps** button. (1)
- 4) Press **+**, followed by **usbdisk**, then click available cap. (2)
- 5) Select **Open**, then **Restart** when prompted. (3)
- 6) Allow robot to reboot.
- 7) Go to initialization screen and press **ON**, **START**, and **OK**.

NOTE: Leave USB flash drive in Teach Pendant until instructed in “Installation of Gripper with Tooling.” See next page.

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phd[®] INSTALLATION OF GRIPPER WITH TOOLING



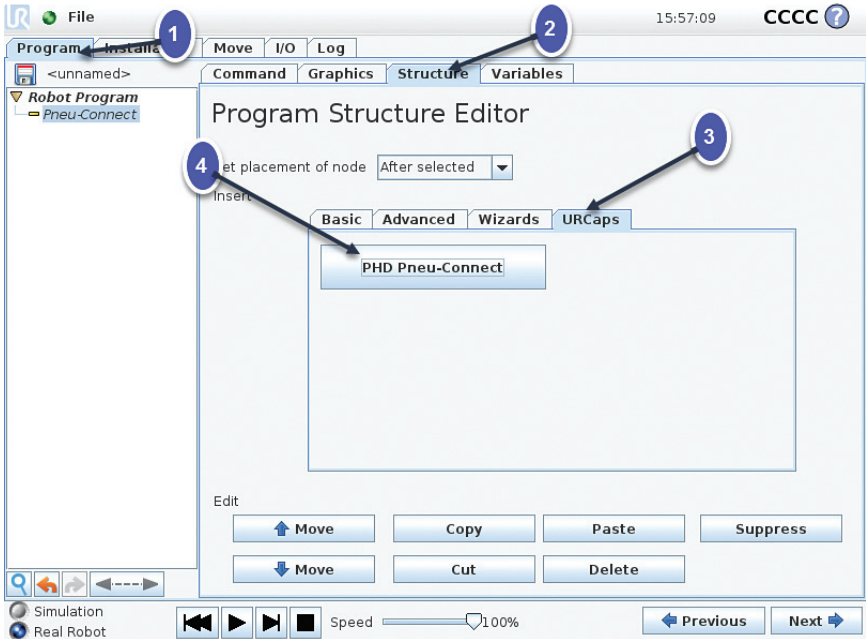
- 1) Select **Program Robot** on the main menu.
- 2) Navigate to the **Installation** tab and click **Pneu-Connect**.
NOTE: You may now take out USB flash drive.
- 3) Use dropdown menu to select desired Gripper option.
NOTE: Gripper may open upon selection
- 4) Use available number boxes to change tool settings.
(Center of gravity is calculated and set by the Cap.)
- 5) Use **Action:** buttons followed by **Execute** for real time functionality.
NOTE: In move instruction, set TCP to **Use Active TCP**.

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phd[®] URCAP LOCATION

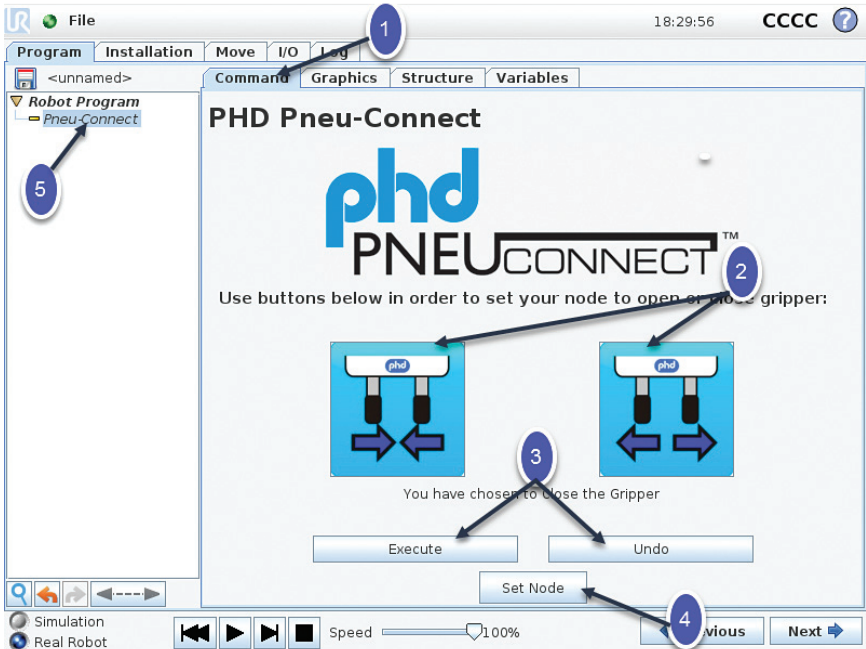


- 1) Go to **Program** tab and press **Empty Program**.
- 2) Select **Structure**.
- 3) Select **URCaps**.
- 4) Press **PHD Pneu-Connect** button.

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phd[®] PROGRAMMING WITH CAP



- 1) Go to **Command** tab.
- 2) Press **open** and **close** buttons to choose action.
- 3) **Execute** and **Undo** are used to perform the action live.
- 4) **Set Node** will add selection to the program tree.
- 5) Title updates based on option set.

NOTE: (If using GRT with no switches, a wait function must be added in the program tree to handle time to close or open).

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