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Release Information

Release Name

The release name of the product is Machining PowerPac 5.13 (MPP5.13).

The installed program version is displayed in the *About Machining* dialog box of the *Ribbon* menu. The build number of Machining PowerPac 5.13 is 5.13.1328.0225

Release Information

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

For more information please visit the support web site at
http://www.robotstudio.com/community

Release Date

Release date **2010-04**

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Supported Platforms

Before you install Machining PowerPac, make sure your system conforms to the following requirements:

Required Software

RobotStudio 5.13

RobotWare 5.13.0222 or later releases

Supported Operating Systems

Microsoft Windows XP Professional 32-bit edition with Service Pack 2 or higher.

Microsoft Windows Vista Business or Enterprise 32-bit edition

Note 1*: Machining PowerPac 5.13 does not support 64-bit operating systems.*

Recommended Hardware

High performance desktop or laptop workstation:

CPU:	2.0 GHz or faster processor
Memory:	1 GB system memory at minimum, 2 GB if running Windows Vista, stations with several robot systems, or large CAD-models.
Free disk-space:	5+ GB free space
Graphics card:	High performance DirectX 9 or OpenGL-compatible graphics card with the corresponding up-to-date drivers installed
Display settings:	Screen resolution: 1280 x 1024 pixels or higher
DPI:	Normal size (96 dpi)

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Features in Machining PowerPac 5.13

This section describes the features that have been made in MPP5.13 since MPP5.12.02.

New Features

Optimize Corner Targets

Check the option to optimize corner targets (i.e., two consecutive targets that have the same position but different orientations) when offsetting a path. This function is especially useful for offsetting path in the Y direction of RCS.

Support External Axis

If the robot system supports the external axis to which the work piece is attached, The created targets will have the value for external axis automatically. Additionally, these targets can be modified and simulated in path view.

Fixed Bugs

1) After closing robot system in RobotStudio or warmstart the virtual controller while MPP is open, the button of 'Closing Machinig' is still appearing while the tab of 'Machining' is closed.

2) The pre-selected configuration template in the first wizard page will be changed to 'Default' after clicking 'Back' from the second wizard page.

Known Limitations

Parts' Name

Imported parts to be machined cannot have a same name.

Adjust Starting Points

Based on the geometrical features, the starting points of all paths within a solution cannot be close to each other.

Limited Support of "MoveC" Instruction

MPP5.13 supports modifying "MoveL" and "MoveJ" motion instructions to "MoveC" from path view, but does not support creating "MoveC" motion instructions from surface directly.

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Limited Support of Two Robot Systems in One Cell

MPP5.13 do not support a second robot system if it is added after MPP5.13 has been launched in RobotStudio. Two robot systems have to be added prior to the launch of MPP5.13.

Performance Limitation

It normally takes a long time to generate more than one thousand paths and ten thousand targets. In cases like this, operations like opening the path view or saving the station can be very slow, or even fail due to memory limitation.

Different Results for Path Configuration

There are several path configuration algorithms in MPP5.13 and none of them is perfect. They are also different from the one used in RS5.13. Therefore, you might get different results when using the path configuration functions in RS5.13 and MPP5.13.

Problem with Undo

Several empty items will be inserted into the undo list after several actions, such as creating a new solution with the wizard and creating calibrations.

Out of Memory

When creating a solution with wizard, it generates temporary objects that will be deleted after finishing. However, the application might run out of memory due to the large amount of temporary objects created.

Difficulty in Adjusting Start or End Points Automatically

In cases where several holes or obstacles exist in a machining surface, the generated path will be sectored accordingly. Unfortunately the sequence of the sections is not well-defined.

MPP will try to adjust the sequence automatically, deciding which are the first and the last section in the whole path and then arranging other sections accordingly. However, the result may turn out not to be what users expect, since, for example, they may need a different section as the start or end place.

Name Convention Collision with Robotware Machining FC

In the current version of MPP and RWMFC, different name conventions for some objects are used:

"Departing" target in MPP is called as "Withdraw" target in RWMFC.

"Via" target in MPP is called as "Process" target in RWMFC.

This will be resolved in the next major release from RWMFC side.

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Coordinated MultiMove Programming Not Supported

Programming coordinated MultiMove targets are not directly supported. Users can use RobotStudio basic functionality to access these information.

For independent MultiMove, users can create paths for multi-tasks, open them in PathView and simulate together.

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Installation of Machining PowerPac 5.13

How to Install Machining PowerPac 5.13

Machining PowerPac 5.13 can be installed on an installation of RobotStudio 5.13 with or without a previous installation of Machining PowerPac 5.13. Install Machining PowerPac 5.13 by double-clicking on the file ***Machining PowerPac 5.13.exe*** in the Machining PowerPac installer package.

How to Uninstall Machining PowerPac 5.13

Select to uninstall Machining PowerPac 5.13 from the *Add or Remove Programs* tool of the Windows *Control Panel*.

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