

Cooper App Software Update Guide Cooper CRX Cobots



CONTENTS

CONTENTS	2
Section 1.0: Prerequisites	3
Section 1.1: Cooper App Background Logic STOP	3
Section 1.2: Cooper App Plug-In Uninstall	4
Section 1.3: FANUC App – Cache Clear	5
Section 1.4: Cooper App Plug-In Install	6
Section 1.5: Cooper App Background Logic RUN	7
Section 1.6: IO Setup	10
Section 1.7: Weld Procedure Creation	13
Section 1.8: Cooper App Start	15
Section 1.9: Reload Consumables	16

Section 1.0: Prerequisites

- (1) The robot must have previously been set up with standard IO configuration to support the welder and payload data for the torch.
- (2) The robot must be loaded with FANUC software release V9.40P/50 and Tablet TP Android App Software – V1.27
- (3) The robot must have options R796 (Ascii Program Loader) and R632 (KAREL) authorized and installed. R877 (Thick Plate Weld Pkg) is required if Thru-Arc Seam Tracking will be licensed.

Section 1.1: Cooper App Background Logic STOP

First step in the software update process is to STOP the Cooper App Background Logic to allow for an all-inclusive uninstallation of the older version of the Cooper App.

From the FANUC verbose version of the dropdown navigate to SETUP / BG Logic. From the

BG Logic Screen ensure that IPL_LE_COBOT is highlighted then press the STOP button







Section 1.2: Cooper App Plug-In Uninstall

- 100% 🛄 📒 N TPIF-279 Re ote iP × 7DF5/44 roduction ghts Reserved Setur rporation use constitutes roduct protected Status Utility LUGINS Install 3 TYPE]
- (1) From the FANUC reduced version of the dropdown navigate to PLUGINS -> Plugin List and click on Plugin List.

(2) From the FANUC Plugin List ensure that Cooper_App is highlighted. Scroll down on the page until the Uninstall button is shown. Click on "Uninstall" and then OK on the pop-up to confirm the uninstallation of the Cooper App. Note, the teach pendant will need to be enabled.

Issue Date: February-02-2024



Section 1.3: FANUC App – Cache Clear

From within the FANUC Timeline application swipe the screen from the left to the right to expose the Clear Cache option. Press the Cache Clear button and then OK. Once the cache is cleared the FANUC Timeline application will close and you will be required to restart the FANUC Application.



Section 1.4: Cooper App Plug-In Install

 Insert a USB drive with the file Cooper_App.ipl in it. The Cooper_App.ipl should be at the root level and not located within a folder. It should be named exactly 'Cooper_App.ipl'. If multiple copies of the app have been downloaded i.e. Cooper_App(1).ipl, please rename the file and ensure there are NO spaces in the name. From the FANUC reduced version of the dropdown navigate to PLUGINS ->Install



(2) Verify that you're installing the expected version of the software. Once confirmed press Install -> OK buttons and wait for the install to complete. The installation process will take a few minutes (5 – 10). Once completed you will be presented with a "Plugin software successfully installed!" message.



Section 1.5: Cooper App Background Logic RUN

From the FANUC verbose version of the dropdown navigate to SETUP / BG Logic.
 From the BG Logic Screen press [CHOICE] and double click to select
 IPL_LE_COBOT_FREEHANDTEACH. Select Run to start the program.

:二 🔨 LE_DE>☑ 🚫 100% 🚛 🕥	:= 🕤 LE_DE> 🗖 🚫 100% 📖 📮 🕅	- 451 ↔ 27 ↔ . :== 🖕 LE_PATLONG 🖬 🛛 🔉 100% 🚚	• ۲
		Background learc FILE-067 UD1 Removed	RESI
		Normal mode scan time: 8msec 1/8	
× #		PROGRAM STATUS MODE 1 IPL_LE_COROT_GS R Normal	
successfully!	Successfully!	2 PERFECTPOINT_BO Running Normal 3 Stop Normal	
Undimes and a successfully.	Port Init	4 Stop Normal	
TEST CYCLE	Ovrd Select	5 Stop Normal	
		7 Stop Normal	
MANUAL FCTNS	User Alarm	8 Stop Normal	
ALARM ►	Error Table		
1/0 >	iPendant Setup		
SETUP	BG Logic		
FILE ►	Resume Offset		
USER	Resume Tol.		
SELECT	Weave		
EDIT	Touch Frame		
DATA	Touch I/O		
STATUS ►	Host Comm		
4D GRAPHICS	ZDT EOAT Setup	>IPL_LE_COBOT_GLOBALFREEHANDTEACH	
SYSTEM	FILE >		_
		TT [TYPE] RUN STOP [CHOICE] CLEAR	
USER2	USER	▲ Play ▲ Robot Operation	6

EFAULT		
OME		
NITIAL_TCP	x2	
PL-LE COBOT FREEHANDTEACH		
PL_LE_COBOT_GLOBALFREEHANDTEA	CH	
PL_LE_COBOT_MOVE_TO		
PL_LE_COBOT_SEARCH1DMTN		
PL_LE_COBOT_SEARCHEXTERR		
PL_LE_COBOT_SEARCHVOLTAGEOFF		
PL_LE_COBOT_WELDERCHECK		
PL_LE_COBOT_WIREBRAKE		
FL_LE_COBOT_WIREBRAKEWITHFEED		
e_circlepattern		
		Terrare and the second

≔ 5 ^{LE_DEFA>} 🗛 100%			LE_D)efa>s	- 🔁 I	100%		Ø
Background logic		Backgro	und logic	1				
Normal mode scan time: 8msec PROGRAM STATUS MOD 1 [PL_LE_COBOT_G> 2 Stop Norr 3 Stop Norr 4 Stop Norr 5 Stop Norr 6 Stop Norr 8 Stop Norr 8 Stop Norr 8 Stop Norr 9	1/8 E mal mal mal mal mal	Normal PRC 1 IP 3 4 5 6 7 8	mode sc OGRAM <u>LE_COE</u>	Can time	e: 8m STATUS Running Stop Stop Stop Stop Stop		1/8 MODE Normal Normal Normal Normal Normal Normal	
>IPL_LE_COBOT_GLOBALFREEHANDTEACH		>IPL_LH	E_COBOT_	GLOBALI	FREEHANI	TEACH		
	LEAR		[TYPE]	RUN	STOP	[CHOICE]		

(2) If the user has been licensed for Touch Sensing, select the next available BG Logic slot, press [CHOICE], select IPL_LE_COBOT_SEARCHEXTERR by double clicking it on the list. Click Run to start the program.



(3) Finally, if a wire break torch is being used on the system, select the next available BG Logic slot, press [CHOICE]. If the wire break torch has a button to feed wire, select IPL_LE_COBOT_WIREBREAKWITHFEED by double clicking, otherwise select IPL_LE_COBOT_WIREBREAK by double clicking and Run the program.



Section 1.6: IO Setup



(1) From the FANUC verbose version of the dropdown navigate to IO / INTERCONNECT. Press [SELECT] and choose ES->DO. Disable EMGOP and EMGTP.

(2) From the FANUC verbose version of the dropdown navigate to IO / Weld Ext DO. Set Arc Enable to DO105.

	GRAM_6₽	× 1	00% 🖼 🛌	
	FILE-067 UD	1 Removed		RESET
X J	E			
Norm IN mode ad 1	e: 8	msec	3/8	
UTILITIES	> STATUS	MODE		
TEST OVOLE	Stop	Normal		
	Bunning	Normal		
MANUAL FCTNS	Running	Normal		
ALARM	Running	Normal		
	▼ Stop	Normal		
	Stop	Normal		
Weld	Stop	Normal		
Cell Intface				
Weld Ext DO				
Custom				
Digital				
Analog				
Group				
Robot				
Interconnect				
Link Device				
Flag				
	•			
	•			
USER	ANCIEXTERR			
EDIT			_	
DATA		STOP [CHOICE]	CLEAR	
P	ŧ	Robot O	peration	

SIGNAL INFUT OUTFUT 1 Arc starting 001 001 001 0 2 Arc established 001 001 001 0 3 Arc established 001 001 001 0 4 Meid simulated 001 001 001 0 6 Arc loss 001 001 001 0 7 Nower fault 001 1010 001 001 0 0 Mire fault 001 1010 001 001 0 10 Water fault 001 1010 001 0111 001 011	:=		M_6 ⊠		×	100% 🛄	2 6
3100AL INPUT OUTPUT 1 Are established DOI DOI 3 Are established DOI DOI 4 Meid simulated DOI DOI 5 As faile DOI DOI 7 Power fault DII DII DOI 8 Meid simulated DOI DOI DOI 9 As faile DOI DOI DOI 9 Nore fault DII DII DOI DOI 10 Water fault DII DII DOI DII 10 Water fault DII DII DII DII	WEL	D EXTERNAL OUTPU FILI	E-067 UD'	1 Remove	d		RESET
Star Star 1 Arc starblished D0[0] 2 Arc stablished D0[0] 3 Arc stablished D0[0] 4 Weid simulated D0[0] 5 As failed D0[0] 6 Arc loss D0[0] 7 Power fault D0[10] 9 Wire fault D1[115] 11 Touch detect D1[114] 11 Touch detect D1[114]							3/11
1 Arc extable 2 Arc extable 00 00 3 Arc extable 01 00 5 Asfaile 00 00 5 Asfaile 00 00 6 Arc extable 00 00 5 Asfaile 00 00 7 Power fault 00 00 0 Waid simulated 00 00 1 Basfault 01 116 0 00 0 Wait simulated 00 00 0 Wait simulated 01 116 00 00 0 Wait simulated 01 117 01 111 01 117 01 111 01 111 01 111 01 111 01 111 01 111 <th></th> <th>SIGNAL</th> <th>INPUT</th> <th>ou</th> <th>TPUT</th> <th></th> <th>3/11</th>		SIGNAL	INPUT	ou	TPUT		3/11
1 mor established D0[00] 4 Weild simulated D0[00] 5 M5 failed D0[00] 6 Arc loss D0[00] 7 Power fault D0[10] 9 Mire fault D1[116] 10 Mater fault D1[117] 11 Touch detect D1[114] 12 Mater fault D1[114] 13 Touch detect D1[114] 14 Weil D0[11]	1	Arc starting		** DO[0]		
<pre> 3 Arc enable</pre>	2	Arc established		** DO[01	4	
4 Weil 5 Main 5 Main 5 Main 5 Main 5 Main 5 Main 5 Main 6 Main 5 Main 7 Power fault 5 Main 9 Mire fault 5 Min 10 Mater fault 5 Min 11 Touch detect 5 Min 11 Touch detect 5 Min	3	Arc enable		** DO[105		
5 Af falled 00[0] 6 Afc loss 00[0] 7 Power fault 00[0] 8 Gas fault 01[115] 00[0] 0] 9 Wire fault 01[116] 10 Water fault 01[117] 10 Water fault 01[117] 11 Touch detect 01[114] 00[114] 00[111]	4	Weld simulated	******	** DO[0]		
6 Arc loss	5	AS failed	******	** DOI	0]		
7 Power fault D[115] D0[0] 0] 8 Gas fault D[115] D0[0] 0] 9 Wire fault D[117] D0[0] 0] 10 Water fault D[117] D0[0] 0] 11 Touch detect D[114] D0[111]	6	Arc loss	******	** DO[0]		
8 Gas fault DI [15] DO[0] 9 Wire fault DI [16] DO[0] 10 Water fault DI [17] DO[0] 11 Touch detect DI [14] DO[11] ## (YM)	7	Power fault		** DO[0]		
9 Wire fault DI 116 DO 0 1 10 Water fault DI 117 DO 0 0 11 Touch detect DI 114 DO 111	8	Gas fault	DI[11	5] DO[0]		
10 Water fault D[117] DO[0] 11 Touch detect D[[114] DO[111]	9	Wire fault	DI[11	6] DO[0]		
11 Touch detect DI[114] D0[111]	10	Water fault	DI[11	7] DO[0]		
# (99)	11	Touch detect	DI(11.	4] DO[111]		
# (1996) Q							
HED	1	1 [TYPE]				Q HELP	

(3) From the FANUC verbose version of the dropdown navigate to System / Config. Scroll down to item 33 and set the E-Stop signal to DO104. Cycle power on the robot after completing these changes.

	v. 8	1:54 😳 🖄 🚱
LE_PROGRAM_6	i - C	$\equiv \uparrow^{\text{LE}_{PROGRAM_6}}$ $\gg 100\%$
ERNAL OUTPUFILE-067 UD1 Removed	RESET	System/Config FILE-067 UD1 Removed
INDUT OUTDUT	3/11	22 Simulate ant is P STOP DOLLARS
DOI 01		34 Cat if INDIT SIMULATED DO[0]
IF POI 01		34 Set if OUTPUT SIMULATED DO(0)
DO[109]		36 Sim Input Wait Delaw: 0.00 sec
FCTNS DOI 01		37 Set if Sim Skin Enabled: DO[0]
Dol ol		38 Set when prompt displayed: DO(0)
Loss Dol 01		39 Output when WAIT on Input:<*DETAIL*>
r fault DO[0]		40 Signal if OVERRIDE = 100 DO[0]
Inult DI[115] DO[0]		41 Hand broken : <* GROUPS*>
Exult => DI[116] DO[0]		42 Remote/Local setup: Soft OP panel
Eault DI[117] DO[0]		43 External I/O(ON:Remote):DI [0]
detect: DI[114] DO[111]		44 UOP auto assignment: Simple(JRM18)
		45 Multi Program Selection: TRUE
		46 WAIT at Taught Position: FALSE
		47 Brake control ECO mode: FALSE
		48 J7.J8 jog key Setup : <*DETAIL*>
•		49 Collection name(F1): [STYLE]
		50 Collection name(F2): [COL]
s . 🛌		51 Collection name(F3): [*******]
		52 Collection name(F4): [*******]
		53 Collection name(F5): [******]
		54 Confirmation of TOUCHUP: FALSE
		55 No motion PR operate mode: FALSE
		55 Use No-display Sub-Program: FALSE
		57 Export diagnosis data: <*DETAIL*>
		50 Confirmation for MUTO, DI [0]
		59 Confirmation for AUIO: DI [0]
		61 Allow I/O chg in serve off: TRUE
		62 Prohibit I/O change anytime: FALSE
		ou rioniore 170 change anychie, FALSE
tivest 🔒		III [TYPE]
5.		
A 日間衣 A Robot Operation		▲ Play ▲ Robot Operatio

(4) From the FANUC verbose version of the dropdown navigate to System / Variables.
 Scroll down to \$aweprr. Note: Variables are in alphabetical order. Click 'Detail' twice and scroll down to find the following variables and ensure they are set as follows:
 \$aweprr[1].\$wfs_units = 3 and \$aweprr[1].\$wire_units = 3

	GRAM_30 💦 100% 📼 💭
System/Config SYST-3	20 Contact force exceeds limit 1,1
* #	33/74
UTILITIES	E-STOP DO[104]
TEST OVOLE	ULATED DOI 01
	Delay: 0.00 sec
MANUAL FCTNS	Enabled: DO[0]
ALARM	displayed: DOI 0]
	on Input:<*DETAIL*>
	DE = 100 DOI 01
	<*GEOUPS*>
	IN Remote 1 DT 1 01
USER	ent: Simple(JRM18)
	lection: TRUE
FDIT	m position: FALSE
	0 node: FALSE
DATA	tup : <*DETAIL*>
	F2): COL I
4D GRAPHICS	F3); [******]
EVETEN.	₽4): [*******]
araitm	[F5]: [******]
Clock	TOUCHUP: FALSE
Variables	rate mode: FALSE
OT Release	data: <*DETAIL*>
Avia Limita	iben FWD/BWD: FALSE
Akis Limits	AUTO: DI [0]
	ure: <*DETAIL*>
Motion	n servo-off: TRUE
	inge anytime: FALSE
LICED?	
o suna	
BROWSER	
PLUGINS	
	L A Robot Operation

SYST-320	Contact force excee			RESET
			83/1	036
80 SAWEPOSRAMP	AWEFOSBAMP_T			
81 SAWEPROSEL	[1,8] of AWEP	ROSEL_T		
82 SAWEPRODSTAT	WELD_STAT_T			
83 SAWEPRE	MINUSIAN			
84 SAMEPERS	11.81 OF AMER	CR		
SS DAWERARP	THERAPPLI			
ST RAVESCH	[1 64] of AW	T. HOS		
88 SAWEUPR	AWEUPB_T			
89 SAWEWELDSTAT	WELD_STAT_T			
90 SAWEWIRE	AWEWIRE_T			
91 SAWSCFG	AWSCFG_T			
92 SAWSCOUPLE	[8] of APCOUP	CELT)		
TT [TYPE]	01 02 03	fa [15	seat	UNET
	ferrer ferre fe	10		AUG1
NDM	100000 40000 400		PETR	
i		P 4	din .	
			4 (2 4 (2 4 (2 4 (2 4 (2 4 (2 4 (2 4 (2	
			100 × 10 × 10 × 10	
			S & S & G + 5 + 5 +	
			1 2 5 2 3 7 2 5 2 5 3 5	
			Fa Ba Ba Ba Ba Ba	
			3. Eb 86 62 87. 84 32	
			1 3 B 2 B 2 B 2 B 2 B 2 B 2 B 2 B 2 B 2 B	
			a. 3. 24 24 24 24 24 24 24 24	

CL_TROUCHERSUL Constant force enceeds limit 1: SAMETER [1] SAMETE		LE PROCE	AM 202				-	-	100
BANKINGKI, SVST5200 Contact force exceeds limit 1,1 37/60 SANKINGKI, JANUTA ANDTO.T 37/60 27 SANKINGKI, FANUTA ANDTO.T 37/60 28 SANKINGKI, FANUTA ANDTO.T 37/60 29 SANKINGKI, FANUTA ANDTO.T 3 20 SANKINGKI, ANDTO.T 33 SANKINGKI, ANDTO.T 20 SANKINGKI, ANDTO.T 33 SANKINGKINGKI, ANDTO.T 20 SANKINGKINGKI, ANDTO.T 33 SANKINGKINGKINGKINGKINGKINGKINGKINGKINGKIN	=	J LL_PROOK	AW_50		~	100%		R	È
AMERER(1) 20 ARC. DETECT ANDIO.T 21 GAD.F. ZALLT ANDIO.T 23 WINEL.FAULT ANDIO.T 33 WINEL.FAULT ANDIO.T 33 INFL.ARLT ANDIO.T 33 INFL.ARLT ANDIO.T 33 INFL.INFUT ADDO.T 33 INFL.INFUT ADDO.T 33 INFL.INFLT ANDIO.T 33 INFL.INFLT ANDIO.T 34 INFL.INFLT ANDIO.T 35 INFL.INFLT ANDIO.T 35 INFL.INFLT ANDIO.T 36 INFL.INFLT ANDIO.T 37 INFL.INFLT ANDIO.T 38 INFL.INFLT ANDIO.T 39 INFL.INFLT ANDIO.T 30 INFL.IN		SYST-320	Contact force	exceeds	limit 1,				RES
AMPEREIA) 25 (ARC, DETECT AMDIO.T 25 (ARC, DETECT AMDIO.T 25 (ARC, PATTA AMDIO.T 25 (AMER, PATTA AMDIO.T 26 (AMER, PATTA AMDIO.T 27 (AMER, PATTA AMDIO.T 28 (AMER, P									
24 SARC, DETECT ANDIO.T 25 SARC, DETECT ANDIO.T 28 WINEE, FAULT ANDIO.T 30 SING, ARACE, MADIO.T 31 SING, ARACE, MADIO.T 31 SING, ARACE, BARA, ANDIO.T 31 SING, ARACE, BARA, ANDIO.T 32 SING, ARACE, BARA, ANDIO.T 33 SING, ARACE, BARA, ANDIO.T 34 SING, ARACE, BARA, ANDIO.T 35 SING, ARACE, BARA, ANDIO.T 35 SING, ARACE, BARA, ANDIO.T 35 SING, ARACE, BARA, ANDIO.T 36 SING, ARACE, BARA, ANDIO.T 37 SING, ARACE, BARA, ANDIO.T 38 SING, ARACE, BARA, ANDIO.T 39 SING, ARACE, BARA, ANDIO.T 30 SING, ARACE, BARA, ANDIO.T 30 SING, ARACE, BARA, ANDIO.T 30 SING, ARACE, BARA, ANDIO.T 31 SING, ARACE, BARA, ANDIO.T 31 SING, ARACE, BARA, ANDIO.T 32 SING, ARACE, BARA, ANDIO.T 33 SING, ARACE, BARA, ANDIO.T 34 SING, ARACE, BARA, ANDIO.T 35 SING, ARACE, BARA, ANDIO.T 35 SING, ARACE, BARA, ANDIO.T 35 SING, ARACE, BARA, ANDIO.T 36 SING, ARACE, BARA, ANDIO.T 37 SING, ARACE, BARA, ANDIO.T 38 SING, ARACE, BARA, ANDIO.T 39 SING, ARACE, BARA, ANDIO.T 30 SING, ARACE, BARA, ANDIO.T 30 SING, ARACE, BARA, ANDIO.T	SAWEP	RR[1]					37/6	2	
22 GARA, PARLT ANDEO, T 23 WIRE, PARLT ANDEO, T 24 WIRE, PARLT ANDEO, T 25 WIRE, RAINT ANDEO, T 25 WIRE, RAINT ANDEO, T 26 WIRE, RAINT ANDEO, T 26 WIRE, TARE, BRA ANDEO, T 26 WIRE, THERMO ANDEO, T 26 WIRE, THERMO ANDEO, T 26 WIRE, THERMO ANDEO, T 28 WIRE, JUNITS 29 WIRE, JUNITS 20 W	26 \$.	ARC_DETECT	AWDIO_T						
21 S WILELFAULT ANDIO.T 20 SIVATELFAULT ANDIO.T 31 SINT.ALSE PARA ANDIO.T 32 SINT.LIBUT ANDIO.T 33 SINT.C.ASC PARA ANDIO.T 33 SINT.C.ASC PARA ANDIO.T 33 SINT.C.ASC PARA ANDIO.T 34 SINT.SINTED ANDIO.T 34 SINT.SINTED ANDIO.T 35 SINT.C.ASC PARA ANDIO.T 35 SINT.C.ASC PARA ANDIO.T 36 SINT.SINTED ANDIO.T 37 SINT.SINTED ANDIO.T 38 SINT.C.ASC PARA ANDIO.T 39 SINT.C.ASC PARA ANDIO.T 39 SINT.SINTED ANDIO.T 30 SINT.C.ASC PARA ANDIO.T 39 SINT.C.ASC PARA ANDIO.T 30 SINT.C.ASC PARA ANDIO.T 30 SINT.C.ASC PARA ANDIO.T 30 SINT.SINT.SINT.SINT.SINT.SINT.SINT.SINT.	27 \$	GAS_FAULT	AWDIO_T						
22 MARELPART ANDED.T 33 SHER, ANDEL SAN 34 SHER, ANDEL SAN 35 SHER, ANDEL SAN 35 SHER, ANDEL SAN 36 SHER, THORNO ANDED.T 35 SHER, THORNO AND	28 5	WIRE_FAULT	AWDIO_T						
19 STRUE, JARUET ANDEOL, T. 31 STRUE, JARUET ANDEOL, T. 33 STRUE, JARUET ANDEOL, T. 33 STRUE, JARUET ANDEOL, T. 34 STRUE, JARUET ANDEOL, T. 35 STRUE, JARUET ANDEOL, T. 35 STRUE, JARUET ANDEOL, T. 36 STRUE, JARUET ANDEOL, T. 37 STRUE, JARUET ANDEOL, T. 38 STRUE, JARUET ANDEOL, T. 38 STRUE, JARUET ANDEOL, T. 39 STRUET ANDEOL, T. 30 STRUE, JARUET ANDEOL, T. 30 STRUET, JARUET ANDEOL, T. 30 STRUET ANDEOL, T. 30 STR	29 8	WATER_FAULT	AWDIO_T						
	30 \$	PWR. FAULT	AWDIO_T						
32 SVETCSUPUT APDIOT 34 SVETCSUPUT APDIOT 35 SVETCSUPUT APDIOT 35 SVETCSUPUT APDIOT 35 SVETCSUPUT APDIOT 35 SVETCSUPUT APDIOT 36 SVETCSUPUT APDIOT 37 SVETCSUPUT APDIOT 38 SVETCSUPUT APDIOT 39 SVETCSUPUT APDIOT 30 SVETCSUPUT APDIOT 30 SVETCSUPUT APDIOT 30 SVETCSUPUT APDIOT 30 SVETCSUPUT APDIOT 31 SVETCSUPUT APDIOT 32 SVETCSUPUT APDIOT 33 SVETCSUPUT APDIOT 34 SVETCSUPUT APDIOT 35 SVETCSUPUT APDIOT 34 SVETCSUPUT APDIOT 35 SVETCSUPUT APDIOT 35 SVETCSUPUT APDIOT 36 SVETCSUPUT APDIOT 37 SVETCSUPUT APDIOT 38 SVETCSUPUT APDIOT 39 SVET	31 \$	RMT_ARC_ENA	AWDIO_T						
33 SINT. CAS AND AND C. T. 34 SINT. TROUM NOT C. T. 35 SINT. TROUM NO AND C. T. 35 SINT. TROUM NO AND C. T. 35 SINT. SINT S. 37 SINT S. 38 SINT S. SINT S. 39 SINT S. 39 SINT S. 30 SINT S	32 \$	WSTK_INPUT	AWDIO_T						
34 BINT, INCHTWO ADDO,T 35 BINT, INCHTWO ADDO,T 36 BINT, INCHTWO ADDO,T 37 BINT, INCHTWO ADDO,T 38 BINT, INCHTWO ADDO,T 39 BINT, INCHTWO ADDO,T 38 BINT, INCHTWO ADDO,T 39 BINT, INCHTWO ADDO,T 30 BINT, INCHTWO ADDO,T 31 BINT, INCHTWO ADDO,T 32 BINT, INCHTWO ADDO,T 33 BINT, INCHTWO ADDO,T 34 BINT, INCHTWO ADDO,T 35 BINT, INCHTWO ADDO,T 36 BINT, INCHTWO ADDO,T 37 BINT, INCHTWO ADDO,T 38 BINT, INCHTWO ADDO,T 3	33 \$	EMT_GAS	AWDIO_T						
34 SHET, THORNO ADDLO,T 35 SHET, THORNO ADDLO,T 35 SHETE, THORN 36 SHETE, THORN 36 SHETE, THORNO 36 SHETE, THO	34 5	RMT_INCHFWD	AWDIO_T						
30 MIRLETTER 201 31 MIRLETTER 201 32 MIRLETTER 201 33 MIRLETTER -045	35 8	EMT_INCHBWD	AWDIG_T						
AT AVES, UNITS 38 INTER-DIA	36 \$	WIRE_TYPE	261	_	_				
A TYTELDIA .045	37 5	WFS_UNITS	3						
	38.5	WIRE_DIA	.045						
		[TYPE]							
		SHIFT MIN	п п	F3 F4	n	NOT RETN		IIFT.	
		(i)	200 TT 100	31128	un .	in)			
		SECTOR N		HOLD	1.021	im			
		1.10		110	4	15			
		414CT							
		7	8 9 971		640	Ling			
			-	COORD	-	12			
1 2 3 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0			کا لیے بین						
			2 3 ****	Cinc.	LAY	(10)			
					im	100			
A Play		Canal I		(10000)	- 10				
A Play A Robot Operation		HILP	NODE 1 NO STATU		1.00	(4)			
		+ Play			Dohot	Operati			1



Select 'Prev' twice and navigate to \$awspcr. Click 'Detail' and scroll to find the following variable and ensure it is set as follows: \$awspcr.\$def_spduni = 3





Section 1.7: Weld Procedure Creation

(1) From the FANUC verbose version of the dropdown navigate to Browser/Weld Procedure and select Add WP.



(2) Set the Weld Procedure No to '90' then click the next arrow.

≔ ?"	FROGRAM_I	2014			A 100	% [uni	
Weld Procedure							
Create new	Weld Proced	lure					
Set each item	of the newly	created welding	g data.				
	W	Aeld Procedure	No. :	90			
	с	omment	-				
				L.			
					1 /3	>	X
	TYPE]	63 BACK	(3) FORWARD	REFRESH	P. Nove		>

(3) Click 'Select Weld Mode' and select the tab 'Enter the No directly'. Enter the Mode No as 13 then click 'Select'. Click the next arrow to move to the last step.





(4) Click the checkmark to create the weld procedure.

Section 1.8: Cooper App Start

From the FANUC reduced version of the dropdown navigate to PLUGINS and click on the Cooper_App plugin to start the application. This will initiate the start-up process and present you with the Cooper App.



Section 1.9: Reload Consumables

Navigate to Settings -> Setup Consumables. Hit 'Clear Selections' and the reselect the appropriate Wire-Type, Wire-Size, and Gas being used with the system. Once selected, click 'OK'. This process will take approximate 10 minutes.

