System and Error Messages

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1 Operational error messages

10002: Program reset2:Program reset
The task %!%!%s has
been rewound to its start point.

10005:Program stopped
The task %!%!%s has
stopped. The reason is that
%s

10007:Program started
The task %!%!%s has
start to execute.
%s

10008:Program restarted
The task %!%!%s has
restart to execute.
%s

10009:Work memory full
No memory left for new RAPID
instructions or data.
The task is %!%!%s
Check:
Save the program and then
restart.

10010:Motors off state

10011:Motors on state

10012:Guard stop state
Runchain opened by any safety guard
except the emergency stop.
Check:
Close runchain, it could be broken
by the following devices (if used):
Access gate, light screen, servo
disconnector or any other safety
device connected to the run chain.

10013:Emergency stop state
Runchain opened by emergency stop.
Em stop reset is required.
Use the motors off button.

10014:System failure state
Fatal non recoverable system error.
Warm start is required.

10015:Manual mode selected

10016:Automatic mode requested

10017:Automatic mode confirmed

10018:Manual mode FS requested
Manual mode with full speed requested

10019:Manual mode FS confirmed
Manual mode with full speed con-
firmed

10020:Execution error state
The program execution has reached
a spontaneous error state

10021:Execution error reset
The program execution has left
a spontaneous error state

10022:Hold to run waiting
Waiting for hold to run button to be
pressed on the programming unit.

10023:Hold to run timeout
The hold to run button on the
programming unit must be pressed
within timeout limit.

10024:Collision triggered
A collision has been detected.

10025:Collision resetted
The collision detection has
been resetted.

10026:Collision confirmed
Returned to the path after
a collision detection.

10027:Collision not confirmed
The system has not returned
to the path after a collision
detection.

System and Error Messages

10030:All axes commutated

10031:All axes calibrated

10032:All rev counters updated

10033:All axes synchronized

10034:Axis not commutated

10035:Axis not calibrated

10036:Rev counter not updated

10037:Axis not synchronized

10040:Program loaded
The task %!%!%s has
loaded a program or program module.
The free user space was %i bytes
before this operation and
%i bytes after.
Check:
Note! 1 Kbyte = 1024 bytes.

10041:Program erased
The task %!%!%s has
erased a program.

10043:Restart failed
The task %!%!%s
can't restart

10044:Program Pointer updated
The task %!%!%s
could have changed the PP pos.

10045:System restarted
An already installed system
was restarted.

10046:System restarted in cold
mode
First start after installation.

10047:Background task %s
refuse to start
%s

10049:Protected area not finish
A power fail did occur in the
middle of a protected area for
the task %!%s
%s

10050:Execution cancelled
The restart will clear the execution
in task %!%.16s of a
%s

10051:Event routine error
The task %!%s could not start
the specified system event routine
%s
The routine is either unknown to
the system or unlinkable.
Check:
Insert the routine in a system
module or correct the program.

10052:Regain start
A regain movement has started

10053:Regain ready
The regain movement is ready

10054:Regain rejected
Regain on path not possible one client
has already order it.
Check:
A new regain movement is ordered during
an already started regain movement.
Reduce the number of start order from
e.g system I/O

10060:Test of enable chain
The enable chain is always tested at
startup. If the test failed an error
message concerning enable will follow.
Check:
If enable chain test at startup failed
the related error message will be
"Enable chain timeout"

10070:Backup step ready
The backup %!%s is ready

10071:Backup error
Error during the backup
of %!%!%s
%s
Check:
%s

10072:Restore step ready
The restore %!%s
is ready

10073:Restore error
Error during the restore
of %!%!%s
%s
Check:
%s

10074:NFS server up
The connection to the NFS server
'%s' is working.
All devices remotely mounted from
this server are now available.

10075:NFS server down
The connection to the NFS server
'%s' has been lost.
All devices remotely mounted from
this server are unavailable.

10076:FTP server up
The connection to the FTP server
'%s' is working.

10077:FTP server down
The connection to the FTP server
'%s' has been lost.

10080:Background task %s
has an older version of a module
installed than the source
%s
Check:
Restart the system with a P-START
to install the newer version

10081:Background task %s
failed to load a newer version of a
module The source of the module is
%s
Check:
See previous messages for the cause
Or restart the system with a P-START
to load the newer version

10082:RAPID Task supervision
Task %s is not running
the system will be set in SysFail
state. It's now impossible to change
to motors on
%s
Check:
See previous messages for the cause
Restart the system to reset the
error state

10083:RAPID Task supervision
Task %s is not running
the system will be set in motors off
state.
%s
Check:
See previous messages for the cause

10084:RAPID Task supervision
Task %s is not running
the main task will also stop
%s
Check:
See previous messages for the cause

10085:RAPID Task supervision
Task %s can't be stopped
the trustLevel is set to
a safety level.
Check:
If the task should be possible to stop
change the trustLevel or task
type in the system parameters.

10086:Robot is purged OK
Purging pressure regained after a purge
fault.

10087:Purge state: %s.
State changed.

2 System error messages

20010:Em stop state active
Em stop reset is required.
Press the panel button.

20011:Em stop state active
Em stop reset is required.
First release the Em stop button
and then press the panel button.

20012:Sys failure state active
Fatal non recoverable system error.
Warm start is required.
Check:
Switch the mains switch off and on
again if the soft restart command is
ignored or not possible to reach.

20024:Enable chain timeout
Two channel status timeout.
Check:
The acknowledgement for a two chan-
nel
enable chain status change was not
received within the expected time.

20025:Stop order timeout
The stop order was carried out
as a forced guard stop when
no acknowledgement was received
within the expected time

20030:Axis not commutated
One or several internal drive unit
axes are not commutated.

20031:Axis not calibrated
One or several absolute/relative
measurement axes are not calibrated.

20032:Rev counter not updated
One or several absolute measurement
axes are not synchronized.
Move the robot to the sync position
and update the revolution counters.

20033:Axis not synchronized
One or several relative measurement
axes are not synchronized.
Order Motors On and synchronize all
mechanical units in the list.

20050:Not allowed command
Not allowed in this operating mode.

20051:Not allowed command
Not allowed when client not in control
of the resource (program/motion).

20052:Not allowed command
Not allowed in this cabinet state.

20053:Not allowed command
Not allowed in this manipulator state.

20054:Not allowed command
Not allowed when program is executing.

20060:Not allowed command
Not allowed in Auto mode.

20061:Not allowed command
Not allowed when changing to Auto
mode.

20062:Not allowed command
Not allowed in Manual mode.

20063:Not allowed command
Not allowed in Manual full speed mode.

20064:Not allowed command
Not allowed when changing to Manual
full speed mode.

20070:Not allowed command
Not allowed in Motors On state.

20071:Not allowed command
Not allowed while changing to
Motors On state.200

20072:Not allowed command
Not allowed in Motors Off state.

20073:Not allowed command
Not allowed while changing to
Motors Off state.

20074:Not allowed command
Not allowed in Guard Stop state.

20075:Not allowed command
Not allowed in Emergency Stop state.
Em stop reset is required.
Press the panel button.

20076:Not allowed command
Not allowed in System Failure state.
Fatal non recoverable system error.
Warm start is required.
Check:
Switch the mains switch off and on
again if the soft restart command is
ignored or not possible to reach.

20080:Not allowed command
Not allowed when axis is not commutated.

20081:Not allowed command
Not allowed when axis is not calibrated.

20082:Not allowed command
Not allowed when axis rev counter is not
updated.

20083:Not allowed command
Not allowed when axis is not
synchronized.

20092:Not allowed command
Not allowed in state
System IO Start Blocked.

20100:Teachpendant in ctrl
A teachpendant application
is in control of the requested
resource (program/motion)

20101:Teachp (prg) in ctrl
The teachpendant programming
window has focus and is in control
of the program server.
Change to the production window
and perform the command again.

20102:Teachp (joystick) in ctrl
The teachpendant joystick is in
control of the motion server.
Release the joystick and perform
the command again.

20111:Teachp (prg) in ctrl
The teachpendant programming
window has focus and is in control
of the program server.
Change to the production window
and perform the command again.

20112:Program 1 in ctrl
The program server 1 is in
control of the motion server.
Stop the program and perform
the command again.

20113:Program 2 in ctrl
The program server 2 is
in control of the motion server.
Stop the program and perform
the command again.

20114:Program 3 in ctrl
The program server 3 is
in control of the motion server.
Stop the program and perform
the command again.

20115:Program 4 in ctrl
The program server 4 is
in control of the motion server.
Stop the program and perform
the command again.

20116:Program 5 in ctrl
The program server 5 is
in control of the motion server.
Stop the program and perform
the command again.

20120:System IO in ctrl

20125:Client %s in ctrl
Specified client is in
control of the requested
resource (program/motion)

20130:Out of memory in cfg

20131:Unable to read file

20132:Parameters not saved
Parameters cannot be saved.
Probably, because disk is write
protected or no space available.
Check:
Check if disk is write-protected or
if space on disk is enough.

System and Error Messages

20133:Cannot modify instance
Description\Reason:
Can't replace instance in line %d
of file %s
Check:
The instance is write protected.

20134:Wrong version
Description\Reason:
The cfg domain version is wrong in file
%s
The software is made for
version %s
Check:
Change the version of the cfg domain.

20135:Line too long
Description\Reason:
Line %d > %d characters
Check:
Reduce the number of characters.

20136:Attr out of range
Description\Reason:
Attribute %s is out of range
in line %d
Check:
Change the value on the attribute.

20137:Dublicate inst name
Description\Reason:
Dublicate name in line %d
of file %s
Check:
Change the name.

20140:Motors On rejected.
Motors On via System IO
not allowed.

20141:Motors Off rejected.
Motors Off via System IO
not allowed.

20142:Start rejected.
Start/restart of program via System
IO not allowed.
Check:
The reason could be that the robot
is outside of regain distance.

20143:Start main rejected.
Start of main program via System IO
not allowed.

20144:Stop rejected.
Stop of program via System IO
not allowed.

20145:Stop cycle rejected.
Stop of program cycle via System IO
not allowed.

20146:Man interrupt rejected.
Manual interrupt of program via
System IO not allowed.

20147:Load and start rejected.
Load and start of program via
System IO not allowed.
Program file name (including mass
memory unit) to be loaded must
be defined.

20148:Confirm rejected.
Emergency Stop Reset Confirm via
System IO not allowed.

20149:Error reset rejected.
Program execution error reset via
System IO not allowed.

20150:Syncronization rejected.
Syncronization of mechanical unit
via System IO not allowed.

20151:Faulty signal name.
Signal name not possible to
subscribe to for Sysio.
The Signal name might not be in
the cfg-file for Sysio.

20152:Too many restrictions.
For an action (signal) in
Sysio, no restrictions are set.
The total number of restrictions
(signals) for an action in the
cfg-file for Sysio are too high.

20153:Mot. On, Start rejected.
Motors On, Start/restart of program
via System IO not allowed.
Check:
The reason could be that the robot
is outside of regain distance.

20154:Stop instr. rejected.
Stop of program instruction via
System IO not allowed.

20155:Undefined Argument
SyncExtAx mechanical_unit_name
is not defined

20156:Undefined Argument
Interrupt routine_name
is not defined

20157:Undefined Argument
LoadStart program_name
is not defined

20158:No System Input signal
A system input has been declared to
a signal that doesnt exist.

20159:No System Output signal
A system output has been declared to
a signal that doesnt exist.

20160:Not in configuration
The system module %!%s in task
%s has no corresponding
specification in the configuration
for "Task modules"
Check:
View "Task modules" in the "System
Parameter" menu and add an item for
this system module

20161:Path not find
The system module %!%s in task
%s has a corresponding
specification in the configuration
for "Task modules" that point out
a non existing file path
Check:
View "Task modules" in the "System
Parameter" menu and change the path
in the item for this system module

20162:Write error
A write error occur when the system try
to save the system module %!%.14s
at %.37s
in task %.16s. Or the file
system was full
Check:
View "Task modules" in the "System
Parameter" menu and change the path
in the item for this system module

20163:Reconfig failed
Some user module(s) changed but not
saved. See previous warnings stored
in the log.
Check:
Save those modules that are specified
by earlier warnings and try another
system start.

20164:Reconfig failed
There are still some unsaved system
module
Check:
Read error descriptions in earlier
messages.
Try another system start

20165:PP lost!
Restart is no longer possible from
current position. The program has to be
started from the beginning.

20166:Refuse to save module
The module %!%.14s
is older than the source
at %.37s
in task %.16s.

20167:Unsaved module
The module %!%.14s
is changed but not saved
in task %.16s.

20170:SYS_STOP
Program motion stopped along path.

20171:SYS_HALT
Program and motion stopped with
motors off.

20172:SYS_FAIL
System Failure, restart system.

20175:Teachpendant fail
Teachpendant lost contact
this will force Guard Stop

20180:System IO restriction
System IO restrictions are active for
other clients, e.g. teach pendant or
computer link.
Check:
Motor on is restricted by System IO
MotorOff.
Program start is restricted by
System IO Stop, StopCycle or StopInstr.

20181:System Reset rejected.
System Reset via System IO
not allowed.

20182:Quick Stop rejected.
Quick Stop via System IO
not allowed.

20183:Stiff Stop rejected.
Stiff Stop via System IO
not allowed.

20184:Incorrect Argument
An undefined Start Mode has been
declared for System IO.

20185:Incorrect Name
An undefined Name has been declared
in current runchn_bool configuration.

20201:Limit Switch open

20202:Emergency Stop open

20203:Enabling Device open

20204:Operation Key open

20205:Auto Stop open

20206:General Stop open

20207:Backplane Enable open
Check:
1. Check other error messages for
primary fault reason.
2. If no other error messages,
please check line voltage for
one phase missing.

20208:Chain switches open
One or many switches in chain open.

20209:External Contactor open

20210:Motor Contactor open

20211:Two channel fault
Enable from backplane was not allowed
to be closed.
Runchain two channel fault has not
been reset.
Check:
First open both channels and then close
them again to reset runchain.
Please check the safety guard that
caused the status conflict.

20212:Two channel fault
Runchain was not allowed
to be closed.
Runchain two channel fault has not
been reset.
Check:
First open both channels and then close
them again to reset runchain.
Please check the safety guard that
caused the status conflict.

20213:Two channel fault
Runchain two channel fault has not
been reset.
Check:
First open both channels and then close
them again to reset runchain.
Please check the safety guard that
caused the status conflict.

20221:Chain conflict
Status conflict
for one or many switches in chain.
Check:
Please check the two channel safety
guard that caused the status conflict.

20222:Limit Switch conflict
Status conflict
for the Limit Switch chain.
Check:
Please check the two channel safety
guard that caused the status conflict.

20223:Emergency Stop conflict
Status conflict
for the Emergency Stop chain.
Check:
Please check the two channel safety
guard that caused the status conflict.

20224:Enabling Device conflict
Status conflict
for the Enabling Device chain.
Check:
Please check the two channel safety
guard that caused the status conflict.

20225:Auto Stop conflict
Status conflict
for the Auto Stop chain.
Check:
Please check the two channel safety
guard that caused the status conflict.

20226:General Stop conflict
Status conflict
for the General Stop chain.
Check:
Please check the two channel safety
guard that caused the status conflict.

20227:Motor Contactor conflict
Status conflict
for the Motor Contactor chain.
Check:
Please check the two channel safety
guard that caused the status conflict.

20228:Ordered ES conflict
Status conflict
between ordered and configured type of
Emergency Stop Turn Off (immediate or
delayed).
Check:
Replace Panel Board.

20229:Ordered AS conflict
Status conflict
between ordered and configured type of
Auto Stop Turn Off (immediate or
delayed).
Check:
Replace Panel Board.

20230:Ordered GS conflict
Status conflict
between ordered and configured type of
General Stop Turn Off (immediate or
delayed).
Check:
Replace Panel Board.

20231:Delayed ES conflict
Status conflict
between ES1 and CH1 or ES2 and CH2
after a delayed Emergency Stop.
Check:
Replace Panel Board.

20232:Delayed AS conflict
Status conflict
between AS1 and CH1 or AS2 and CH2
after a delayed Auto Stop.
Check:
Replace Panel Board.

20233:Delayed GS conflict
Status conflict
between GS1 and CH1 or GS2 and CH2
after a delayed General Stop.
Check:
Replace Panel Board.

20234:Immediate ES conflict
Status conflict
between ES1 and CH1 or ES2 and CH2
after an immediate Emergency Stop.
Check:
Replace Panel Board.

System and Error Messages

20235:Immediate AS conflict
Status conflict
between AS1 and CH1 or AS2 and CH2
after an immediate Auto Stop.
Check:
Replace Panel Board.

20236:Immediate GS conflict
Status conflict
between GS1 and CH1 or GS2 and CH2
after an immediate General Stop.
Check:
Replace Panel Board.

20241:Key speed status fault
Status conflict
for the operating mode key signals
and the speed signal.
Check:
Check operating mode key hardware
or replace Panel Board.

20242:Auto mode conflict
Status conflict
for the operating mode key signals
in Auto operation.
Check:
Check operating mode key hardware
or replace Panel Board.

20243:Manual mode conflict
Status conflict
for the operating mode key signals
in Manual operation.
Check:
Check operating mode key hardware
or replace Panel Board.

20244:Manual FS mode conflict
Status conflict
for the operating mode key signals
in Manual Full Speed operation.
Check:
Check operating mode key hardware
or replace Panel Board.

20251:Transformer temp. high
Status active for over temperatur
in main transformer.
Make sure to let the transformer cool
down before ordering Motors On again.
Check:
View Safety in the IO window and wait
until the signal TRFOTMP equals 0
before ordering Motors On again.

20252:Motor temp. high
Status active
for over temperature in
motors of manipulator.
Make sure to let the Motors cool down
before ordering Motors On again.
Check:
View Safety in the IO window and wait
until the signal PTC equals 0 before
ordering Motors On again.

20253:Ext. device temp. high
Status active
for over temperature in
external device.
Make sure to let the Motors cool down
before ordering Motors On again.
Check:
View Safety in the IO window and wait
until the signal PTCEXT equals 0 before
ordering Motors On again.

20254:Power supply fan stopped
Status active
when fan in power supply not running.
Check:
Check the power supply fan hardware.

20255:Panel Board voltage low
Status active
when Panel Board 24 V failed.
Check:
Check the Panel Board voltage.

20260:Run control status fault
Status conflict between
motor contactors and run control.
Check:
Replace Panel Board.

20261:Strings to long
Description\Reason:
- Elog message number %d:
  Total String length %d >
  %d characters
Check:
1. Reduce the total string length.

20270:Access error
Panel Module access error.
Check:
Examine your EIO configuration files.

20280:Symbol conflict
The signal %s defined in the IO
configuration conflict with another
program symbol with the same name.
Due on that fact the signal will not be
mapped to a program variable.
Check:
Rename the signal in
the IO configuration.

20301:Fan stopped
Status active when
drive unit fan 1 not running.
Check:
Check drive unit fan 1 hardware.

20302:Fan stopped
Status active when
drive unit fan 2 not running.
Check:
Check drive unit fan 2 hardware.

20303:Fan stopped
Status active when
drive unit fan 3 not running.
Check:
Check drive unit fan 3 hardware.

20304:Fan stopped
Status active when
drive unit fan 4 not running.
Check:
Check drive unit fan 4 hardware.

20305:Fan stopped
Status active when
computer system fan 1 not running.
Check:
Check computer system fan 1 hardware.

20306:Fan stopped
Status active when
computer system fan 2 not running.
Check:
Check computer system fan 2 hardware.

20311:Enable 1 open
Status active when
enable from I/O Computer open.
Check:
1. Check other error messages for
primary fault reason.
2. If no other error messages,
please check line voltage for
one phase missing.

20312:Enable 2 open
Status active when
enable from Axis Computer open.
Check:
1. Check other error messages for
primary fault reason.
2. If no other error messages,
please check line voltage for
one phase missing.

20313:IOC EN Supervision fault
Supervision of the IO Computer ENABLE
signal has detected an error.The ENABLE
signal path is broken.
Check:
1. Check other error messages for
possible stop reasons.
2. Check cables(Panel Board - IO Comp)
3. Replace IO Computer, Panel board, or
Connector board.

20314:AXC EN Supervision fault

Supervision of the Axis Computer ENABLE signal has detected an error.The ENABLE signal path is broken.
Check:
1. Check other error messages for possible stop reasons.
2. Check cables(Panel Board - AX Comp)
3. Replace AX Computer, Panel board, or Connector board.

20320:SoftStop

SoftStop has been detected on channel %.0f.
Check:
Em button has been pressed with SoftStop activated. This will open runchain. Make sure the Em button is reset and press the panel button.

20501:HW Motor On relay open

The HW Motor On relay opens when Emergency Stop, General Stop or Enable Chain fault occurs, and opens also when Motor Off push button is pressed.
Check:
The HW Motor On relay can be closed by pressing the Motor On push button or by activating HW signal ExtEmyReset.

20502:Soft-start relay open

The Soft-start relay (KM3) should be closed when the brakes are released.
Check:
Check relay KM3.

20551:Purge system fault

Status active
when system not purged OK:
1. Pressure too low.
2. Pressure too high.
3. High flow on.
Check:
1. Check other error messages for primary fault reason.
2. If no other error messages, check purge unit and air supply, and search for leaks in the purge system.

20552:Manipulator fault

Status active
when power to manipulator is lost, or manipulator's enable chain conditions is not OK.
Check:
1. Check the power to the manipulator.
2. Check that the enable chain on MCOB is OK.

20553:ACA SW module not OK

Status active
when ACA software module is not OK, or communication with AMA is down.
Check:
1. Check that the ACA SW is running.
2. Check the communication towards AMA.
3. Check that the AMA SW is running.

20554:Collition sensor active

Status active
when digital collition sensor on CMB is active.
Check:
Check the collition sensors connected to CMB.

20555:Collition sensor active

Status active
when digital collition sensor on MCOB is active.
Check:
Check the collition sensors connected to MCOB.

3 Hardware error messages

31114:Bus error

Bus error when accessing LED on main computer
Check:
1. Replace main computer board
2. Replace robot computer board

31133:Overflow serial channel 2

Check:
1. Check communication parameters
2. Replace robot computer board

31138:Overflow serial console
Check:
1. Check communication parameters
2. Replace robot computer board

31142:Error in tpu channel
Received data not equal to transmitted data
Check:
1. Check communication parameters
2. Replace robot computer board

31203:Floppy Disk Error
Bad floppy disk or not formatted
Check:
1. Repeat attempt
2. Change disk
3. Check floppy drive cables

31206:Floppy Disk Error
Bad floppy disk or internal error
Check:
1. Check the floppy drive
2. Change disk
3. Restart the system

31207:Floppy Disk Error
No floppy disk or disk not ready
Check:
1. Repeat attempt

31210:Floppy Disk Error
Invalid format
Check:
1. Change disk

31211:Floppy Disk Error
Data transfer error to/from floppy
Check:
1. Repeat attempt
2. Change disk
3. Restart the system

31214:Floppy Disk Error
Data transfer was interrupted
Check:
1. Repeat attempt
2. Restart the system

31215:Floppy Disk Error
Internal command invalid
Check:
1. Repeat attempt
2. Restart the system

31216:Floppy Disk Error
Floppy disk was moved during tranfer
Check:
1. Repeat attempt
2. Restart the system

31217:Floppy Disk Error
Bad floppy disk or floppy device
Check:
1. Repeat attempt
2. Change Disk
3. Restart the system

31219:Floppy Disk Error
Floppy device not ready
Check:
1. Repeat attempt
2. Restart the system

31220:Floppy Disk Error
Bad floppy disk or internal error
Check:
1. Repeat attempt
2. Change Disk
3. Restart the system

31221:Floppy Disk Error
Data error
Check:
1. Repeat attempt
2. Change Disk
3. Restart the system

31222:Floppy Disk Error
Internal error - Overrun
Check:
1. Repeat attempt
2. Restart the system

System and Error Messages

31223:Floppy Disk Error
Bad floppy or internal error
Check:
1. Repeat attempt
2. Change Disk
3. Restart the system

31224:Floppy Disk Error
Floppy write protected
Check:
1. Remove write protection

31225:Floppy Disk Error
Bad Floppy - Address mark missing
Check:
1. Change Disk

31226:Floppy Disk Error
Bad data on floppy
Check:
1. Change Disk

31227:Floppy Disk Error
Bad floppy - Missing cylinder
Check:
1. Change Disk

31228:Floppy Disk Error
Bad floppy - Bad cylinder
Check:
1. Change Disk

31229:Floppy Disk Error
Bad floppy - Bad address mark in data
Check:
1. Change Disk

31401:DMA error
DMA transfer error in ROBOT COMPUTER
Check:
Replace robot computer board

31402:DMA error
DMA transfer error in ROBOT COMPUTER
Check:
Replace robot computer board

31403:DMA error
DMA transfer error in ROBOT COMPUTER
Check:
Replace robot computer board

31404:DMA error
DMA transfer error in ROBOT COMPUTER
Check:
Replace robot computer board

31408:Axis computer error
Check:
Replace robot computer board

31409:Robot computer error
Check:
Replace robot computer board

31410:Axis computer error
Check:
Replace robot computer board

31411:Axis computer error
Check:
Replace robot computer board

31414:Main computer error
Check:
1. Replace main computer board
2. Replace robot computer board

31415:Main computer error
Check:
Replace main computer board

31418:DMA transfer error
DMA transfer error in ROBOT COMPUTER
Check:
Replace robot computer board

31419:DMA transfer error
DMA transfer error in ROBOT COMPUTER
Check:
Replace robot computer board

31420:DMA transfer error
DMA transfer error in ROBOT COMPUTER
Check:
Replace robot computer board

31605:Memory error IO-computer
Check:
Replace robot computer board

32247:Mailbox 1 interrupt error
Mailbox 1 interrupt error on
IO computer
Check:
Replace robot computer board

32248:Mailbox 2 interrupt error
Mailbox 2 interrupt error on
IO computer
Check:
Replace robot computer board

32301:Memory error MAIN COMP.
Check:
Replace main computer board

32302:Memory error MAIN COMP.
Check:
Replace main computer board

32303:Memory error MAIN COMP.
Check:
Replace main computer board

33150:Axis Computer Int Error
Axis computer was stopped with
hw interrupt due to interrupt error
Check:
Reload system
Replace robot computer board

33158:Axis Comp Driver Clk fail
Axis computer driver clock failure
Main computer is not responding on
request
Check:
Reload system
Replace main computer board

33159:Manual Mode Speed Warning
Manual mode speed exceeded for
joint %s.
Check:
Check for correct load mass definition
Check controller parameters on external
axes
Check for robot singularity
Replace drive unit

33201:Axis cpu Read Error
Error in reading from axis computer
driver. Axis computer driver did not
return correct number of bytes.
Check:
Check system configuration
Reload system
Replace robot computer board

33202:Axis cpu Write Error
Error in writing to the axis computer
driver. Axis computer driver did not
return correct number of bytes.
Check:
Check system configuration
Reload system
Replace robot computer board

33203:Axis cpu ioctl Error
Error in ioctl to the axis computer
driver.
Fail to execute ioctl command
Check:
Restart system
Reload system
Replace robot computer board

33210:Feedback Position Error
Driver failed to read feedback position
on joint %s
Check:
Restart system
Replace main computer board

33211:Position Control Underrun
Unable to complete position control in
the allowed time
Check:
Reload system
Check noise level on I/O connections

System and Error Messages

33212:DMA Time out Error
DMA access failed from main computer to
axis computer
Check:
Reload system
Replace main computer board and
axis computer board

33213:DMA Operation Error
DMA Control Operation failed from Main
computer to Axis computer
Check:
Reload system
Replace main computer board and
axis computer board

33214:Float number error
Illegal references sent from Main
computer to Axis computer for joint %.f
Check:
Reload system
Check system parameters

33220:Axis computer failure
Axis computer has returned an error code
indicating hardware failure
Check:
Reload system
Replace robot computer board

33302:Error in axis computer
Axis computer was not able to
deactivate VME signal SYSFAIL
Check:
Replace robot computer board

33303:Error in axis computer
Axis computer was not able to
activate VME signal SYSFAIL
Check:
Replace robot computer board

33304:Error in axis computer
Check:
Replace robot computer board

33311:Axis computer
Current ref. loopback error
Check:
Replace robot computer board

33312:Axis computer error
RUNNING/DRVFLT signal error
Check:
1. Replace robot computer board
2. Check drive system boards

33314:Axis computer error
Check:
Replace robot computer board

33315:Axis computer error
Check:
Replace robot computer board

33316:Axis comp err loopb comm.
Axis computer error loopback
comm. error.
Check:
Replace Axis Computer board

33401:Over writing mea. system
Over writing of output data to
measurement system %d,
connector board %d.
Check:
Reload system
Replace Axis Computer board
Replace measure board

33402:Over writing drive sys.
Over writing of output data to
drive system %d,
connector board %d.
Check:
Reload system
Replace Axis Computer board
Replace drive unit

33403:Over writing mea. system
Over writing of input data from
measurement system %d,
connector board %d.
Check:
Reload system
Replace Axis Computer board
Replace measure board

33404:Over writing drive sys.
Over writing of input data from
drive system %d,
connector board %d.
Check:
Reload system
Replace Axis Computer board
Replace drive unit

33405:Timeout mea. system
Contact lost with measurement
system %d, connector board %d.
Axis computer stopped
due to transmission timeout.
Check:
Check connections from cabinet to
measurement board(s).
Replace measurement board or
Axis Computer

33406:Timeout drive sys.
Contact lost with drive system %d,
connector board %d.
Axis computer stopped due to
transmission timeout.
Check:
Check connections from cabinet to
drive unit(s).
Replace drive modeule or
Axis Computer

33407:Access violation.
Access violation of measurement system
in axis computer connected to connector
board %d.
Check:
Reload system
Replace Axis Computer board

33408:Access violation.
Access violation of drive system
in axis computer connected to connector
board %d.
Check:
Reload system
Replace Axis Computer board

33409:Access violation.
Access violation of R6 calculation unit
in axis computer connected to connector
board %d.
Check:
Reload system
Replace Axis Computer board

33410:Access violation.
More than one status in R6 cleared
simultanously in axis computer connected
to connector board %d.
Check:
Reload system
Replace Axis Computer board

33411:Unknown error interrupt
Unknown error interrupt from the axis
computer connected to connector
board %d.
Check:
Restart system
Replace Axis Computer board

33412:Clock error
Axis computer connected to connector
board %d has detected clock failure
Main computer is not responding on
request
Check:
Reload system
Replace main computer board

33413:Loopback error
Error in measurement system %d at
connector board %d when
testing seriel link in loopback mode
Check:
Replace Axis Computer board

33414:Loopback error
Error in drive system %d at connector
board %d when testing
seriel link in loopback mode
Check:
Replace Axis Computer board

System and Error Messages

33415:Drive system error
Error in the drive system %d at
connector board %d when
testing seriel link in normal mode
Check:
Check seriel link
Check drive unit
Check dc link
Check/Replace Axis Computer board

33416:Reference underrun
Reference underrun in Axis computer
connected to connector board %d
Check:
Restart controller
Replace Axis computer board.

33417:Transmission error mea
Error in measurement system %d at
connector board %d when
testing seriel link in normal mode.
Check:
Check seriel link
Check/Replace measurement board(s)
Check/Replace Axis Computer board

33501:Axis computer boot error
Boot loader error in axis computer
connected to connector board %d
Internal (English only):
%s
Check:
Restart controller
Replace Axis computer board
Reinstall the system

33502:Axis computer file error
Error in biary file
%s
Internal (English only):
%s
Check:
Reinstall the system

33503:Axis computer synch fail
One or more Axis computers didn't
synchronize
Check:
Restart controller
Replace axis computer board(s)

33504:Axis computer not found
Could not find Axis computer board
connected to connector board %d
Check:
Check configuration
Check/replace cables
Check/replace axis computer board
Check replace connector board

33505:DSP program missing
Axis compuer program
%s
not found.
Check:
Reinstall the system

33506:Axis computer cmd. error
Time out when sending or reciving motion
command to axis computer conected to
connector board %d
Check:
Restart the controller
Reinstall the system
Replace Axis computer board

33507:Feedback position error
Fedback position for joint
%s (connected to
connector board %d)
not updated within specified time
Check:
Restart controller
Replace Axis computer board

33508:Unknown interrupt type
Unknown Interrupt (%d) recived
from axis computer conected to
connector board %d.
Check:
Restart cotroller
Replace Axis computer board

33509:Message queue error
Message queue in Axis computer
conected
to connector board %d
not ready with last message
Check:
Restart controller
Replace Axis computer board
Reinstall the system

33510:Motion command error
Cmd handler in Axis comp. connected
to connector board %d
not ready with last command
Check:
Restart controller
Replace Axis computer board
Reinstall the system

33511:Time slot alloc. error
Failed to allocate timeslot for joint
%s
Check:
For this joint or other joint connected
to same drive module:
-Change reslover group [R1..R3][R4..R6].
-Remove parameter -reserve_timeslot
from
 AXC_CHANNEL.

33512:Wrong axis board revision
Wrong board revision (%d) detected
for axis computer board %d
Check:
Replace Axis computer board.

33513:Axis board adr. conflict
More than one axis computer board
conected to connector board with same
adress. Board no %d
Check:
Check connections between connector
board and axis computer board.
Replace connector board.
Replace Axis computer board.

37001:Contactor activate Error
Motor On contactor for mechanical unit
%s did not activate or was already
activated
Check:
1. Check/replace contactors (M.On/AUX)
2. Replace panel board

37003:Main computer error
Check:
Replace main computer board

37004:Main computer error
Check:
Replace main computer board

37005:Main computer error
Check:
Replace main computer board

37006:Main computer error
Check:
Replace main computer board

37007:Main computer error
Check:
Replace main computer board

37008:Main computer error
Check:
Replace main computer board

37009:Main computer error
Check:
Replace main computer board

37010:Main computer error
Check:
Replace main computer board

37011:Main computer error
Check:
Replace main computer board

37012:Main computer error
Check:
Replace main computer board

37013:Main computer error
Check:
Replace main computer board

System and Error Messages

37014:Main computer error
Check:
Replace main computer board

37015:Main computer error
Check:
Replace main computer board

37016:Main computer error
Check:
Replace main computer board

37017:Main computer error
Check:
Replace main computer board

37018:Main computer error
Check:
Replace main computer board

37019:Main computer error
Check:
Replace main computer board

37020:Main computer error
Check:
Replace main computer board

37021:Main computer error
Check:
Replace main computer board

37022:Main computer error
Check:
Replace main computer board

37023:Main computer error
Check:
Replace main computer board

37024:Main computer error
Check:
Replace main computer board

37025:Main computer error
Check:
Replace main computer board

37026:Main computer error
Check:
Replace main computer board

37027:Main computer error
Check:
Replace main computer board

37028:Main computer error
Check:
Replace main computer board

37029:Main computer error
Check:
Replace main computer board

37030:Main computer error
Check:
Replace main computer board

37031:Main computer error
Check:
Replace main computer board

37032:Main computer error
Check:
Replace main computer board

37033:Main computer error
Check:
Replace main computer board

37034:Main computer error
Check:
Replace main computer board

37035:Main computer error
Check:
Replace main computer board

37036:Main computer error
Check:
Replace main computer board

37037:Main computer error
Check:
Replace main computer board

37038:Main computer error
Check:
Replace main computer board

37039:Main computer error
Check:
Replace main computer board

37040:Main computer error
Check:
Replace main computer board

37041:Main computer error
Check:
Replace main computer board

37042:Main computer error
Check:
Replace main computer board

37043:Main computer error
Check:
Replace main computer board

37044:Main computer error
Check:
Replace main computer board

37045:Main computer error
Check:
Replace main computer board

37046:Main computer error
Check:
Replace main computer board

37047:Main computer error
Check:
Replace main computer board

37048:Main computer error
Check:
Replace main computer board

37049:Contactor activate Error
Contactor for station %s or
Supervisory contactor or auxiliary
contactor did not activate or energize
Check:
Restart system
Check contactor or Supervisory
contactor or auxiliary contactor
Check digital output/input to contactor
Replace system board

37050:Temperature high
Main computer CPU has reached the
WARNING level.(%.f degrees C)
The System will be shut down if the
temperature reaches the ERROR level.
Check:
1. Check air inlets
2. Check fans

37051:Temperature too high
Main computer CPU has reached the
ERROR level.(%.f degrees C)
The System is shut down in order to
prevent permanent damage.
Check:
1. Check air inlets
2. Check fans

37052:Voltage error
%.1f V is out of tolerance
Check:
1. Check Power supplies.

37053:Battery Voltage error
Main CPU Board Battery output
(%.1f V) is out of tolerance
Check:
1. Replace Main CPU Board battery

37054:CPU fan error
Main CPU fan has stopped or is
rotating very slowly.
(Less than %.f rpm)
Check:
1. Check the fan cables.
2. Replace the fan.

37055:Computer fan error
Computer enclosure fan has stopped or
is rotating very slowly.
(Less than %.f rpm)
Check:
1. Check the fan cables.
2. Replace the fan.

System and Error Messages

37056:Cooling fan error
Cooling unit fan has stopped or
is rotating very slowly.
(Less than %.f rpm)
Check:
1. Check the fan cables.
2. Replace the fan.

37057:SMBUS unit lost
SMBUS unit at address %.0f is not
responding.
Check:
1. Restart the system.
2. Check cables.
3. Replace unit.

37058:POWER Supply error
The computer Power Supply reports an
error. Voltage %.1f is out of range.
Check:
1. Restart the system.
2. Replace the Computer Power unit.

37059:POWER Supply warning
The computer Power Supply reports an
error.Incoming voltage is out of range.
Check:
1. Restart the system.
2. Check incoming Voltage.
3. Replace the Computer Power unit.

37060:POWER Supply warning
The Process Power Supply reports an
error.24VSYS is out of range.
Check:
1. Restart the system.
2. Check units connected to 24V SYS.
3. Replace the Process Power unit.

37061:POWER Supply warning
The Process Power Supply reports an
error.24VIO is out of range.
Check:
1. Restart the system.
2. Check units connected to 24V IO.
3. Replace the Process Power unit.

37062:POWER Supply warning
The Process Power Supply reports an
error.24V BRAKE is out of range.
Check:
1. Restart the system.
2. Check units connected to 24V BRAKE.
3. Replace the Process Power unit.

37063:POWER Supply warning
The Process Power Supply reports an
error.24V COOL is out of range.
Check:
1. Restart the system.
2. Check units connected to 24V COOL.
3. Replace the Process Power unit.

37064:POWER Supply warning
The Process Power Supply reports an
error.24VPC is out of range.
Check:
1. Restart the system.
2. Check units connected to 24V PC.
3. Replace the Process Power unit.

37065:POWER Supply warning
The Process Power Supply reports an
error. +15V is out of range.
Check:
1. Restart the system.
2. Check units connected to +15V.
3. Replace the Process Power unit.

37066:POWER Supply warning
The Process Power Supply reports an
error. -15V is out of range.
Check:
1. Restart the system.
2. Check units connected to -15V.
3. Replace the Process Power unit.

37067:POWER Supply warning
The Process Power Supply reports an
error. The FAN has stopped.
Check:
1. Restart the system.
2. Replace the Process Power unit.

37068:Battery Backup warning.
Backup cycle initiated.
Check:
1. Restart the system.
2. Check/replace main computer.
3. Check/replace Battery Backup unit.

37069:Battery Backup warning.
Backup charger malfunction.
Check:
1. Restart the system.
2. Check/replace Battery Backup unit.

37070:Battery Backup warning.
Backup unit program has stalled.
Check:
1. Restart the system.
2. Check/replace Battery Backup unit.

37071:Battery Backup warning.
Battery is drained.
System parameters will not be saved to
hard drive at Power Off.
Check:
Do not turn Power off until battery
is charged.
If battery does not seem to charge,
Check/replace Battery Backup unit.

37072:Battery Backup warning.
Battery needs to be replaced in less
than %.0f days.
Check:
1. Check/replace Battery Backup unit.

37073Battery Backup warning.
Battery currently has capacity for at
least %.0f parameter saves.

37074:Purge pressure too low
Purge system number: %i
Check:
Check the purge air supply and search
for leaks in:
1. The purge unit.
2. The flexible hose conduit.
3. The manipulator itself.

37075:Purge pressure too high
Purge system number: %i
Check:
Check the purge unit and the air supply.

37076:Unexpected low purge flow
Purge system number: %i
Check:
Check the purge unit and the air supply.
Search for leaks in the purge system.

37077:Unexp. high purge flow
Purge system number: %i
Check:
Check the purge unit and the air supply.

37078:Wrong purging time set
Init timer is out of range.
Range 10 - 998.
Check:
Change the init timer on the CMPU
board to a value >= 10 and < 999.

37079:Purge timers differ
Unacceptable difference between software
and hardware count down timers.
Check:
Change CMPU board.

37080:Purge timer restarted
Purge hardware has restarted the count
down timer.
Check:
1. Check other error messages for
primary fault reason.
2. If no other error messages, the
system will try to purge once again.

37081:Signal on purge system 2
Sensor number: %i overrided.
Check:
Check the dummy plug for purge system 2.
No sensor signals shall be connected if
dummy plug is inserted.

37082:Signal on purge system 3
Sensor number: %i overrided.
Check:
Check the dummy plug for purge system 3.
No sensor signals shall be connected if
dummy plug is inserted.

System and Error Messages

37083:Low purge flow expected
Purge system number: %i
Check:
Check the purge unit and the air supply.

37084:High purge flow expected
Purge system number: %i
Check:
Check the purge unit and the air supply.
Search for leaks in the purge system.

37090:Temp. too high, sensor %d
System overheat detected.
Sensors 1-7: motor 1-7,
sensor 8: Serial measurement board.
Run chain has been opened.

37091:Battery is charging.
Battery currently has capacity for at
least %.0f parameter saves.
Charging is normal.

38001:Battery backup lost
Battery backup on serial measurement
board %.f on measurement system %.f at
connector_board %.f lost since last
power down or restart
Check:
Check battery voltage during power off
after 18 hours recharging in power on
Check battery connection to serial
measurement board
Replace battery

38010:Serial Board not found
Serial measurement board %.f at
measurement system %.f at
connection board %.f not found
Check:
Check system configuration parameters
Check connections and cables to
serial measurement system
Replace serial measurement board

38012:Serial Offset X Error
Offset error in X signal on serial
measurement board %.f at
measurement system %.f at
connection board %.f
Check:
Replace serial measurement board

38013:Serial Offset Y Error
Offset error in Y signal on serial
measurement board %.f at
measurement system %.f at
connection board %.f
Check:
Replace serial measurement board

38014:Serial Linearity Error
Linearity error in X-Y signal difference
on serial measurement board %.f at
mea. system %.f at\ connector board %.f
- System may still operate with warning
- System will not function with error
Check:
Replace serial measurement board

38015:Serial Linear X Error
Linearity error in X signal on serial
measurement board %.f at
measurement system %.f at
connection board %.f
Check:
Replace serial measurement board

38016:Serial Linear Y Error
Linearity error in Y signal on serial
measurement board %.f at
measurement system %.f at
connection board %.f
Check:
Replace serial measurement board

38030:Resolver error
Failure in X or Y resolver signal on
joint %s
Sum of squared X and Y exceeds max
Check:
Check resolver and resolver connections.
Replace measurement boards

38031:Resolver error
Failure in X or Y resolver signal on
joint %s
Sum of squared X and Y below min
Check:
Check resolver and resolver connections.
Replace measurement boards

38032:Transmission failure
Axis computer connected to connector
board %d has detected failure in
transmission to/from serial
measurement system %d.
Check:
Check connections/cables for serial
measurement system. Check shieldings
Check for high electromagnetic
disturbances along cable run to robot
Replace measure board or Axis Computer

38033:Transmission warning
Axis computer connected to connector
board %d has detected failure in
transmission to/from serial
measurement system %d.
Accumulated errors since warmstart: %d.
Check:
Check connections/cables for serial
measurement system. Check shieldings
Check for high electromagnetic
disturbances along cable run to robot
Replace measure board or Axis Computer

38034:Transmission failure
Axis computer connected to connector
board %d detected failure in transm.
to/from serial measurement system %d.
Accumulated errors since warmstart: %d.
%d absent transmission of %d detected.
Check:
Check connections/cables for serial
measurement system. Check shieldings
Check for high electromagnetic
disturbances along cable run to robot
Replace measure board or Axis Computer

38035:Transmission warning
Axis computer connected to connector
board %d has detected failure in
transmission to/from serial
measurement system %d.
Accumulated errors since warmstart: %d.
Check:
Check connections/cables for serial
measurement system. Check shieldings
Check for high electromagnetic
disturbances along cable run to robot
Replace measure board or Axis Computer

39101:DC-link over temperature
Temperature too high on DC-link,
drive system %d, connector board %d.
Check:
Check cooling fans and filter.
Too much power consumption,
modify user program.
Replace DC-link.

39102:Bleeder Overload
Bleeder overload,
drive system %d, connector board %d.
Check:
Check bleeder connections.
Too much deceleration,
modify user program.
Check AC voltage to DC-link.
Replace DC-link.

39103:Mains missing
Incoming voltage to DC-link too low,
drive system %d, connector board %d.
Check:
Check voltage from Motor On contactor.
Replace DC-link.

39104:Low DC-bus voltage
DC-link voltage not OK,
drive system %d, connector board %d.
Check:
Check voltage from Motor On contactor.
Replace DC-link.

39105:+/- 15V error
+/- 15V out of limit, detected by
DC-link, drive system %d, connector
board %d.
Check:
Check cabling.
Check +/- 15V from power supply.
Replace DC-link.

39110:Unknown type code
Unknown type code for DC-link
%s. Read type code %d when
expecting %d.
Check:
Check cabling.
Replace DC-link.

System and Error Messages

39111:Wrong type code
Wrong type detected for
DC-link %s. %s found when
expecting %s.
Check:
Check/modify configuration.
Change DC-link type.

39201:Drive Unit reset error
Reset from Drive Unit,
joint: %s.
Check:
Restart start controller.
Replace Drive Unit.

39202:Drive Unit reset error
Watchdog reset from Drive Unit,
joint: %s.
Check:
Restart start controller.
Replace Drive Unit.

39203:+/- 15V error
+/- 15V out of limit, detected by
Drive Unit, joint: %s.
Check:
Check cabling.
Check +/- 15V from power supply.
Replace Drive Unit.

39204:Communication error
Too many consecutive communication
errors reported by Drive Unit driving
joint: %s.
Check:
Check cabling.
Replace Drive Unit at previous Unit Pos
Replace Drive Unit at reported Unit Pos
Replace Axis Computer Board.

39205:Int. Drive Unit Error
Internal error detected by Drive Unit,
joint: %s.
Please report
internal error code %s
Check:
Ignore if any other Drive Unit errors
are present.
Replace drive unit.
Replace Axis Computer Board.

39206:Glitch Warning
Glitch in short circuit detector at
Drive Unit, joint: %s.
Check:
Check cabling and motor.

39207:Short Circuit
Short circuit detected in Drive Unit,
joint: %s.
Check:
Check cabling and motor.
Replace Drive Unit.

39208:Drive Unit Temp. Warning
High temperature warning in
Drive Unit, joint: %s.
NOTE: ALLOW SYSTEM TO COOL
DOWN!
Check:
Check cooling fans and filter.
Ambient temperature.
Too much power consumption, modify
user program.
Replace Drive Unit.

39209:Drive Unit Temp. Alarm
High temperature alarm in
Drive Unit, joint: %s.
NOTE: ALLOW SYSTEM TO COOL
DOWN!
Check:
Check cooling fans and filter.
Ambient temperature.
Too much power consumption, modify
user program.
Replace Drive Unit.

39210:Over Temperature
Over temperature in Drive Unit,
joint: %s.
NOTE: ALLOW SYSTEM TO COOL
DOWN!
Check:
Check cooling fans and filter.
Ambient temperature.
Too much power consumption, modify
user program.
Replace Drive Unit.

39211:Drive Unit Overload
High temperature in transistors on
Drive Unit caused by overload,
joint: %s.
Check:
Too much torque, modify user program.
Check if robot is jammed.
Replace Drive Unit.

39212:High Voltage
DC-bus voltage higher than allowed
detected by drive unit,
joint: %s.
DC-bus voltage: %s (V)
Check:
Check incoming mains.
Check/replace bleeder resistors
and cabling.
Check/replace DC-link.
Replace Drive Unit.

39213:Over Voltage
Critical over voltage on DC-bus
detected by drive unit,
joint: %s.
DC-bus voltage: %s (V)
Check:
Check incoming mains.
Check/replace bleeder resistors.
Check/replace DC-link.

39214:Low DC-bus voltage
Low voltage on DC-bus detected by
Drive Unit, joint: %s.
Voltage: %s (V).
NOTE !! This error will be disabled
until next MOTOR ON.
Check:
Check incoming mains.
Check program, configuration.
Check/replace Drive Unit, DC-link.

39215:Torque Command Error
Too big difference in 3 consecutive
torque references detected by
Drive Unit, joint: %s.
Check:
Check resolver cabling.
Check resolver ground connections.
Check for external noise at
resolver cabling.
Check configuration, speed_gain.

39216:Resolver Position Error
Too big difference in 3 consecutive
rotor positions detected by Drive Unit,
joint: %s.
Check:
Check resolver cabling.
Check resolver ground connections.
Check for external noise at
resolver cabling.

39217:Saturated Current Contr.
Drive Unit unable to supply ordered
current, due to low DC-voltage or
broken motor connections. Drive unit,
joint: %s.
Measured DC-bus voltage: %s (V)
Check:
Check DC-bus voltage.
Check motor/cables.
Check configuration.
Replace Drive Unit.

39219:Motor Under Current Err.
Torque producing current lower than
ordered, detected by Drive Unit,
joint: %s.
DC-bus voltage: %s (V)
Check:
Check configuration.
Check DC-bus voltage.
Check motor/cables.

39220:Motor Over Current Error
Torque producing current higher than
ordered, detected by Drive Unit,
joint: %s.
DC-bus voltage: %s (V)
Check:
Check configuration.
Check DC-bus voltage.
Check motor/cables.

39221:Motor Current Error
Non torque producing current higher than
allowed, detected by Drive Unit,
joint: %s.
DC-bus voltage: %s (V)
Check:
Check configuration.
Check DC-bus voltage.
Check motor/cables.

39222:Motor Over Current Error
Motor current higher than Max. measur-
able, due to short circuit or unstable
current controller, detected by
Drive Unit, joint: %s.
DC-bus voltage: %s (V)
Check:
Check motor/cables for short circuit.
Check configuration, motor parameters.
Replace Drive Unit.

39230:Unknown Type Code
Unknown Drive Unit type detected for
joint %s. Read typecode %d when
expecting %d.
Check:
Check cabling.
Replace Drive Unit.

39231:Wrong Drive Unit Rev.
Wrong program revision in Drive Unit
for joint %s.
Read revision (%d) out of range.
Check:
Replace Drive Unit.

39232:Drive Unit CPU Error
Drive Unit CPU for joint %s did
not start.
Check:
Replace Drive Unit.

39233:Drive Sys. Com. Error
Axis computer connected to connector
board %d has detected too many
consecutive communication errors in
serial link to/from drive system %d.
Accumulated errors since warmstart: %d.
Check:
Restart start controller
Check serial link.

39234:Drive Sys. Com. Error
Axis computer connected to connector
board %d has detected a single
communication error in serial link
to/from drive system %d.
Accumulated errors since warmstart: %d.
Check:
Check serial link.

39235:Drive Unit Checksum Err.
Axis computer has detected a checksum
error when transmitting parameters to
Drive Unit for joint %s.
Check:
Restart controller.
Replace Drive Unit.
Replace Axis Computer Board.

39236:Wrong Type Code
Wrong Drive Unit type detected for
joint %s. Read type code %s
when expecting %s.
Check:
Check/modify configuration.
Replace Drive Unit.

39237:Drive Sys. Com. Error
Axis computer connected to connector
board %d detected too many com. errors
in serial link to/from drive system %d.
Errors since warmstart: %d.
%d absent transmission of %d detected.
Check:
Restart start controller.
Check serial link.

39238:Drive Sys. Com. Error
Axis computer connected to connector
board %d has detected com. error
in serial link to/from drive system %d.
Accumulated errors since warmstart: %d.
Check:
Check serial link.

39239:Drive unit conflict
Mix of internal and external controlled
drive units on same serial link, drive
system %d on connector board %d.
Conflict detected for joint %s.
Check:
Check system parameters (-drive_system
in type DRIVE_UNIT). for this and/or
other joints.

39301:External Drive Error
DC voltage out of range detected by
drive unit,
joint: %s.
Check:
See documentation for Atlas DMC-C/FBU.
Check inkomming mains.
Check/replace shunt resistors.
Check/replace External Drive Unit.

39302:External Drive Error
High motor temperature detected by
drive unit,
joint: %s.
Check:
Allow motor to cool down.
Check/replace External Drive Unit.
See documentation for Atlas DMC-C/FBU.

39303:External Drive Error
High Power device temperature on
external drive unit,
joint: %s.
Check:
Allow drive unit to cool down.
Check/replace External Drive Unit.
See documentation for Atlas DMC-C/FBU.

39304:External Drive Error
Current regulator fault detected on
external drive unit,
joint: %s.
Check:
See documentation for Atlas DMC-C/FBU.
Check/replace External Drive Unit.

39305:External Drive Error
Short circuit detected on drive unit,
joint: %s.
Check:
See documentation for Atlas DMC-C/FBU.
Check/replace External Drive Unit.

39306:External Drive Error
Missing ENABLE for external drive
unit, joint: %s.
Check:
See documentation for Atlas DMC-C/FBU.

39307:External Drive Error
External drive unit, joint:
%s has performed
a CPU reset.
Check:
Restart the system.
See documentation for Atlas DMC-C/FBU.
Check/replace External Drive Unit.

39308:External Drive Error
Too many consecutive communication
errors on external drive unit,
joint: %s.
Check:
Restart start controller.
Replace drive unit.
Replace drive unit right to the one
reporting the error.
Replace Axis Computer Board.

39309:External Drive Error
Too many consecutive synchronization
errors on external drive unit,
joint: %s.
Check:
Restart start controller.
Replace external drive unit.
Replace Axis Computer Board.

39310:External Drive Stop
External drive, joint:
%s has order
a program stop.
Check:
See documentation for Atlas DMC-C/FBU.

39311:External Drive EM-Stop
External drive, joint:
%s has order
an emergency stop.
Check:
See documentation for Atlas DMC-C/FBU.

39320:External drive error
Time out in communication with external
drive unit, joint: %s
Check:
Restart system and external drive
Replace external drive
See documentation for Atlas DMC-C/FBU.

4 Program error messages

40001: Argument error
Task %.16s: More than one
occurence of optional parameter
%.16s
Check:
Make sure that the optional parameter is
not specified more than once in the same
routine call.

40002:Argument error
Task %.16s: Excluding
arguments must have conditional value
(%.16s has value)
Check:
Arguments may not be specified for more
than one parameter from a list of
parameters that exclude each other
unless all values are conditional
argument values.

40003:Argument error
Task %.16s: Expecting
argument for required parameter
%.16s but found optional
argument %.16s
Check:
Check that the arguments are specified
in the same order as the parameters for
the routine being called.

40004:Argument error
Task %.16s: Argument for REF
parameter %.16s is not data
reference
Check:
Make sure the argument expression is
just a data or parameter reference.

40005:Argument error
Task %.16s: Argument for
'INOUT' parameter %.16s is
not variable or persistent reference or
is read only.
Check:
Make sure the argument is
just a variable, persistent, variable
parameter or persistent parameter
reference and it is writeable.
Do not use () around the argument.

40006:Argument error
Task %.16s: Missing optional
argument value for parameter
%.16s
Check:
Only 'switch' parameters may be
specified by name only. Optional
parameters of other types must be
assigned a value. Add a value.

40007:Argument error
Task %.16s: Optional argument
%.16s at wrong place in
argument list
Check:
Check that the arguments are specified
in the same order as the parameters for
the routine being called.

40008:Argument error
Task %.16s: Reference to
optional parameter %.16s in
required argument
Check:
An argument corresponding to an optional
parameter must be specified with a
leading '\' character. Change the
required argument into an optional.

40009:Argument error
Task %.16s: Reference to
required parameter %.16s in
conditional argument value
Check:
A conditional value for an optional
parameter must refer an optional
parameter in the calling routine.
Change the conditional value.

40010:Argument error
Task %.16s: Reference to
required parameter %.16s in
optional argument
Check:
An argument corresponding to a required
parameter must not be specified with the
leading '\' character. Change the
optional argument into a reguired.

40011:Argument error
Task %.16s: Named required
argument %.16s at wrong place
in argument list
Check:
Check that the arguments are specified
in the same order as the parameters for
the routine being called.

40012:Argument error
Task %.16s: 'switch' argument
%.16s cannot have a value
Check:
An argument corresponding to a 'switch'
parameter may not be assigned a value.
Remove the value.

40013:Argument error
Task %.16s: Too few arguments
in call to routine %.16s
Check:
A routine call must supply values for
all required parameters of the routine
being called. Add more arguments to fit
the parameter list.

40014:Argument error
Task %.16s: Too many
arguments in call to routine
%.16s
Check:
Remove arguments so that no arguments
are supplied in excess to those defined
by the parameter list of the called
routine.

40015:Data declaration error
Task %.16s: Array dimension
must be > 0 (value is %i)
Check:
Array dimensions must be positive.
Change the dimension expression.

40016:Data declaration error
Task %.16s: Too many
dimensions in array definition
Check:
An array may have at most 3 dimensions.
Rewrite the program so that no more than
3 dimensions are needed.

40017:Type error
Task %.16s: Indexed data
%.18s %.18s is
not of array type
Check:
Only data that have been declared to be
arrays may be indexed. Remove the index
or indices, or declare the data to be an
array.

40018:Type error
Task %.16s: Data
%.18s %.18s is
not of record type
Check:
Components are only available for data
of record type. Check the type and name
of the referenced data.

40019:Limit error
Task %.16s: Error when
creating the persistent variable
(internal error code %i)
%.16s
Check:
An error occurred when the persistent
was to be inserted into the shared
database. Probably the database is full.
Ref. to system parameter AveragePers.

40020:Data declaration error
Task %.16s: Expression not
constant expression (%.16s
not constant)
Check:
Expressions contained within data
declarations must be constant
expressions. Make sure the expression
does not contain any variable or
persistent reference, or function call.

40021:Instruction error
Task %.16s: RETURN from
function must have an expression
Check:
A RETURN instruction within a function
must specify a function value to be
returned. Add a value expression.

40022:Type error
Task %.16s: Illegal
combination of operand types
%.18s and
%.18s for '*' operator
Check:
The allowed type combinations for the
two operands of the '*' operator are
'num'*'num', 'num'*'pos', 'pos'*'num',
'pos'*'pos' and 'orient'*'orient'. Check
the types of the operands.

40023:Instruction error
Task %.16s: Cannot transfer
control into another instruction list
Check:
Make sure that the label is located in
the same instruction list as the GOTO
instruction, at the same or an outer
level. It is not possible to jump into
a program flow instruction.

40024:Type error
Task %.16s: Illegal type
%.18s for left operand of
binary '+' or '-' operator
Check:
The allowed types for the operands of
the '+' operator are 'num', 'pos' and
'string', for the '-' operator 'num' and
'pos'. Check the type of the operand.

40025:Type error
Task %.16s: Illegal type
%.18s for operand of unary
'+' or '-' operator
Check:
The allowed types for the operands of
the '+' and '-' operators are 'num' and
'pos'. Check the type of the operand.

40026:Type error
Task %.16s: Illegal type
%.18s for right operand of
binary '+' or '-' operator
Check:
The allowed types for the operands of
the '+' operator are 'num', 'pos' and
'string', for the '-' operator 'num' and
'pos'. Check the type of the operand.

40027:Type error
Task %.16s: Illegal type
%.18s for left operand of
'/', 'DIV' or 'MOD' operator
Check:
The only allowed type for the operands
of the '/', 'DIV' and 'MOD' operators
is 'num'. Check the type of the operand.

40028:Type error
Task %.16s: Illegal type
%.18s for right operand of
'/', 'DIV' or 'MOD' operator
Check:
The only allowed type for the operands
of the '/', 'DIV' and 'MOD' operators
is 'num'. Check the type of the operand.

40029:Type error
Task %.16s: Illegal type
%.18s for left operand of
'<', '<=', '>' or '>=' operator
Check:
The only allowed type for the operands
of the '<', '<=', '>' and '>=' operators
is 'num'. Check the type of the operand.

40030:Type error
Task %.16s: Illegal type
%.18s for right operand of
'<', '<=', '>' or '>=' operator
Check:
The only allowed type for the operands
of the '<', '<=', '>' and '>=' operators
is 'num'. Check the type of the operand.

40031:Type error
Task %.16s: Illegal type
%.18s for left operand of
'*' operator
Check:
The allowed types for the operands of
the '*' operator are 'num', 'pos' and
'orient'. Check the type of the operand.

40032:Type error
Task %.16s: Illegal type
%.18s for right operand of
'*' operator
Check:
The allowed types for the operands of
the '*' operator are 'num', 'pos' and
'orient'. Check the type of the operand.

40033:Type error
Task %.16s: Illegal type
%.18s for operand of 'NOT'
operator
Check:
The only allowed type for the operand of
the 'NOT' operator is 'bool'. Check the
type of the operand.

40034:Type error
Task %.16s: Illegal type
%.18s for left operand of
'OR', 'XOR' or 'AND' operator
Check:
The only allowed type for the operands
of the 'OR', 'XOR' and "AND' operator is
'bool'. Check the type of the operand.

40035:Type error
Task %.16s: Illegal type
%.18s for right operand of
'OR', 'XOR' or 'AND' operator
Check:
The only allowed type for the operands
of the 'OR', 'XOR' and "AND' operator is
'bool'. Check the type of the operand.

40036:Type error
Task %.16s: Incorrect number
of indices in index list for array
%.18s with %i dimension(s)
Check:
Make sure that the number of indices in
the index list is the same as the number
of dimensions of the indexed data array.

40037:Data declaration error
Task %.16s: LOCAL illegal in
routine constant declaration
Check:
Only program data declarations may have
the LOCAL attribute. Remove the LOCAL
attribute or move the declaration
outside of the routine.

40038:Data declaration error
Task %.16s: LOCAL illegal in
routine variable declaration
Check:
Only program data declarations may have
the LOCAL attribute. Remove the LOCAL
attribute or move the declaration
outside of the routine.

40039:Name error
Task %.16s: Constant name
%.16s ambiguous
Check:
Routine data must have names that are
unique within the routine. Program data
must have names that are unique within
the module. Rename the data or change
the conflicting name.

40040:Name error
Task %.16s: Global constant
name %.16s ambiguous
Check:
Global data must have names that are
unique among all the global types, data,
global routines and modules in the
entire program. Rename the data
or change the conflicting name.

40041:Name error
Task %.16s: Global persistent
name %.16s ambiguous
Check:
Global data must have names that are
unique among all the global types, data,
global routines and modules in the
entire program. Rename the data
or change the conflicting name.

40042:Name error
Task %.16s: Global routine
name %.16s ambiguous
Check:
Global routines must have names that are
unique among all the global types, data,
global routines and modules in the
entire program. Rename the routine
or change the conflicting name.

40043:Name error
Task %.16s: Global variable
name %.16s ambiguous
Check:
Global data must have names that are
unique among all the global types, data,
global routines and modules in the
entire program. Rename the data
or change the conflicting name.

40044:Name error
Task %.16s: Label name
%.16s ambiguous
Check:
Labels must have names that are unique
within the routine. Rename the label or
change the conflicting name.

40045:Name error
Task %.16s: Module name
%.16s ambiguous
Check:
Modules must have names that are unique
among all the global types, global data,
global routines and modules in the
entire program. Rename the module
or change the conflicting name.

40046:Name error
Task %.16s: Parameter name
%.16s ambiguous
Check:
Parameters must have names that are
unique within the routine. Rename the
parameter or change the conflicting
name.

40047:Name error
Task %.16s: Persistent name
%.16s ambiguous
Check:
Program data must have names that are
unique within the module. Rename the
data or change the conflicting name.

40048:Name error
Task %.16s: Routine name
%.16s ambiguous
Check:
Routines must have names that are unique
within the module. Rename the routine or
change the conflicting name.

40049:Name error
Task %.16s: Variable name
%.16s ambiguous
Check:
Routine data must have names that are
unique within the routine. Program data
must have names that are unique within
the module. Rename the data or change
the conflicting name.

40050:Type error
Task %.16s: Operand types
%.18s and
%.18s for binary '+' or '-'
operator not equal
Check:
The two operands of the '+' and '-'
operators must have equal type. Check
the operand types.

40051:Type error
Task %.16s: Operand types
%.18s and
%.18s for '=' or '<>'
operator not equal
Check:
The two operands of the '=' and '<>'
operators must have equal type. Check
the operand types.

40052:Instruction error
Task %.16s: RETURN with
expression only allowed in function
Check:
In a procedure or trap the RETURN
instruction must not specify a return
value expression. Remove the expression.

40053:Instruction error
Task %.16s: RAISE in error
handler must not have an expression
Check:
A RAISE instruction within an error
handler can only be used to propagate
the current error, and may therefore not
specify an error number. Remove the
error number expression.

40054:Type error
Task %.16s: Different
dimension of array type (%i) and
aggregate (%i)
Check:
Make sure that the number of expressions
in the aggregate is the same as the
dimension of the data array.

40055:Type error
Task %.16s: Assignment target
type %.18s is not value or
semi-value type
Check:
The type, of the data to be assigned a
value, must be a value or semi-value
type. Data of non-value types may only
be set by special type specific
predefined instructions or functions.

40056:Type error
Task %.16s: Type
%.18s for left operand of
'=' or '<>' operator not value or
semi-value type
Check:
The '=' and '<>' operators may only be
applied to expressions of value or semi-
value type. If comparisons are to be
made, special type specific predefined
functions are needed.

40057:Type error
Task %.16s: Type
%.18s for right operand of
'=' or '<>' operator not value or
semi-value type
Check:
The '=' and '<>' operators may only be
applied to expressions of value or semi-
value type. If comparisons are to be
made, special type specific predefined
functions are needed.

40058:Type error
Task %.16s: TEST expression
type %.18s not value or
semi-value type
Check:
The TEST instruction may only be applied
to an expression of value or semi-value
type. If comparisons are to be made,
special type specific predefined
functions are needed.

40059:Data declaration error
Task %.16s: Place holder for
value expression not allowed in
definition of named constant
Check:
Complete the data declaration or change
the data name to a place holder.

40060:Data declaration error
Task %.16s: Place holder for
array dimension not allowed in
definition of named constant or variable
Check:
Complete the data declaration or change
the data name to a place holder.

40061:Routine declaration error
Task %.16s: Place holder for
parameter array dimensions not allowed
in definition of named routine
Check:
Complete the parameter declaration or
change the routine name to a place
holder.

40062:Name error
Task %.16s: Place holder for
parameter name not allowed in definition
of named routine
Check:
Complete the routine declaration or
change the routine name to a place
holder.

40063:Data declaration error
Task %.16s: Place holder for
initial value expression not allowed in
definition of named persistent
Check:
Complete the data declaration or change
the data name to a place holder.

40064:Routine declaration error
Task %.16s: Place holder for
parameter not allowed in definition of
named routine
Check:
Complete the parameter declaration,
remove the place holder or change the
routine name to a place holder.

40065:Reference error
Task %.16s: Place holder for
type not allowed in definition of named
data, record component or routine
Check:
Complete the data or routine declaration
or change the data or routine name to a
place holder.

40066:Data declaration error
Task %.16s: Place holder for
initial value expression not allowed in
definition of named variable
Check:
Complete the data declaration or change
the data name to a place holder.

40067:Type error
Task %.16s: Too few
components in record aggregate of type
%.18s
Check:
Make sure that the number of expressions
in the aggregate is the same as the
number of components in the record type.

40068:Type error
Task %.16s: Too many
components in record aggregate of type
%.18s
Check:
Make sure that the number of expressions
in the aggregate is the same as the
number of components in the record type.

40069:Reference error
Task %.16s: Data reference
%.16s is ambiguous
Check:
At least one other object sharing the
same name as the referred data is
visible from this program position. Make
sure that all object names fulfill the
naming rules regarding uniqueness.

40070:Reference error
Task %.16s: Function
reference %.16s is ambiguous
Check:
At least one other object sharing the
same name as the referred function is
visible from this program position. Make
sure that all object names fulfill the
naming rules regarding uniqueness.

40071:Reference error
Task %.16s: Label reference
%.16s is ambiguous
Check:
At least one other object sharing the
same name as the referred label is
visible from this program position. Make
sure that all object names fulfill the
naming rules regarding uniqueness.

40072:Reference error
Task %.16s: Procedure
reference %.16s is ambiguous
Check:
At least one other object sharing the
same name as the referred procedure is
visible from this program position. Make
sure that all object names fulfill the
naming rules regarding uniqueness.

40073:Reference error
Task %.16s: Trap reference
%.16s is ambiguous
Check:
At least one other object sharing the
same name as the referred trap is
visible from this program position. Make
sure that all object names fulfill the
naming rules regarding uniqueness.

40074:Reference error
Task %.16s: %.16s
not entire data reference
Check:
The specified name identifies an object
other than data. Check if the desired
data is hidden by some other object with
the same name.

40075:Reference error
Task %.16s: %.16s
not function reference
Check:
The specified name identifies an object
other than a function. Check if the
desired function is hidden by some other
object with the same name.

40076:Reference error
Task %.16s: %.16s
not label reference
Check:
The specified name identifies an object
other than a label. Check if the desired
label is hidden by some other object
with the same name.

40077:Reference error
Task %.16s: %.16s
not optional parameter reference in
conditional argument value
Check:
The specified name identifies an object
other than an optional parameter. Change
the name to refer to an optional
parameter.

40078:Reference error
Task %.16s: %.16s
not optional parameter reference
Check:
The specified name identifies an object
other than an optional parameter. Change
the name to refer to an optional
parameter.

40079:Reference error
Task %.16s: %.16s
not procedure reference
Check:
The specified name identifies an object
other than a procedure. Check if the
desired procedure is hidden by some
other object with the same name.

40080:Reference error
Task %.16s: %.16s
not required parameter reference
Check:
The specified name identifies an object
other than a required parameter. Change
the name to refer to a required
parameter.

40081:Reference error
Task %.16s: %.16s
not trap reference
Check:
The specified name identifies an object
other than a trap. Check if the desired
trap is hidden by some other object with
the same name.

40082:Reference error
Task %.16s: %.16s
not type name
Check:
The specified name identifies an object
other than a type. Check if the desired
type is hidden by some other object with
the same name.

40083:Type error
Task %.16s: %.16s
not value type
Check:
Only variables which lack initial value,
and 'VAR' mode parameters may be of
semi-value or non-value type.

40086:Reference error
Task %.16s: Reference to
unknown label %.16s
Check:
The routine contains no label (or other
object) with the specified name.

40087:Reference error
Task %.16s: Reference to
unknown optional parameter
%.16s
Check:
The called routine contains no optional
parameter (or other object) with the
specified name.

40089:Reference error
Task %.16s: Reference to
unknown record component
%.16s
Check:
The record type contains no record
component with the specified name.

40090:Reference error
Task %.16s: Reference to
unknown required parameter
%.16s
Check:
The called routine contains no required
parameter (or other object) with the
specified name.

40092:Reference error
Task %.16s: Unknown type name
%.16s
Check:
No data type (or other object) with the
specified name is visible from this
program position.

40093:Instruction error
Task %.16s: Assignment target
is read only
Check:
The data to be assigned a value may not
be a constant, read only variable or
read only persistent.

40094:Data declaration error
Task %.16s: Persistent
declaration not allowed in routine
Check:
Persistents may only be declared at
module level. Move the persistent
declaration from the routine.

40095:Instruction error
Task %.16s: RAISE without
expression only allowed in error handler
Check:
Add an error number expression to the
RAISE instruction.

40096:Instruction error
Task %.16s: RETRY only
allowed in error handler
Check:
The RETRY instruction may only be used
in error handlers. Remove it.

40097:Instruction error
Task %.16s: TRYNEXT only
allowed in error handler
Check:
The TRYNEXT instruction may only be used
in error handlers. Remove it.

40098:Parameter error
Task %.16s: 'switch'
parameter must have transfer mode IN
Check:
Remove the parameter transfer mode
specifier. If IN transfer mode is not
sufficient, change the data type of the
parameter.

40099:Parameter error
Task %.16s: 'switch'
parameter cannot be dimensioned
Check:
Remove the array dimension
specification, or change the data type
of the parameter.

40100:Parameter error
Task %.16s: 'switch' only
allowed for optional parameter
Check:
Change the parameter into an optional
parameter, or change the data type of
the parameter. If the object is not a
parameter, change the data type.

40101:Type error
Task %.16s: Type mismatch of
expected type %.18s and
found type %.18s
Check:
The expression is not of the expected
data type.

40102:Type error
Task %.16s: Type mismatch of
aggregate, expected type
%.18s
Check:
The aggregate does not match the
expected data type.

40103:Type error
Task %.16s: Persistent
%.18s %.16s type
mismatch
Check:
There is already a persistent data with
the same name but with another data
type. Rename the persistent, or change
its data type.

40104:Data declaration error
Task %.16s: Cannot determine
array dimensions (circular constant
references ?)
Check:
Check that any referred constants are
correctly defined. If so, the program is
too complex. Try to rewrite the
declarations.

40105:Data declaration error
Task %.16s: Cannot determine
type of constant value (circular
constant references ?)
Check:
Check that any referred constants are
correctly defined. If so, the program is
too complex. Try to rewrite the
declarations.

40106:Data declaration error
Task %.16s: Cannot evaluate
constant value expression (circular
constant references ?)
Check:
Check that any referred constants are
correctly defined. If so, the program is
too complex. Try to rewrite the
declarations.

40107:Data declaration error
Task %.16s: Cannot determine
type of variable value (circular
constant references?)
Check:
Check that any referred constants are
correctly defined. If so, the program is
too complex. Try to rewrite the
declarations.

40108:Type error
Task %.16s: Unknown aggregate
type
Check:
An aggregate may not be used in this
position since there is no expected data
type. Declare data with the desired data
type and aggregate value. Use the name
of the data instead of the aggregate.

40109:Type definition error
Task %.16s: Cannot determine
type of record component
%.16s
(circular type definitions?)
Check:
Check that the type of the component is
correctly defined. If so, it could be
a circular definition, the type of a
component could not refere to the its
own record type.

40110:Reference error
Task %.16s: Record name
%.16s is ambiguous
Check:
At least one other object sharing the
same name as the referred record name is
visible from this program position. Make
sure that all object names fulfill the
naming rules regarding uniqueness.

40111:Name error
Task %.16s: Global record
name %.16s ambiguous
Check:
Global type must have names that are
unique among all the global types, data,
global routines and modules in the
entire program. Rename the record
or change the conflicting name.

40112:Reference error
Task %.16s: Alias name
%.16s is ambiguous
Check:
At least one other object sharing the
same name as the referred alias name is
visible from this program position. Make
sure that all object names fulfill the
naming rules regarding uniqueness.

40113:Name error
Task %.16s: Global alias
name %.16s ambiguous
Check:
Global type must have names that are
unique among all the global types, data,
global routines and modules in the
entire program. Rename the alias
or change the conflicting name.

40114:Type definition error
Task %.16s: Type reference
of alias name %.16s
is an alias type
Check:
Check that the type of the component is
correctly defined. If so, it could be
a circular definition, the type of a
component could not refere to the its
own record type.

40115:Type definition error
Task %.16s: Cannot determine
type of alias %.16s
(circular type definitions?)
Check:
Check that the type of the alias is
correctly defined. If so, it could be
a circular definition, the type of an
alias could not refere to a record that
use this alias as a component.

40116:Reference error
Task %.16s:
Record component name
%.16s is ambiguous
Check:
At least one other object sharing the
same name as the referred component is
visible from this program position. Make
sure that all object names fulfill the
naming rules regarding uniqueness.

40117:Type definition error
Task %.16s: Place holder for
record component not allowed in
definition of named record
Check:
Complete the definition or change
the data name to a place holder.

40118:Not authorized
Task %.16s: The function:
User defined data types is not
installed in this system
Check:
Install the option Developer Functions
in the system.

40119:Reference error
Task %.16s:
Cannot use the semi-value type
%.16s for record components

40120:Reference error
Task %.16s: Illegal reference
to installed task object
%.16s from shared object
Check:
Install the referred object shared, or
install the referring ReaL object/
archive or RAPID module in each task
(not shared).

40121:Reference error
Task %.16s:
Cannot use semi-value type for arrays

40141:Argument error
Task %.16s: Argument for
'PERS' parameter %.16s is not
persistent reference or is read only
Check:
Make sure the argument is just
a persistent or persistent parameter
reference and it is writeable.
Do not use () around the argument.

40142:Argument error
Task %.16s: Argument for
'VAR' parameter %.16s is not
variable reference or is read only
Check:
Make sure the argument is just
a variable or variable parameter
reference and it is writeable.
Do not use () around the argument.

40157:Instruction error
Task %.16s: Interrupt number
is not static variable reference, is
shared, or is read only
Check:
Make sure the interrupt number is just
a variable or variable parameter
reference. The variable must be
static and not shared. The variable may
not be read only.

40158:Value error
Task %.16s: Integer value
%G too large
Check:
The value of the expression must be an
integer value. The current value is
outside the integer range.

40159:Value error
Task %.16s: %G not
integer value
Check:
The value of the expression must be an
exact integer value. The current value
has a fraction part.

40165:Reference error
Task %.16s: Reference to
unknown entire data %.16s
Check:
No data (or other object) with the
specified name is visible from this
program position.

40166:Reference error
Task %.16s: Reference to
unknown function %.16s
Check:
No function (or other object) with the
specified name is visible from this
program position.

40168:Reference error
Task %.16s: Reference to
unknown procedure %.16s
Check:
No procedure (or other object) with the
specified name is visible from this
program position.

40170:Reference error
Task %.16s: Reference to
unknown trap %.16s
Check:
No trap (or other object) with the
specified name is visible from this
program position.

40191:Instruction error
Task %.16s: Variable and trap
routine already connected
Check:
It is not legal to connect a specific
variable with a specific trap routine
more than once.

40192:Argument error
Task %.16s: %.16s
is second present conditional argument
for excluding parameters
Check:
Arguments may not be present for more
than one parameter from a list of
parameters that exclude each other.

40193:Execution error
Task %.16s: Late binding
procedure call error %i
Check:
There is an error in the procedure call
instruction. See previous message for
the actual cause.

40194:Value error
Task %.16s: Division by zero
Check:
Cannot divide by 0. Rewrite the program
so that the divide operation is not
executed when the divisor is 0.

40195:Limit error
Task %.16s: Exceeded maximum
number %i of allowed RETRYs
Check:
The error correction performed before
the RETRY instruction is executed, is
probably not enough to cure the error.
Check the error handler.

40196:Instruction error
Task %.16s: Attempt to
execute place holder
Check:
Remove the place holder or the
instruction containing it, or make the
instruction complete. Then continue
execution.

40197:Execution error
Task %.16s: Function does not
return any value
Check:
The end of the function has been reached
without a RETURN instruction being
executed. Add a RETURN instruction
specifying a function return value.

40198:Value error
Task %.16s: Illegal
orientation value
%.40s
Check:
Attempt to use illegal orientation
(quaternion) value

40199:Value error
Task %.16s: Illegal error
number %i in RAISE
Check:
Only error numbers in the range 1-99 are
allowed in the RAISE instruction.

40200:Limit error
Task %.16s: No more interrupt
number available
Check:
There is a limited number of interrupt
numbers available. Rewrite the program
to use fewer interrupt numbers. This
message may also occur as a consequence
of a system error.

40201:Value error
Task %.16s: Negative operand
%i not allowed
Check:
The 'MOD' operator only allows non
negative operands. Change the program
to make sure that the operator is not
applied to negative values.

40202:Type error
Task %.16s: Dimensions %i
and %i of conformant array
dimension number %i are incompatible
Check:
The array is not of the expected size.
Array assignment may only be performed
on arrays of identical size.

40203:Reference error
Task %.16s: Optional
parameter %.16s not present
Check:
The value of a non present optional
parameter may not be referred. Use the
predefined function 'Present' to check
the presence of the parameter before
using its value.

40204:Value error
Task %.16s: Array index %i
for dimension number %i out of bounds
(1-%i)
Check:
The array index value is non-positive or
violates the declared size of the array.

40205:Value error
Task %.16s: String too long
Check:
String value exceeds the maximum allowed
length. Rewrite the program to use
strings of lesser length.

40221:Execution error
Task %.16s: Execution aborted
Check:
Execution was aborted due to a fatal
error.

40222:Limit error
Task %.16s: Execution stack
overflow
Check:
The program is too complex to execute.
Probably the program contains recursive
routines.

40223:Execution error
Task %.16s: Fatal runtime
error
Check:
A fatal runtime error has occurred.
Fatal runtime errors causes immediate
termination of execution. See previous
message for the actual cause.

40224:Execution error
Task %.16s: Illegal return
code %i from ReaL routine
Check:
This is always caused by an internal
error in the ReaL routine.

40225:Execution error
Task %.16s: Execution could
not be restarted
Check:
Execution could not be continued after
power failure. Restart the program.

40226:Name error
Task %.16s: Procedure name
%.40s
is not a RAPID identifier excluding
reserved words
Check:
The procedure name, must be a legal
RAPID identifier not equal to any of
the reserved words of the RAPID
language. Change the name expression.

40227:Limit error
Task %.16s: Runtime stack
overflow
Check:
The program is too complex to execute.
Probably the program contains recursive
routines.

40228:Execution error
Task %.16s: Unhandled
non-fatal runtime error %i
Check:
A non-fatal runtime error has occurred
but was not handled by any ERROR
clause. See previous message for the
actual cause.

40229:Execution error
Task %.16s: Unhandled raise
error %i
Check:
An error was raised by a RAISE
instruction but was not handled by any
ERROR clause.

40230:Execution error
Task %.16s: Unhandled
non-fatal runtime error
Check:
A non-fatal runtime error has occurred
but was not handled by any ERROR
clause.

40241:Value error
Task %.16s: Array dimension
number %G out of range (1-%i)
Check:
The value of the 'DimNo' parameter of
the 'Dim' function must be an integer
value in the specified range.

40242:Type error
Task %.16s: Data is not an
array
Check:
The 'DatObj' parameter of the 'Dim'
function must be an array.

40243:Value error
Task %.16s: Unknown interrupt
number
Check:
Check that the specified interrupt
variable has been initialized by
CONNECT, and that the interrupt has been
defined using the ISignalDI or other
interrupt definition instruction.

40244:Value error
Task %.16s:
Object %.16s is of
non-value type
Check:
Use expression or data object of value
or semivalue type.

40245:Parameter error
Parameters in %.16s
and %.16s is not
matching (late binding)
Check:
Make sure that all procedures that are
called from the same late binding node
have matching parameters. I.e they
should be matching concerning base type,
mode and required/optional parameters.

40251:Name error
Task %.16s: Ambiguous symbol
name %.16s
Check:
Installed objects must have names that
are unique. Rename the object or change
the conflicting name.

40252:Limit error
Task %.16s: Error %i when
creating sdb entry for %.16s
Check:
An error occurred when the persistent
was to be inserted into the shared
database. Probably the database is full.

40253:Type definition error
Task %.16s: Alias
%.16s of alias
%.16s not allowed
Check:
Is is not possible to define an alias
type equal to another alias type.
Instead, define two alias types equal to
the same atomic or record type.

40254:Symbol definition error
Task %.16s: 'ANYTYPE#'
parameter %.16s cannot be
dimensioned
Check:
Remove the dimension specification.
'ANYTYPE#' includes array types.

40255:Symbol definition error
Task %.16s: 'ANYTYPE#' only
allowed for parameter (not for
%.16s)
Check:
Use another type.

40256:Parameter error
Task %.16s: 'alt' must not be
set for first optional parameter
%.16s in alternatives list
Check:
Make sure that only the second and
following in each list of excluding
optional parameters are marked as
alternatives.

40257:Parameter error
Task %.16s: REF mode
parameter %.16s cannot be
dimensioned
Check:
Remove the array dimension
specification, or change the mode of the
parameter.

40258:Parameter error
Task %.16s: 'switch'
parameter %.16s can not be
dimensioned
Check:
Remove the array dimension
specification, or change the data type
of the parameter.

40259:Parameter error
Task %.16s: 'switch'
parameter %.16s must have
transfer mode IN (specified value
%i)
Check:
Remove the parameter transfer mode
specifier. If IN transfer mode is not
sufficient, change the data type of the
parameter.

40260:Symbol definition error
Task %.16s: 'switch' only
allowed for optional parameter
(not for %.16s)
Check:
Change the parameter into an optional
parameter, or change the data type of
the parameter. If the object is not a
parameter, change the data type.

40261:Type definition error
Task %.16s: Value type class
for %.16s must be one of
REAL_SYMVALTYP_VAL, _SEMIVAL,
_NONVAL or
_NONE (specified value %i)
Check:
Change the value type class.

40262:Data declaration error
Task %.16s: Too many array
dimensions for %.16s
(specified value %i)
Check:
An array may have at most 3 dimensions.

40263:Name error
Task %.16s: Symbol name
%.40s
is not a RAPID identifier excluding
reserved words
Check:
The names of installed objects,
including parameters and components,
must be legal RAPID identifiers not
equal to any of the reserved words of
the RAPID language. Change the name.

40264:Symbol definition error
Task %.16s: Missing C
function for %.16s
Check:
A C-function that executes the ReaL
function being defined, must be
specified.

40265:Symbol definition error
Task %.16s: Missing value
initialization function for
%.16s
Check:
A value initialization function must be
specified.

40266:Reference error
Task %.16s: %.16s
is not a data type name (object
%.16s)
Check:
The specified name identifies an object
other than a type.

40267:Reference error
Task %.16s: %.16s
is not a value data type (object
%.16s)
Check:
Only record components, alias types,
variables and 'VAR' mode parameters
may
be of semi-value or non-value type.

40268:Symbol definition error
Task %.16s: Missing value
conversion function for %.16s
Check:
A value conversion function must be
specified for a semi-value type.

40269:Symbol definition error
Task %.16s: Not enough
memory for value of data
%.16s
Check:
More memory required.

40270:Type definition error
Task %.16s: Private type
%.16s can only be semi-value
or non-value type (specified value
%i)
Check:
Change the value type class.

40271:Type definition error
Task %.16s: Private type
%.16s size must be multiple
of 4 (specified value %i)
Check:
All RAPID types must have a size that is
a multiple of four. Change the specified
type size.

40272:Type error
Task %.16s: Persistent type
mismatch for %.16s
Check:
There is already a persistent data with
the same name but with another data
type. Rename the persistent, or change
its data type.

40273:Reference error
Task %.16s: Unknown data type
name %.16s for
%.16s
Check:
There is no data type (or other object)
with the specified name.

40274:Parameter error
Task %.16s: Unknown parameter
transfer mode %i for
%.16s
Check:
The specified parameter transfer mode is
not one of IN, 'VAR', 'PERS', 'INOUT' or
REF. Use corresponding
REAL_SYMPARMOD_x.

40275:Symbol definition error
Task %.16s: Unknown symbol
definition type %i
Check:
The symbol definition type tag does not
specify one of the allowed symbol
types (REAL_SYMDEF_x).

40276:Symbol definition error
Task %.16s: Initialization
function may not be specified for shared
variable %.16s
with per task value
Check:
Remove initialization function, install
variable in all tasks, or make variable
value shared.

40301:I/O error
Task %.16s: Permission denied
(file name
%.39s)

40302:I/O error
Task %.16s: No such file or
directory (file name
%.39s)

40303:I/O error
Task %.16s: No space left on
device (file name
%.39s)

40304:I/O error
Task %.16s: I/O error %!
(file name
%.39s)
Check:
One of:
 Permission denied (write protected)
 No such file or directory
 No space left on device

40321:Load error
Task %.16s:
Module loaded with path
%.40s
is active
Check:
A module containing routines or data
that are still active cannot be erased.

40322:Load error
Task %.16s: RAPID syntax
error(s) in file
%.40s
Check:
The source file to be loaded contains
RAPID syntax errors. Correct the source
file. The syntax errors are logged in a
separate file.

40323:Load error
Task %.16s: Syntax error(s)
in header in file
%.40s
Check:
The source file to be loaded contains
syntax error in the file header. Correct
the source file. The syntax errors are
logged in a separate file.

40324:Load error
Task %.16s: Keywords not
defined in specified language (file
%.39s)
Check:
Cannot load RAPID source code in the
national language specified in the file
header.

40325:Load error
Task %.16s: Not enough heap
space
Check:
There is not enough free memory left.

40326:Load error
Task %.16s: Parser stack
full (file
%.39s)
Check:
The program is too complex to load.

40327:Load error
Task %.16s: Not current RAPID
version (file
%.39s)
Check:
Cannot load RAPID source code of the
version specified in the file header.

System and Error Messages

40351:Memory allocation error
Task %.16s: Failed to
allocate hash table, use linear list

40352:Memory allocation error
Task %.16s: Failed to
update persistent expression, keep old
one

40501:Timeout
%s
%s

40502:Digital input break
%s
%s

40503:Reference error
Device descriptor is
%s

40504:Parameter error
%s
Check:
%s

40505:File access error
%s
%s
Check:
Possible error:
1. Wrong path or filename
2. Max number of simultaneously opened
   files exceeded
3. I/O device reference already in use

40506:System access error
%s
%s

40507:Limit error
%s

40508:Wrong orientation value
in %s

40509:Search warning
%s
Before performing next search,
make sure that TCP is moved back
to the start position of the
search path.
Check:
If no repositioning is done, before
restart of circular search, movement
that can cause damage might occur.

40510:Security warning
The move instruction can't restart
due to security problem.
Try to move the PP

40511:Parameter error
The parameter %.16s
in %.16s is specified
with a negative value
Check:
The parameter must be set positive.

40512:Missing ext. axis value
Some active external axis have
incorrect or no order value.
Reprogram the position.

40513:Mechanical unit error
Not possible to activate or
deactivate mechanical unit.

40514:Execution error
Too far from path to perform
StartMove of the interrupted
movement.
Check:
Position the robot to the
interrupted position in the program.

40515:Type error
Task %s: Illegal data type
of argument for parameter %s

40516:Value error
Task %s: Illegal value of
argument for parameter %s

40517:Search error

%s

No search hit or more than 1 search
hit during stepwise forward execution.
The search instruction is ready and
next instruction can be executed.
Check:
Note that no position has been returned
from the search instruction.

40518:Type error

%s

40519:End of file found during

%s

40521:Parameter error

Task %.16s:
Can not open %.25s.
Only a device specified.
%.40s
Check:
Specify a file or directory.

40522:Limit error

Stop watch overflow.
Check:
Recovery: %.16s

40590:ParId error

%.40s
%.40s
Check:
%.40s

40591:Argument error

Unknown type of parameter
identification.

40592:ParId Program Stop

Any type of program stop during
load identification is not allowed.
Check:
Start the identification procedure from
beginning again.

40593:ParId Power Fail

Power Fail during load identification
results in faulty load result.
Check:
Restart the program execution again
with same run mode (without PP move)
for load identification from beginnig.

40594:ParId user error

Error resulting in raise of PP to the
beginning of the parameter
identification procedure.
Check:
Start the identification procedure from
beginning again.

40595:Argument error

Unknown type of load
identification.

40596:ParId Program Stop

Any type of program stop during
load identification is not allowed.
Check:
Restart the program execution again
for load identification from beginnig.
(From old PP pos. and with same run mode
if try to move PP within program list.)

40597:ParId Speed Override

Speed override not 100 per cent.
Check:
Change the speed override to 100.
Restart the program execution again
for load identification from beginnig.

40600:Argument error

No \WObj specified
for movement with stationary TCP.
Check:
Add argument \WObj
for actual work object.
If not movement with stationary TCP,
change argument Tool to
"robot holds the tool".

System and Error Messages

40601:Argument error
Undefined if robot holds the tool
or the work object.
Check:
Check if mismatch between
argument Tool and argument \WObj
for data component robhold.

40602:Argument error
Argument %s has
at least one data component
with negative value.
Check:
Set all data components
in argument %s
to positive values.

40603:Argument error
Argument %s may not have
a negative value.
Check:
Set argument %s to
a positive value.

40604:Argument error
Argument Tool has undefined
load of the tool.
Check:
Define the actual load of the tool
before use of the tool for jogging
or program movement.

40605:Argument error
Argument Tool has negative
load of the tool.
Check:
Define the correct load of the tool
before use of the tool for jogging
or program movement.

40606:Argument error
Argument Tool has at least
one inertia data component
with negative value.
Check:
Define all inertia data components
(ix, iy or iz) to actual
positive values.

40607:Execution error
Not allowed to change run mode
from forward to backward or vice versa
during running a circular movement.
Check:
If possible, select the original run
mode and press start to continue the
stopped circular movement. If not
possible, move robot and program pointer
for a new start.

40608:Argument error
Orientation definition error
in %s.
Check:
All used orientations must be normalized
i.e. the sum of the quaternion elements
squares must equal 1.

40609:Argument error
Argument \WObj specifies a mechanical
unit with too long name.
Check:
Use max. 16 characters to specify the
name of a mechanical coordinated unit.

40610:Argument error
Argument \WObj specifies a mechanical
unit name, which is not activated
or unknown in the system.
Check:
The mechanical unit name defined in
\WObj must correspond to the name
earlier defined in the system
parameters and must be activated.

40611:Execution error
Not allowed to step backwards
with this move instruction.
Check:
Step backwards to a position
defined with another tool
or work object could result in
fualty path.

40612:Argument error
No argument programmed for
the name of the output signal.
Check:
Possible to set one position fix IO
such as digital, group of digitals
or analog output signal during the
robot movement.

40613:Argument error
Optional argument %s
can only be combined with
output signal argument %s.

40614:Argument error
Argument %s
is not 0 or 1.
Check:
Digital output signals can only be
set to 0 or 1.

40615:Argument error
Argument %s
is not an integer value.
Check:
Digital group of output signals,
process identity or process selector
can only have an integer value.

40616:Argument error
Argument %s
is outside allowed limits.
Check:
Used group of digital output signals
can only be set within 0 to %s
according configuration in
the system parameters.

40617:Argument error
Argument %s
is outside allowed limits.
Check:
Used analog output signals can only be
set within %s to %s
according configuration in
the system parameters.

40618:Argument error
Argument %s
contains an illegal interrupt number.
Check:
Input interrupt number is illegal
because it has not been allocated by
the instruction CONNECT.
CONNECT do allocation and connection of
interrupt number to trap routine.

40619:Argument error
Argument %s
contains an interrupt number, which
is already in use for other purpose.
Check:
Before reuse of an interrupt variable
again in the program, cancel old
interrupt generation and interrupt
number with instruction IDelete.

40620:Argument error
Argument %s have
too large negative value.
Check:
Set argument %s to
%.16s or more.

40622:Argument error
The value of argument Time in ITimer
is too low for cyclic interrupts.

40623:Argument error
The value of argument Time in ITimer
is too low for single interrupts.

40624:Argument error
Task %.16s:
Argument %s
is not between 0 and 2.
%.40s
Check:
Specify the flank to generate the
interrupt.
0 Negative flank (high -> low).
1 Positive flank (low -> high).
2 Both negative and positive flank.

System and Error Messages

40631:Instruction error
Too many move instructions in
sequence with concurrent RAPID
program execution.
Check:
Edit the program to max. 5 MoveX \Conc
in sequence on the basic
execution level of the program.

40632:Instruction error
No move instructions with concurrent
RAPID program execution are allowed
within the StorePath-RestoPath part of
the program.
Check:
Edit the program so it does not
contain any MoveX \Conc instructions
within the StorePath-RestoPath part of
the program.

40633:Reference error
Trigg parameter no %s reference to
undefined trigg data.
Check:
Define trigg data by executing
instruction TriggIO, TriggInt,
TriggEquip or TriggSpeed
before TriggL, TriggC or TriggJ.

40634:Reference error
Signal reference in parameter %s
contains unknown signal for the robot.
Check:
All signals should be defined in the
system parameters and should not be
defined in the RAPID program.

40635:Reference error
Argument reference
in parameter %.16s
is not a entire persistent variable.
Check:
Not possible to use record component or
array element in arg. %.16s.
Only possible to use entire persistent
variables for Tool, WObj or Load
in any motion instructions.

40636:Sensor error
No measurement from sensor.
Check:
Requested data is not available.

40637:Sensor error
Not ready yet.
Check:
Requested function is not ready yet.

40638:Sensor error
General error.
Check:
General error has occurred which is not
specifically connected to the requested
action. Read the block "Error log" if
the function is available.

40639:Sensor error
Sensor busy, try later.
Check:
The sensor is busy with an other
function.

40640:Sensor error
Unknown command.
Check:
The function requested from the sensor
is unknown.

40641:Sensor error
Illegal variable or block number.
Check:
Requested variable or block is not
defined in the sensor.

40642:Sensor error
External alarm.
Check:
Alarm from external equipment.

40643:Sensor error
Camera alarm.
Check:
Some error has been detected in
the camera. Run Camcheck to test if the
camera is OK.

40644:Sensor error
Temperature alarm.
Check:
The camera is overheated it needs more
cooling air or water.

40645:Sensor error
Value out of range.
Check:
The value of the data sent to the
sensor is out of range.

40646:Sensor error
Camera check failed.
Check:
The CAMCHECK function failed. The
camera is broken. Send it for repair.

40647:Sensor error
Communication time out.
Check:
Increase the time out time and check
the connections to the sensor.

40648:Search error
Not possible to do StorePath while
searching on basic path level.
Check:
If using program with robot movement
in TRAP, then such interrupt must be
deactivated during any searching.
E.g. ISleep - SearchL - IWatch

40649:Path limit error
%s already done.
Check:
Instruction %s must first be
executed, before a new %s can
be done.

40650:Wrong param combination
Optional parameters and switches are
not used in a correct combination.
Check:
No optional parameters and no switch
keeps the old coordinate system.
The switch Old has the same function.
RefPos or RefNum has to be defined with
Short, Fwd or Bwd.

40651:Use numeric input
Use numeric input for the position
instead of a robtarget.
Check:
The position can not be defined with
a robtarget for robot axes.
Use the optional parameter for numeric
input of the position.

40652:Axis is moving
A Robot axis, an external axis
or an independent axis is moving.
Check:
All Robot axes, external axes and
independent axes have to stand still.
E.g Use MoveL with Fine argument for
the Robot and ext. axes. And IndRMove
for the independent axes.

40653:Switch is missing
One of the switch parameters %s
or %s has to be defined.

40654:Axis is not active
The axis is not active
or it is not defined.
Check:
The mechanical unit has to be activated
and the axis has to be defined, before
this instruction is executed and before
a robtarget is saved.

40655:Axis is not independent
The axis is not in independent mode.
Check:
It is only possible to get the status
from an axis in independent mode.

40656:Execution error
Not possible to set a new scale
value for the AO signal.
Check:
The internal process, that control
the output of the AO signal,
are for some unknown reason "dead".

System and Error Messages

40657:Execution error
The output of the AO signal are not
TCP-speed proportional any more.
The reason could be following:
Check:
- Use of MoveX between TriggX instr.
- No setup of TriggSpeed in the used
  TriggX instr.
- The used ScaleLag is too small in
  relation to actual robot servo lag.

40658:Parameter error
Parameter %s can only
be used, if parameter %s
is greater than zero.
Check:
Parameter %s has effect
only in the first TriggX, in a
sequence of several TriggX, that
controls the speed proportional
AO signal.

40659:Undefined load
WARNING: Argument %.16s has
undefined load (mass equal to 0 kg).
IMPORTANT TO DEFINE CORRECT
LOAD to
avoid mechanical damages of the robot
and to get good motion performance.
Check:
Define the actual load for the tool
or the grip load before program
movement or jogging.

40660:Undefined load
WARNING: Argument %.16s has
undefined load centre of gravity.
IMPORTANT TO DEFINE CORRECT
LOAD to
avoid mechanical damages of the robot
and to get good motion performance.
Check:
Define the actual centre of gravity
for the tool load or the grip load
before program movement or jogging
(cog.x, cog.y and cog.z can not be
0 mm at the same time).

40661:Search error
The signal %.16s for the
SearchX instruction is already high
at the start of searching.

40662:Invalid worldzone type
The switch \%.16s must be
associated with a %.16s
worldzone.
Check:
If use of switch \Temp, the datatype
must be wztemporary in WorldZone.
If use of switch \Stat, the datatype
must be wzstationary in WorldZone.

40663:World zone not in use
The '%.16s' argument of the
instruction %.16s must refer
to a worldzone that has been defined
and activated by a WZLimSup or WZDOSet
instruction.

40664:World zone already in use
The '%.16s' worldzone has
already been defined and activated.
A world zone can only be defined once.
Check:
Use a worldzone with another name.

40665:Too many world zones
It is not possible to add the world
zone %.16s.
The world zone table is full

40666:Illegal world zones
Task %.16s:
Worldzone '%.16s' is
defined locally in current routine
Check:
Only a global or local in module
entire world zone argument can be used.

40667:Illegal world zones
Task %.16s:
WorldZone %.16s is
not entire data reference.
Check:
Only an entire world zone argument
can be used.

40668:shapedata not in use
The '%.16s' argument of the
instruction %.16s must refer
to a defined shapedata.
Check:
A shapedata is used to store a volume
definition. It must have been defined
by WZBoxDef, WZSphDef or WZCylDef
prior
to be used by WZLimSup or WZDOSet.

40669:World zone too small
At least one side or radius is less
than the minimal allowed in
instruction %.16s.
Check:
Check previous volume definition
instruction.

40670:Invalid world zone
The index of the world zone argument
%.16s in %.16s
is not a valid index defined by
WZLimSup or WZDOSet.

40671:Illegal use of world zone
Task %.16s:
'%.16s'
argument for %.16s
must be a temporay world zone.

40672:World zone already in use
It is not possible to add the world
zone %.16s. Another world
zone with the same name is already
defined in the system.

40673:I/O access error
The signal given in parameter
%s is write protected
for RAPID access.
Check:
Select other user signal or
change the access mode for the signal

40674:I/O access error
The signal given in parameter
%s is not write protected
for user access from TP or RAPID.
Check:
Change the access mode to system type
for the signal in the I/O
configuration.

40675:Execution error
Not allowed to change the run mode from
forward to backward or vice versa during
running an invisible trap routine.
Check:
If possible, select the original run
mode and press start to continue.

40700:Syntax error
Task %s: Syntax error
%s

40701:Program memory full
The task %s, has only
%i free bytes in its
user space
Check:
Remove some other module and try
again.

40702:File not found
%.40s
Check:
The file path or the file name is wrong
or the file doesn't exist.

40704:UnLoad error
%.40s
The program module couldn't be unloaded
The reason could be:
- Module not loaded with Load instr.
- Not same file path as used for Load
Check:
The program module must have been
loaded with the instruction Load.
The file path and name must be the same
in the UnLoad and Load instruction.

System and Error Messages

40705:Syntax error
Task %s: Syntax error
%s
Check:
More syntax errors will follow this

40706:Loaded error
The program module is already loaded
Check:
The module name in the head of the file
%.40s
already exists in the program memory

40707:I/O Unit name invalid
Task %s:
The unit name
%.40s
doesn't exist or can't be disabled.
Check:
The unit name is misspelled, not
defined or can't be disabled.

40708:I/O unit is not enabled
Task %s:
I/O unit
%.40s
was not enabled.
Check:
The maximum period of waiting time was
too short. Increase the waiting time
or make a retry.

40709:I/O unit is not disabled
Task %s:
I/O unit
%.40s
was not disabled.
Check:
The maximum period of waiting time was
too short. Increase the waiting time
or make a retry.

40710:Argument error
Task %.16s: Argument error
from %.16s !
The argument is expression value,
is not present or is of the type switch.
Check:
Change the parameter
(%.16s) to a
valid one.

40711:Alias type error
Task %s:
The data types for the arguments
FromSignal and ToSignal must be the
same and must be one of signalxx.
(signalai/ao, signaldi/do, signalgi/go)
Check:
Change the type
to a valid one.

40712:Event routine error
Task %s: Too many event routines,
the routine %s will not be
executed. Maximum 4 routines
could be specified for each event
Check:
Encapsulate the routine in one of
the others that are specified for
the same event.

40713:Alias define error
Task %s:
FromSignal must be defined in
the io-system. ToSignal must not be
defined in the io-system, it should
just be defined as a variable.

40714:Argument error
Orientation definition error
in %s.
Check:
This is probably an off-line generated
"dummy" position (undefined orienta-
tion), that needs to be MODPOS.

40715:IOEnable call interrupted
Task %s:
Call to I/O unit
%.40s
was inerrupted.
Check:
IOEnable or IODisable have been exec
from an other task. Make a retry.

40720:Alias IO installation
The task %s, could not
refresh all alias IO

40721:IO installation
The task %s, could not
refresh all IO
as RAPID symbols
Check:
Check the IO configuration.

40722:Mechanical units
The task %s, could not
refresh all mechanical
units as RAPID symbols
Check:
Check the Motion
configuration.

40724:Save error
The program module
%.40s
could't be saved.
Check:
The module name is misspelled or
the module is not loaded.

40726:Reference error
The reference to the load session is
not valid
Check:
The specified reference must be same
as in StartLoad.

40727:Save error
Module %.16s:
Missing file source
Check:
Use FilePath argument
to specify the file destination.

40728:Frame error
Task %.16s: Unable to
calculate new frame. The positions
have not the required relations or are
not specified with enough accuracy.
%.40s
Check:
Check if the positions are too close
or not specified with enough accuracy.
Recovery: %.16s

40729:I/O error
Task %.16s
(file name
%.39s)
Check:
One of:
 Permission denied (write protected)
 No such file or directory
 No space left on device

40730:I/O error
Task %.16s:
%s
Check:
%s

40731:Task %s: %s argument
for signal %s
is above its max logical value
Check:
Change the argument or
change the max logical value parameter
for the signal.

40732:Task %s: %s argument
for signal %s
is below its min logical value
Check:
Change the argument or
change the min logical value parameter
for the signal.

40733:Task %s: %s argument
for signal %s
is below %s argument
Check:
Change the arguments.

40734:Symbol definition error
Task %.16s:
String too long in
text table %.16s
at index %.16s
Check:
Change the file for the text table
and do a cold start.

40735:Argument error
The axis is not defined
Check:
The axis has to be defined, before
this instruction is executed.

40736:Mechanical unit error
Not possible to define a payload on the
robot with this instruction.
Check:
Use the instruction GripLoad
instead of MechUnitLoad.

40737:Symbol definition error
Task %.16s:
The requested text or text package
does not exist.
Text table %.16s
Index %.16s

40738:I/O error
Unable to access the I/O signal
%.16s unit %.16s.
Impossible to restart.
Check:
The connection with the I/O module is
broken. Reestablish the connection
with the I/O unit. To make it possible
to restart the program move PP to a
safe restart position.

40739:Parameter error
Task %.16s:
None of the option
parameters DO1, GO1, GO2, GO3 or
GO4
are specified.
%.40s
Check:
At least one of the parameters must be
specified.

40740:Execution error
The PERS variable specified in the
instruction TriggStopProc can not
be updated, because it not exists
any more.
Check:
The program module with the PERS
variable is probably removed from the
program memory.

40741:Context error
Instruction %.16s
may only be used in an event routine.

40742:Parameter error
Task %.16s:
The timing parameter dip lag is larger
than the system parameter Event preset
time.
%.40s
Check:
Increase the system parameter
Event preset time or check the
equipment dip lag (delay)
compensation.

40743:Parameter error
Task %.16s:
Not a valid subtype in
parameter %.16s
%.40s

40744:Parameter error
Task %.16s:
Invalid value in
%.32s
in parameter %.16s.
%.40s

40745:Parameter error
Task %.16s:
%.32s is less
than %.32s
in parameter %.16s.
%.40s

40746:Parameter error
Task %.16s:
%.16s TRUE in parameter
%.16s in
combination with conveyor coordination.
%.40s
Check:
Cannot use fine points when leaving
conveyers after coordinated stoppoint.
Use a zone instead.

40747:Access error
Task %.16s:
Can not read or write to the system
parameter. The parameter is internal
and protected from reading and writing.
%.40s

40748:Value error
Task %.16s:
The data to write from parameter
CfgData to the system parameter,
is outside valid limits.
%.40s
Check:
Recovery: %.16s

40900:Discr. App. System Error
%s
Check:
%s

40901:Discr. App. Sys Message
WARNING: A new application or process
has been ordered
A warm start is required to install a
new configuration
Check:
%s

40902:Discrete Application
Task %s:
Error from %.16s. Can't
find the process %.16s.
Check:
Check the installed process(es).

41000:Item source exists
Item source %.16s
already exists. Two item sources may
not have the same name.

41001:Not a valid name
Choose %.16s
or %.16s

41002:Buffer size exceeded
Fatal internal error for item source
%.16s. Try warm start or cold
start. Please report this error.

41003:Item source not defined
The item source object has not been
defined.

41004:Itmsrc internal error
Internal error for item source
%.16s.
Error type: %.25s.

41005:Flush item source first
Item source %.16s must be
flushed before it is used.

41006:Ack item target first
Item target must be acknowledged
before executing the GetItmTgt(s)
instruction again.
Error occured for item source
%.16s.

41007:Item target buffer full
Item target buffer full for
item source %.16s.

41008:Conveyor eio init error
Error in the initialization of the
I/O signal for item source
%.16s, for conveyor
%.16s. Eio signal name
%.16s.

41009:Conveyor does not exist
Error for item source
%.16s.
The conveyor %.16s
does not exist.

41010:No conveyor name given
Error for item source
%.16s.
No conveyor name specified.

41011:Conveyor limits error
Error for item source
%.16s, conveyor
%.16s. The limits are
are incorrectly specified.

41012:Cnv data defined late
Error for item source
%.16s, conveyor
%.16s. The ItmSrcCnvDat
instruction must be called before the
ItmSrcFlush instruction.

**41100:Too many corrections con-
nected.**
Check:
Too many correction descriptors
connected. Max 5 are allowed.

41101:Correction not connected
Can't write to correction descriptor
Check:
Check that the current correction
decriptor is connected.

41102:No corrections connected.
Correction unable to be read.
Check:
No correction descriptor connected.
Check if any correction generator is
connected.

5 Motion error messages

50001: Serious motion error
Not possible to proceed motion control
Check:
Start up the system again

50021:Joint position error
Actual position of joint %s
is too far away from the ordered
position
Check:
Check trim parameters, external
forces or hardware.

50022:Too low DC-link voltage
Check:
Check voltage from Motor On contactors
Replace DC-link

50023:Stop-/Restart error
The stop was made when too many move
instructions were queued for execution.
Restart is not possible
Check:
Check the number of move instructions
with concurrency. Move the program
pointer and start a new movement.

50024:Corner path failure
A corner path was executed as stop point
due to some of the following reasons:
1 Time delay
2 Closely programmed points
3 System requires high CPU-load
Check:
1 Reduce the number of instructions
  between consecutive move instructions
2 Reduce speed, use wider spaced
  points, use /CONC option
3 Increase ipol_prefetch_time

50025:Restart too far from path
Check:
Move back to path.

50026:Singularity or Zone error
1 Robot too close to singularity
2 MoveL to MoveJ corner zone error
Check:
1 Use the joystick to move away from
  the singularity or run a program in
  joint coordinates
2 Use fine point or modify position

50027:Joint Out of Range
Joint %s is out of working range
Check:
Use the joystick to move the joint into
its working range

50028:Jog in wrong direction
Joint %s is out of working range
Check:
Use the joystick to move the joint in
opposite direction.

50029:Robot outside its limits
The robot has reached the configuration
limit for the parallelogram
transmission.
Check:
Use the joystick to move the involved
joint into the working range again.

50030:Robot outside its limits
Jogging was made in wrong direction
when
parallelogram was out of working range
Check:
Use the joystick to move the joint in
opposite direction.

50031:Command not allowed.
System parameters cannot be
changed in MOTORS ON state.
Check:
Change to MOTORS OFF.

50032:Calibration command error
An attempt was made to calibrate while
in MOTORS ON state.
Check:
Change to MOTORS OFF.

50033:Commutation command error
An attempt was made to commutate the
motors in MOTORS ON state.
Check:
Change to MOTORS OFF.

50035:Synchronization error
An attempt was made to synchronize
in MOTORS ON state.
Check:
Change to MOTORS OFF.

50036:Correct regain impossible
Correct regain impossible. A stop
occurred with too many close points
with corner zones. At restart the robot
will move to a point farther forward in
the program.
Check:
Reduce the number of close points,
increase the distance between them or
reduce the speed.

50037:MOTORS ON order ignored
MOTORS ON order ignored since the
previous stop was not yet acknowledged.
Check:
Order MOTORS ON again.

50041:Robot in a singularity
The Robot is too close to a singularity.
Check:
During program execution, use SingArea
instruction or joint interpolation.
During jogging, use axis by axis.

50042:System error
Check:
Increase the distance between close
points and/or decrease speed and/or
change acceleration value.

50050:Position outside reach
Position for IRB joint %.f
is outside working area.
Check:
Check the work object.
Check the joint working range.
Move the joint in joint coordinates.

50052:Joint speed error
The speed of joint %s is too high
relative the ordered speed
Check:
1. Check the tune parameters, external
   forces on the joint and hardware.
2. Reduce programmed speed.

50053:Revolution counter error
Too big difference between the counter
in the serial measurement board and
the expected value in the robot computer
for joint %s
Check:
1. Update the revolution counter
2. Replace serial measurement board
3. Check resolver and cables

50055:Joint load error
Actual torque on joint %s too high
May be caused by incorrect load data,
too high acceleration, high external
process forces, low temperature or
hardware error
Check:
1. Check load data
2. Reduce acceleration or speed
3. Check hardware

System and Error Messages

50056:Joint collision error
Actual torque on joint %s is
higher than ordered while at low
or zero speed.
Check:
May be caused by jam error (the arm
has got stuck) or hardware error.

50057:Joint sync. error
The position of joint %s after
power down/failure is too far away
from the position before the power
down/failure.
Check:
Make a new update of the revo-
lution counter.

50058:Tool coord. sys. error
The z-direction of the tool coordinate
system is almost parallel with the path
direction.
Check:
Change the tool coordinate system to
achieve at least 3 degrees deviation
between z-direction and path direction.

50059:Frame error
The definition of robot
fixed tool is not correct.
Check:
Check the tool and object data.

50060:Frame error
The definition of robot
fixed tool is not correct.
Check:
Check the tool and object data.

50061:Frame error
The definition of robot
fixed tool is not correct.
Check:
Check the tool and object data.

50062:Circle programming error
Start and end positions for the circle
are too close.

50063:Circle programming error
All circle points on a straight line or
the circle position is too close to the
start or end position of the circle or
conflict when selecting reorientation
Check:
Verify the points in the circle.
Check reorientation or split circle
segment in two separate segments.

50065:Kinematics error
The destination of the movement is
outside the reach of the robot or too
close to a singularity.
Check:
Change the destination position.

50066:Robot not active
Attempt to coordinate motion or
calculate position of deactivated
robot %s.
Check:
Activate robot via the Motion Unit key,
then Jogging window, or program.
Check work object and program.

50067:Unit not active
Attempt to coordinate motion or
calculate position of deactivated
single unit %s.
Check:
Activate unit via Motion Unit key,
then Jogging window, or program.
Check work object and program.

50076:Orientation def. error
Orientation is incorrectly defined.
Check:
Make an accurate normalization of
the quaternion elements.

50078:Too many close positions
Too many consecutive closely spaced
positions.
Check:
Increase the distance between
consecutive close positions.

50079:Wrist weaving not possible.
Check:
Use smaller weaving amplitude or a
larger TCP.

50080:Position not compatible.
Position cannot be reached with the
given robot configuration
Check:
Modify the robot position
in the program.

50082:Deceleration limit
Calculation of joint deceleration time
exceeds internal limits for this motion.
You cannot proceed without removing the
cause(s) of this error (see Check).
Check:
Increase path resolution (sys param or
by PathResol for critical movements).
Reduce speed, use fine, increase AccSet,
increase Queue time, avoid singularity
(SingArea\Wrist), inc. dynamic resol.

50083:Speed lowered by system.
The speed has been lowered by the system
due to dynamic limitations.
Check:
Decrease speed and/or do not use close
positions at high speed and/or increase
acceleration (if below 100%).

50085:Too many user frames.
For mech_unit %s more than one
user frame has been defined.
Check:
Take away one user frame or define
one more mech_unit.

50086:Singularity calc. error
Too close to wrist singularity with
respect to numerical resolution
for joint 4 of IRB.
Check:
Change destination position a few
increments.

50087:Singularity problems.
Too close to wrist singularity with
respect to numerical resolution
for joint 6 of IRB.
Check:
Change destination position a few
increments.

50088:Restart not possible.
It is not possible to restart the path
due to a previous error.
Check:
Move the program pointer and start
a new movement.

50089:Weaving changed
The ordered weaving is not achieved due
to: high weaving frequency, not allowed
shift of weave method or that
SingArea/Wrist is used with wrist weave
Check:
Increase weave length or period time.
Don't shift between arm and wrist weave.
Use SingArea/Off with wrist weave.

50091:Restart not possible.
Restart no longer possible. Change of
unit state made restart of program
impossible.
Check:
Move the program pointer and start
a new movement.

50092:Axis computer comm. error
Incorrect response from axis computer
Check:
Check motion configuration parameters.
Check axis computer hardware.

50094:ServoTune not possible.
Tuning is not implemented for the
specified Joint.

50095:Cannot access joint.
Cannot access external joint. Check
configuration and activation of
external Joints.

50096:ServoTune not allowed.
Tuning is not allowed for the
specified joint.

50100:Manipulator error
There are more configuration or
numerical errors in motion domain.
Check:
Correct previous ones and try again.

50101:Manipulator config. error
'%s' is not free
for the param. '%s'
in type '%s' named
'%s'.
Check:
Use another one.
For internal names, see moc_chk.log.

50102:Manipulator config. error
'%s' used in the
parameter '%s' in
type '%s' named
'%s' is not
defined.
Check:
Use another one that is defined or
define the used one.
For internal names, see moc_chk.log.

50103:Num. error in manipulator
The orientation defined by quaternions
including '%s' in
the type '%s' named
'%s' is not
normalized.(SQRSUM =1)
Check:
Check the quaternions and/or recalculate
them.
For internal names, see moc_chk.log.

50104:Num. error in manipulator
The parameter '%s'
in type '%s' named
'%s' is not '%s'.
Check:
Check the value.
For internal names, see moc_chk.log.

50128:Manipulator error
Terminating the topic check for
manipulator due to earlier errors.
Check:
Correct the reported errors and run
topic check again.

50130:Synchronization failed.
Synchronization failed for joint
%s.
Check:
Make a new synchronization.
Restart System.

50131:Calibration failed.
Calibration failed for joint
%s.
Check:
Make a new calibration.
Restart System.

50132:Commutation failed.
Commutation failed for joint
%s.
Check:
Make a new commutation.
Restart System.

50133:Test signal error.
No test signals are available
for the master robot.

50134:Corr. vector warning
Sensor correction vector calculations
failed due to previous error.

50135:SoftAct not possible.
Soft servo is not possible to activate.

50137:Fine point inserted
Corner zone is changed to fine point
Too many consecutive Move instructions
without fine point

50138:Arm check point outside
The robot has reached the limit for arm
check point
Check:
Use the joystick to move the involved
joint into the working range again

50139:Arm check point outside
Jogging was made in wrong direction when
arm check point was out of working range
Check:
Use the joystick to move the joint in
opposite direction.

50140:Payload too large
Heavy payload caused static torque
limit to be exceeded on joint %s
Check:
Check and reduce payload
for arm and/or wrist.
Reduce joint working range to decrease
static torque due to gravity.

50141:Jog or Speed error
1. Jogging error
2. High speed error
3. Robot too close to singularity
Check:
1. Jog with incremental movement
2. Reduce the programmed speed

50142:Manipulator config. error
Configuration of the manipulator failed.
%s
%s
Check:
Check the parameter values under
System parameters:Manipulator.

50143:Robot axes config. error
Actual configuration is not the same
as ordered and/or reorientation of
joint 4/6 is too large.
Check:
Use SingArea_Wrist, ConfL_Off,
modify position or insert
intermediary point.

50144:Displ frame uncertain.
Calibration of displ frame uncertain
1. Wrong TCP
2. Ref. points inaccurate
3. Ref. points badly spaced
Check:
If estimated error is unacceptable:
1. Verify that correct TCP is used.
2. Try more than 3 ref. points.
3. Be careful when positioning robot
   to ref. points.

50145:Kinematic limitation
Kinematic limitation, no solution found.
1. Long segment.
2. Position close to singularity.
3. Joint 1, 2 or 3 out of range.
4. Position outside reach.
Check:
1. Insert an intermediary point to
   reduce the length of the segment.
2. Use MoveAbsJ.
3-4. Check working range.

50146:Restart limitation
Corner path executed as a stop point.
Power fail restart not possible near
the stop point.
Check:
Use finepoint in the Move-instr before
RestoPath, ActUnit, Wait or Stop-instr
to make power fail restart possible.

50147:Power fail restart failed
Re-creation of the path failed
Check:
Move the program pointer and start
a new movement.

50151:MOC_MAILBOX1_ERROR
The axis computer driver failed
to generate a new mailbox 1 interrupt
since the previous interrupt has
not been serviced properly.
Check:
Reload system
Replace robot computer board

50152:MOC_MAILBOX2_ERROR
The axis computer driver failed
to generate a new mailbox 2 interrupt
since the previous interrupt has
not been serviced properly.
Check:
Reload system
Replace robot computer board

50153:Command not allowed
The given instruction, or command, was
not allowed since the robot program was
executing in a hold state.
(%s %d %d)
Check:
Modify program or stop program execution
before issuing command.

50154:Command not allowed
SingArea\Wrist mode interpolation is
not supported for the IRB6400C robot.
Check:
Replace SINGAREA\WRIST instruction
with
SINGAREA\OFF.

50155:Power fail restart failed
Not possible to restart the Move-instr
before RestoPath, ActUnit, Wait or
Stop-instr
Check:
Make program free from MOTION
WARNING
50146 Restart limitation, by changing
the Move-instr to finepoint
Move the program pointer and start
a new movement.

50156:Independent joint error
Joint %s is not configured as an
independent joint.
Check:
Modify the program or configurate
the joint as an independent joint.

50157:Corr. vector warning
Sensor correction vector X calculations
failed due to previous error.

50158:Sensor process missing
Sensor process missing during
initialization.
Named sensor process %s
could not be found or initialized.
Check:
Check process name in motion and
process configuration files.

50159:No external process
Attempt to coordinate motion or
calculate position of single %s
without an external process.
Check:
Check process name in motion and
process configuration files.

50160:Cannot reach position
Programmed position of indep. joint
%s is outside working range and
thus cannot be reached.
Check:
Change the position.
Check the joint working area limits.
Check the used work object.

50161:Singularity area
Robot is close to a singularity.
Work area with kinematic limitations.
Check:
During jogging, use axis by axis.
During program execution,
use MoveAbsJ.

50162:Internal position error
Error caused by internal
numerical limitation
Check:
Reset independant joint
Reduce work area if extended
Remove or separate close points

50163:External Pos adjustment
External Pos adjustment too large.
TCP speed, orientation speed, or
external position speed exceed
allowed robot performance.
Check:
1. Reduce programmed TCP and
   orientation speeds
2. Modify the path
3. WaitWObj closer to sync
4. Run in AUTO

50164:Ind. deactivation error
Independent deactivation error
Deactivation of mechanical unit may not
be done while in independent mode.

50167:Warning: new sync
Warning: a new object sync signal has
arrived while conveyor is active and
program is running.

50168:New sync on %s
New object sync arrived while conveyor
was tracking the previous object.
Cannot track two objects simultaneously
Check:
Reduce speed of conveyor
Increase programmed speed

50170:Process missing
External control process missing during
initialization.
Named process %s
could not be found or initialized.
Check:
Check process name in motion and
process configuration files.

50171:Speed too low
Numerical problem when interpolation
of long segments with low speed and
heavy external axes or
when interpolation close to singularity
Check:
Split segments with long interpolation
time (path_resolution * 4 minutes) or
change to joint interpolation or move
position away from singularity.

50172:MoveJ not allowed
MoveJ not allowed with work object
coordinated with external
position mechanical unit.
Check:
Change interpolation mode or
work object.

50173:Use fine point
Use fine point when changing tool
or work object coordination
when work object is coordinated with
external pos mechanical unit.
Check:
Create a fine point and
then change the tool.

50174:WObj not connected
The WObj is not connected to the
conveyor %s . Robot TCP cannot be
coordinated to work object.
Check:
Check for missing WaitWObj.
Check for DropWObj occuring before end
of coordination.

50175:Conveyor moving %s
Conveyor moving while attempt to
coordinate robot TCP to conveyor work
object while in prohibited mode.
Check:
It is not possible to coordinate to
conveyor while in Manual Reduced Speed,
or stepping in Auto, and the conveyor
is moving.

50176:Conveyor %s not active
Conveyor mechanical unit was not active
when attempt to coordinate robot TCP to
conveyor work object.
Check:
Make sure conveyor mechanical unit is
active. Check for fine point for last
coordinated motion before DeactUnit.

50177:Unable to restart.
Conveyor %s moving while attempting
to restart or before pressing
Stop or stepping through program
Check:
Make sure conveyor is standing still.
Move the program pointer and start
a new movement.

50178:Non optimal movement
Non optimal movement
Required torque too high
Manual adjustment of acceleration or
speed is needed.
Check:
Reduce acceleration (AccSet 50 100) in
this movement, restore it afterwards
(AccSet 100 100). Optimize performance
by search for max acceleration 50-99
Alternatively, reduce speed.

50180:Corr. vector warning
Sensor correction vector calculations
failed due to previous error.

System and Error Messages

50181:Out of coupled range
Joint %s and %s are out of
coupled working range.
Check:
Use the joystick to move joints into
their coupled working range.

50182:Jog in wrong direction
Joint %s and %s are out of
coupled working range.
Check:
Use the joystick to move joints into
their coupled working range.

50183:Robot outside work area.
The robot has reached the
World Zone %s.
Check:
Check the reason of the World Zone.
Use the joystick to move the robot
out of the World Zone if needed.

50184:Corr. vector warning
Sensor correction vector calculations
failed due to previous error.

50185:Corr. vector warning
Sensor correction vector calculations
failed due to previous error.

50186:Coordination error.
Not possible to run robot %s
with coordinated base frame.
Function not installed in this system
Check:
Install the option Advanced Motion.

50187:Coordination error.
Not possible to coordinate user with
robot %s
Function not installed in this system
Check:
Install the option Advanced Motion.

50188:Non optimal movement
Non optimal movement
Required torque too high
Manual adjustment of weave frequency or
amplitude is needed.
Check:
Reduce weave frequency or
weave amplitude in
this movement
Alternatively, reduce speed.

50189:Relay signal not found
The signal %s for relay %s
is not found in the I/O configuration.
The mechanical unit using this relay is
ignored.
Check:
Check I/O signal definitions and System
Parameters definition of Manipulator,
Types: Relay.

50190:Permanent ipol lock error
Scanned no of active joints not equal
expected no of joints.
Check:
Check configuration of unit using
general kinematics.

50191:Too many TCP speed's
The number of TCP speed's in one
segment is too large. Maximum number
of TCP speed's is %d.
Check:
Check if one segment has too many
TCP speed's set or if a sequence of
segments have increasing DipLag.

50192:Jogging error
Jogging is started too soon after
program stop.
Check:
Restart and try again.

50193:Joint sync. error
The speed of joint %s before
power down/failure was too high.
Check:
Make a new update of the
revolution counter.

50194:Internal position error.
Error caused by internal
numerical limitation.
Joint number %2.0f.
Check:
Calculated reference position = %f

50195:Independent move error
Joint %s cannot be moved in
independent mode.

50196:Calibration error.
Points 0 and 1 too close

50197:Calibration error.
Points 0, 1, 2 on a line or
point 2 too close to points 0 or 1

50198:Calibration error.
Internal error
Check:
Report the occurance.

50199:Calibration error.
External joints have been moved
during calibration.
Check:
Avoid moving external joints.

50200:Torque error.
Torque error due to
high speed.
Check:
1 Check load data.
2 Reduce speed.

50201:Orientation outside reach
The error of the programmed orientation
exceeds the acceptance limit.
Check:
1 Adjust robtarget orientation.
2 Adjust/check orientations of currently
used frames: tool frame, base frame,
user frame, object frame...

50202:No dc link configured
The dc-link(%s) and
drive unit(%s) used
by joint: %s is not
connected to same serial link.
Check:
Select another dc-link.
Change serial link for drive unit.
Set the parameter '-no_dc_link'
to TRUE.

50203:Measurement node used
The measurement node for joint
%s is already used.
Check:
Select another node.

50204:Motion supervision
Motion supervision triggered
for joint %s.
Possible causes: collision,
incorrect load definition,
external process forces.
Check:
If load definition incorrect,
use load identification.
If external forces, use RAPID
command or system parameters
to raise supervision level.

50205:Data logger error:
%s
Check:
Solution:
%s

50206:Probe warning
Probe buffer is full.

50207:Add intermediate point
Add intermediate point
not coordinated to external pos
mechanical unit.
when changing conveyor.
Check:
Create an intermediate point
then change the conveyor.

System and Error Messages

50208:Missing function
Friction Compensation can not be
activated for joint %s.
Check:
Install the option Advanced Motion.

50209:Kinematic limitation.
No accepted solution found.
Residual: %ld deg in orientation,
%ld mm in x,
%ld mm in y,
%ld mm in z.
Check:
Insert an intermediary point.
Check singularity.
Increase position and orient. tolerance.
Use MoveAbsJ.
Check working range.

50210:Load identification error
Check:
Possible problem:
Load identification not allowed
for this robot.
Configuraion angle is too small.

50211:External Drive error.
External controlled drives can not
be used without the option
'External Drive'

50212:General kinematics
General kinematics can not
be used without the option
'General Kinematics'

50213:Frame rotation error.
Possibly due to unnormalized
quaternion
or position out of bounds.
Check:
Check the normalization of
input quaternions
or magnitude of input positions.

50214:Config error of work area
Possibly the defined work area
are larger than max allowed area.

50215:Load identification error
Axis %d will move outside
working range.
Check:
Move the axis to a position
further from the working range
limit.

50216:MS configuration failed
EIO signal %s is not configurated
but needed for MS process.
MS coordination will not work.
Check:
Check configuration of EIO signals.

50217:MS restart failed
MS restart failed due to large path
error. Path difference is too large
Check:
Verify that ext ax. speed is the same
for both M and S units.
Reduce speed of external axis.
Reduce weld length before extern axis
motion.

50218:Path not finished
Previous motion path was not finished
before new motion was sent.
Check:
Use StorePath when in Trap routines.
Move the program pointer and start
a new movement.

50219:M/S Communication
M/S communication failure during syn-
chronized welding.
Check:
Check that both robots receive Stops
at the same time,
Check CAN bus communications,
Increase sync_time_factors under
Manipulator: MS_PROCESS.

50220:No input signal
No input signal to contactor relay
for mechanical unit %s
Check:
Ensure that an input signal is
connected and configured.

50221:Conveyor %s
Conveyor outside max dist
min dist limits
Object Dropped
Check:
Check limits or
reduce conveyor speed.

50222:Mismatch type - MechUnit
Mismatch between selected manipulator
type and selected mechanical unit.

50223:To long deceleration
The deceleration time for an axis
is to long
Check:
Check the performance characteristics
for the axes or reduce the speed.

50224:Error when defining load
It is not allowed to define a load
on axis %d for mechanical unit
%s.
Check:
Change axis no or mechanical unit.

50225:Boot safe area inaccur.
System not synchronized.
Check:
Update all revolution counters.

50226:Underrun in reference master.

50227:Test signal error.
Invalid channel number %d.
Check:
Allowed channel numbers are 1 - 12
for test signals and 1 - 6 for
data log signals.

50228:Test signal error.
Unknown test signal number %d.

50229:Test signal error.
Unknown mechanical unit %s.
Check:
Check spelling or configuration.

50230:Test signal error.
Invalid axis number %d for mechanical
unit %s.
Check:
Check mechanical unit and axis number.

50231:Test signal error.
Mechanical unit %s not active.
Check:
Activate mechanical unit before
defining test signals.

50232:Kv saturation
Kv limited to %d for joint %s

50233:Ki saturation
Ki saturated for joint %s
Check:
Reduce Kv or increase Ti

50234:Overflow during logging
An overflow occured when logging
test signals or data log signals.
Check:
Define fewer signals.
Reduce load on main computer.
Reduce network load.

50235:No interrupts received from an
Axis Computer within timeout.
Check:
Replace Axis Computer board(s).

50236:Reference underrun
Reference underrun in Main computer
interrupt routine for Axis computer
connected to connector board %d
Check:
Reduce load on main computer.
Restart controller.
Replace Axis computer board.

50237:Reference task error
Reference task queue full
(Slot id = %d)
Check:
Reduce load on main computer.
Restart controller.
Replace Axis computer board(s).

6 Operator error messages

60001: %s missing
Tool %s is not used in
current program.
Maybe because it has been deleted or
it is not defined.
Check:
Change to another tool using the
Jogging window.

60002:%s missing
Wobj %s is not used in
current program.
Maybe because it has been deleted or
it is not defined.
Check:
Change to another workobject using
the Jogging window.

60003:Directory not created!
The directory %s cannot be created.
Probably, because directory already
exists or the disk is write-protected.
Check:
Check if directory exists or if disk
is write-protected.
Check also if space on disk is enough.

60004:Robot Hold confusion!
The used tool and the used work object
cannot both, at the same time, be held
by robot or be stationary.
Check:
Check the robhold component of the
used tool and work object.

60005:%s missing!
The workobject %s contains
a coordinated mechanical unit which
cannot be found.
Check:
Check the mechanical unit component
of
the workobject.

60006:%s Userframe!
The workobject %s contains
a coordinated mechanical unit which
has no defined userframe.
Check:
Check the mechanical unit component of
the workobject.

60007:Jogging not permitted!
Jogging cannot be done in this mode.
Check:
Release the joystick and enabling
device and repeat.
Check also active mechanical unit.

60008:Tool mass undefined!
Jogging cannot be done if the used tool
has an undefined mass
Check:
Enter a value for the mass, into the
tooldata for the used tool.

60009:Unsynchronized robot!
The robot or external axis are
unsynchronized.
Check:
Synchronize robot or external axis.

60010:Orientation error!
Orientation in %s is unnormalized.
Check:
Check orientation value.

60011:Parameter faults!
Loading of parameters in
%s
cannot be fulfilled.
For reason, see
%s
Check:
Copy the file
%s
to a floppy and examine reasons
using an ordinary text editor!

60012:No Parameters loaded!
There are no parameters in
%s
Check:
Check the file
%s
using an ordinary text editor!

60013:Jogging not permitted!
Jogging of mechanical unit is
not possible.
Unit is not activated.
Check:
Activate the mechanical unit.

60014:Disk is full!
No info is saved in Change Log about
the parameter change because no space
available on disk.
Check:
Try to delete files or
reorganize your disk.

60015:PP cannot be set!
PP cannot be set to routine
'%s' because it has parameters.
Check:
Make a routine which call '%s' or
remove the parameters.

60016:PP cannot be set!
PP cannot be set to routine
'%s' because it resides in a
module which has NOSTEPIN as
module attribute.
Check:
Copy the routine '%s' to
another module or change the
module attribute.

60017:PGM_TELLBACK code %d
Check:
No more information available.

60018:RAPID syntax error!
The program cannot be loaded because of
syntactical error(s).
Check:
A RAPID syntax check program for the
PC
or QuickTeach can be used to detect the
error(s). The file PGMCPL1.LOG on the
internal RAM disk contains information
about the error(s).

60019:Data input error!
The component '%s' in data
type '%s' is not correct.
The limits are
%s!
Check:
Check data and enter the correct
value.

60020:PP cannot be set!
PP cannot be set to routine
'%s' because it is defined as
a trap routine.
Check:
Change the definition for the
routine '%s'
to 'Procedure'.

60021:Cannot show items!
The number of selected items exceeds the
current memory limit specified for this
configuration. The items can thus not
be shown.
Check:
Reduce the number of data or
change the configuration to a memory
board with more memory.

60022:Cannot show all items!
Only %d variables (out of %d)
will be listed.
All variables cannot be shown because
the current memory limit specified for
this configuration will be exceeded.
Check:
Reduce the number of data or
change the configuration to a memory
board with more memory.

60023:Limit ModPos!
You cannot modify this position because
limit modpos is activated with ABS.
ABS, absolute mode, means that the
original position should be saved.
This cannot be done while tuning.
Check:
If executing, stop the program. Modify
the position in the Program Window.
This will create an original position.
This position will thereafter allow
tuning. Limits are set by Limit Modpos.

System and Error Messages

60024:Outside Limits!
The change is either outside the
internal limit 10 mm or exceeds the
limit set by limit modpos parameter
Max Trans.
Check:
A single change cannot exceed 10 mm.
Do the change in smaller steps.
If Limit Modpos is set and the parameter
Max Trans is less than 10 mm this
parameter has to be changed.

60025:Name not allowed!
The name already exist or is a
reserved word.
Check:
Please use an other name. See list of
reserved words in Rapid manual.

60026:Program memory soon full
Save program or take other
appropriate actions.

60027:Cannot calc. tool frame!
It is not possible to calculate the
tool frame with the selected approach
points.
Check:
Select new approach points as accurate
as possible.

60028:Cannot show all signals!
Only %d signals (out of %d)
will be listed.

60029:Cannot show all units!
Only %d units (out of %d)
will be listed.

60030:Too many signals!
Too many signals are selected for the
Most Common list. Only the first %d
will be listed.

60031:Incompatible file!
The version of the configuration file
is not compatible with this system.
Check:
Check the version of the configuration
file.

60032:Cannot calc. user frame!
It is not possible to calculate a
user frame with the selected approach
points.
Check:
Select new approach points as accurate
as possible.

60033:Cannot calc. object frame
It is not possible to calculate an
object frame with the selected
approach points.
Check:
Select new approach points as accurate
as possible.

60034: Volume is not aviable !

60035: Can not save disk is full

60036:File not found !

60037:Cant open/create file !
No file descriptor aviable

60038:Invalid number of bytes !

60039:File already exists

60040:Illegal name !

60041:Can not delete root !

60042:Not file !

60043:Not directory !

60044:Not same volume !

60045:File/directory read only

60046:Root directory if full !

60047:Directory is not empty !

60048:Bad disk !

60049:No lable !

60050:Invalid parameter !

60051:No contig space !

60052:Can not change root !

60053:File descriptor obsolete

60054:Deleted !

60055:No block device !

60056:Bad seek !

60057:Internal error !

60058:File/directory write only

60059:Disk changed !

60060:No disk in driver !

60061:Operator ignored warning!
A warning about lost
calling hierarchy was ignored.
Check:
No action recommended.

60062:Operator ignored warning!
A warning that the current
stack do not have it's base
in the main routine was ignored.
Check:
No action recommended

7 IO & Communication error messages

71000:Bus/Type incompatible
Description\Reason:
- Unit %s has a type
  that isn't compatible with it's bus
Check:
1. Change the bus for the unit
2. or change the unit type

71001:Duplicated address
Description\Reason:
- Same address for unit %s and %s
Check:
1.Check the address
2.Check the bus

71002:Invalid unit type
Description\Reason:
- Unit %s: has an unspecified
  unit type named: %s.
Check:
1.Check the unit type against the one
  specified for the unit

71003:Invalid unit
Description\Reason:
- The unit specified for the signal %s
  is not specified in the unit section
Check:
1.Change the name of the unit
2.Add a new unit to the unit list

71004:Invalid signal length
Description\Reason:
- The length of the digital
  signal %s must be 1
Check:
1.Change the length to 1 or remove
  the statement.

71005:Filter time invalid
Description\Reason:
- Signal %s: The passive filter time
  should be 0 or %d - %d ms
Check:
1.Change the filter time

71006:Filter time invalid
Description\Reason:
- Signal %s: The active filter time
  should be 0 or %d - %d ms
Check:
1.Change the filter time

71007:Logic. value out of range
Description\Reason:
- Signal %s: Logical Max is less or
  equal to Logical Min
Check:
1.Correct the values to be max greater
  than min

System and Error Messages

71008:Phys. value out of range
Description\Reason:
- Signal %s: Physical Max is less or
  equal to Physical Min
Check:
1.Correct the values to be max greater
  than min

71009:Type invalid
Description\Reason:
- Signal %s: the type of signal
  is invalid
Check:
1.Change the type

71010:Signal out of range
Description\Reason:
- Signal %s: the physical signal
  number + length -1 cannot exceed
  max. physical signal number for
  the unit. Maximum value = %d
Check:
1.Change the physical signal number.
2.Change the length.
3.Check the signal type.

71015:Digital Input overflow
Description\Reason:
- Number of digital input channels
  for board %s is greater
  than %d
Check:
1. Reduce the number digital inputs

71016:Digital Output overflow
Description\Reason:
- Number of digital output channels
  for board %s is greater
  than %d
Check:
1. Reduce the number of digital outputs

71017:No activate signal
Description\Reason:
- Missing activate signal for cross
Check:
1. One activate signal must be given

71018:Activate signal overflow
Description\Reason:
-Number of activate signals for
 cross too high
Check:
1. Only one activate signal must
   be given

71019:Missing signal definition
Description\Reason:
-The signal: %s, at cross is
 not defined
Check:
1. Define the signal name
   in signal section

71020:No result signal
Description\Reason:
- Missing result signal
Check:
1. At least one result signal must
   be given

71021:Duplicate cross signals
Description\Reason:
- The signal: %s, appears both as FROM
  and as TO.
Check:
1. The same signal can not be given for
   both FROM and TO

71022:Physical max too high
Description\Reason:
- Signal: %s
- The physical max value > %.3f
Check:
1. Change value in configuration

71023:Physical min too low
Description\Reason:
- Signal: %s
- The physical min value < %.3f
Check:
1. Change value in configuration

71024:Physical value too high
Description\Reason:
- Signal: %s
- Current value = %.1f >
- Maxvalue = %.1f
- Value set to Maxvalue
Check:
1. Change physical max value in
   configuration

71025:Physical value too low
Description\Reason:
- Signal: %s
- Current value = %.1f <
- Minvalue = %.1f
- Value set to Minvalue
Check:
1. Change physical min value in
   configuration

71026:Logical value too high
Description\Reason:
- Signal: %s
- Current value = %.1f >
- Maxvalue = %.1f
- Value set to Maxvalue
Check:
1. Change logical max value in
   configuration

71027:Logical value too low
Description\Reason:
- Signal: %s
- Current value = %.1f <
- Minvalue = %.1f
- Value set to Minvalue
Check:
1. Change logical min value in
   configuration

71033:Dig. input out of range
Description\Reason:
- The number of digital inputs is
  out of range at board address %d
  max inputs are %d
Check:
1. Change the configuration for
   the board

71034:Dig. output out of range
Description\Reason:
- The number of digital outputs is
  out of range at board address %d
  max outputs are %d
Check:
1. Change the configuration for
   the board

71036:Name out of range
Description\Reason:
- The number of characters in
- name %s
- is greater than %d characters or
- the name is missing.
Check:
1. Give a new name that fits within
   the limits.

71037:IO Cross connection fault
Description\Reason:
- The signal %s appears on both
  FROM and TO in the same chain
Check:
1. Correct the configuration for the
cross connections where the signal above
is connected.

71038:IO Cross depth to high
Description\Reason:
- The Cross connection in the same chain
- is too deep.
- First signal name: %s
Check:
1. Make the Cross connection less deep.

71041:Analog output overflow
Description\Reason:
- Number of analog output for
- board, %s is greater than %d.
Check:
1. Reduce the number of analog outputs.

71042:Analog inputs overflow
Description\Reason:
- Number of analog inputs for
- board, %s is greater than %d.
Check:
1. Reduce the number of analog inputs.

71043:Signal type error
Description\Reason:
- The type specified for signal %s
 can't be connected to specified board
Check:
1. Change to another type.
2. Change to another board.

71044:Physical signal overflow
Description\Reason:
- The range of phsig, or length, or
 phsig and length for signal %s is
 greater than %d
Check:
1. Change the physical signal number
2. Change the length.

71045:Filter specification err.
Description\Reason:
- Signal %s : No filter time can be
 specified for this type of signal.
Check:
1. Set filter time to 0 or remove the
  statement.

71046:Scaling error
Description\Reason:
- Signal %s: No scaling can be done.
Check:
1. Remove the scaling statements.

71049:Parameter Invert error
Description\Reason:
- Signal %s: This type of signal
 can't be inverted.
Check:
1. Only digital signals can be inverted.

71050:Cross signal not digital.
Description\Reason:
- Signal %s: Is not a digital signal
Check:
1. Only digital signals can be cross.
  connected.

71052:Cross table full.
Description\Reason:
- The sum of different FROM signals
 added with total sum of TO signals
 must not exceed %d
Check:
1. Reduce the number of signals.

71053:Connection to board down
Description\Reason:
- Can't access the board due to
 communication is down
Check:
1. Check the communication cable to
  the board
2. Check if the board is switched off

71054:Wrong signal type
Description\Reason:
- Signal %s:
 The type of signal is wrong
Check:
1. Change the type

71055:Invalid signal name
Description\Reason:
- Symbol %s: is not defined
Check:
1. Change the symbol name above

71056:Power fail restore full
Description\Reason:
- Symbol %s: could not be setup for
 power failure restore.
 The table for power fail is full.
Check:
1. Increase the table size in
  startup file.
2. Remove some other signal from restore
  list.

71058:No contact with I/O unit
Description\Reason:
- No contact with I/O unit: %s
 on bus: %s
Check:
1. Check the addresses on all
  I/O units connected to the bus
2. Change the address

71059:Error config. Can node
Description\Reason:
- Error when configuring Can node
  connected at node address %d
Check:
1. Correct the configuration for the
   Can node at given address.

71061:I/O bus error
Description\Reason:
- An abnormal rate of errors on
  bus %s has been detected.
Check:
1. Check the bus.
2. Restart System.

71072:No save set on signal
Description\Reason:
- Signal %s
  has not Set the Store attribute to YES
Check:
1. Set the Store attribute.

71073:Error on I/O Bus
Description\Reason:
- An abnormal rate of errors on the
  %s Bus has been detected.
  The connector for External CAN I/O
  has been switched off
Check:
1. Check bus terminators.
2. Check I/O bus for short-circuit.
3. Restart system.

71074:Config. out of range
Description\Reason:
- The IBS starting quarter and rack
  size is out of range for
  board %s
Check:
1. For starting quarter 1 rack size
   must be less than 5

71076:Comm error from rtp1
Description\Reason:
- No response from the
  serial line
Check:
1. Check the device or connection

71077:Comm error from rtp1
Description\Reason:
- Not possible to deliver
  the received message
Check:
1. Check the communication flow

71078:Comm error from rtp1
Description\Reason:
- The response from the device
  has a non valid frame sequence
Check:
1. Check for noise on the serial
   line

71079:Pulsing group output
Description\Reason:
- Pulsing group output not allowed.
Check:
1. ---

71080:Unit type table full.
Description\Reason:
- The number of unit types
  must not exceed %d
Check:
1. Reduce the number of unit types.

71081:Physical table full.
Description\Reason:
- The number of physical signals
  must not exceed %d
Check:
1. Reduce the number of physical
   signals.

71082:Signal table full.
Description\Reason:
- The number of user defined signals
  plus panel signals must not
  exceed %d
Check:
1. Reduce the number of signals.

71083:Symbol table full.
Description\Reason:
- The number of symbols
  must not exceed %d
Check:
1. Reduce the number of symbols.

71084:Triggr table full.
Description\Reason:
- The number of Subcribed signals
  must not exceed %d
Check:
1. Reduce the number of Subcribed
   signals.

71085:Unit table full.
Description\Reason:
- The number of boards
  must not exceed %d
Check:
1. Reduce the number of defined boards.

71090:Invalid unit type.
Description\Reason:
- The vendor id read from
  unit %s doesn't match
  value in unit type configuration
  Configuation: %d   Actual: %d
Check:
1. Change vendor id in configuration.
2. or check module.

71091:Invalid unit type.
Description\Reason:
- The profile read from
  unit %s doesn't match
  value in unit type configuration.
  Configuration: %d   Actual: %d
Check:
1. Change profile in configuration.
2. Check that the type of board is
   correct.

71092:Invalid unit type.
Description\Reason:
- The product code read from
  unit %s doesn't match
  value in unit type configuration.
  Configuration: %d   Actual: %d
Check:
1. Change product code in configuration.
2. or check module.

71093:Invalid unit type.
- The major revision read from
  unit %s doesn't match
  value in unit type configuration.
  Configuration: %d   Actual: %d
Check:
1. Change major revision.
2. or check module.

71094:Too many cross-actors def
Description\Reason:
- The cross-connection has too
  many "From" signals : %s
Check:
1. Check the cross configuration.

71095:Too long cross-actor str
Description\Reason:
- The "From" part in the cross-string
  is too long : %s
Check:
1. Check the cross configuration.

71097:Parameter store error
Description\Reason:
- Signal %s: This type of signal
 can't have store option.
Check:
1. Only digital output signals can
   have store.

71098:NFS server lost
Description\Reason:
- The contact with the NFS server
   '%s' was lost.
Check:
1. Check the NFS server.
2. Check the network connection.
3. Check the configuration.

71099:Trusted NFS server lost
Description\Reason:
- The contact with the trusted
  NFS server '%s'
  was lost.
Check:
1. Check the NFS server.
2. Check the network connection.
3. Check the configuration.

71100:Bus table full.
Description\Reason:
- The number of buses
  must not exceed %d
Check:
1. Reduce the number of buses.
2. Increase the number of buses
   allowed.

71101:Unknown bus name.
Description\Reason:
- Board %s: Unknown bus
  name %s
Check:
1. Change the bus name for the board
   at unit type configuration.

71102:DeviceNet incompatible
Description\Reason:
- Node %d:
  Internal info:
  %s,%d
  (%s)
Check:
1. Disconnect the node from bus
2. Contact ABB.

71103:Error on I/O Bus
Description\Reason:
- An abnormal rate of errors on the
  %s Bus has been detected.
  The connector for Robot CAN I/O
  has been switched off
Check:
1. Check bus terminators.
2. Check I/O bus for short-circuit.
3. Restart system.

71104:Error on I/O Bus
Description\Reason:
- An abnormal rate of errors on the
  %s Bus has been detected.
The connectors for External CAN I/O
and Robot CAN I/O has been switched
off
Check:
1. Check bus terminators.
2. Check I/O bus for short-circuit.
3. Restart system.

71105:Disable group failed
Description\Reason:
- Failed to disable unit %s
  at address %d.%d
Check:
1. Check I/O system parameters
2. Check unit

71106:dsqc344 board failure
Description\Reason:
- Faulty or re-started IBS board
  Board internal error code: %d
Check:
1. Check above error, see IBS manual:
   Firmware Service and Error Messages
2. Update board firmware
3. Replace InterBus-S board

71107:InterBus-S bus failure
Description\Reason:
- Lost contact at address %d.%d
Check:
1. Check InterBus-S bus
   at the above address
2. Restart the system

71108:InterBus-S module failure
Description\Reason:
- The unit %s at address %d.%d
  reported internal unit error
Check:
1. Check the unit at
   the above address
2. Restart the system

71109:InterBus-S module failure
Description\Reason:
- Incompatible definition
  of unit %s
  at address %d.%d!
Check:
1. Check the I/O system parameters
2. Restart the system

71110:InterBus-S module failure
Description\Reason:
- Illegal address "%s" on unit %s
Check:
1. Change the address in the system
   parameters I/O unit configuration.

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71111:Wrong product code.
Description\Reason:
- The product code of unit %s
  doesn't compare to any known id code.
Check:
1. Change product code in configuration.
2. or check module.

71112:Unequal # of units.
Description\Reason:
- Definied number of units is different
  to the one binded to the board.
Check:
1. Change unit definition in
   the configuration.
2. or check the modules.

71113:IBS user command failure
Description\Reason:
- Warning due to: %d
Check:
1. Check the InterBus-S configuration
   according to above error code.

71114:Invalid IP address
Description\Reason:
'%s' is not a valid IP address
Check:
1.Check the Communication configuration.

71115:Invalid subnet mask
Description\Reason:
'%s' is not a valid subnet mask
Check:
1. Check the Communication configuration

71116:Disable & Trust Level = 0
Description\Reason:
Unit '%s' has been configured disabled
with Trust Level set to 0.
This is NOT allowed.
Check:
1. Change the configuration.

71117:Battery supervision res.
Description\Reason:
The battery capacity = %d
Check:

71118:Battery supervision state
Description\Reason:
The battery supervision is in wrong
state .
The state is = %s
Check:

71119:IO-unit table full.
Description\Reason:
- Maximum number of IO-units
  of type %s exceeded.
  Max = %d
Check:
1. Reduce the number of IO-units.

71120:RAP option not installed.
Description\Reason:
- The RAP Communication option has to be
  installed when configuring RAP or
  using SCWrite.
Check:
1. Reboot and install the
   RAP Communication option.

71121:RAP start-up failed.
Description\Reason:
- The initialization of RAP failed.
Check:
1. Check internal log for decription.

71122:Incorrect IP address.
Description\Reason:
- The address '%s'
  in protocol '%s'
  is not a correct IP address.
Check:
1. Change the address.

71123:No matching trans. prot.
Description\Reason:
The transmission protocol '%s'
given for application protocol '%s'
could not be found.
Check:
1. Change the transmission protocol.

71124:Wrong trans prot. for NFS
Description\Reason:
The transmission protocol for
the NFS protocol '%s' must be
TCP/IP.
Check:
1. Change the transmission protocol.

71125:Mount Permission denied
Description\Reason:
Permission was denied to mount
the directory '%s'
on the server '%s'.
Check:
1. Change the User or Group ID.

71126:Directory not exported
Description\Reason:
Mounting directory '%s'
as '%s' failed
since it is not exported on the server
computer '%s',Protocol: '%s'.
Check:
1. Export the directory on
   the server computer.

71127:ID's not the equal
Description\Reason:
The User and Group ID's has to have
the same value for all remote disks
Check:

71128:Ethernet option not inst.
Description\Reason:
- The Ethernet Services option has to be
  installed when remomte mounted disks
Check:
1. Reboot and install the Ethernet
   Services option.

71129:Too many remote disks
Description\Reason:
The maximum number of remote mounted
disks is '%d'.
Check:
1. Reduces the number of remote mounted
   disk.

71130:Too many remote servers
Description\Reason:
The maximum number of servers for
remote mounted disks is '%d'.
Check:
1. Reduces the number of servers

71131:Could not mount directory
Description\Reason:
Mounting directory '%s'
on the computer '%s' failed
Protocol: '%s'.
Check:
1. Check the NFS server setup

71132:Battery supervision block
Description\Reason:
The battery superviosion is blocked
becaurse a power off/on is made.
Will be released %s
Check:

71133:Battery not charged
Description\Reason:
The battery is not charged after
the first charging state.
Check:
1. Check that the batlow signal is
   connected to the DSQC347.
2. Check the battery connections
3. Check the battery.

71134:Parameter value not found
Description\Reason:
Unit %s refers to values(%s)
that don't exists.
Check:
1. Check unit configuration.

71135:Parameter defs. not found
Description\Reason:
Unit type %s refers to
parameter definitions (%s)
that don't exists.
Check:
1. Check unit type configuration.

71136:Parameter Error
Description\Reason:
Parameter %s could not be
downloaded to unit %s
Check:
1. Check unit configuration.
2. Check precceding error messages

71137:Error code from unit
Description\Reason:
The following error was returned:
%s
Check:
1. Check unit parameter configuration.

71138:Unknown Parameter
Description\Reason:
%s is not a valid parameter
for unit %s
Check:
1. Check unit parameter configuration.

71139:Access error from IO
Description\Reason:
- Cannot Read or Write signal %s
  due to communication down.
Check:
1. Check 'No contact with I/O unit'
   report for reason.

71140:Parameter act high error
Description\Reason:
- Signal %s: This type of signal
  can't be set to active high.
Check:
1. Only output signals can be
   set to active high.

71141:Default out of range
Description\Reason:
- The default value for
signal %s is out of range
Check:
1.Change the default value in
  configuration.

71142:Parameter Default error
Description\Reason:
- Signal %s: This type of signal
  can't be assigned a default value
Check:
1. Only output signals can be assigned
default values.

71143:CTS/RTS not allowed
Description\Reason:
- Serie channel %s:
  can't have option RTS/CTS.
Check:
1. Remove the option from configuration.

71144:Enable group failed
Description\Reason:
- Failed to enable unit %s
  at address %d.%d
Check:
1. Check I/O system parameters
2. Check unit

71145:IBS bus deactivated
Description\Reason:
- IBS bus changed into a none
  running mode.
Check:
1. Check the bus and restart the system

71146:Subscribe error
Description\Reason:
- The maxlimit is less then minlimit
  maxlimit = %f minlimit = %f.
Check:
1. Make the correction and try again

71147:No response dsqc344
Description\Reason:
- Access to the dsqc344 is denied
Check:
1. Check dsqc344 board
2. Check dsqc344 internal confiuration
3. Reduce cycle time on the slave unit

71148:No access to dsqc344
Description\Reason:
- Access to the dsqc344 is denied
  due to %d
Check:
1. The dsqc344 is faulty. Replace board
2. Check dsqc344 internal confiuration

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71149:IBS command failure
Description\Reason:
- Incompatible definition
  due to %d!
Check:
1. Check the I/O system parameters
2. Restart the system

71150:The dsqc344 is busy
Description\Reason:
- The response service capability
  is limited due to IBS configuration
Check:
1. Check dsqc344 internal confiuration
2. Change cycle time on the slave unit

71152:InterBus-S bus failure
Description\Reason:
- %s bus failure.
  Lost contact at
  address %d.%d
Check:
1. Check InterBus-S bus
  at the above address
2. Restart the system

71153:Can't access parameter
Description\Reason:
- Unit %s has parameters
  that can't be edited from
  the teach pendant.
Check:
1. Save the EIO configuration to
  a file
2. Use a text editor to change
  the parameters

71154:The unit has no power
Description\Reason:
- Unit %s has no power connected
Check:
1. Attach power to the unit

71155:The unit is faulty
Description\Reason:
- Unit %s has not been correctly
  connected
Check:
1. Diagnose with CMD application
2. Modify the dsqc344 loacal start-up
  procedure
3. Replace the dsqc344 firmware

71156:IPC queue full
Description\Reason:
- The ipc queue %s was
  full, when sending to trap routine.
Check:
1. Restart the system

71157:Invalid app type
Description\Reason:
- Com Unit %s: has an unspecified
  Com app type named: %s.
Check:
1.Check the Com app type against
  the one specified for the Com app

71158:Address out of range
Description\Reason:
- The address of unit %s is out of
  range.
Check:
1.Change the address
2.Check the address syntax

71159:Signal Access illegal
Description\Reason:
- Signal %s:
  The number of characters in
  Access %s
  is greater than %d or name missing.
Check:
1. Give a new Access that fits within
  the limits.

71160:Access level illegal
Description\Reason:
- Signal %s:
  Access level %s in
  group %s is illegal.
- Legal choices all/man/auto/none.
Check:
1. Give a new access level for group
  that fits.

71161:Access name not found
Description\Reason:
- Signal %s
  The Access name %s
  not found in EIO_USER_ACCESS.
Check:
1. Define %s in EIO_USER_ACCESS
  or change Access name.

71163:Signal on internal unit
Description\Reason:
- Signal %s is not allowed
  to connect to %s
  because the unit is internal
Check:
1. Connect the signal to another unit

71164:Internal signal in cross
Description\Reason:
- Signal %s is not allowed
  to be cross connected to
  signal %s
Check:
1. Make sure that none of the signals
   are internal.

71170:Delay table full
Description\Reason:
- The number of delays in a queue is
  greater than %d.
Check:
1.Make another call

71172:Illegal watchdog time
Description\Reason:
- The watchdog time for unit %s
  must be larger than the largest
  min_slave_interval = %d.
Check:
1. Increase the watchdog time

71171:Illegal I/O Unit
Description\Reason:
- The unit type %s used by unit
  %s is a non ABB device
Check:
1. Make sure that the I/O Plus Option
   is installed

71173:Illegal MaxTsdr
Description\Reason:
- The MaxTsdr for unit %s is larger
  than the MaxTsdr for the bus = %d.
Check:
1. Increase MaxTsdr for the bus
2. or set the bus MaxTsdr to -1
3. Check the unit type configuration

71174:Illegal MinSlaveInt
Description\Reason:
- The MinSlaveInt for unit %s is larger
  than the MinSlaveInt for the bus = %d.
Check:
1. Increase MinSlaveInt for the bus
2. or set the bus MinSlaveInt to -1
3. Check the unit type configuration

71175:Illegal Data_Ctrl_Time
Description\Reason:
- The Data_Ctrl_Time must be larger
  than %d (6 * T_WatchDog for
  unit %s)
Check:
1. Increase Data_Ctrl_Time for the bus
   or set the bus Data_Ctrl_Time to -1
   or decrease T_WatchDog for the
   I/O Unit.

71176:Illegal T_TargetRot
Description\Reason:
- The T_TargetRot must be smaller
  than %d (T_WatchDog (%d)
  for unit %s)
Check:
1. Decrease T_TargetRot for the bus
   or set the bus T_TargetRot to -1
   or increase T_WatchDog for the
   I/O Unit

71177:No contact with I/O unit
Description\Reason:
- I/O Unit %s is already locked by
  another master.
Check:
1. Remove the I/O Unit from the other
   masters configuration.
2. Restart the system.

71178:Incorrect User Prm Data
Description\Reason:
- I/O Unit %s reports incorrect
  parameter data.
Check:
1. Modify the User Prm Data according
   to the DP-slaves manual.
2. Restart the system.

71179:Service not supported
Description\Reason:
- I/O Unit %s reports that an
  unsupported functionality
  was requested.
Check:
1. Check the Sync_Req parameter
2. Check the Freeze_Req parameter
3. Restart the system.

71180:Incorrect configuration
Description\Reason:
- I/O Unit %s reports incorrect
  configuration data.
Check:
1. Check all Module parameters
   for the I/O Unit.
2. Restart the system.

71181:Dsqc368 board missing.
Description\Reason:
- ProfiBus DP-master and DP-slave
  board is not connected or is.
  not working properly.
  (internal info: %d).
Check:
1. Connect board.
2. Run board diagnostics.
3. Replace board.

71182:Missing signal name
Description\Reason:
- A signal name was expected at posi-
  tion %d in cross-connection actor
  %s.
Check:
1. Correct the cross-connection syntax
   in the EIO-configuration file.
2. Restart the system.

71183:Missing logical operator
Description\Reason:
- A logical operator was expected before
  %s in cross-connection actor
  %s.
Check:
1. Correct the cross-connection syntax
   in the EIO-configuration file.
2. Restart the system.

71184:Illegal logical operator
Description\Reason:
- A unexpected logical operator found in
  %s at cross-connection actor
  %s.
Check:
1. Correct the cross-connection syntax
   in the EIO-configuration file.
2. Restart the system.

71185:Duplicated name
Description\Reason:
- The name %s has already been
  used. It has either been used as a
  BUS, TYPE, UNIT, or SIGNAL.
Check:
1. Remove one of the names
   in the EIO-configuration file.
2. Restart the system.

71186:Illegal serial channel
Description\Reason:
- The serial channel %s
  was not possible to create.
Check:
1. Remove the option from configuration.

71187:Abnormal rate of errors
Description\Reason:
- An abnormal rate of errors
  on ProfiBus DP-master bus.
  Service IND: %s. Reason: %d
Check:
1. Check bus connections
2. Check terminators.

71188:PBUS disconnected
Description\Reason:
- A major error on bus has been
  detected on ProfiBus DP-master
  bus.
Check:
1. Check previous message for reason
2. A restart is required.

71189:Profibus bus param error
Description\Reason:
- Faulty bus parameters has been
  downloaded into the Profibus system
  Parameter: %s. Value %d.
Check:
1. Change bus parameter

71190:Illegal module definition
Description\Reason:
- Unit %s has zero bytes input and
  output according to the module
  definitions.
Check:
1. Check all Module parameters
   for the I/O Unit.

71191:No receiver sync
Description\Reason:
- Profibus master synchronization error.
Check:
1. Check for short circuits
2. Check cable connections
3. Check termination
4. Bad shilding

71192:Physical IO mapping error
Description\Reason:
- IO Mapping error on unit %s.
  Physical signal %s-%d
  overrides %s-%d
Check:
1. Check configuration for physical
   signal mapping

71193:Physical IO mapping error
Description\Reason:
- IO Mapping error on unit %s.
Check:
1. Check configuration for physical
   signal mapping

71194:Illegal physical signal
Description\Reason:
- Physical signal %d on unit %s.
  is of type %s
  it should be of type AI, AO, DI or DO
Check:
1. Check configuration for physical
   signal type

71195:Illegal I/O Unit
Description\Reason:
- The unit %s is not
  a configured unit
Check:
1. Change the name to an existing unit
2. Add a new unit to the configuration

71196:Invalid encoding type
Description\Reason:
- The encoding type: %s for
  physical signal %s-%d on unit %s
  is invalid.
Check:
1. Change the encoding type in the
   configuration

71197:Signal bitswap error
Description\Reason:
- The NoOfBits and StartBit is not
  valid for bitswap on signal %s-%d
  at unit %s.
Check:
1. Check that NoOfBits and StartBit
   is valid for signal bitswap.
   NoOfBits = 16 or 32
   StartBit = even multiple of NoOfBits

71198:Address out of range
Description\Reason:
- The address of bus %s is out of
  range.
Check:
1.Change the address
2.Check the address syntax

71199:Baudrate out of range
Description\Reason:
- The baudrate of bus %s is out of
  range.
Check:
1.Change the baudrate
2.Check the baudrate syntax

71200:Invalid slave response
Description\Reason:
- I/O Unit %s sends
  invalid slave responses
Check:
1. Check User_Prm_Data
2. Restart the system.

71201:Unknown bus
Description\Reason:
- %s can not be found in the system
Check:
1. Check the bus configuration
2. Check the installed options.

71202:Phys. value out of range
Description\Reason:
- Signal %s-%d at unit %s:
  Physical Max is less or equal to
  Physical Min
Check:
1. Correct the values to be max
   greater than min

71203:Phys. value out of range
Description\Reason:
- Signal %s-%d at unit %s:
  HighAnalog is less or equal to
  LowAnalog
Check:
1. Correct the values to be max
   greater than min

71204:Phys. value out of range
Description\Reason:
- Signal %s-%d at unit %s:
  HighDigital is less or equal to
  LowDigital
Check:
1. Correct the values to be max
   greater than min

71205:Could not mount directory
Description\Reason:
Mounting directory '%s'
on the computer '%s' failed
Protocol: '%s'.
Check:
1. Check the FTP server setup

8 Arcweld error messages

110001: Gas supervision
Check:
Check the welding equipment.

110002:Water supervision
Check:
Check the welding equipment.

110003:Arc supervision
Check:
Check the welding equipment.

110004:Voltage supervision
Check:
Check the welding equipment.

110005:Current supervision
Check:
Check the welding equipment.

110006:Wirefeed supervision
Check:
Check the welding equipment.

110007:Wirestick supervision
Check:
Check the welding equipment.

110008:Arc ignition failed
Check:
Check the welding equipment.

110009:Schedule transfer error
Check:
Define a weld schedule strobe input

110010:Schedule transfer error
Check:
The schedule port was busy with previous
transfer.

110011:Process stopped
Check:
Process was stopped by digital input.

110012:Arc fill ignition failed
Check:
Check the welding equipment.

System and Error Messages

110013:Torch supervision
Check:
Check the welding equipment.

110021:Gas supervision
Seam name: %.16s
Time from weld start: %.16s min
Check:
Check the welding equipment.

110022:Water supervision
Seam name: %.16s
Time from weld start: %.16s min
Check:
Check the welding equipment.

110023:Arc supervision
Seam name: %.16s
Time from weld start: %.16s min
Check:
Check the welding equipment.

110024:Voltage supervision
Seam name: %.16s
Time from weld start: %.16s min
Check:
Check the welding equipment.

110025:Current supervision
Seam name: %.16s
Time from weld start: %.16s min
Check:
Check the welding equipment.

110026:Wirefeed supervision
Seam name: %.16s
Time from weld start: %.16s min
Check:
Check the welding equipment.

110027:Process stopped
Seam name: %.16s
Time from weld start: %.16s min
Check:
Process was stopped by digital input.

110028:Torch supervision
Seam name: %.16s
Time from weld start: %.16s min
Check:
Check the welding equipment.

110029:Arc ignition failed
Seam name: %.16s
Time from weld start: %.16s min
Check:
Check the welding equipment.

110030:Arc fill ignition failed
Seam name: %.16s
Time from weld start: %.16s min
Check:
Check the welding equipment.

110500:Arcitec welddata error
Loading or storing welddata failed.
Max allowed time for operation has
expired.
Check:
Check external equipment.

110501:Arcitec welddata error
Storing welddata failed.
Check:
Check file path and external equipment.

110502:Arcitec welddata error
Loading welddata failed.
Check:
Check file path and external equipment.

110503:Switch is missing
One of the switch parameters %s
or %s has to be defined.
Check:
Define one of the switch parameters.

110504:Value error
Argument %.16s must have an
integer value.
Check:
The value of the argument must be an
exact integer value. The current value
has a fraction part. Change value.

110505:Argument error
Argument %s has a
not allowed negative value.
Check:
Set argument %s to positive.

111000:Weave pattern error
Weave interpolation type error
[Geometric = 0, Rapid = 1]
Check:
Adjust weave parameters

111001:Weave pattern error
Weave pattern shape error
[No shape = 0, Zig-zag shape   = 1]
[V-shape = 2, Triangular shape = 3]
Check:
Adjust weave parameters

111002:Weave pattern error
Weave pattern cycle length error
(0 - 1) [m]
Check:
Adjust weave parameters

111003:Weave pattern error
Weave pattern cycle time error
(0 - 100) [s]
Check:
Adjust weave parameters

111004:Weave pattern error
Weave pattern width error
(0 - 1) [m]
Check:
Adjust weave parameters

111005:Weave pattern error
Weave pattern height error
(0 - 1) [m]
Check:
Adjust weave parameters

111006:Weave pattern error
Weave pattern left dwell error
(0 - 1) [m]
Check:
Adjust weave parameters

111007:Weave pattern error
Weave pattern center dwell error
(0 - 1) [m]
Check:
Adjust weave parameters

111008:Weave pattern error
Weave pattern right dwell error
(0 - 1) [m]
Check:
Adjust weave parameters

111009:Weave pattern error
Weave pattern bias error
(-1 - 1) [m]
Check:
Adjust weave parameters

111010:Weave pattern error
Weave pattern direction angle error
(-PI/2 - PI/2) [rad]
Check:
Adjust weave parameters

111011:Weave pattern error
Weave pattern tilt angle error
(-PI/2 - PI/2) [rad]
Check:
Adjust weave parameters

111012:Weave pattern error
Weave pattern rotation angle error
(-PI/2 - PI/2) [rad]
Check:
Adjust weave parameters

111013:Weave pattern error
Weave pattern horizontal offset error
(-1 - 1) [m]
Check:
Adjust weave parameters

111014:Weave pattern error
Weave pattern vertical offset error
(-1 - 1) [m]
Check:
Adjust weave parameters

System and Error Messages

111015:Weave pattern error
Weave pattern sync condition left error
(0 - 100) [%]
Check:
Adjust weave parameters

111016:Weave pattern error
Weave pattern sync condition right error
(0 - 100) [%]
Check:
Adjust weave parameters

111017:Weave pattern error
Forbidden combination of bias and shape
Bias only allowed for Zig-zag shape
Check:
Adjust weave parameters

111018:Weave pattern error
Forbidden combination of bias and width
Bias must be less than half the width
Check:
Adjust weave parameters

111019:Weave pattern error
Forbidden combination of dwells and
cycle length
Dwells must be less than cycle length
Ramp slope (amplitude/length) is limited
Check:
Adjust weave parameters

112000:Board eipaw error
Incorrect digital output length
Check:
Change digital output length to 1

112001:Board eipaw error
Incorrect schedule port length
Check:
Change shedule port length to %.16s

112003:Board eipaw error
Incorrect wirefeeder port length
Check:
Change length

112004:Board eipaw error
Schedule number zero is not allowed.
Previous number will still be active.

112500:Arcweld MMC
Original value is zero.
Revert causes present value to be zero.
Revert to zero is prohibited.
Check:
Revert to zero can be performed from
the ArcWare menu when the program is
stopped.

113000:Equipment config error
Check:
AW and EIO configurations do not match

114000:Weldguide error
Check:
Check weldguide parameters
and equipment

115000:Arcitec Data Error
Invalid parameter_id: %.16s
detected.
Check:
Check Arcitec configuration file or
Power Source external communication.

115001:Arcitec Data Error
Invalid unit_id: %.16s
detected.
Check:
Check Arcitec configuration file or
Power Source external communication.

115002:Arcitec Data Error
Invalid transmission length:
%.16s detected.
Check:
Check Arcitec configuration file or
Power Source external communication.

115003:Arcitec Data Error
Invalid selection_id: %.16s
detected.
Check:
Check Arcitec configuration file or
Power Source external communication.

115004:Arcitec Data Error
Arcitec systems with different units.
%.16s and %.16s.
Check:
Check Arcitec configuration file.

115005:Arcitec Data Error
Units not defined for Arcitec system.
Check:
Check Arcitec configuration file.

115006:Arcitec Data Error
Illegal number: %.16s
of tuning parameters.
Check:
Check Arcitec configuration file.

116000:Track error
Check:
Check joint definition

116001:Track start error
Check:
Check joint definition

116002:Track max path corr error
Check:
Check joint definition

116003:Track communication error
Check:
Check hardware

117001:Welding equipment error
EPROM checksum error in Welddata Unit
detected at power up.
Check:
EPROM in Welddata Unit is faulty.
Running with this error gives
unpredictable result.
Exchange EPROM.

117002:Welding equipment error
Internal RAM read/write error in
Welddata Unit detected at power up.
Check:
At least one memory cell in internal
microprocessor memory failed in read
/write test. Running with this error
gives unpredictable result.
Replace Welddata Unit.

117003:Welding equipment error
External RAM read/write error in
Welddata Unit detected at power up.
Check:
At least one memory cell in external
microprocessor memory failed in read
/write test. Running with this error
gives unpredictable result.
Replace Welddata Unit.

117004:Welding equipment error
DC supply voltage for 5 Volt regulator
in Welddata Unit has been down.
Check:
Indicates that there is a problem in
power supply but the function is
probably not affected. Check incoming
power supply to Welddata Unit.

117012:Welding equipment error
Welddata Unit CAN-controller for
internal bus is in WARNING state.
Check:
Change data several times or reset
welding equipment with power switch.
If the error do not disappear, check
bus connections and/or exchange
Welddata Unit.

117013:Welding equipment error
Welddata Unit CAN-controller for
external bus is in WARNING state.
Check:
Change data several times or reset
welding equipment with power switch.
If the error do not disappear, check
bus connections and/or exchange
Welddata Unit.

117014:Welding equipment error
Welddata Unit CAN-controller for
internal bus is in BUS-OFF state.
Check:
Reset welding equipment with power
switch. If the error do not disappear,
check bus connections and/or exchange
Welddata Unit.

System and Error Messages

117015: Welding equipment error
Welddata Unit has detected that a received internal CAN message was lost (Overwritten by a later message).
Check:
Reset welding equipment with power switch.

117016: Welding equipment error
Welddata Unit has detected that a received external CAN message was lost (Overwritten by a later message).
Check:
Reset welding equipment with power switch.

117017: Welding equipment error
Welddata Unit lost contact with Wirefeed Unit.
Check:
Check connection cable between Welddata Unit and wirefeed control board, check power supply to wirefeed control board.

117018: Welding equipment error
Welddata Unit has lost contact with Olivia Unit.
Check:
Check connection cable between Welddata Unit and Olivia unit, check power supply to Olivia Unit

117019: Welding equipment error
Non-volatile RAM data value failure detected in Welddata Unit at power up. Checksum error.
Check:
Probably caused by low memory backup battery voltage. Welding equipment will be reset to a default state. Data in Welddata Unit will be lost. Possible to run without limitations.

117020: Welding equipment error
Non-volatile RAM data value failure detected in Welddata Unit at power up. Non numeric setting parameter out of range.
Check:
Welding equipment will be reset to a default state. Data in Welddata Unit will be lost. Possible to run without limitations.

117021: Welding equipment error
Invalid combination of non-numeric setting parameters in Welddata Unit detected at power up.
Check:
Welding equipment will be reset to a default state. Data in Welddata Unit will be lost. Reset welding equipment with power switch.

117022: Welding equipment error
CAN-bus (external) transmit buffer overflow in Welddata Unit.
Check:
Welddata Unit are unable to transmit data at the needed rate. Could be caused by unnormal occupation on the bus. Reset welding equipment with power switch.

117023: Welding equipment error
CAN-bus (external) receive buffer overflow in Welddata Unit.
Check:
Welddata Unit are unable to process received messages at the needed rate. Reset welding equipment with power switch.

117024: Welding equipment error
Fragments not in number order when Welddata Unit received a fragmented message.
Check:
The parts of a fragmented message were not received in proper order. A weld data block transmission has been faulty received. Reset welding equipment with power switch.

117025:Welding equipment error
Incompatible format of weld data block.
Welddata Unit received data that is
stored in another program version with
other format version.
Check:
Find data with correct version or enter
new data.

117026:Welding equipment error
Program execution error.
Watch dog in Welddata Unit program
activated.
Check:
Reset welding equipment with
power switch.

117027:Welding equipment error
Undocumented Welddata Unit error.
Check:
Request additional information from
ESAB/ABB.

117028:Welding equipment error
Undocumented Welddata Unit error.
Check:
Request additional information from
ESAB/ABB.

117029:Welding equipment error
Undocumented Welddata Unit error.
Check:
Request additional information from
ESAB/ABB.

117201:Welding equipment error
EPROM checksum error in Powersource
Control Unit.
Check:
EPROM in Powersource Control Unit is
faulty. Running with this error gives
unpredictable result.
Replace EPROM.

117202:Welding equipment error.
Internal RAM read/write error in
Powersource Control Unit detected at
power up.
Check:
At least one memory cell in internal
microprocessor memory failed in read
/write test. Running with this error
gives unpredictable result.
Replace Powersource Control Unit.

117204:Welding equipment error
DC supply voltage to 5 Volt regulator in
Powersource Control Unit has been down.
Check:
Indicates that there is a problem in
power supply but the function is
probably not affected. Check incoming
power supply to Powersource Control Unit

117205:Welding equipment error
High DC inverter bus voltage. Hardware
will shut down inverter till voltage
comes down to normal.
Check:
Might be caused by high mains impedance
or transients, possible to restart
welding as soon as voltage has dropped
below limit.

117206:Welding equipment error
Temperature in power source heatsink too
high. Inverter is shut down until
temperature switch is closed again.
Check:
Ensure that there is no obstacle that
reduces the cooling airflow that passes
through the heatsink of the powersource.
Wait until temperature switch is closed.

117207:Welding equipment error
High current in inverter circuit. Might
be caused by component failure.
Check:
Reset welding equipment with power
switch. Check that the power source does
not consume unnormal high current
without start command. If so: there is
a component failure.

System and Error Messages

117208:Welding equipment error
PCB supply voltage 15VC on Powersource
Control Unit to high or to low.
Check:
Replace Powersource Control Unit.

117209:Welding equipment error
PCB supply voltage -15V on Powersource
Control Unit to high or to low.
Check:
Replace Powersource Control Unit.

117210:Welding equipment error
PCB supply voltage 15VB on Powersource
Control Unit to high or to low.
Check:
Replace Powersource Control Unit.

117211:Welding equipment error
Long term difference between requested
and actual weld current value.
Check:
Hardware problem in current servo system
(Power source control board or inverter
block) or unnormal load conditions
(= bad welding).

117212:Welding equipment error.
Internal CAN communication failure CAN
circuits in Powersource Control Unit
is in WARNING state.
Check:
Change data several times or reset
welding equipment with power switch. If
the error do not disappear, check bus
connections and/or exchange Powersource
Control Unit.

117215:Welding equipment error
Powersource Control Unit has detected
that a received internal CAN message was
lost (overwritten by a later message).
Check:
Reset welding equipment with power
switch.

117226:Welding equipment error
Program execution error.
Watch dog in Powersource Control Unit
program activated.
Check:
Reset welding equipment with
power switch.

117227:Welding equipment error
Undocumented Powersource Control Unit
error.
Check:
Request additional information from
ESAB/ABB.

117228:Welding equipment error
Undocumented Powersource Control Unit
error.
Check:
Request additional information from
ESAB/ABB.

117229:Welding equipment error
Undocumented Powersource Control Unit
error.
Check:
Request additional information from
ESAB/ABB.

117301:Welding equipment error
EPROM checksum error in Wirefeed unit
detected at power up.
Check:
EPROM in Wirefeed unit is faulty.
Running with this error gives
unpredictable result.
Exchange EPROM.

117302:Welding equipment error
Internal RAM read/write error in
Wirefeed Unit detected at power up.
Check:
At least one memory cell in internal
microprocessor memory failed in read
/write test. Running with this error
gives unpredictable result.
Replace Wirefeed Unit.

117304:Welding equipment error
DC supply voltage for 5 Volt regulator
in Wirefeed Control Unit has been down.
Check:
Indicates that there is a problem in
power supply but the function is
probably not affected. Check incoming
power supply to Wirefeed Control Unit.
Reset welding equip. with power switch.11

117308:Welding equipment error
PCB supply voltage 15V on Wirefeed
Control Unit to high or to low.
Check:
Check incoming power supply from
transformer. Reset the welding equipment
with power switch. If the error do not
disappear, replace Wirefeed Control Unit

117309:Welding equipment error
PCB supply voltage 24V on Wirefeed
Control Unit to high or to low.
Check:
Check incoming power supply from
transformer. Reset the welding equipment
with power switch. If the error do not
disappear, replace Wirefeed Control Unit

117311:Welding equipment error
Long term difference between requested
and actual wirefeed velocity. Speed
fault, speed deviated $> \pm 1.5$ m/min
during time longer than time in
configuration
Check:
Check MotorControlErrorTimeLimit in
Wirefeed Control configuration.
Hardware problem in wirefeed servo
system or voltage drop in 42 V AC
supply.

117312:Welding equipment error
Internal CAN communication failure
CAN circuits in Wirefeed Unit is in
WARNING state.
Check:
Change wirefeed speed several times
or reset welding equipment with power
switch. If the error do not disappear,
check bus connections and/or exchange
Wirefeed Unit.

117315:Welding equipment error
Wirefeed Unit has detected that a
received internal CAN message was lost
(overwritten by a later message).
Check:
Reset welding equipment with power
switch.

117326:Welding equipment error
Program execution error.
Watch dog in Wirefeed Unit program
activated.
Check:
Reset welding equipment with
power switch.

117327:Welding equipment error
Undocumented Wirefeed Unit error.
Check:
Request additional information from
ESAB/ABB.

117328:Welding equipment error
Undocumented Wirefeed Unit error.
Check:
Request additional information from
ESAB/ABB.

117329:Welding equipment error
Undocumented Wirefeed Unit error.
Check:
Request additional information from
ESAB/ABB.

117500:File error
Failed open file.
File name unknown.
Check:
Check file name.

117501:File error
Failed writing to file.
Check:
Check file name.

117502:File error
Failed reading from file.
Check:
Check file name.

System and Error Messages

117503:Illegal schedule number
Schedule number %.16s
is not allowed.
Check:
Change schedule number.

117504:Communication error
Message header form Arcitec
power source unknown.
Check:
Check connection to power source.
Check Arcitec configuration file.

117505:Communication error
Arcitec power source is not responding.
Check:
Check connection to power source.

117506:Communication error
Messages from Arcitec power source are
not possible to evaluate.
Messages are too short.
Check:
Check connection to power source.
Check Arcitec configuration file.

118000:Ext CAN com failure
Too many requests without response
Check:
Check communication configuration

118500:Arcitec tuning error
There are no Arcitec system defined.
Check:
Define Arcitec system or do not write
towards Power Source.

118501:Arcitec tuning error
Parameter does not exist.
Check:
Change parameter identity.

118502:Arcitec tuning error
Parameter must be numerical.
Check:
Change parameter identity.

118503:Arcitec tuning error
Parameter value outside limits.
Check:
Change parameter value.

119000:Installation error
External axes are not allowed in this
type of robot configuration
Check:
Remove mechanical units

119500:Communication failure
Master slave data transfer failed
Check:
Restart the robots

119501:Master slave IO error
%.16s is not defined
Check:
Check configuration

119502:Master slave missmatch
Both robots master in seam %.10s
Check:
Check robot programs

119503:Master slave missmatch
Both robots slave in seam %.10s
Check:
Check robot programs

119504:Start point missmatch
in seam %.10s
Check:
Check robot programs

119505:End point missmatch
in seam %.10s
Check:
Check robot programs

119506:To short execution time
in seam %.10s
Check:
Check robot programs

119507:Restart not possible
Restart not possible after switching
mech units.
Move the PP before starting

119508:Weld speed modified
in MsArc instruction %.10s of seam %.10s
Programmed, Actual: %.20s

119509:External axis modified
in MsArc instruction %.10s of seam %.10s
Programmed, Actual: %.20s

119510:Seam name not found
Seam %.20s not found
Check:
Check the seam setup table

9 Spotweld error messages

120001: Spot weld system error
Spot weld proc not idle
Check:
Set the process state defined by SwInit
to idle

120002: Spot weld system error
Parameter %s

120003:SwStart Timeout negative

120004:SwInit Interrupt negative

120005:ProcId. The reason is:
-ProcId does not correspond to the
 value given from SwInit
-The spot weld process has been
 cancelled

120006:Spot weld comm. error
Reason: %s

120007:Comm. error
Response slower than poll rate

120008:No more BOSCH connection

120010:Spot gun error
Reason:%s

120011:Spot gun bad config.
Reason: %s

120012:IO signal missing
Check:
1.Configure the mandatory
signals used

120013:PERS var missing
the swtimer.sys module doesn't
fit with this kind of gun
Check:
2.Replace it

120014:Error Number %d
Check:
See Nc gun manual

120057:Gun jog. forbidden
Gun jogging is not allowed
when axis not synchronised
Check:
1.Axis calibration state

120058:Gun Calibration Ok

120060:Gun Position Error
Gun can't reach the position
reference
Check:
1.The drive for power on
2.The encoder
3.Mechanical parts or stuck tips

120061:Gun refer. overrun
Swit timer can't consume
the position reference received
Check:
1.Swit timer is welding and a move
instr. is executing concurrently

120062:Gun Force error
Gun can't apply the force
reference
Check:
1.Make a gun init
2.Drive and force sensor calibration

120063:Gun Refer. underrun
Swit timer has no more
reference to consumme
Check:
1.Serial link and comm log error

120064:Gun Force sensor fault
force sensor out of
order
Check:
1.Force sensor wiring
2.Change sensor

120065:Gun motor overcurrent
motor current too great
Check:
1.Drive calibration
2.Mechanical unit or obstacle

120066:Gun reference fault
gap between references
too great
Check:
1.Robot or gun calibration
2.Gun position

120067:Gun command not allowed
Motion forbidden during
an action
Check:
1.Wait until the end of
the action before ordering new one

120070:Gun drive fault
fault detected by drive unit
Check:
1.drive unit leds

120075:Gun encoder error
Check:
1.Encoder wring

120084:Gun wrong pos computed
inconsystency between revolution
counter and encoder value
Check:
1.Drive and swit measurement bus
2.Make a gun first init

120085:Gun revol. counter error
Check:
1.Encoder wiring

120090:Gun not calibrated
No calibration done or lost
Check:
1.Make a gun first init

10 Paint error messages.

130001: Equipment error.
Paint process and motion stopped.
Check:
Check the paint equipment.

130002:Equipment error
Paint process stopped.
Check:
Check the paint equipment.

130003:Trig plane error
In PaintL %s: One trig plane, %s,
are defined outside the programmed
path.
Check:
Change eventdata or reprogram path.

130004:Trig plane error
In PaintL %s: Two trig planes, %s
and %s, are defined outside the
programmed path.
Check:
Change eventdata or reprogram path.

130005:Trig plane error
In PaintL %s: Three trig planes, %s,
%s, and %s, are defined outside the
programmed path.
Check:
Change eventdata or reprogram path.

130006:Trig plane error
In PaintL %s: Four trig planes, %s,
%s, %s and %s, are defined outside the
programmed path.
Check:
Change eventdata or reprogram path.

130007:Trig plane error
In PaintL %s: Four trig planes, %s,
%s, %s and %s and more are defined
outside the programmed path.
Check:
Change eventdata or reprogram path.

131000:Argument error.
The argument is not an integer.
Check:
Change the argument to an integer.

131001:Argument error.
The argument is not an array.
Check:
Change the argument to an array.

131002:Argument error.
The argument is not a persistent
variable.
Check:
Change the argument to a persistent.

131003:Argument error.
The array argument has too many
dimensions.
Check:
Change the array to one dimension.

131004:Brush table error.
Only brush table %s is allowed.
Check:
Change to allowed brush table.

131005:Brush number error.
Only brush numbers less than or
equal to %s is allowed.
Check:
Change to allowed brush number.

132000:Brush number error.
The brush number is outside the limits
for the activated brush table.
Check:
Change argument within limits.

132001:Brush table error.
There is no brush table activated.
Check:
Activate a brush table.

132500:Unable to open symbol.
Output for symbol %s not found.
NOTE: No paint-related outputs availa-
ble
    due to this error.
Check:
1. Output for symbol not defined.
2. Output for symbol has wrong name.
3. Internal problem (memory etc..)
   Try a restart.

132501:Paint System not inst.
Paint System not available
or not installed.
Check:
PaintWare process not activated, due to
incomplete Paint System configuration.
1. Use IPS option diskette to install.
2. Custom-configure Paint System
using the Teach Pendant.

System and Error Messages