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1 Operational error messages

10002: 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 confirmed

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 %1%%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 %1%%s has erased a program.
10043: Restart failed
The task %1%%s can’t restart
10044: Program Pointer updated
The task %1%%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 %1%%s %s
10050: Execution cancelled
The restart will clear the execution in task %1%.16s of a %s
10051: Event routine error
The task %1%%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 %1%%s is ready
10071: Backup error
Error during the backup of %s
Check:

10072: Restore step ready
The restore %s is ready

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

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
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.

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: Synchronization rejected.**
Synchronization 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 doesn’t exist.

20159: **No System Output signal**
A system output has been declared to a signal that doesn’t 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.
System and Error Messages

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 temperature 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.
**System and Error Messages**

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

20555: Collision sensor active
Status active when digital collision sensor on MCOB is active.
Check:
Check the collision 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 transfer
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
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
**System and Error Messages**

**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 module 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 simultaneously 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 serial link in loopback mode.
Check:
Replace Axis Computer board

**33414: Loopback error**
Error in drive system %d at connector board %d when testing serial link in loopback mode.
Check:
Replace Axis Computer board
33415: Drive system error
Error in the drive system %d at connector board %d when testing serial link in normal mode
Check:
- Check serial 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 measurement
Error in measurement system %d at connector board %d when testing serial link in normal mode.
Check:
- Check serial 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 binary file %s
Internal (English only):
- %s
Check:
- Restart controller
- Replace Axis computer board
- 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 computer program %s not found.
Check:
- Reinstall the system

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

33507: Feedback position error
Feedback 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) received from axis computer connected to connector board %d.
Check:
- Restart controller
- Replace Axis computer board
33509: Message queue error
Message queue in Axis computer connected
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 resolver 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 addr. conflict
More than one axis computer board connected 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
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<td>Check: Replace main computer board</td>
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37040: Main computer error
Check:
Replace main computer board

37041: Main computer error
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37042: Main computer error
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37043: Main computer error
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37044: Main computer error
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37045: Main computer error
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37046: Main computer error
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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
%.f V is out of tolerance
Check:
1. Check Power supplies.

37053: Battery Voltage error
Main CPU Board Battery output (%.f 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. 24V SYS 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.

37073: **Battery 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
System and Error Messages

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 transmission 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.
System and Error Messages

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. measurable, 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 a single communication error in serial link to/from drive system %d.
Accumulated errors since warmstart: %d.
Check:
- Check serial link.

39234: Drive Sys. Com. Error
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.

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.
System and Error Messages

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 occurrence 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 writable.
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.
**System and Error Messages**

**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 required.

**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.
System and Error Messages

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 '+' and '-' operators 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 '/' or '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.
System and Error Messages

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.
System and Error Messages

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.
**System and Error Messages**

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.
**System and Error Messages**

**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.

**40084:** 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.
System and Error Messages

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.
**System and Error Messages**

**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
**System and Error Messages**

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.
System and Error Messages

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.
**System and Error Messages**

### 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.
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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
System and Error Messages

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:
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.)

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.

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".

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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 faulty 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 IDDelete.

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".
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.
**System and Error Messages**

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 temporary 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 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.

40674: 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.

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
Check:
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 %s 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 %s: 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 orientation), that needs to be MODPOS.

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

40720: Alias IO installation
The task %s, could not refresh all alias IO
System and Error Messages

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:
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.
System and Error Messages

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.
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.
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

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

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

40746: Parameter error
Task %.16s:
%.16s TRUE in parameter %.16s in combination with conveyor coordination.
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.
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 connected.
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 descriptor 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.
System and Error Messages

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.

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 revolution 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.
**System and Error Messages**

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 configurated as an independent joint.
Check: Modify the program or configure 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.

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.

50162: Internal position error
Error caused by internal numerical limitation
Check: 1. Reduce programmed TCP and orientation speeds
2. Modify the path
3. WaitWObj closer to sync
4. Run in AUTO

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 occurring 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 occurrence.

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 configurated  
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 intermediate 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 synchronized 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.
System and Error Messages

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 occurred 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!
System and Error Messages

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 available!

60035: Can not save disk is full

60036: File not found!

60037: Cant open/create file!
No file descriptor available

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 label!

60050: Invalid parameter!

60051: No contiguous 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
System and Error Messages

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.
System and Error Messages

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.
System and Error Messages

71084: Triggr table full.
Description\Reason:
- The number of Subscribed 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
  Configuration: %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.
System and Error Messages

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:
- Defined 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 description.

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 remote 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 supervision is blocked because 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 preceeding 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 configuration
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 configuration
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 configuration
  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 local 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.
System and Error Messages

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 position %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.
**System and Error Messages**

**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
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.
### System and Error Messages

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 schedule 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.
System and Error Messages

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 Welldata Unit detected at power up.
Check:
EPROM in Welldata Unit is faulty.
Running with this error gives unpredictable result.
Exchange EPROM.

117002: Welding equipment error
DC supply voltage for 5 Volt regulator in Welldata 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 Welldata Unit.

117003: Welding equipment error
External RAM read/write error in Welldata 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 Welldata Unit.

117004: Welding equipment error
Welldata 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 Welldata Unit.

117012: Welding equipment error
Welldata 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 Welldata Unit.

117013: Welding equipment error
Welldata 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 Welldata Unit.

117014: Welding equipment error
Welldata 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 Welldata Unit.
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. Welldata 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 Welldata Unit program activated.
Check:
Reset welding equipment with power switch.

117027: Welding equipment error
Undocumented Welldata Unit error.
Check:
Request additional information from ESAB/ABB.

117028: Welding equipment error
Undocumented Welldata Unit error.
Check:
Request additional information from ESAB/ABB.

117029: Welding equipment error
Undocumented Welldata 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.

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 > ±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 mismatch
Both robots master in seam %.10s
Check:
Check robot programs

119503: Master slave mismatch
Both robots slave in seam %.10s
Check:
Check robot programs

119504: Start point mismatch
in seam %.10s
Check:
Check robot programs

119505: End point mismatch
in seam %.10s
Check:
Check robot programs

119506: Too 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
System and Error Messages

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:
1. Drive calibration
2. Mechanical unit or obstacle

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 consume
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 wiring

120084: Gun wrong pos computed
-- inconsistency 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

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-
bale
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.