

MANUAL

Connecting ArtiMinds RPS with KUKA Robots

Quick Start Guide

Version 2

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Contact

Support:

support@artiminds.com

Sales:

sales@artiminds.com

ArtiMinds Robotics GmbH
Albert-Nestler-Str. 11
76131 Karlsruhe, Germany

Managing Directors: Dr.-Ing. Sven R. Schmidt-Rohr, Dr.-Ing. Rainer Jäkel
Registration Court: Amtsgericht Mannheim
Commercial Register Number: HRB 717563
VAT Number under § 27a UStG: DE290656974

Content

1	Overview of the KUKA Robot System.....	3
2	Prerequisites.....	6
2.1	Supported Platforms.....	6
2.2	Required Technology Packages.....	6
3	Installation.....	7
3.1	ArtiMinds Robot Programming Suite (RPS).....	7
3.2	ArtiMinds Learning and Analytics for Robots (LAR).....	7
3.3	Usage of Force-Torque Sensor.....	7
4	Configuration.....	8
4.1	Network Setup.....	8
4.2	Network Drive Setup.....	9
4.2.1	KUKA Robot.....	9
4.2.2	Computer.....	11
4.3	KUKA Directory Loader.....	12
4.4	KUKA Robot Sensor Interface (RSI).....	13
4.4.1	Computer.....	14
4.4.2	KUKA Robot.....	16
4.5	ArtiMinds Robot Programming Suite (RPS).....	16
4.5.1	Coordinate Systems Setup.....	16
4.5.2	Network setup.....	17
4.5.3	RPS Settings Pages.....	19
4.5.4	Network Tab.....	20
4.5.5	Payload Tab.....	21
4.5.6	Technology Packages Tab.....	21
4.5.7	Force Control Tab.....	22
4.5.8	Custom Code.....	22
4.5.9	Miscellaneous.....	22
4.6	ArtiMinds Learning and Analytics for Robots (LAR).....	23
4.6.1	Local Mode.....	24
4.6.2	Mixed Mode.....	26
4.6.3	Distributed Mode.....	27
5	Operations.....	33
5.1	Copying programs to the robot.....	33
5.1.1	ArtiMinds RPS.....	33
5.1.2	KUKA robot.....	33
5.2	Teaching/Demonstrations.....	33
5.3	Change IP adress of the connected PC (with ArtiMinds RPS).....	34
5.4	Live data streaming with the headless RPS (hRPS).....	35
7.	Troubleshooting.....	36
Notes.....		39
Changelog.....		40

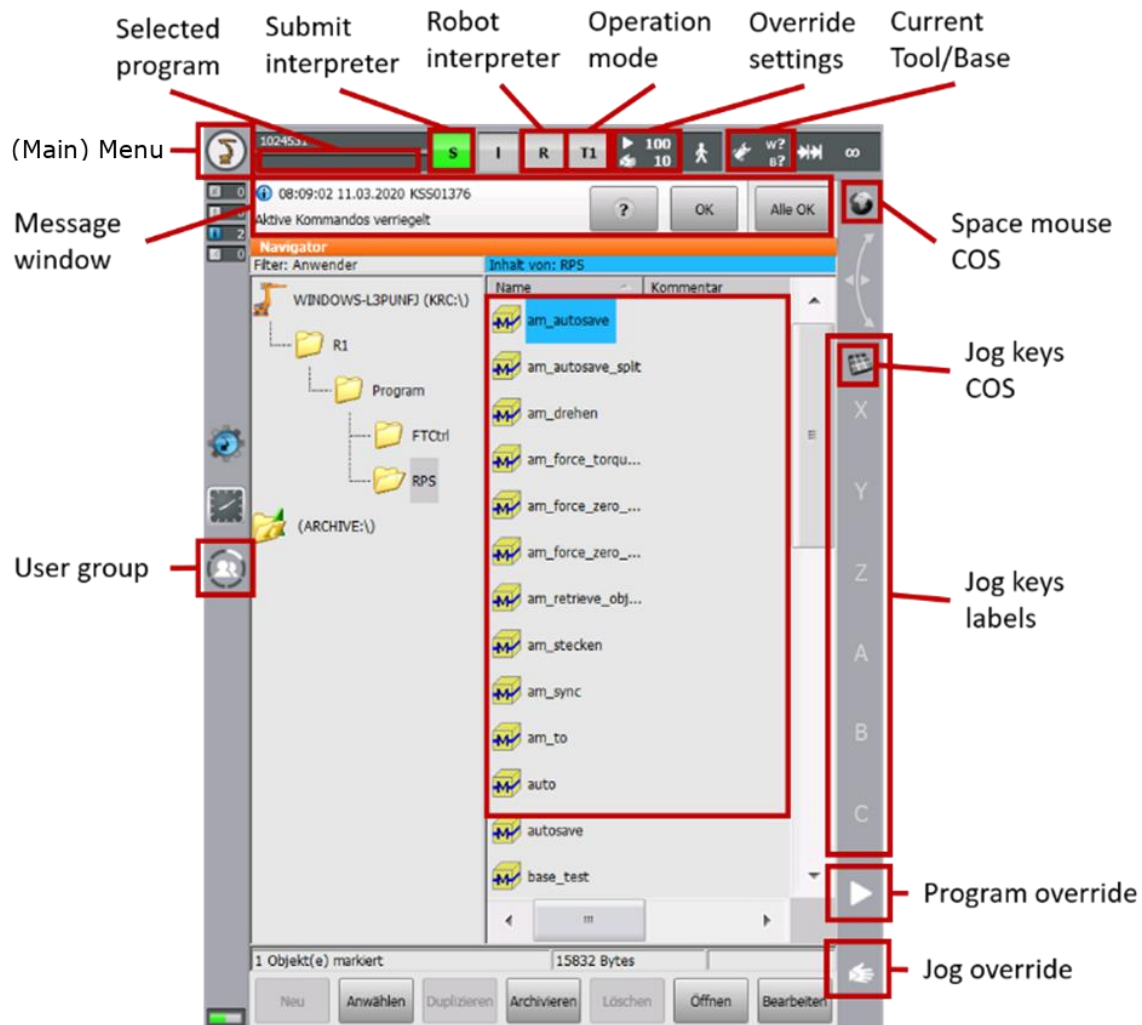
1 Overview of the KUKA Robot System

This chapter mainly explains some basic terms and provides an overview of important operating keys of a KUKA robot. Further information can be found in the KUKA manuals. Users who are already familiar with the KUKA robot system can skip this topic.

The following pictures will give you a brief overview about the KUKA controller.



Source: KUKA



Function	Location	Summary
(Main) menu	Top left corner	Setup and configuration of the robot
User group	Center left	Manage the current user group. Some settings are only available to the Expert/Administrator user. Default password: "kuka"
Current override	Top right	"Program" (play symbol): Percentage value of the programmed velocity "Jog" (play + hand symbol): Percentage value of the velocity for manual motions
Set override	Bottom right corner	Setup the overrides
Robot interpreter	Top center	Displays the currently selected program and the program status: Gray: No program selected Yellow: Program is ready to start (first line of selected program) Green: Program is being executed Red: Selected and started program has been stopped Black: Program has finished

Function	Location	Summary
Current Tool/Base	Top right	Displays the current selected Tool/Base id. ?: No Tool/Base selected
Operation mode	Top right	Change/Select the operation mode of the robot: T1: For test operation, programming and teaching, max. velocity of 250 mm/s T2: For test operation, programmed velocity, jog mode not possible AUT: Robot without higher-level controllers, programmed velocity, jog mode not possible EXT: Robot with higher-level controllers, programmed velocity, jog mode not possible

Please notice that some functions on the KUKA teach pendant are only available if no program is selected. Also pay attention to the selected user group, some settings are only available to the Expert/Administrator user.

The KUKA controller uses a multi-file system, therefore it may happen that changes made to the file system via the mounted network share are overwritten. It helps to open the altered file on the teach pendant again, adding a space symbol and closing the file. This also triggers the parsing of all dependencies.

The KUKA controller uses an advance run system, so certain commands are executed earlier while the robot still executes a former motion command. This can lead to the premature execution of commands which can be suppressed by certain blocking commands (e.g. "WAIT for TRUE"). This is relevant when a vision system is used. The recording of the camera image should only be triggered after the robot arrived at the correct position (advance run must not trigger the camera).

KUKA provides a software called KUKA.WorkVisual to communicate with a KUKA robot from a computer and configuring it. It is recommended to use this software, although ArtiMinds RPS does not need it during execution. Many options, especially safety relevant settings and hardware extensions, can only be altered via KUKA.WorkVisual.

2 Prerequisites

2.1 Supported Platforms

Currently the controller generation KR C4 and KR C5 are supported, running KUKA.SystemSoftware (KSS) up to version 8.6.8 (KR C4) and 8.7.3 (KR C5). Newer versions will most likely work, but have not been fully verified yet.

2.2 Required Technology Packages

The following technology packages are required for basic ArtiMinds RPS usage:

- KUKA.DirectoryLoader: Required to transfer and start programs on the robot
- KUKA.EthernetKRL: Required to send and receive data over network

Attention:

- For KSS < 8.5 the EthernetKRL Version 2.2.9 had a bug that affected ArtiMinds RPS communication. Either upgrade or downgrade to Version 2.2.7
- For KSS > 8.5 the EthernetKRL Version 3.1.0 had a bug that affected ArtiMinds RPS communication. Please upgrade to a newer version
- The listed versions cause blocking of the used communication ports, resulting in an error in *KRC\Roboter\Vog\EthernetKRL\EKI*.log* like:
CTcpSock: Socket *** on port **** failed to bind with code 48

The following technology packages are required for force guided motions:

- KUKA.RobotSensorInterface (RSI): Required for sensor adaptive motions.
Attention: For KSS 8.5 the versions older than 4.0.9.3190 of RSI had a bug that affected ArtiMinds RPS code
- KUKA.ForceTorqueControl: Required to connect to a Force-Torque Sensor

Please consult your KUKA sales representative to obtain the required technology packages. KUKA.WorkVisual or “Main (Menu) → Start-up → Add-on Software” (German KUKA “Hauptmenü → Inbetriebnahme → Zusatzsoftware”) on the robot teach pendant (KUKA SmartPad) can be used to verify the installed technology packages on the KUKA controller.¹

Additional system requirements about ArtiMinds RPS can be obtained in the document “ArtiMinds RPS - Installation and technical information for use in corporate IT environments”.

¹ Setting is only visible if logged in as Expert/Administrator user (default password “kuka”).

3 Installation

3.1 ArtiMinds Robot Programming Suite (RPS)

Additional information about ArtiMinds RPS installation and technical details can be found in “ArtiMinds RPS Installation and Technical Infos Release <Version>.pdf”.

3.2 ArtiMinds Learning and Analytics for Robots (LAR)

Additional information about ArtiMinds LAR installation and technical details can be found in “LAR <Version> Setup and User Manual.pdf”.

3.3 Usage of Force-Torque Sensor

There are several ways to connect the sensor to the robot, depending on the brand of sensor that you are using. In all cases the measured data is read over the RSI interface and partly processed via the ForceTorqueControl technology package.

Prerequisites:

The RSI network interface that connects to your sensor must be configured to a different subnet than the regular interface used by ArtiMinds RPS (see chapter 4.4).

Apart from that, please follow a separate manual from KUKA or the sensor manufacturer to connect your specific sensor. If you connect the sensor via EtherCAT, ArtiMinds also offers a specific manual for that (*Instructions for using Ethercat-based sensor on KUKA robots.pdf*).

4 Configuration

4.1 Network Setup

Physically connect the KUKA robot and the computer that runs ArtiMinds RPS to the same network (Ethernet recommended, no WIFI) e.g. by using a network switch.

Often computer and network switch are able to set suitable IP addresses automatically. If static IP addresses are used (recommended), please make sure that the robot and computer are in the same network.

The IP address of the KUKA robot can be configured on the KUKA teach pendant by clicking on the “(Main) Menu” button (KUKA robot icon), then “Start-up → Network Configuration” (German KUKA: “Hauptmenü → Inbetriebnahme → Netzwerk”). Setting is only visible if logged in as Expert/Administrator user (default password “kuka”) and no program is selected.

On the computer the IP address is set in the “Windows Control Panel → Network and Sharing Center” (Windows 7 or newer). Here you can see an overview of all network adapters. Click on the network adapter that is connected to the KUKA robot and then on “Properties” to verify or alter the IP address of the computer.

Optionally you can use the Windows command shell (opening the Windows start menu and typing in “cmd.exe”) and execute the command “ping IP_ADDRESS_OF_THE_ROBOT” to verify that the connection is working. Replace IP_ADDRESS_OF_THE_ROBOT with the IP address of your robot, for example “ping 192.168.2.10”.

If the “ping” command is not working, check the Windows firewall if it blocks the connection. Also make sure that no additional anti-virus or security software is involved. Consult the manual *“ArtiMinds RPS - Installation and technical information for use in corporate IT environments.pdf”* for more details and what network ports must be open.

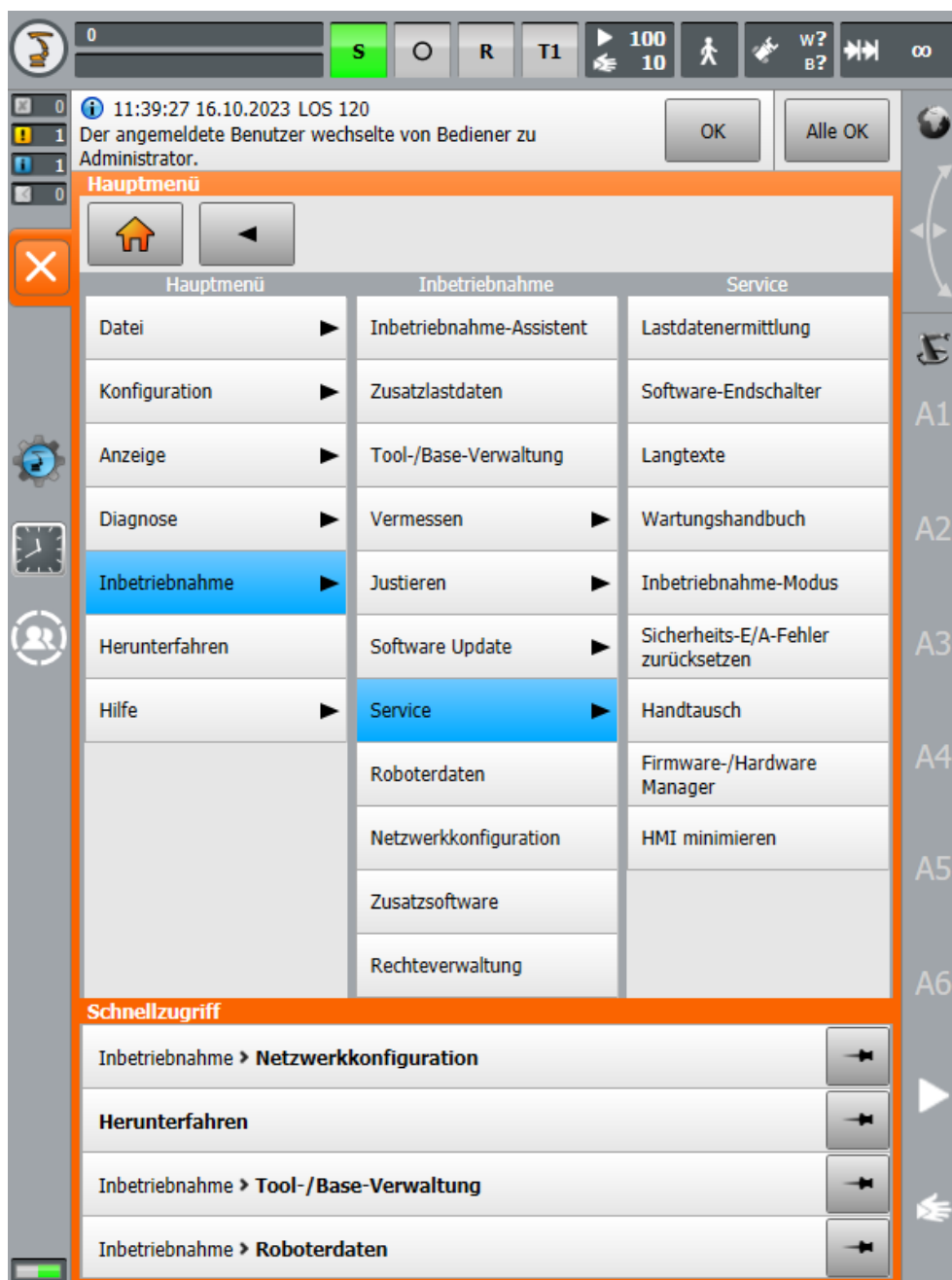
Note: During programming, the robot will try to establish a connection to the PC. The configuration on the robot must be adjusted if the IP address of the PC is changed after initial setup, or if another PC is connected. See chapter 5.3 for details.

4.2 Network Drive Setup

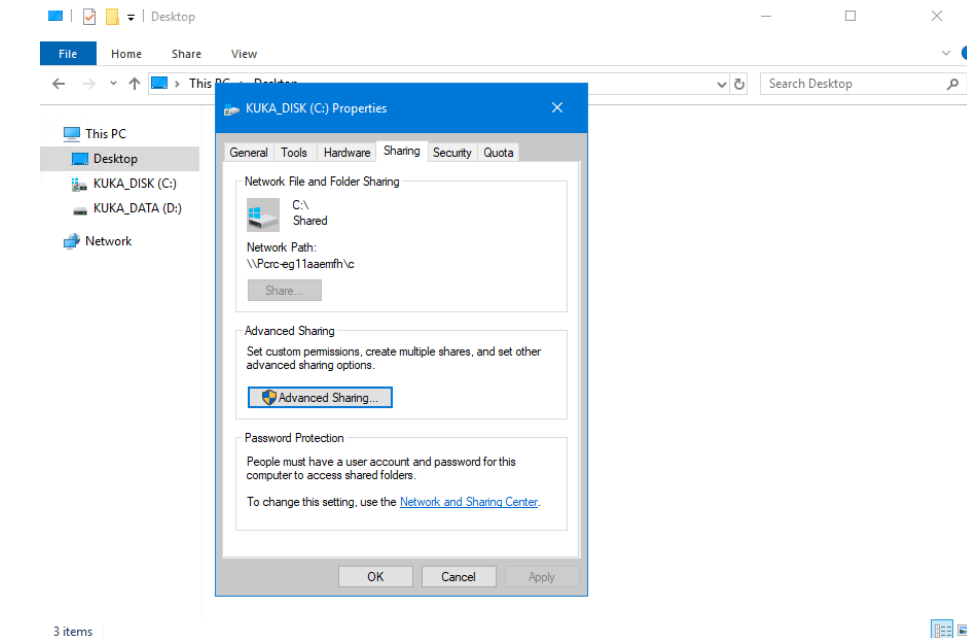
4.2.1 KUKA Robot

Configuring the basic network share is always needed when ArtiMinds RPS should be able to communicate with the robot and generate robot programs. For this, the hidden KUKA C: drive has to be shared and mounted as a network drive on the computer. All following steps are executed on the KUKA teach pendant.

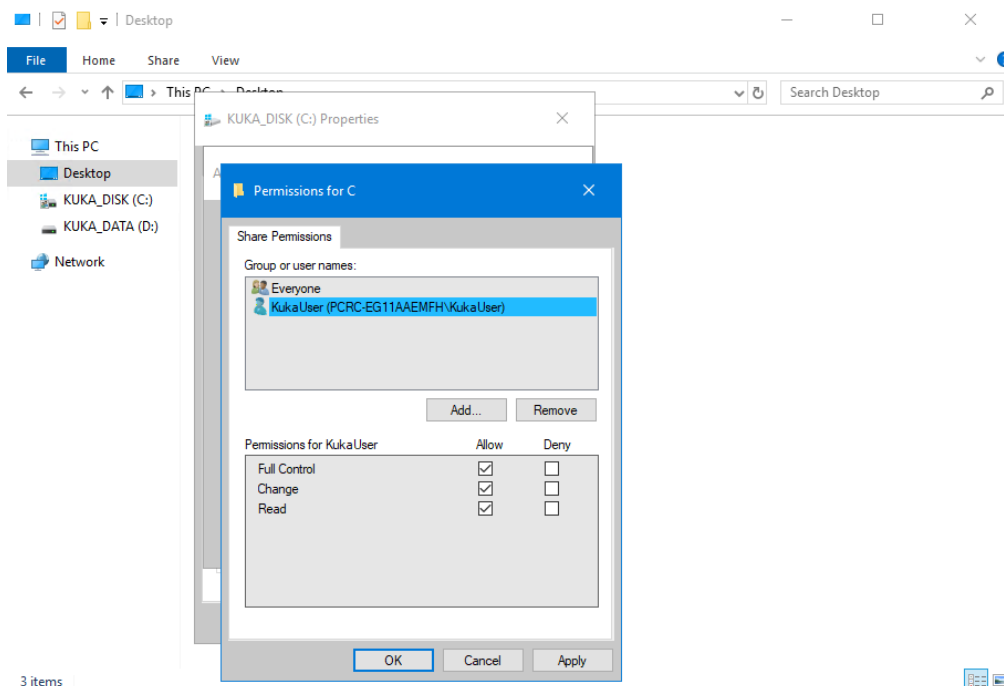
1. Log in as Administrator on the robot, go into the settings, then “Start-up → Service → Minimize HMI” (German KUKA: “Inbetriebnahme → Service → HMI minimieren”).



- Now the KUKA user interface is disabled and the underlying Windows operating system that runs on the KUKA controller is visible. Select the C: drive and open its “Properties”. Then go to the “Sharing” tab.



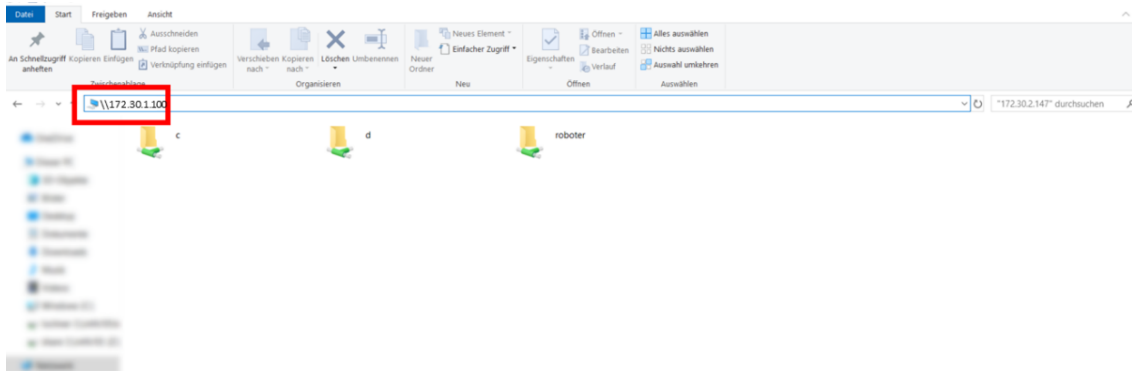
- Click on the “Advanced Sharing → Permissions” button and enable all access rights of the “KukaUser” user. All checkboxes for “Full Control”, “Change” and “Read” need to be enabled. If the “KukaUser” is not visible, create it via the “Add” button.



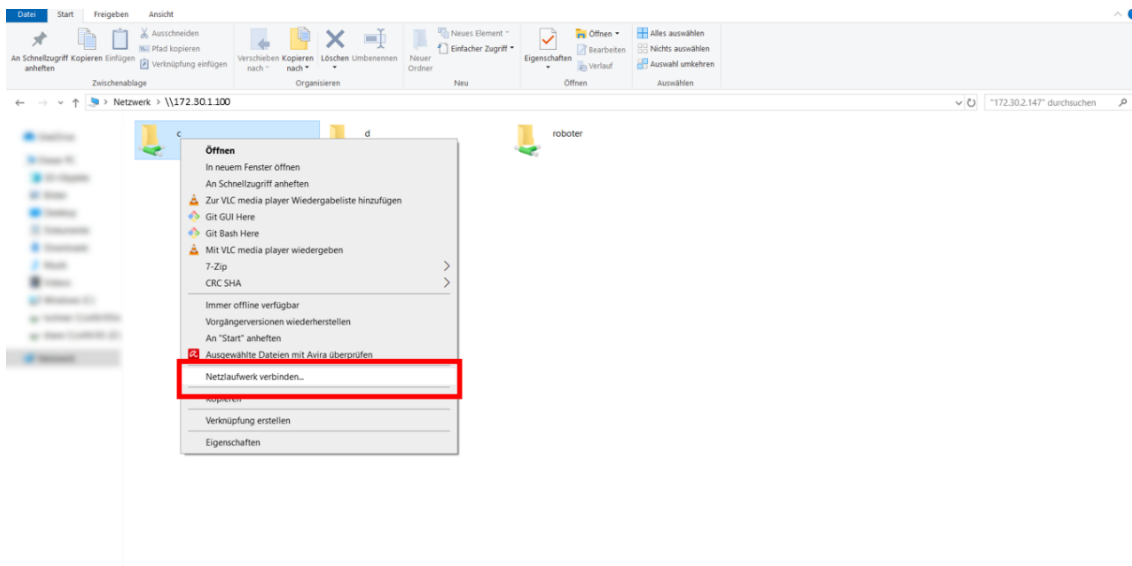
4.2.2 Computer

Now the C: drive of the KUKA is visible to the computer and can be mounted as any regular network drive in Windows. On the computer execute the following steps:

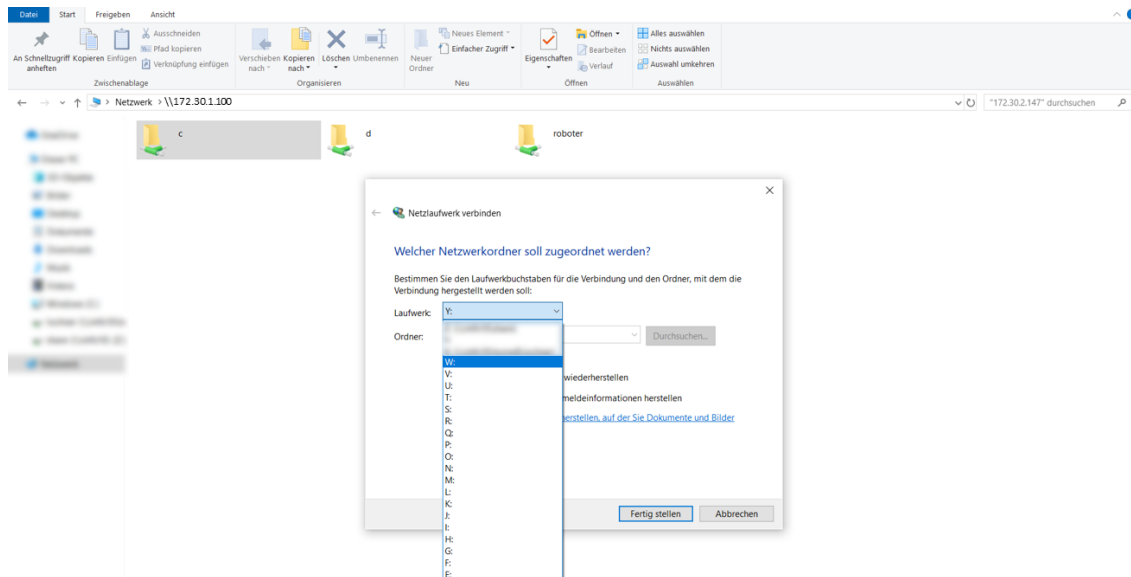
1. Open a Windows Explorer window and type in “\\IP_ADDRESS_OF_THE_ROBOT”, e.g. “\\172.30.1.100”.



2. Click with the right mouse button on the C: drive and then on “Connect Network Drive...”. If login credentials are required, enter the username and password of the KUKA. Default user: “kukauser” with the default password “68kuka1secpw59”.



3. Select a free local drive letter and enable the “Reconnect at sign-in” checkbox. Remember the chosen drive letter (in this case W:) for later.



4.3 KUKA Directory Loader

Check and adapt the setup of the DirectoryLoader by defining the temporary upload directory somewhere on the C: drive. Create the folder if it does not exist already. **Attention:** The DirectoryLoader mechanisms might be configured to delete the content of the folder on a regular basis. Therefore, do not use folders which contain relevant files!

ArtiMinds RPS copies its programs temporarily into this folder. The KUKA DirectoryLoader then performs a syntax check and if no errors are found it copies the files from that folder to the KUKA programs folder. Remember the name of the (created) temporary folder as it will be needed in chapter 4.5.2 again.

The configuration is specific for the KSS Version, e.g.:

1. KSS 8.5:
Open the file C:\KRC\ROBOTER\KRC\R1\TP\DirectoryLoader\directoryloader.dat (the directory may be hidden). Create or adapt the line
DLSourceDir]="C:\DirLoaderInbox\"
2. KSS < 8.5:
Open the file C:\KRC\ROBOTER\KRC\R1\System\\$config.dat (the directory may be hidden). Create or adapt the lines
KRDLSOURCEDIR]="C:\DirLoaderInbox\"
BOOL PGNOcaseKRDL=FALSE

Restart the KUKA controller. After booting up the robot, have a look at the log messages and make sure the DirectoryLoader started without errors.

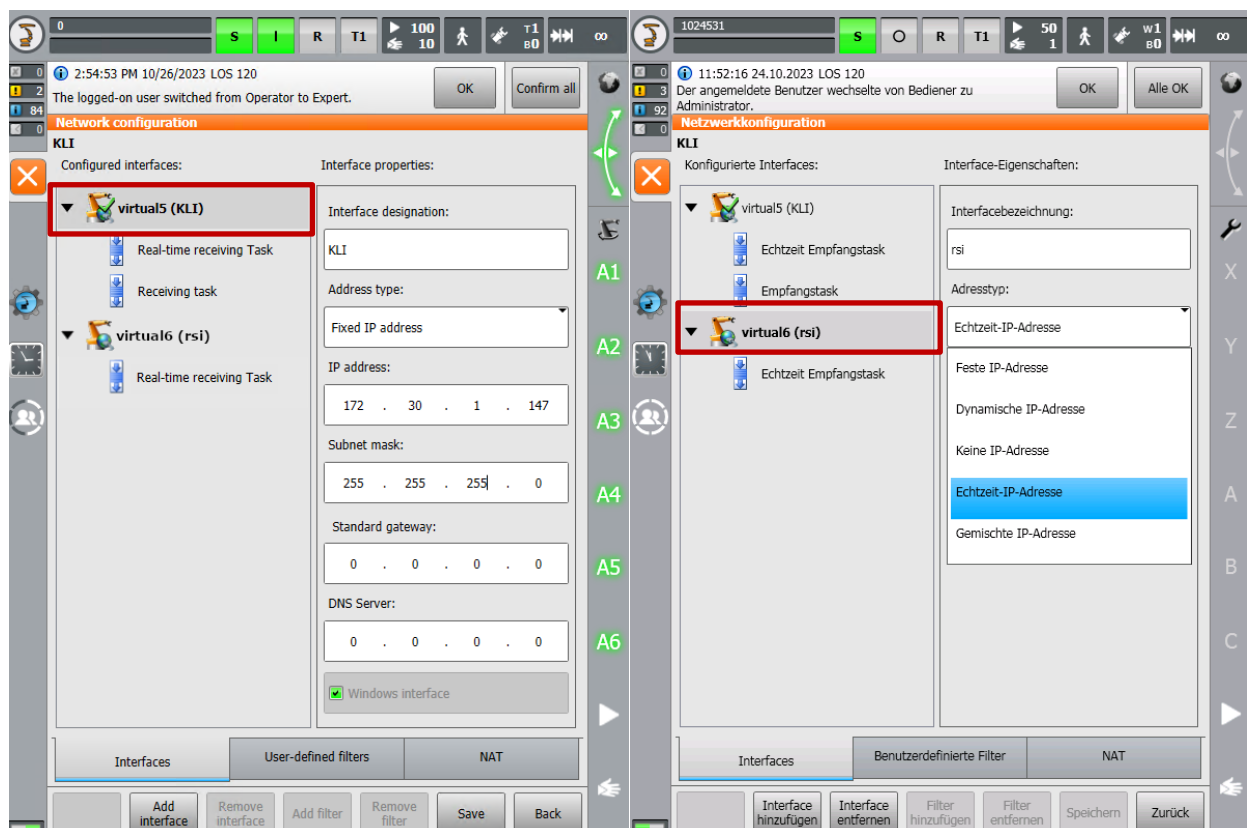
4.4 KUKA Robot Sensor Interface (RSI)

This chapter is only necessary if force-torque control is to be used or if high-resolution data is to be visualized or recorded in ArtiMinds LAR. That requires fast data streaming of 4ms via RSI. If this is not the case, skip this chapter and immediately go to chapter 4.4.1.

Please note that there are additional manuals available to configure force-torque sensors with ArtiMinds RPS. Also have a look at the official KUKA documentation on configuring force-torque sensors and RSI with KUKA.Work-Visual (e.g. “Kuka.RobotSensorInterface 4.0” manual).

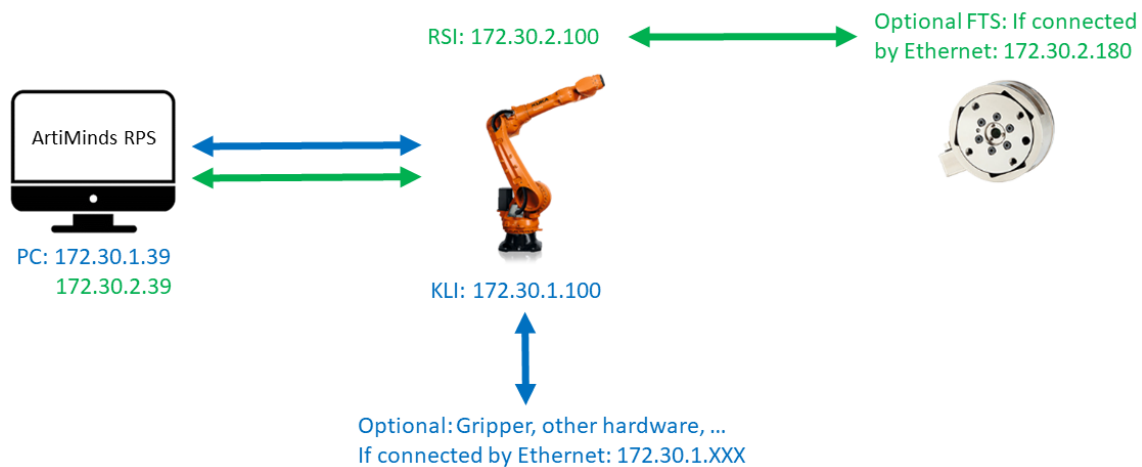
The RSI technology package requires an additional subnet for data streaming. For details see the KUKA documentation below (e.g. chapter 5). **Pay close attention to the IP address setup.** KUKA recommends using similar network segments. In this manual we use 172.30.1.XXX for the Ethernet KLI network and 172.30.2.XXX for RSI. These IP addresses are only meant as an example and other addresses can also be used.

Use “Real-time/Mixed IP address” in the KUKA network configuration. Do not use the KUKA KONI network for connecting a force-torque sensor as this network is optional and not real-time capable.



“Main Menu → Start-up → Network Configuration” (German KUKA: “Hauptmenü → Inbetriebnahme → Netzwerkkonfiguration”).

Manuals for KUKA can be found on the KUKA website or on the KUKA controller itself (KUKA D: drive: e.g. enter `\\<IP_ADDRESS_ROBOT>\d\KUKA_OPT` in Windows explorer with mounted D drive).



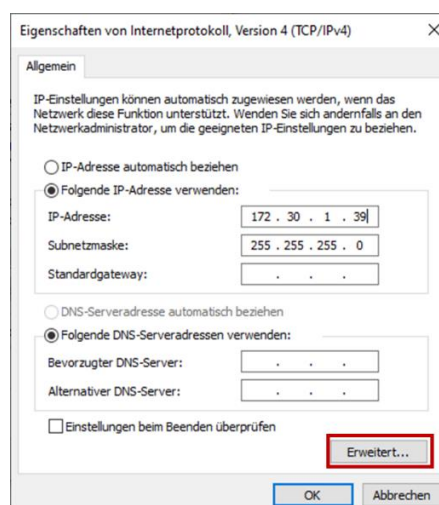
The above image shows the configuration used in this example. The KUKA robot has a KLI and RSI network. The force-torque sensor is connected via RSI and additional hardware (e.g. gripper) via KLI. Both networks are in a similar subnet as required by KUKA.

ATI Net-F/T sensors do not require a mapping of the channels in KUKA WorkVisual. For ATI ForTTran or EtherCAT based sensors, please consult our additional manual “Instructions for using Ethercat-based sensor on KUKA robots.pdf” as additional configuration is required.

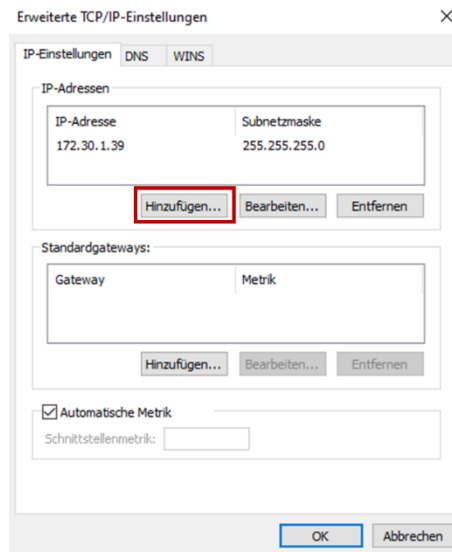
The correct configuration of the force-torque sensor can be confirmed on the KUKA teach-pendant by navigating to “Configuration → FTCtrl → Sensor”.

4.4.1 Computer

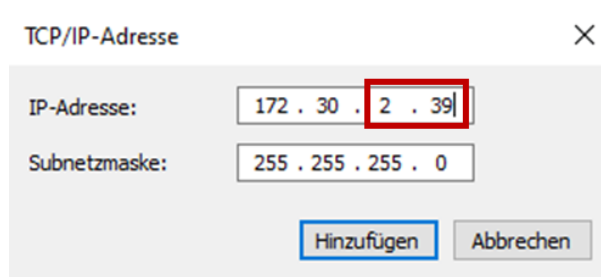
1. Go to Windows network settings. On the computer open the Windows Control Panel and then “Network and Sharing Center” (Windows 7 or newer). Here you can see an overview of all network adapters. Click on the network adapter that is connected to the KUKA robot and then on “Properties”.
2. Click on the “Advanced...” button.



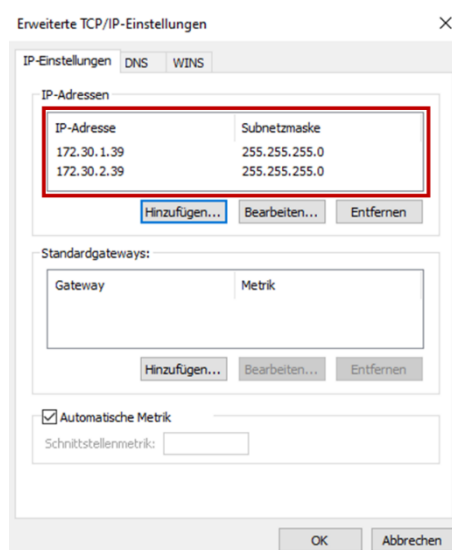
- Click on “Add...” and add another network interface.



- The additional network interface should have the same IP address, but in a different subnet (only required for RSI). Add the same subnet mask and click on “Add”.



- The network should look like this (adapt the IP addresses as needed):
172.30.1.39: Network interface to the KUKA robot
172.30.2.39: RSI robot sensor interface



4.4.2 KUKA Robot

The IP address of the KUKA robot can be configured on the KUKA teach pendant by clicking on the “(Main) Menu” button (KUKA robot icon), then “Start-up → Network Configuration” (German KUKA: “Hauptmenü → Inbetriebnahme → Netzwerk”). This setting is only visible if logged in as Expert/Administrator user (default password “kuka”) and no program is selected.

Detailed information about the network setup for RSI can be found in chapter 5.1 *Configuring Ethernet via KLI network configuration* of the *Kuka.RobotSensorInterface 4.0* manual.

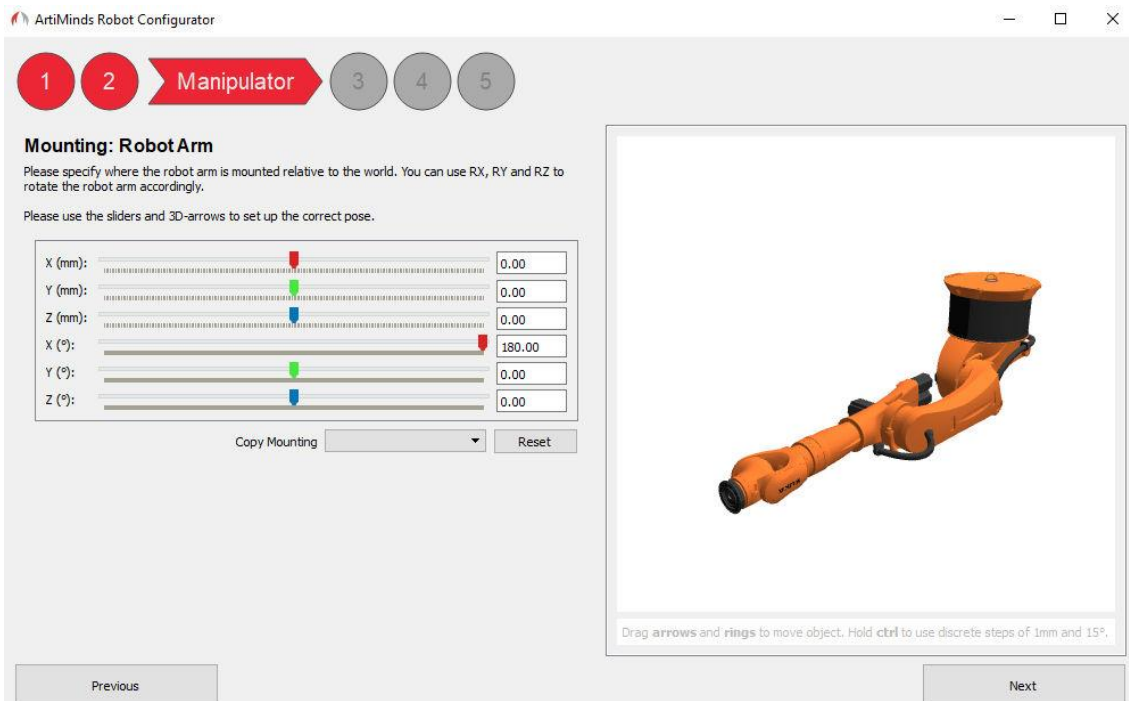
4.5 ArtiMinds Robot Programming Suite (RPS)

Start ArtiMinds RPS on the computer which is connected to the KUKA robot.

4.5.1 Coordinate Systems Setup

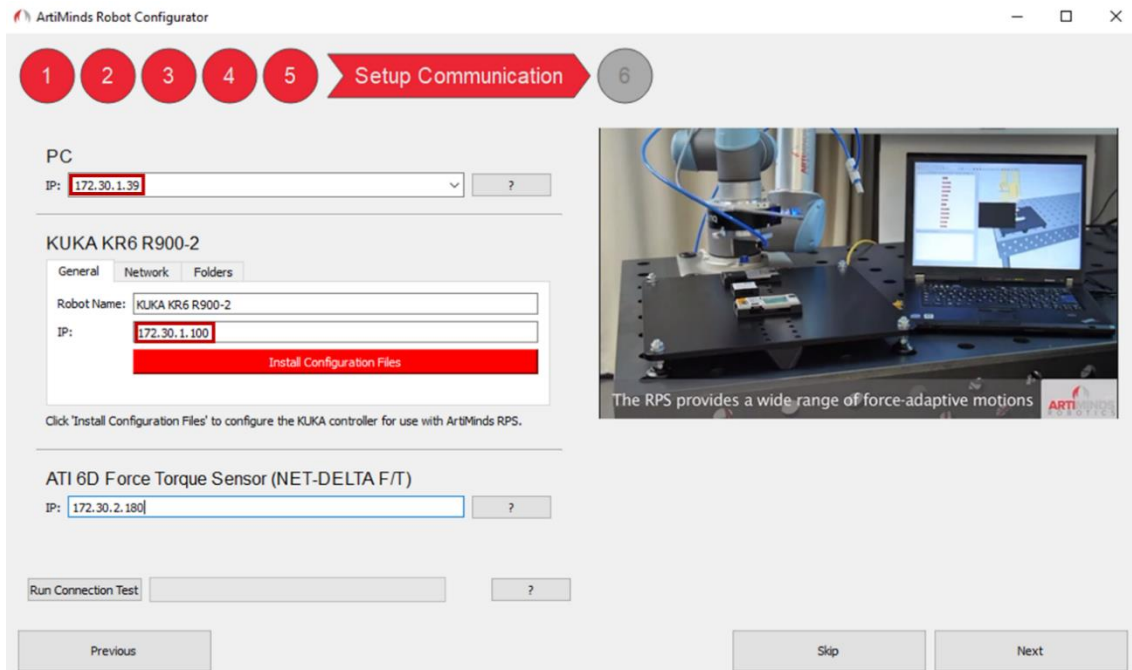
The **Robot Configurator** allows you to define and setup your hardware. Launch it via “File → Robot → New Robot Setup”. In the first pages, setup your components and coordinate systems as required.

Attention: If you choose to mount your robot base differing from the world origin via “Mounting: Robot Arm”, you have to apply the same offsets in the machine-data configuration in KUKA.WorkVisual (“Editors → Machine Data Configuration”)! Since this is a safety-critical step, ArtiMinds RPS cannot perform it automatically.



4.5.2 Network setup

On the “Setup Communication” page make sure to choose the right network device of your computer (“PC”: “IP”) with an IP in the same subnet as the robot’s main Windows network IP. Then enter the main IP address of the robot on the “General” tab below.



ArtiMinds Robot Configurator

1 2 3 4 5 **Setup Communication** 6

PC
IP: 172.30.1.39

KUKA KR6 R900-2
General Network Folders
Robot Name: KUKA KR6 R900-2
IP: 172.30.1.100
Install Configuration Files

Click 'Install Configuration Files' to configure the KUKA controller for use with ArtiMinds RPS.

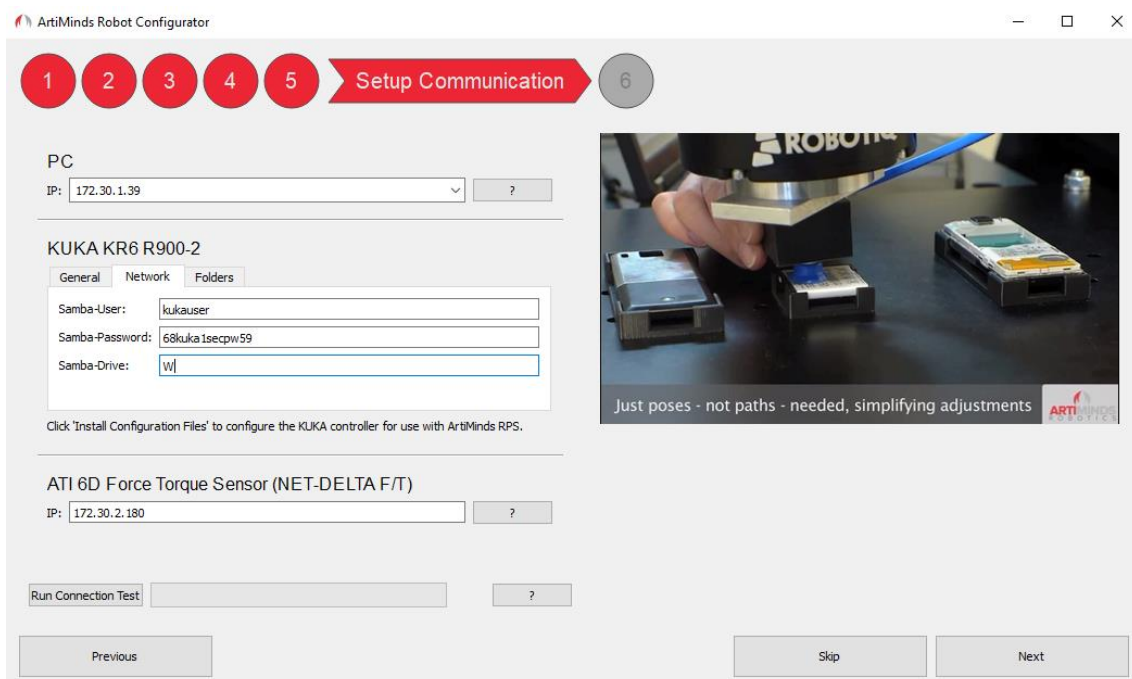
ATI 6D Force Torque Sensor (NET-DELTA F/T)
IP: 172.30.2.180

Run Connection Test

Previous Skip Next

The RPS provides a wide range of force-adaptive motions

Switch to “Network” and enter the drive letter of the previously mounted network drive of the robots C: drive (W in the example above). Keep the credentials if they did not change on the robot.



ArtiMinds Robot Configurator

1 2 3 4 5 **Setup Communication** 6

PC
IP: 172.30.1.39

KUKA KR6 R900-2
General Network Folders
Samba-User: kukauser
Samba-Password: 68kuka1secpw59
Samba-Drive: W

Click 'Install Configuration Files' to configure the KUKA controller for use with ArtiMinds RPS.

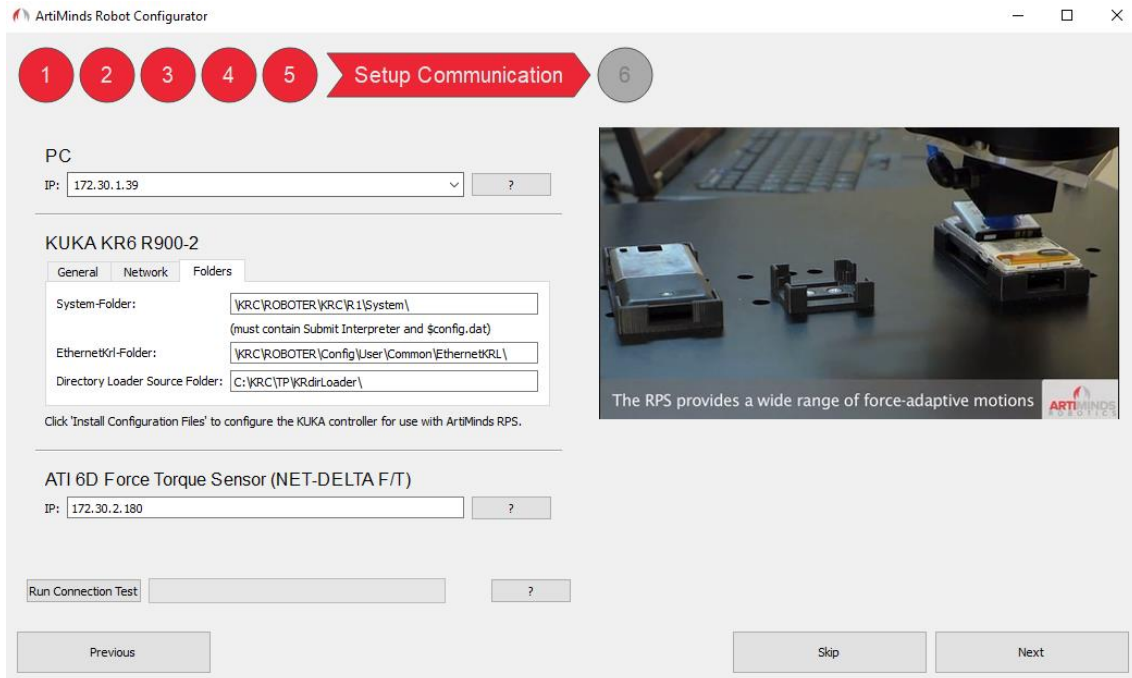
ATI 6D Force Torque Sensor (NET-DELTA F/T)
IP: 172.30.2.180

Run Connection Test

Previous Skip Next

Just poses - not paths - needed, simplifying adjustments

Also, keep the entries in the “Folders” tab if not changed manually on the robot. “Directory Loader Source Folder” should point to the folder that has been created on the KUKA C: drive in step 4.3.



When testing the connection, ArtiMinds RPS tries to copy and modify several files on the robot. For that purpose, the Submit Interpreter has to be stopped and deselected: Click on the green “S” indicator on the KUKA teach pendant and choose “Deselect” (German KUKA “Abwählen”). Click the “Install Configuration Files” in the “General” tab so that ArtiMinds RPS can copy and modify various files on the robot controller. It’s also possible to read in settings from the controller directly, so that not everything has to be configured manually. Restart the KUKA controller, so that the new files are read in. Afterwards you can test the communication in ArtiMinds RPS by clicking the “Run Connection Test” button.

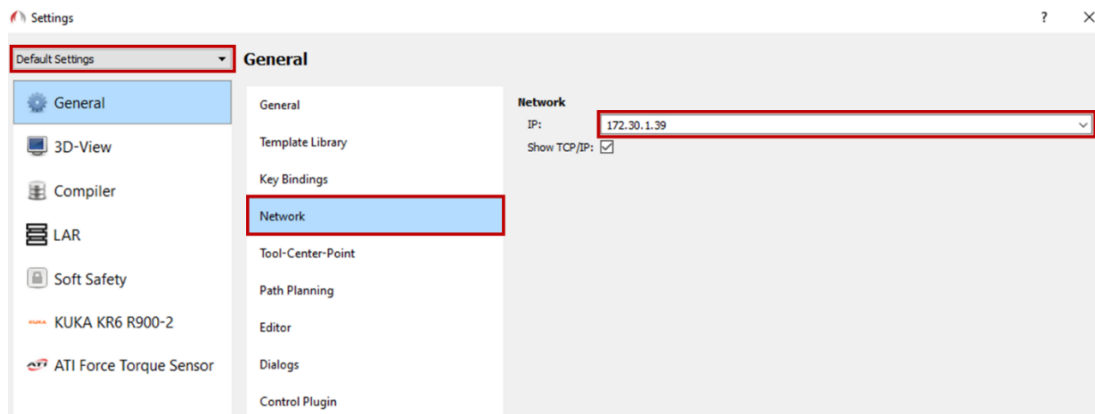
If the connection test is not successful, it may be easier to skip the connection test for now (“Skip” button) and complete the ArtiMinds Robot Configurator. You will be prompted to visit the settings after closing the Robot Configurator. Otherwise go to “File → Settings → Kuka” in ArtiMinds RPS and check the settings individually (see next chapter).

One simple way to test the communication with the KUKA robot in general later is by clicking on the “Offline” toggle button in the main menu bar at the top of ArtiMinds RPS. ArtiMinds RPS should switch to “Online” mode. Press the “Record” button (also in the main menu bar) to retrieve the current position of the real KUKA robot. The virtual robot in ArtiMinds RPS should show the same pose. Make sure a tool is selected on the teach pendant of the KUKA robot.

4.5.3 RPS Settings Pages

The following options are all available in the KUKA settings pages of ArtiMinds RPS (“File → Settings → Kuka”).

Go to “General -> Network” and make sure the “IP” dropdown shows the IP address of the PC network adapter that is connected to the KUKA robot controller. You may have to switch from “Project Settings” to “Default Settings” at the top to alter this setting. In the above example 172.30.1.39.



Open the Kuka settings pages in “Kuka → Network” and confirm all settings are correct.

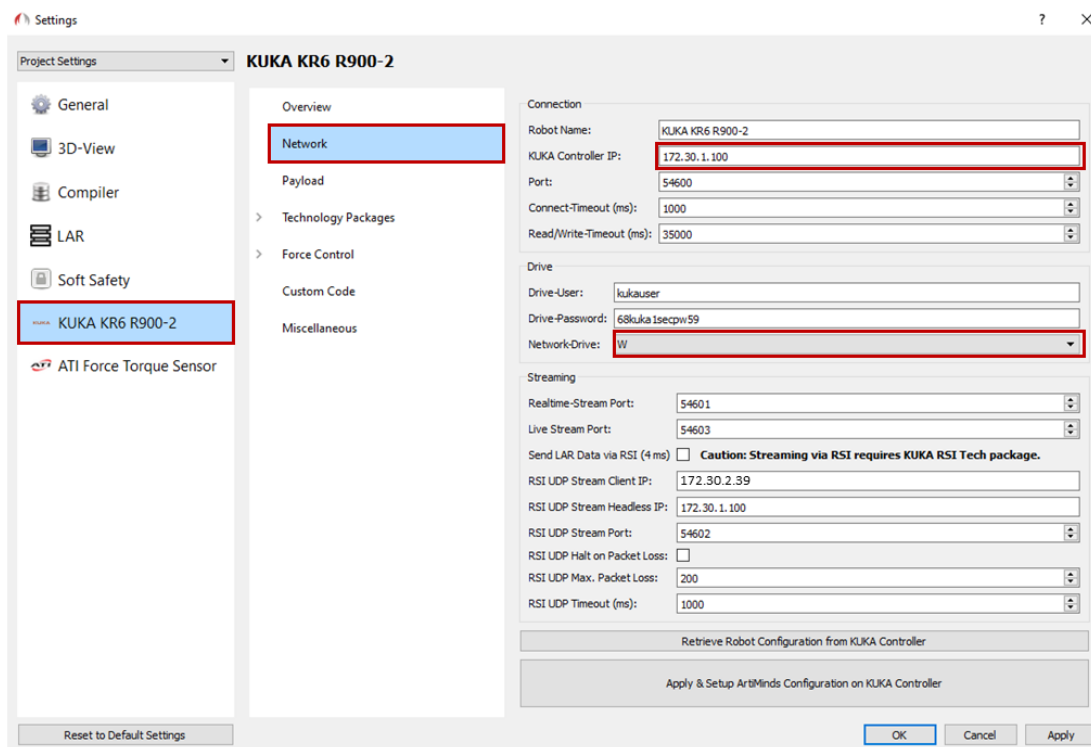
4.5.4 Network Tab

The “Kuka Controller IP” should contain the IP address of the KUKA robot. In the above example 172.30.1.100. The Robot and ArtiMinds RPS should be in the same subnet (here first three numbers equal, e.g. 172.30.1.XXX as the subnet mask 255.255.255.0 has been used).

Note: During programming, the robot will try to establish a connection to the PC. The configuration on the robot must be adjusted if the IP address of the PC is changed after initial setup, or if another PC is connected. See chapter 5.3 for details.

“Samba-Network-Drive” should contain the drive letter of the KUKA C: drive that has been used for mounting on the computer. Here W:.

Make sure the “Samba-User” and “Samba-Password” are correct. You can keep the default values if this has not been altered on the KUKA. This is required for file transfer to the robot.



“RSI UDP Stream Client IP”: These settings are only relevant if a force-torque sensor with RSI or ArtiMinds LAR is used (see chapter 4.4). This is the IP address of a network interface of your computer (172.30.2.39 in the example of chapter 4.4). This can simply be an additional address of your main network adapter and does not require additional hardware (see chapter 4.1). It will be used as target for the real-time UDP packages sent from the robot via RSI to realize 4ms data logging. The setup of RSI UDP Stream Headless IP depends on the ArtiMinds LAR setup. Chapter 4.6 contains a detailed description for LAR setup.

Enable the “Send LAR Data via RSI (4ms)” checkbox if needed. It creates an RSI container to stream high resolution real-time data in addition to the live data sent via the submit interpreter.

The other settings usually do not need to be modified. However, the ports must be open in the Windows firewall and must also not be blocked by any other security software that may be installed on the computer.

Do **NOT** add those ports to the port-forwarding rules of the KUKA HMI Network Settings.

It is recommended to press the “Retrieve I/O Settings from KUKA KRC4” in the “Network” tab and the “Retrieve Acceleration Limits from Controller” in the “Options (Expert)” tab once so that ArtiMinds RPS settings are consistent with the KUKA controller.

Whenever you make changes, make sure you deselect the Submit Interpreter on the KUKA teach pendant first (green “S” icon at the top). Then click the “Apply & Setup ArtiMinds Configuration on KUKA KRC4” button in the ArtiMinds RPS KUKA settings page. This will write all ArtiMinds settings to the KUKA controller.

Restart the KUKA controller so that the new settings are read in and confirm that the Submit Interpreter is running again. Otherwise check the error list on the KUKA.

Individual settings and configurations can be written to the KUKA controller by using the other tabs in the ArtiMinds RPS KUKA settings page (“Submit Interpreter”, “KUKA.DirectoryLoader”...).

4.5.5 Payload Tab

Configures the payload mounted to the robot flange.

- “Robot Payload”: Important for teaching and dynamics calculation of motions. Complete weight attached to the robot flange
- “Force Sensor Payload”: Mainly important for gravity compensation and force-based applications. The weight after the bottom half of the force-torque sensor. It is recommended to execute the KUKA.LoadDataDetermination program on the KUKA teach pendant (“Start-up -> Service -> Load data determination”) to determine the exact values

4.5.6 Technology Packages Tab

- **Submit Interpreter Tab:** Change the IDs of the global flags. Make sure they do not collide with your project specific programming or with flags already used on the KUKA controller. “Submit program folder” should contain the path to the \$config.dat file on the KUKA controller.
- **DirectoryLoader Tab:** Click on “Load directory loader settings from KUKA controller”. This should result in the correct settings for your robot and the settings above should reflect the settings from the previously adapted configuration files on the robot. Make sure the correct Directory Loader version is selected. “DLSourceDir[] = ” is configured in chapter 3.2 and contains the created temporary DirectoryLoader inbox folder on the KUKA C: drive. Pressing the “Apply” button only copies the Directory Loader specific settings.
- **EthernetKRL Tab:** This defines the directory, where data-format definitions are stored. Keep at default settings.
- **ForceTorqueControl/RSI Tab:** Change these values according to your robots KSS / RSI version and according to the force-torque sensor that you are using. If you’re using an ATI sensor that is connected via EtherCat, select the “EtherCat (FieldBus)” checkbox and not the “ATI” one.

4.5.7 Force Control Tab

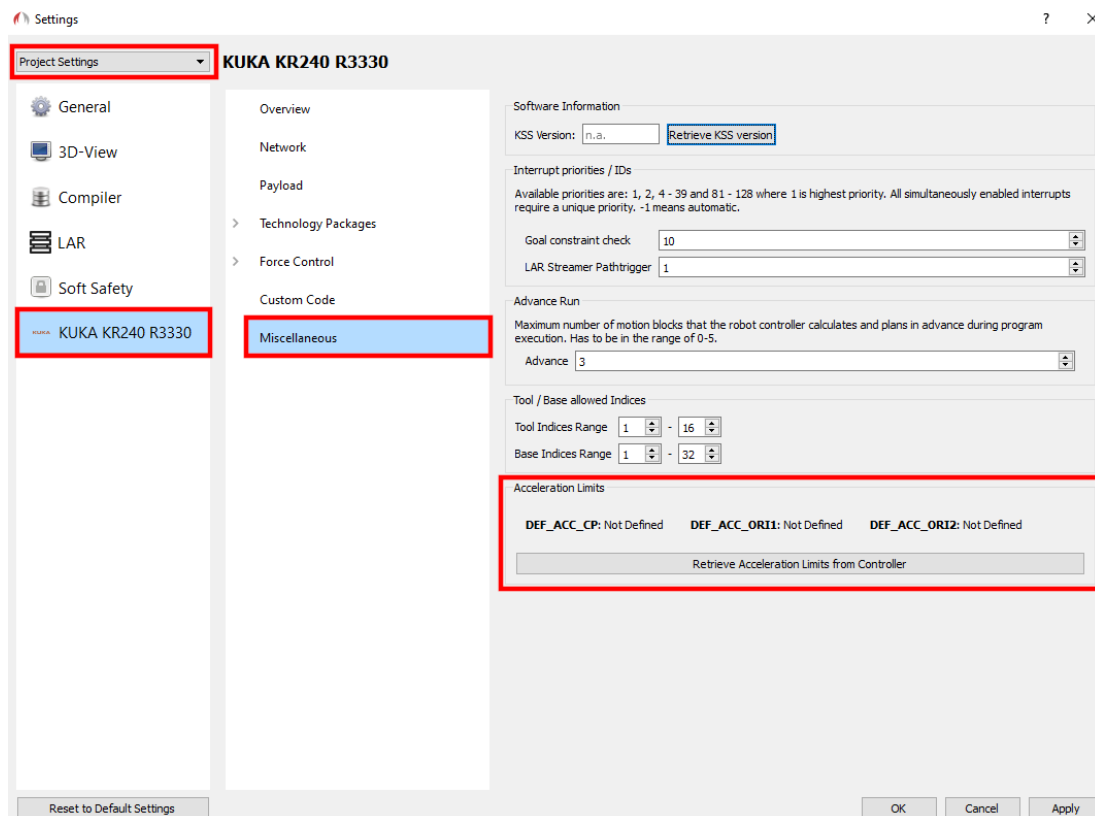
- **Force-based Guiding:** Defines PID controller based parameters for force-based guiding. These settings affect all robot programs.
- **Force Controller:** Defines PID controller based parameters for force-based applications. These settings affect all robot programs. Presets are provided to alter the reactivity of the robot when measuring forces.

4.5.8 Custom Code

Here you can insert custom initializations, custom code and custom function definitions, which will always be compiled into the generated .src and .dat files. The entered code will not be checked, so make sure the syntax of the code is correct.

4.5.9 Miscellaneous

Change the priorities of the interrupts defined by ArtiMinds RPS if they collide with your project specific programming. ArtiMinds RPS generates tools and bases for the created robot program as needed. “Tool Indices Range” and “Base Indices Range” allow to restrict the allowed indices used for tools and bases by ArtiMinds RPS. This helps preventing overwriting already defined tools and bases on the KUKA robot controller. You must also read the acceleration limits once from the controller, to allow a correct simulation and runtime estimation within ArtiMinds RPS.



4.6 ArtiMinds Learning and Analytics for Robots (LAR)

ArtiMinds LAR captures and stores data of program executions (“Runs”) in a SQL database. One ArtiMinds LAR database can store program data of multiple robots. In order to stream data from the robot into the database, a running instance of either ArtiMinds RPS or ArtiMinds hRPS is needed.

The general data flow is displayed in the image below. The data recorded by the robot during execution is streamed to ArtiMinds RPS and then transferred to ArtiMinds LAR.



If the robot is in productive operation it is not necessary to use ArtiMinds RPS with graphical user interface. Then ArtiMinds headless RPS can be used. ArtiMinds headless RPS is capable of receiving data from multiple robots at the same time (contrary to ArtiMinds RPS, which can only receive data from one Robot at a time).



Depending on the installation setup (local or distributed mode → see chapters 4.6.1, 4.6.2, 4.6.3) of ArtiMinds LAR, the current operation mode and the overall network setup, it is possible to configure the robot, RPS/hRPS and LAR server in different ways.

If RSI should be used for high performance data streaming, some network devices must have an additional IP address in the RSI subnet (see chapter 4.4). The first network (non RSI network) is referred to as **network N1**. On the KUKA controller this network is also called **KLI** (KUKA Line Interface). The second **network N2** is the **RSI** network (Robot Sensor Interface).

First, an overview of the different modes is given. Then, in the following chapters the setup process is described in detail for each mode.

There are several ways in which you can set up the IT infrastructure for ArtiMinds LAR. Which option is the right one depends on individual requirements. The different options are described in more detail below.

Mode	RPS	hRPS	LAR	Typical usecase	Number of robots
Local	PC	×	PC	Comissioning	1
Mixed	PC	×	Server	Comissioning	1
Distributed 1	×	Server	Server	Production line	Multiple
Distributed 2	×	IPC	Server	Multiple production lines	Many

¹⁾ in Distributed mode, ArtiMinds RPS will still be used to initially create the robot programs.

4.6.1 Local Mode

The simplest setup is **local mode**. For this mode ArtiMinds RPS and ArtiMinds LAR are installed on the same computer. The robot program is created with ArtiMinds RPS and transferred to the robot (see chapter 5.1). During execution of the program, the robot connects to the computer and streams the data to ArtiMinds RPS. Within ArtiMinds RPS the data is processed and forwarded to ArtiMinds LAR (on the same computer). ArtiMinds LAR stores the streamed data in the database (on the computer). The data can be visualized in the browser. This setup is typical during commissioning.

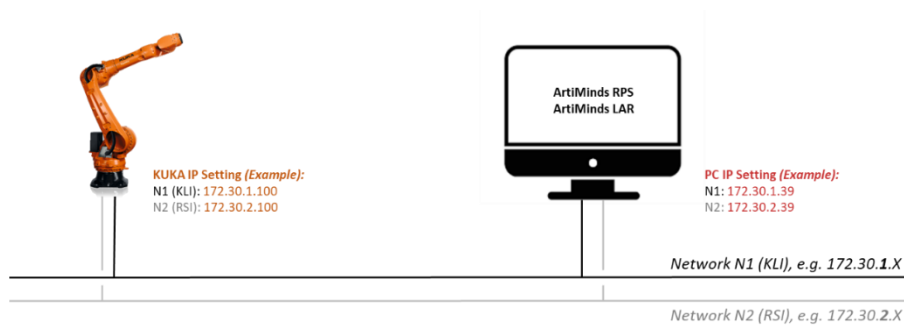
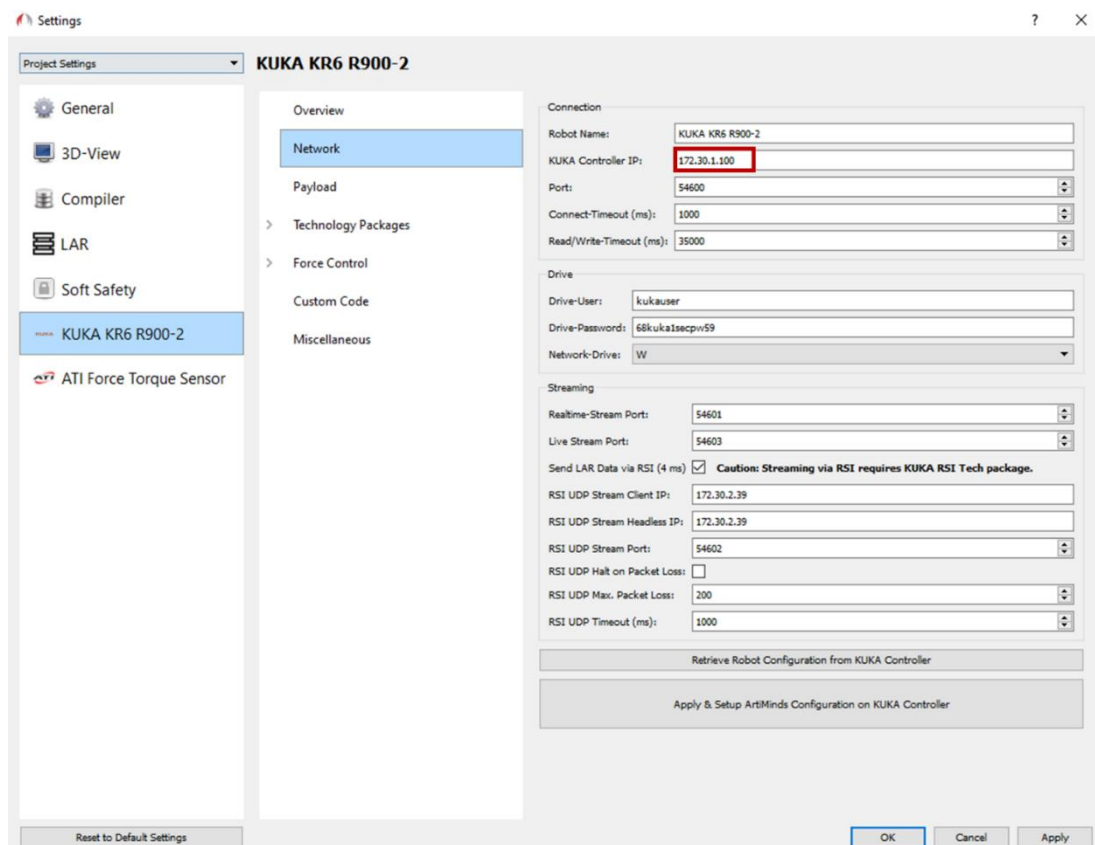


Figure 1 - Local mode

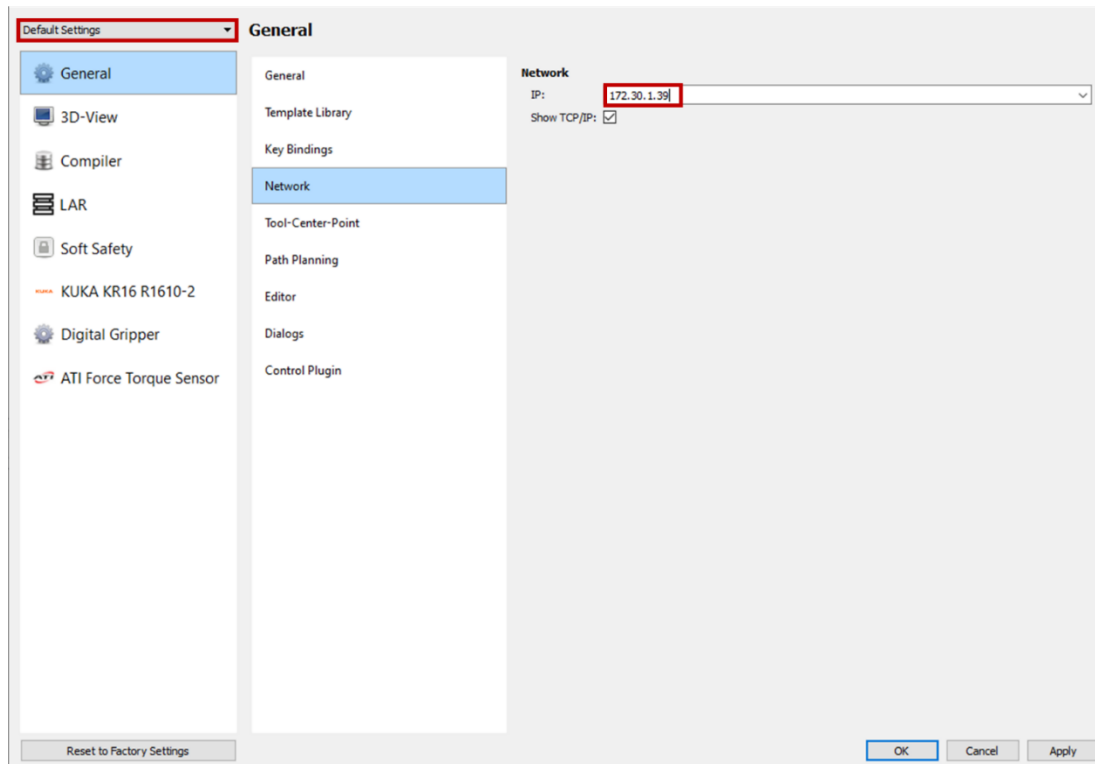
Configuration for Local Mode

The following steps are necessary to configure ArtiMinds LAR in local mode.

1. Robot IP address N1

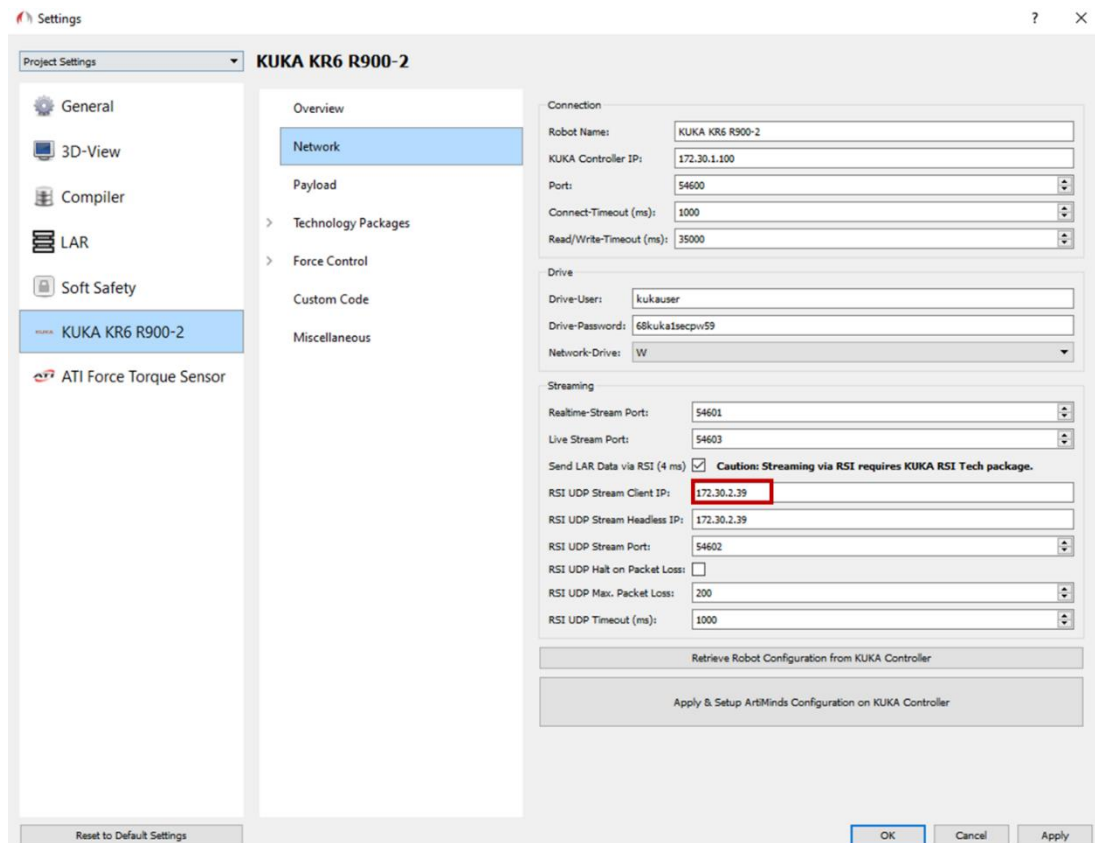


2. Computer/RPS IP address N1 (important: switch to default settings)



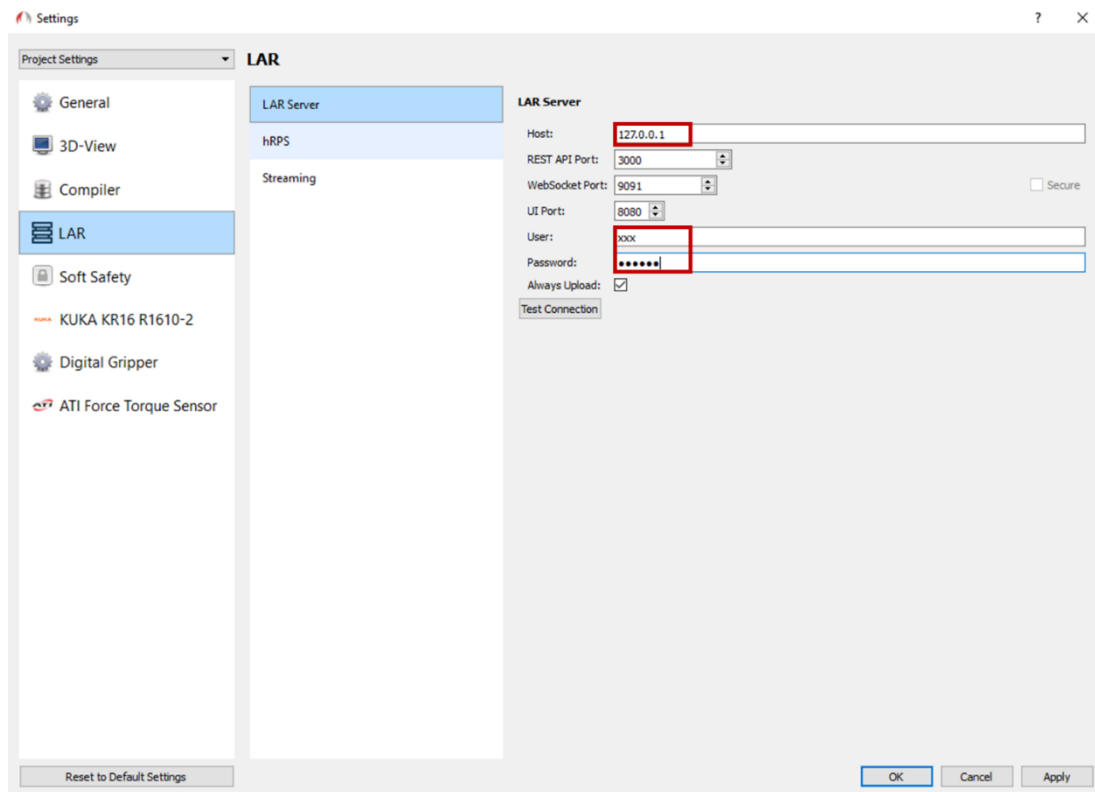
The screenshot shows the 'Default Settings' dialog box with the 'General' tab selected. In the 'Network' section, the 'IP' field is highlighted with a red box and contains the value '172.30.1.39'. The 'Show TCP/IP' checkbox is checked. The 'Reset to Factory Settings' button is visible at the bottom left, and 'OK', 'Cancel', and 'Apply' buttons are at the bottom right.

3. Computer/RPS IP address N2



The screenshot shows the 'Settings' dialog box for 'KUKA KR6 R900-2' with the 'Network' tab selected. In the 'Streaming' section, the 'RSI UDP Stream Client IP' field is highlighted with a red box and contains the value '172.30.2.39'. The 'Send LAR Data via RSI (4 ms)' checkbox is checked, and a caution message states: 'Caution: Streaming via RSI requires KUKA RSI Tech package.' The 'Retrieve Robot Configuration from KUKA Controller' and 'Apply & Setup ArtiMinds Configuration on KUKA Controller' buttons are visible at the bottom. 'OK', 'Cancel', and 'Apply' buttons are at the bottom right.

4. LAR IP address (127.0.0.1 → localhost) + credentials



4.6.2 Mixed Mode

For the **mixed mode** setup, ArtiMinds LAR is installed on an additional server. In this case, the robot data is first streamed (N1 & N2) to the computer and then after processing in ArtiMinds RPS forwarded to ArtiMinds LAR on the server. With this setup it is possible to separate the production network (robot and computer) and the network of the server (computer and server).

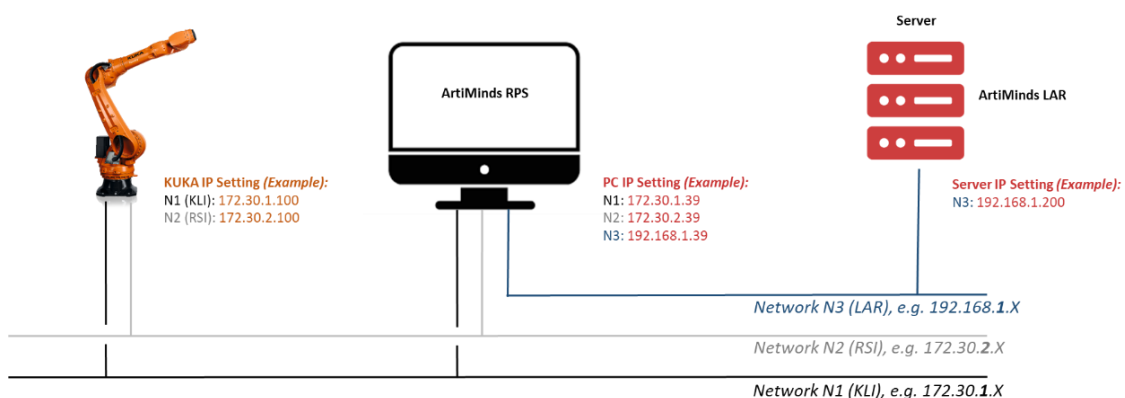
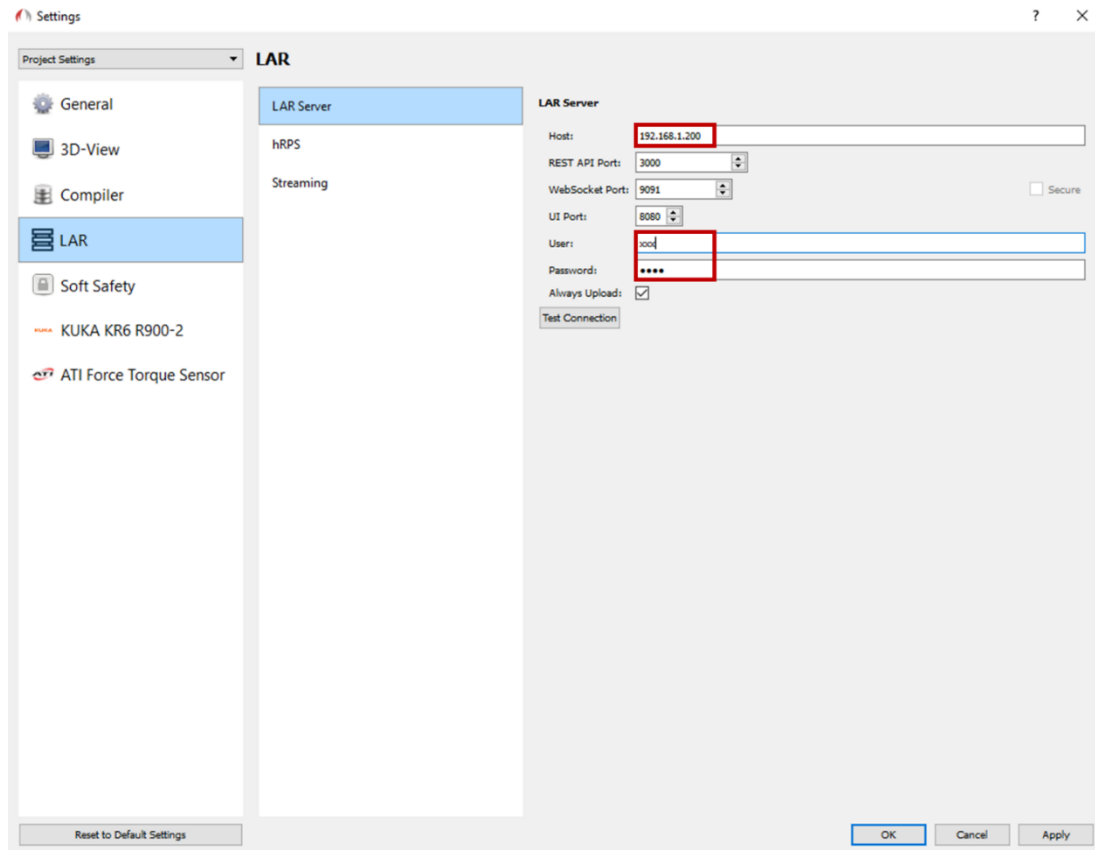


Figure 2 - Mixed mode

Configuration for Mixed Mode

The following steps are necessary:

1. Robot IP address N1 (see above)
2. Computer/RPS IP address N1 (see above)
3. Computer/RPS IP address N2 (see above)
4. LAR IP address + credentials in the new network N3



4.6.3 Distributed Mode

The main difference between the **distributed mode** and the modes above concerns the data flow. For the distributed mode the robot connects to ArtiMinds **headless RPS**. ArtiMinds headless RPS is a multi instance RPS without graphical user interface. ArtiMinds headless RPS can connect to multiple robots at the same time. For each connected robot, headless RPS will spawn one “worker” (internal mechanism). This worker collects and processes all data streamed by the robot and transfers the data to ArtiMinds LAR. ArtiMinds RPS (with GUI) installed on the computer is only used for programming. Therefore, during operation it is not necessary to connect the computer. For the distributed mode there are two different options:

Distributed Mode 1: ArtiMinds headless RPS and ArtiMinds LAR on the same device

- Recommended for automation lines with one of few robots streaming data into one ArtiMinds LAR database. The server must be connected to the production networks N1 and N2.

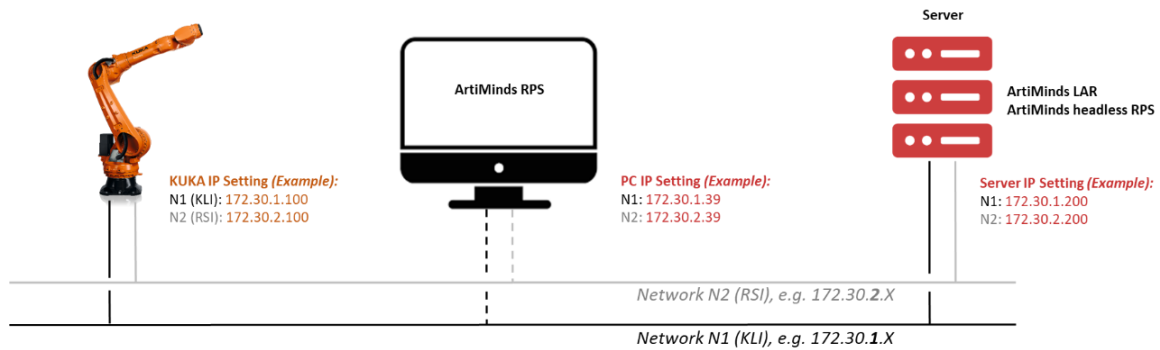
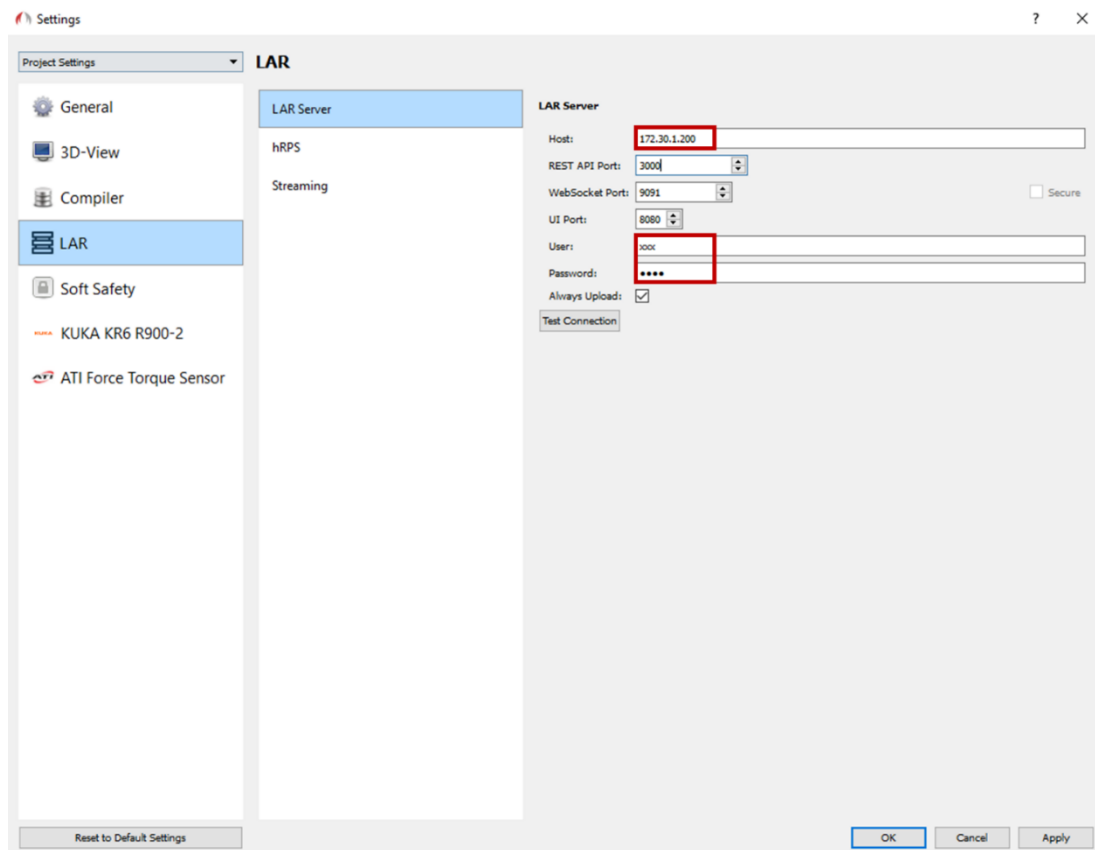


Figure 3 - Distributed mode (1)

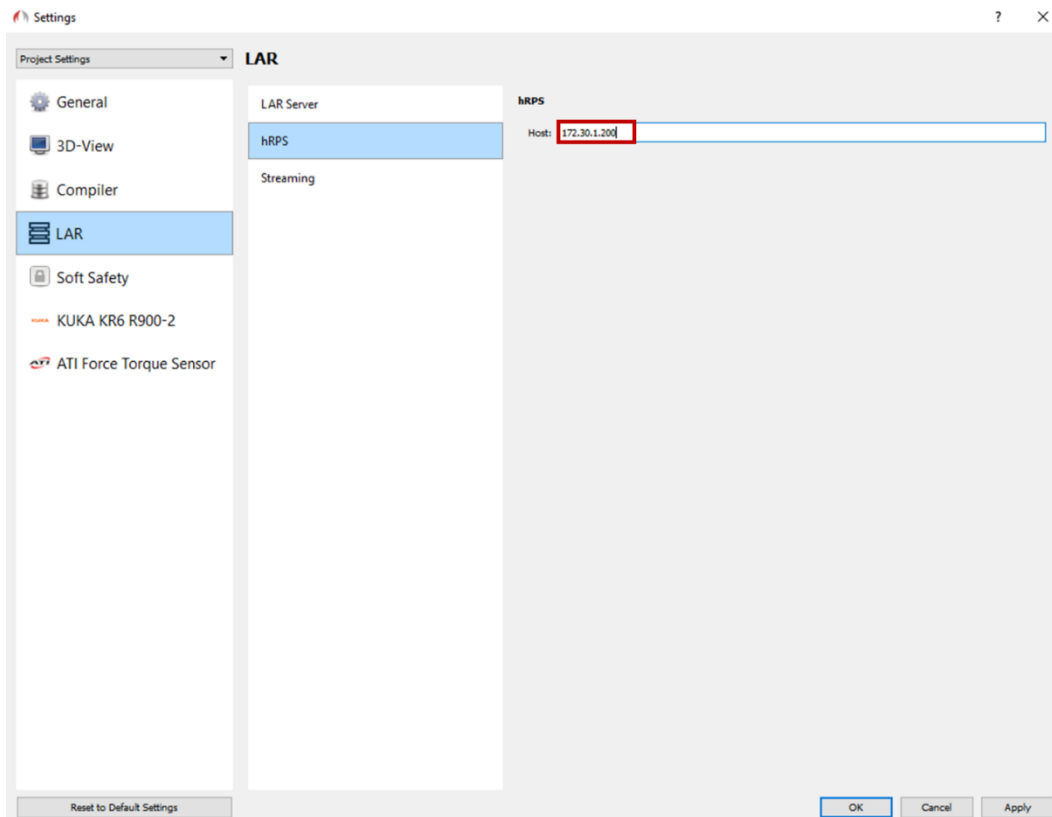
Configuration for Distributed Mode 1

The following steps are necessary:

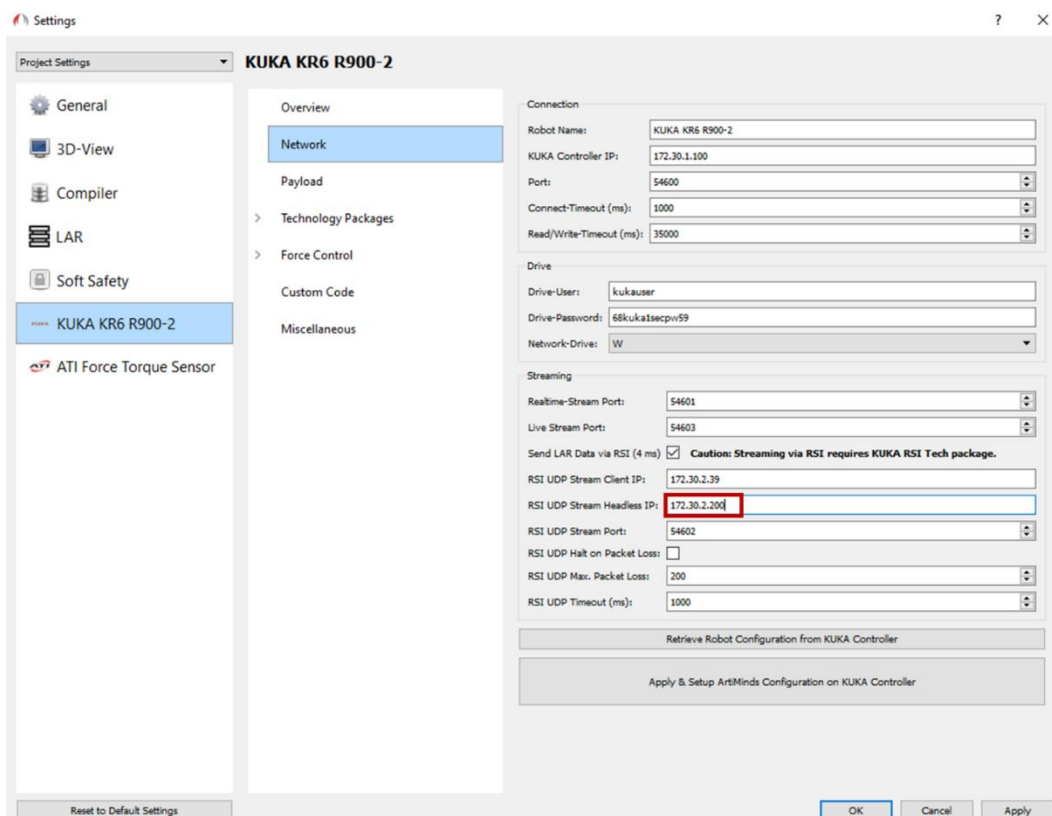
1. Robot IP address N1 (see above)
2. Computer/RPS IP address N1 (see above; only for programming)
3. Computer/RPS IP address N2 (see above; only for programming)
4. LAR IP address + credentials N1



5. Headless RPS IP address N1



6. Headless RPS IP address N2



Distributed Mode 2: ArtiMinds headless RPS and ArtiMinds LAR on different devices

- Recommended if it is necessary to separate the server from the production network, i.e. if it's desired to access the ArtiMinds LAR analyses from a separated office network.
- Recommended if multiple automation lines (potentially each with an individual, separated production network) with multiple robots stream into one ArtiMinds LAR database.
- In this use-case, the IPC must be an edge device connecting both, the local production network (N1 and N2) and the data network (N3).

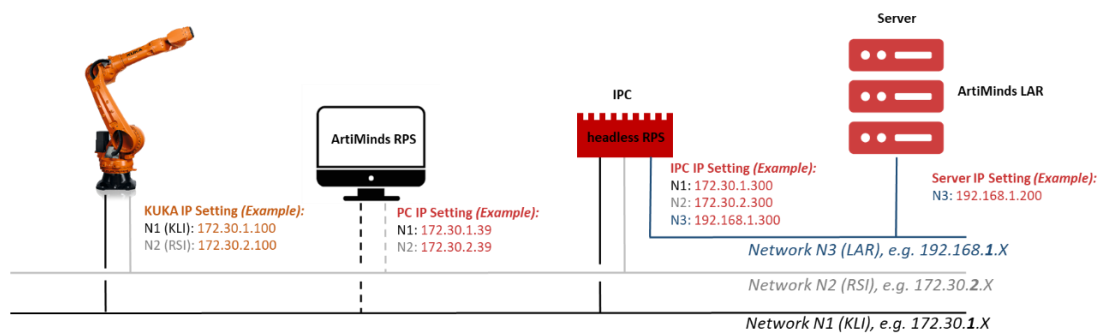
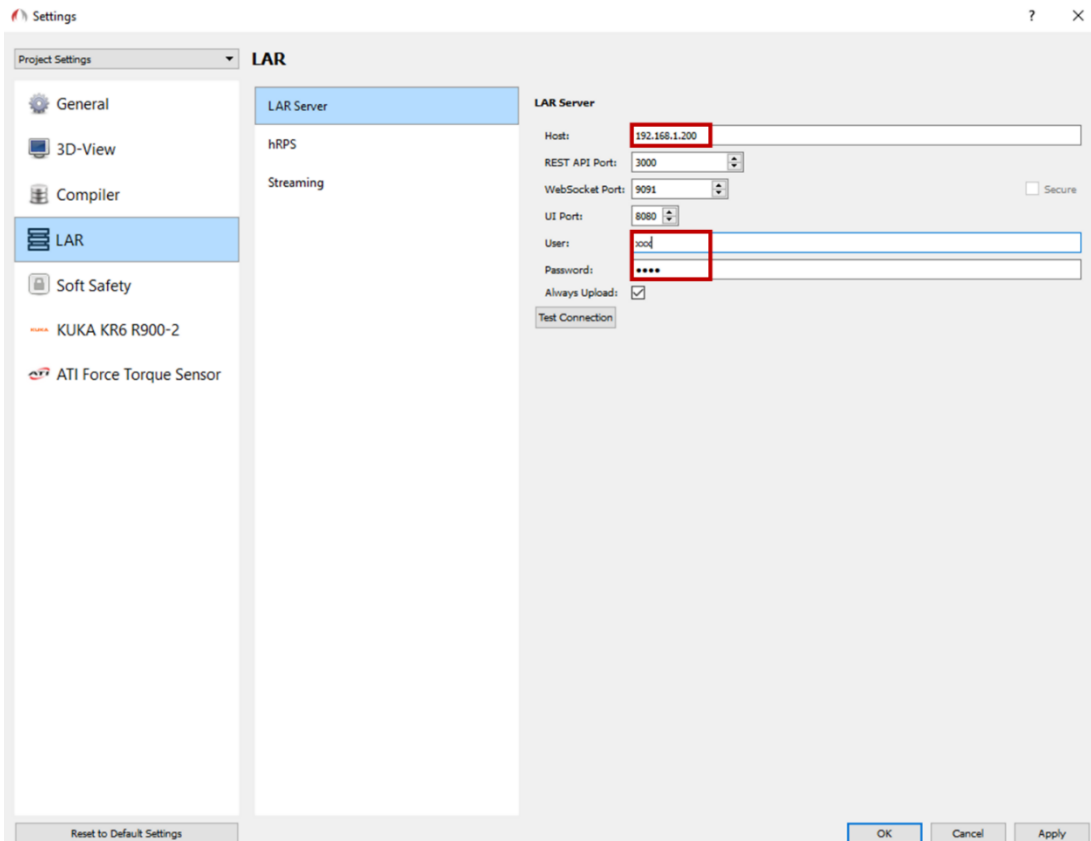


Figure 4 - Distributed mode (2)

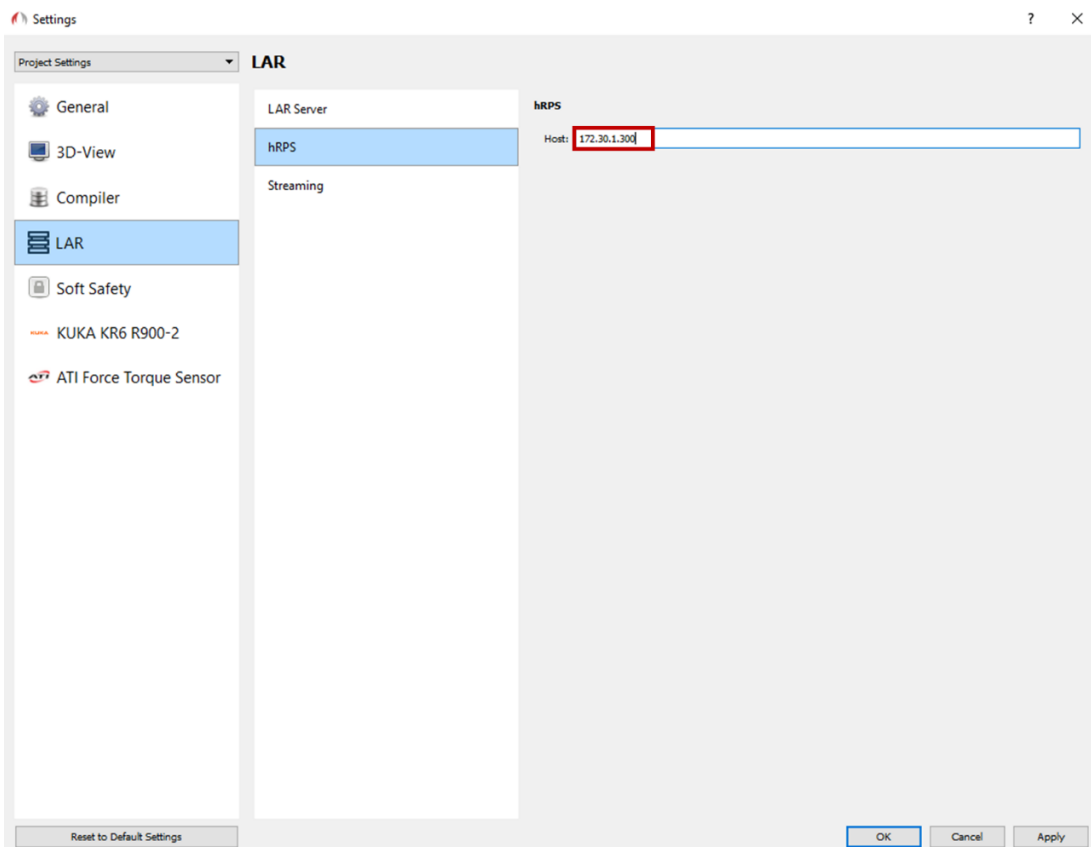
Configuration of Distributed Mode 2

The following steps are necessary:

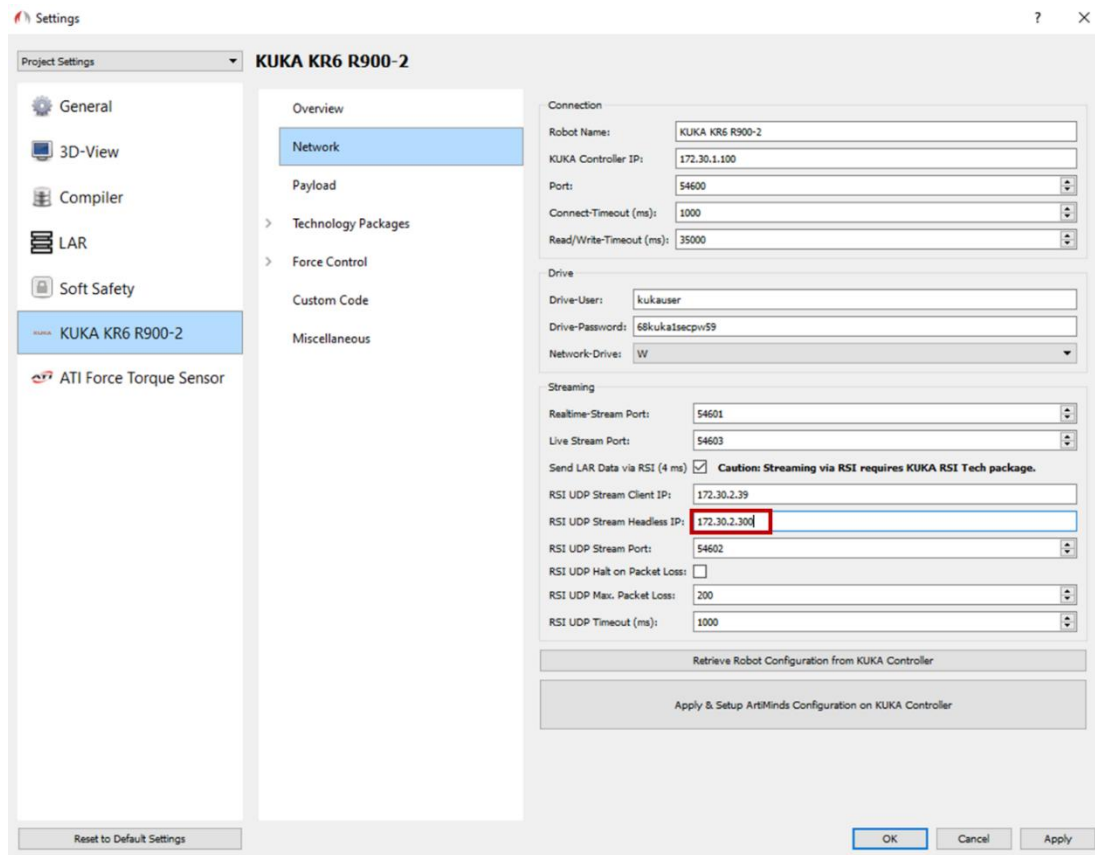
1. Robot IP address N1 (see above)
2. Computer/RPS IP address N1 (see above; only for programming)
3. Computer/RPS IP address N2 (see above; only for programming)
4. LAR IP address + credentials N3



5. Headless RPS IP address N1



6. Headless RPS IP address N2



The screenshot shows the 'Settings' window for a 'KUKA KR6 R900-2' robot. The 'Network' tab is selected under the 'Overview' section. The 'Connection' section contains the following fields:

- Robot Name: KUKA KR6 R900-2
- KUKA Controller IP: 172.30.1.100
- Port: 54600
- Connect-Timeout (ms): 1000
- Read/Write-Timeout (ms): 35000

The 'Drive' section contains:

- Drive-User: kukauser
- Drive-Password: 68kuka1secpr59
- Network-Drive: W

The 'Streaming' section contains:

- RealTime-Stream Port: 54601
- Live Stream Port: 54603
- Send LAR Data via RSI (4 ms): ☒ **Caution: Streaming via RSI requires KUKA RSI Tech package.**
- RSI UDP Stream Client IP: 172.30.2.39
- RSI UDP Stream Headless IP: 172.30.2.300 (highlighted with a red box)
- RSI UDP Stream Port: 54602
- RSI UDP Halt on Packet Loss: ☐
- RSI UDP Max. Packet Loss: 200
- RSI UDP Timeout (ms): 1000

At the bottom of the settings panel, there are two buttons: 'Retrieve Robot Configuration from KUKA Controller' and 'Apply & Setup ArtiMinds Configuration on KUKA Controller'. The 'OK', 'Cancel', and 'Apply' buttons are at the bottom right of the window.

5 Operations

5.1 Copying programs to the robot

5.1.1 ArtiMinds RPS

After you created a program, you can use the red “Play” button to initiate a transfer of the generated source code to the robot:

1. Click the red “Play” button.
2. The current pose of the robot is queried from the robot and if it does not correspond with the set home-position of your program, a joint-based transfer motion is generated and simulated. Acknowledge it by clicking “Yes”.

5.1.2 KUKA robot

DirectoryLoader Version \geq 3.0:

No manual actions are required on the teach pendant. Status messages about the copy-process will be displayed on the teach pendant and the program is activated automatically after a successful transfer.

DirectoryLoader Version $<$ 3.0:

1. On the teach pendant you will be asked to switch to external mode. Do so by turning the key, choose “Ext” and turn the key back to operational mode. You have a timeout of 30 seconds to do so.
2. The program is copied to the robot and you will be asked to switch to an execution mode. Again turn the switch and choose “T1” / “T2” or “Auto”. Attention: The robot will perform with full speed in Auto mode! Turn switch back.
3. The program will be loaded for execution.
4. Depending on the chosen mode you can now start execution:
5. In T1 / T2 mode: Hold down one of the dead-man switches on the backside of the panel and press and hold the green play-button on the front. The robot will drive to its home position and stop there. Let go of the play-button. Press and hold it down again to start executing the actual program.

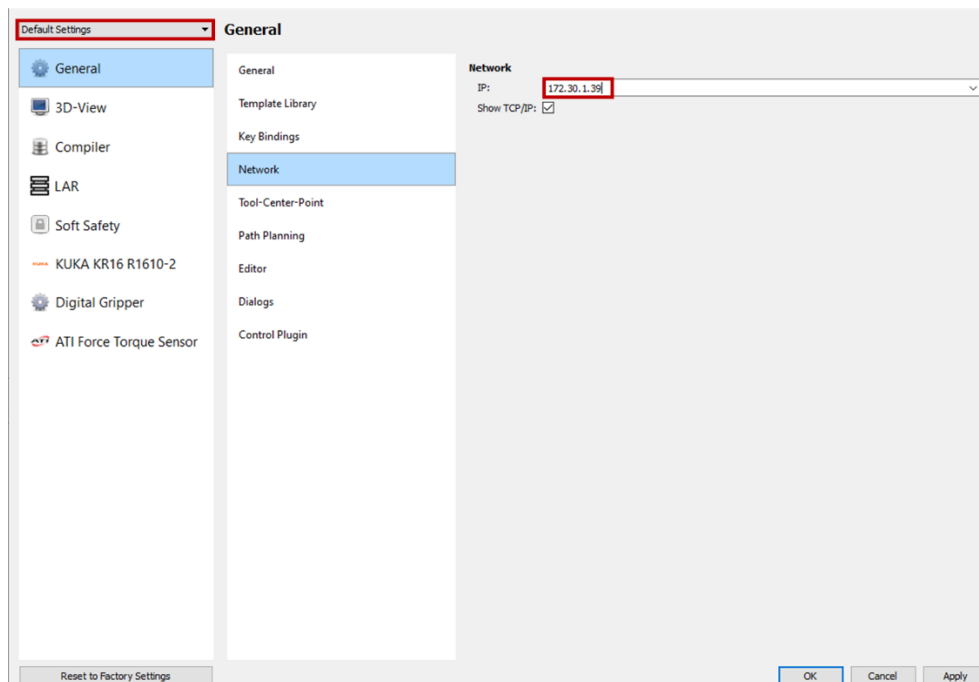
In Auto mode it is sufficient to press the play-button only once to start the execution of the complete program. Make sure the robot is at its home-position. Otherwise let it drive to home-position on T1 / T2 mode as described above.

5.2 Teaching/Demonstrations

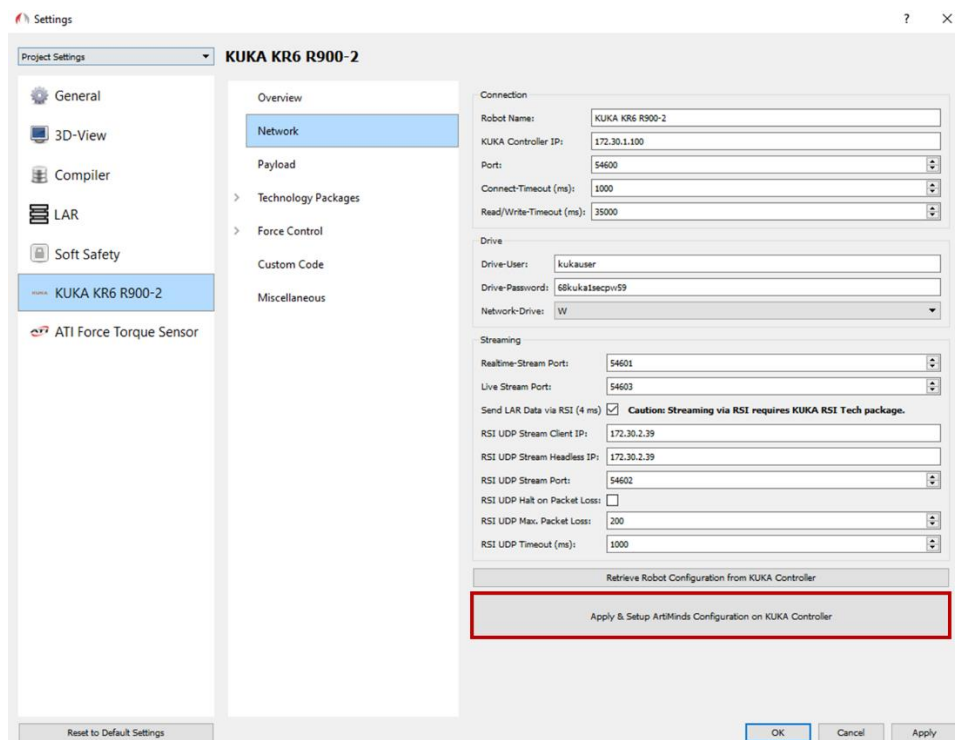
“Use Demonstration” button in the wizard of an ArtiMinds RPS template: When teaching target points of templates with the robot, make sure to have the right tool selected on the teach pendant. Especially if you defined the weights of your tools, always choose the same tool for demonstration and execution. Otherwise calibration issues will occur. The same applies when using the “Record” button in the main menu bar at the top.

5.3 Change IP address of the connected PC (with ArtiMinds RPS)

The connection between the KUKA robot and the PC which runs ArtiMinds RPS is established by the robot. Therefore, the setup of the KUKA robot must be adjusted when the IP address of the PC is changed. First check if the correct IP address for the PC is selected:

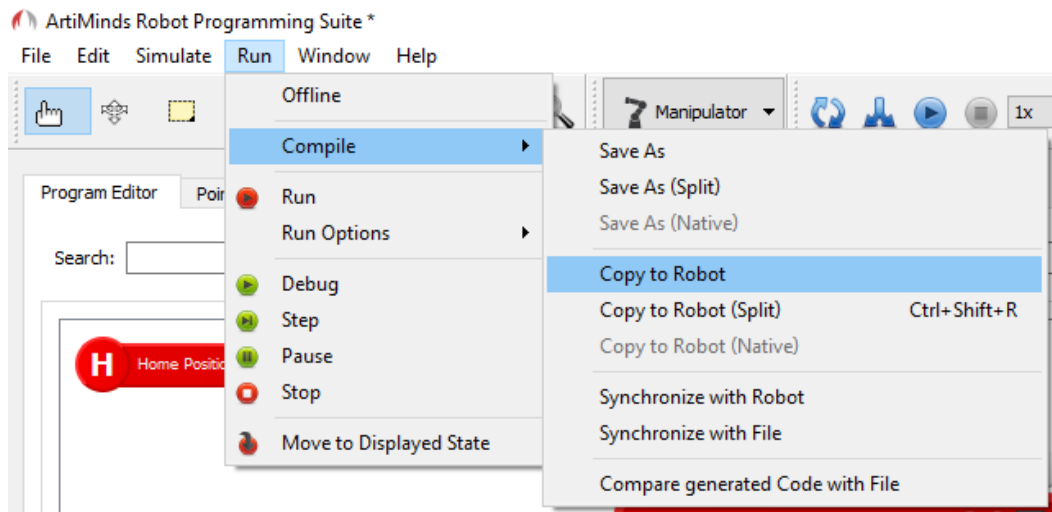


Then go to the KUKA settings page, click the “Apply & Setup” button and following the instruction of the user dialog:

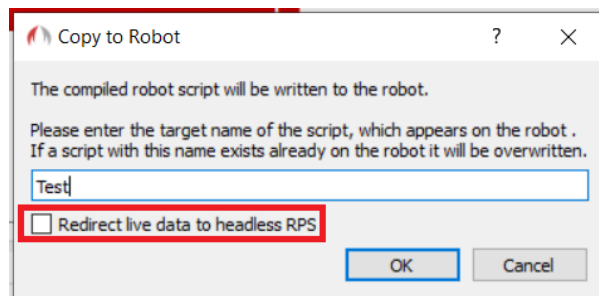


5.4 Live data streaming with the headless RPS (hRPS)

If you intend **LAR via Headless RPS**, you must use the main menu bar to copy your programs to the robot: “Run → Compile → Copy to robot”. As only here you have the option to activate “Redirect live data to headless RPS”.



After clicking “Copy to Robot”, a pop-up window will appear. Make sure that the checkbox is selected to forward the live data to the headless RPS. For better understanding, take a look at the following screenshot.



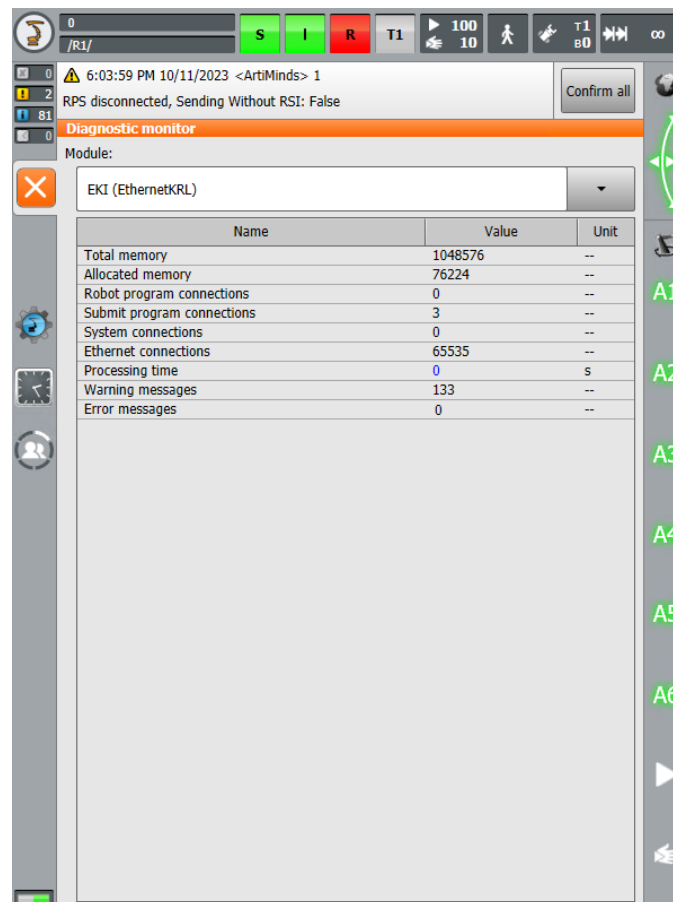
7. Troubleshooting

- In general check the log/error messages on the teach pendant of the KUKA robot.
- Additional help pages and manuals are provided, e.g. for configuring force-torque sensors or grippers. Open the tutorials by pressing the “F1” key in the ArtiMinds RPS.
- When the copying to the robot fails, this may also indicate syntax errors in your code. Check the syntax of manually added code in your “Code” templates in the ArtiMinds RPS and in “File->Settings->Kuka>Custom Code (Expert)”.
 - Select the file on the teach pendant and look at the error list (“Fehlerliste”).
 - Code on the controller has to use Windows \r\n linebreaks.
- Network-Drive setup: If you cannot connect to the drives of the robot via Windows Explorer, make sure that Port 445 is listed in the Port-Forwarding of the KUKA Control Panel Network Settings.
- Setup process (ArtiMinds RPS config page):
 - If errors occur while configuring settings on the KUKA controller (modifying sps.sub or \$config.dat), please assure that those files have write access. Check file permissions and properties by accessing the shared network C: drive via Windows Explorer.
- Communication problems (ArtiMinds RPS cannot switch to “Online” mode):
 - Acknowledge all error messages on the teach pendant.
 - Make sure that the submit interpreter is running (“S” indicator is green)
 - Start the “Diagnose Monitor”: It should list two open connections for the Submit program.
 - Check your PC side: Use the following PowerShell commands (Windows start menu and typing in PowerShell) to test if both ports can be reached over network:

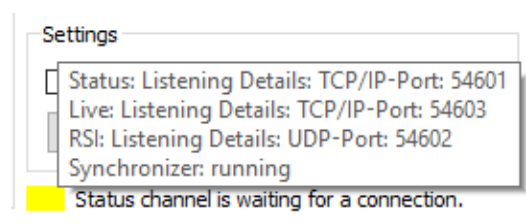

```
Test-NetConnection -RemoteAddress 172.30.1.39 -Port 54600
Test-NetConnection -RemoteAddress 172.30.1.39 -Port 54601
```

➔ Replace 172.30.1.39 by your computers IP address! The commands basically test if one (e.g. KUKA robot) can connect to the PC with the IP address 172.30.1.39 and ports 54600/54601. If these tests fail, check Windows Firewall and additional installed security software on the PC if one blocks these ports/incoming connections.
 - If this test fails, make sure you did **not** add the ports to the NAT settings of the controller!
 - When the entered IP address of the PC is correct, make sure the ports are not blocked on the computer by the Windows Firewall or additional security software.
- If variables within the .src files are unknown, open up the according .dat file on the teach pendant, add a “Space” character at the end of an arbitrary line and save the .dat again. This will trigger a reparsing.
- If you see a “RSI bad” error, check, if you are using a real-time capable network for RSI. You can look this up in the KUKA teach pendant network (German “Netzwerk”) settings. Click on “Advanced” (“Erweitert”) and choose the virtual interface called “RSI”. There the address-type must be “Mixed IP Address” (“Gemischte IP-Adresse”) or Real-Time Network (“Echtzeit Netzwerk”).
- When further support is needed, please contact support@artiminds.com and provide a KRCDiag file for easier debugging if possible. A KRCDiag can be generated as follows:
 1. Connect an USB drive to the KUKA teach pendant (formatted as FAT32).
 2. On the KUKA teach pendant click on “File -> Archive -> USB (KCP) -> KRCDiag” (German KUKA “Datei -> Archivieren -> USB (KCP) -> KRCDiag”).
 3. The KRCDiag file is written to the USB drive. Depending on the stored data on the robot, the file can have sizes of 30MB+.
- On KUKA open the main menu and click on “Diagnosis->Diagnostic Monitor” (German KUKA “Diagnose->Diagnosemonitor”) to inspect details of any installed tech package. Especially check “EKI: EthernetKRL” for connection between robot and PC/RPS via Submit Interpreter.

Three “Submit program connections” should be visible as ArtiMinds RPS uses three. No errors should be visible. Check the EthernetKRL logs for further details (“KRC\Roboter\log\EthernetKRL”).



- On Kuka go to “Main Menu → Display → Variable → Flags” (German KUKA: “Anzeige → Variable → Flags”) and check the used flags. Flags can be defined in ArtiMinds RPS by clicking on “File → Settings → Kuka → Technology Package → Submit Interpreter”. The ArtiMinds RPS submit program should not use the same flags as other submit programs. When the Submit Interpreter is green (no error) and displays the rps_send_data task this is usually a good sign.
- In ArtiMinds RPS open the “Points & Paths → Live” tab and hover of the colored status checkbox to validate the connection state, used ports etc.



- Check the configuration of the network interface on KUKA. A KLI network with real-time/mixed IP address should be used. “Windows Interface” checkbox enabled. Additionally a RSI interface should be configured when a force-torque sensor or ArtiMinds LAR are used. It’s recommended to use 255.255.255.0 as subnet mask and IP addresses that share a subnet. E.g. 172.30.1.XXX and 172.30.2.XXX.

Please note that KUKA does allow certain IP address ranges, e.g. 192.168.0.0 ... 192.168.0.255. For more details see Kuka KSS manual, chapter Configuration.

Notes

Changelog

- V1.0:** Initial version
- V1.1:** Added section 2.1 about moving robot base via Machine-Data-Configuration in KUKA.WorkVisual.
Corrected section 1.3 with KSS specific variable names.
- V1.2:** Added hint to create DirectoryLoader target folder on robot if not present. Section 1.3.
- V1.3:** Changed example target directories for DirectoryLoader in section 1.3.
- V1.4:** Extended section 1.4: Copy to robot with DirectoryLoader 3.x.

Clarified variable declaration in section 1.3.
- V1.5:** Restructured network setup. Changed capitalization of DLSourceDir.

Added pages of the KUKA settings dialogs. Clarified the IP settings for RSI streaming.
- V1.6:** Fixing some spelling errors and improving the layout.
- V1.7:** Added images, additional explanations and reworked the structure.
- V1.8:** Formatting.
- V1.9:** Added additional image to explain the KUKA teach pendant user interface.
- V1.10:** Extended list of broken EthernetKRL versions and the resulting error messages.
- V1.11:** Added hints to not add Ports to Port Forwarding settings on the HMI. Added troubleshooting for SMB Port. Added troubleshooting for write protected config files on the controller.
- V2:** Restructure, additional explanations (mainly LAR and RSI), retook pictures.