Adept Cheat Sheet:

Adept Limits:

        Max force = 178N   Max speed = 9.15 m/s   Max payload = 9kg

Start up:

        Turn on power from below. Make sure fan is on.
        Type "en po" to enable power. Type "ca" to calibrate.

During operation:

        Ctrl + S = stop   Ctrl + Q = continue
        Ctrl + C = break   Ctrl + U = cancel current input line

Writing commands: (every command can be typed in lowercase)

        To type instructions into a text file: type MC or continuing reading **Text editor**
        To execute commands from terminal: type DO

Text editor:

        LOAD [insert directory name]   --> to open a directory of files
        SEE [insert filename]   --> open a text file to edit
        press Insert Key   --> to edit code
        press F4   --> exit (saves program only to memory)
        STORE [insert directory name]   --> saves the program on the disk

Function in text editor: (Let me know if you figure out how to copy and paste...)

        Shift key accesses the yellow commands
        Ctrl + Delete   --> deletes the current line
        COPY   --> copy current line
        CUT   --> cut current line
        PASTE   --> paste current line

Parameters and Switches:

I thought these won't be as necessary, so I didn't include them. If necessary, I can include them in a few minutes.

Useful Switches:

        TRACE   --> program step displays before execution
        DRY.RUN   --> for testing program without robot motion

Motion Instructions:

        Two types of motion. Joint motion (tell joints to move), translation (Cartesian coordinates to move)
        Measured in degrees and millimeters (mm)

	ENABLE CP	--> makes motions continuous between points.
		"disable cp" stops cp

Move:	MOVE loc	--> moves the robot to a location
	DRIVE joint, degree, speed	--> moves a single joint
	APPRO loc, distance	--> moves to a position given a distance from a location
	DEPART distance	--> moves vertically away from current location

Speed:	SPEED percentage	--> sets speed as a percentage of max speed
	SPEED percentage [ALWAYS]	--> sets speed again. "ALWAYS" applies speed to following code
	ACCEL acc, decc	--> sets acceleration, deceleration as percentage of max

Time:	DELAY seconds	--> delays motion for "seconds"
	PAUSE	--> stops till user types "proceed"
	BREAK	--> delays motion till current motion finishes
	DURATION seconds	--> sets time for subsequent motion to take

Location / Transformsformation

	WHERE	--> displays location of robot (can be typed in console)
	HERE variable_name	--> assigns the current location to variable_name
	POINT loc_var	--> assigns a location expression to loc_var.
		(Eg: loc_var = loc_exp)
	SET loc_var = loc_exp	--> assigns a location expression to a location variable
	TRANS(x, y, z, n, p, r) (FUNCTION)	--> translate to defined location
	INRANGE (loc)	--> determines of loc is within workspace

Program Execution

	EXECUTE [insert filename]	--> runs program
	ENABLE/DISABLE TRACE	--> displays code being run
	ABORT	--> stops program. Type "proceed" to continue

Programming Features

	;	--> to add comments to code

Logical/relational operators: <, >, <=, =<, ==, >=, =>, <>, AND, NOT, OR, XOR

conditional execution:	IF logical_exp THEN ..... [ELSE] ..... END

iteration:	FOR var = start TO final [STEP inc] ..... END

WHILE logical_exp DO ..... END

DO ..... UNTIL logical_exp