

Synopsis



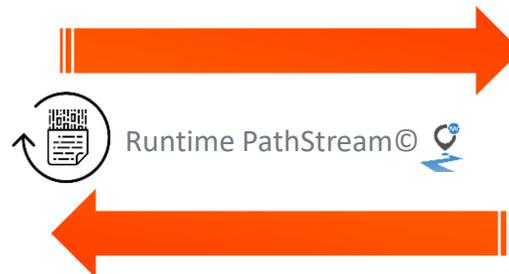
Editeur 3D de trajectoires
(Exemple: AdaOne  ADAXIS)
+
Post-Processeur PathStream©
(compatible .adaStream)



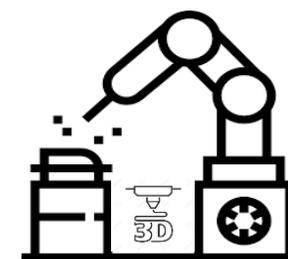
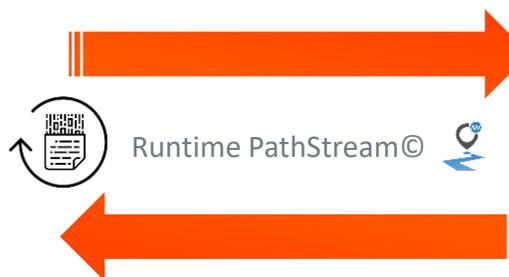
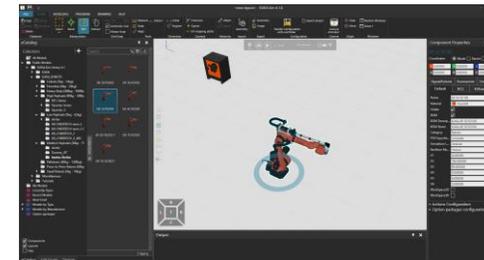
KUKA.OfficeLite



Contrôleur KRC4 ou KRC5



Trajectoires et actions robot
Simulées sur KUKA.Sim



Trajectoires et actions robot
réelles

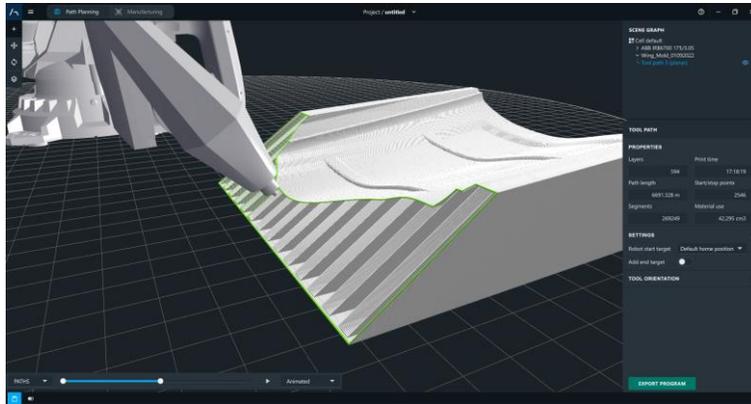


Logiciel puissant et intuitif pour la fabrication additive robotique.

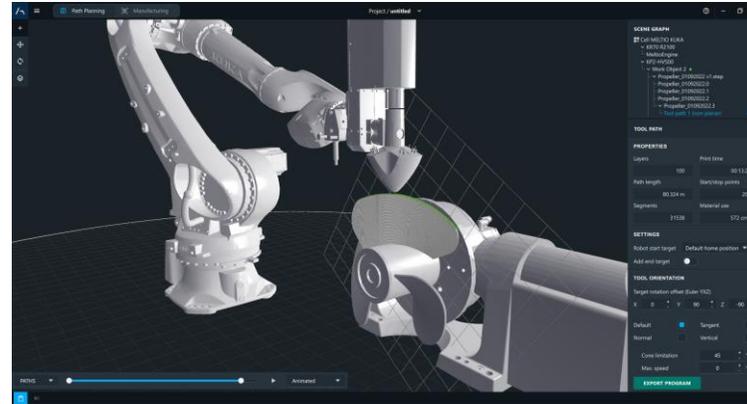
- > Planification de trajectoires multi-axes
- > Simulation de fabrication
- > Détection de collisions
- > Correction en temps réel



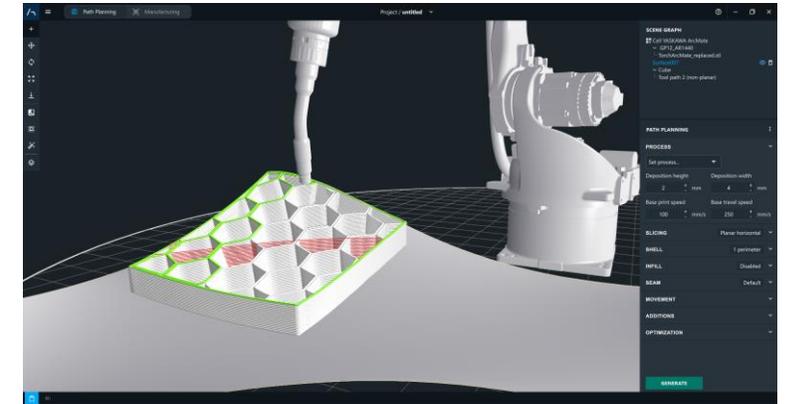
Autonome pour réaliser facilement une programmation complexe



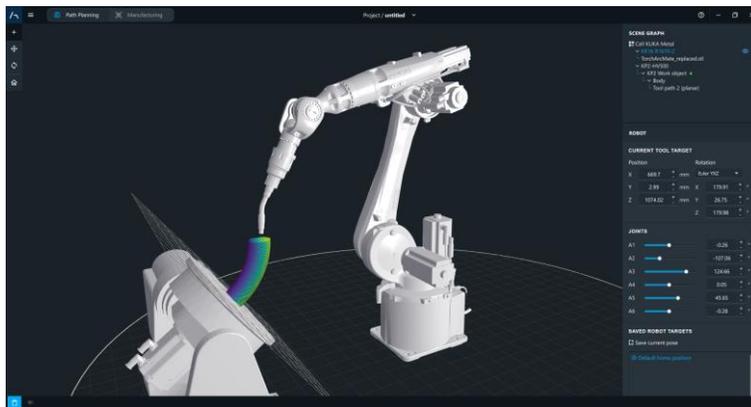
Angleg slicing



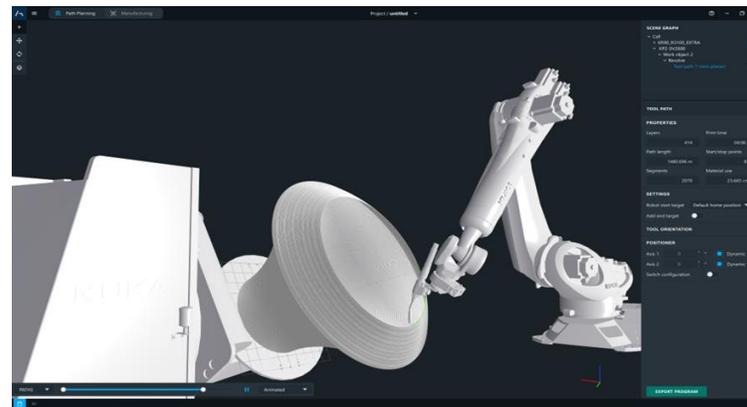
Radial slicing



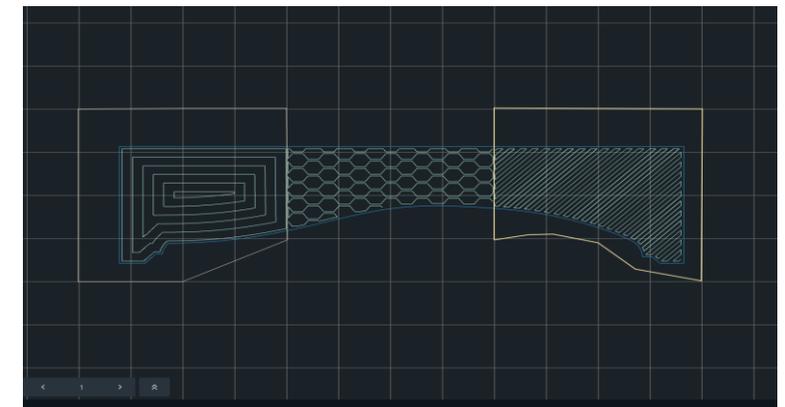
Non-planar slicing



Along a curve slicing



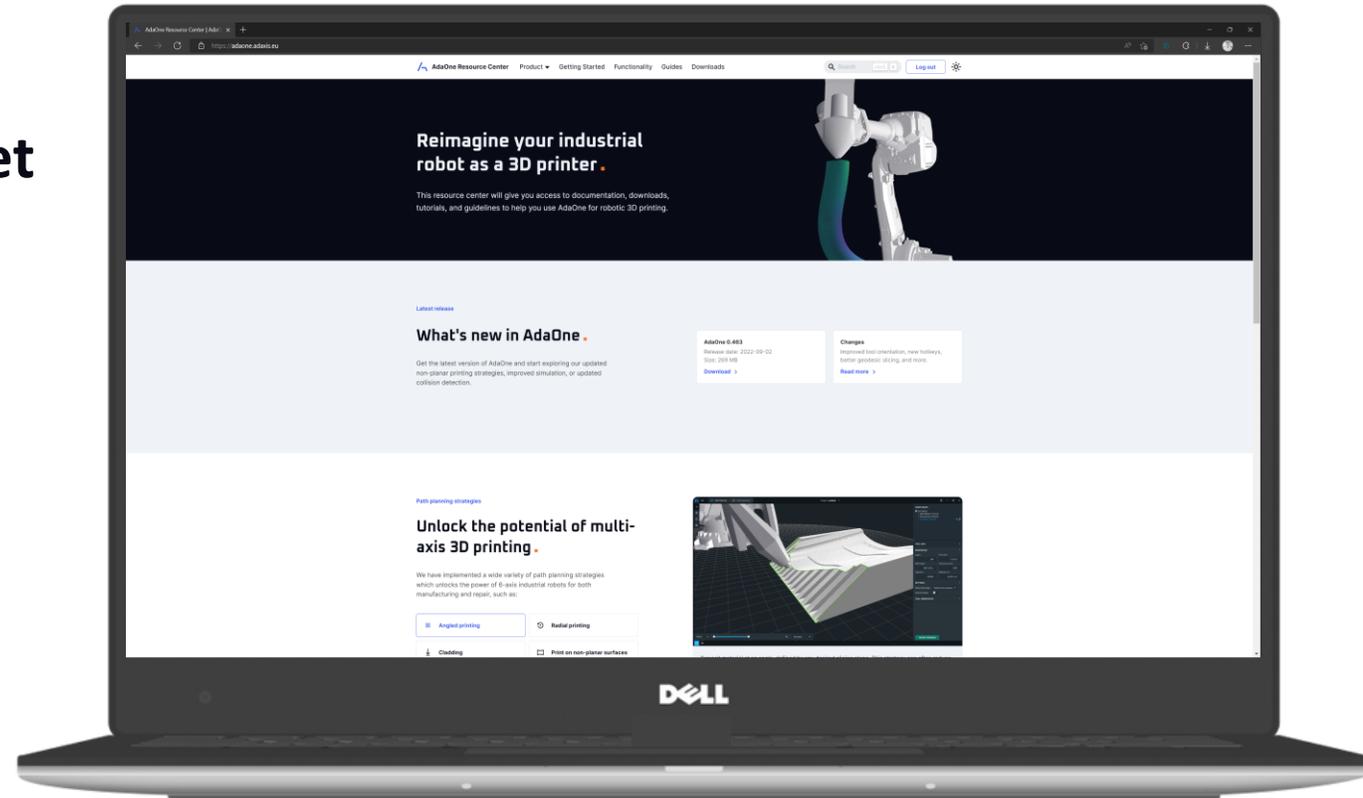
Revolution slicing

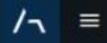


Advanced infill

Plateforme de connaissances unique et à jour

- > Documentation et didacticiels vidéo
- > Profils d'impression et exemples de projets
- > Gestion des téléchargements et des licences
- > Feuille de route et forum de discussion

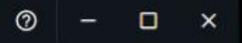




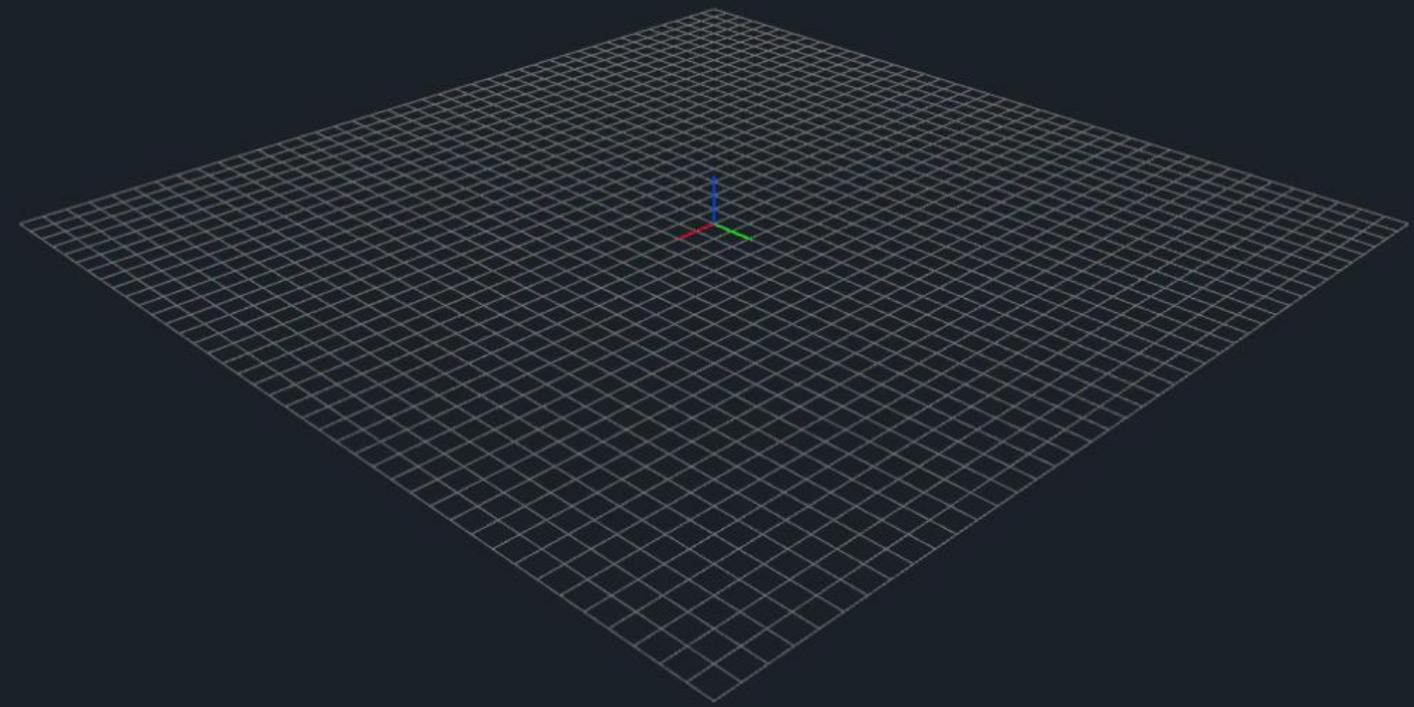
Path Planning

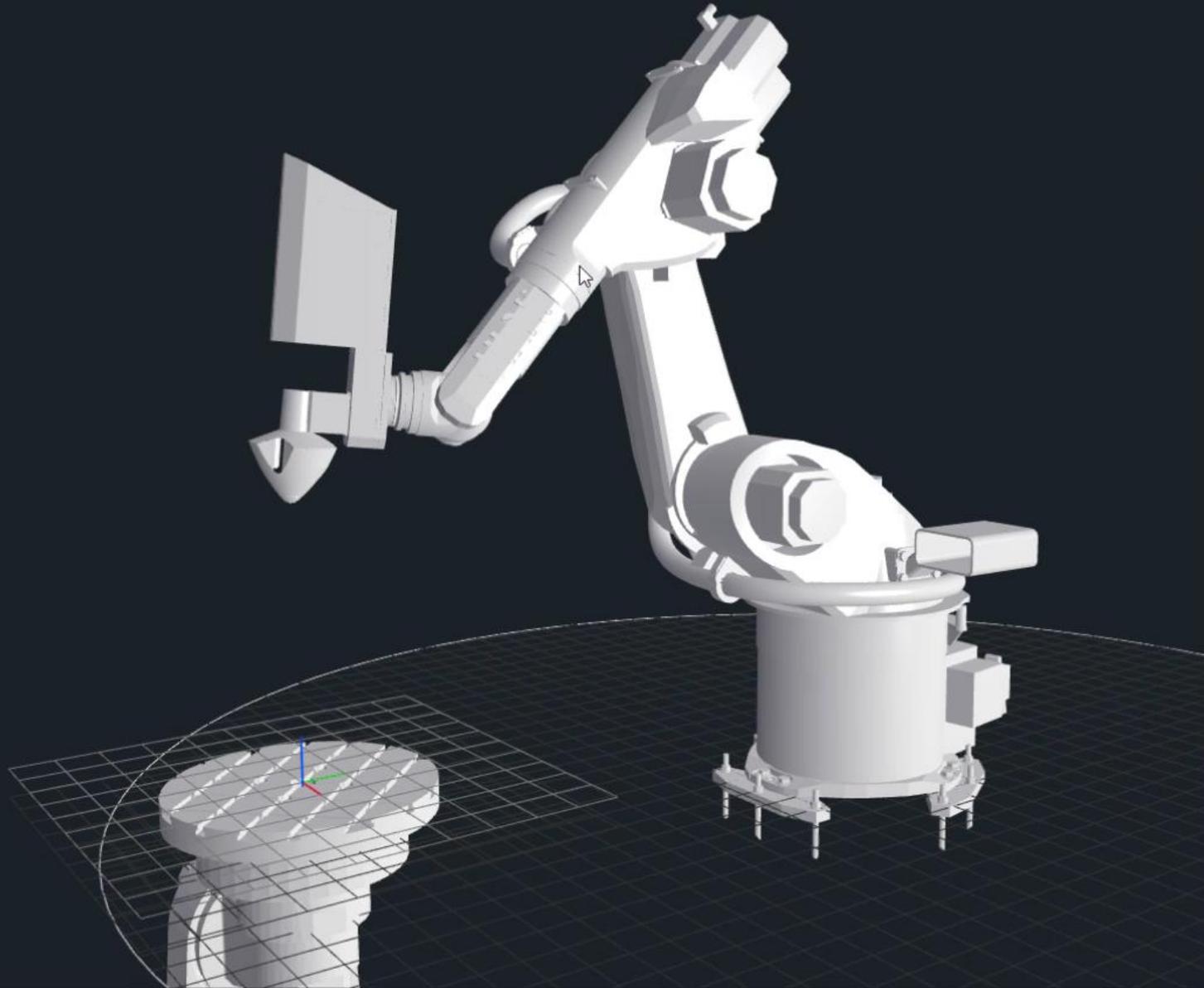
Manufacturing

Project / **untitled**



SCENE GRAPH
Cell untitled





SCENE GRAPH

- Cell cell_webinar
 - > KR60HA
 - ▼ DKP-400
 - ↳ DKP Work object
 - ↳ Unnamed-Cellule_WLAM_Table_...
 - ↳ Work Object 3

WORK OBJECT

SETTINGS

Set as active

Grid spacing 100 mm

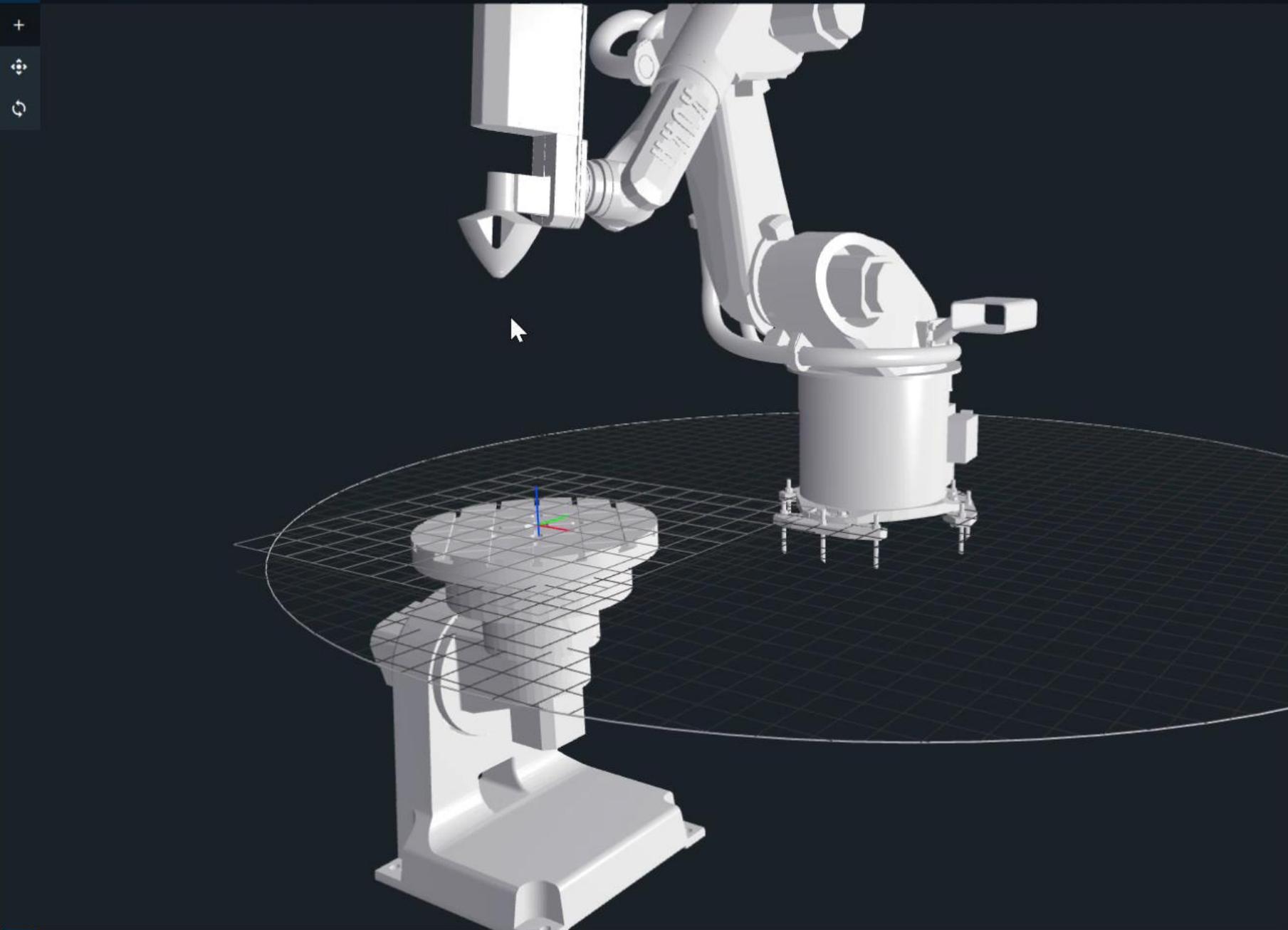
TRANSFORM

Position			Rotation		
X	0 mm		Euler XYZ		
Y	0 mm		X	0 °	
Z	0 mm		Y	0 °	
			Z	0 °	

SIZE

Minimum			Maximum		
X	-500 mm		X	500 mm	
Y	-500 mm		Y	500 mm	





SCENE GRAPH

- Cell cell_webinar
 - KR60HA
 - meltio.obj
 - DKP-400
 - DKP Work object
 - Unnamed-Cellule_WLAM_Table_...
 - Work Object 3

WORK OBJECT

Set as active

Grid spacing 100 mm

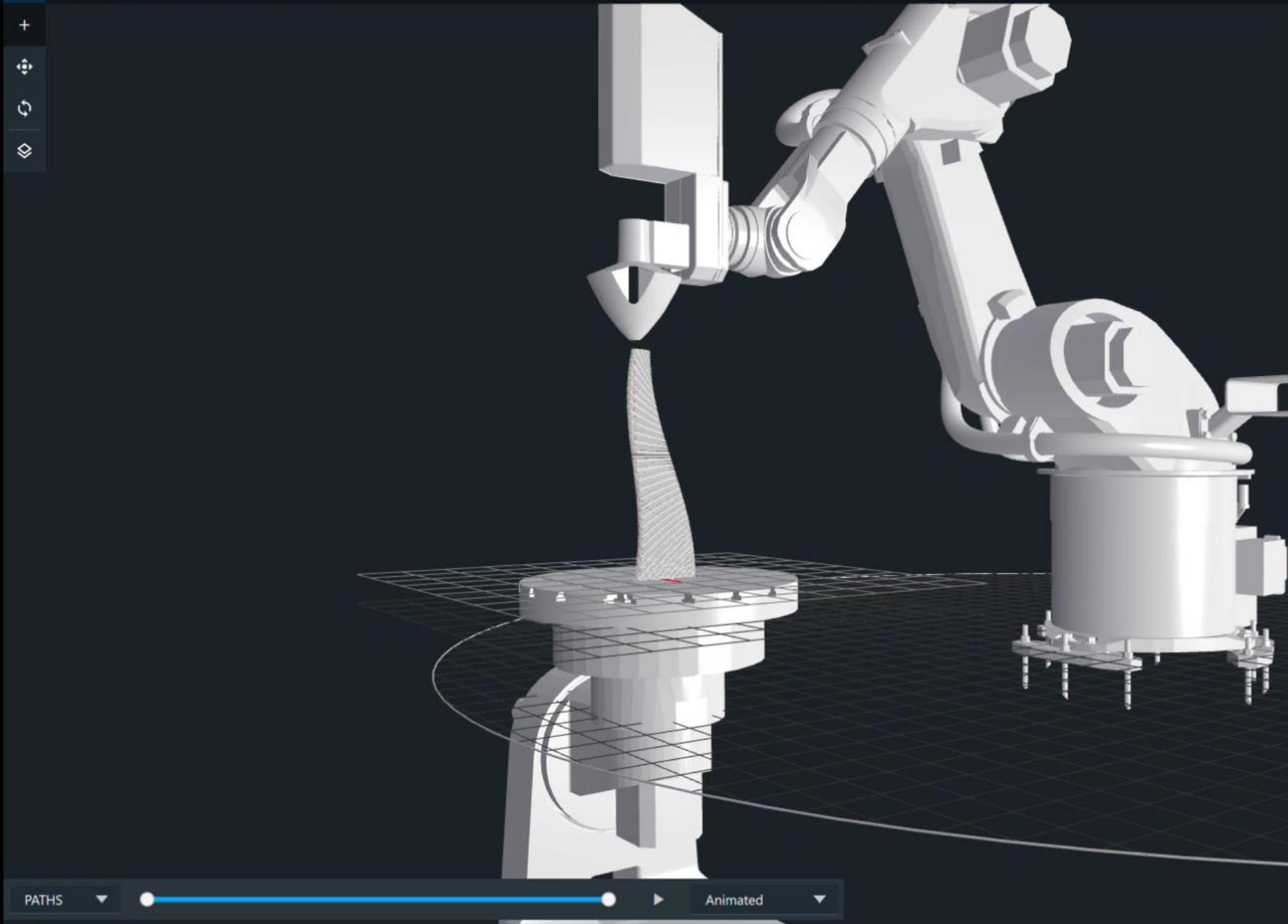
TRANSFORM

Position			Rotation		
X	0 mm		Euler YXZ		
Y	0 mm		X	0 °	
Z	67 mm		Y	0 °	
			Z	0 °	

SIZE

Minimum		Maximum	
X	-500 mm	X	500 mm
Y	-500 mm	Y	500 mm





SCENE GRAPH

- Cell untitled
 - > KR60HA
 - DKP-400
 - Work Object 2
 - Work Object 3
 - ADDIMADOUR_FORMNEXT_2...
 - Tool path 1 (planar)
 - Unnamed-Cellule_WLAM_Table_...

TOOL PATH

Layers	499	Print time	00:36:55
Path length	222.207 m	Start/stop points	1996
Segments	100758	Material use	221 cm3

SETTINGS

Robot start target: Joint target 1

Add end target:

TOOL ORIENTATION

POSITIONER

EXPORT PROGRAM

PATHS Animated



AdaOne rend l'impression 3D robotisée accessible à tous.

10x plus rapide

80% d'économie

Robot et processus agnostique



Synopsis



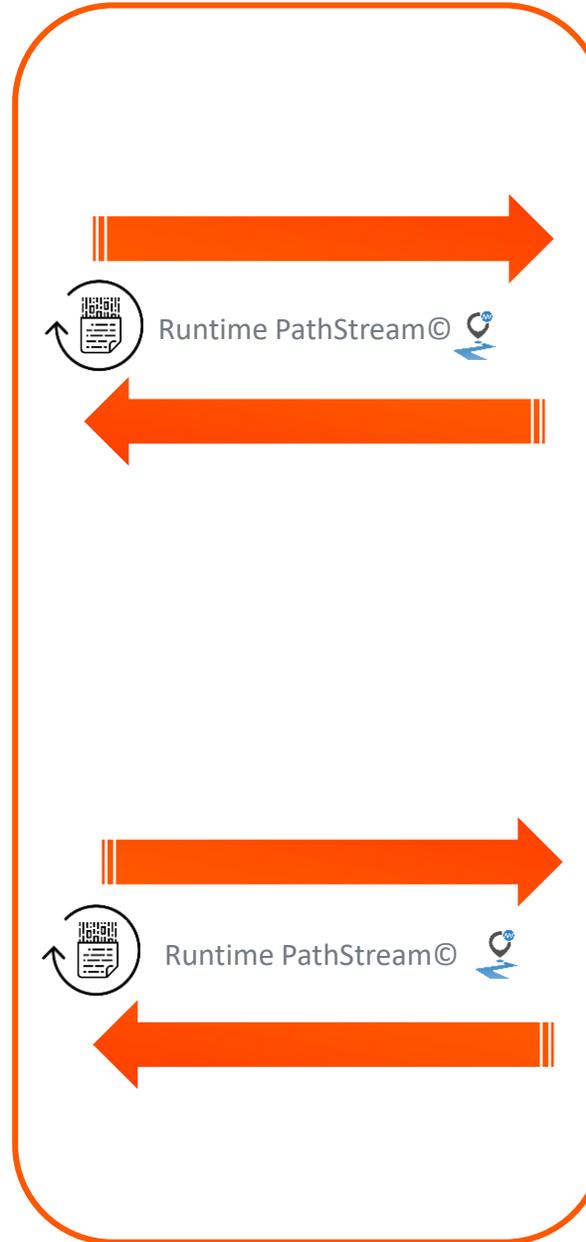
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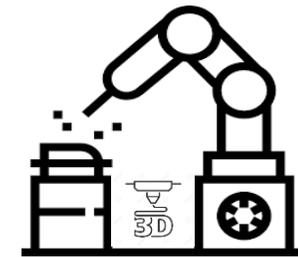
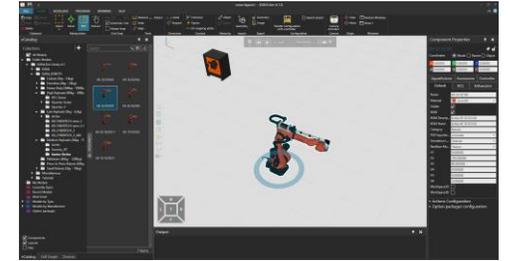
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Trajectoires et actions robot
réelles

Avantages de PathStream©

- KUKA KRL dans les fichiers générés
- Chargement de trajectoires manuel
- Transfert du fichier généré directement sur le disque dur du robot
- Fichier de points de taille illimitée, plus de saturation mémoire les commandes sont fluides
- Possibilité de mise à jour du fichier à la volée
- Bibliothèques d'interpolation du robot
- Performances du robot optimales
- Personnalisable



Synopsis



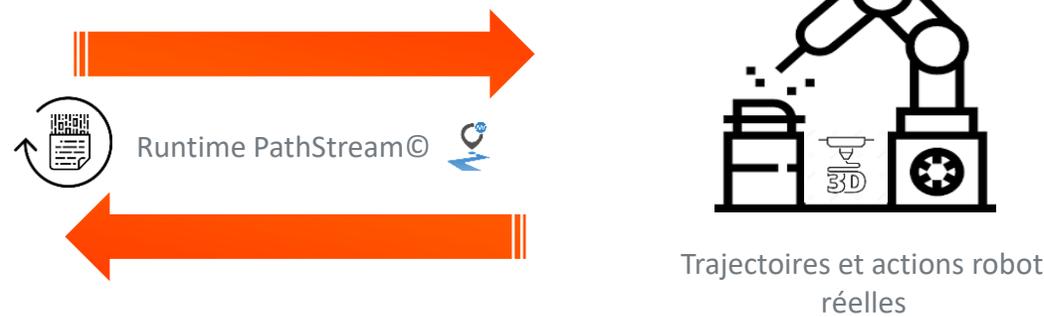
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KUKA.OfficeLite



Contrôleur KRC4 ou KRC5



FILE HOME MODELING PROGRAM DRAWING HELP CONNECTIVITY

Clipboard Manipulation CAPUTILITIES Show

Process Visualization Path Visualization Traces

Teach Overlay Menu Simulation configuration

Interfaces Signals I/O mapping editor Connect

Edit Detectors Enable Detectors Stop on Collision Collision Detection

To Reference To World Lock Positions

Color Highlight Stop at Limits Message Panel Output Limits

Restore Windows Show Windows

Kuka Stop Services Kuka Stop Services

Jog

Robot Anna

Coordinate W P O

X 0.0000 Y 0.0000 Z 0.0000

A 0.0000 B 0.0000 C 0.0000

Base Null

Tool Null

Approach +Z

Configur

Turn 0.000000

External False

Joints

BodyX + 0.000000

BodyY + 0.000000

BodyZ + 0.000000

BodyA + 0.000000

BodyB + 0.000000

BodyC + 0.000000

Snap Options

Edge Face

Edge & Face

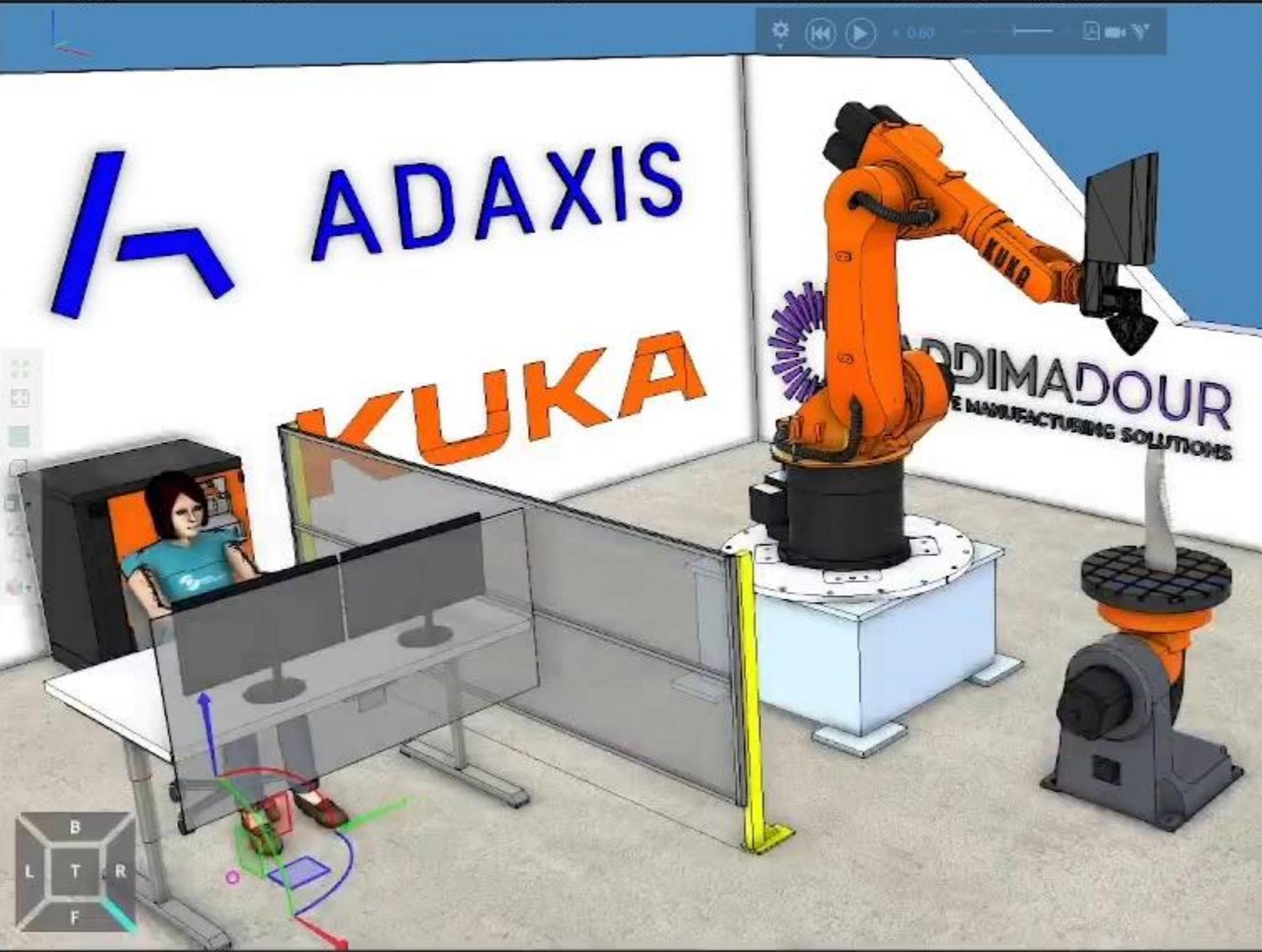
Frame Origin

Bound

Bisector

Set Position

Set Orientation



/R1/TestPathStream

18:31:08 26/09/2022 KSS01350

Coincidence de bloc attendue

Cause: /R1/Master

```

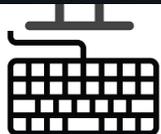
2 PTP $POS_ACT
3
4
5 repli()
6
7 X_pathstreaminebatch = 15
8 X_pathstreamfileendu = 2
9
10 ;read and run Csv file
11 X_PathStreamFilePath["trajectoire_csv/blade.adastream"
12
13 ;X_PathStreamFilePath["trajectoire_csv/cylindre_1.csv"
14
15 X_PathStreamReset=TRUE
16
17 wait sec 1
18
19 X_PathStreamStartReader=TRUE
20
21 PathStream(.)
22 X_PathStreamReset=TRUE

```

SZ 21 KRC01\PROGRAM\WORKING PATHS\TESTPALn 21, Col 0

Modifier Instructions Déplacement D'arrêt/Arrêt de Sélection de bloc Touch-Up Edition

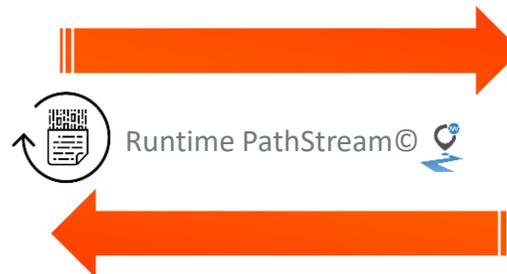
Synopsis



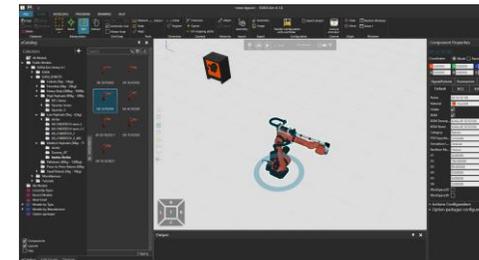
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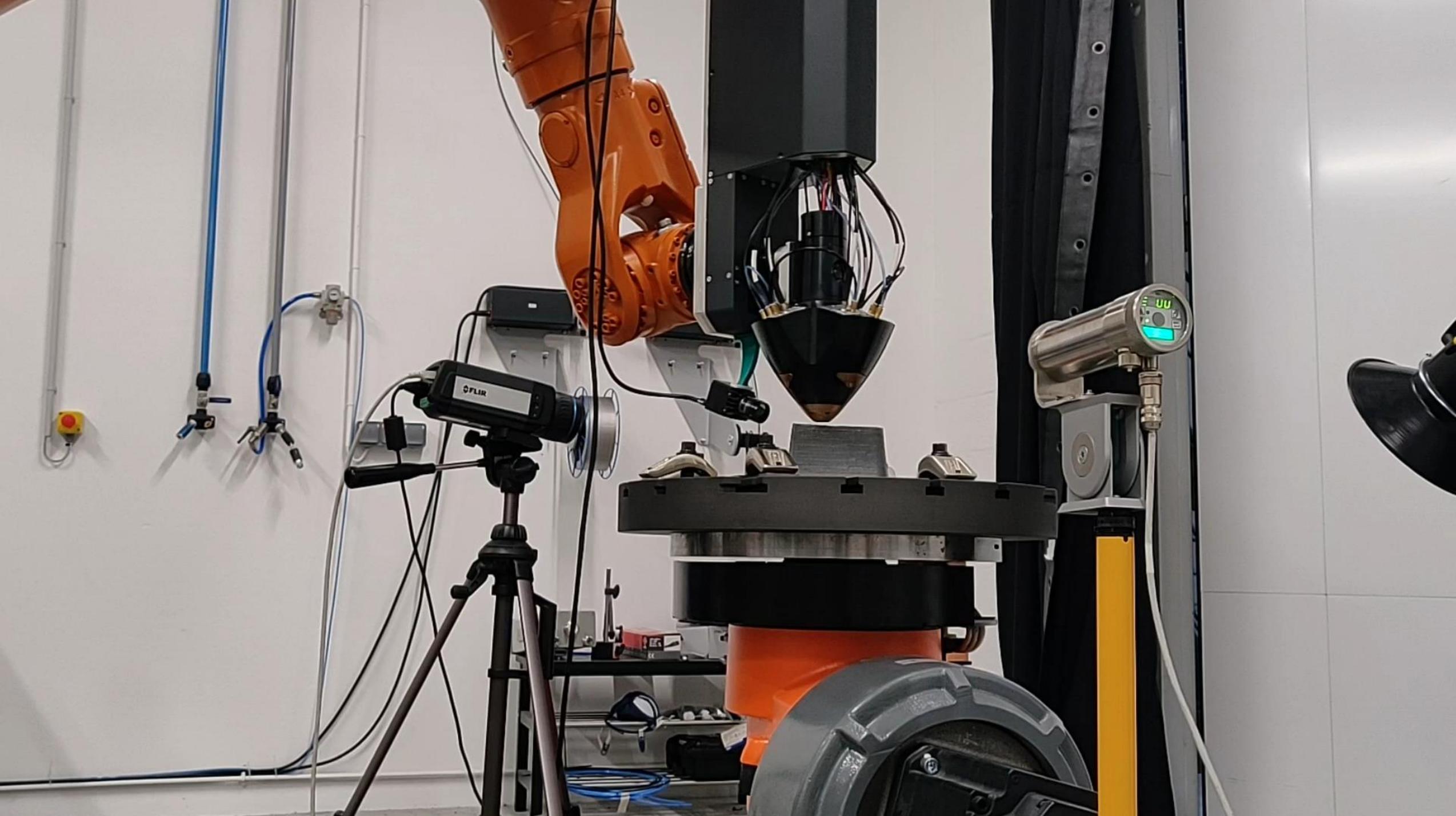


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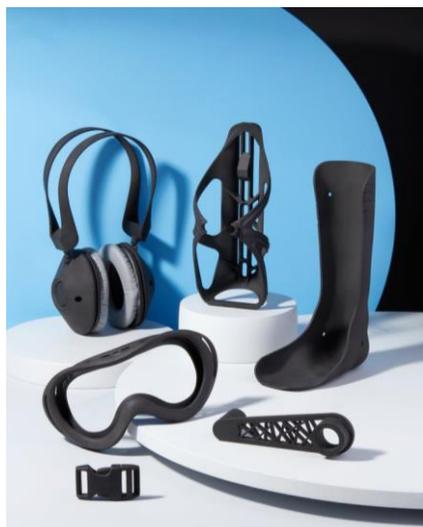


Statut de PathStream

- Développé en France
- Post-processeur *adaStream* déjà disponible avec la plateforme 3D *AdaOne*  ADAXIS
- Possibilité de simulation avec *KUKA.Sim* et *KUKA.OfficeLite*
- **Possibilité de mise à jour des solutions robotisées déjà en service (KRC4 - KSS8.5 et supérieur)**



L'impression 3D aujourd'hui



© FORMLABS



© SIEMENS ENERGY



L'impression 3D de demain



© MAGNUS WALANDER



Package PathStream & AdaOne



8 500€ la première année
7 500€ les années suivantes



Contacts :

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- **Adaxis** : info@adaxis.eu