[0] Warnings and messages

0.0 : Undefined error

Code : &H0000

Meaning/Cause	Undefined system error.
Action	Contact your distributor with details of the problem.

0.1 : Origin incomplete

* If the cause of the origin incomplete error can be pinpointed, an error code will be attached in parentheses at the end.

Code : &H0001

Meaning/Cause	a. One of the following operations was performed while return-to-origin was incomplete. • Execution of program or command was attempted. • Point teaching was attempted. • Movement on Cartesian coordinates was attempted. Absolute reset for absolute type axis has not been performed, or return-to-origin for increment type axis has not been performed. b. Absolute battery was removed from controller or robot position data becomes undefined due to battery voltage drop. c. ROB I/O cable was removed or disconnected. d. Absolute reset was interrupted. e. System generation was changed or parameters initialized. Or parameters for specifying the origin position such as for the return-to-origin direction or axis polarity were changed. (Equivalent to writing ALL or PRM file on controller.)
Action	Perform absolute reset or return-to-origin so that "origin complete" status is set.

0.2 : Running

Code : &H0002

Meaning/Cause	Program or command is running.
Action	—

0.3 : Program terminated by "HALT"

Code : &H0003

Meaning/Cause	Program execution was terminated by a HALT command.
Action	—

0.4 : Compiling

Code : &H0004

Meaning/Cause	Robot language compiling (making an object program) is in progress.
Action	—

0.5 : Busy

Code : &H0005

Meaning/Cause	Data is being saved on a memory card or internal ROM.
Action	—

0.6 : Program suspended by "HOLD"

Code : &H0006

Meaning/Cause	Program execution was interrupted by a HOLD command.
Action	Press the RUN key to cancel hold condition and start running the program from the next command.

0.7 : Turn on power again

Code : &H0007

Meaning/Cause	a. System generation was performed due to a robot change, etc. b. Parameter was changed by data transfer. c. System generation data was destroyed. d. Error occurred when servo was turned ON.
Action	Turn the controller on again.

0.8 : Try again

Code : &H0008

Meaning/Cause	Operation failed.
Action	Try again.

0.9 : Arrived at breakpoint

Code : &H0009

Meaning/Cause	Break point was reached during program execution.
Action	—

0.10 : INC.motor disconnected

Code : &H000A

Meaning/Cause	Return-to-origin command was attempted on an absolute axis or an axis that does not exist.
Action	1. Specify the correct axis. 2. Check the system generation data.

0.11 : ABS.motor disconnected

Code : &H000B

Meaning/Cause	Absolute reset was attempted on an incremental type axis or semi-absolute type axis, or an axis that does not exist.
Action	1. Specify the correct axis. 2. Check the system generation data.

0.14 : Stop excuted

Code : &H000E

Meaning/Cause	An external stop command was input during execution of a direct command, so operation was interrupted.
Action	—

0.15 : Can't execute while servo on

Code : &H000F

Meaning/Cause	Writing in "ALL" or "PRM" files was attempted during servo ON. "ALL" or "PRM" files cannot be written in servo ON.
Action	Turn off the servo before writing files.

0.16 : Changed SERVICE mode input

Code : &H0010

Meaning/Cause	Writing in "ALL" or "PRM" files was attempted during servo ON. "ALL" or "PRM" files cannot be written in servo ON.
Action	Turn off the servo before writing files.

0.17 : Can't edit while STD.DIO DC24V on

Code : &H0011

Meaning/Cause	Setting to disable the 24V DC monitoring function of STD.DIO was attempted even though 24V DC was being supplied at STD.DIO connector. (Monitor function cannot be disabled while 24V DC is being supplied to STD. DIO.)
Action	To disable the monitor function, change the parameter after first stopping the 24V DC supply.

0.18 : Gripper not included in Origin

Code : &H0012

Meaning/Cause	A gripper axis other than the command target axis was specified for the gripper axis when the other parameter, "Include Gripper in Origin", was set at "NO" and any of the following commands was executed. (1) "ORIGIN" command (2) "@ORGRTN" command (3) "@ORGRTN2" command
Action	1. Set "Include Gripper in Origin" to "YES". 2. For "@ORGRTN" and "@ORGRTN2" commands, execute an axis other than the gripper axis individually.

[1] Warnings (error history entry)

1.31 : CPU Reset start

Code : &H011F

Meaning/Cause	Power was turned on and CPU operation commenced.
Action	—

1.32 : CPU Normal start

Code : &H0120

Meaning/Cause	Start-up checks and initialization ended and controller operation started.
Action	—

1.33 : ABS.Backup start

Code : &H0121

Meaning/Cause	Power was cut off so backup of robot position data commenced.
Action	—

1.34 : ABS.Backup fin

Code : &H0122

Meaning/Cause	Finished making backup of robot position data during power cutoff.
Action	—

[2] Robot operating area errors

2.1 : Over soft limit

Code : &H0201

Meaning/Cause	Soft limit value preset in the parameter for operation position was exceeded.
Action	1. Change the operating position to within the soft limits. 2. Change the soft limit value.

2.2 : Std. coord. doesn't exist

Code : &H0202

Meaning/Cause	Setting of standard coordinates is incomplete.
Action	1. Set the standard coordinates. 2. Set the parameter arm length and offset pulse.

2.3 : Coordinate cal. failed

Code : &H0203

Meaning/Cause	a. Preset calculation for setting standard coordinates is not functioning. b. Operating position exceeded the operating area range.
Action	1. Set the standard coordinates correctly. 2. Change operating position to within operating area.

2.5 : Shift cal. failed

Code : &H0205

Meaning/Cause	Calculating for setting shift coordinates failed.
Action	Set shift coordinates correctly.

2.6 : Hand cal. failed

Code : &H0206

Meaning/Cause	Calculation for setting hand definition failed.
Action	Set hand definition correctly.

2.7 : Illegal Pallet parameter

Code : &H0207

Meaning/Cause	Calculation for setting pallet definition failed.
Action	Set pallet definition correctly.

2.8 : Movable range cal. failed

Code : &H0208

Meaning/Cause	a. Calculation of movement path failed. b. Current position is not within movement range.
Action	1. Change to a correct movement point. 2. Change current position to within movement range.

2.9 : Overlap soft limit

Code : &H0209

Meaning/Cause	On SCARA robots, the sum of the absolute values for the X-axis (or Y-axis) minus soft limit and the X-axis (or Y-axis) plus soft limit is making the arm move 1 rotation or more.
Action	1. Set the soft limit values correctly. 2. Set the soft limit values so that the movement range of the arm is less than 1 rotation.

2.10 : Exceeded movable range

Code : &H020A

Meaning/Cause	Area is outside the movable range of movement path.
Action	1. Set movement points correctly. 2. Specify movement path to be within the movable range.

2.11 : ? exceeded shift coord. range

Code : &H020B

Meaning/Cause	Shift coordinate range ? value was exceeded.
Action	1. Change the operating position of ? value to within the shift coordinates range. 2. Change shift coordinates range ? value.

2.17 : Arch condition bad

Code : &H0211

Meaning/Cause	Arch motion cannot be performed on the X and Y axes of SCARA and Cartesian robots if the arch position is specified in "mm" units. Arch motion cannot be performed on the X and Y axes of SCARA robots if the target position is specified in "mm" units.
Action	Change to correct arch motion command.

2.18 : RIGHTY now selected

Code : &H0212

Meaning/Cause	On SCARA type robots, the arm will now use the right-handed system for starting Cartesian movement.
Action	—

2.19 : LEFTY now selected

Code : &H0213

Meaning/Cause	On SCARA type robots, arm will now use the left-handed system for starting Cartesian movement.
Action	—

2.20 : Illegal hand type

Code : &H0214

Meaning/Cause	An R-axis hand definition was attempted on a robot not having an R-axis.
Action	1. Change to Y-axis hand definition. 2. Do not use a hand definition.

2.22 : Arm length is 0

Code : &H0216

Meaning/Cause	When arm length setting is 0 on SCARA type robots, movement on Cartesian coordinates was attempted.
Action	1. Set standard coordinates. 2. Set the arm length parameter.

2.23 : Cannot move(RIGHTY to LEFTY)

Code : &H0217

Meaning/Cause	Interpolation movement shifting from the right-handed system to the left-handed system was executed with a SCARA robot.
Action	Check the current hand system and point data hand system flag.

2.24 : Cannot move(LEFTY to RIGHTY)

Code : &H0218

Meaning/Cause	Interpolation movement shifting from the left-handed system to the right-handed system was executed with a SCARA robot.
Action	Check the current hand system and point data hand system flag.

2.25 : Cannot use TOOL coord.

Code : &H0219

Meaning/Cause	Failed to select tool coordinates could because no hand data has been entered.
Action	Set the hand data.

CAUTION

An R-axis unit must be installed to a SCARA or Cartesian robot. Set the hand data while a hand or gripper is attached to the tip of the R-axis.

2.26 : Collision in W.carrier

Code : &H021A

Meaning/Cause	Failed to move the double-carrier axis, because one carrier will interfere with the other carrier.
Action	If this error occurred during MANUAL mode: 1. Move the other carrier to a position where the two carriers will not interfere with each other and then move the robot manually. If this error occurred during AUTO mode: 1. Change the target position of one carrier so it will not interfere with the other carrier. 2. Move the other carrier to a position where it will not interfere with the first carrier's target position, and then move that first carrier. 3. Set the double-carrier parameter control mode to "Off" or "On". When set to "Off", this error does not occur, but the anti-collision function for double-carriers will not work so the carriers might collide with each other. When set to "On", one carrier starts moving after waiting until the other carrier moves to a position where no interference occurs.

2.27 : W.carrier deadlock

Code : &H021B

Meaning/Cause	Failed to move the double carrier axis and a deadlock occurred, because the target positions of both carriers will interfere with each other.
Action	Check the robot program.

2.29 : Cannot move without the limit

Code : &H021D

Meaning/Cause	1. The DRIVE statement used a "movement direction option" for an axis where the "limitless motion" parameter is set to INVALID. 2. DRIVE statement movement was attempted with a "limitless motion" VALID setting for the SCARA robot's X or Y axis. 3. DRIVE statement movement was attempted with a "limitless motion" VALID setting for a non-rotary type axis. 4. The attempted simultaneous movement of multiple axes by a MOVE or MOVEI statement, etc., included an axis with a "limitless motion" VALID setting. 5. A Point Trace was executed with a "limitless motion" VALID setting specified at one of the robot axes.
Action	1. Use the DRIVE statement to perform movement without the "movement direction option". Or, set the "limitless motion" parameter to VALID. 2. Set the "limitless motion" parameter to INVALID. 3. Set the "limitless motion" parameter to INVALID. 4. Set the "limitless motion" parameter to INVALID. Or, specify an "additional axis" setting in the system generation data for the axis where "limitless motion" is desired.*1 5. Set the "limitless motion" parameter to INVALID. Or, specify an "additional axis" setting in the system generation data for the axis where "limitless motion" is desired.*1

*1 An "additional axis" is excluded from the axes which are moved by a MOVE statement, etc. An "additional axis" can be moved by using the DRIVE statement.

2.30 : Can't move(Different rot.)

Code : &H021E

Meaning/Cause	Interpolation movement with the arm rotation information on the start point different from that on the target position is executed by the ceiling-mount SCARA robot YK500TW.
Action	Check the arm rotation information on the start point and that of the point data.

2.31 : Illegal soft limit

Code : &H021F

Meaning/Cause	In the ceiling-mount SCARA robot YK500TW, the total of the plus soft limit absolute value and minus soft limit absolute value of the X-axis or Y-axis exceeds the movement range of the arm.
Action	Set the soft limit values so that the total value is within the movement range of the arm.

[3] Program file operating errors

3.1 : Too mamy programs

Code : &H0301

Meaning/Cause	Making of a new program was attempted after number of programs exceeded 100.
Action	Make a new program after deleting an unnecessary program. (Make a backup if necessary.)

3.2 : Program already exists

Code : &H0302

Meaning/Cause	An attempt to make/copy/transmit (by using SEND command) a new program with a name already registered was attempted.
Action	Making a new program/copy/transmission (by using SEND command) using a new (unregistered) program name.

3.3 : Program doesn't exist

Code : &H0303

Meaning/Cause	A registered program of the specified name does not exist.
Action	Correctly enter a registered program name.

3.4 : Writing prohibited

Code : &H0304

Meaning/Cause	The specified program is write protected.
Action	Use a program that is not write protected.

3.5 : File type error

Code : &H0305

Meaning/Cause	Software error occurred.
Action	Contact your distributor with details of the problem.

3.6 : Too many breakpoints

Code : &H0306

Meaning/Cause	Setting of break point exceeding 4 points was attempted.
Action	After deleting unnecessary break points, set the new break point. (Up to 4 break points can be set in one program.)

3.7 : Breakpoint doesn't exist

Code : &H0307

Meaning/Cause	Break point was not found during search.
Action	Set a break point if needed.

3.9 : Cannot find strings

Code : &H0309

Meaning/Cause	Could not find specified character string during search.
Action	If needed change the character string and try searching again.

3.10 : Object program doesn't exist

Code : &H030A

Meaning/Cause	The object program name is not registered.
Action	Make an object program.

3.11 : Cannot use function

Code : &H030B

Meaning/Cause	Unable to execute or unneeded hierarchy was selected.
Action	—

3.12 : Cannot overwrite

Code : &H030C

Meaning/Cause	In AUTO mode or PROGRAM mode, overwrite of a program being selected cannot be made by communication with a program of the same name.
Action	1. Change the mode. 2. Change the program name.

3.13 : Changing data prohibited

Code : &H030D

Meaning/Cause	Data cannot be changed because access level is not at 0.
Action	Set the access level to 0.

3.14 : Cannot use mode

Code : &H030E

Meaning/Cause	Specified mode cannot be changed because access level is set to level 2 or level 3.
Action	Change the access level to 0 or 1.

3.15 : Illegal password

Code : &H030F

Meaning/Cause	There is a mistake in the password entry.
Action	Enter the correct password.

3.16 : Cannot reset ABS

Code : &H0310

Meaning/Cause	Failed to perform absolute reset or return-to-origin correctly.
Action	1. Perform absolute reset or return-to-origin again. 2. Replace the robot cable. 3. Replace the controller.

3.17 : Cannot erase current program

Code : &H0311

Meaning/Cause	Currently selected program cannot be deleted.
Action	1. Cancel deletion of program. 2. Change the specified program.

3.18 : Duplicated Breakpoint

Code : &H0312

Meaning/Cause	Setting of breakpoint was attempted on line already set with breakpoints.
Action	To set the breakpoint, specify a line where breakpoints have not yet been set.

[4] Data entry and edit errors

4.1 : Point number error

Code : &H0401

Meaning/Cause	A point number was entered exceeding P9999.
Action	Input a correct point number.

4.2 : Input format error

Code : &H0402

Meaning/Cause	Wrong format was used to enter the data.
Action	Use the correct data format.

4.3 : Undefined pallet

Code : &H0403

Meaning/Cause	Specified pallet is undefined.
Action	1. Change the specified pallet. 2. Define the pallet.

4.4 : Undefined robot number

Code : &H0404

Meaning/Cause	Specified robot number does not exist.
Action	Enter a correct robot number.

4.5 : Undefined axis number

Code : &H0405

Meaning/Cause	Specified axis number does not exist.
Action	Enter a correct axis number.

4.6 : Invalid input number

Code : &H0406

Meaning/Cause	Invalid data was entered. a. Invalid data was entered in the area check output port number. b. Same port number was set for "G1 status output (DO & SO)" and "G2 status output (DO & SO)" of electrical gripper.
Action	1. Enter a port number that can be used. 2. Enter different port numbers.

4.7 : Invalid input axis

Code : &H0407

Meaning/Cause	An axis specified as "no axis" was selected for one axis of double carrier.
Action	Select an axis that is not specified as "no axis".

[5] Robot language syntax (compiling) errors

5.1 : Syntax error

Code : &H0501

Meaning/Cause	Syntax error found in program.
Action	Change to the correct syntax.

5.2 : Data error

Code : &H0502

Meaning/Cause	Data entered in wrong format.
Action	Input the data in the correct format.

5.3 : Number error

Code : &H0503

Meaning/Cause	a. Mistake in the number entry. b. Expression value is wrong.
Action	1. Change to the correct number. 2. Change to the correct value.

5.4 : Bit number error

Code : &H0504

Meaning/Cause	Specified bit number is not within 0 to 7.
Action	Change to the correct bit number.

5.5 : Port number error

Code : &H0505

Meaning/Cause	a. Port number specified for DO, DI, MO, SI, SO ports is outside the range 0 to 7, 10 to 17, or 20 to 27. b. Specified port number for LO, TO is not 0. c. An output to port 0 or port 1 was set for ports DO, MO, SO.
Action	1. Change to the correct port number. 2. Change output for ports DO, MO, SO to a port other than port 0 or port 1.

5.6 : Digit number error

Code : &H0506

Meaning/Cause	a. Binary number has exceeded 8 digits (places). b. Octal number has exceeded 6 digits (places). c. Decimal number has exceeded the specified range. d. Hexadecimal number has exceeded 8 digits (places). e. Cartesian coordinate point data has more than 3 decimal places.
Action	1. Change to the correct number of digits (places). 2. Specify the Cartesian coordinate point data of up to 2 decimal places.

5.7 : Illegal axis name

Code : &H0507

Meaning/Cause	Robot axis name is wrong.
Action	Change to the correct axis name.

5.8 : Illegal order

Code : &H0508

Meaning/Cause	Wrong bit specified for input/output port.
Action	Change to ascending order starting from right.

5.10 : Too many characters

Code : &H050A

Meaning/Cause	a. Character string was defined in excess of 75 characters. b. Addition to the character string total exceeds 75 characters.
Action	1. Change to character string count of 75 characters or less. 2. Change additions to character string to a total of 75 characters or less.

5.12 : Stack overflow

Code : &H050C

Meaning/Cause	a. Parenthesis was used 6 times or continuously in an expression. b. Overflow in stack area for compiling/execution.
Action	1. Reduce parentheses in the expression to 5 times or less. 2. Reduce program size. 3. Reduce nesting of GOSUB statement, CALL statement and FOR to NEXT statement. 4. Reduce argument of CALL statement. (especially character variables)

5.13 : Illegal variable

Code : &H050D

Meaning/Cause	A variable other than a global variable was used in SEND/@READ/@WRITE commands.
Action	Change to a global variable.

5.14 : Type mismatch

Code : &H050E

Meaning/Cause	a. Expression does not match on both sides. b. Prohibited type constant/variable/expression was used.
Action	1. Change so that both sides of expression match. 2. Use a correct type of constant/variable/expression.

5.15 : FOR variable error

Code : &H050F

Meaning/Cause	Variable names for NEXT statement and corresponding FOR statement do not match.
Action	Change so that FOR statement variable names match with NEXT statement variable names.

5.16 : WEND without WHILE

Code : &H0510

Meaning/Cause	There is no WHILE statement corresponding to the WEND statement.
Action	1. Delete the WEND statement. 2. Add a WHILE statement corresponding to the WEND statement.

5.17 : WHILE without WEND

Code : &H0511

Meaning/Cause	There is no WEND statement corresponding to WHILE statement.
Action	1. Delete the WHILE statement. 2. Add a WEND statement corresponding to the WHILE statement.

5.18 : NEXT without FOR

Code : &H0512

Meaning/Cause	a. There is no FOR statement corresponding to NEXT statement. b. NEXT command was executed without executing FOR command.
Action	1. Delete the NEXT statement. 2. Add a FOR statement corresponding to the NEXT statement. 3. Confirm execution of FOR command.

5.19 : FOR without NEXT

Code : &H0513

Meaning/Cause	There is no NEXT statement corresponding to FOR statement.
Action	1. Delete the FOR statement. 2. Add a NEXT statement corresponding to the FOR statement.

5.20 : ENDIF without IF

Code : &H0514

Meaning/Cause	There is no IF statement corresponding to ENDIF statement.
Action	1. Delete the ENDIF statement. 2. Add an IF statement corresponding to the ENDIF statement.

5.21 : ELSE without IF

Code : &H0515

Meaning/Cause	There is no IF statement corresponding to ELSE statement.
Action	1. Delete the ELSE statement. 2. Add an IF statement corresponding to the ELSE statement.

5.22 : IF without ENDIF

Code : &H0516

Meaning/Cause	There is no ENDIF statement corresponding to IF statement.
Action	1. Delete the IF statement. 2. Add an ENDIF statement corresponding to the IF statement.

5.23 : ELSE without ENDIF

Code : &H0517

Meaning/Cause	There is no ENDIF statement corresponding to ELSE statement.
Action	1. Delete the ELSE statement. 2. Add an ENDIF statement corresponding to the ELSE statement.

5.24 : END SUB without SUB

Code : &H0518

Meaning/Cause	a. There is no SUB statement corresponding to END SUB statement. b. END SUB command was executed without SUB command.
Action	1. Delete the END SUB statement. 2. Add a SUB statement corresponding to the END SUB statement. 3. Confirm execution of SUB command.

5.25 : SUB without END SUB

Code : &H0519

Meaning/Cause	There is no END SUB statement corresponding to SUB statement.
Action	1. Delete the SUB statement. 2. Add an END SUB statement corresponding to the SUB statement.

5.26 : Duplicated variable

Code : &H051A

Meaning/Cause	Two or more array variables were defined for the same name.
Action	Delete a definition statement for the array variables with the same name.

5.27 : Duplicated identifier

Code : &H051B

Meaning/Cause	Two or more identifiers were defined for the same name.
Action	Define another identifier.

5.28 : Duplicated label

Code : &H051C

Meaning/Cause	Two or more of the same labels were defined.
Action	Define another label.

5.29 : Undefined array

Code : &H051D

Meaning/Cause	Assignment/reference was made for undefined array.
Action	Define the undefined array.

5.30 : Undefined identifier

Code : &H051E

Meaning/Cause	An undefined identifier was used.
Action	Define an identifier for undefined identifier.

5.31 : Undefined label

Code : &H051F

Meaning/Cause	Reference made to undefined label.
Action	Set definition for undefined label.

5.32 : Undefined user function

Code : &H0520

Meaning/Cause	Undefined function was called.
Action	Set definition for undefined function.

5.34 : Too many dimensions

Code : &H0522

Meaning/Cause	An array exceeding 3 dimensions was defined.
Action	Change array to within 3 dimensions.

5.35 : Dimension mismatch

Code : &H0523

Meaning/Cause	The number of array dimensions does not match that defined by the DIM statement.
Action	1. Make the number of array dimensions match that defined by the DIM statement. 2. Make the number of array dimensions match the DIM statement.

5.36 : Argument mismatch

Code : &H0524

Meaning/Cause	The number of SUB statement arguments does not correspond to the CALL statement.
Action	Make the number of SUB statements correspond to the CALL statement.

5.37 : Specification mismatch

Code : &H0525

Meaning/Cause	Cannot execute command under present robot specifications.
Action	Change command for execution.

5.38 : Illegal option

Code : &H0526

Meaning/Cause	Error is present in command option.
Action	Define another identifier.

5.39 : Illegal identifier

Code : &H0527

Meaning/Cause	Reserved word was used as an identifier.
Action	Change to an identifier not used as a reserved word. Refer to the programming manual.

5.40 : Illegal command in procedure

Code : &H0528

Meaning/Cause	Cannot execute command within procedure (from SUB to END SUB statements).
Action	Delete command that cannot be executed within procedure.

5.41 : Illegal command outside proce.

Code : &H0529

Meaning/Cause	Command cannot be executed outside of procedure (between SUB to END SUB statements).
Action	Delete command that cannot be executed outside of procedure.

5.42 : Illegal command inside IF

Code : &H052A

Meaning/Cause	Cannot execute command between IF to ENDIF statements. (Command can be executed for one IF statement line.)
Action	Delete command that cannot be executed between IF to ENDIF statements.

5.43 : Illegal direct

Code : &H052B

Meaning/Cause	Independent execution of command is impossible.
Action	1. Change execution according to program. 2. Change it to a command that can be executed independently.

5.44 : Cannot use external label

Code : &H052C

Meaning/Cause	Command cannot use an external label.
Action	1. Change to an internal label. 2. Change execution command.

5.45 : Illegal program name

Code : &H052D

Meaning/Cause	a. When transmitting a program file by SEND command, the NAME statement was not defined on beginning line of the program data. b. Characters other than alphanumeric and underscore (_) were used in the program name. c. Program name has exceeded 8 characters.
Action	1. Define NAME statement on beginning line of program data. 2. Use only alphanumeric and underscore (_) characters in the program name. 3. Use 8 characters or less in the program name.

5.46 : Too many identifiers

Code : &H052E

Meaning/Cause	Number of identifiers exceeded 500.
Action	Ensure the number of identifiers is within 500 items.

5.47 : CASE without SELECT

Code : &H052F

Meaning/Cause	There is no SELECT statement corresponding to CASE statement.
Action	1. Delete the CASE statement. 2. Add a SELECT statement corresponding to the CASE statement.

5.48 : END SELECT without SELECT

Code : &H0530

Meaning/Cause	There is no SELECT statement corresponding to END SELECT statement.
Action	1. Delete the END SELECT statement. 2. Add a SELECT statement corresponding to the END SELECT statement.

5.49 : SELECT without END SELECT

Code : &H0531

Meaning/Cause	There is no END SELECT statement corresponding to SELECT statement.
Action	1. Delete the SELECT statement. 2. Add an END SELECT statement corresponding to the SELECT statement.

5.50 : CASE without END SELECT

Code : &H0532

Meaning/Cause	There is no END SELECT statement corresponding to CASE statement.
Action	1. Delete the CASE statement. 2. Add an END SELECT statement corresponding to the CASE statement.

5.51 : Illegal command line

Code : &H0533

Meaning/Cause	Cannot execute command statement between SELECT and CASE statements.
Action	Delete the command statement between SELECT and CASE statements.

5.52 : Command doesn't exist

Code : &H0534

Meaning/Cause	Line does not have a command statement.
Action	1. Add a command statement. 2. Delete the line that does not have a command statement.

5.53 : Compile failure

Code : &H0535

Meaning/Cause	Error occurred in software.
Action	Contact your distributor with details of the problem.

5.54 : ELSEIF without IF

Code : &H0536

Meaning/Cause	There is no IF statement corresponding to ELSEIF statement.
Action	1. Delete the ELSEIF statement. 2. Add an IF statement corresponding to the ELSEIF statement.

5.55 : ELSEIF without ENDIF

Code : &H0537

Meaning/Cause	There is no ENDIF statement corresponding to ELSEIF statement.
Action	1. Delete the ELSEIF statement. 2. Add an ENDIF statement corresponding to the ELSEIF statement.

[6] Robot language execution errors

6.1 : Illegal command

Code : &H0601

Meaning/Cause	Execution of a non-supported or non-executable command was attempted.
Action	Change to a command that can be executed.

6.2 : Illegal function call

Code : &H0602

Meaning/Cause	The expression "ON <expression> GOTO"/"ON <expression> GOSUB" command was a negative value.
Action	Change <expression> to a positive value.

6.3 : Division by 0

Code : &H0603

Meaning/Cause	A command to divide by 0 (÷ 0) was attempted.
Action	Change from the divide by 0 command.

6.4 : Point doesn't exist

Code : &H0604

Meaning/Cause	Assignment/movement/reference to an undefined point was attempted.
Action	Define the point.

6.5 : Coordinate type error

Code : &H0605

Meaning/Cause	a. Arithmetic operations of joint coordinate point data and Cartesian coordinate point data were attempted. b. Joint coordinate system and Cartesian coordinate system were mixed together within the MOVE C, command point data. c. Point data in PMOVE command was not specified in Cartesian coordinates.
Action	1. Change to same coordinate system. 2. Change to Cartesian coordinate system.

6.6 : Subscript out of range

Code : &H0606

Meaning/Cause	A subscript of an array variable has exceeded the range defined in DIM statement.
Action	Change the subscript of array variable to within the defined range.

6.7 : RETURN without GOSUB

Code : &H0607

Meaning/Cause	RETURN command was executed without executing the GOSUB command.
Action	Confirm execution of GOSUB command.

6.8 : END SUB without CALL

Code : &H0608

Meaning/Cause	END SUB command was executed without executing CALL command.
Action	Confirm execution of SUB command.

6.9 : EXIT SUB without CALL

Code : &H0609

Meaning/Cause	EXIT SUB command was executed without executing CALL command.
Action	Confirm execution of SUB command.

6.10 : SUSPEND without START

Code : &H060A

Meaning/Cause	SUSPEND command was executed for a task not executed by START command.
Action	Confirm execution of START command.

6.11 : CUT without START

Code : &H060B

Meaning/Cause	CUT command was executed for a task not executed by START command.
Action	Confirm execution of START command.

6.12 : RESTART without START

Code : &H060C

Meaning/Cause	RESTART command was executed for a task not executed by START command.
Action	Confirm execution of START command.

6.13 : RESTART without SUSPEND

Code : &H060D

Meaning/Cause	RESTART command was executed for a task not executed by SUSPEND command.
Action	Confirm execution of SUSPEND command.

6.14 : Task number error

Code : &H060E

Meaning/Cause	a. Task number is outside the range 2 to 8. b. START, CUT, SUSPEND or RESTART command was executed for task 1 (main task). c. START, CUT, SUSPEND or RESTART command was executed for its own task.
Action	1. Change to a correct task number. 2. Delete task command for task 1. 3. Delete command for its own task.

6.15 : Task running

Code : &H060F

Meaning/Cause	START command was executed for a task currently in operation.
Action	Delete START command.

6.16 : Task suspending

Code : &H0610

Meaning/Cause	START or SUSPEND command was executed for a task in pause (suspend) condition.
Action	Delete START or SUSPEND command.

6.17 : Illegal command in error routine

Code : &H0611

Meaning/Cause	Command which could not be executed was attempted within an error processing routine.
Action	Delete the command which could not be executed.

6.18 : EXIT FOR without FOR

Code : &H0612

Meaning/Cause	EXIT FOR command was executed without executing FOR command.
Action	Confirm execution of FOR command.

6.19 : SUB without CALL

Code : &H0613

Meaning/Cause	SUB command was executed without executing CALL command.
Action	Confirm execution of CALL command.

6.20 : Not execute CALL

Code : &H0614

Meaning/Cause	CALL command was not executed.
Action	Confirm execution of CALL command.

6.21 : Same point exists

Code : &H0615

Meaning/Cause	a. Same points exist for 1 of 3 points of an MOVE C command. b. Same points are consecutively on the path of PATH motion.
Action	1. Change the MOVE C command to 3 different points. 2. Make changes so that the same points are not consecutively on the path of PATH motion.

6.22 : 3 points on line

Code : &H0616

Meaning/Cause	3 points of an MOVE C command were placed on a straight line.
Action	Change the 3 different points of the MOVE C command so they are not on the same straight line.

6.23 : Circular arc radius too small

Code : &H0617

Meaning/Cause	MOVE C command radius is less than 1mm.
Action	Change MOVE C command to 1mm or more for circular arc radius.

6.24 : Circular arc radius too large

Code : &H0618

Meaning/Cause	MOVE C command radius exceeded 5000mm (5 meters).
Action	Change MOVE C command to within 5000mm (5 meters) for circular arc radius.

6.25 : Too low speed

Code : &H0619

Meaning/Cause	Specified speed was too low so movement time exceeded 300 seconds. Maximum movement time is 300 seconds.
Action	Increase the specified speed.

6.26 : No sufficient memory for OUT

Code : &H061A

Meaning/Cause	Failed to run an OUT command due to insufficient memory caused by multiple OUT commands that were run in succession.
Action	Check the number of OUT commands. The maximum number of OUT commands that can be run in parallel is 16.

6.27 : PATH without SET

Code : &H061B

Meaning/Cause	Any of PATH L, PATH C and PATH END was executed without executing PATH SET.
Action	First execute PATH SET when setting a path.

6.28 : PATH without END

Code : &H061C

Meaning/Cause	PATH START was executed without executing PATH END.
Action	Execute PATH END to end the path setting and then execute PATH START.

6.29 : No PATH data

Code : &H061D

Meaning/Cause	No path is set for PATH motion.
Action	Set a path with PATH L and PATH C. The previously set path will be lost in the following cases: • When PATH SET is executed. • When program is changed. • When program is reset. • When controller power is turned off.

6.30 : Too many PATH data

Code : &H061E

Meaning/Cause	The number of PATH motion paths has exceeded 300.
Action	Reduce the number of PATH motion paths to 300 or less in total of straight lines and circular arcs.

6.31 : Not PATH start position

Code : &H061F

Meaning/Cause	Robot's current position is not the start position of PATH motion.
Action	Move the robot to the start position specified with PATH SET and then execute PATH START.

6.32 : PATH execute error

Code : &H0620

Meaning/Cause	Cannot execute PATH motion. a. Acceleration zone distance is too short. b. Speed is too high in the position where the direction changes.
Action	1. Reduce the speed setting. 2. Lengthen the straight line or circular arc distance containing acceleration/deceleration. 3. Make setting so that the direction at the connection point of straight lines does not change greatly.

6.33 : ABS of MARK incomplete

Code : &H0621

Meaning/Cause	Absolute reset was attempted with an ABSRST statement or dedicated input while absolute reset on an axis whose return-to-origin method is set to "Mark" is incomplete.
Action	First perform absolute reset on the axes whose return-to-origin method is set to "Mark".

6.34 : MARK method is not allowed

Code : &H0622

Meaning/Cause	Return-to-origin was attempted with an ORIGIN statement or dedicated input while the return-to-origin method for an incremental type axis or semi-absolute type axis is set to "Mark".
Action	Return-to-origin on the incremental type axis or semi-absolute type axis cannot be performed by the mark method. Change the return-to-origin method.

6.35 : Expression value error

Code : &H0623

Meaning/Cause	The expression value is other than -1 and 0 even though conditional expression is a numeric expression.
Action	1. Set the expression value correctly. 2. Change the "TRUE condition" parameter setting.

[9] Memory errors

9.1 : Program destroyed

Code : &H0901

Meaning/Cause	a. Part or all of the program data has been destroyed. b. This error message is sometimes issued due to a major error or the power being turned off during rewrite of program data.
Action	1. Delete that program during selection. 2. Initialize the program data.

9.2 : Point data destroyed

Code : &H0902

Meaning/Cause	a. Part or all of the point data has been destroyed. b. This error message is sometimes issued due to a major error or the power being turned off during rewrite of point data.
Action	Initialize the point data.

9.3 : Memory destroyed

Code : &H0903

Meaning/Cause	Error or malfunction occurred in the memory.
Action	Initialize memory.

9.4 : Parameter destroyed

Code : &H0904

Meaning/Cause	Part or all of the parameter data has been destroyed.
Action	Initialize the parameter data.

9.5 : Illegal object code

Code : &H0905

Meaning/Cause	An object program has been destroyed.
Action	Compile and make an object program.

9.6 : Shift data destroyed

Code : &H0906

Meaning/Cause	Part or all of the shift data has been destroyed.
Action	Initialize the shift data.

9.7 : Hand data destroyed

Code : &H0907

Meaning/Cause	Part or all of the hand data has been destroyed.
Action	Initialize the hand data.

9.8 : POS.OUT data destroyed

Code : &H0908

Meaning/Cause	Part or all of the POS.OUT data was destroyed.
Action	Initialize the POS.OUT data.

9.9 : Pallet data destroyed

Code : &H0909

Meaning/Cause	Part or all of the pallet definition data was destroyed.
Action	Initialize the pallet definition data.

9.31 : Memory full

Code : &H091F

Meaning/Cause	No available space in the program/point data area.
Action	Delete unnecessary programs/points.

9.32 : Object memory full

Code : &H0920

Meaning/Cause	Object program size exceeded the upper limit.
Action	Compress the source program size, so that the object program size is smaller.

9.33 : Sys. generation destroyed

Code : &H0921

Meaning/Cause	Part or all of the system generation data has been destroyed.
Action	Remake the system generation data correctly.

9.34 : Sys. generation mismatch

Code : &H0922

Meaning/Cause	Mistake made in specifying the robot type/axis number of system generation data.
Action	Redo the system generation correctly.

9.35 : Program too big

Code : &H0923

Meaning/Cause	Source program size exceeded the permissible size.
Action	Compress the source program size.

9.36 : Task data destroyed

Code : &H0924

Meaning/Cause	Part or all of the data used in a task has been destroyed.
Action	Reset the program.

9.37 : Object program destroyed

Code : &H0925

Meaning/Cause	Part or all of an object program has been destroyed.
Action	Make the object program again.

9.38 : Sequence object memory full

Code : &H0926

Meaning/Cause	Sequence object program exceeded its memory capacity.
Action	Compress the source size of sequence program, so that the object program size is reduced.

9.39 : Sequence object destroyed

Code : &H0927

Meaning/Cause	Part or all of the sequence object program has been destroyed.
Action	Make the sequence object program again.

9.40 : Cannot found sequence object

Code : &H0928

Meaning/Cause	No sequence object program.
Action	Make the sequence object program.

9.41 : Local variable memory full

Code : &H0929

Meaning/Cause	Number of local variables defined within subroutine has exceeded upper limit.
Action	1. Reduce number of local variables defined in the subroutine. 2. Use the global variable.

9.50 : Indiv. origin data destroyed

Code : &H0932

Meaning/Cause	Part or all of the definition data of the individual axis origin return function by DI/SI has been destroyed. The individual axis origin return definition data by DI/SI is initialized.
Action	—

9.51 : Gripper origin data destroyed

Code : &H0933

Meaning/Cause	Part or all of the data saved after completion of the return-to-origin of the electric gripper was destroyed.
Action	Perform the return-to-origin of the electric gripper.

[10] System setting or hardware errors

10.1 : Robot disconnected

Code : &H0A01

Meaning/Cause	Axis control was attempted with "no axis" specified for all axes of system generation.
Action	Re-perform the system generation.

10.3 : D.unit disconnected

Code : &H0A03

Meaning/Cause	Manual movement was attempted on the axis that is not specified.
Action	Do not perform any axis-related operation.

10.6 : DRIVER.unit version mismatch

Code : &H0A06

Meaning/Cause	Driver unit version does not match the CPU unit.
Action	Make sure the CPU unit and driver unit versions match each other.