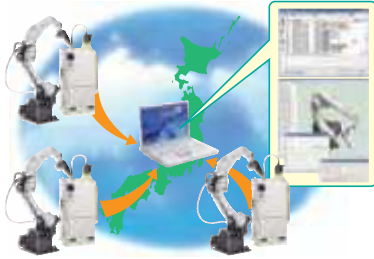


### External Communication (Ethernet)

#### Production and Quality Control on LAN

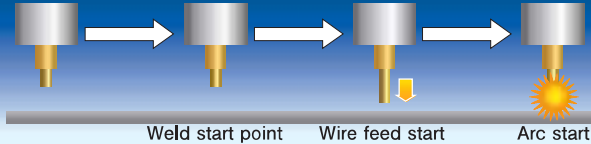
The LAN connection allows you to share welding data with other robots and improve production and quality control.



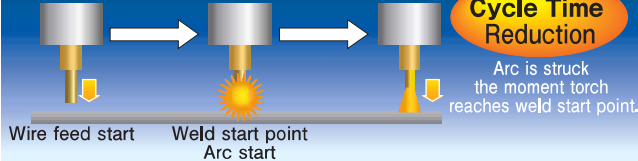
### Flying Start

Executes arc-on/off programs a little before the torch reaches the weld start/end point to reduce cycle times.

#### Standard Arc Start

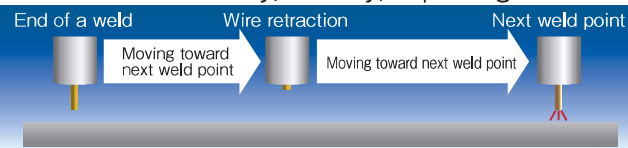


#### Flying Start



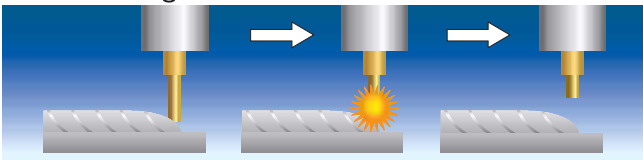
### Wire Auto Retract

As the robot moves to weld start points, the wire is retracted automatically; thereby, improving arc start.



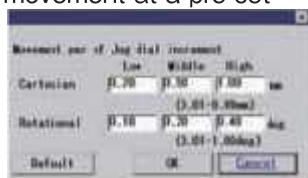
### Wire Stick Auto Release (for CO<sub>2</sub>/MAG)

Automatically detects a wire stuck at the end of a weld and re-ignites the arc to release the wire.



### Pitch Movement ("Jog settings")

This function enables robot movement at a pre-set distance by every click of the jog dial. This is useful when working in narrow, constricted spaces or in fine-tuning robot position.

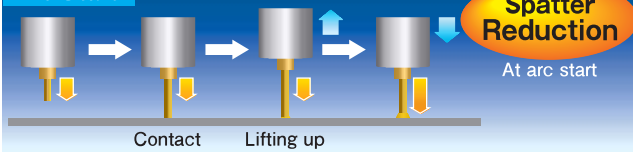


### Lift Start / Lift End

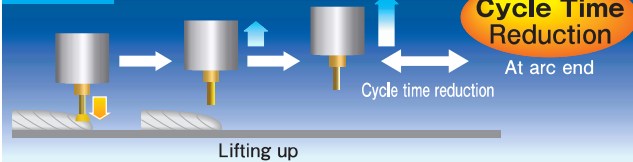
#### Quality Weld Starts and Ends. Spatter and Cycle Time Reduction.

The robot lifts up the welding torch quickly at the start and end of the weld. By coordinating the robot motion with the welding waveform and wire feed control, quality and cycle time are improved. (Much quicker than wire retraction.)

#### Lift Start

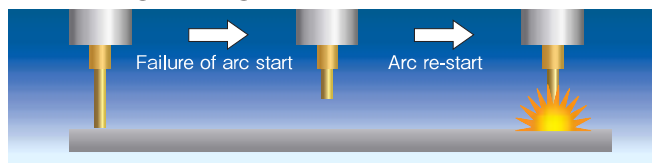


#### Lift End



### Arc Start Retry (for CO<sub>2</sub>/MAG)

Detecting a failure of arc start, the robot automatically starts arc ignition again.



### Torch Angle Display (Teach Pendant)

Torch angle is displayed on the screen, making it possible to reduce teaching time and obtain consistent bead appearance.



### Program Test

In Teach mode, operator can safely verify taught program including welding without switching to Auto mode.

