CEBORA

Robot Analyzer

art.125.01

Instruction Manual

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Introduction

The CEBORA Robot Analyzer (art.**125.01**) is a diagnostic tool designed for CEBORA automated welding or cutting systems. The IXXAT USB-to-CAN V2 interface is used to capture the CAN messages exchanged between the power source and the robot controller. The CEBORA software application is designed to decode, log and display process data in a human readable format.

Related documents

Before using this device, read the *General Warnings Manual* (cod.**3301151**) and the specific *Machine Instruction Manual* available from the Support-Documentation section of the CEBORA website (https://welding.cebora.it).

Hardware requirements

A personal computer running Microsoft Windows 11, 10, 8 or 7 with a USB port.

Software Installation

Do not connect the IXXAT USB-to-CAN device to the USB port before completing the installation.

System administrator rights are required to perform the installation.

Installing the IXXAT VCI4 driver

From the HMS IXXAT manufacturer page:

https://www.ixxat.com/technical-support/resources/downloads-and-documentation?ordercode=1.01.0281.12001

Download the **VCI V4** driver if you are using Windows 11 or 10.

or the **VCI V4 LEGACY** driver if you are using Windows 8 or 7.

Run the installer and from the component selection page, select the following items:

- SDKs
  - ✔ SDK VCI4 (.NET)
- Kernel-mode driver
  - ✔ USB-to-CAN V2
  - ✔ USB-to-CAN compact
  - ✔ USB-to-CAN II
  - ✔ USB-to-CAN FD

Optionally (minimal application supplied with the driver)

- Tools
  - ✔ canAnalyser3 Mini

All other components must be deselected.

During the installation procedure you may be asked several times to trust the HMS vendor.

Restart the PC and then connect the device to the USB port waiting for the recognition of the new hardware.

Installing the application

Download the Robot Analyzer application from the CEBORA website:

https://welding.cebora.it/en/products/accessories/mig-mag-accessories/robot-analyzer-per-usb?set_language=en

Start the installation by double-clicking the downloaded file.

If not already present in the system, the installation of the .NET Framework from the Microsoft site may be required.

Connections

Two types of connetions are included in this kit.

For welding systems (MIG or TIG) connect the cable to the rear CAN connector of the power source and to the robot controller directly or to the robot interface depending on the specific installation.

For plasma cutting systems connect the cable between the power source and the gas console.

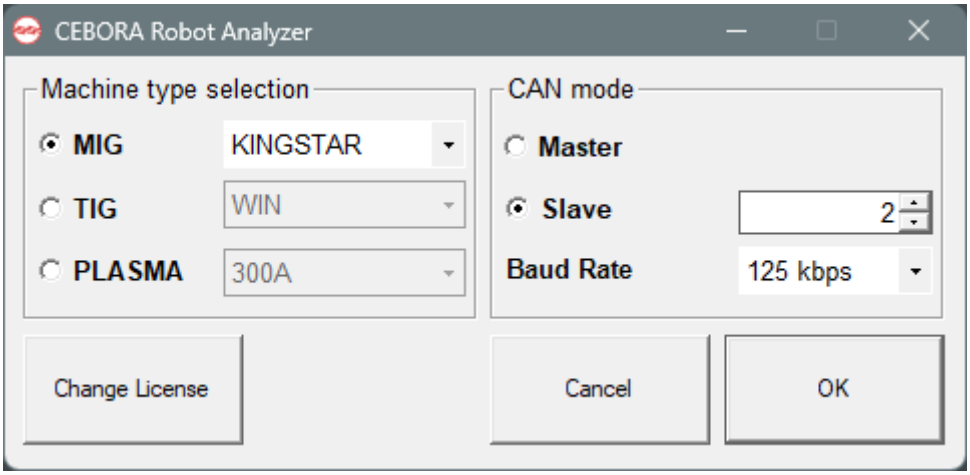
Running the application

Double-click on the Robot Analyzer icon to start the application.

On first launch you will be asked to enter the 16-digit code to activate the license.

Power source selection

Select the power source model from the startup window:



Three types of power source are supported:

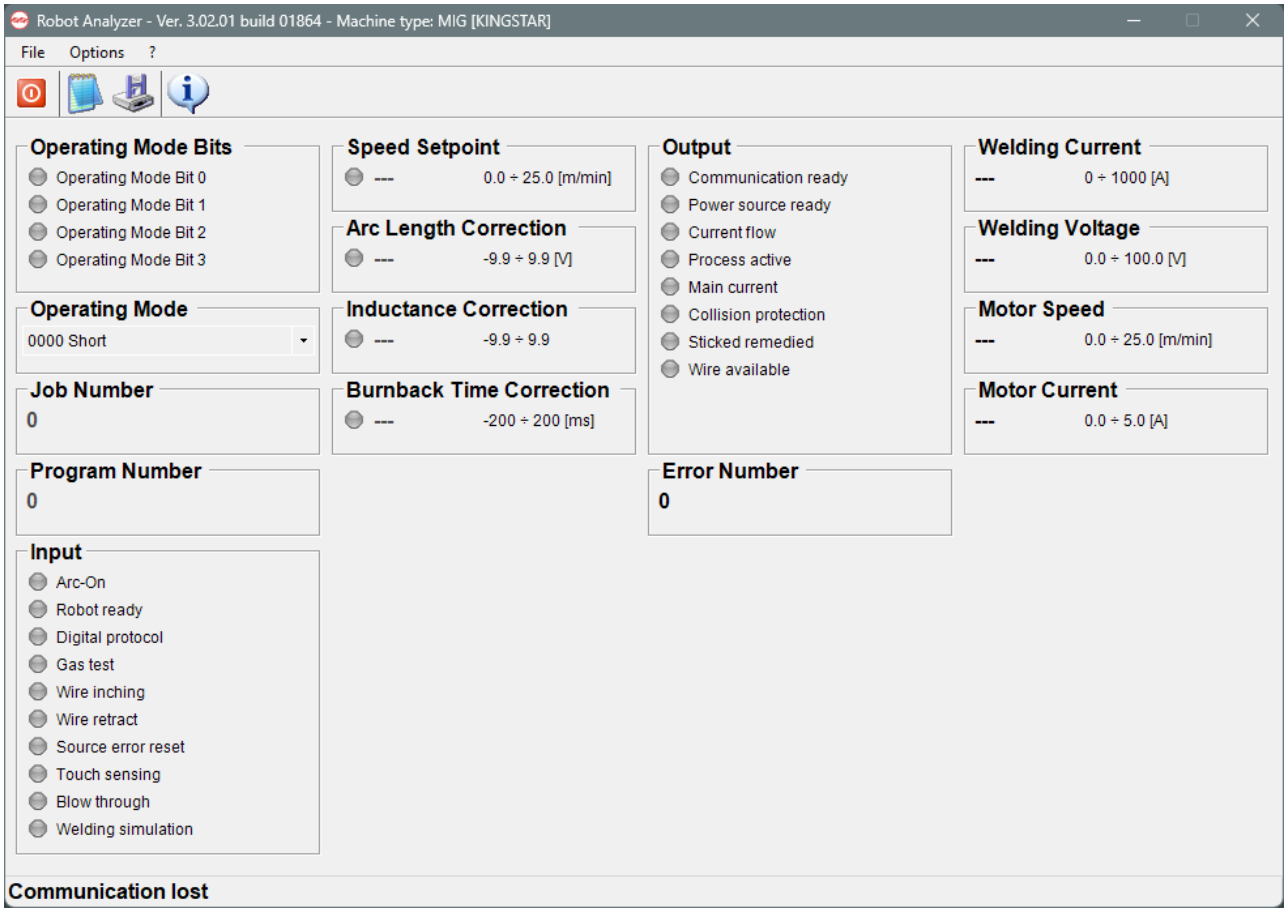
- **MIG** KINGSTAR and SPEEDSTAR families
- **TIG** WIN and EVO families
- **PLASMA** HQC family

From the right panel select the CAN configuration.

Main window

Checks the status of the signals exchanged between the generator and the robot controller from the main window.

- **Active** signals are indicated in **green** (received bit with value 1)
- **Not active** signals are indicated in **red** (received bit with value 0)
- **Unavailable** signals are indicated in **gray** (data not received or not valid).



Logging

From the log window it is possible to record all CAN messages.

Filters are available to show some types of messages only.

Logged data can also be saved as a file for further analysis.