

iRC Operator HMI – User Manual

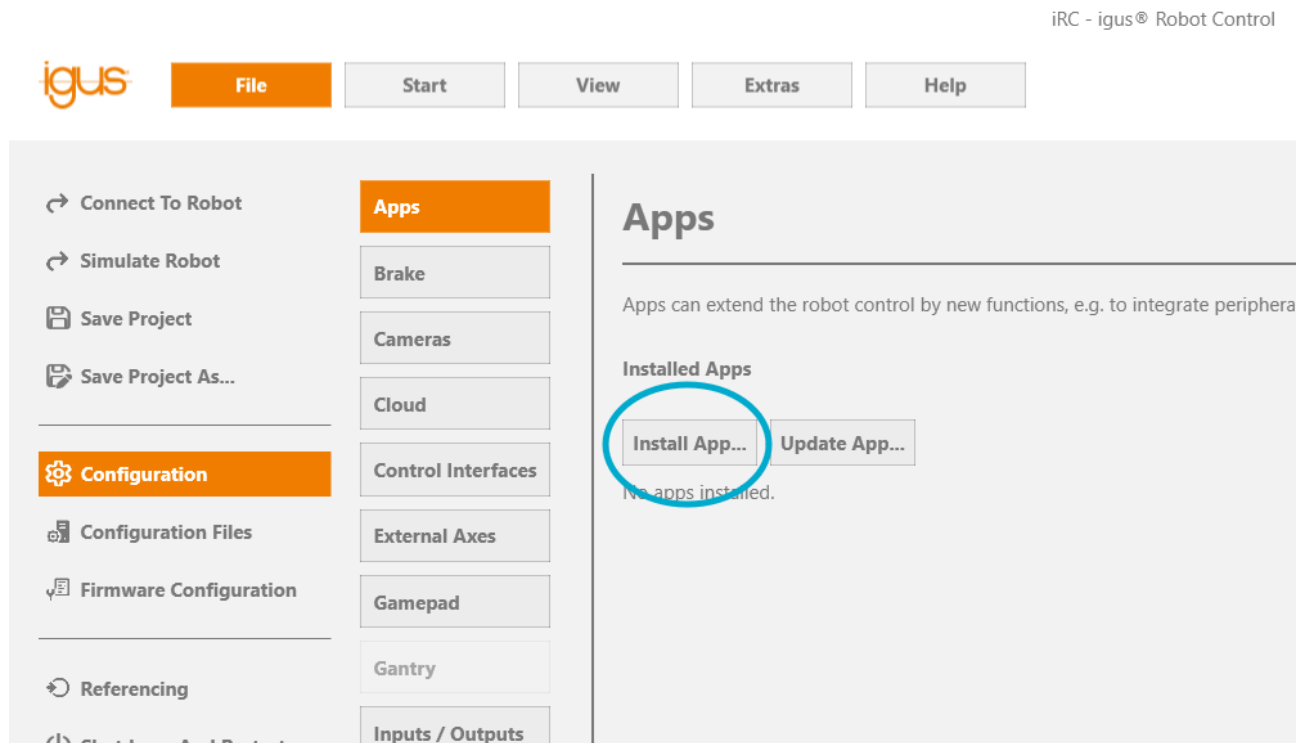
V 1.0 7.1.2026

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1. Installation

Connect the iRC PC Software with your robot and go to “File-> Configuration-> Apps”.

Click on “Install App...” and choose the .zip-file of the iRC Operator HMI.



2. Licensing

This App needs a license for continuous operation. Without a valid license, you will have a 30 minute timeframe for testing (resets after each start-up). Afterwards the App will not be usable anymore for this session.

To create a license, we need the device ID of your robot control. Connect to the robot via the iRC and go to “File-> License”. Copy the string you find at “Device ID” and give it to us.

You will then get a license file that you can install via the “Install license” button.



File

Start

View

Extras

Vision App Pro

Help

➔ Connect To Robot

➔ Simulate Robot

💾 Save Project

💾 Save Project As...

⚙️ Configuration

📁 Configuration Files

🔧 Firmware Configuration

🔄 Referencing

🔌 Shutdown And Restart

📄 License

🔍 About

Licenses

Additional features can be unlocked by installing a device-specific license file. Most of these features can be tested during the e

License of Robot Control

Validity: Valid

Licensed to: CPR

Date: 2026-06-23T11:39:38

Features: OperatorHMI

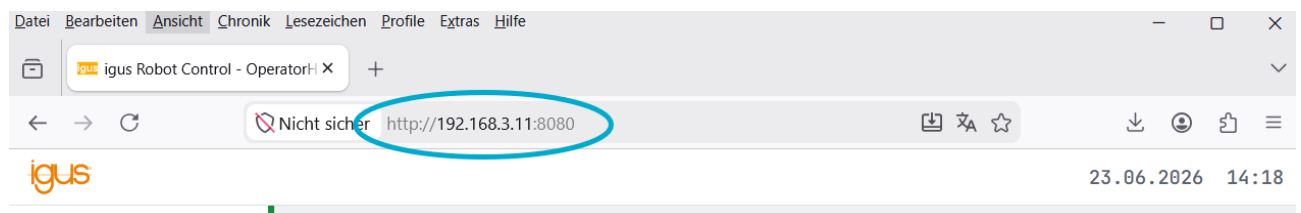
Evaluation period: Evaluation period for extended features exceeds in 0:26:23

Device ID: TC:deec2b84917bad3f947f650252a97b14d7ece0fe9c4755871a3ffefaf78e

Install License

3. Connection

Make sure your HMI-Device is in the same Network as the robot (per default "192.168.3.XXX") and open the web browser of your choice. Enter the robot's IP address followed by ":8080" (Default: "192.168.3.11:8080").

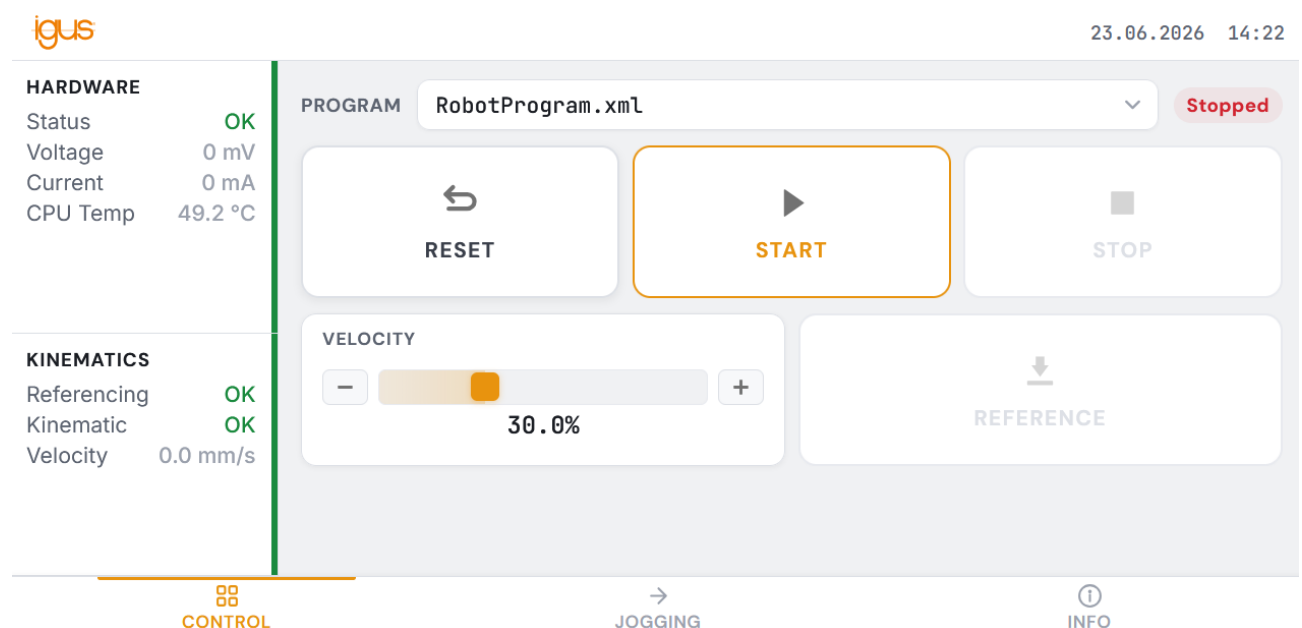


4. Functionality

4.1 Control

The “CONTROL” tab is the main view for operating the robot. Here you can enable and reference the robot, setting the speed as well as choose and start a robot program.

You can also see the main status information on the left side.



4.2 Jogging

The “JOGGING” tab enables you to jog the robot’s axes if needed. You can jog each axis by pre-defined values ($\pm 1, 10, 100$) in ‘millimeters’ for linear axes, or ‘degrees’ for rotary axes.


23.06.2026 14:25

HARDWARE
Status OK
Voltage 0 mV
Current 0 mA
CPU Temp 49.7 °C

KINEMATICS
Referencing OK
Kinematic OK
Velocity 0.0 mm/s

JOINT **CARTESIAN**

STOP

A1 103.6 mm/°

-100 -10 -1 +1 +10 +100

A2 6.5 mm/°

-100 -10 -1 +1 +10 +100

A3 77.4 mm/°

-100 -10 -1 +1 +10 +100

CONTROL

JOGGING

INFO

4.3 Info

In the “INFO” tab you can see all relevant information about the robot, like program cycles, operating time and current cartesian position.

You can also check the amount of direction changes of each axis, which can be used to estimate the axes’ wear.


23.06.2026 14:25

HARDWARE
Status OK
Voltage 0 mV
Current 0 mA
CPU Temp 50.1 °C

KINEMATICS
Referencing OK
Kinematic OK
Velocity 0.0 mm/s

PROGRAM
Program starts total 2951
Program starts 1
Last program duration 0 s
Parts good 0 (0.00%)
Parts bad 0 (0.00%)

SYSTEM
Operating time 44 min
Operating time total 100 h 14 min
Operating time enabled 42 h 22 min
Operating time in motion 7 h 58 min

TCP POSITION
X -107.2 mm
Y 90.1 mm
Z 97.2 mm
A 0.0°
B 0.0°
C 180.0°

CONTROL

JOGGING

INFO

5. Errors

In case of an error a red pop-up will appear on the top of screen that indicates the reason for the error using error codes. Please check the following site to get more information on these codes:

https://wiki.cpr-robots.com/index.php/Error_Codes

