

# [Robótica] Canal de Juan Carlos Martín Castillo

- [Canal Juan Carlos Martín Castillo](#)
- [RAPID avanzado](#)
- [Revista de Electricidad, Electrónica y Automática](#)

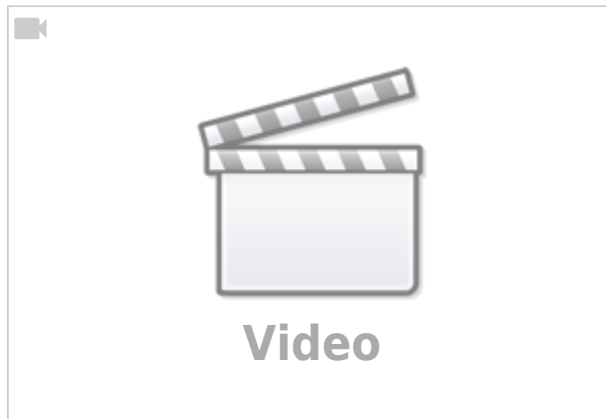
## Otros



Videos

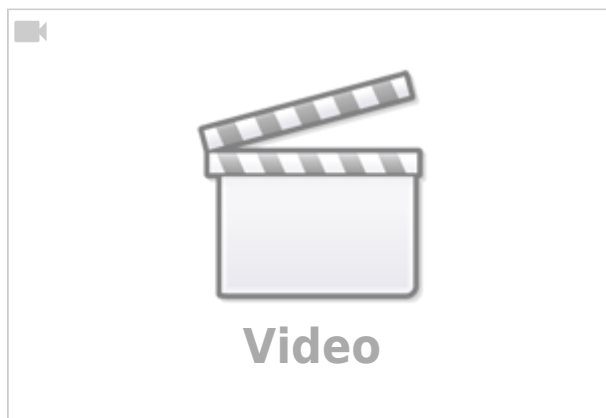
1

[Entradas y Salidas \(I\) \(28m 35s\)](#)



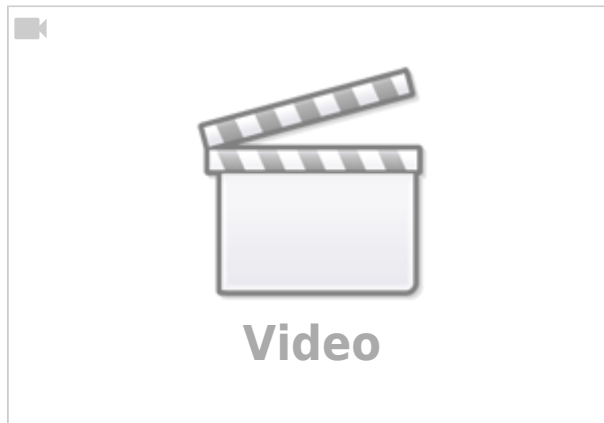
2

[Entradas y Salidas \(II\) \(42m 53s\)](#)



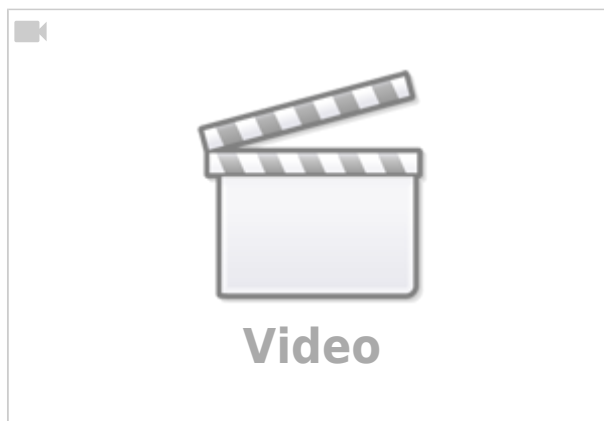
3

[Entradas y salidas virtuales en Robotware 6 \(14m 34s\)](#)



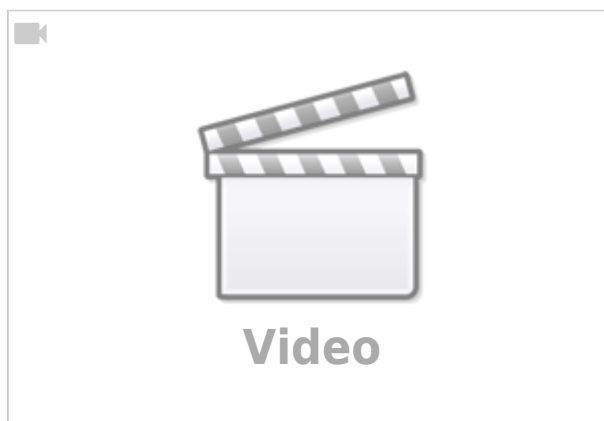
4

[Detener o reanudar el movimiento de un robot con entradas digitales \(4m 01s\)](#)



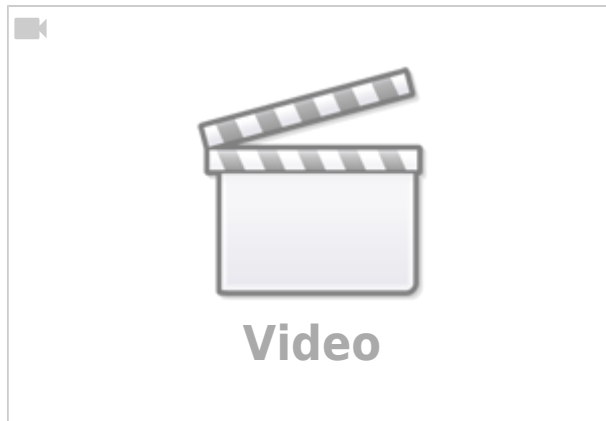
5

[Propuesta de actividad: Paletizado \(0m 43s\)](#)

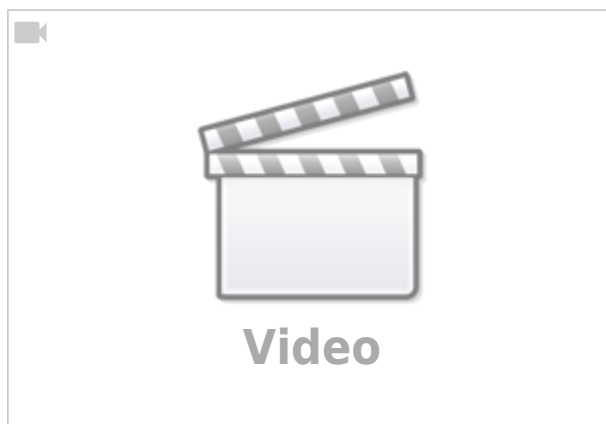


6

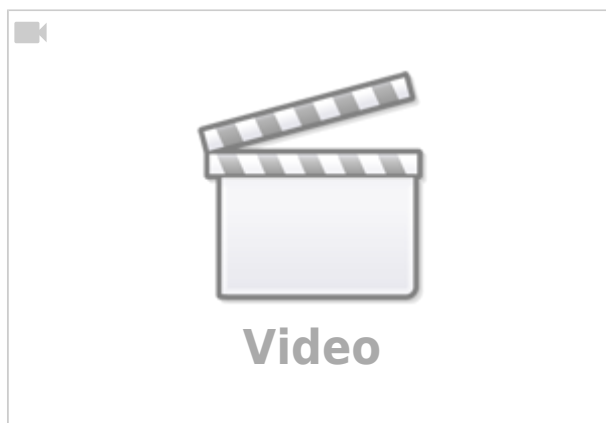
[Iniciación al uso de Smart Components \(34m 03s\)](#)



7

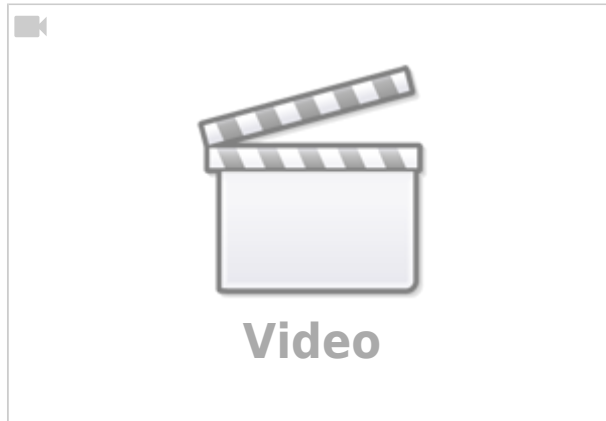
[Kit de Smart Components para RobotStudio \(11m 58s\)](#)

8

[Comunicación con WinCC Flexible mediante OPC Server \(51m 40s\)](#)

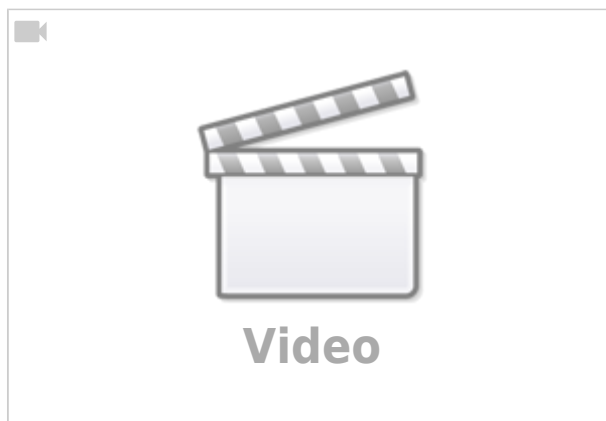
9

[Proyecto \(1\): Programando y copiando trayectorias \(19m 12s\)](#)



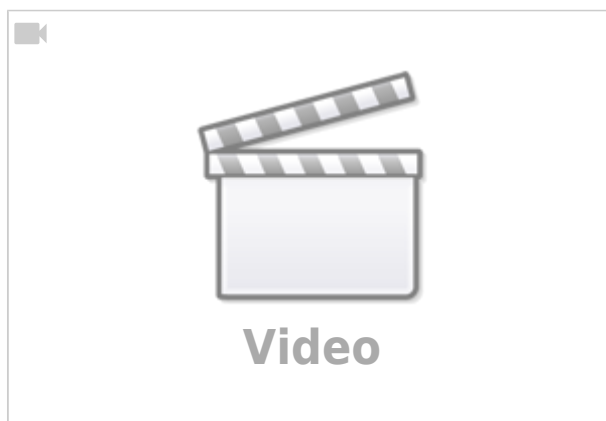
10

Proyecto (2): Uso de If-Then, For, CallByVar, TPReadNumb (21m 36s)



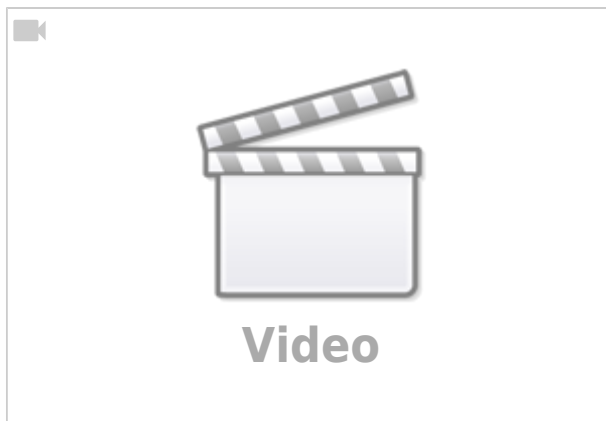
11

Proyecto (3): Activar salidas digitales con SetDO (22m 05s)



12

Proyecto (4): HMI en FlexPendant con ScreenMaker (42m 45s)



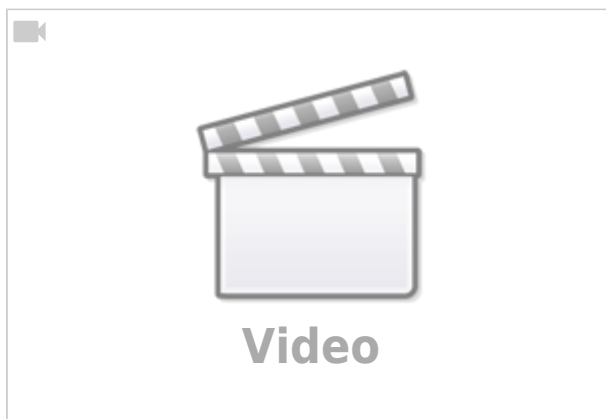
## RAPID avanzado



Videos

1

01 - Tipos de datos y procedimiento con argumentos (21m 48s)



2

02 - AliasIO para controlar salidas digitales (7m 47s)





Video

3

[03 - Posicionamiento basado en variables \(uso del pos.trans y Cpos\) \(34m 48s\)](#)



Video

4

[04 - Array de posiciones tipo robtarget \(11m 11s\)](#)



Video

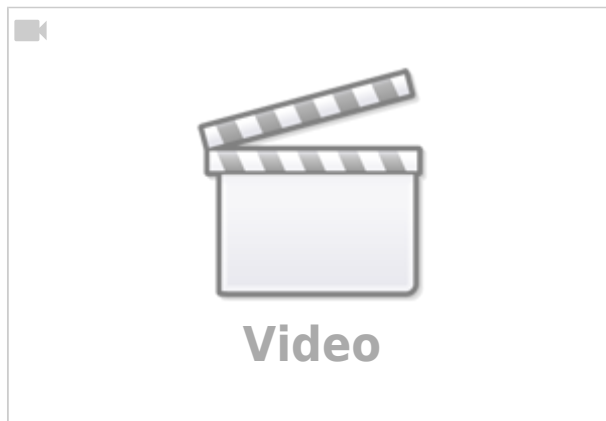
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[05 - Paletizado con Offset y bucles FOR \(22m 6s\)](#)

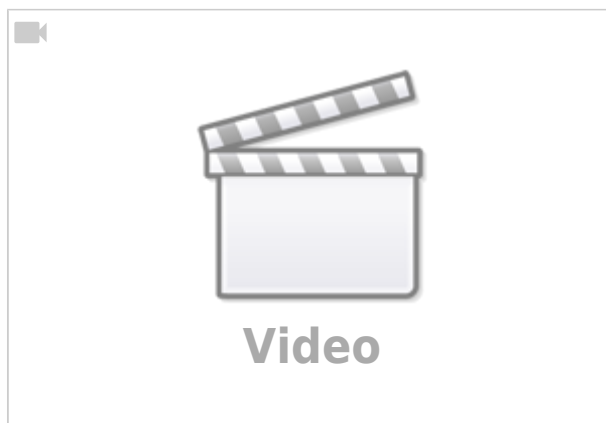


Video

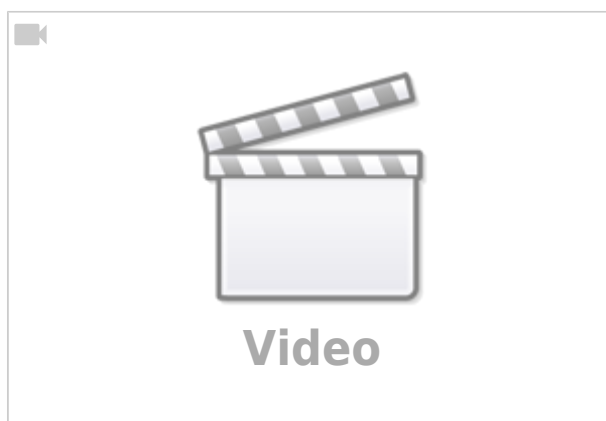
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[06 - Trayectoria rectangular dinámica \(18m 38s\)](#)

7

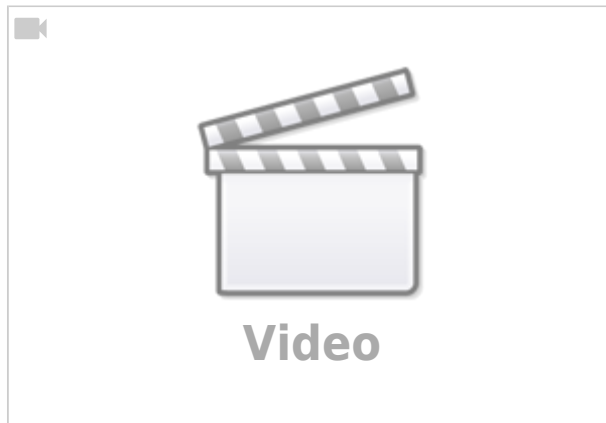
[07 - Trayectoria triangular dinamica \(11m 22s\)](#)

8

[08 - Trayectoria circular dinamica \(14m 5s\)](#)

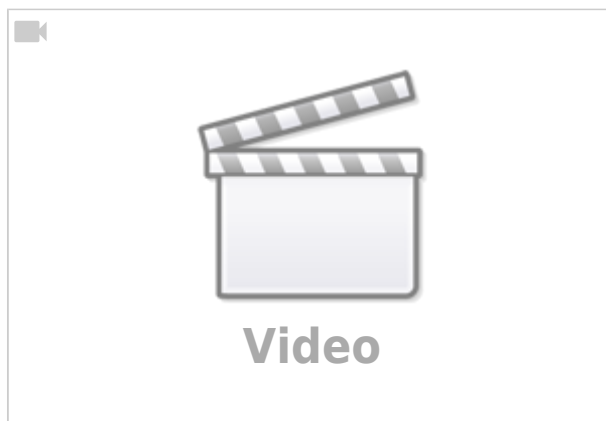
9

[09 - Posicionamiento relativo Offs vs RelTool \(14m 25s\)](#)



10

10 - Trayectoria circular dinamica con Offs y RelTool (7m 24s)



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