Notices

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⚠️ A WARNING notice denotes a hazard. It calls attention to an operating procedure, practice, or the like that, if not correctly performed or adhered to, could result in personal injury or death. Do not proceed beyond a WARNING notice until the indicated conditions are fully understood and met.

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Letter to our Customers

Dear Customer,

The Agilent Technologies acquisition of Velocity11 resulted in the following changes:

- Creation of Agilent Technologies Automation Solutions, formerly Velocity11
- Renaming of some Velocity11 products
- New Customer Service and Technical Support contact information
- New website address for product information

Please make a note of the following changes as they impact this user guide.

**Velocity11 product name changes**

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**New contact information**

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Introduction

This chapter introduces Velocity11 device drivers and provides some basic procedures that are needed to use them.

A Velocity11 device driver is software that plugs into VWorks or BenchWorks software to allow them to control a specific device.

Before reading this guide, you should be familiar with the VWorks or BenchWorks software user interface. Information about using VWorks or BenchWorks software can be found in the VWorks Version 3 Automation Control User Guide or BenchWorks Automation Control User Guide.

To set up and use Velocity11 device drivers, become familiar with the content in this guide as well as the guides for the devices that use VWorks or BenchWorks software.

This chapter contains the following topics:
- “Who should read this guide” on page 2
- “About Velocity11 user guides” on page 3
- “What this guide covers” on page 5
- “About devices” on page 6
- “About device drivers” on page 7
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- “Using JavaScript to set task parameters” on page 21
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Who should read this guide

Job roles

This user guide is for people with the following job roles:

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<td>Someone who writes software and configures hardware controlled by device drivers.</td>
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<td>Lab manager, administrator, or technician</td>
<td>Someone who is responsible for:</td>
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<td></td>
<td>❑ Installing device drivers</td>
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<td>❑ Managing device drivers</td>
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<td>❑ Developing the applications that are run using device drivers</td>
</tr>
<tr>
<td></td>
<td>❑ Solving the more challenging problems that might arise</td>
</tr>
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<td></td>
<td>❑ Developing training materials and standard operating procedures for operators</td>
</tr>
<tr>
<td>Operator</td>
<td>Someone who performs the daily production work using the device driver and solves routine problems. Your organization may choose to create its own procedures for operators including the procedures in this guide.</td>
</tr>
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</table>

Related topics

| For information about...                     | See...                                                               |
|----------------------------------------------|                                                                     |
| Contacting Velocity11                        | http://www.velocity11.com/contact.html                            |
| Accessing online help                        | “About Velocity11 user guides” on page 3                          |
| Device drivers                               | “About device drivers” on page 7                                   |
About Velocity11 user guides

About this topic
This topic describes the different formats of Velocity11 user information and explains how to access the user information.

Formats available
Velocity11 user information is provided to you as:
- Online help
- A PDF file
- A printed book

The information in each format is the same but each format has different benefits.

Where to find user information

Online help
The online help is added to your computer with the Velocity11 lab automation system software installation.

PDF file
The PDF file of the user guide is on the software CD that is supplied with the product.

Velocity11 website
You can search the online help or download the latest version of any PDF file from the Velocity11 website at www.velocity11.com.

Note: All Velocity11 user information can be searched from the website at www.velocity11.com.

Online help
The online help is the best format to use when you are working at the computer and when you want to perform fast or advanced searches for information.

To open the online help:
1. In the Velocity11 lab automation software, press F1. The online help window opens.

Main features
The online help window contains the following:
- **Navigation pane.** Consists of four tabs. The Contents, Index, and Search tabs provide different ways to locate information. The Using tab contains information about using the help system.
- **Content pane.** Displays the online help topics.
- **Navigation buttons.** Enables you to navigate through the pages. The online help includes a navigation pane, content pane, and navigation buttons.
Computer requirements

To open a user guide in PDF format, you need a PDF viewer. You can download a free PDF viewer from the internet.

Printing and searching

The user guides in PDF format are mainly for printing additional copies. You can perform simple searches in the PDF file, although these searches are much slower than online help searches.

More information

For more information about using PDF documents, see the user documentation for the PDF viewer.

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<tr>
<td><strong>About this topic</strong></td>
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<tr>
<td>This topic presents an overview of what procedures and information are provided in this user guide. This guide explains how to:</td>
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<td>- Install the driver for the device</td>
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<td>- Configure the device in the device manager</td>
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<td>- Set and use the tasks associated with the device</td>
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<td>- Use Device Diagnostics</td>
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<tr>
<td><strong>Also read</strong></td>
<td></td>
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<tr>
<td>Information about device drivers not covered in this guide and about running VWorks or BenchWorks software can be found in the VWorks Version 3 Automation Control User Guide or the BenchWorks Automation Control User Guide.</td>
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<tr>
<td><strong>Driver version</strong></td>
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<tr>
<td>To find version information for a driver in VWorks:</td>
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<tr>
<td>1. Start VWorks.</td>
<td></td>
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</tr>
<tr>
<td>2. Click Help and select About VWorks. The About VWorks dialog box lists the version numbers of all the current software for all the devices and plug-ins.</td>
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<tr>
<td><strong>To find version information for a driver in BenchWorks:</strong></td>
<td></td>
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<tr>
<td>1. Start BenchWorks.</td>
<td></td>
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<tr>
<td>2. Click Help and select About BenchWorks. The About BenchWorks dialog box lists the version numbers of all the current software for all the devices and plug-ins.</td>
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<tr>
<td><strong>Firmware version</strong></td>
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<tr>
<td>Some devices have firmware installed on them. Because each device is different, the version number may not be the same for all devices.</td>
<td></td>
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<tr>
<td>To find version information for device firmware:</td>
<td></td>
<td></td>
</tr>
<tr>
<td>1. Open Device Diagnostics dialog box.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>2. Click About. The About Device Control message box appears displaying the current version of firmware.</td>
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<td><strong>What this guide does not cover</strong></td>
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<td>This guide does not cover the following:</td>
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<tr>
<td>- The operation of the device</td>
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<td>- The operation of VWorks or BenchWorks software</td>
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<tr>
<td>- Velocity11 devices, such as the PlateLoc Sealer, VCode Microplate Labeler, and VPrep Pipettor when used in stand-alone mode</td>
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Chapter 1: Introduction
Translator Robot Device Driver User Guide

VWorks or BenchWorks compatibility
If you have purchased a device driver plug-in and are installing it yourself, check with the Velocity11 Technical Support to be sure your version of VWorks or BenchWorks software and the device driver plug-in are using the same version of IWorks software.

BenchWorks versions
Device driver plug-ins used with BenchWorks software may not include some newer features that were specifically added for use with VWorks software and that are described in this manual.

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About devices

About this topic
This topic presents a definition of a Velocity11 device and the device file.
Read this topic if you are unfamiliar with Velocity11 devices and VWorks or BenchWorks software.

Device defined
A device is an item on your lab automation system that has an entry in the device manager. A device can be a robot, an instrument, or a location on the lab automation system that can hold a piece of labware.
Examples of devices:
- Velocity11 robot
- Human robot
- PlateLoc Thermal Plate Sealer
- Labcyte Echo550
- Platepad
- VPrep shelf
- Waste

Device file defined
The data entered into the device manager and saved as a device file contains the configuration information for your devices.
Device file location

Device files have the file name format `filename.dev` and are stored in the folder location that you specify when saving the file.

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About device drivers

About this topic

This topic describes what device drivers are and what they do. Velocity11 device drivers enable mechanical devices or software programs to work with VWorks or BenchWorks software.

Read this topic if you are:

- An administrator in charge of installing device drivers and managing Velocity11 devices
- A lab automation system integrator who writes software and configures hardware controlled by VWorks or BenchWorks software

Device driver defined

A Velocity11 device driver enables VWorks or BenchWorks software to control and communicate with the specific type of device. Each type of device that you operate with VWorks or BenchWorks software requires a device driver.

For example, VWorks software uses the:

- VPrep Pipettor device driver to communicate with the Velocity11 VPrep Pipettor device
- Softmax Reader device driver to communicate with Molecular Devices readers

Plug-in defined

A plug-in is a software program that when added to another program extends it.

Plug-in device drivers

Some device drivers are incorporated directly into the VWorks or BenchWorks software application. Other device drivers are distributed as plug-ins. All the device drivers covered in this guide are the plug-in type.
Advantages of distributing device drivers as plug-ins are:

- You only need to install the plug-ins for the devices you use.
- When new plug-ins become available, they can be easily added. There is no need to re-install the VWorks or BenchWorks software application.

**IWorks interface**

The device driver plug-ins and VWorks or BenchWorks software use IWorks software as a common interface to communicate with each other. Using a common interface allows the creation of a device driver plug-in without the necessity of changing the software.

**!! IMPORTANT !!** Both VWorks or BenchWorks software and the device driver must be using the same version of IWorks to work properly.

**Writing your own device driver**

If you are a lab automation system integrator who writes software and configures hardware controlled by VWorks or BenchWorks software, you can write your own driver plug-in for a new device. Contact the Velocity11 Technical Support for information about how to do this.

**What functions do the device drivers provide?**

Once installed, the following items are enabled:

- Tasks associated with the device.
  
  Device-specific tasks appear in the Protocol Tasks list and are available for use in protocol editor processes.

- Task parameters associated with the device.
  
  Device-specific task parameters appear in the Protocol Task Parameters toolbar. These determine the conditions with which to execute the tasks of the device.

- Diagnostic commands specific to the device.
  
  Device-specific diagnostic commands and options appear in the Device Diagnostics dialog box. These commands enable direct control of the device.

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Installing device drivers

About this topic

Devices are integrated into VWorks or BenchWorks software using device driver plug-ins. Plug-ins need to be installed before the device can be configured and used.

This topic describes how to install device drivers if they are not already installed on your system. Read this topic if you are an administrator in charge of managing Velocity11 devices.

Procedure

To install device drivers:

1. Insert the device driver installation disc into the CD-ROM of the computer running VWorks or BenchWorks software.
2. Follow the on-screen instructions for installation, selecting the default values when available.
3. When finished, exit VWorks or BenchWorks software.
4. Log off Windows and restart your computer.
5. Start VWorks or BenchWorks software.

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<td>C:\VWorks Workspace\bin\plugins</td>
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<tr>
<td>BenchWorks software</td>
<td>C:\Program Files\Velocity11\BenchWorks\plugins</td>
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Adding devices

About this topic
To configure your lab automation system to use a device, you need to add it to a device file in VWorks or BenchWorks software. The VWorks or BenchWorks software device manager uses the information in the device file to communicate and operate the device within the automation system.

This topic describes how to:
- Create a new device file (if one does not already exist)
- Add devices
- Save the device file

Read this topic if you are an administrator in charge of managing Velocity11 devices.

Procedure

To add devices to a device file:

1. Make sure that the devices are physically networked to the VWorks or BenchWorks software computer and turned on.
2. Start VWorks or BenchWorks software and login as an Administrator.
3. Do one of the following:
   - If you have an existing device file that you want to add to, select **File > Device File**, click **Open**, and select your device file.
   - If you are creating a new device file, select **File > Device File** and click **New**.
4. Click the **Device Manager** tab.
5. Click **New device** in the **Device List** toolbar and enter a name for the device you are adding.
6. In the device manager, set the **Device type**.
   The default type is **Plate Pad, Standard**.
7. Repeat step 5 and step 6 for each device.
8. Select **File > Device File > Save.**

If you are creating a new device file, you are prompted to enter a name for your device file.

Alternatively, you can select **File > Save All.** This saves the device file and the current protocol file at the same time.

---

### About diagnostics

**About this topic**

This topic presents an overview of diagnostics software.

Read this topic if you need to set up or troubleshoot a device running VWorks or BenchWorks software.

**Background**

Devices can be controlled in real time directly through the VWorks or BenchWorks software Diagnostics using simple commands.

Diagnostics software is used for:

- Troubleshooting
- Setting teachpoints
- Performing manual operations outside a protocol
- Creating and editing profiles

For example, if an error occurs during a run that leaves a plate and the robot where they should not be, you can use robot diagnostics to move the plate and return the robot to its home position.

**Types of diagnostics software**

Devices and robots manufactured by Velocity11 include their own diagnostics software. You can find instructions for using this software in the relevant user guide.
## Opening diagnostics

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### Opening diagnostics

#### About this topic

Every device has diagnostics software to assist you with troubleshooting and setting up the device. This topic describes how to open a device’s diagnostics in VWorks or BenchWorks software.

Read this topic if you need to access a device’s diagnostics to perform a device setup task or manually operate a device.

#### Procedure 1

**If you are using VWorks4 software**

**To open Diagnostics:**

1. Click **Diagnostics** on the Control toolbar.

   ![Diagnostics icon](image1)

2. In the device file’s window, select the device. Expand the general name of the device, if necessary.

3. Click **Device diagnostics** located at the bottom of the window. The device’s diagnostics dialog box opens.

**If you are using VWorks3 or BenchWorks software**

**To open Diagnostics:**

1. Click **Diagnostics** on the Control toolbar.
2. In the **Diagnostics** window, select the device. Expand the general name of the device, if necessary.

![Diagnostics window with device selected]

3. Click **Device diagnostics**. The device’s diagnostics dialog box opens.

---

**Procedure 2**

**If you are using VWorks4 software**

**To open Diagnostics:**

1. Click the **Device File** tab.
2. Select the device from the **Devices** toolbar. Expand the general name of the device, if necessary.

![Device File tab with device selected]

3. Click **Device diagnostics** located at the bottom of the **Devices** toolbar.

![Device diagnostics option]

The device’s diagnostics dialog box opens.

**If you are using VWork3 or BenchWorks software**

**To open Diagnostics:**

1. Click the **Device Manager** tab.
2. Select the device from the **Device List** toolbar. Expand the general name of the device, if necessary.
3. Click **Device diagnostics** located at the bottom of the **Device List** toolbar.

The device’s diagnostics dialog box opens.

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About profiles

About this topic
This topic describes what profiles are and what they do.
Read this topic if you are an administrator in charge of managing Velocity11 devices.

Profiles defined
A profile contains the initialization settings needed for communication between a device and device driver. The data in a profile is used by VWorks or BenchWorks software to identify each device on the network.

A profile can also contain other basic settings that you are unlikely to change once set up.
Because profiles identify device driver devices on the network, each device driver device must have its own profile.
You can create, modify, and delete profiles as needed.

Stored settings
Profiles are stored in the Windows registry.
The settings stored in a device driver profile include:
- Whether the device is connected using serial or Ethernet
- If the device is connected using Ethernet, the Device ID of the device on the network
- If the device is connected using serial, the COM port that the controlling computer uses for communication
- Configuration of accessories

Related topics

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</table>
Setting the properties for a device

About this topic

The device properties provide VWorks or BenchWorks software with additional information about the device's current configuration, such as which profile to use, and stores the information in the device file. The device file is automatically loaded when you open a protocol.

The device properties need to be set when configuring the device. Typically, these properties only need to be set once. This topic describes how to set the following device properties:

- General
- Teachpoint
- Barcode
- Location (for devices with multiple teachpoints)
- Device Properties

Read this topic if you are an administrator in charge of managing Velocity11 devices.

Before you start

Make sure that you have installed the device driver plug-in and have added the device to the device manager.

See “Related information” for procedures on how to do these tasks.

Setting general properties

To set the general properties for a device:

1. Click the Device Manager tab.
2. Select the device from the Device List toolbar. (Expand the device name, if necessary.)

   Note: For devices with Locations, see “Setting location properties” on page 17. If no Locations, continue with step 3.

3. In the General group, set the following:

   a. Approach height. This is the height to raise the robot gripper above the teachpoint when the robot moves the plate horizontally towards or away from it.

   b. Allowed/prohibited labware. Click the adjacent field to open the dialog box. Move the labware classes by selecting them and clicking one of the arrow buttons.

4. In the Device Properties, select the desired profile if it is not already selected.
5. Select File > Device File > Save to save the changes to the device file.
Setting teachpoints

Teachpoints are the coordinates in space that a robot travels to in order to interact with a device. Only the devices that are accessible by robots are able to have teachpoints.

To set the teachpoint properties:
1. Open the Device Properties page.
2. In the Teachpoints property group, set the following:
   a. **Device is accessible from robot robot’s name.** Choose Yes or No.
   b. **Teachpoint for robot robot’s name.** Choose a file.

<table>
<thead>
<tr>
<th>Teachpoints</th>
<th>Teachpoint for robot robot’s name</th>
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<tbody>
<tr>
<td>Yes</td>
<td></td>
</tr>
<tr>
<td>No</td>
<td></td>
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</tbody>
</table>

Setting barcode location

If your device has a barcode reader, indicate where the reader is located.

To set the barcode readers property:
1. In the Barcode Readers property group, set the side that has the barcode to Yes.
2. Enter the number of the COM port to which the device is connected.

<table>
<thead>
<tr>
<th>Barcode Readers</th>
<th>Device has south side BCR</th>
<th>Device has north side BCR</th>
</tr>
</thead>
<tbody>
<tr>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
</tr>
<tr>
<td>No</td>
<td>No</td>
<td></td>
</tr>
</tbody>
</table>

Note: The options available under Location groups might differ for software and hardware device drivers. Software devices do not have robot-accessible labware positions.

For hardware devices that have more than one robot-accessible labware position, the approach height, allowable/prohibited labware, teachpoint, and barcode properties are located under Location groups.

To set the Location properties:
1. **Hardware device drivers only.** Set the Use linked location. Follow the procedure in “Setting the Use linked location” on page 18.
2. **Hardware device drivers only** Set the Teachpoints. Follow the procedure in “Setting teachpoints” on page 17.
3. **Some software device drivers only.** Set the **Approach height** and **Allowed/prohibited Labware.** Follow the procedure in “Setting general properties” on page 16.

4. Set the **Barcode Readers** location. Follow the procedure in “Setting barcode location” on page 17.

5. Assign the **Labware** used by the location by selecting the correct labware type from the list.

6. In the **Device Properties**, select the desired profile if it is not already selected.

7. Select **File > Device File > Save** to save the changes to the device file.

### Setting the Use linked location

Currently, this feature is enabled for the special situations in which there is a storage device such as a PlateHub Carousel, StoreX, or Cytomat and a robot, such as the Velocity11 Translator robot that is shuttling plates between systems.

To use this feature, select yes and then select the device location to which you want to link. This tells the software that the current device location is the same physical location as the device selected from the Device to use list.

**Note:** Selecting this option when it is not enabled will have no effect on the system.

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Adding and linking Sub Process tasks

About this topic
This topic describes how to add a sub-process to a protocol and configure it. Read this topic if you are an administrator or technician and are responsible for creating protocols in VWorks or BenchWorks software.

Before you read this
Before you read this topic, become familiar with the topics in the VWorks Version 3 Automation Control User Guide or BenchWorks Automation Control User Guide describing what a protocol is and how it is created.

Sub Process task defined
Sub Process tasks indicate the existence of a subroutine within a protocol. Sub-processes typically contain a series of liquid handling tasks used by devices such as the VPrep Pipettor or Multimek dispenser.

Adding a Sub Process task
The first step in creating a pipette process is to add a Sub Process task to the protocol editor. Drag the Sub Process icon into the process.

Setting Sub Process task parameters
When you add the Sub Process task, a new sub-process is started in the pipette process editor. This process is identified by its sub-process link icon.

Because you can have more than one sub-process in a protocol, you must link the Sub Process task to the correct sub-process.

To link the Sub Process task to the correct sub-process:
1. In the Protocol Editor, add a Sub Process task to the protocol and then select it in the protocol sequence.
2. In the Protocol Task Parameters toolbar, select the sub-process that you want to use for this pipetting task from the Use Sub Process list.
3. If there is only one sub-process and you need to create a second one, click **Add New**.

**Associating the sub-process to a device**

Because you can have more than one device that uses sub-processes on a lab automation system, you must link each sub-process link icon with one or more devices that you want the sub-process to be able to use. You do this by setting the parameter for the sub-process link icon.

**To link a Sub Process task to a device:**

1. In the **Pipette Process Editor**, select the **Sub Process** link icon.

2. In the **Available devices** list of the **Pipette Task Parameters** toolbar, select one or more pipettors to link to and click **Add**.

The selected pipettors move to the lower box and become available for use.
Using JavaScript to set task parameters

About this topic

JavaScript programs (scripts) can be used to change the parameters of a protocol task immediately before it is scheduled. This extends the capability of VWorks or BenchWorks software because the parameters can be changed dynamically during a run, based on the following:

- Information passed from an external source, such as a database
- The number of times the protocol has cycled
- Feedback on changing conditions during the run

This topic describes the use of JavaScript to set task parameters in a protocol.

Read this topic if you are an administrator or technician responsible for creating VWorks or BenchWorks software protocols and want to add functionality to a task using JavaScript.

Where scripts are written

Scripts can be written in two ways:

- Directly into the box in the Advanced Settings tab of the Task Parameters toolbar
- As an external file that is located by clicking Browse in the Advanced Settings tab and navigating to its location on the hard drive

Note: You can also call an external file by embedding the “open ()” function in the box.

The following screenshot displays a short script that prints the parameters of a task to the log toolbar, just before the task runs. In this case, the script is written directly in the Advanced Settings box.
For more information about using JavaScript, refer to the *VWorks Version 3 Automation Control User Guide* or the *BenchWorks Automation Control User Guide*.

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### About reader output files

**About this topic**

Plug-in device drivers that are written for plate readers have a common way of naming their output files. This topic explains the concepts related to output file naming. By reading this topic, you will learn how to prevent data in the reader output files from being overwritten by newer data.

Read this topic if you are an operator who wants to make changes to the task parameters for one of these readers:

- VR4000
- Analyst GT
- Fusion
- Viewlux
- Tecan readers

**Plug-in default output file**

When you first install a reader device driver plug-in, all data recorded during a protocol or by a manual read using diagnostics software is written to a single file stored in the C: drive.
The exact name of the file is specific to the device. For example, the RVSI VR4000 device driver creates a file with the name vialreaderresults.txt.

This file can only store data for one read, which means that the set of data for each read overwrites the last set in the file. To avoid this problem you must set up an output file naming convention.

### Profile default output file name

Some device drivers allow more than one device of that type to be used in the lab automation system. In this case, each device must have its own profile. Even if you have only one device, you can still set up multiple profiles for it, with each storing different settings.

In these cases, you probably want each profile to have a separate default output filename to prevent the data from runs using one profile overwriting those of another.

### Filename suffixes

To prevent the data from one read overwriting the data from another, you need to append a variable suffix to the file name. You can append a date/time stamp and one or more bar codes on the rack or plate.

#### Example

The example output file folder below shows that a profile default file name of output.txt was created at one time. At another time, a suffix was appended in the profile for the device driver, which added a barcode identifier to the file name (for example output_C100040329.txt).
Overriding output file names with tasks

You can override the default output file name that is set in the profile using the Output filename property of the Read task parameters.

This allows you to use different output file names for every task.

The suffix used for the file name that you set in the task parameters is taken from the suffix specified in the device diagnostics profile. So if you select date/time stamp in the profile, the date/time stamp will also be appended during a run in which you have specified a different file name.

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About device initialization

About this topic
When working in device diagnostics software, you are often required to initialize the device. This topic explains why device initialization is necessary.

Opening communications
Initializing a device opens communications with it. For example, if the device is connected with a serial cable, the COM port is opened, and if the device is connected with an Ethernet cable, the TCP/IP socket is connected.

Homing motors
Initializing a device homes motors that do not track their position along their line of travel. Homing a motor moves it until it triggers an event, called a home flag. This tells the motor its location.

The motors on some devices automatically move to their home positions when the device is turned on. The motors on other devices must be initialized to be homed.

Setting profile parameters
Initializing a device applies relevant parameters set in the device’s profile.

Setting state and memory variables
Most devices store variables in software or firmware. Initializing a device sets these variables to their initial values.

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The Robo Cylinder Translator Robot is a custom, proprietary, two-axis robot.

It can be configured to work in a lab automation system using VWorks.

This chapter contains the following topics:

- “Workflow for configuring the Translator Robot” on page 28
- “Creating a Translator Robot profile” on page 28
- “Creating a Translator Robot profile” on page 28
- “Operating the Translator Robot with diagnostics” on page 31
Workflow for configuring the Translator Robot

About this topic
Before you can use the Translator Robot in a protocol, you need to configure the Translator Robot in VWorks. This topic presents the workflow for configuring the Translator Robot. Read this topic if you are an administrator who is responsible for setting up a Translator Robot in VWorks.

Before you start
Before you can configure the Translator Robot device driver you must have installed it. For installation instructions, see “Setting the properties for a device” on page 16.

Workflow

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Creating a Translator Robot profile

About this topic
This topic describes how to create a profile for the Translator Robot. Read this topic if you are an administrator who is responsible for setting up a Translator Robot in VWorks.

Before you start
Before you can create a profile, you must install the Translator Robot device driver plug-in and add the Translator Robot to the device manager.

Procedure

To create a Translator Robot profile:
1. Open TBot Diagnostics.
2. Click the Profiles tab.
3. Select the Translator Robot **COM port** and the **Gripper COM port** from the list boxes.
   These are the numbers of the computer ports that are connected to the Translator Robot.

4. If different, change the default values for the X and Z axes screw pitch.
   The screw pitch value is dependent on the type of motor the robot uses. See the Translator Robot documentation for the values.

5. Optionally, change the default timeouts for X and Z movements.
   This is the maximum time the robot is allowed to carry out a command for that direction before sending an error message.

6. Optionally, select the **Turn off...** check box to turn off plate detection when you are using diagnostics.

7. Select a **Teachpoint file**. If you do not have one, create one:
   a. Click **Create new teachpoint file**.
   b. Enter a name for the file in the **Create a blank TBot teachpoint file** dialog box.
   c. Optionally, change the directory for the teachpoint file.
   d. Click **Save**.

8. Click **Create a new profile**.

9. Enter a name and click **OK**.
### Related topics

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### Managing Translator Robot profiles

**About this topic**

This topic describes how administrators and technicians can manage Translator Robot profiles.

**Managing profiles**

To manage Translator Robot profiles:

1. Open **TBot Diagnostics**.
2. Click the **Profiles** tab.
3. Select a profile from the **Profile name** list.
Chapter 2: Translator Robot
Translator Robot Device Driver User Guide

4. Perform the management task.
   Management tasks include the following:
   - Updating the profile. Use this command to save edits to an existing profile.
   - Copying a profile.
   - Renaming a profile.
   - Deleting a profile.

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Operating the Translator Robot with diagnostics

About this topic

This topic describe how to use Translator Robot Diagnostics to:
- Initialize the Translator Robot
- Create and modify teachpoints
- Check robot grippers

Read this topic if you are an operator who wants to troubleshoot a problem or otherwise operate the robot without running a protocol.

Initializing the Translator Robot

Before you can send commands to the Translator Robot, or receive status information from the Translator Robot, you need to open communications with it.

To open communications with the Translator Robot:
1. Open Translator Robot Diagnostics.
2. Click the Profiles tab.
3. Click Initialize this profile.

Creating teachpoints

Use the Teachpoints page of TBot Diagnostics to create, rename, and delete teachpoints. Once created, use the commands on the Control page to modify and fine tune the teachpoints.
To create a teachpoint:

1. Open TBot Diagnostics.
2. Click the Teachpoints tab.

3. Click New.
4. Enter a name for the teachpoint and click OK.
5. Optionally, choose the teachpoint’s initial coordinates.
   - Enter an X and Z-axis position and click Save teachpoints or,
   - Click Use current position and then click Save teachpoints.

Note: You can also create a new teachpoint file and its directory location from the Profiles page.

To modify or fine-tune the Translator Robot teachpoints:

1. Open TBot Diagnostics.
2. Click the Controls tab.
3. Select the teachpoint you want to modify from Teachpoint 1 list. If you want to fine tune the robot travel between two teachpoints, select the second teachpoint from the Teachpoint 2 list.

4. Select the labware that you are using from the Labware list. To edit or add labware, click Editor to open the Labware Editor.

5. Use the commands in the Actions area to pick and place labware and move between teachpoints. Use the following table as a guide.

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<td>Move to the selected teachpoint.</td>
</tr>
<tr>
<td>Pick</td>
<td>Pick up the labware from the selected teachpoint.</td>
</tr>
<tr>
<td>Place</td>
<td>Place the labware at the selected teachpoint.</td>
</tr>
<tr>
<td>Pick and Place</td>
<td>Pick up the labware from the non-selected teachpoint and places it at the selected teachpoint. For example, if you click Pick and Place under Teachpoint 2, the robot picks the plate up from teachpoint 1 and places it at Teachpoint 2.</td>
</tr>
<tr>
<td>Teach</td>
<td>Record the current position as the teachpoint.</td>
</tr>
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6. Use the controls in the Robot Position area to modify the position of the robot to fine-tune the teachpoints.

To move the robot by hand, click the Servo on button to turn off the motor and then move the robot.

To send the robot back to the zero position, click Home.
Note: If you have a problem and need to reinitialize the robot, go to the Profiles page and click Initialize this profile.

7. When you are satisfied with the teachpoints, click Save teachpoints.
8. Click OK to exit the dialog box.

To check the robot’s gripper sensors:
1. Use the commands in the Gripper area to open and close the gripper.
2. Monitor the indicator lights to confirm the gripper action.

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