

What to Expect after Turning on the Controller

Bootup

After the controller boots, you will be greeted by the prompt

```
$
```

which represents the interactive system shell. To enter the application shell of choice, use the command

```
$ ash myash
```

where **myash** is the name of your application. From this point onward, you will be greeted by the prompt

```
myash>
```

Refer to the *Advanced Application Development Guide* to begin your development, or to the section below on basic operations.

Operating the Robot from a Terminal

If there is a teach pendant connected to your controller, the controller will start up with the pendant as the active point of control.

For instructions on how to operate your robot with the teach pendant, refer to the *Teach Pendant User Guide*. To shut down the pendant and pass control to the terminal, press the ESC key on the pendant, and press F1 in response to the prompt.

Consult your robot user guide to learn about the default settings of your system, including joint speeds, accelerations, etc. Refer to your application development guide on how to alter the default settings and how to verify them at anytime.

The default startup speed setting is always 10%.

The basic robot motion commands are shown in the table below. Refer to your application development guide on detailed instructions on these and other commands.

Table 5: Basic robot motion commands

command	action
joint j 30	move joint j by 30°
move <i>posn</i>	move to the taught location <i>posn</i>
speed	display the current speed setting
speed 45	change the speed setting to 45%
accel	display the current acceleration settings
here <i>posn</i>	store the current robot location in the location variable <i>posn</i>