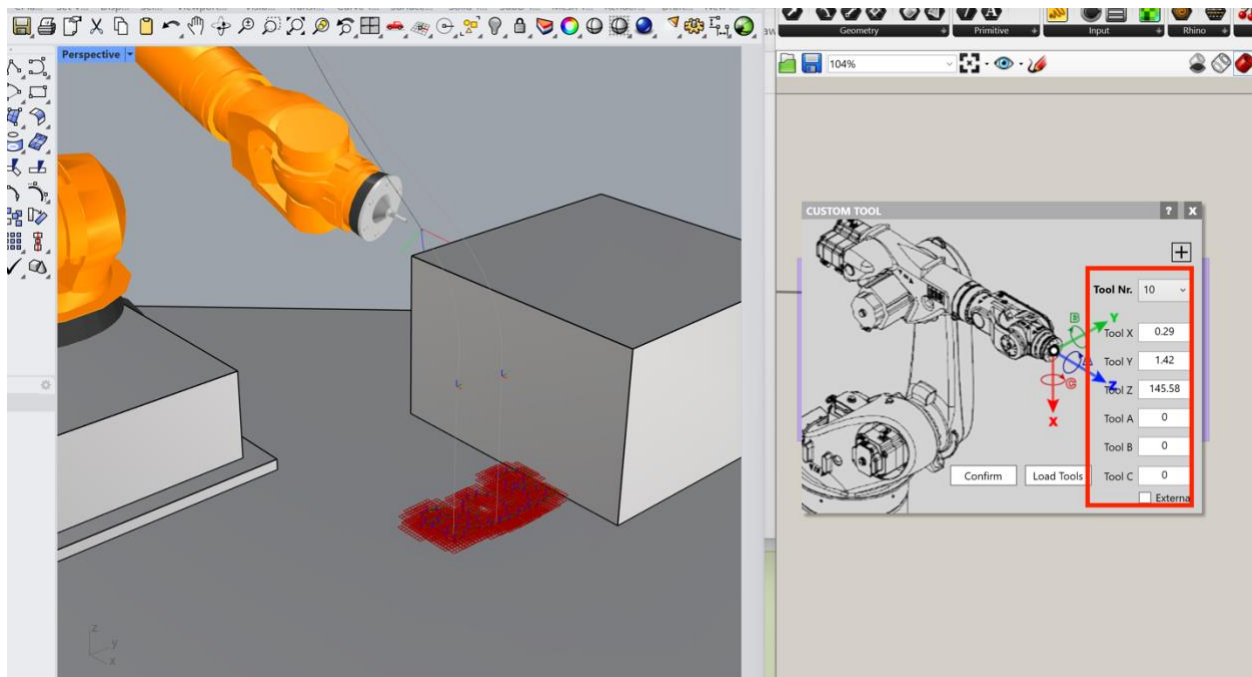


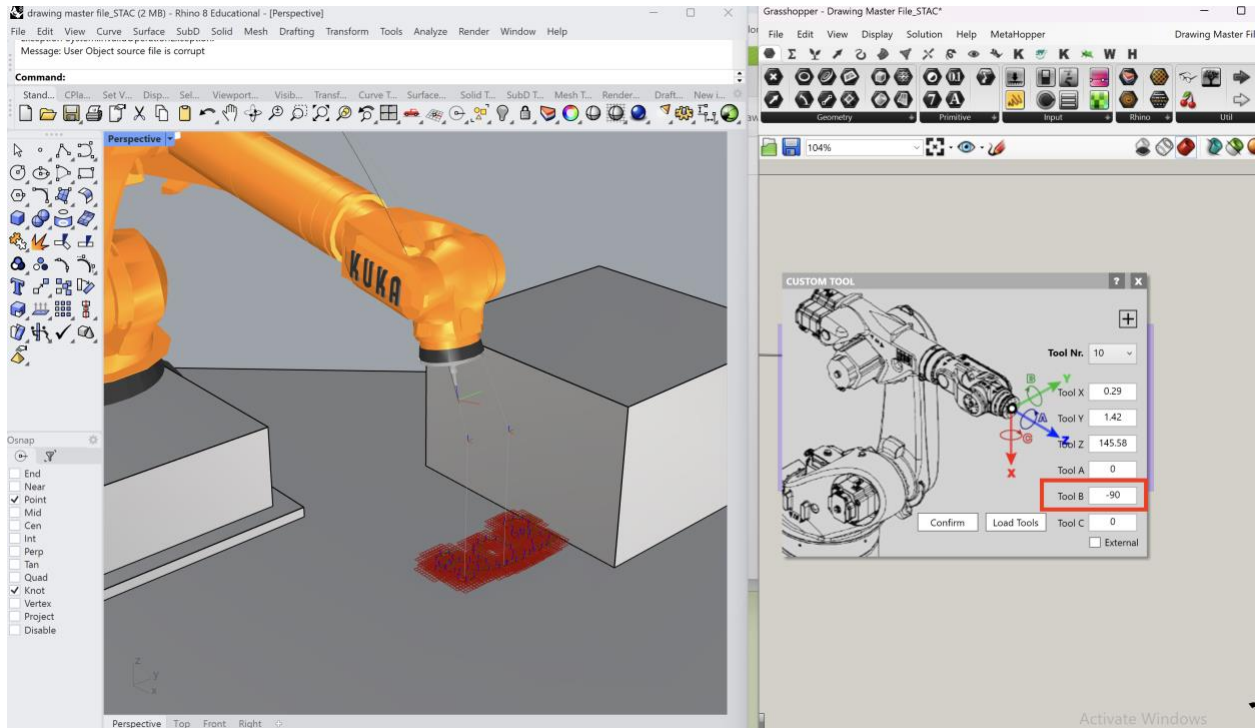
The start/end position in PRC match the robot home position:



The tool was taught on the robot touch pendant (TP) and these values were then added to KUKA PRC as:



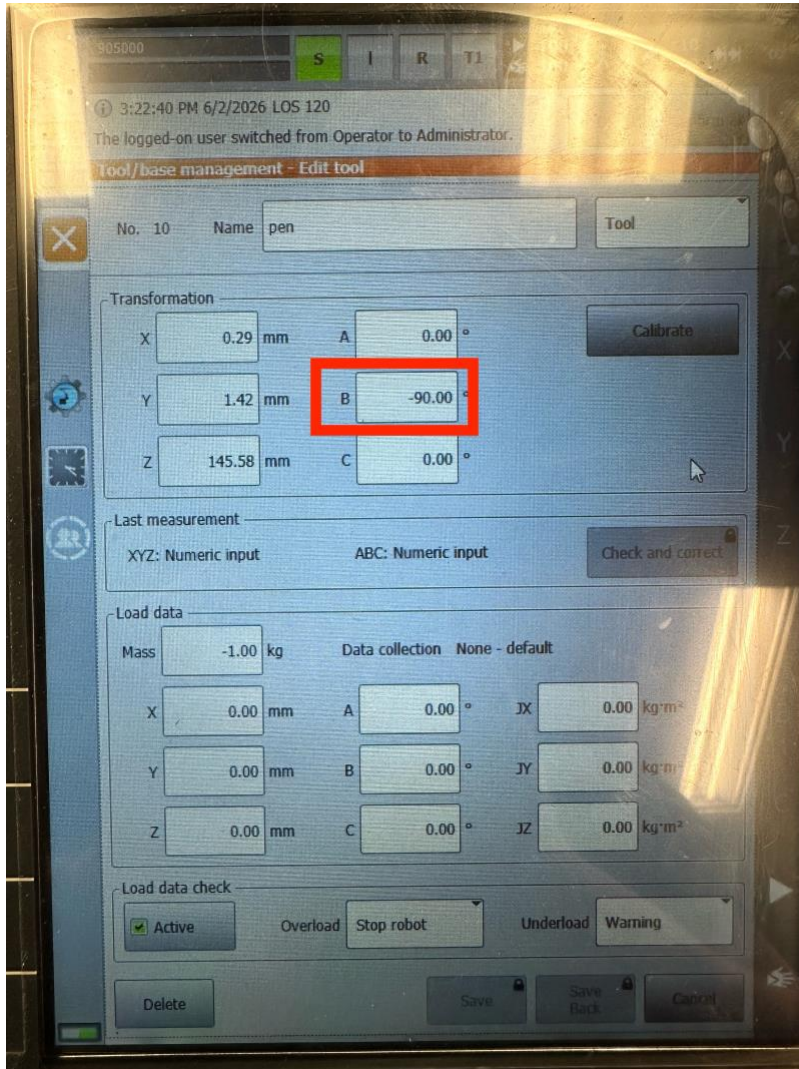
However, the simulation is not ideal with these values and the robot approaches from the side in the wrong direction. The simulation is corrected when the tool axis-B is changed to -90:



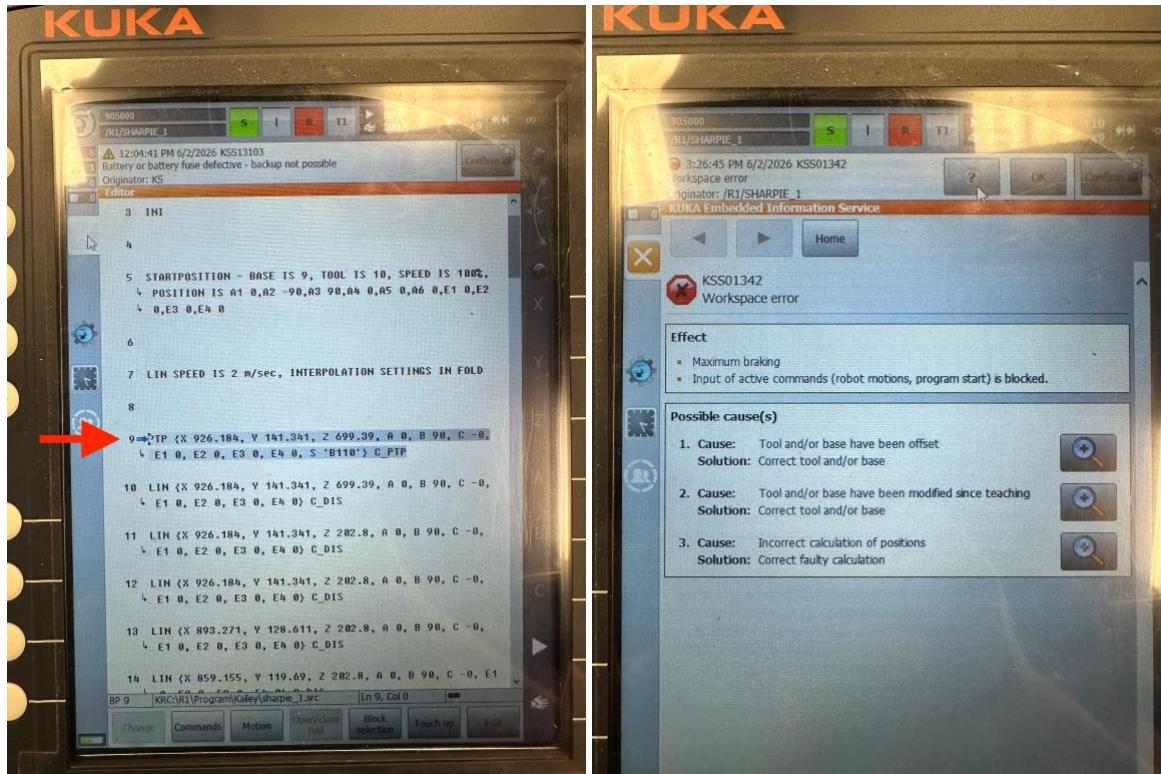
When running this code from PRC with tool axis B = -90, the robot still approaches incorrectly like this:



I therefore change the tool transformation values on the touch pendant (TP) again so that it matches the new KUKA PRC values with B = -90:



Running the program, the robot goes to the initial start/home position but stops on the next line of code (first PTP line) with a “Workspace error” and does not continue the program:



Summary:

The program **runs** when tool transformation value B=0 but **simulation is incorrect**.

The program **does not run** when tool transformation value B=-90 but **simulation is correct**.