




# — ARTIMINDS RPS CHEATSHEET —

This cheatsheet will tell you about the most commonly used keyboard shortcuts for **ArtiMinds RPS**. Note, that many shortcuts only work in the context of their respective area of functionality. If you have any questions while using ArtiMinds RPS, feel free to contact us at [support@artiminds.com](mailto:support@artiminds.com).




## LEGEND

 - Left Click     - Right Click     - Middle Click     - Scroll     - Move Mouse








## FREQUENTLY USED

<b>F1</b>	Opens a context specific online help topic
<b>F2</b>	Open <b>template</b> editor (name, description and color)
<b>F3</b>	Activate the <b>Interact Tool</b>
<b>F4</b>	Activate the <b>Point Tool</b>
<b>Ctrl + I</b>	Move selected TCP to selected Point and cycle through redundant inverse kinematics solutions
<b>Ctrl + </b>	Open a <b>hierarchical template</b> / open <b>all cases</b>
<b>Ctrl + F</b>	Search in <b>program</b>
<b>Ctrl + T</b>	Search for <b>template</b>
<b>Ctrl + Shift + T</b>	Search for <b>builder</b>
 + 	Panning in <b>3D view</b>
<b>Ctrl + H</b>	Open <b>wizard</b> Helper Tools






## GENERAL

 + 	Panning in 3D view
<b>Alt</b>	Toggle top menu
<b>Shift + </b>	Panning in 3D view
<b>Esc</b>	Stop <b>simulation</b>
<b>Alt + Arrows</b>	Arrows navigate through <b>top menu</b>
<b>Ctrl + H</b>	Open <b>wizard</b> Helper Tools
<b>F1</b>	Opens a context specific Online <b>help</b> topic
<b>Ctrl + N</b>	Open new project
<b>Ctrl + O</b>	Load project
<b>Ctrl + S</b>	Save project
<b>Ctrl + Shift + R</b>	<b>Splits</b> the compiled robot program and transfers it to the robot. For each top-level template a file will be created and copied.
<b>Ctrl + F</b>	Search in <b>program</b>
<b>Ctrl + T</b>	Search for <b>template</b>
<b>Ctrl + Shift + T</b>	Search for <b>builder</b>
<b>Ctrl + Shift + +</b>	Open gripper
<b>Ctrl + Shift + -</b>	Close gripper
<b>Ctrl + G</b>	Toggle planning group (manipulator / gripper)
<b>Ctrl + I</b>	Cycle through redundant inverse kinematics solution

## PROGRAM EDITOR

<b>Shift + </b>	Select multiple templates
<b>F2</b>	Open <b>template</b> editor (name, description and color)
<b>Ctrl + </b>	Open <b>all template cases</b>
<b>Del</b>	Delete all selected templates
<b>Ctrl +  [window]</b>	Pan view
<b>Ctrl + W</b>	Close current program editor tab (not available for main tab)
<b>Ctrl +  [Point input]</b>	Link the currently selected <b>3D point</b> to the clicked <b>input</b>
<b>Ctrl + C</b>	Copy selected template
<b>Ctrl + V</b>	Paste template at the end of the graph
<b>Ctrl + X</b>	Cut template
<b>Ctrl + A</b>	Select all templates in the program editor
<b>Ctrl + </b>	Zoom / scroll (depending on preference settings)
<b>Ctrl + D</b>	Duplicate selected template
 + 	Scroll
<b>Ctrl + Z</b>	Undo last action
<b>Ctrl + Shift + Z</b>	Redo last action



## CAD2PATH




 + 	Pan view
 + 	Rotate view
	Zoom
<b>Ctrl + S</b>	Save session
<b>Ctrl + O</b>	Open session
<b>Shift + Del</b>	Delete <b>unselected</b> curve segments
<b>Ctrl + +</b>	Starting from the selected curve, propagate the selection through best tangency
<b>Ctrl + Shift + +</b>	Select all curves connected to the current selection of curves
<b>Ctrl + P</b>	Select all curves in the plane which is defined by the current curve selection
<b>Ctrl + B</b>	Open <b>Blending Wizard</b>
<b>Ctrl + E</b>	Open <b>Curve Extend Wizard</b>
<b>F6</b>	Rotate view along the X axis
<b>F7</b>	Rotate view along the Y axis
<b>F8</b>	Rotate view along the Z axis

## WIZARD


**Ctrl + B** Uses the selected point for teaching in the currently open wizard (equal to selecting a point in the wizard dropdown )

## INTERACTIVE MODE


**Ctrl**  +  Move / rotate **TCP** by discrete steps of [x] mm or [x] degree. The value of [x] can be set in preferences: Settings → 3D view.

**Ctrl** +  Avoid collision with other objects while dragging the robot TCP  
**Ctrl + U** **Record** point  
 +  Zoom in 3D view




## POINT TOOL MODE

**Shift** +  **Select** multiple points  
**Ctrl** + **A** **Select** all points  
**Ctrl** + [Number] **Select** all points of group [Number]  
**Esc** **Deselect** all currently selected points  
**Del** **Delete** all selected points  
**Ctrl** + **R** **Rename** selected point  
**Ctrl** + **U** **Record** point  
**Ctrl** + **Shift** + **U** **Update** point  
**Ctrl** + **D** Toggle the **visibility** state of the currently selected points  
**Ctrl** + **L** Toggle the **lock state** of the currently selected points  
**Ctrl** + **M** **Move** point by offset  
**Ctrl** + **Shift** + **M** **Move** point to coordinates  
**T** Open menu: create template  
**Alt** Show mesh of CAD objects and stick points to edges  
**Alt** + **Shift** Show mesh of CAD objects, stick points to edges and keep orientation as close as possible  
  
**Ctrl** + **Z** **Undo** last action  
**Ctrl** + **Shift** + **Z** **Redo** last action  
**Ctrl** + **X** **Cut** point  
**Ctrl** + **C** **Copy** selected point  
**Ctrl** + **V** **Paste** point  
**D** Set **dynamic scaling** of text labels of points  
**S** Set **static scaling** of text labels of points  
**Alt** + **A** Set all positions and orientations of selected points like first selected  
**Alt** + **O** Set all orientations of selected points like first selected  
**Alt** + **P** Set all positions of selected points like first selected  
**Ctrl** + **Shift** + **A** Set interactive marker group mode to all selected point marker  
**Ctrl** + **Shift** + **F** Set interactive marker group mode to first selected point marker  
**Ctrl** + **Shift** + **N** Set interactive marker group mode to individual points  
**Shift** + **L** Toggle **visibility of the label modes** (display all, display none)  
**C** Toggle **child mode**

## POINTS AND PATHS – LIVE

**Home key** or  Return to the unzoomed graph  
**+** Redo zoom operation  
**-** Undo zoom operation

## POINTS AND PATHS – POINTS

 **x2** Edit the currently highlighted element in the points tab  
**Ctrl** +  Toggle the selection state of the clicked point  
**Del** Delete the currently selected points  
**Shift** +  Select all points between the first and last clicked row

## TROUBLESHOOTING

### 1. Going online / record button fails?

Verify your Network Setup! Are Computer and Robot in the same IP network (Settings > General / Settings > Robot)?

### 2. Simulation fails after xx.x% of the path

One or multiple waypoints are outside of the robot workspace.

- Verify that the position and orientation of all points is reachable. Check the Information tab to see if one of the robot joints reached its limits.
- Mainly for CAD2Path generated motions: Verify that the path does not contain a continuous motion across a workpiece corner that includes a TCP orientation change. Corners with small radius can lead to large motions of the robot arm that are usually not possible.

### 3. The simulation shows a “Trajectory Broken” warning and the robot jumps between two points?

Verify that you have a continuous State-Connection between all templates.

### 4. The robot does not move to home prior to an execution?

Check if the Home Position is reachable and whether or not the “Start at Home” checkbox in the Home Position widget is activated.

### 5. The robot applies too much force during a series of force-controlled templates

Check the Bias connection between templates. If the Bias in-/outputs are not connected, each template will add its force constraints to the already applied force.

## MY NOTES

---

---

---

---

---

---

---

---

---

---