

Notice of Addition of New Conveyor Tracking Order

■ Issued
February 2026

■ Applicable Model
MELFA FR series , MELFA CR series and MELFA ASSISTA series

We would like to express our gratitude for your patronage of MELFA, a Mitsubishi Electric industrial robot. From software version E4, new instructions have been added for conveyor tracking functions using vision sensors other than MELSENSOR.

We are pleased to inform you of the changes below.

1. Contents

New instructions for conveyor tracking function have been added since software version E4. For details, refer to the Tracking Function Instruction Manual.

Item	After Release	Pre-Release
Software Version	E4 version	E4 or earlier
corresponding command	TrkTrg TrkSigWt	TrkTrg -
	(MELSENSOR)(*1) Cognex Vision Sensors	(MELSENSOR) (*1) Cognex Vision Sensors
corresponding vision sensor	Robot can trigger images, Vision sensor capable of outputting output signal to robot when image is captured	-

(*1) Production was discontinued in July 2025.

The function of the new instruction [TrkSigWt] is explained.

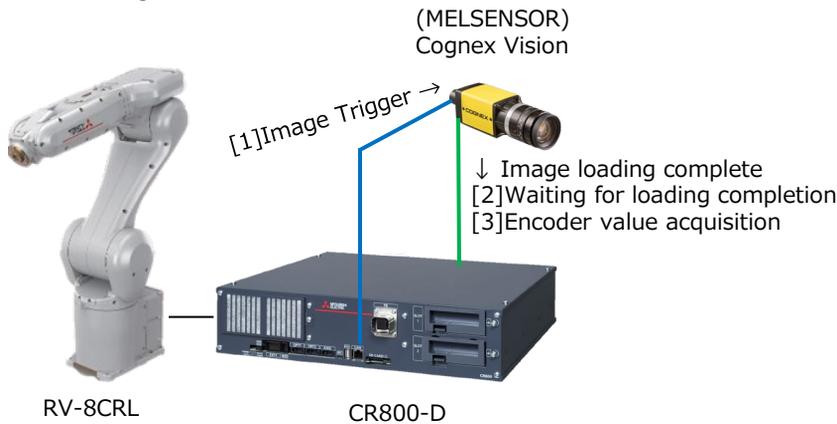
command	Type	Function
TrkSigWt Acquisition of encoder value by external signal input	high speed and precision Tracking	Acquires the encoder value at the moment when the imaging completion signal sent from the vision sensor is received at the specified SKIP input. Since imaging is completed and the encoder value is acquired by one command, there is no variation in the time until the encoder value is acquired, and the tracking operation is stable.

2 Features of the command

Accuracy is not degraded even with other company's sensors. Minimize system migration losses with the new TrkSigWt command.

Deterioration in accuracy due to the introduction of vision sensors made by other companies poses a major risk of reducing production efficiency. With the introduction of the new command "TrkSigWt," encoder values at the time of image capture can be obtained directly, and a high-precision tracking system can be reconstructed.

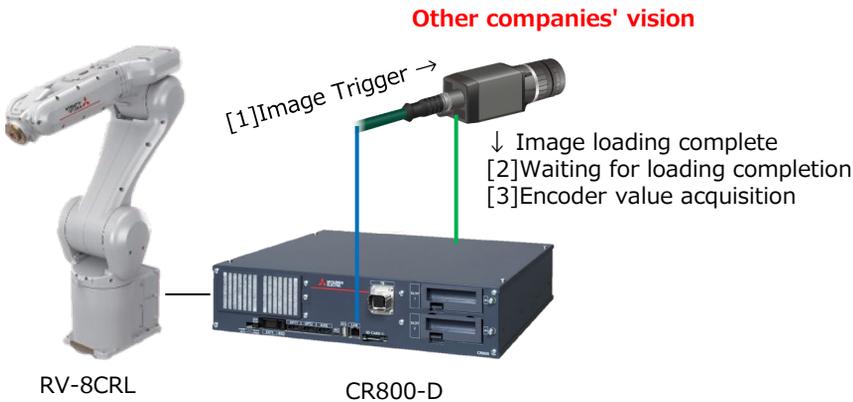
■For the TrkTrg command



```
[Robot Program]
NvOpen "COM2:" As #1
Wait M_NvOpen(1)=1
NvLoad #1, "TEST"
TrkTrg #1, 2, MEnc1#
```

TrkTrg command [1] - [3] and at the time of image capture, Get the encoder value Improved tracking accuracy.

■Print→M_In→M_Enc



```
[Robot Program]
Open "COM2:" As #1
Wait M_Open(1)=1
Print #1, "Go"
Wait M_In(801)=M_On
MEnc# = M_Enc(1)
```

[1] - [3] described on the left are executed with the above three lines.

■For TrkSigWt

```
[Robot Program]
Open "COM2:" As #1
Wait M_Open(1)=1
Print #1, "Go"
TrkSigWait 2, MEnc#
Input #1, CAns$
```

TrkSigWt executes [2] - [3] above

[Issue]

Error in tracking accuracy occurs in 3-line execution.



[Resolve]

Since it is possible to acquire an encoder when capturing an image, Tracking accuracy is determined by the (MELSENSOR) and Equivalent to using Cognex vision.