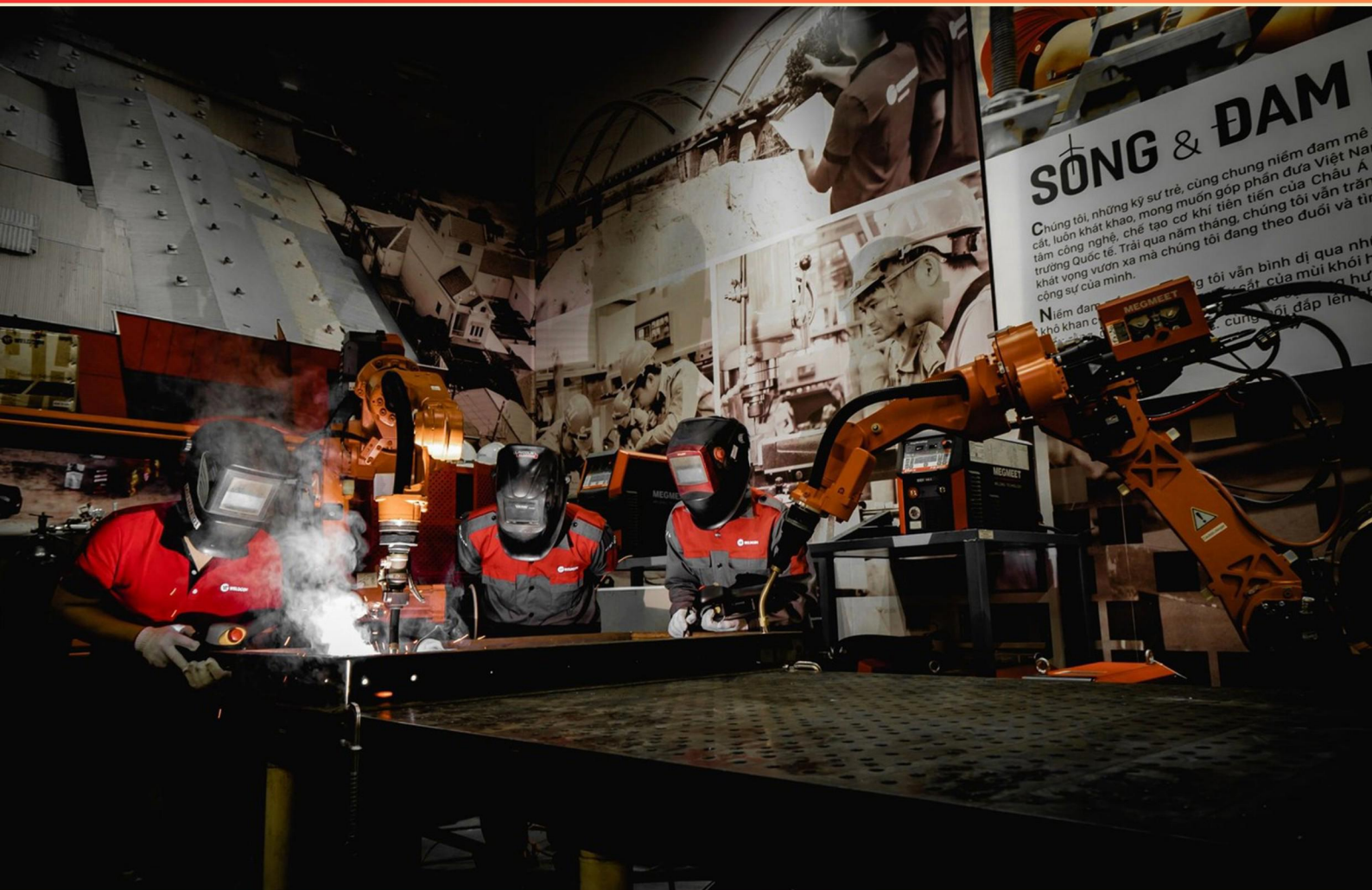


NTA FANUC TEST 2 – TEACH PENDANT, ALARMS, JOGGING AND INITIAL SETUP PRACTICE TEST (SAMPLE)

STUDY GUIDE



SAMPLE STUDY GUIDE WITH LIMITED QUESTIONS

VISIT US ONLINE FOR
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Introduction

Preparing for a certification exam can feel overwhelming, but with the right tools, it becomes an opportunity to build confidence, sharpen your skills, and move one step closer to your goals. At Examzify, we believe that effective exam preparation isn't just about memorization, it's about understanding the material, identifying knowledge gaps, and building the test-taking strategies that lead to success.

This guide was designed to help you do exactly that.

Whether you're preparing for a licensing exam, professional certification, or entry-level qualification, this book offers structured practice to reinforce key concepts. You'll find a wide range of multiple-choice questions, each followed by clear explanations to help you understand not just the right answer, but why it's correct.

The content in this guide is based on real-world exam objectives and aligned with the types of questions and topics commonly found on official tests. It's ideal for learners who want to:

- Practice answering questions under realistic conditions,
- Improve accuracy and speed,
- Review explanations to strengthen weak areas, and
- Approach the exam with greater confidence.

We recommend using this book not as a stand-alone study tool, but alongside other resources like flashcards, textbooks, or hands-on training. For best results, we recommend working through each question, reflecting on the explanation provided, and revisiting the topics that challenge you most.

Remember: successful test preparation isn't about getting every question right the first time, it's about learning from your mistakes and improving over time. Stay focused, trust the process, and know that every page you turn brings you closer to success.

Let's begin.

How to Use This Guide

This guide is designed to help you study more effectively and approach your exam with confidence. Whether you're reviewing for the first time or doing a final refresh, here's how to get the most out of your Examzify study guide:

1. Start with a Diagnostic Review

Skim through the questions to get a sense of what you know and what you need to focus on. Your goal is to identify knowledge gaps early.

2. Study in Short, Focused Sessions

Break your study time into manageable blocks (e.g. 30 – 45 minutes). Review a handful of questions, reflect on the explanations.

3. Learn from the Explanations

After answering a question, always read the explanation, even if you got it right. It reinforces key points, corrects misunderstandings, and teaches subtle distinctions between similar answers.

4. Track Your Progress

Use bookmarks or notes (if reading digitally) to mark difficult questions. Revisit these regularly and track improvements over time.

5. Simulate the Real Exam

Once you're comfortable, try taking a full set of questions without pausing. Set a timer and simulate test-day conditions to build confidence and time management skills.

6. Repeat and Review

Don't just study once, repetition builds retention. Re-attempt questions after a few days and revisit explanations to reinforce learning. Pair this guide with other Examzify tools like flashcards, and digital practice tests to strengthen your preparation across formats.

There's no single right way to study, but consistent, thoughtful effort always wins. Use this guide flexibly, adapt the tips above to fit your pace and learning style. You've got this!

Questions

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1. What are the two main considerations when manually moving the robot?
 - A. Weight and Payload
 - B. Tool orientation and Safety
 - C. Jog Speed and Coordinate System
 - D. Path length and Temperature
2. Which of the following is a valid Key-Sub-Group on the teach pendant?
 - A. Robot motion keys
 - B. Program status lines
 - C. Alarm indicators
 - D. Speed controls
3. Which pendant key is used for navigation?
 - A. MENU
 - B. DATA
 - C. EDIT
 - D. FCTN
4. X+ moves the end of the arm straight forward.
 - A. Z+
 - B. X+
 - C. Y-
 - D. X-
5. Releasing the DEADMAN switch will cause a controller fault that must be reset before robot motion can be initiated.
 - A. False
 - B. It depends on safety configuration
 - C. Must be reset after fault
 - D. True

6. If you want to move the tool in X/Y/Z world coordinates, which jog mode would you use?
- A. Cartesian Jog.
 - B. Joint Jog.
 - C. Tool Jog.
 - D. Axis Jog.
7. What is the difference between PTP (point-to-point) and LIN (linear) motion?
- A. PTP moves to a target pose; LIN moves along a straight line with constant orientation.
 - B. The two motions are identical.
 - C. LIN moves along a straight line with constant orientation; PTP moves to a target pose.
 - D. PTP moves to a target pose; LIN moves along a straight line to the target with constant orientation.
8. Y+ moves the end of the arm laterally to the left.
- A. X+
 - B. Z+
 - C. Y+
 - D. Y-
9. The term 'hard stops' refers to what concept?
- A. Software limit values
 - B. Visual cues
 - C. Temporary stops
 - D. Physical barriers
10. Which information is listed in the Motion Information section?
- A. Coordinate system, group, and subgroup
 - B. Speed override
 - C. Alarm status line
 - D. Program name

Answers

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1. C
2. A
3. A
4. B
5. D
6. A
7. D
8. C
9. D
10. A

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Explanations

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1. What are the two main considerations when manually moving the robot?

- A. Weight and Payload
- B. Tool orientation and Safety
- C. Jog Speed and Coordinate System**
- D. Path length and Temperature

When you manually jog a robot, two things matter most: how fast you move it and which reference frame you're using for the move. Jog speed controls how quickly the robot's joints or end effector travel during manual motion, which directly affects control, precision, and safety in real-time positioning. The coordinate system defines the frame of reference for the jog commands (base/world, tool, or user coordinates), so it determines the direction and plane of movement and how your inputs map to actual motion. Weight and payload aren't changed during jogging, and while tool orientation and safety are important considerations, they aren't the two primary controls for manual movement. Path length and temperature aren't factors in the basic act of jogging.

2. Which of the following is a valid Key-Sub-Group on the teach pendant?

- A. Robot motion keys**
- B. Program status lines
- C. Alarm indicators
- D. Speed controls

Key-Sub-Group on the teach pendant refers to a dedicated set of keys organized for a specific, quick-access task. The group focused on driving the robot's actions is the robot motion keys, because these keys are the ones you use to jog, move, or otherwise command the robot's motion directly from the pendant. Other items listed—program status lines, alarm indicators, and speed controls—are parts of the display or separate control elements, not a key sub-group you assign to perform motion actions. So the robot motion keys are the valid sub-group for this purpose.

3. Which pendant key is used for navigation?

- A. MENU**
- B. DATA
- C. EDIT
- D. FCTN

Navigation on the pendant is done with the MENU key. Pressing MENU opens the system menus so you can move through screens and options, then use the directional controls to highlight what you want and EXE/ENTER to enter it. This is how you move around the interface and pick tasks. The DATA key is for entering and viewing values, EDIT is for modifying programs or data, and FCTN provides access to specialized functions. So for getting around the interface and choosing what to do next, the MENU key is the one to use.

4. X+ moves the end of the arm straight forward.

- A. Z+
- B. X+**
- C. Y-
- D. X-

In this robot teaching context, movement is defined by a Cartesian coordinate system with three axes: X, Y, and Z. The positive direction of the X axis is set to point forward along the arm's reach. So when you command X+, the end effector moves straight ahead along that forward line, with no change in height or sideways position. If you used Z+, you'd move the end effector upward; X- would move it backward along the same line; and Y- would shift it sideways (in the direction opposite of Y+). The key idea is that moving along the X axis in the positive direction corresponds to forward motion, which is why X+ is the correct choice for moving straight forward.

5. Releasing the DEADMAN switch will cause a controller fault that must be reset before robot motion can be initiated.

- A. False
- B. It depends on safety configuration
- C. Must be reset after fault
- D. True**

Releasing the Deadman switch creates a safety fault in the controller by signaling that the operator is no longer actively controlling the robot. The safety logic immediately stops motion and records a fault state to prevent any unintended movement. To clear this condition and allow motion again, a reset (and any required fault acknowledgment) is needed. After the reset, you'll typically re-establish control—often by re-engaging the safety features and then enabling jog/run—before the robot can move again. This behavior is by design to ensure the operator is present and attentive before resuming operation.

6. If you want to move the tool in X/Y/Z world coordinates, which jog mode would you use?

- A. Cartesian Jog.**
- B. Joint Jog.
- C. Tool Jog.
- D. Axis Jog.

Moving in the global X, Y, and Z directions uses the Cartesian (world) frame, so the end effector travels along the fixed world axes regardless of how the arm is oriented. Cartesian jog is designed for this, mapping movement to the world/base coordinate system. If you push along X, it goes along the world X axis, not along the tool's current direction. Tool jog, by contrast, follows the tool's own coordinate system, so its X/Y/Z directions rotate with the tool. That can cause movements that don't align with the global axes, which isn't what you want when you need a world-aligned move. Axis jog moves movement on one axis at a time, which is not the same as commanding a straight move along the global X/Y/Z axes. Joint jog operates in joint space (adjusts individual joints), again not guaranteeing a world-aligned path. So for moving the tool in world coordinates, Cartesian jog is the best choice.

7. What is the difference between PTP (point-to-point) and LIN (linear) motion?

- A. PTP moves to a target pose; LIN moves along a straight line with constant orientation.
- B. The two motions are identical.
- C. LIN moves along a straight line with constant orientation; PTP moves to a target pose.
- D. PTP moves to a target pose; LIN moves along a straight line to the target with constant orientation.**

PTP and LIN differ in how they plan the motion and what stays constant during the move. With a point-to-point move, you specify a final pose (the position and orientation you want the end effector to reach), and the robot uses joint interpolation to get there. The path in Cartesian space isn't constrained to be a straight line, and the orientation can change along the way; only the end pose is guaranteed. With a linear move, the robot follows a straight line in Cartesian space from the start to the target position, and the tool's orientation is kept constant during the travel. This means the motion is straight and the orientation does not ramp or flip mid-path, only reaching the desired pose at the end. So, describing it as PTP moves to a target pose and LIN moves along a straight line to the target with constant orientation cleanly captures the distinct behavior of each type of motion.

8. Y+ moves the end of the arm laterally to the left.

- A. X+
- B. Z+
- C. Y+**
- D. Y-

Understanding how axis directions map to the end-effector motion is being tested. The Y axis controls lateral (side-to-side) movement, and its positive direction is left. So commanding Y+ makes the end of the arm move to the left. That's why this option describes the motion correctly. Movements along the X axis would be forward/back, and along the Z axis would be up/down; Y- would move to the right, the opposite of left.

9. The term 'hard stops' refers to what concept?

- A. Software limit values
- B. Visual cues
- C. Temporary stops
- D. Physical barriers**

Hard stops are physical barriers built into the machine that physically limit motion and stop travel when reached. They provide a concrete, mechanical boundary: once an axis hits the stop, movement is blocked regardless of software commands. This is different from soft limits, which are constraints defined in the controller software and may be bypassed or depend on software logic, not a physical barrier. Visual cues are just indicators or warnings without enforcing movement, and temporary stops aren't a standard mechanism to imply a permanent physical limit. The defining idea is that hard stops are actual mechanical barriers that stop movement.

10. Which information is listed in the Motion Information section?

A. Coordinate system, group, and subgroup

B. Speed override

C. Alarm status line

D. Program name

Motion Information is about how movement commands are interpreted. It shows the coordinate system currently in use (such as base/world, user, or tool) and the motion group and subgroup selected for the move. These elements define the reference frame and which axes or joints participate in the motion, so listing the coordinate system along with the group and subgroup is exactly what this section provides. Speed override, alarm status line, and program name come from other areas: speed override is managed in the drive/override controls, the alarm status appears in the Alarms area, and the program name is shown in the Program or File Information area.

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Next Steps

Congratulations on reaching the final section of this guide. You've taken a meaningful step toward passing your certification exam and advancing your career.

As you continue preparing, remember that consistent practice, review, and self-reflection are key to success. Make time to revisit difficult topics, simulate exam conditions, and track your progress along the way.

If you need help, have suggestions, or want to share feedback, we'd love to hear from you. Reach out to our team at hello@examzify.com.

Or visit your dedicated course page for more study tools and resources:

<https://ntafanuc2.examzify.com>

We wish you the very best on your exam journey. You've got this!

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