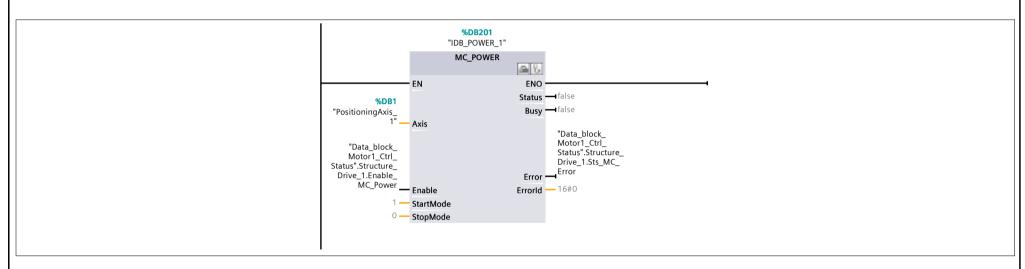
|--|--|

## FC\_Drive\_1 [FC100]

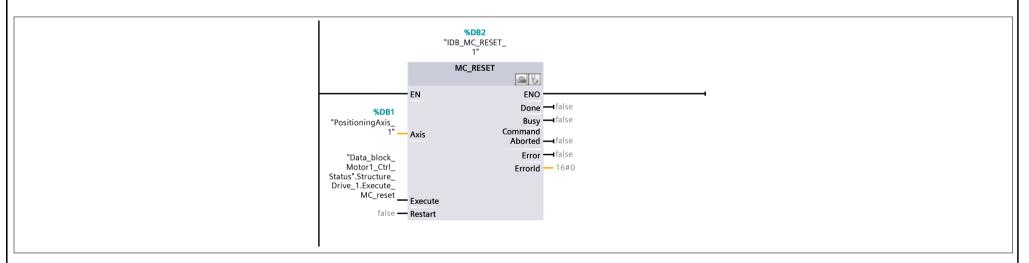
FC_Drive_1 Properties									
General									
Name	FC_Drive_1	Number	100	Туре	FC	Language	LAD		
Numbering	Manual								
Information									
Title		Author		Comment		Family			
Version	0.1	User-defined ID							

Name	Data type	Default value	Comment
Input			
Output			
InOut			
Temp			
Constant			
▼ Return			
FC_Drive_1	Void		

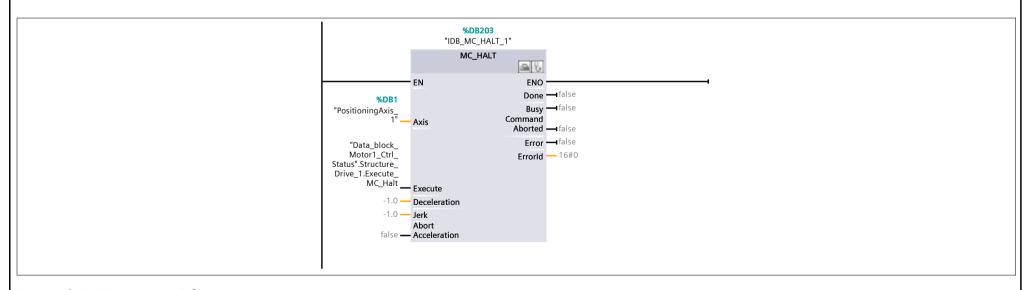
Network 1: Motor\_1\_MC\_Power



Network 2: Motor\_1\_MC\_Reset



Network 3: Motor\_1\_MC\_Halt

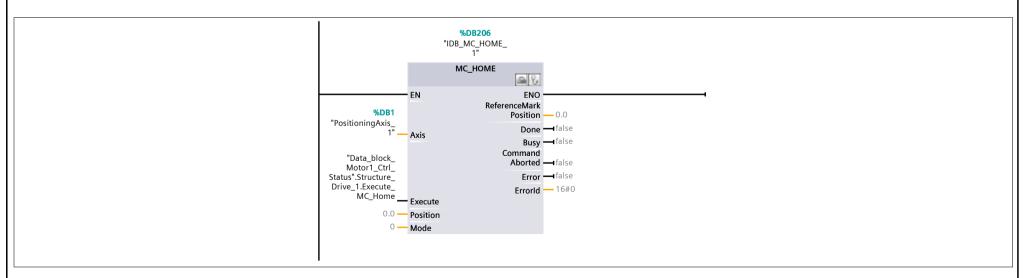


Network 4: Motor\_1\_MC\_jog

Totally Integrated **Automation Portal** %DB204 "IDB\_MC\_ MOVEJOG\_1" MC\_MOVEJOG ું હ ENO InVelocity —false %DB1 "PositioningAxis\_ 1" — **Busy →**false Command
Aborted —false "Data\_block\_ Motor1\_Ctrl\_ Status".Structure\_ Drive\_1.Execute\_ Jog\_Forward \_ Error → false Errorld — 16#0 JogForward "Data\_block\_ Motor1\_Ctrl\_ Status".Structure\_ Drive\_1.Execute\_ Jog\_Backward \_\_ JogBackward "Data\_block\_ Motor1\_Ctrl\_ Status".Structure\_ Drive\_1.Sp\_lr\_ Velocity\_\_ Velocity -1.0 — Acceleration -1.0 — Deceleration -1.0 — **Jerk** "Data\_block\_ Motor1\_Ctrl\_ Status".Structure\_ Drive\_1.Enable\_ Postition\_Control \_ Position
Controlled Network 5: Motor\_1\_MoveVelocity **%DB205**"IDB\_MC\_
MOVEVELOCITY\_
1" MC\_MOVEVELOCITY **₽** 8 ΕN ENO InVelocity — false %DB1 "PositioningAxis\_ 1" — **Busy →**false Command Aborted → false Axis 0 — Execute Error → false 0.0 — Velocity Errorld — 16#0 -1.0 — Acceleration -1.0 — Deceleration -1.0 — **Jerk** 0 — Direction false — Current

"Data\_block\_ Motor1\_Ctrl\_ Status".Structure\_ Drive\_1.Enable\_ Postition\_Control \_ Position Controlled

Network 6: Motor\_1\_Home



Network 7: Motor\_1\_Stop

Totally Integrated **Automation Portal %DB207**"IDB\_MC\_STOP\_1" MC\_STOP <u>₽</u>8 ENO Done —false "PositioningAxis\_ 1" — Axis Busy —false Command
Aborted —Ifalse "Data\_block\_ Motor1\_Ctrl\_ Status".Structure\_ Drive\_1.Execute\_ MC\_Stop\_ Error —false Errorld — 16#0 Execute 0 **— Mode** -1.0 — Deceleration -1.0 — Jerk Abort
false — Acceleration **Network 8: Motor 1 actual velocity** MOVE "PositioningAxis\_ 1".ActualVelocity \_\_ "Data\_block\_ Motor1\_Ctrl\_ Status".Structure\_ Drive\_1.lr\_Actual\_ Velocity 😃 OUT1 -**Network 9: Motor 1 Actual Torque** MOVE EN - ENO "PositioningAxis\_ 1".StatusTorque Data.Actual Torque\_ "Data\_block\_ Motor1\_Ctrl\_ Status".Structure\_ Drive\_1.Lr\_ \_\_Actual\_Torque 😃 OUT1 -**Network 10: Motor 1 Torque Range** "IDB\_MC\_ TORQUERANGE\_1" MC\_TORQUERANGE <u>₽</u> 6 ENO Busy → false %DB1 "PositioningAxis\_ 1" — Axis Error → false Errorld — 16#0 "Data\_block\_ Motor1\_Ctrl\_ Status".Structure\_ Drive\_1.Enable\_ Torque\_Reduction\_ - Enable "Data\_block\_ Motor1\_Ctrl\_ Status".Structure\_ Drive\_1.Sp\_Ir\_ Torque\_Upper\_ Limit\_\_ UpperLimit "Data\_block\_ Motor1\_Ctrl\_ Status".Structure\_ Drive\_1.Sp\_lr\_ Torque\_Lower\_ Limit LowerLimit Network 11: Read Velocity Motor 1 %FC1 "Split" ΕN ENO "dbHolding Registers".Motor Registers[9] "Data\_block\_ Motor1\_Ctrl\_ Status".Structure\_ Drive\_1.lr\_Actual\_ Velocity\_ High "dbHolding Registers".Motor Registers[10] Network 12: Turn on Motor 1

