

Program File List

Name	Number	Type	Rungs	Debug	Bytes
[SYSTEM]	0	SYS	0	No	0
	1	SYS	0	No	0
MAIN_PROG	2	LADDER	7	No	71
UTILITY	3	LADDER	10	No	294
INSPECTION	4	LADDER	19	No	841
IO_COUNTER	5	LADDER	12	No	273
REJ_TIMERS	9	LADDER	235	No	10613
IMS_SCAN	10	LADDER	1	No	3
HSC0	11	LADDER	4	No	67
EII_COUNTS	12	LADDER	1	No	3
STI_SPEED	13	LADDER	6	No	115

TensorVisionZ

New MicroLogix1100 Master Program
Timed or with Encoder

PLC IO:

If using encoder: I1.0/00 - 03 = HSC INPUT (from Encoder)

Otherwise

I:0/0 = Encoder Pulse	O:0/0 = Rejector Output (pulse duration via timer)
I:0/1 = Inspect Trigger	O:0/1 = Linestop Output
I:0/2 = Reject Trigger	O:0/2 = Red Lamp
I:0/3 = Reject Confirm	O:0/3 = Green Lamp
I:0/4 = Pass1	O:0/4 = Power Cycle Cameras
I:0/5 = Fail1A	O:0/5 = not used
I:0/6 = Fail1B	O:0/6 = not used
I:0/7 = Pass2	O:0/7 = not used
I:0/8 = Fail2A	
i:0/9 = Fail2B	

PLC Registers accessed by C#-based operator GUI/HMI

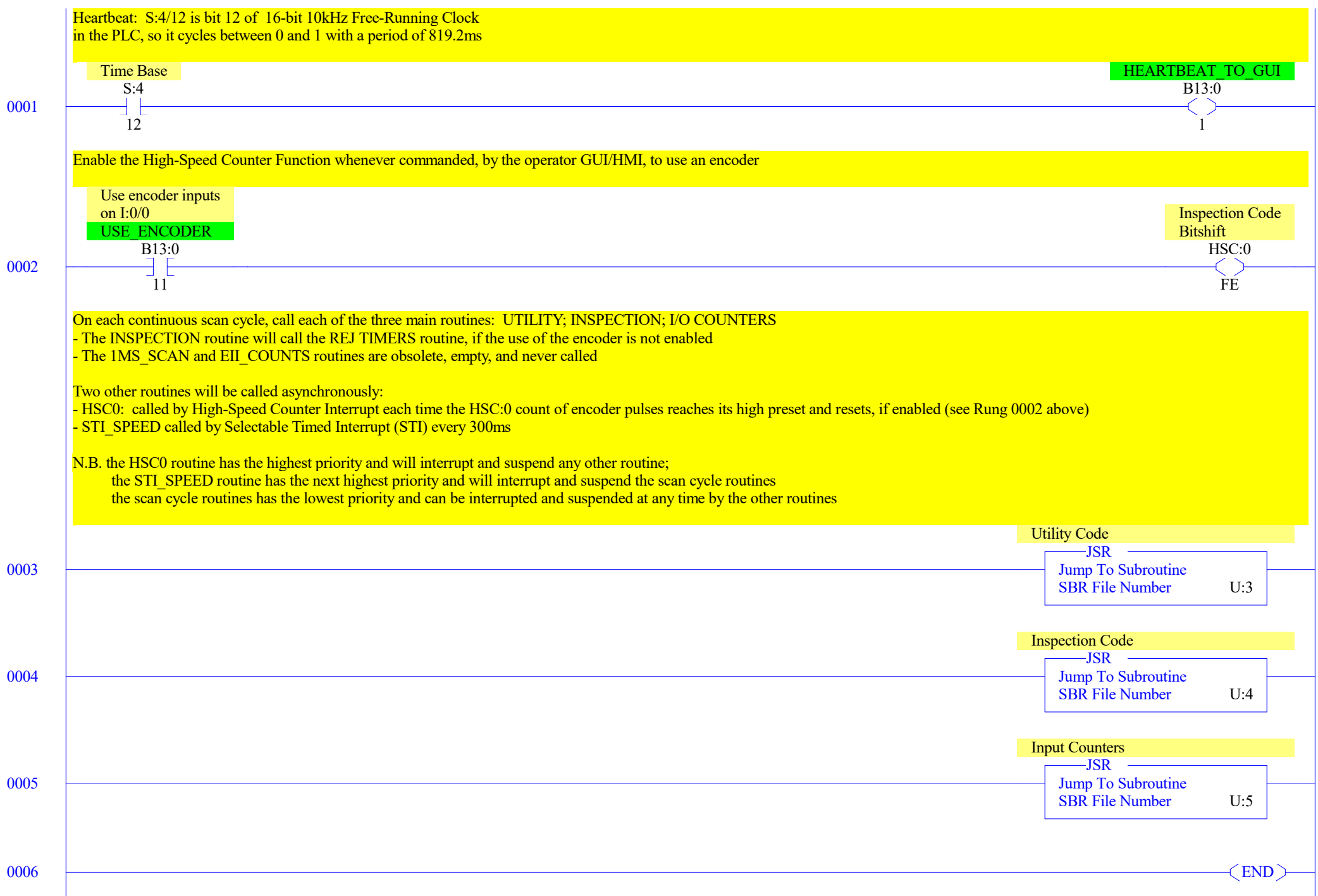
COMMENT IS OUT OF DATE (UPDATE!)

B13:0/0 = Heartbeat indication. from GUI (not implemented)
 B13:0/1 = Heartbeat indication. to GUI
 B13:0/2 = Rejection Mode ON/OFF command. from GUI
 B13:0/3 = Red Lamp Test Command. from GUI; oneshot
 B13:0/4 = Green Lamp Test Command. from GUI; oneshot
 B13:0/5 = Reject Pusher Solenoid Test Command. from GUI; oneshot
 B13:0/6 = Linestop Test Command. from GUI; oneshot; simulates Linestop Active Command for 5s
 B13:0/7 = Linestop Active Command, from GUI
 B13:0/10 = Use Reject Trigger, setting. from GUI (not implemented in this version, as of 2023-07-07)
 B13:0/11 = Use Encoder-based location model, from GUI; if 0, use timing to model movement of cans along conveyor
 B13:0/12 = Reset Counter Command, from GUI; oneshot
 B13:0/15 = Reject Can Now Command, to GUI; 1 => encoder -based model detects failed can is at pusher location
 N17:0 = High Speed Reject Offset, from GUI
 N17:1 = Low Speed Reject Offset, from GUI !!!!!value must be larger than High Speed Reject Offset!!!!!!???is that still true???
 N17:2 = Actual Offset, to GUI; Calculated in PLC based on line speed)
 N17:5 = Rejection Pulse Duration (in milliseconds), from GUI
 N7:11 = Encoder Hi Preset, from GUI; number of encoder counts that triggers the High-Speed Counter interrupt to call routine HSC0
 F18:* = Counters' values, to GUI
 C5:* .ACC = Counters' values, to GUI
 C15:* .ACC = Counters' values, to GUI
 ST19:* = Version and other information as strings, to GUI

comment anchor

B3:0

U
0



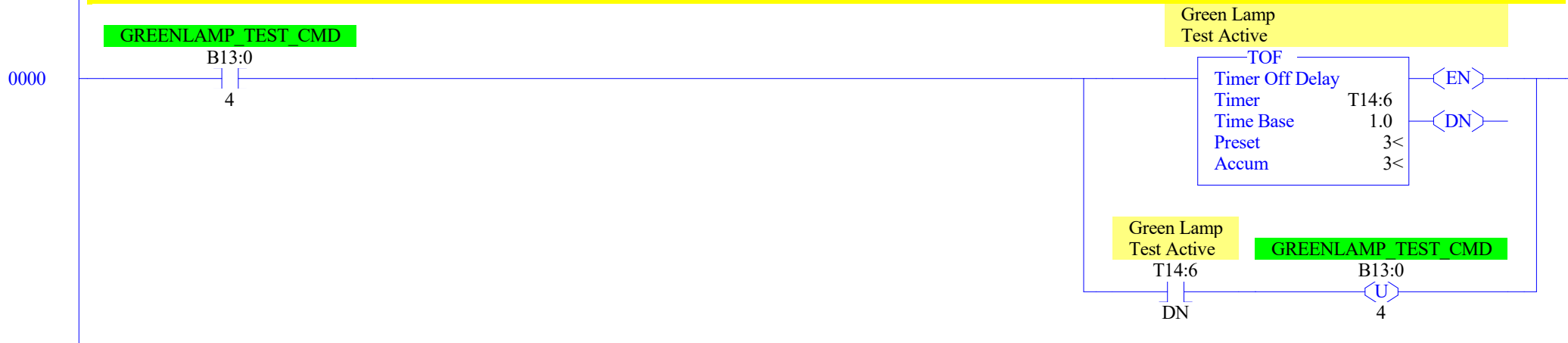
This Program File routine, LAD 3 UTILITY, is unconditionally called from the main routine (LAD 2 MAIN_PROG) once per continuous scan cycle

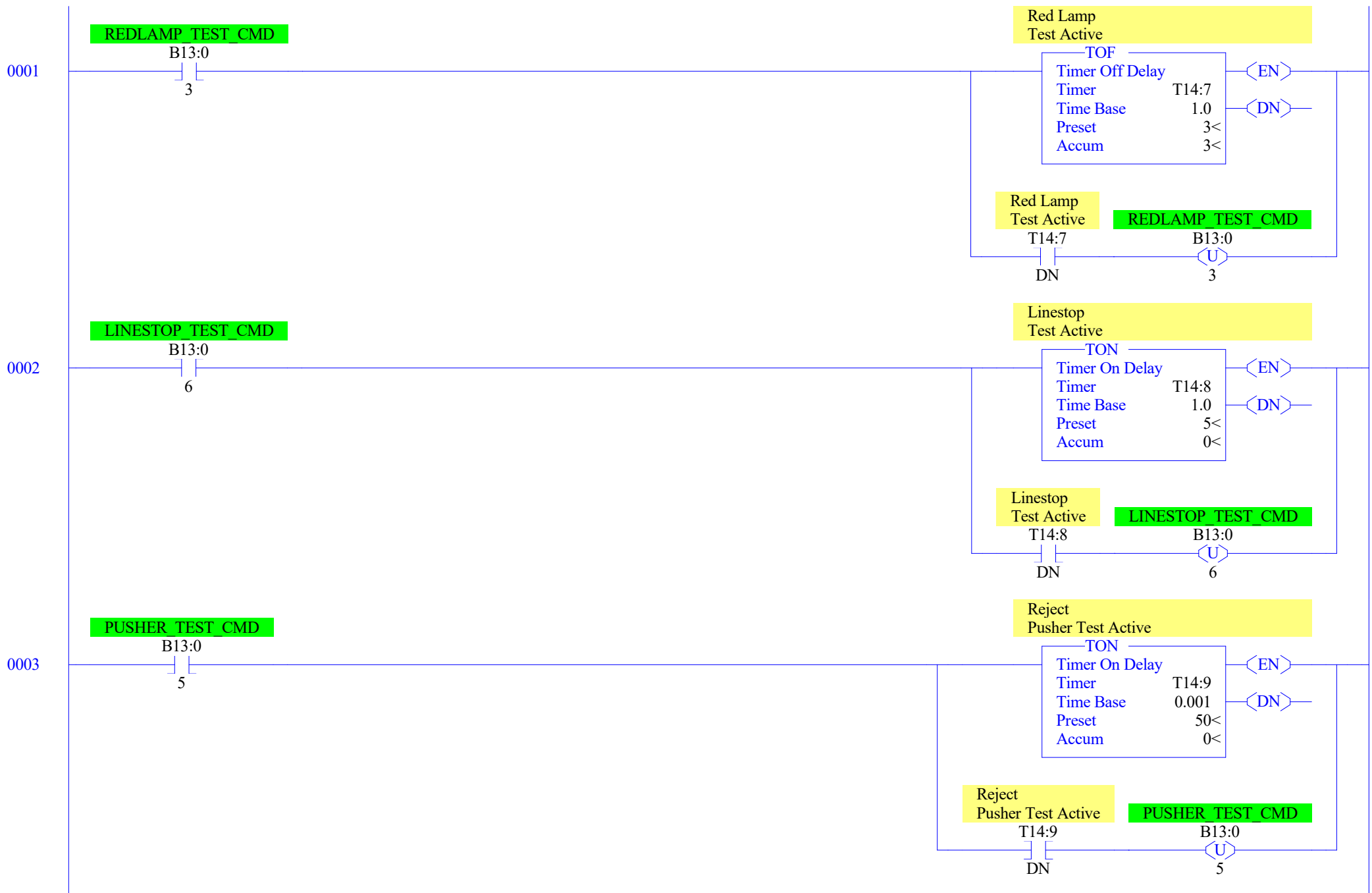
- Respond to test command bits (see below)
- Respond to internal SIM_REJECT bit
- Clamp the actual offset value, then load it as a timer preset
- Enforce a lower limit of 500ms for the preset of a timer that does nothing

Rungs 000-0003: respond to test command bits (see below)

Timers' /TT bits are used as pulse stretchers for test command bits to test pieces of the system: green lamp; red lamp; line stop; reject pusher solenoid.

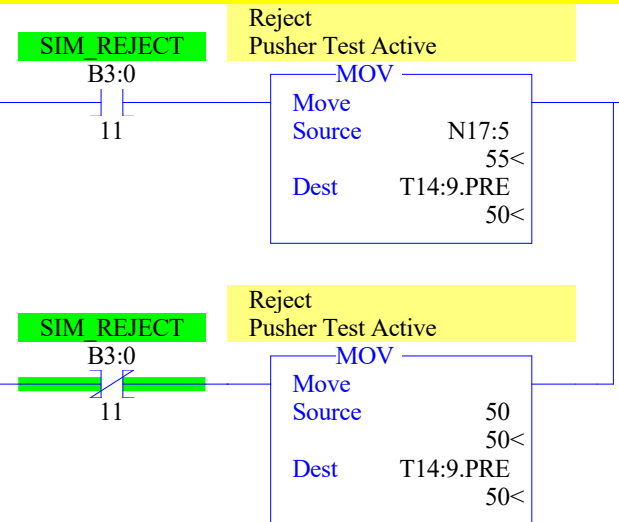
N.B. the test bits are from the operator GUI/HMI, which uses the Set-and-Forget pattern i.e. the GUI writes a 1 ("Set") as the value of the bit on this PLC, and then "Forgets" about it. The PLC detects the bit value is 1 and in response does two things: (i) resets the bit value to 0 so it can detect the next time the value becomes 1 on a future scan cycle; (ii) "stretches" the command by starting a Timer ON-delay (TON), the /TT bit of which will drive the commanded action and have a value of 1 for some duration.





0004

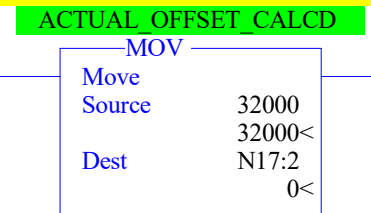
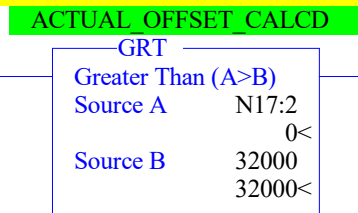
Respond to internal SIM_REJECT bit, which selects the value to use for the reject pusher solenoid duration



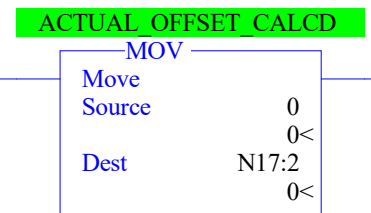
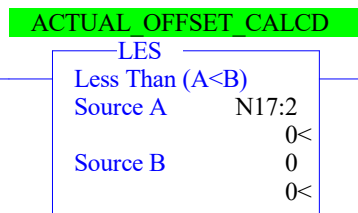
Clamp the actual offset value, then load it as a timer preset

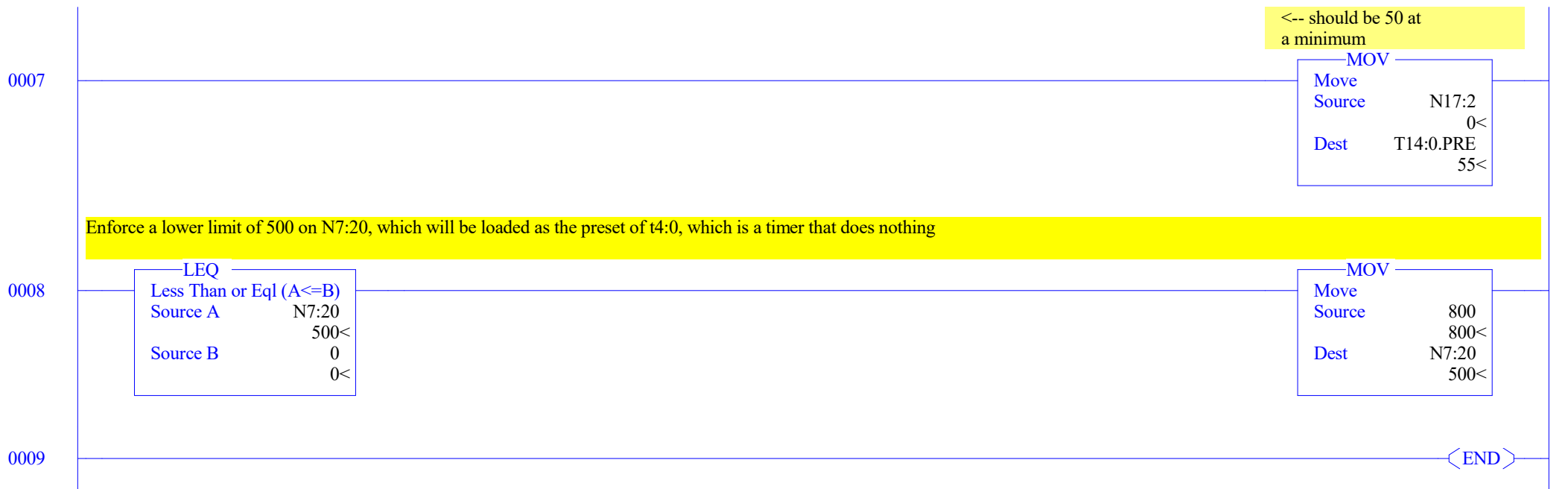
TODO: determine if these rungs are unnecessary, as routine LAD 4 INSPECTION, Rung 8 may overwrite the actual offset value in ACTUAL_OFFSET_CALCD N17:2 with the rejector (reject pusher) duration

0005



0006





Can inspection logic - control output per camera and operator HMI/GUI inputs

This Program File routine, LAD 4 INSPECTION is unconditionally called from the main routine (LAD 2 MAIN_PROG) once per continuous scan cycle

Rung 0000: Not sure what to do with USE_REJECT_TRIGGER yet

These bits USE_REJECT_TRIGGER (B12:0/10; from HMI/GUI) and INSPECTING (B13:5/1) are not used anywhere else in this program as of 2023-07-07.

Wait for
REJECT_TRIGGER to
REJECT

USE_REJECT_TRIGGER

B13:0

10

INSPECTING

B13:5

1

Use encoder inputs
on I:0/0

USE_ENCODER

B13:0

11

BitShift Left 1
Control Register

MOV

Move	Source	2000
		2000<
Dest	R16:0.LEN	2000<

0000

0001

Update High-Speed Counter presets, if encoder is to be used and a new preset (ENCODER_HIPRESET_SP) has been provided by the operator GUI/HMI.

N.B. evaluating/executing the HSL instruction and transitioning /SP bit from 0 to 1 may be redundant

0002

Use encoder inputs
on I:0/0

USE ENCODER

B13:0

11

ENCODER_HIPRESET_SP

NEQ

Not Equal

Source A

N17:11

30<

Source B

HSC:0.HIP

30<

HSL

High Speed Counter Load

HSC Number

HSC0

High Preset

N17:11

Low Preset

N17:11

Output High Source

0

Output Low Source

0

Inspection Code
Bitshift

HSC:0

SP

0003

Use encoder inputs
on I:0/0

USE_ENCODER

B13:0

11

REG1

DIV

Divide

Source A F18:10
0.0<

Source B F18:18
710.0<

Dest F18:31
0.0<

REG2

SUB

Subtract

Source A N17:1
250<

Source B N17:0
1000<

Dest F18:32
-750.0<

REG3

MUL

Multiply

Source A F18:32
-750.0<

Source B F18:31
0.0<

Dest F18:33
0.0<

CALCD_OFFSET

SUB

Subtract

Source A N17:1
250<

Source B F18:33
0.0<

Dest F18:12
250.0<

0004

Use encoder inputs
on I:0/0

USE_ENCODER

B13:0

11

CALCD_OFFSET

LIM

Limit Test

Low Lim

N17:0

1000<

Test

F18:12

250.0<

High Lim

N17:1

250<

ACTUAL_OFFSET_CALCD

MOV

Move

Source

F18:12

250.0<

Dest

N17:2

0<

Use encoder inputs
on I:0/0

USE_ENCODER

B13:0

11

ACTUAL_OFFSET_CALCD

CLR

Clear

Dest

N17:2

0<

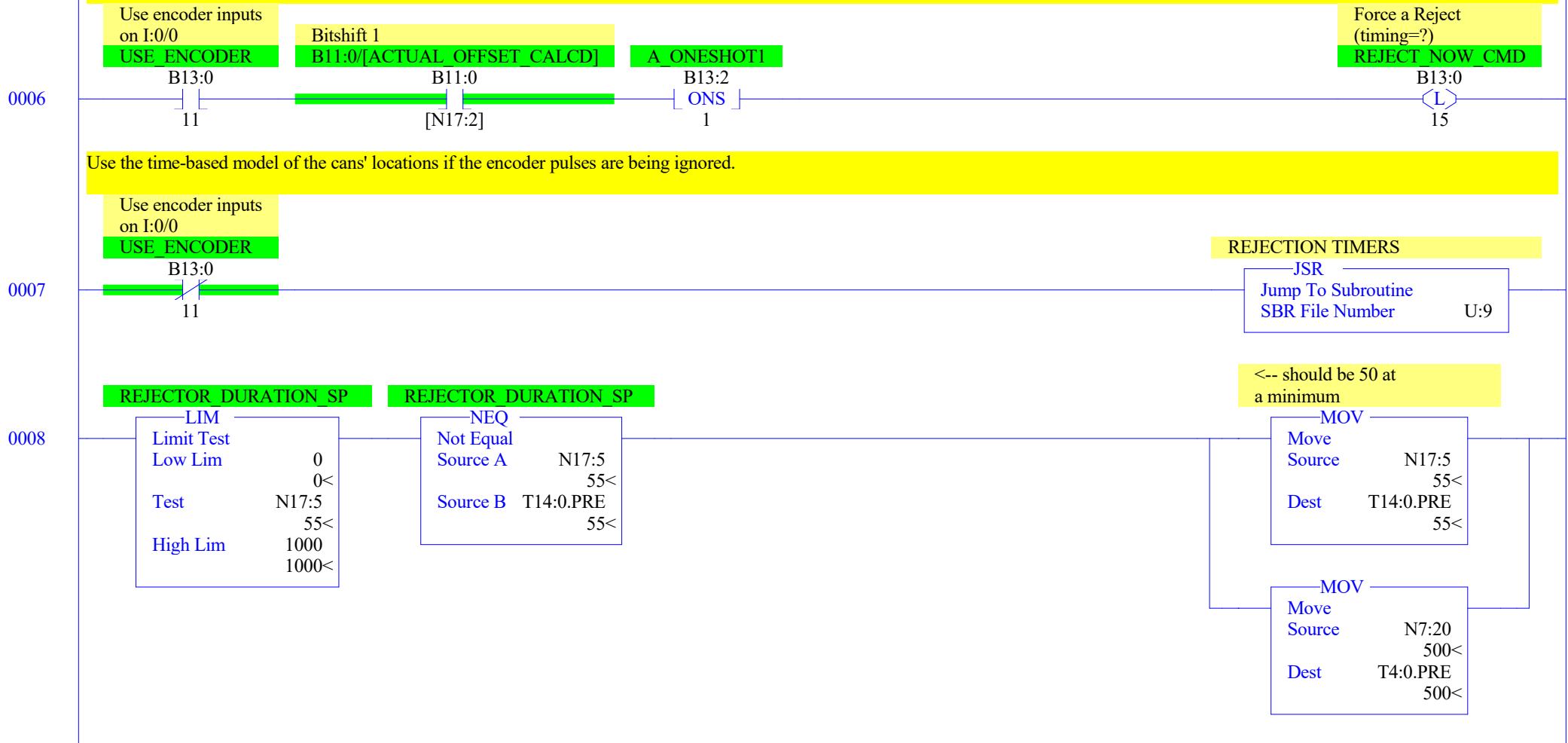
This subroutine fires each time HSC0 accumulated counts meets the HI or LO preset. Since we do not care (and should never get a LO, this logic executes a bitshift. If the bits are shifted too much, increase the HI preset. It is suggested that we get close to 10 shifts per can, the better "resolution" the better the kickout accuracy. Please remember that varied latency in the assignment of the PASS or FAIL result may place this status in inconsistent locations of the bitshift so resolution must be adequate for that but not too fine as to be shift intensive.

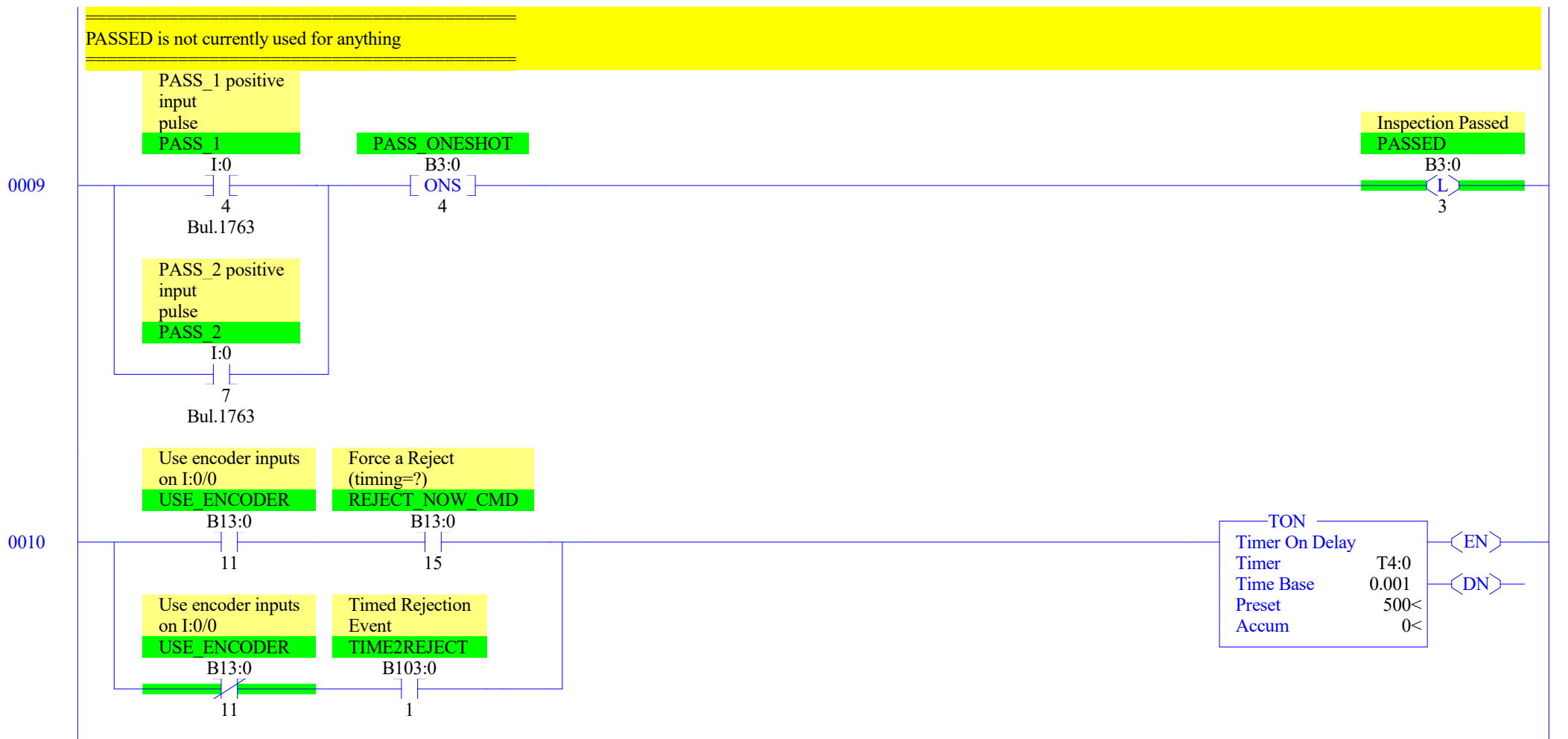
0005



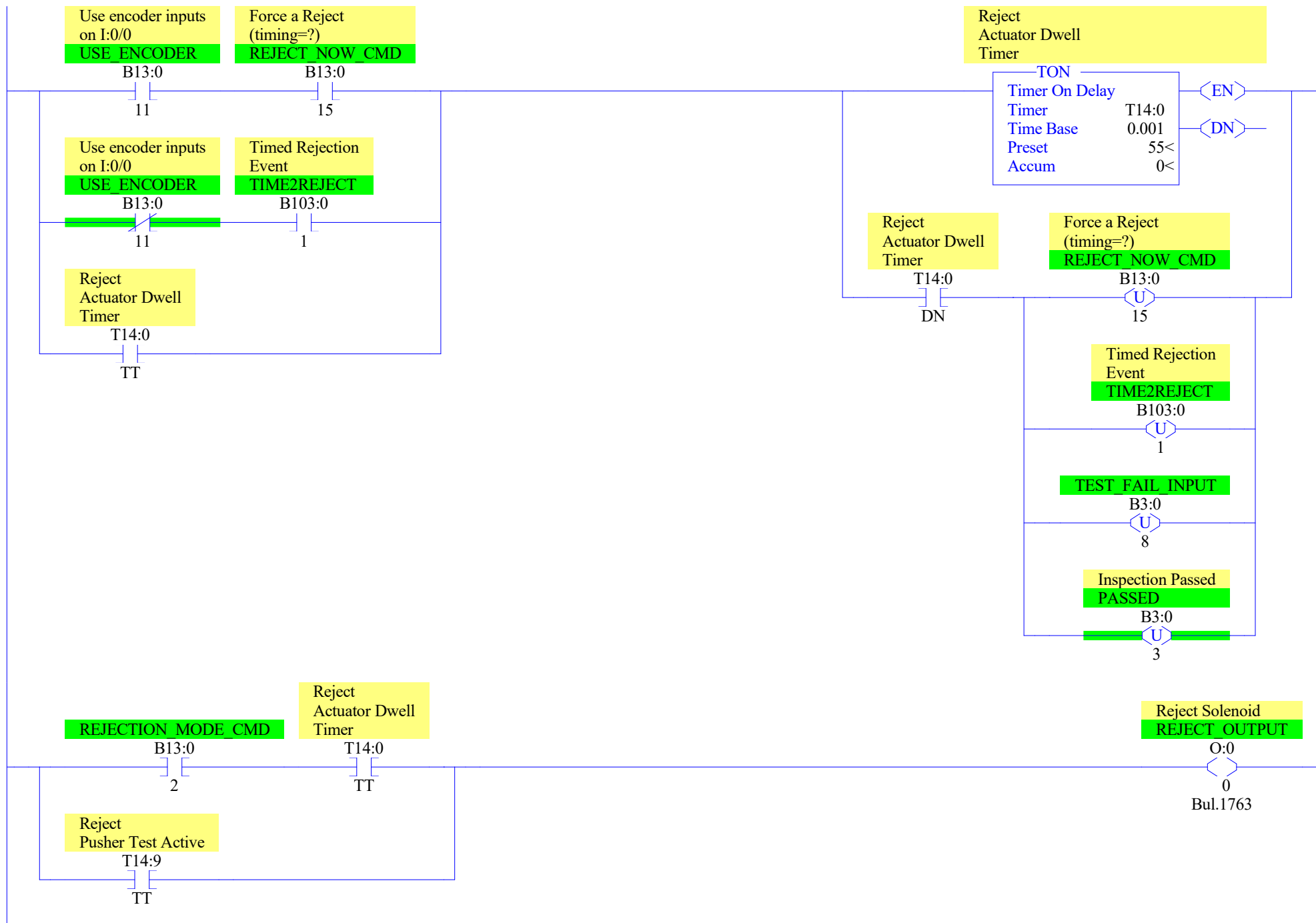
Rejection Logic

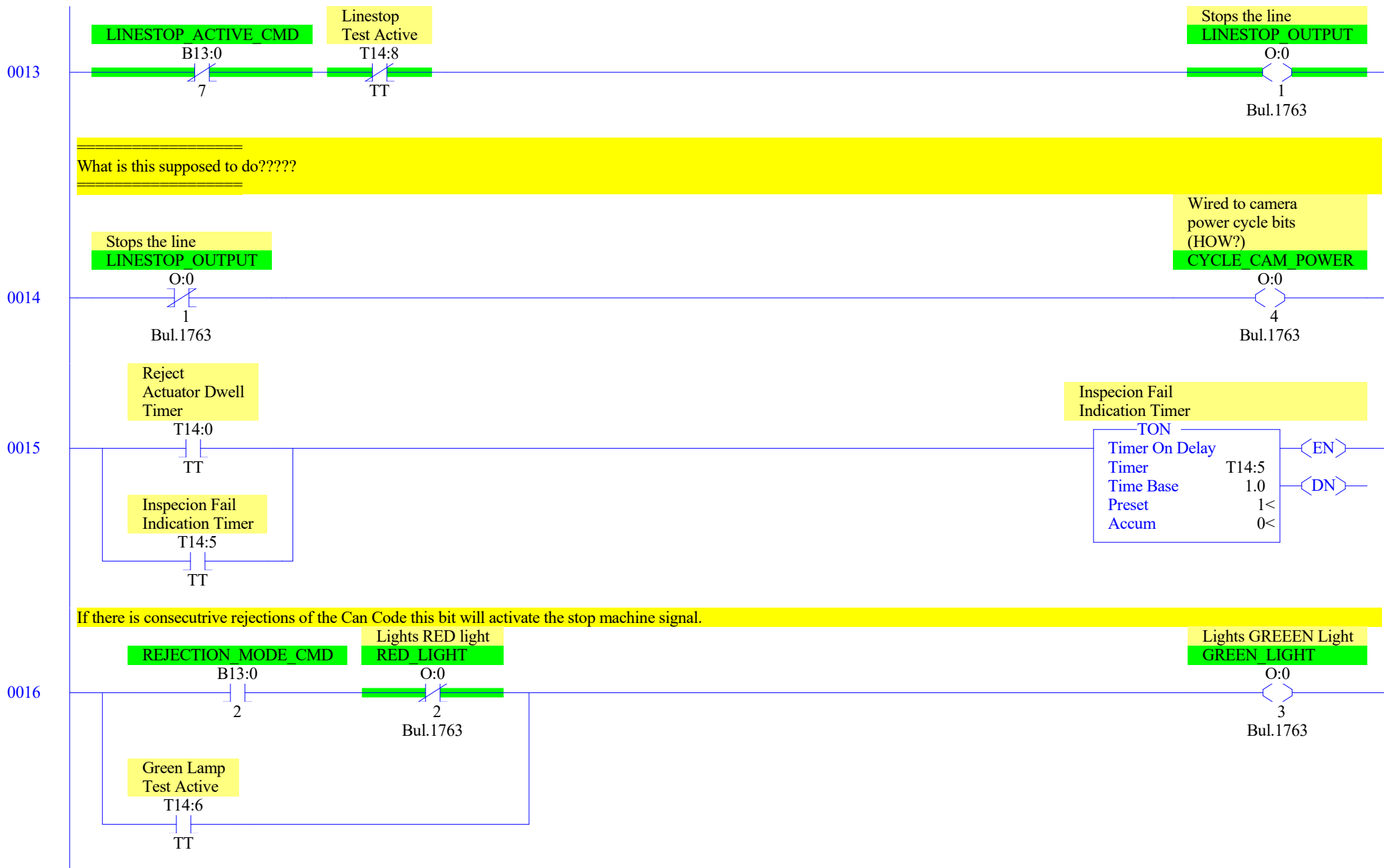
The bitshift conveys the fail status from the point of origin each time the HSC Hi Preset is reached. The REJECT output should fire at a point in the future as assigned by the value of N17:5 which is changeable in the data table. Once this REJECT signal is set, it should be tied to the actual output to trigger the reject actuator then this bit should be reset once kickout has fired.



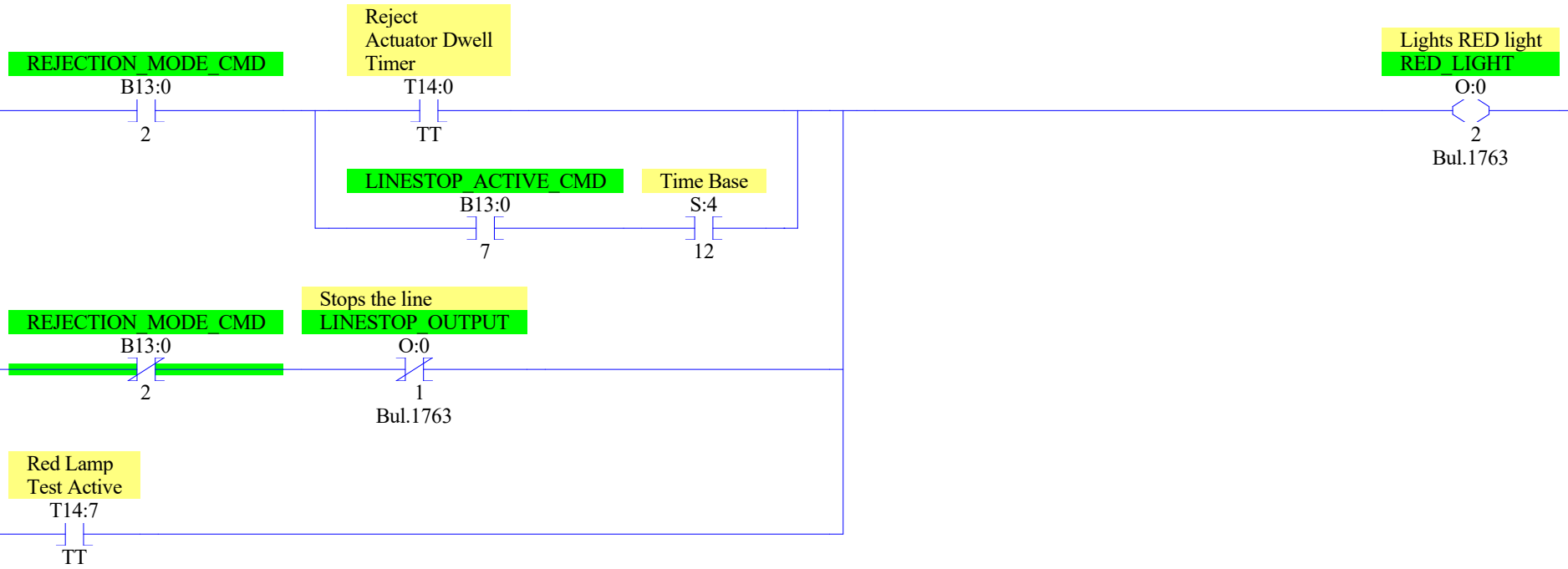


0011



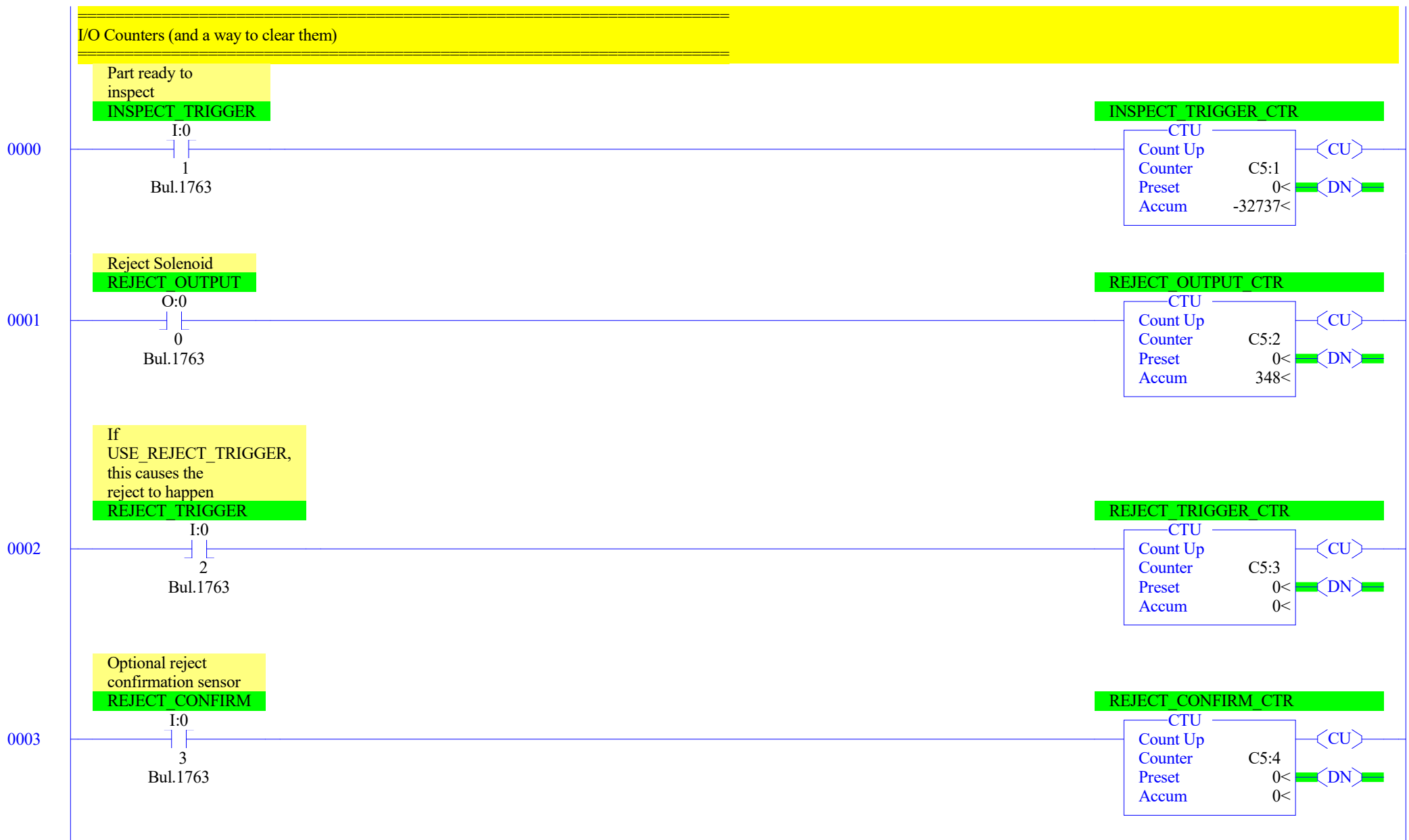


0017

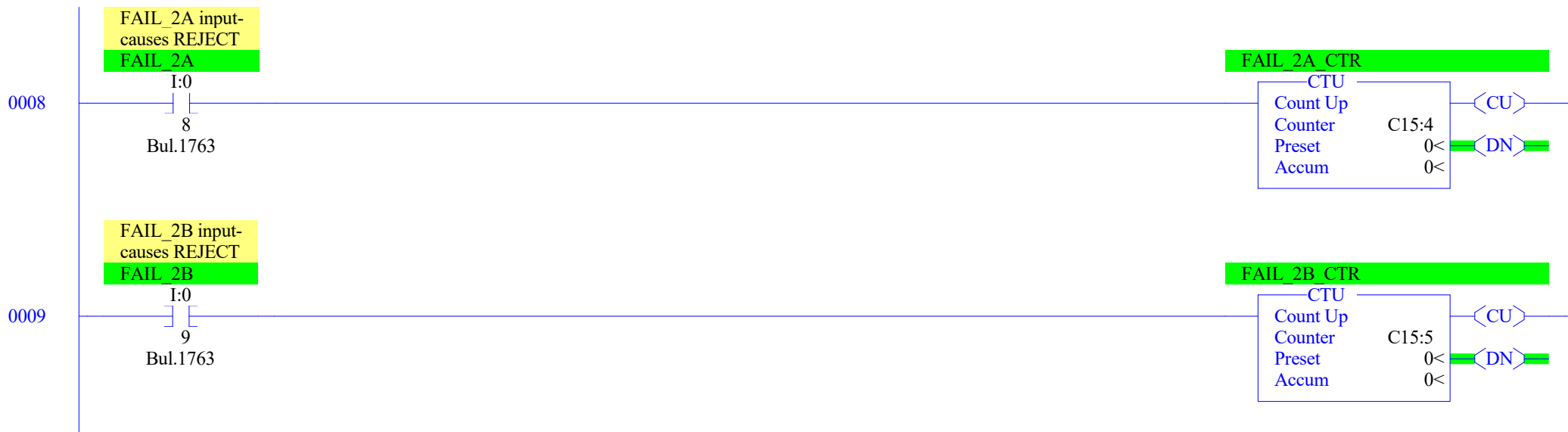


0018

<END>







The GUI/HMI executes the Set-And-Forget pattern to reset the counters

The RESET_COUNTERS_CMD (B13:0/12) bit is driven by the operator GUI/HMI, which sets its value to 1 and expects this program to detect that, execute the counter resets, and reset the bit value back to 0 so the counter reset is a one-shot event.

N.B. if any of the XICed operands (e.g. FAIL_2B I:0.0/9) feeding the counters are 1 on the scan cycle when the reset is commanded, then those counters .ACC values will immediately increment to 1, if the operand are still 1, on the next scan cycle

Clear all of the
counters assigned to
the inputs

RESET_COUNTERS_CMD

B13:0

12

INSPECT_TRIGGER_CTR

C5:1

< RES >

REJECT_OUTPUT_CTR

C5:2

< RES >

REJECT_TRIGGER_CTR

C5:3

< RES >

REJECT_CONFIRM_CTR

C5:4

< RES >

PASS_1_CTR

C15:0

< RES >

FAIL_1A_CTR

C15:1

< RES >

FAIL_1B_CTR

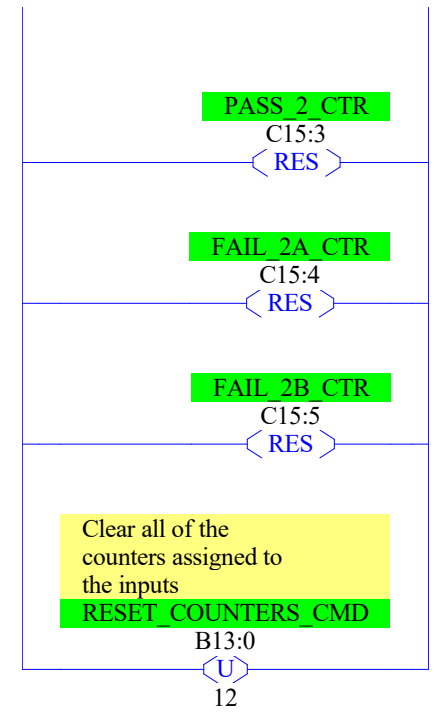
C15:2

< RES >

0010

LAD 5 - IO_COUNTER --- Total Rungs in File = 12

0011



<END>

Timed reject logic when encoder pulses are being ignored

This Program File routine is executed if the use of the encoder as the clock has been disabled via the operator GUI/HMI.

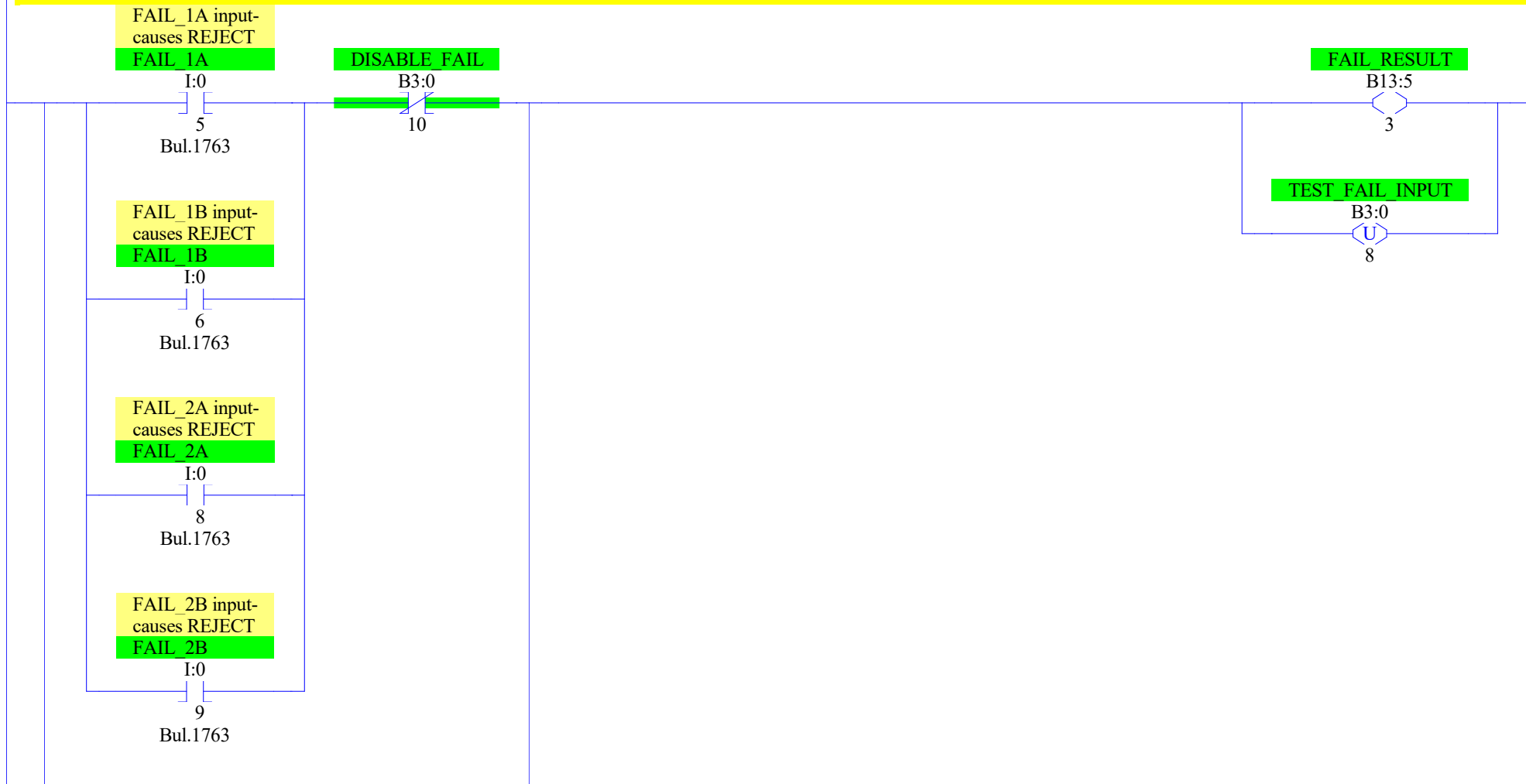
Pulses have been accumulating into the value of WORKING_REGISTER by the High-Speed Counter interrupt routine (LAD11 HSC0).

Calculate combined inspection cameras' failed can signal as any (logical OR) of all possible* failed signals

* Any camera (FAIL_1/2/A/B), when not disabled, or synthetic test event (TEST_FAIL_INPUT; set-and-forget) from the operator GUI/HMI

- Ensure synthetic test event is a one-shot i.e.is 1 for at most 1 scan cycle

0000





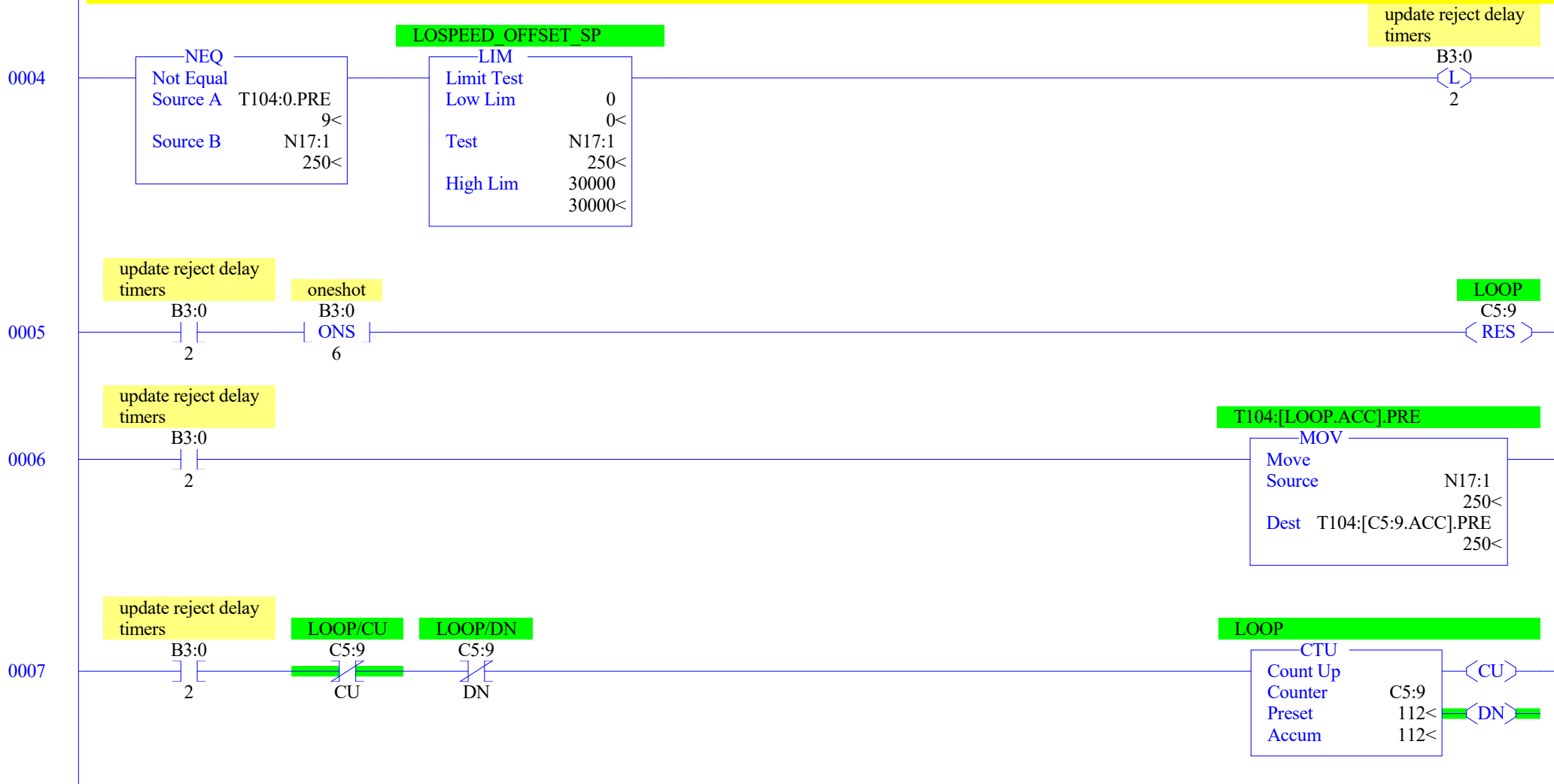
Set reject delay timers

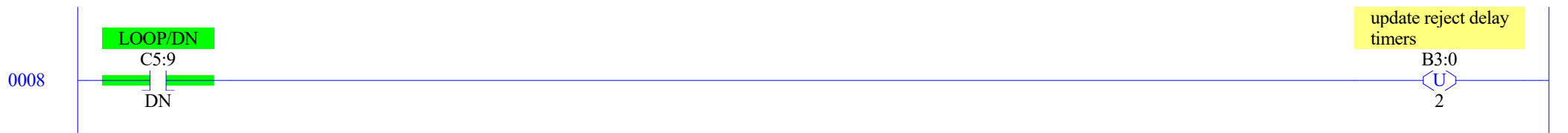
The next five rungs of logic cycles thru all 112 timer objects (T104:0 thru T104:111) to update a changed PRESET

N.B. it will take 223 scan cycles to complete the updates to all timer objects

TODO: why are the LIM instruction limits [0:30000] on this rung, when the previous rungs use [0:32000]?

TODO: refactor these 4 rungs and 14 instructions to do the same task more clearly and concisely (half the rungs, instructions, and scan cycles)





Multiple Overlapping Rejection Timers

Handling a rejected can involves two primary process steps:

- 1) Detecting when that can fails inspection at the cameras station (see FAIL_OS on Rung 001 above)
- 2) Triggering the reject pusher solenoid, when the can arrives at the reject station, to eject the can from the conveyor

This program use Timer ON-delay instructions to model the time between steps (1) and (2) above:

- Start a timer when a can fails inspection at the cameras station
- Run the timer as the failed can travels from the cameras station to the reject station
- Activate the reject pusher solenoid when the timer expires as the failed can arrives at the reject station
- This will be accomplished by latching the TIME2REJECT B102:0/1 bit value to 1

The following code implements that model for one or more failed cans, while all of those cans are simultaneously

- BETWEEN the upstream camera station where they failed inspection,
- AND the downstream reject pusher solenoid where they will be ejected from the conveyor

There are 112 timer objects, T104:0 through T104:111, in the Data File array T104.

There are 112 bits, ...REJECTn, each representing the busy state of one of those timer objects:

- A bit value of 0 means the timer object is not timing a failed can's travel and is available to time a new failed can
- A bit value of 1 means the timer object is timing a failed can's travel and is unavailable to time a new failed can

Each consecutive pair of rungs that follow control the logic for one timer object that can model one failed cans travel from the camera station to the reject station. E.g. Rungs 0009-0010 control the logic for timer object T104:0.

The first rung of each pair tests whether

- BOTH a new failed can still needs to have a timer assigned to it => FAIL_OS bit value is still 1,
- AND if the timer object of the rung pair is not busy => ...REJECTn bit value is 0,

and, if those conditions are both true, then that first rung assigns the timer object the the new failed can by

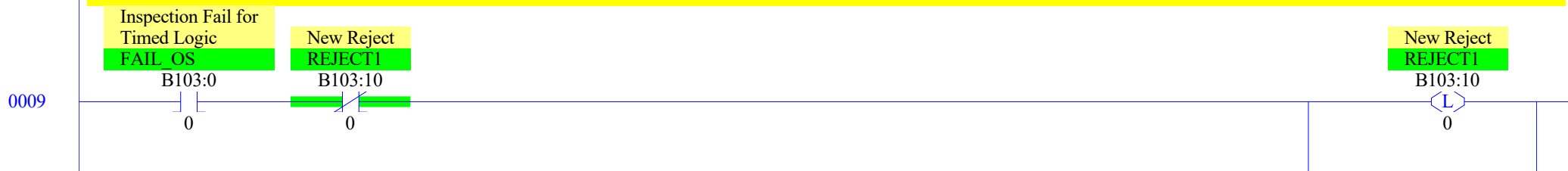
- Marking the timer object as busy => latch the timer object's ...REJECTn bit value to 1, and
- Canceling the new failed can status => unlatch FAIL_OS value to 0, so no other timer will be assigned to the new failed can

The second rung of each pair controls the TON instruction for the timer object of the rung:

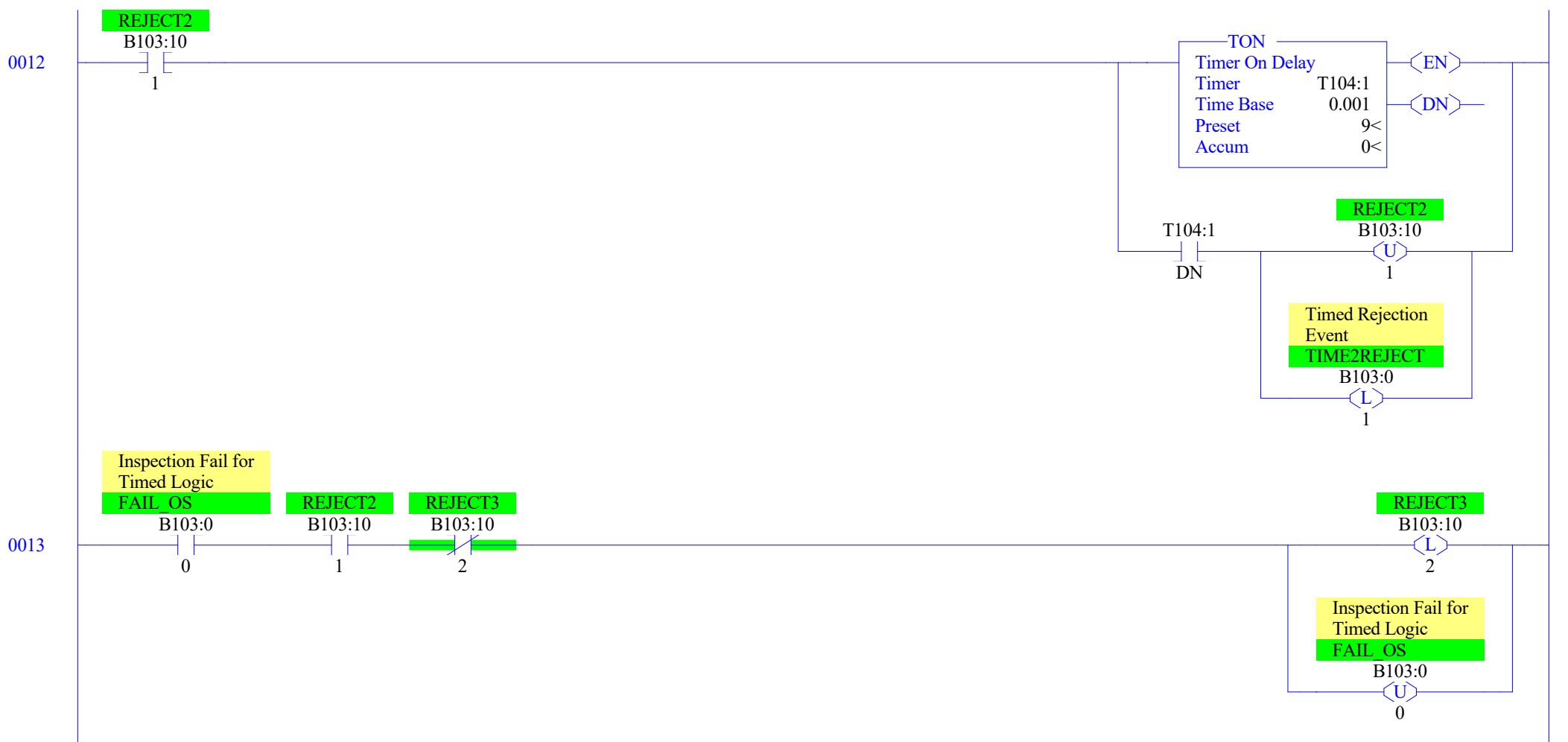
- If the can has not reached the reject station (=> ...REJECTn bit value is 1), then continue running the timer,
- When the can reaches the reject station (timer object /DN bit is 1),
- Unlatch the timer object ...REJECTn bit value to 0, and
- Latch the TIME2REJECT bit value to 1, to trigger the reject pusher solenoid in the routine LAD 4 INSPECTION

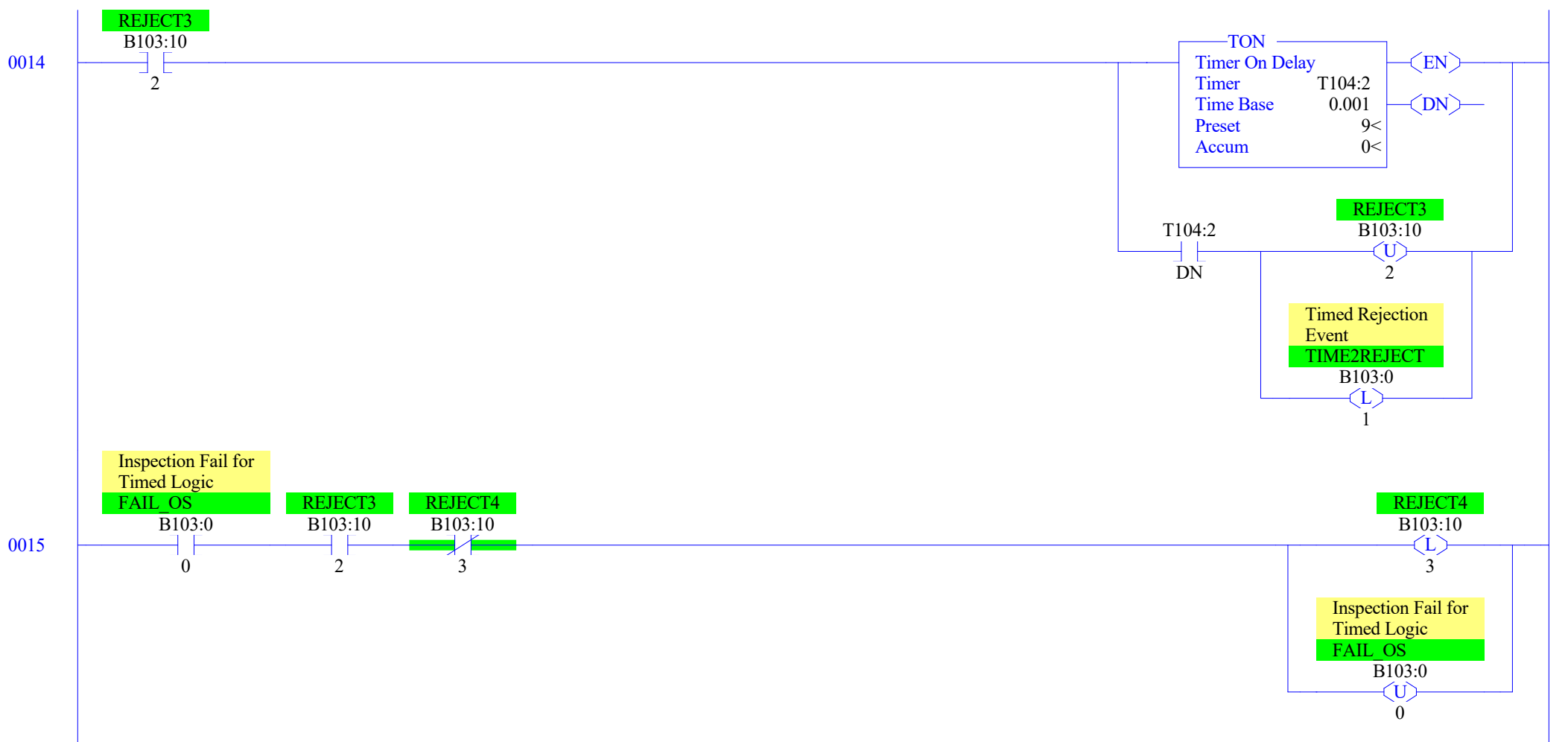
TODO: look into simplifying this logic, e.g. the timer objects' /TT bits could be used instead of the ...REJECTn bits

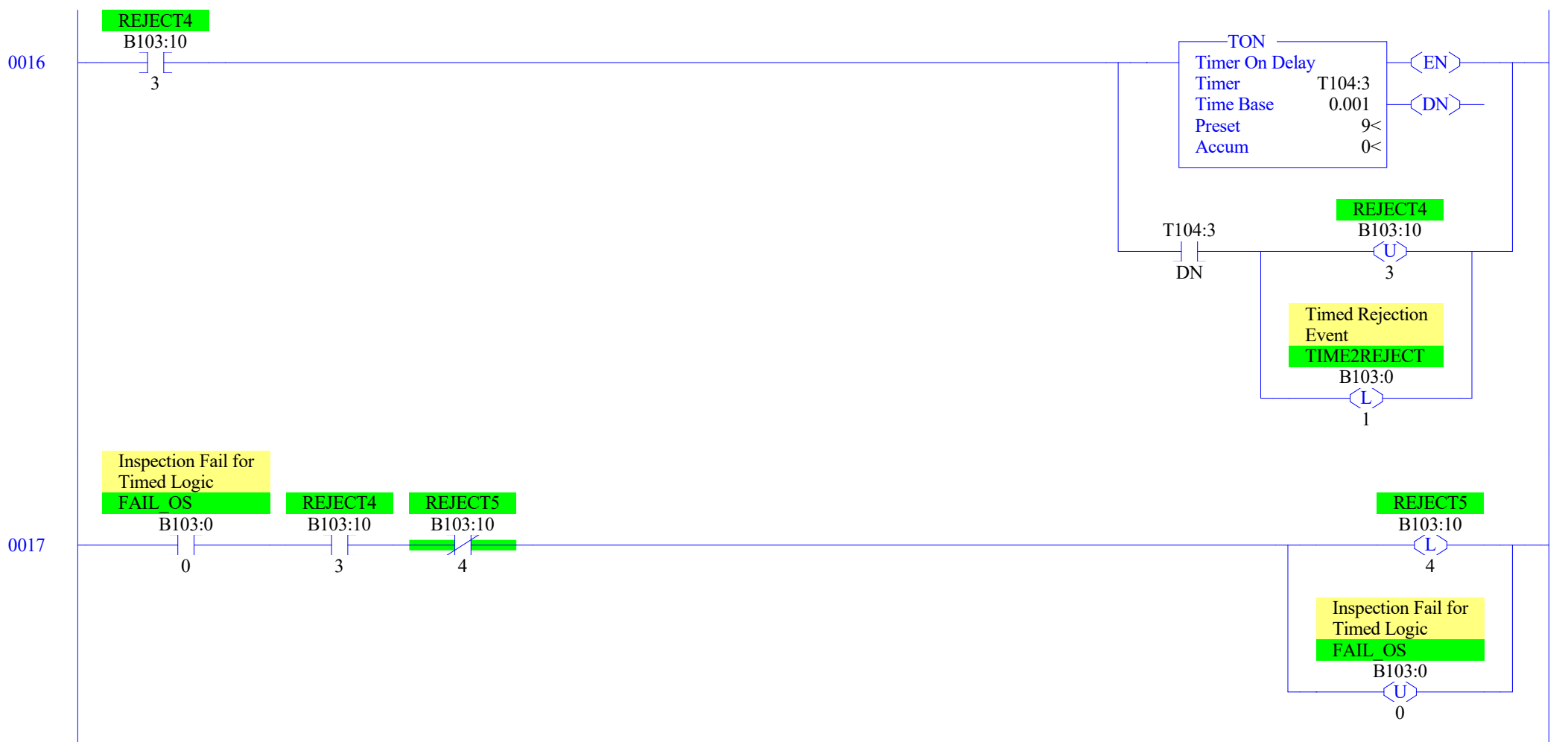
TODO: refactor the second rung of the pair by removing the unnecessary [XIC ...REJECT(n-1)] instructions

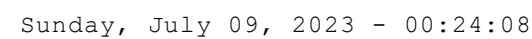


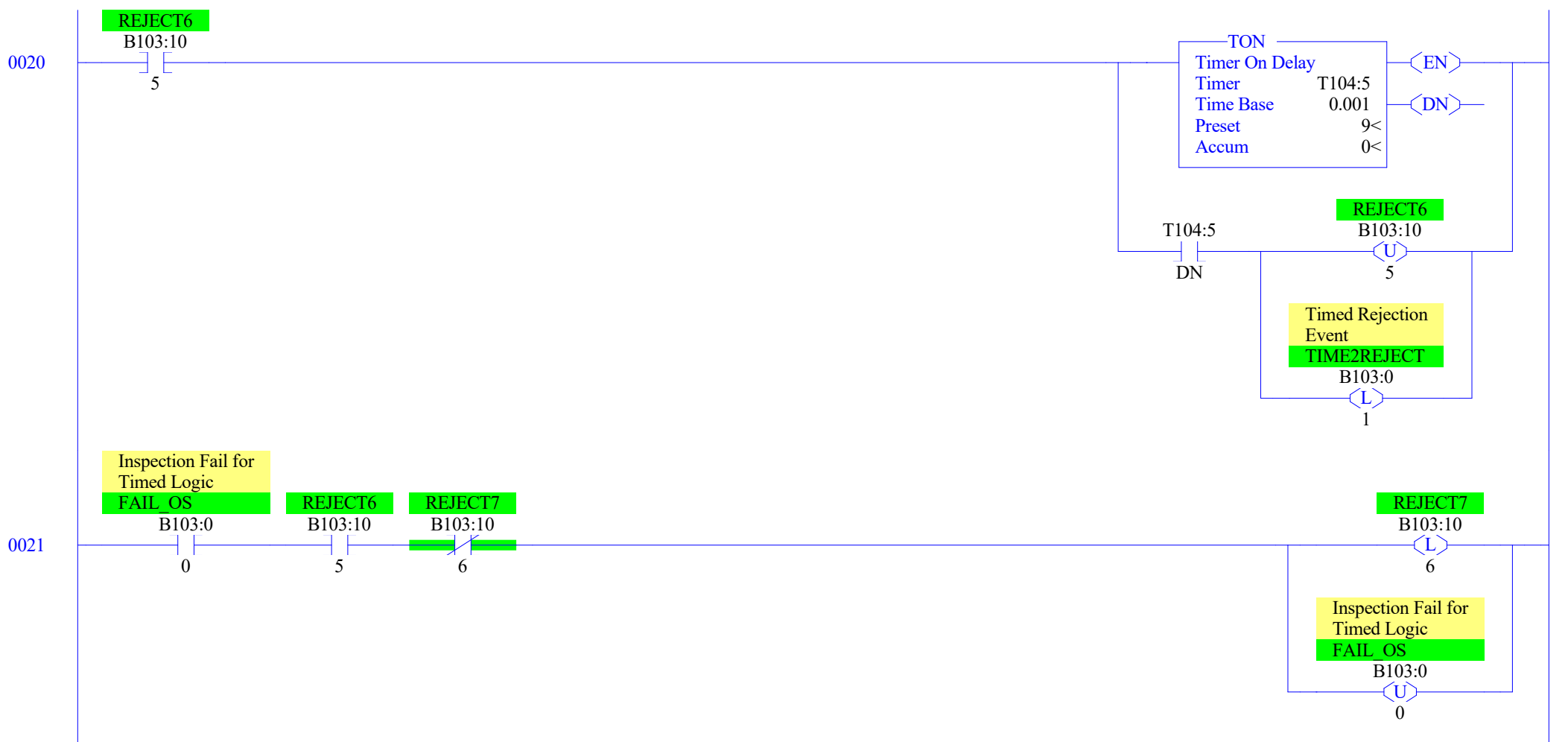


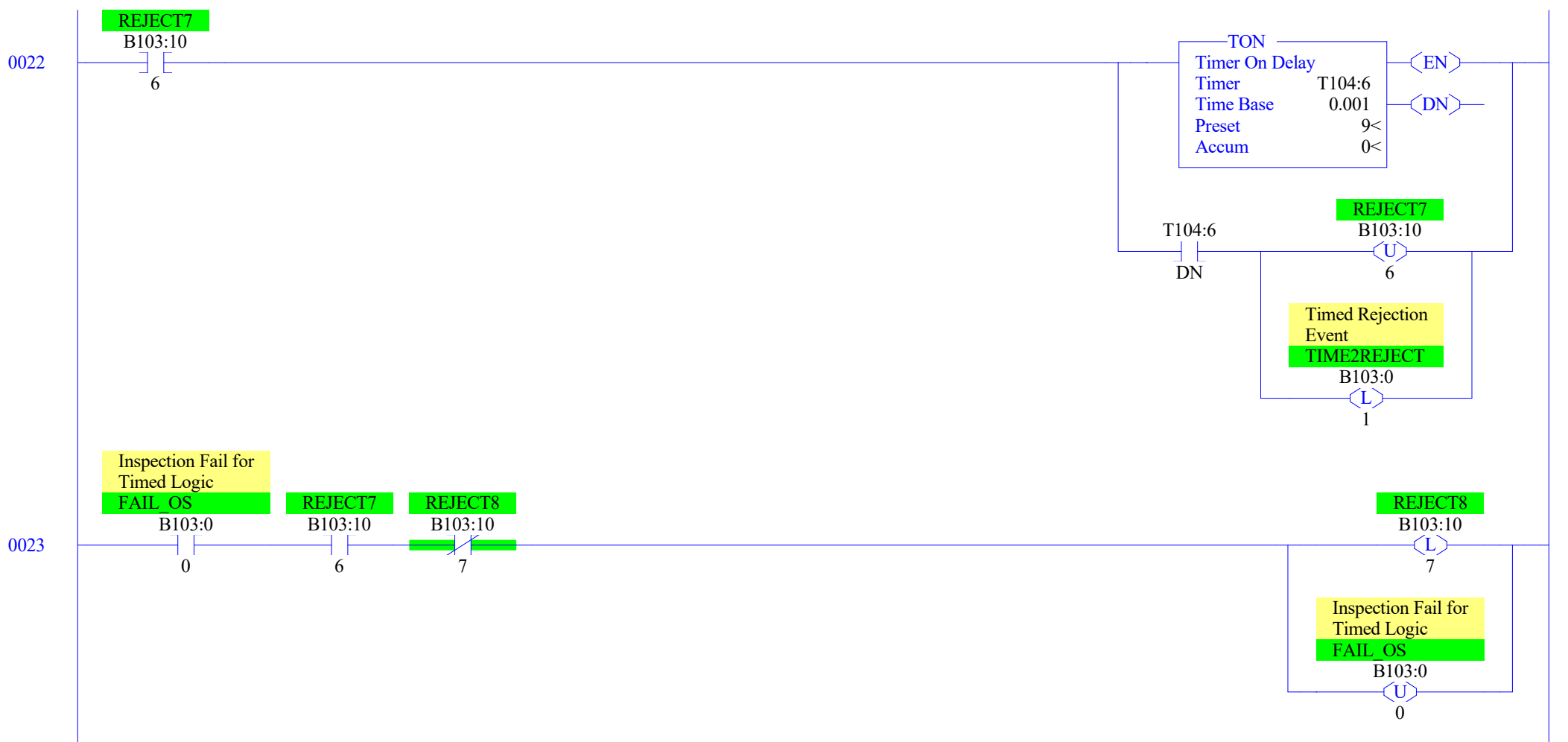


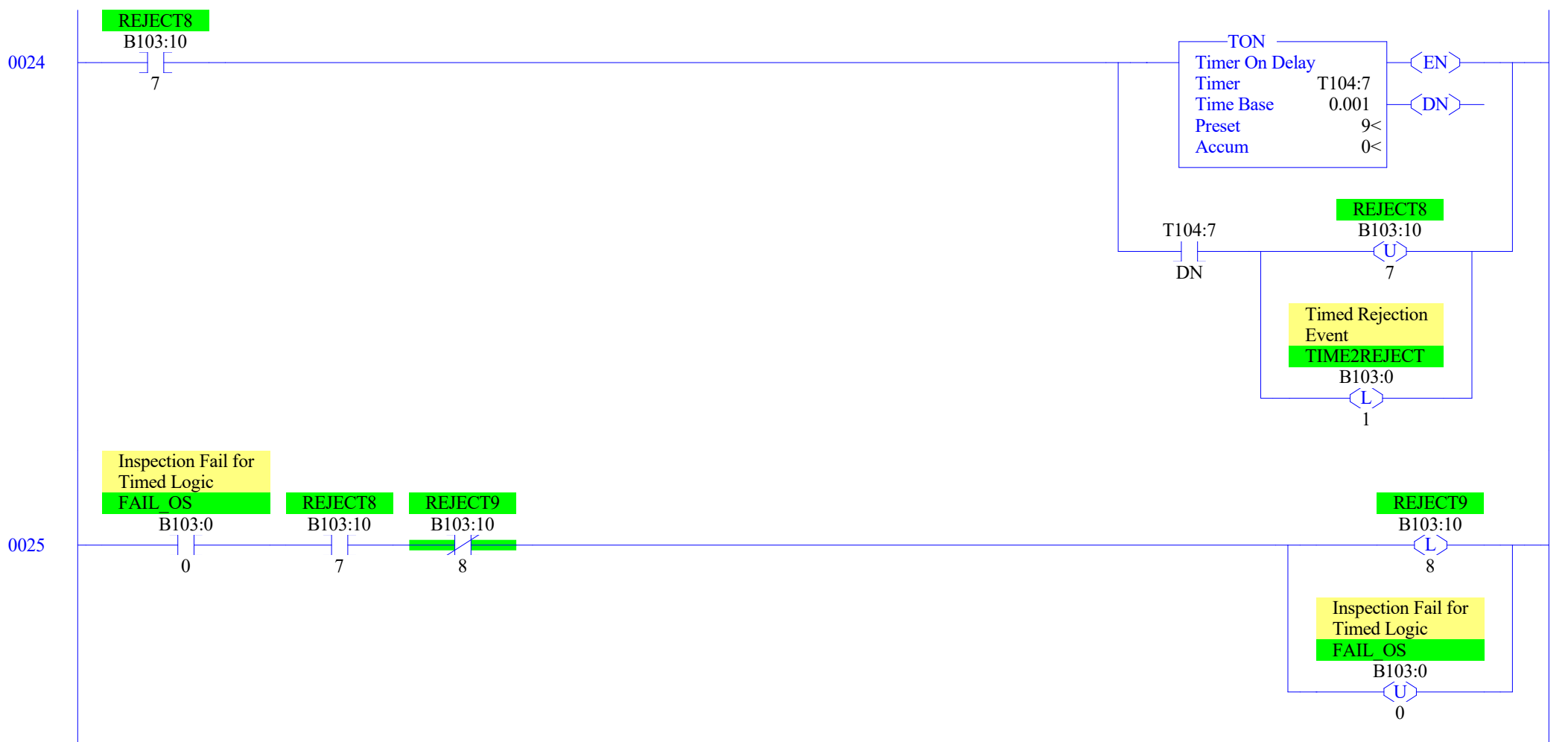


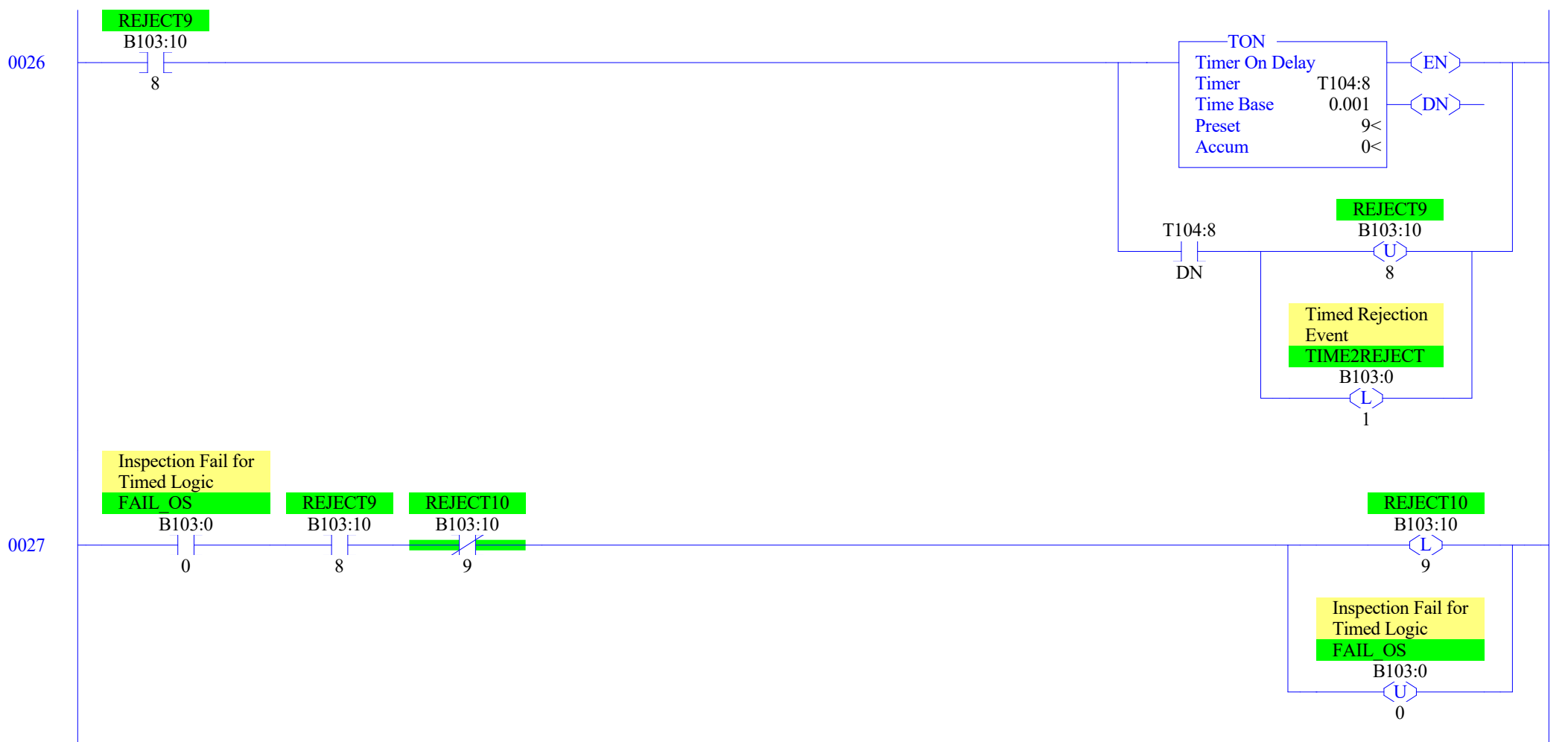


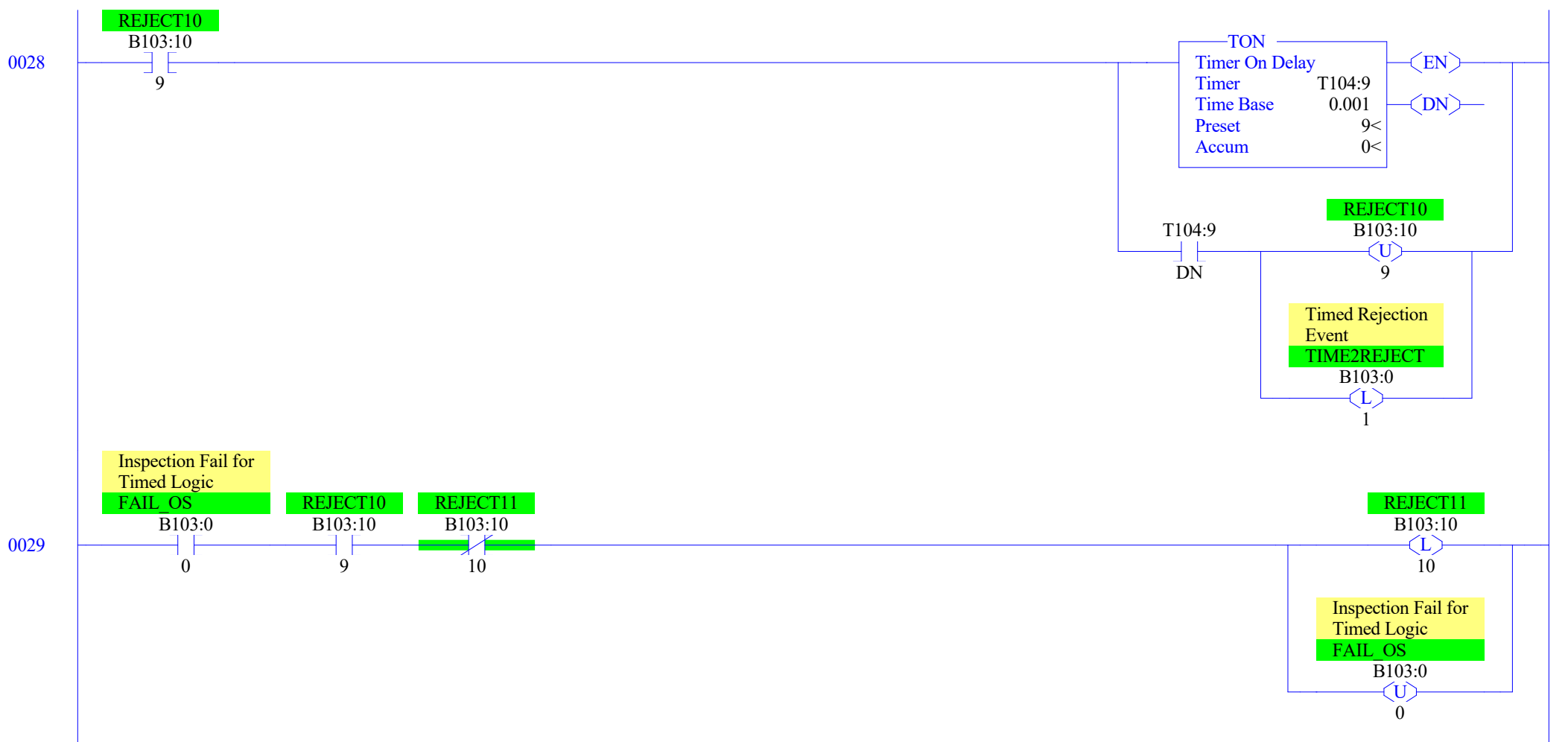


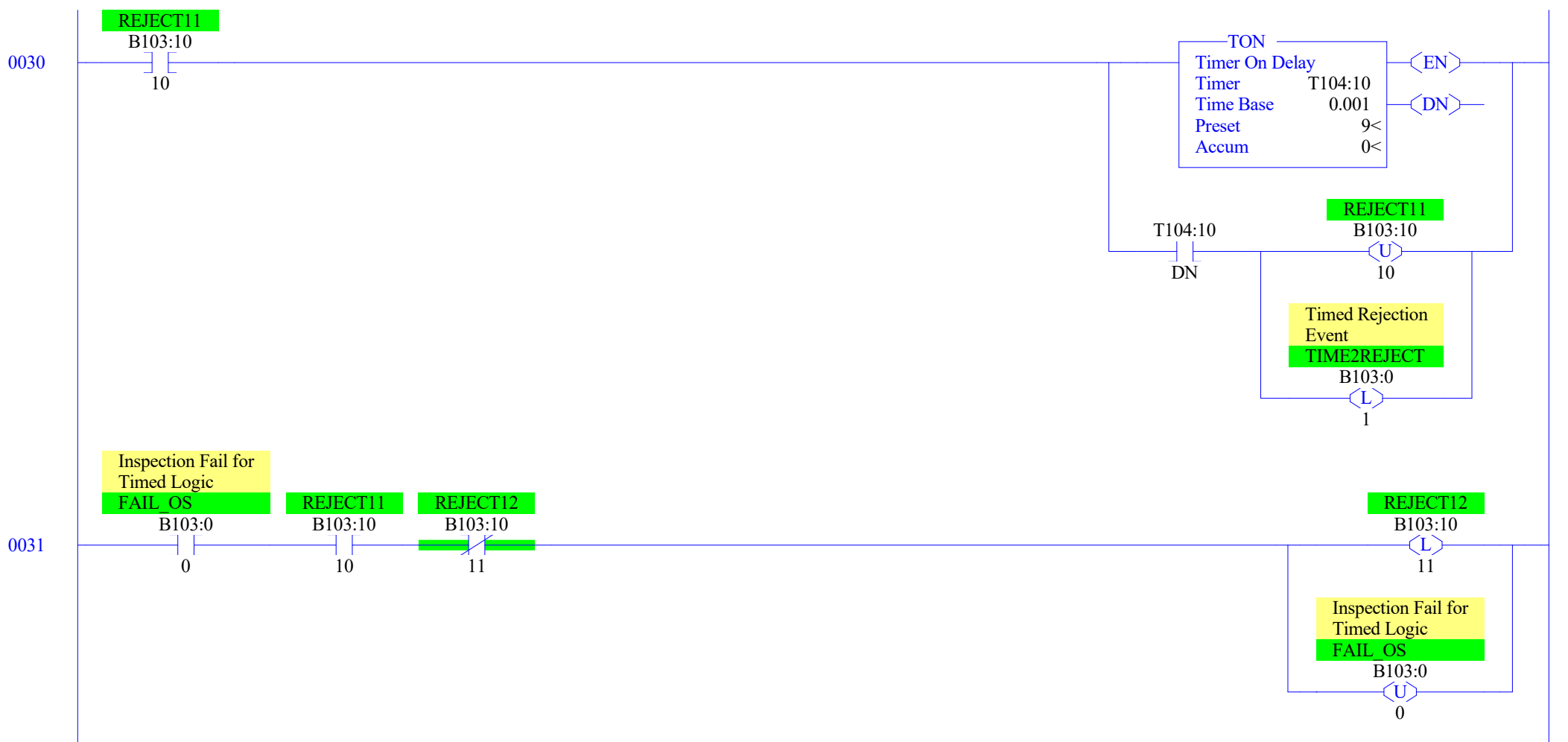


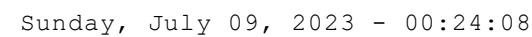


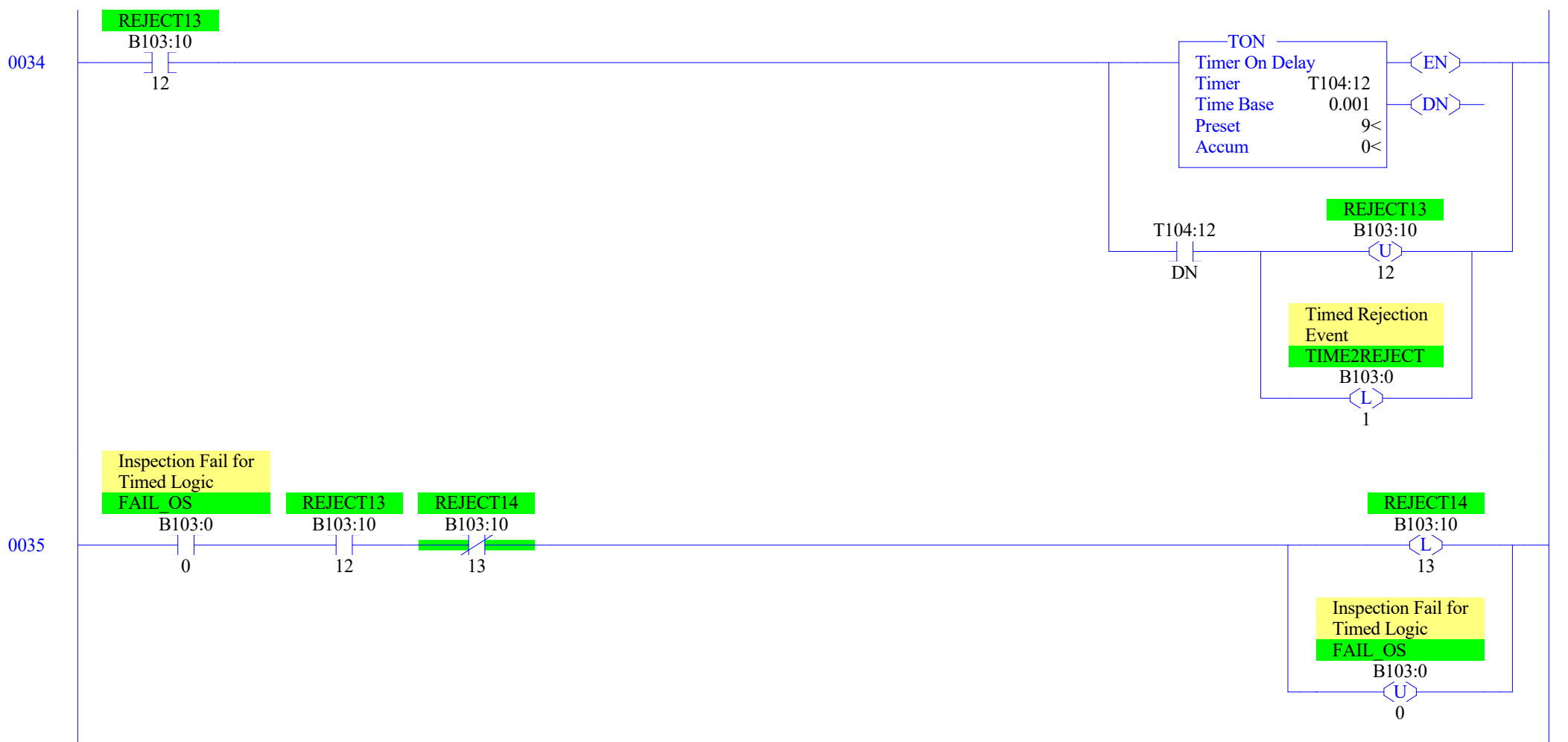


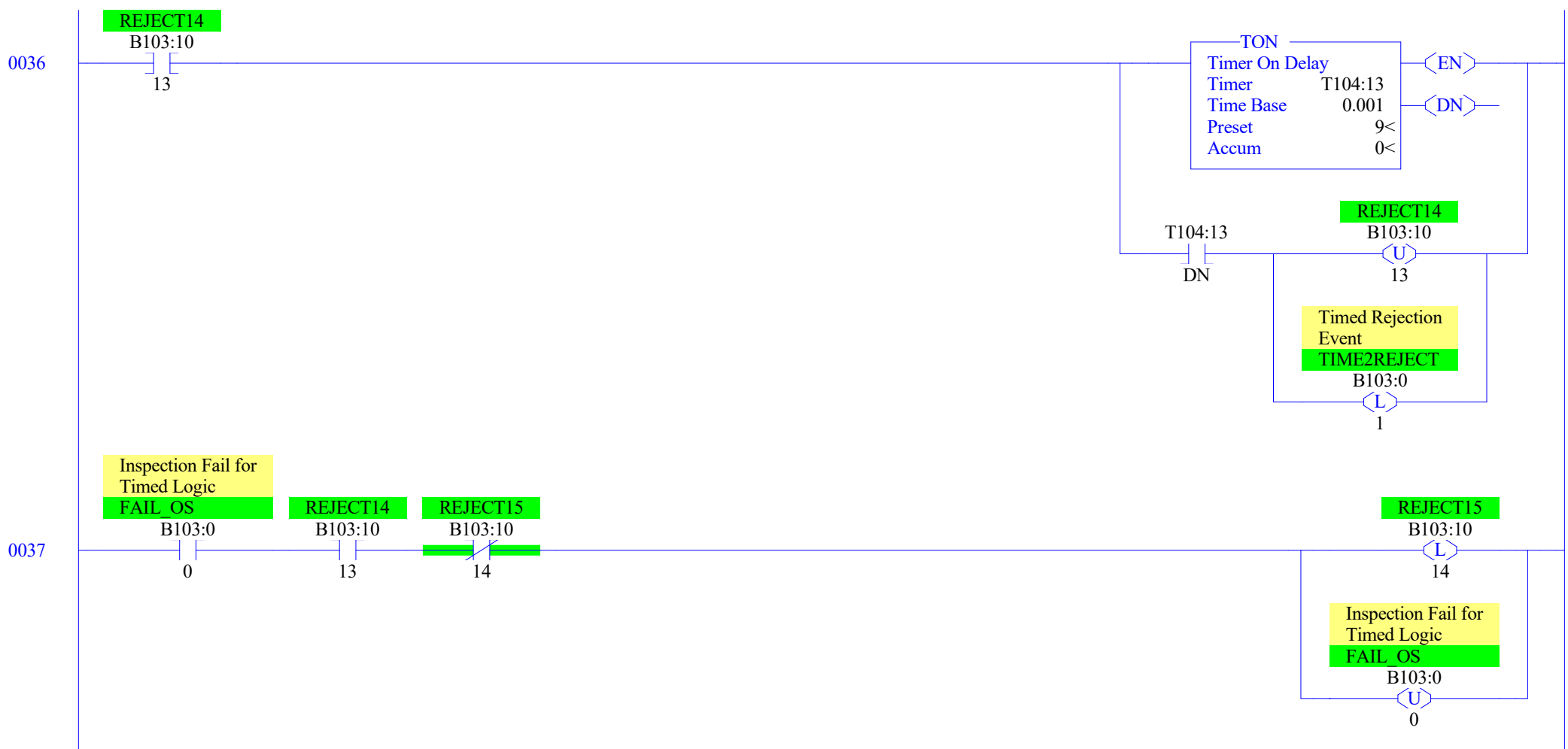


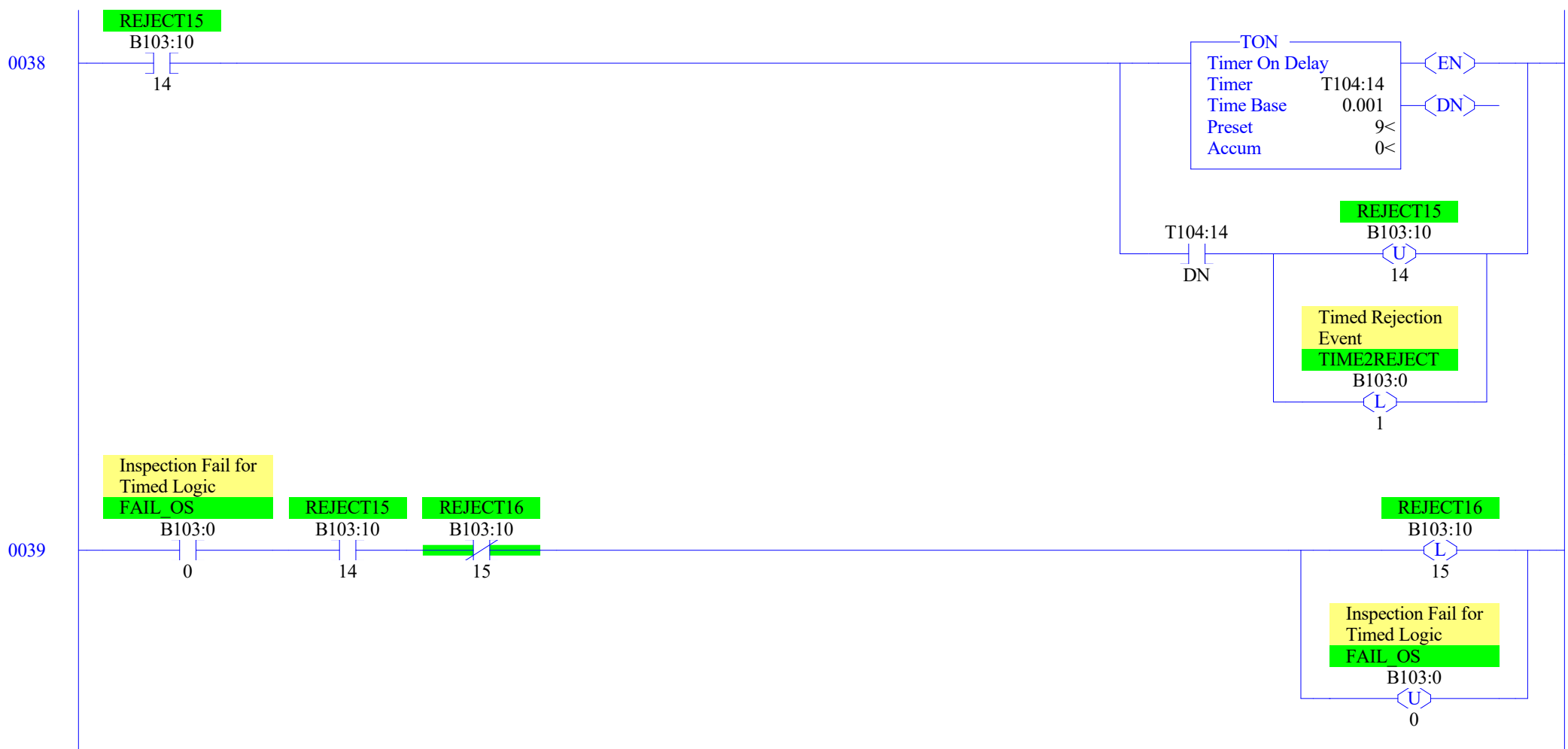


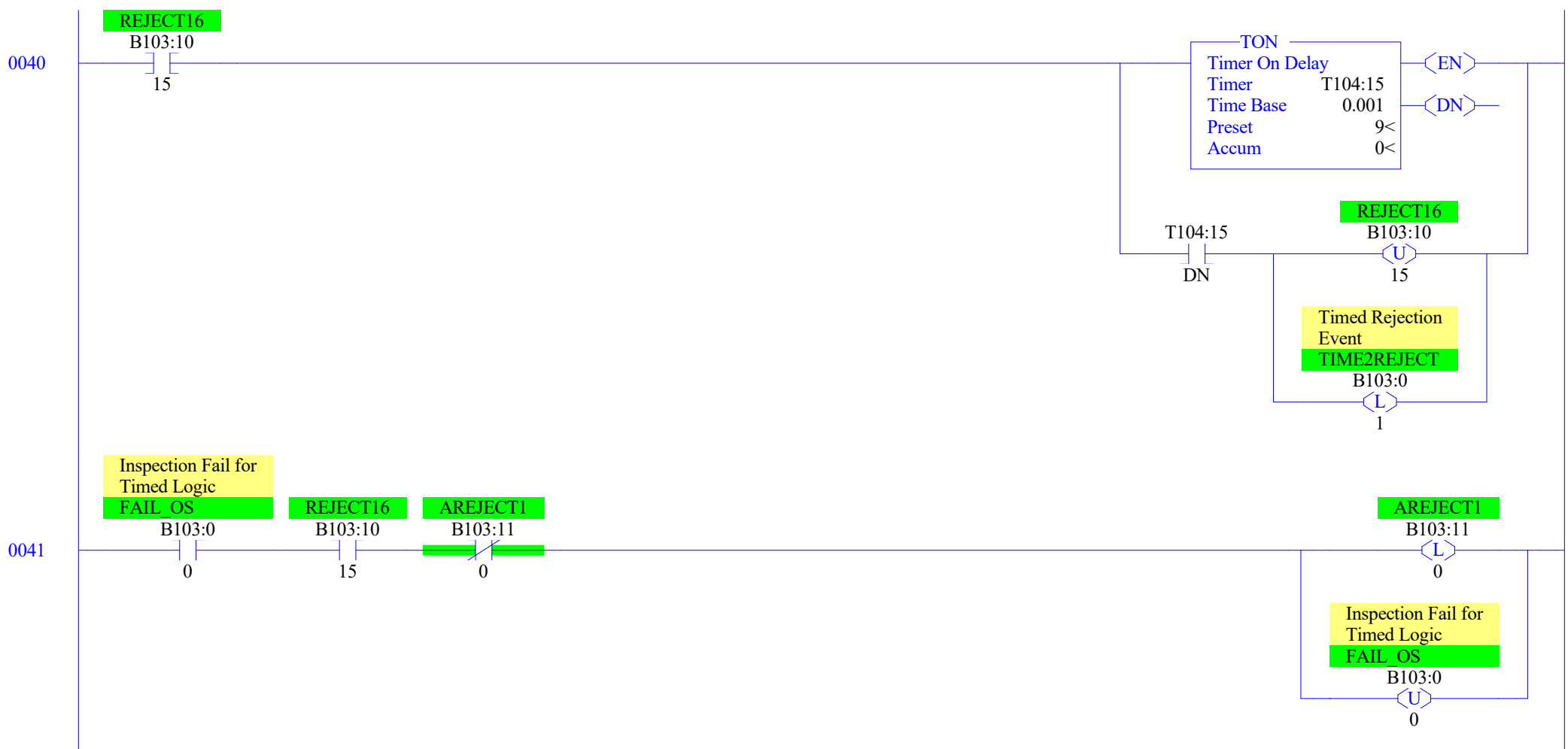


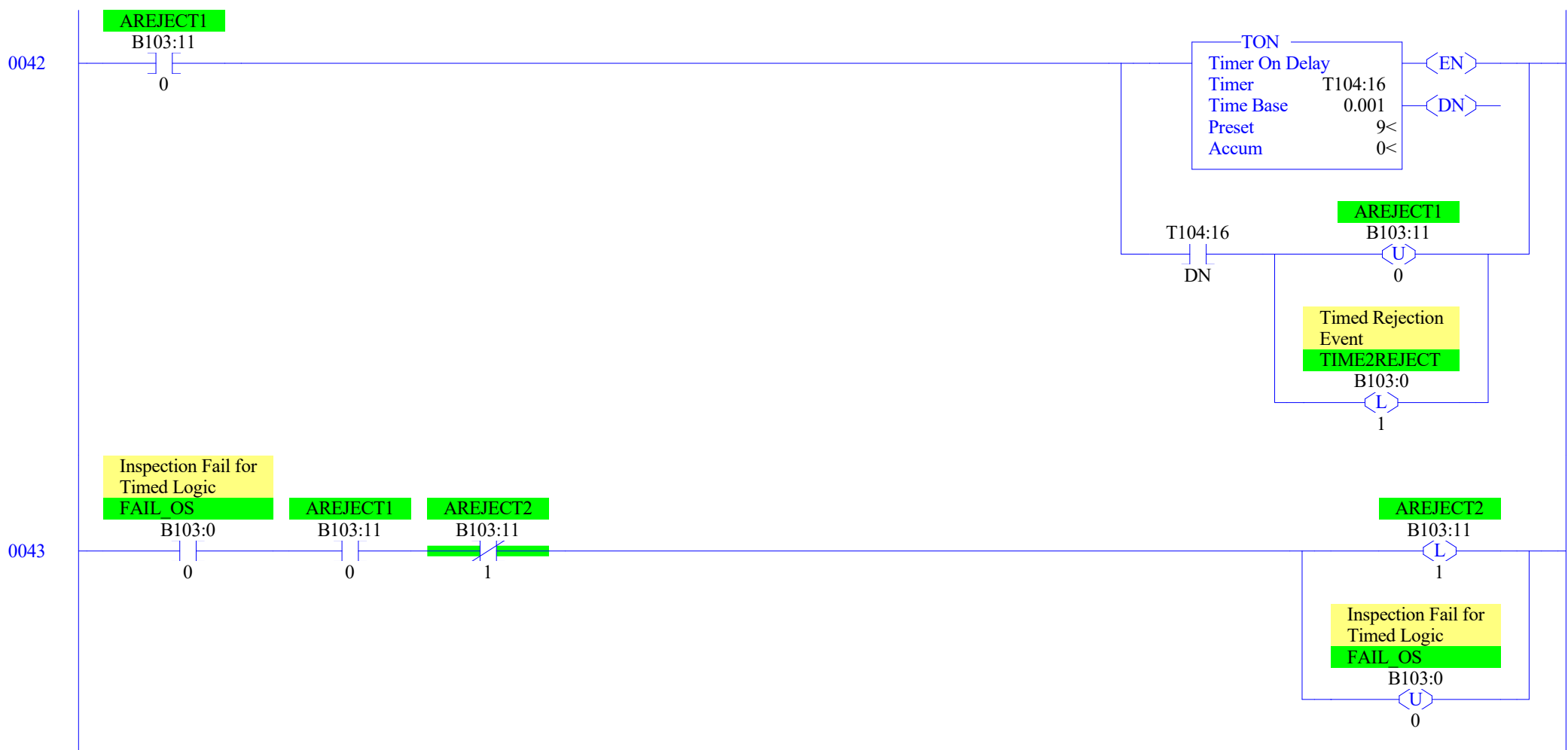


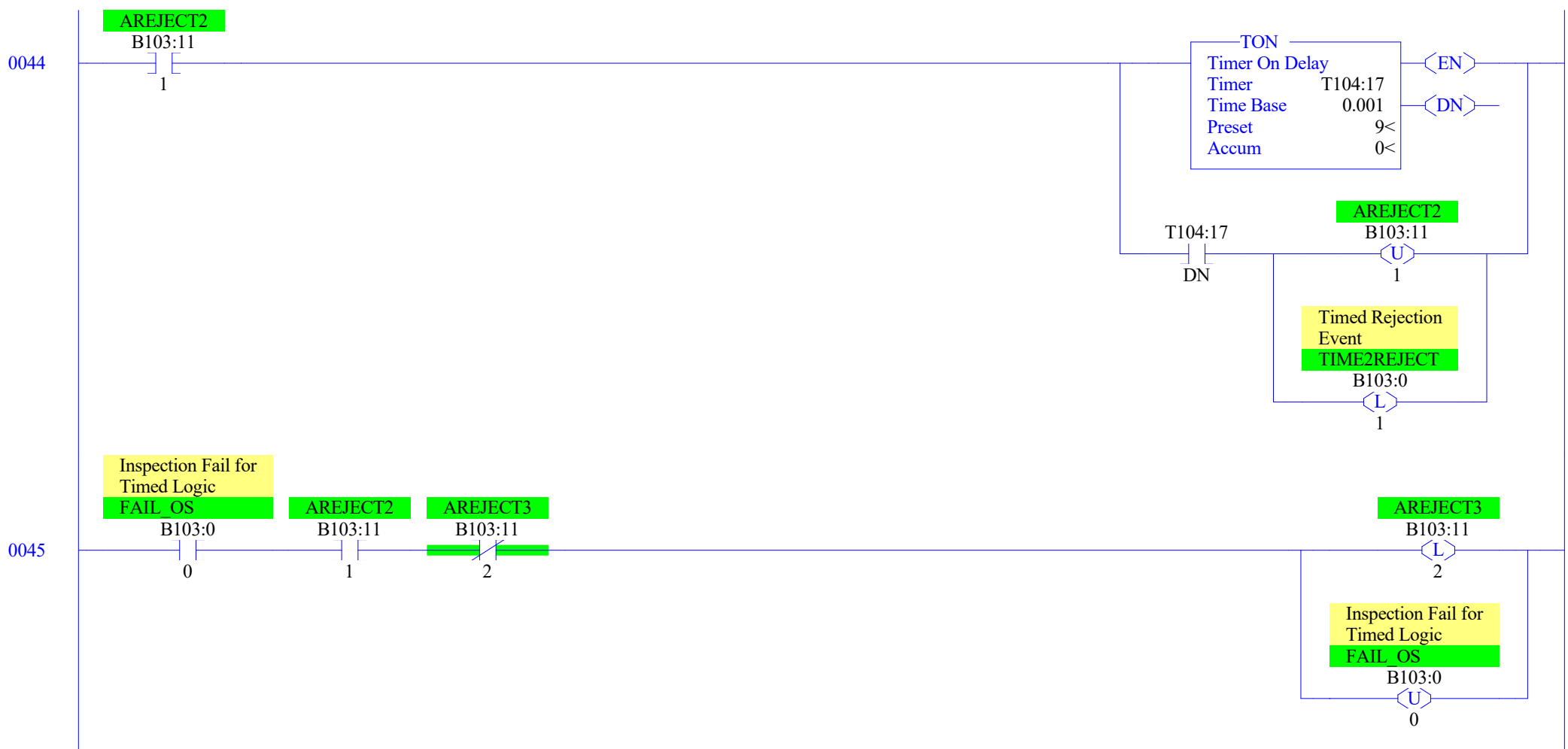


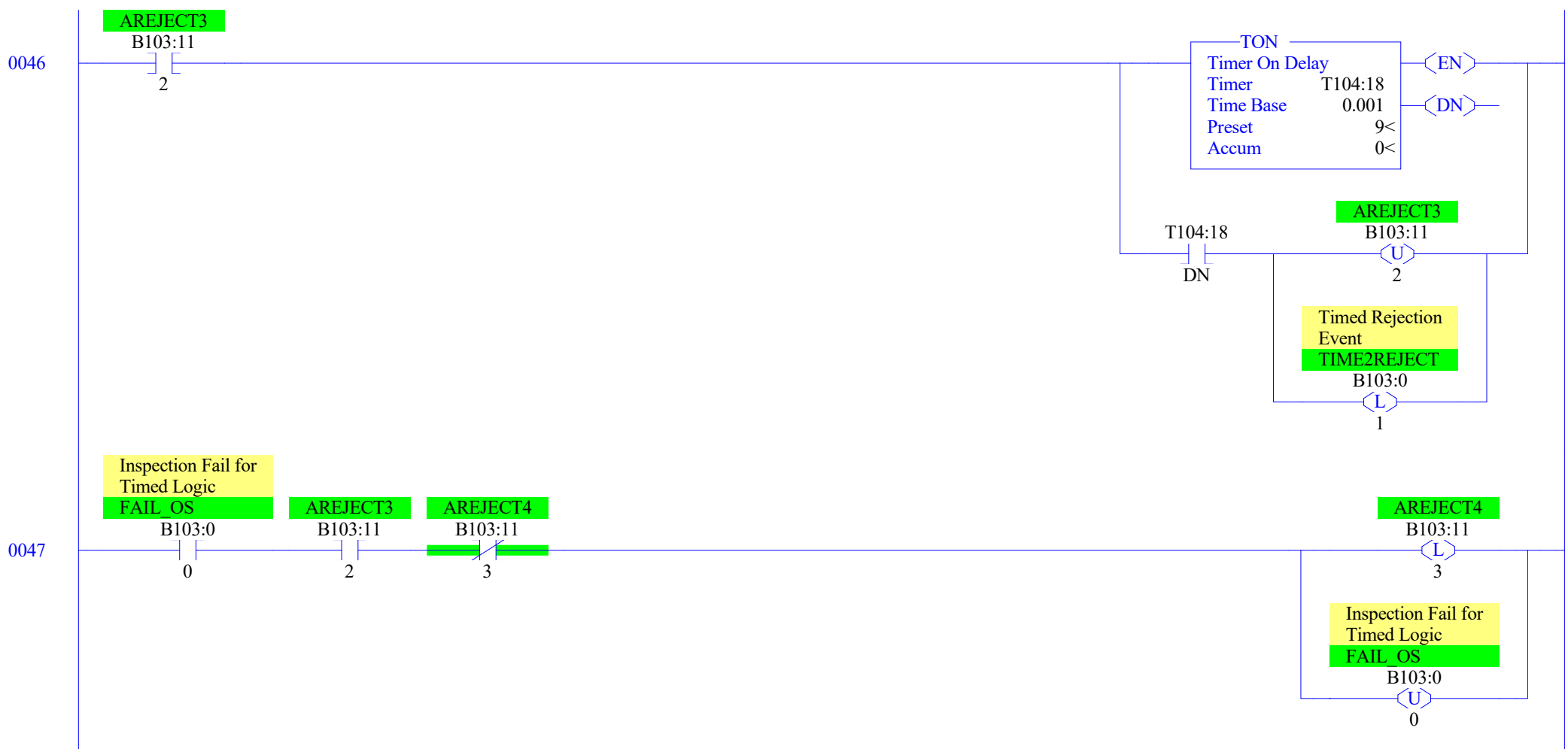


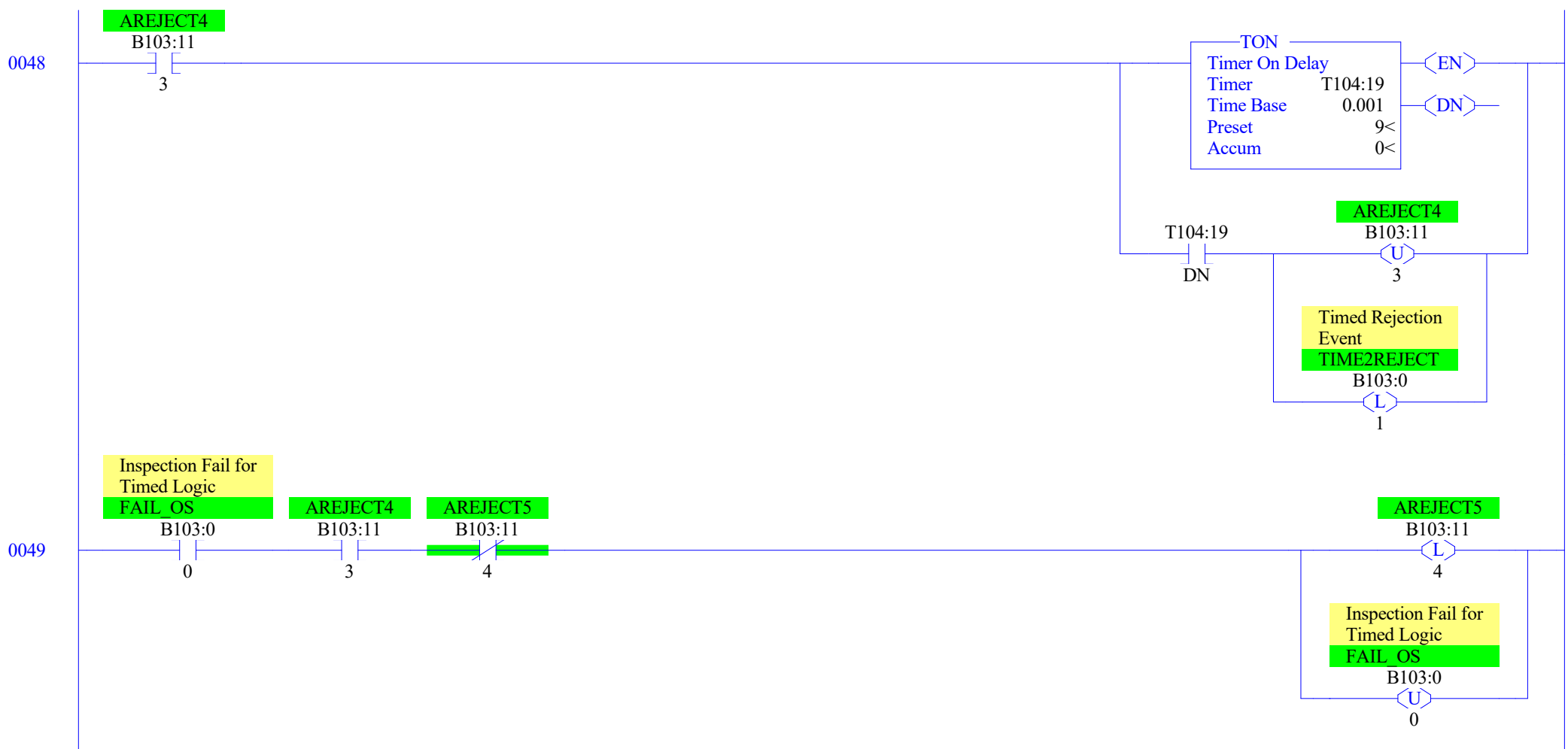


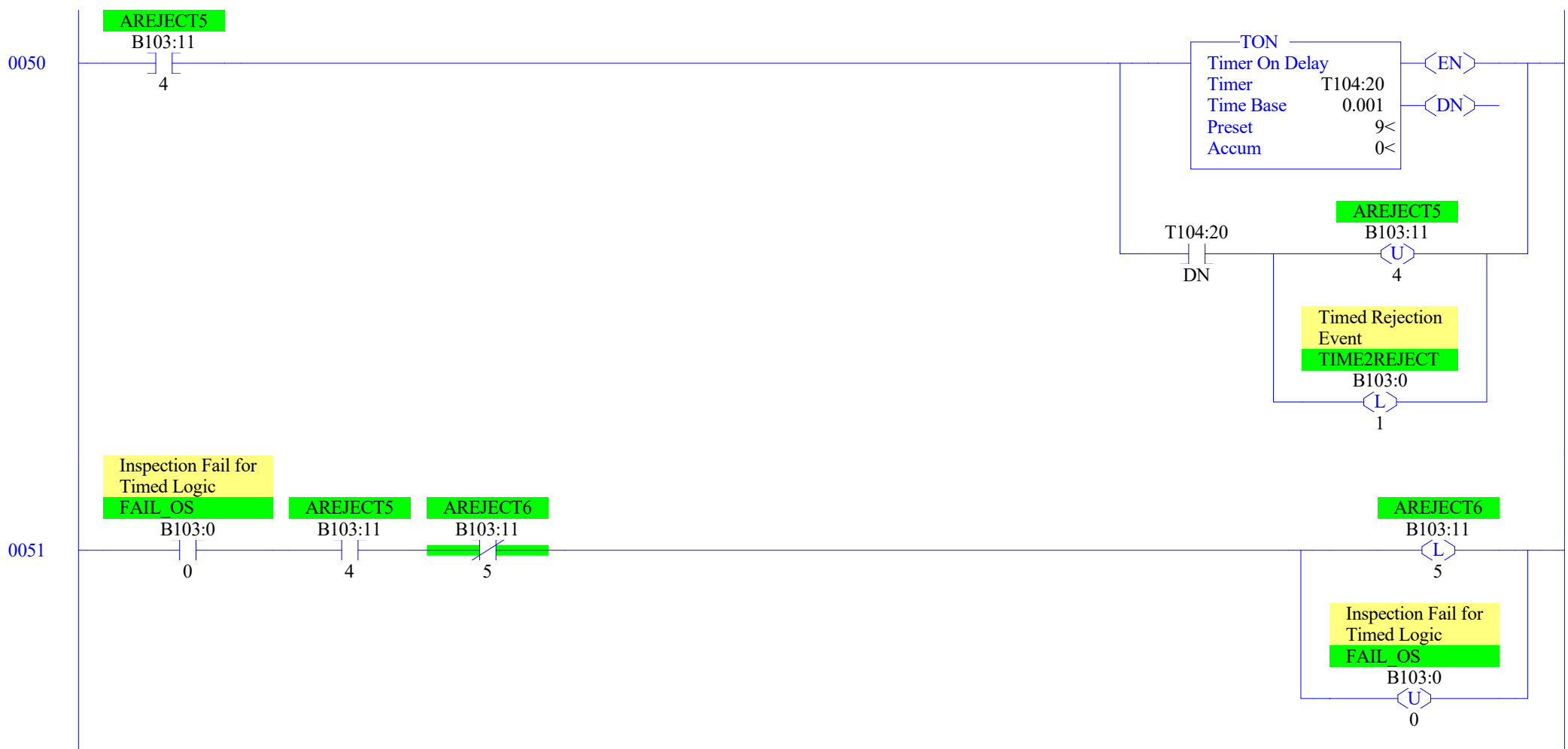


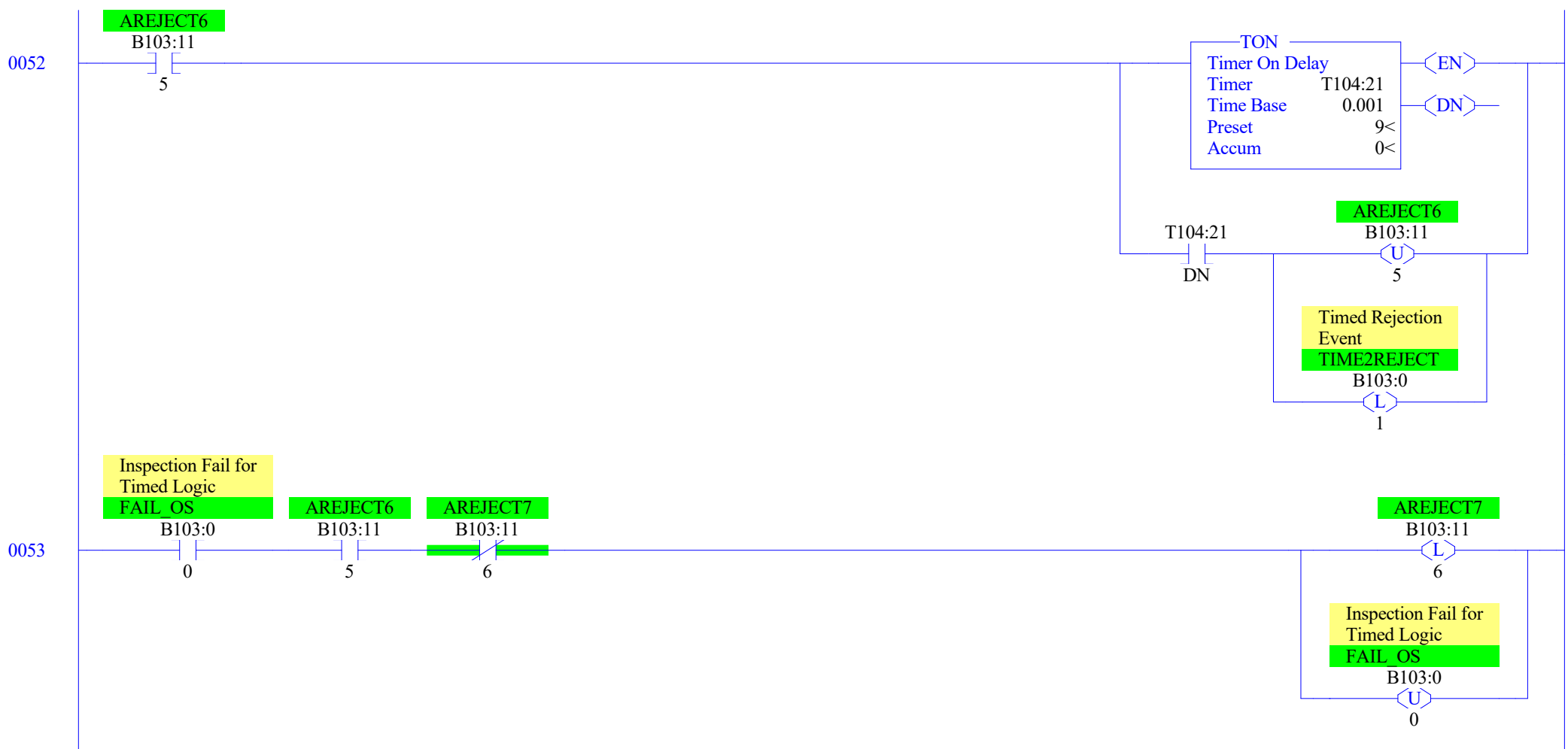


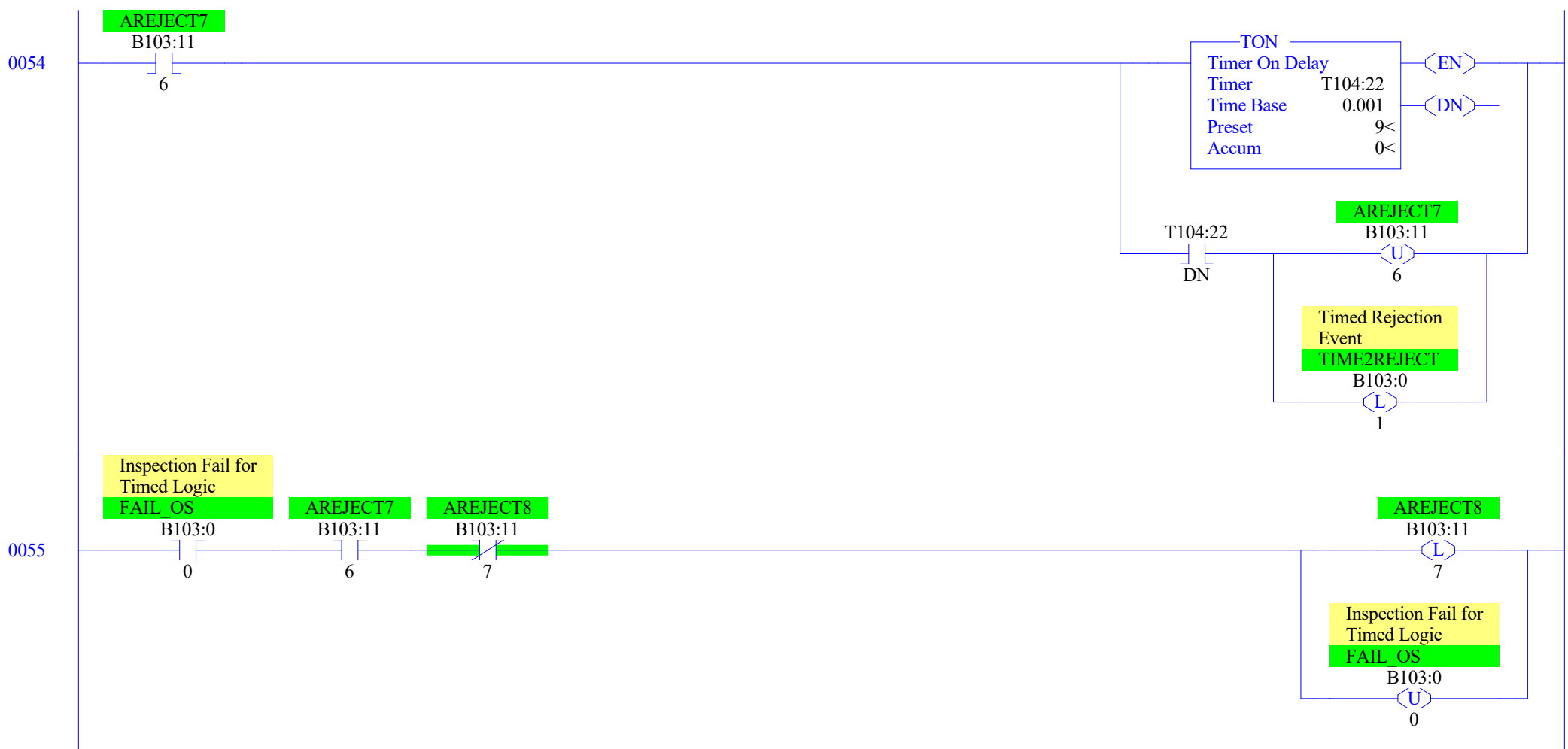


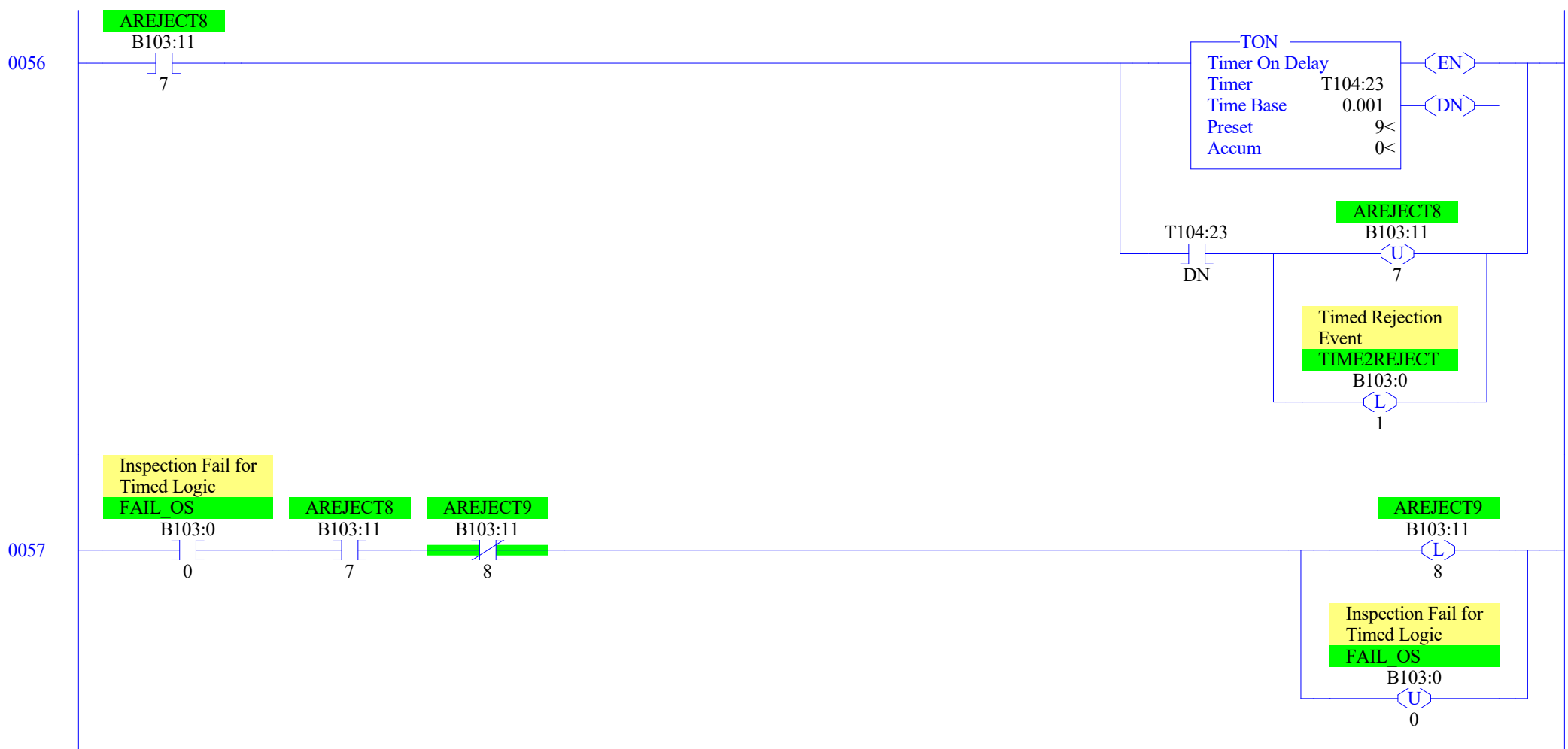


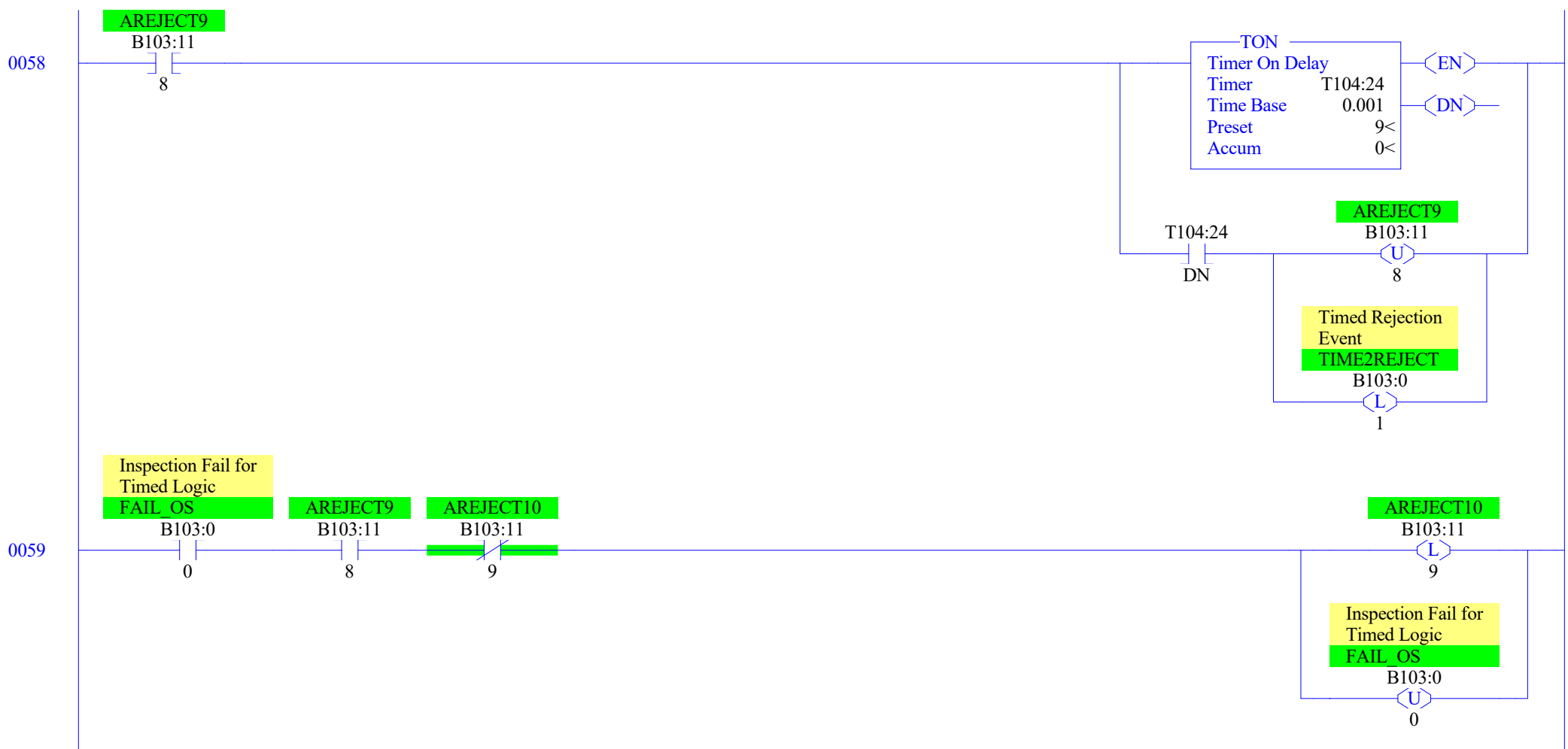


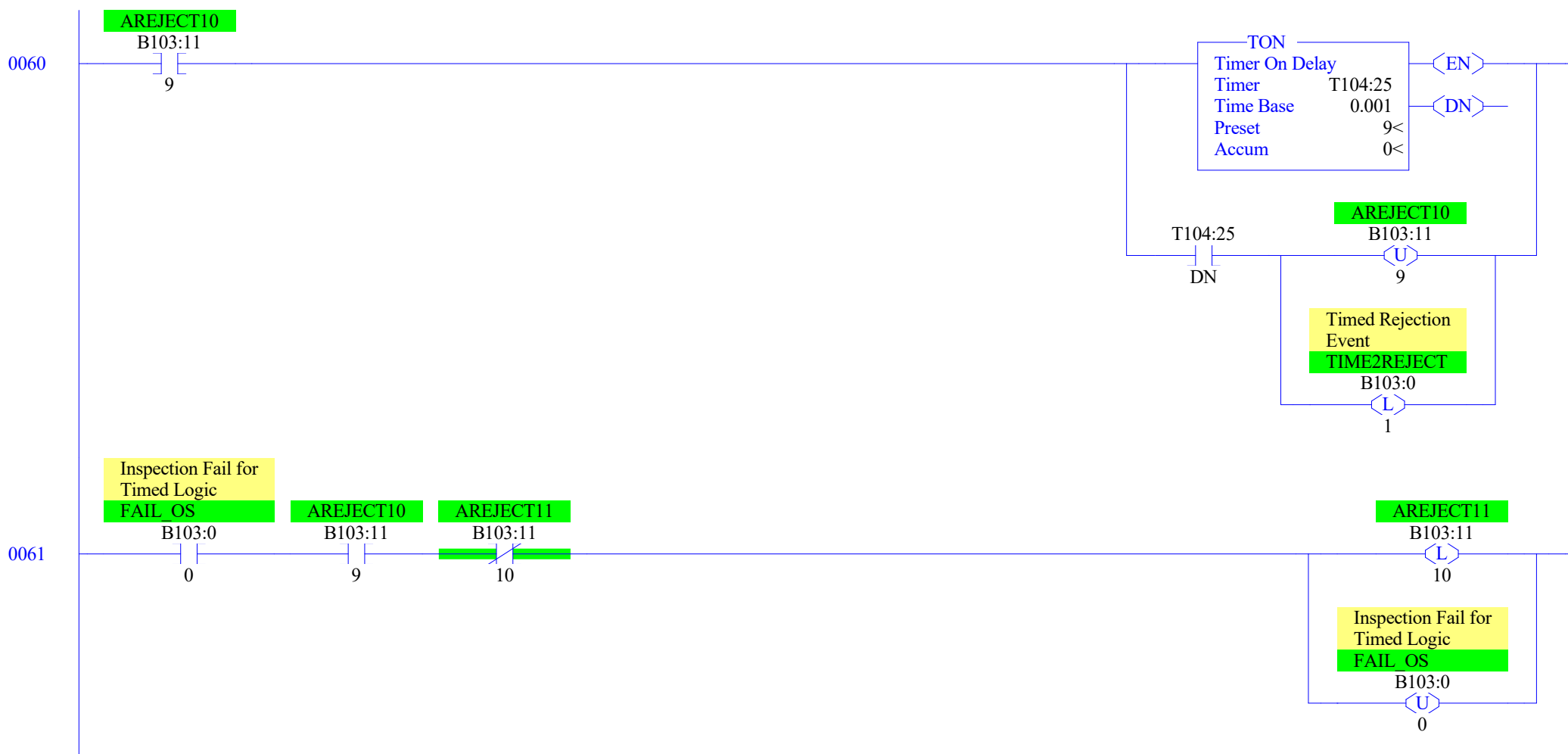


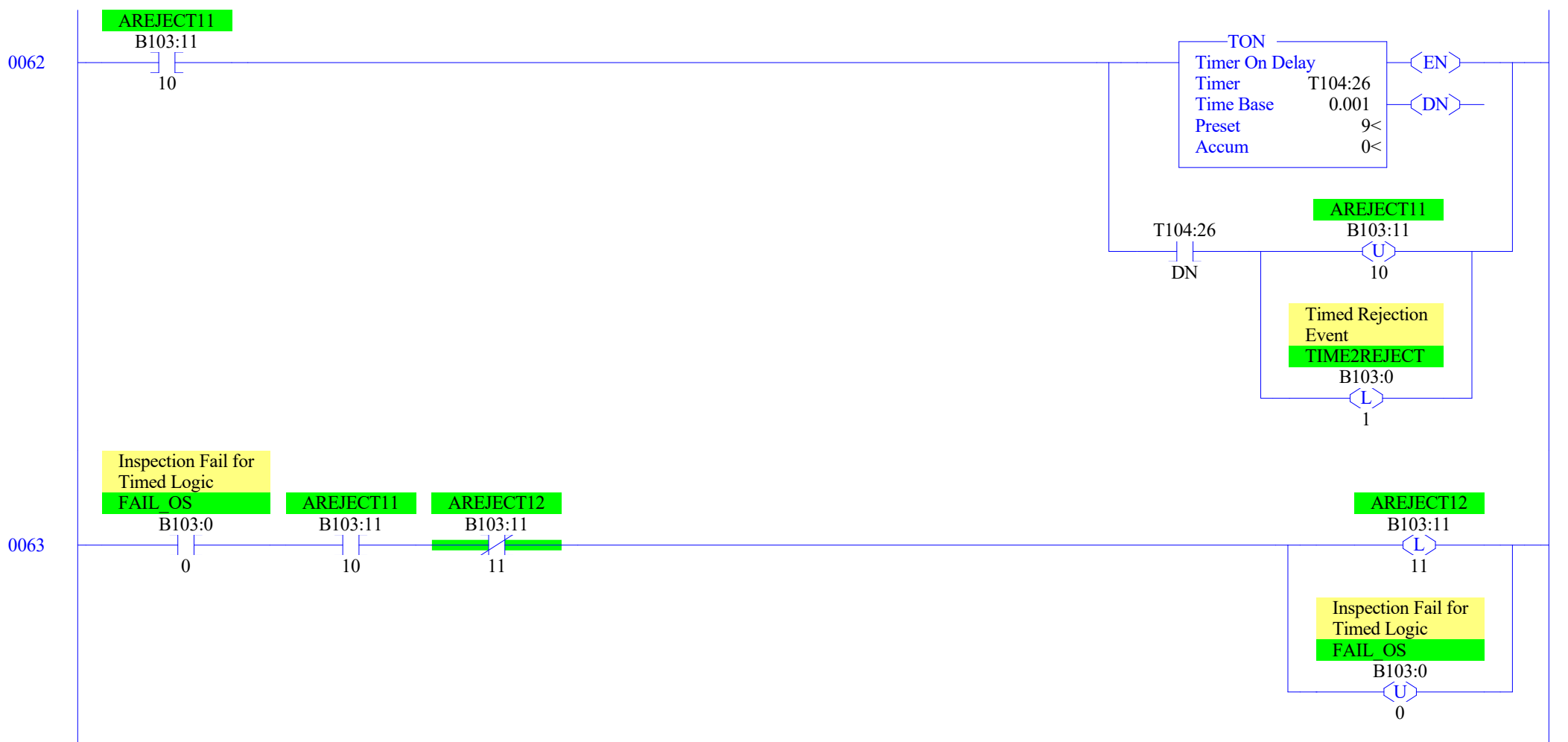


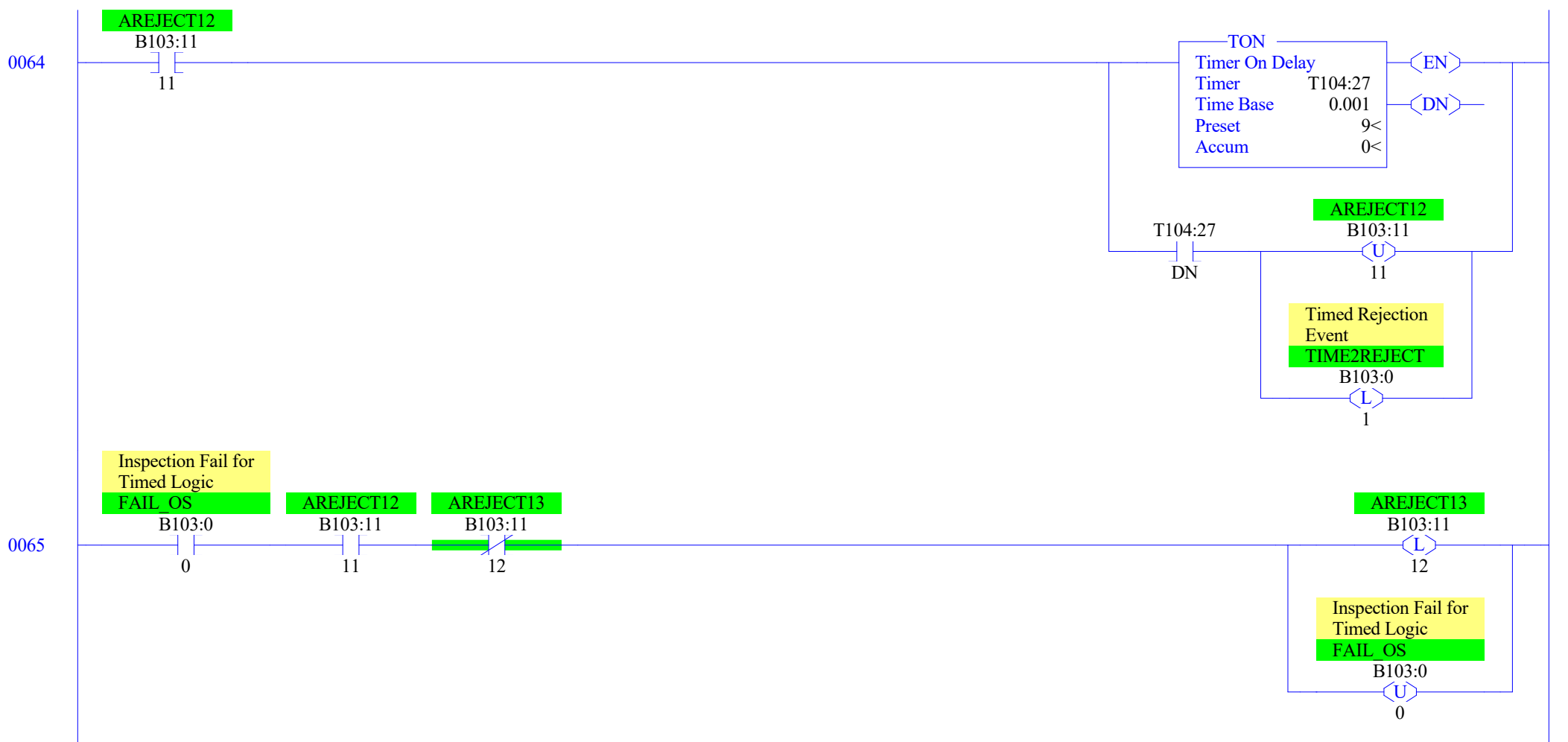


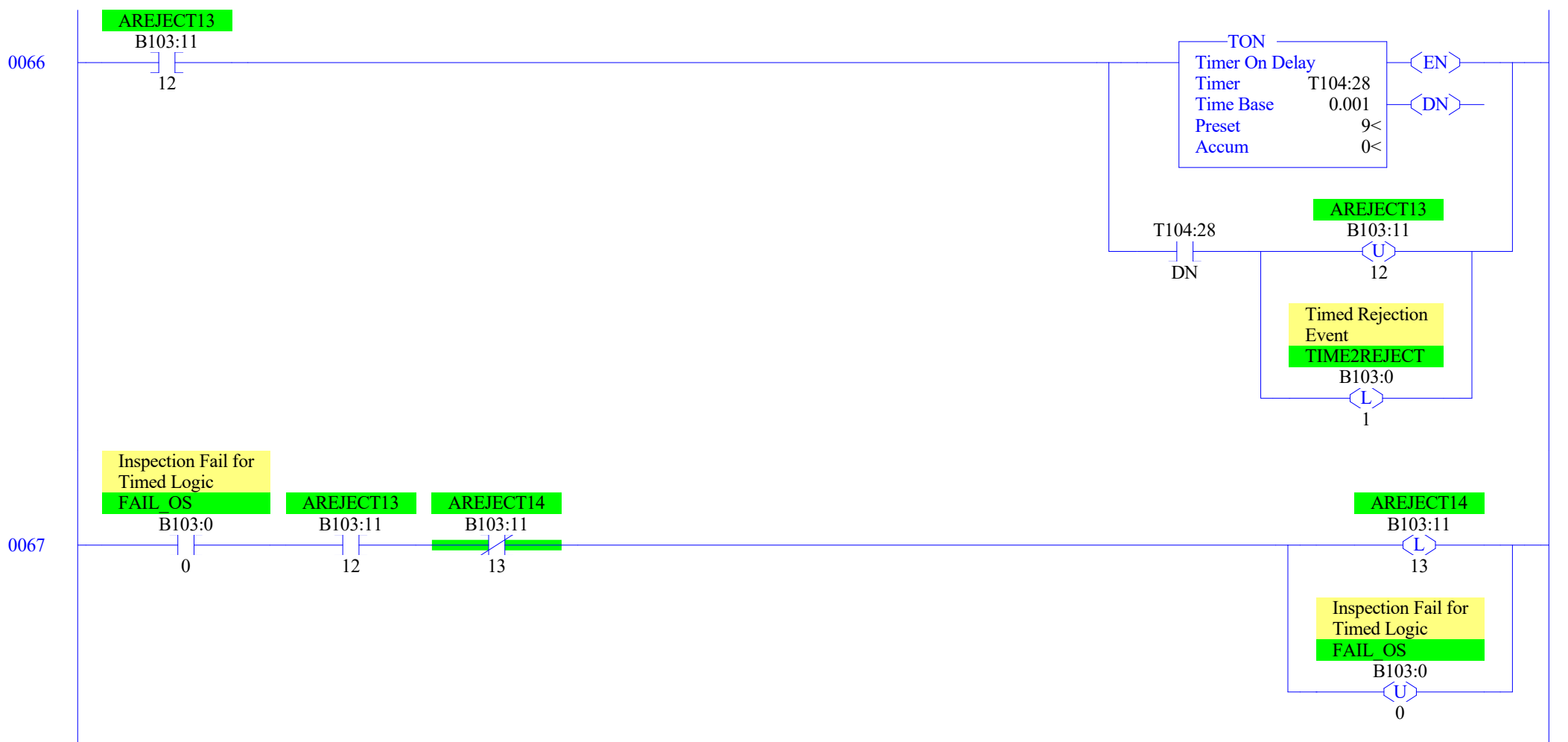


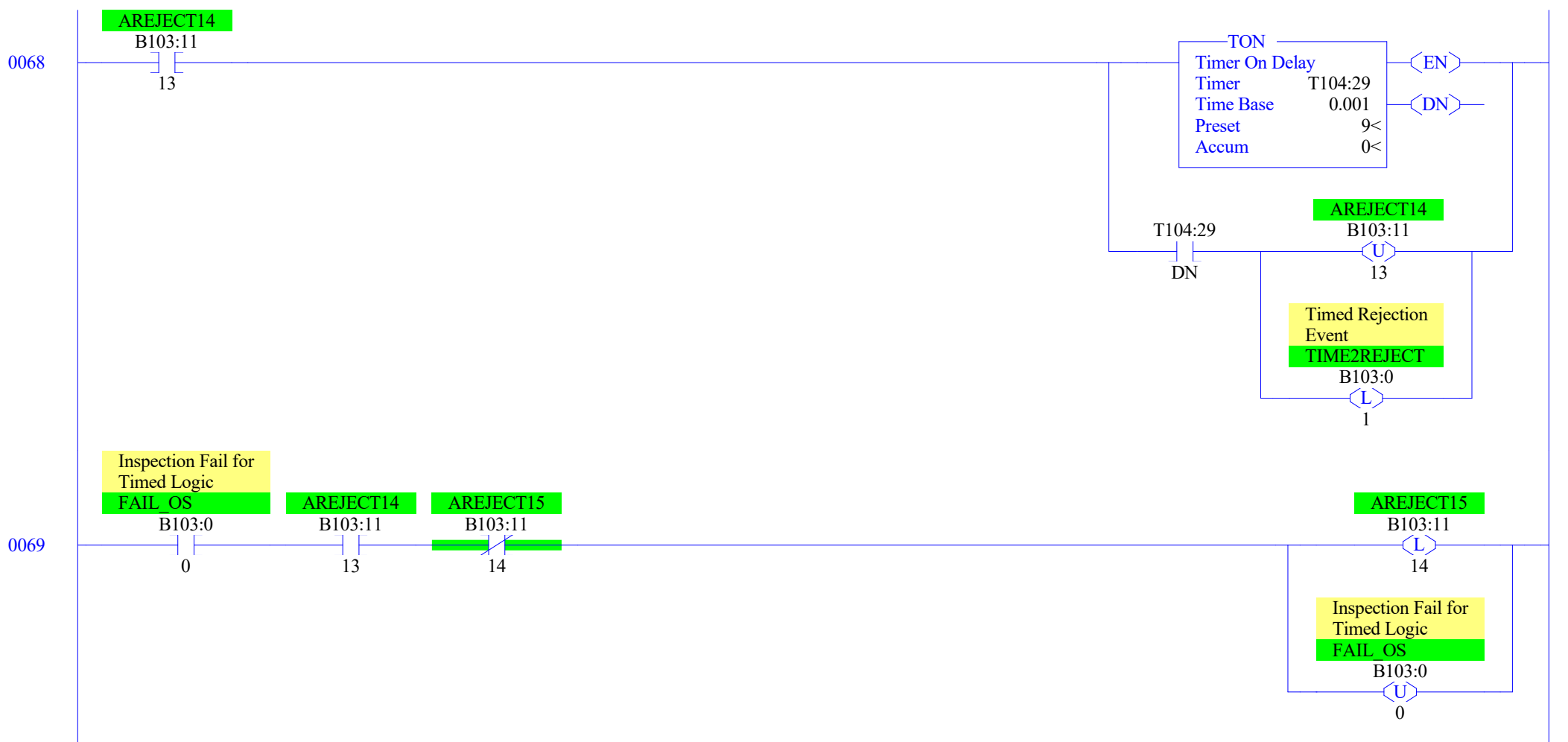


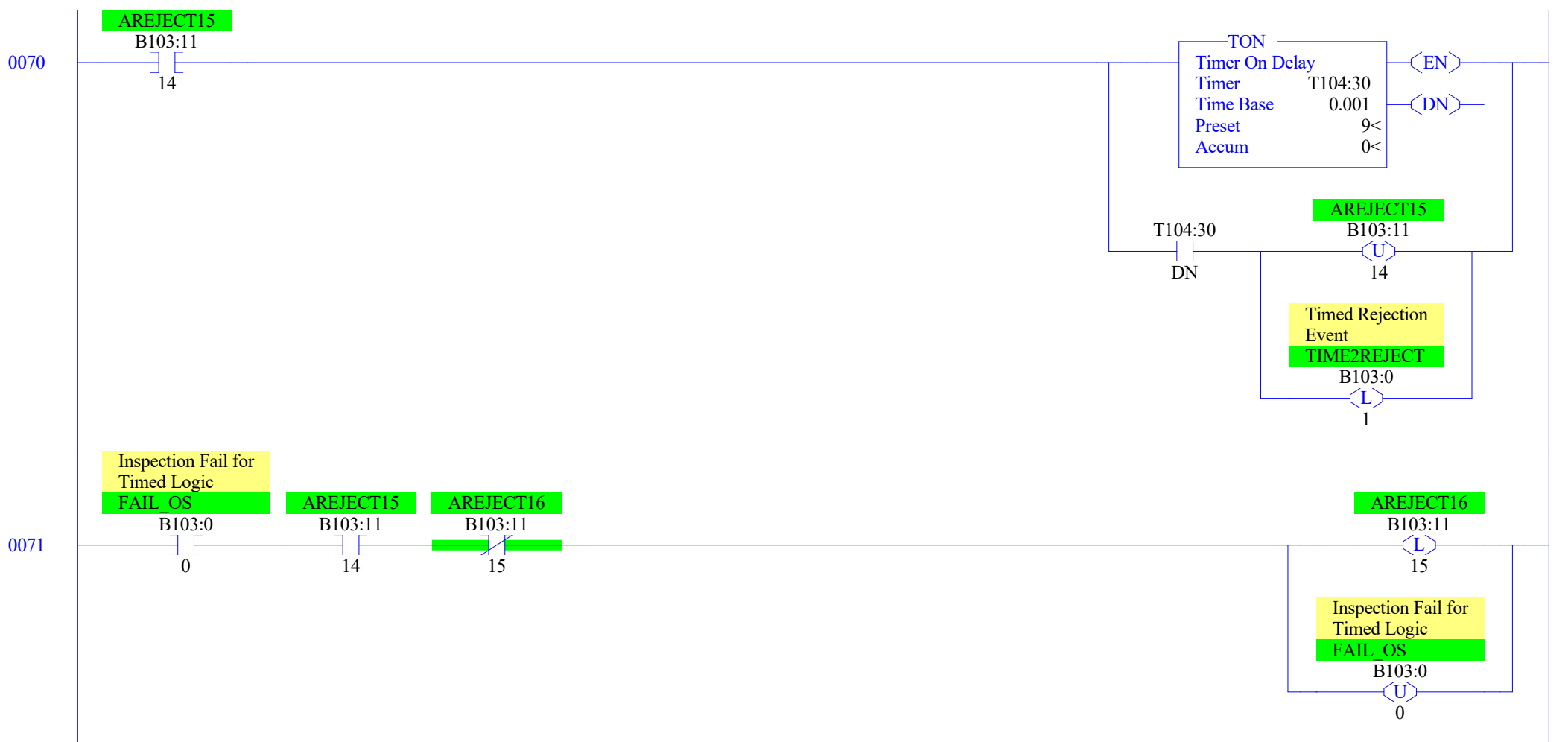


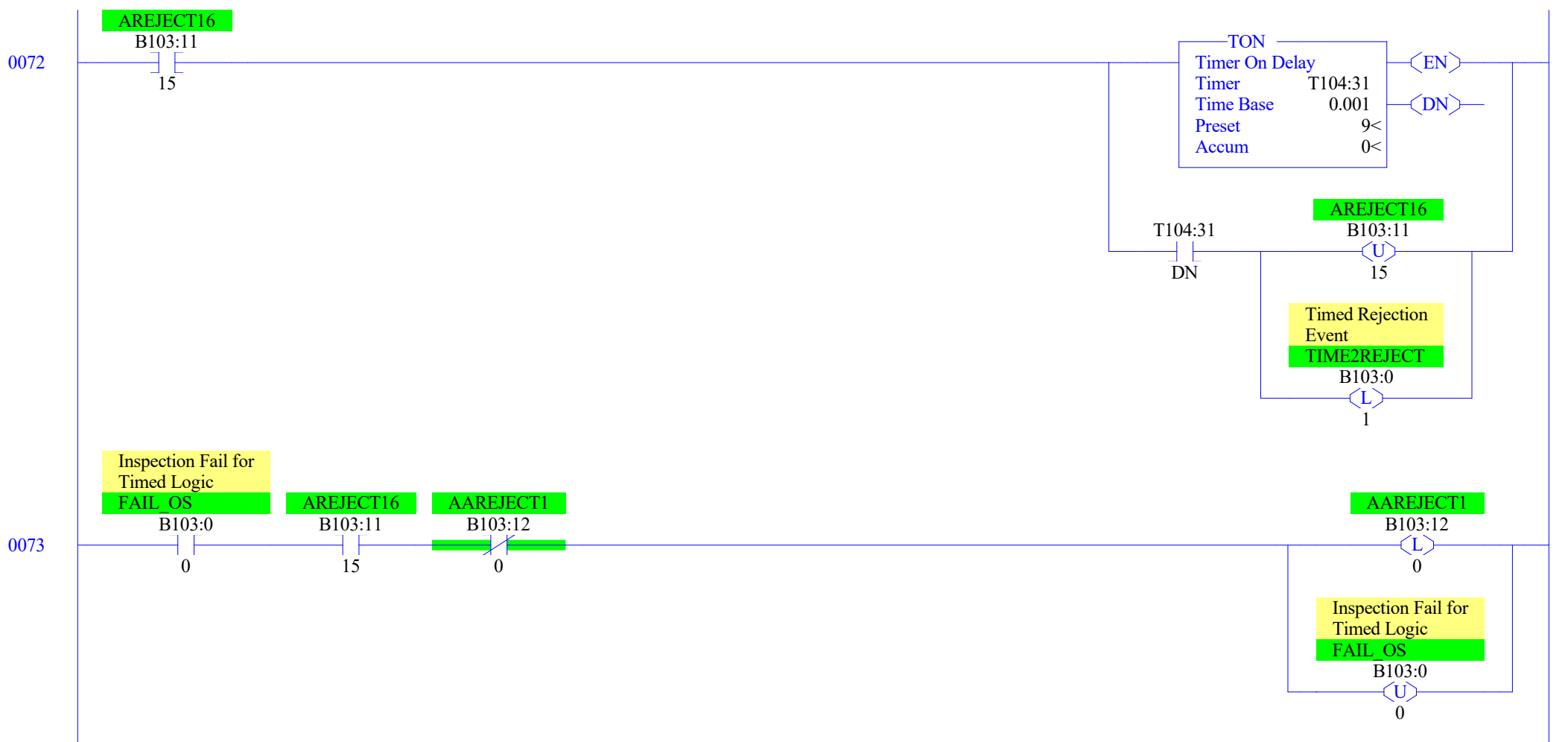


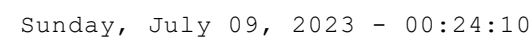


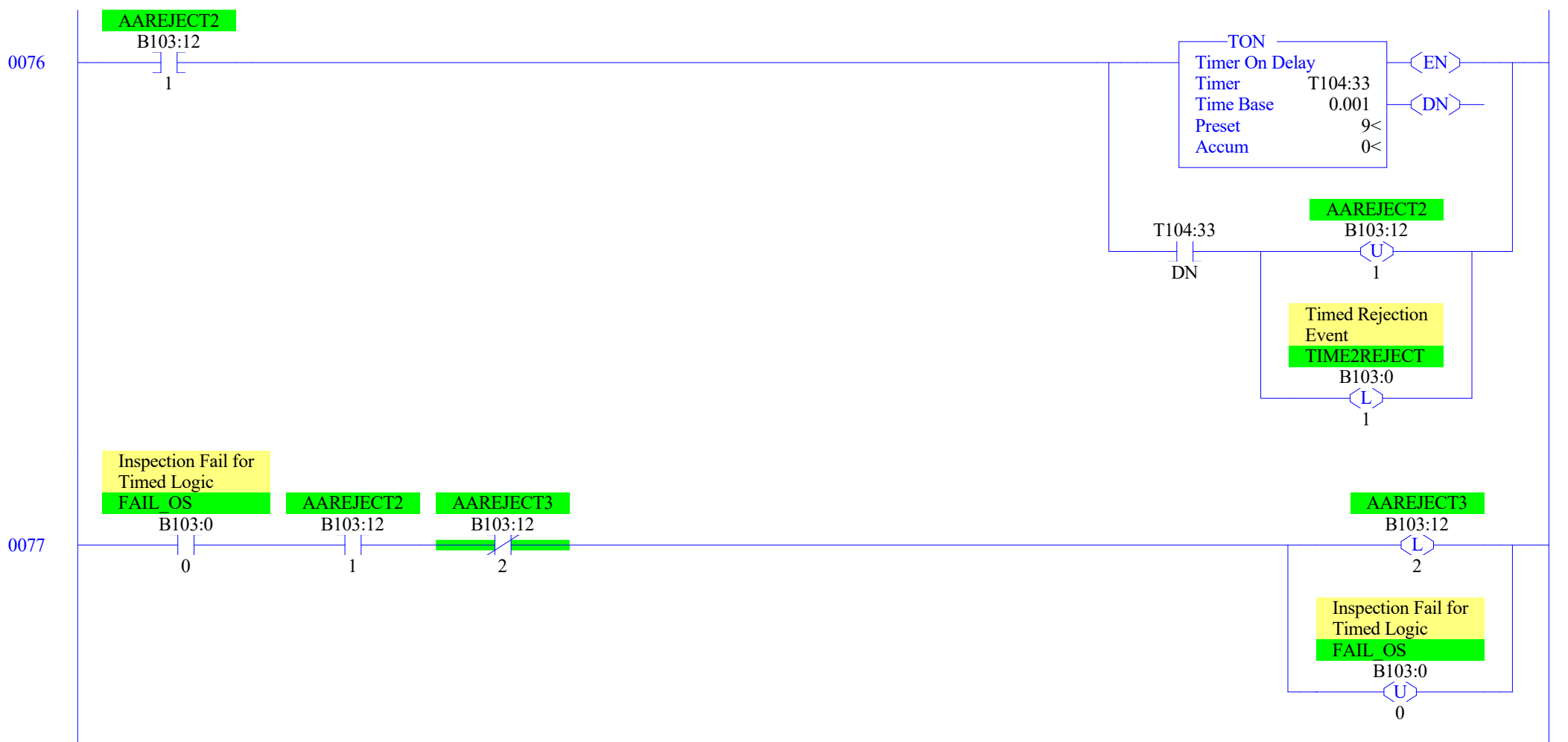


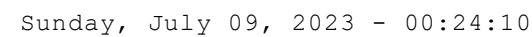


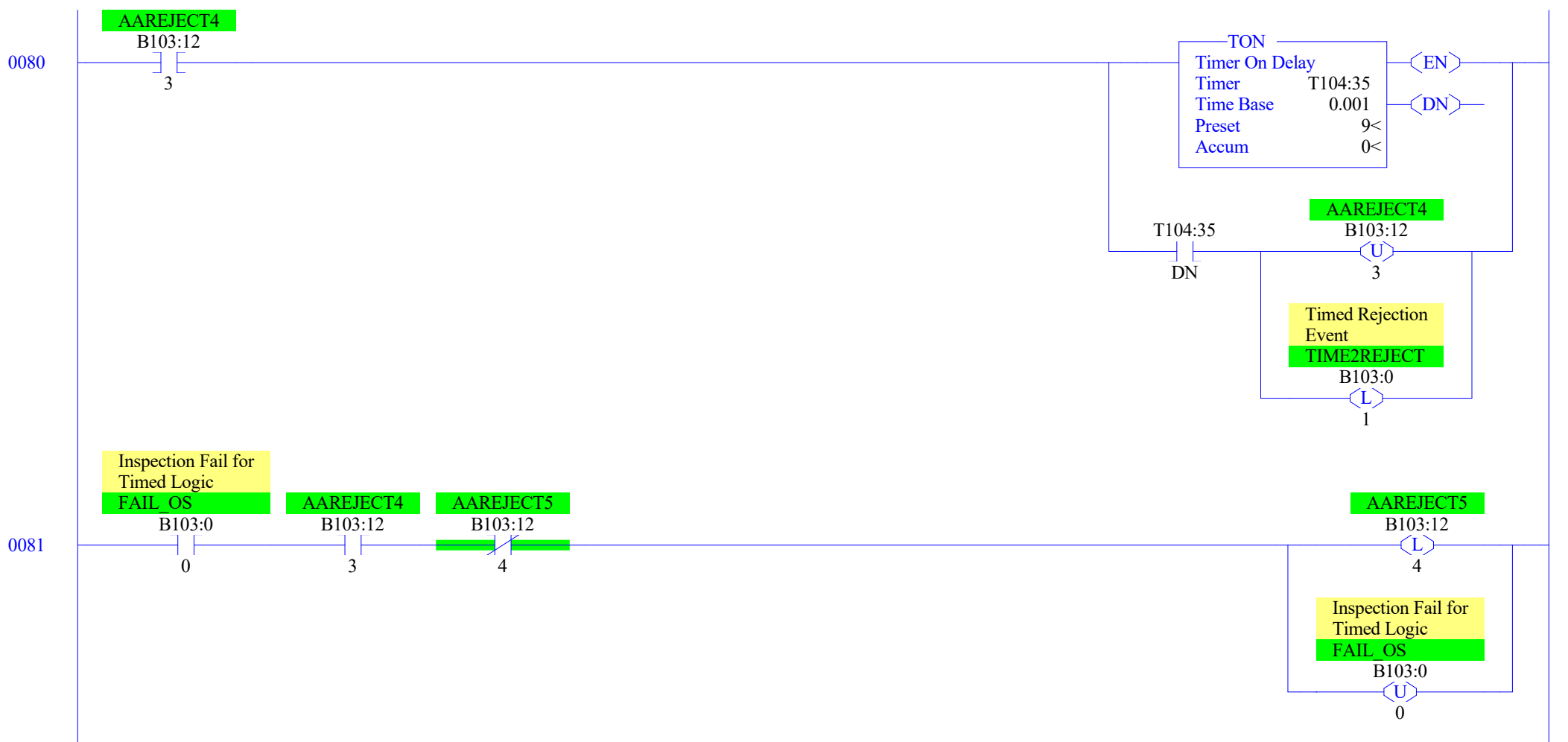


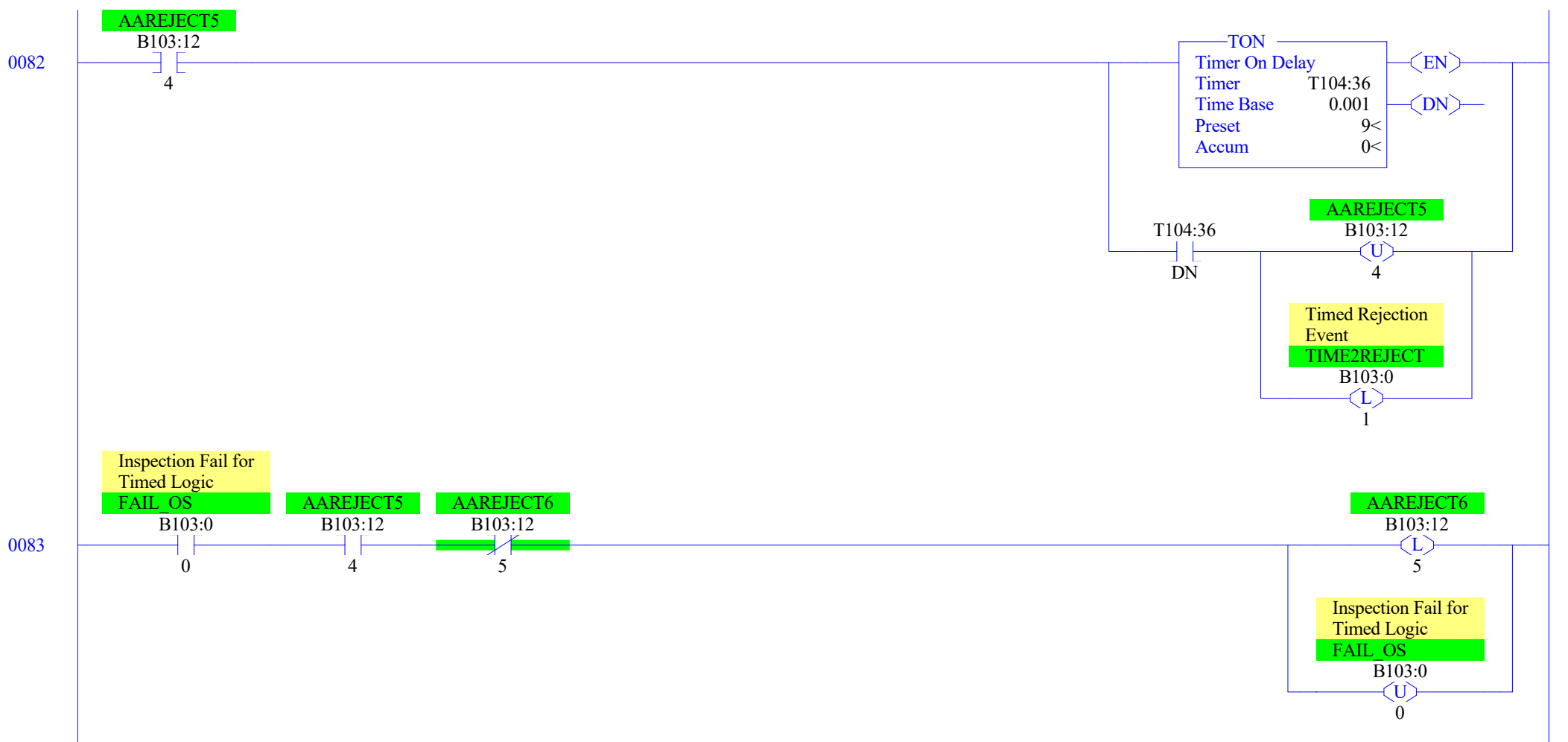


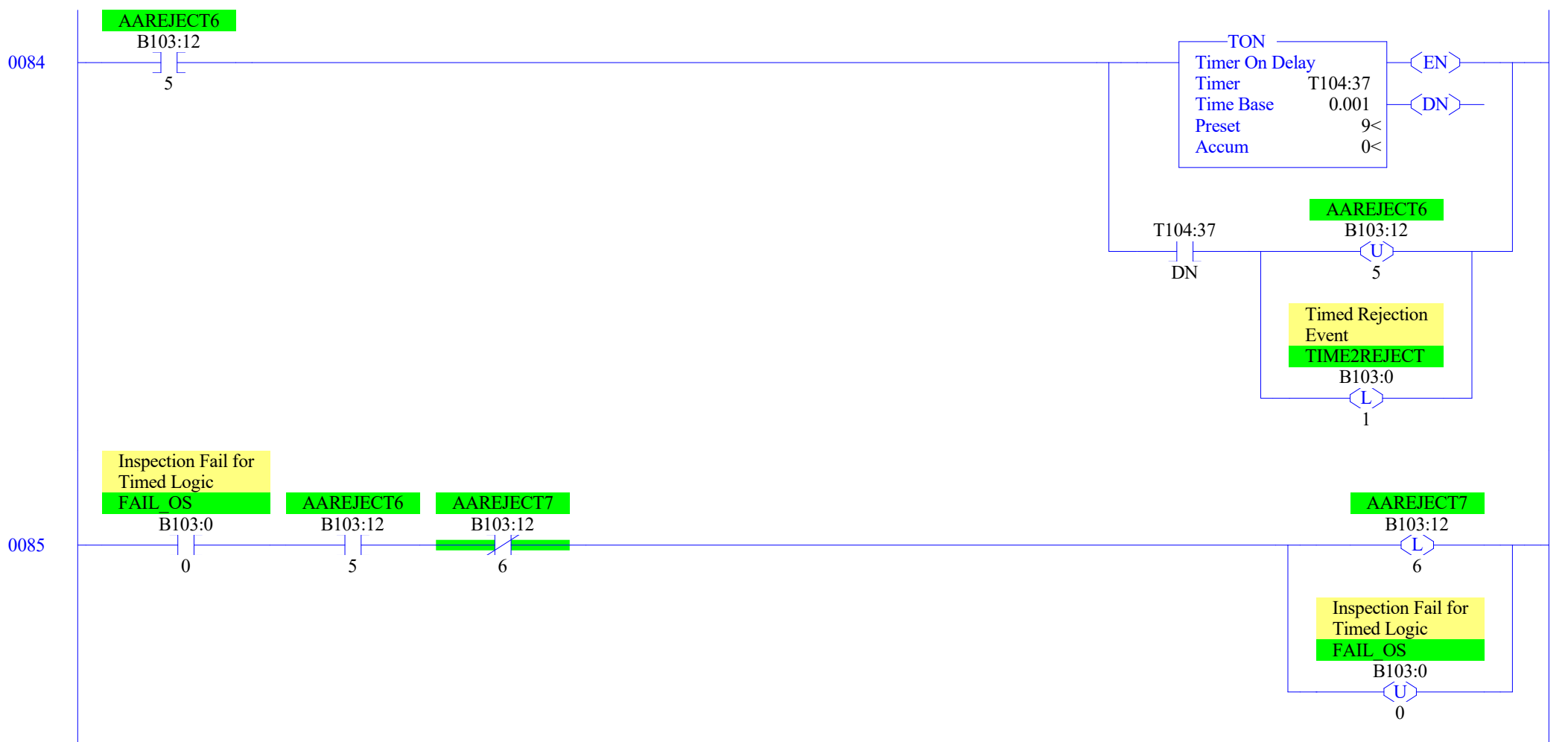


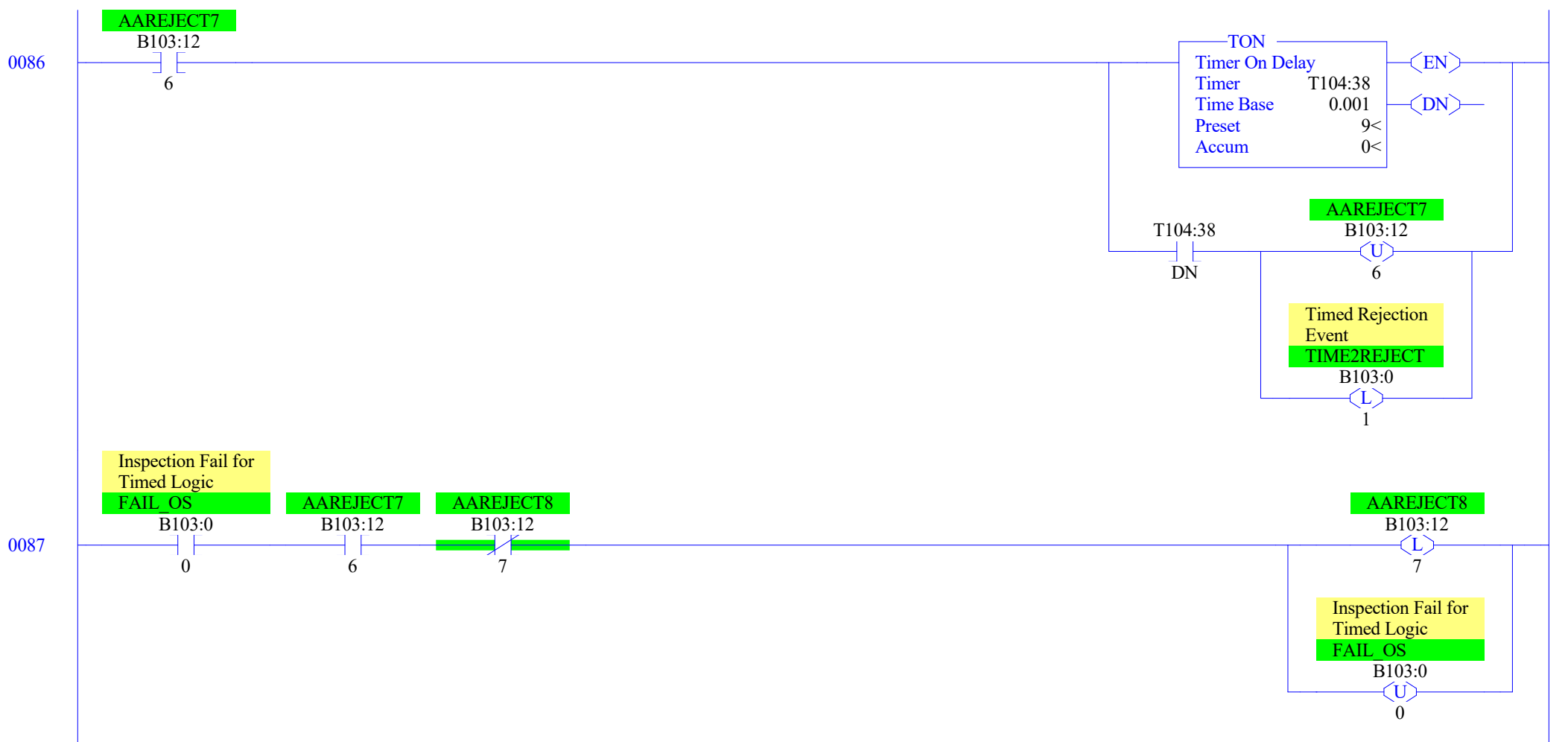


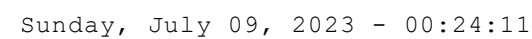


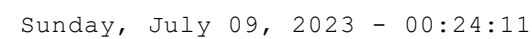


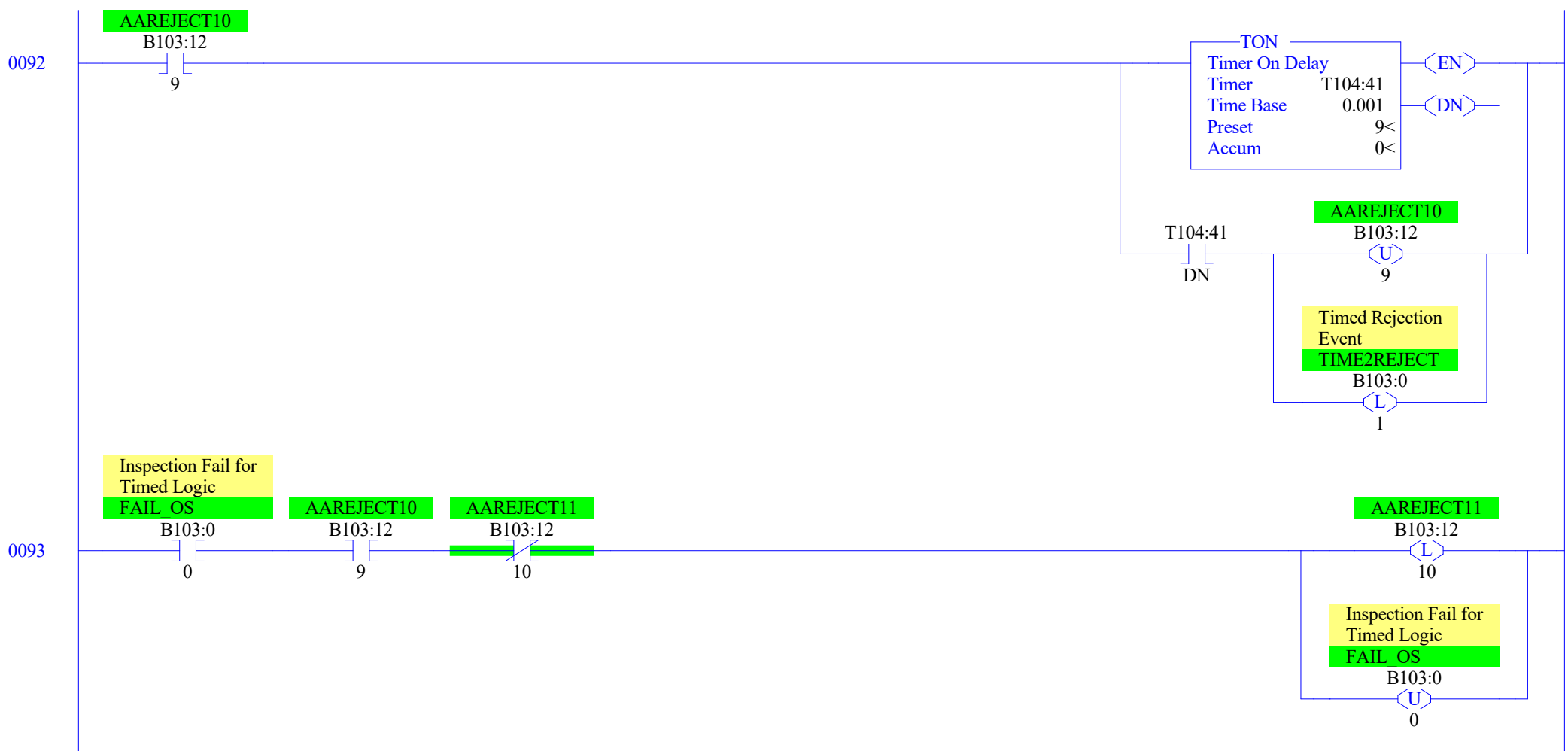


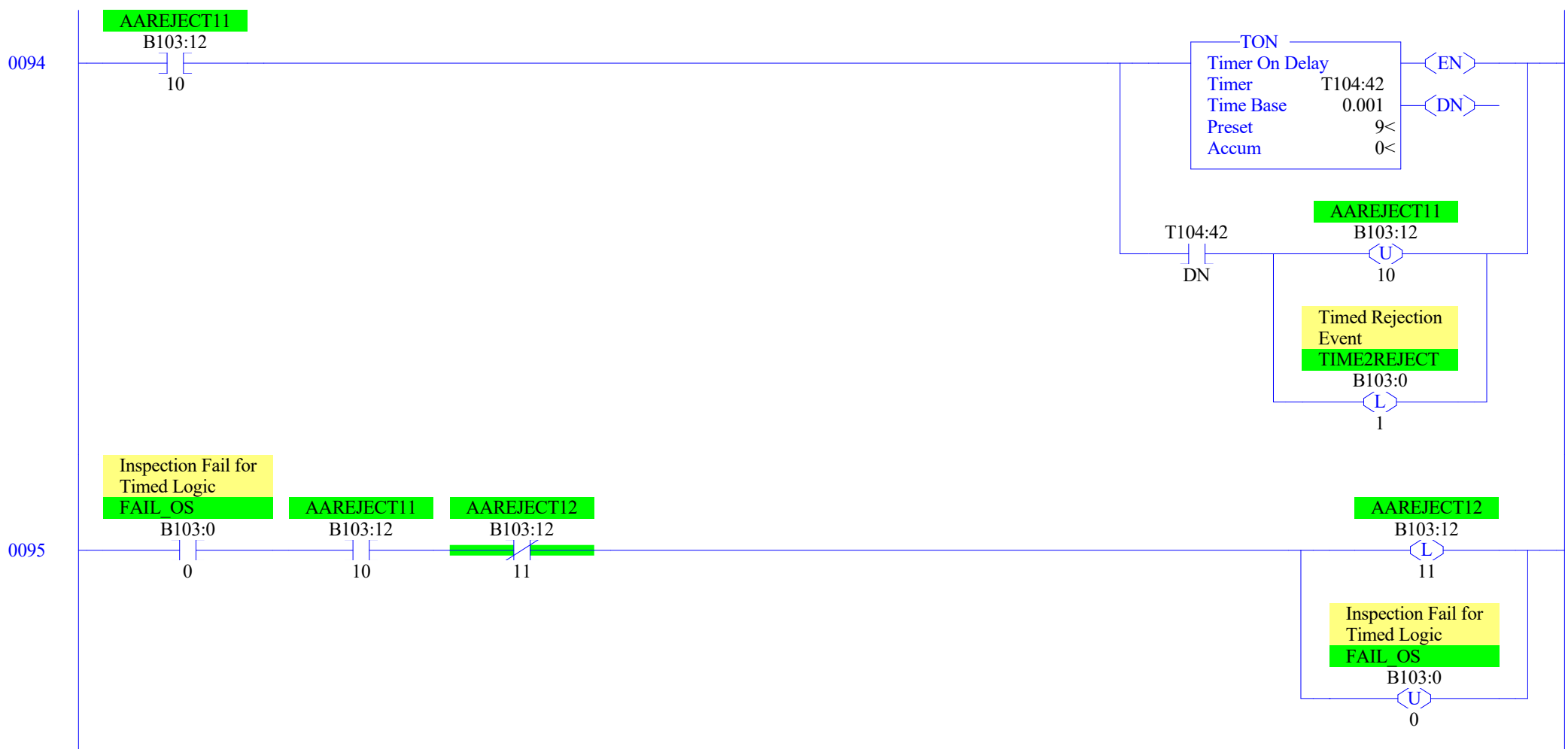


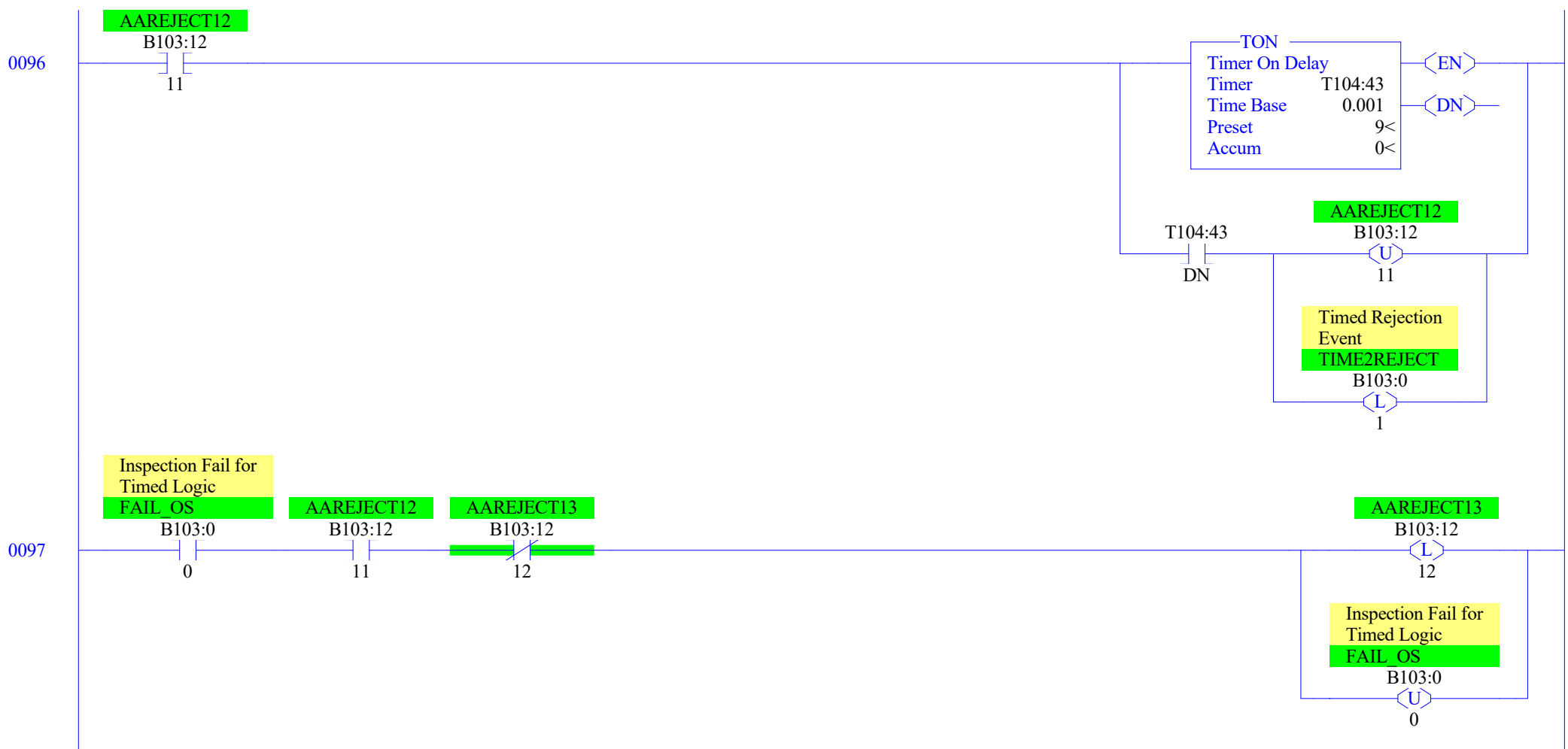


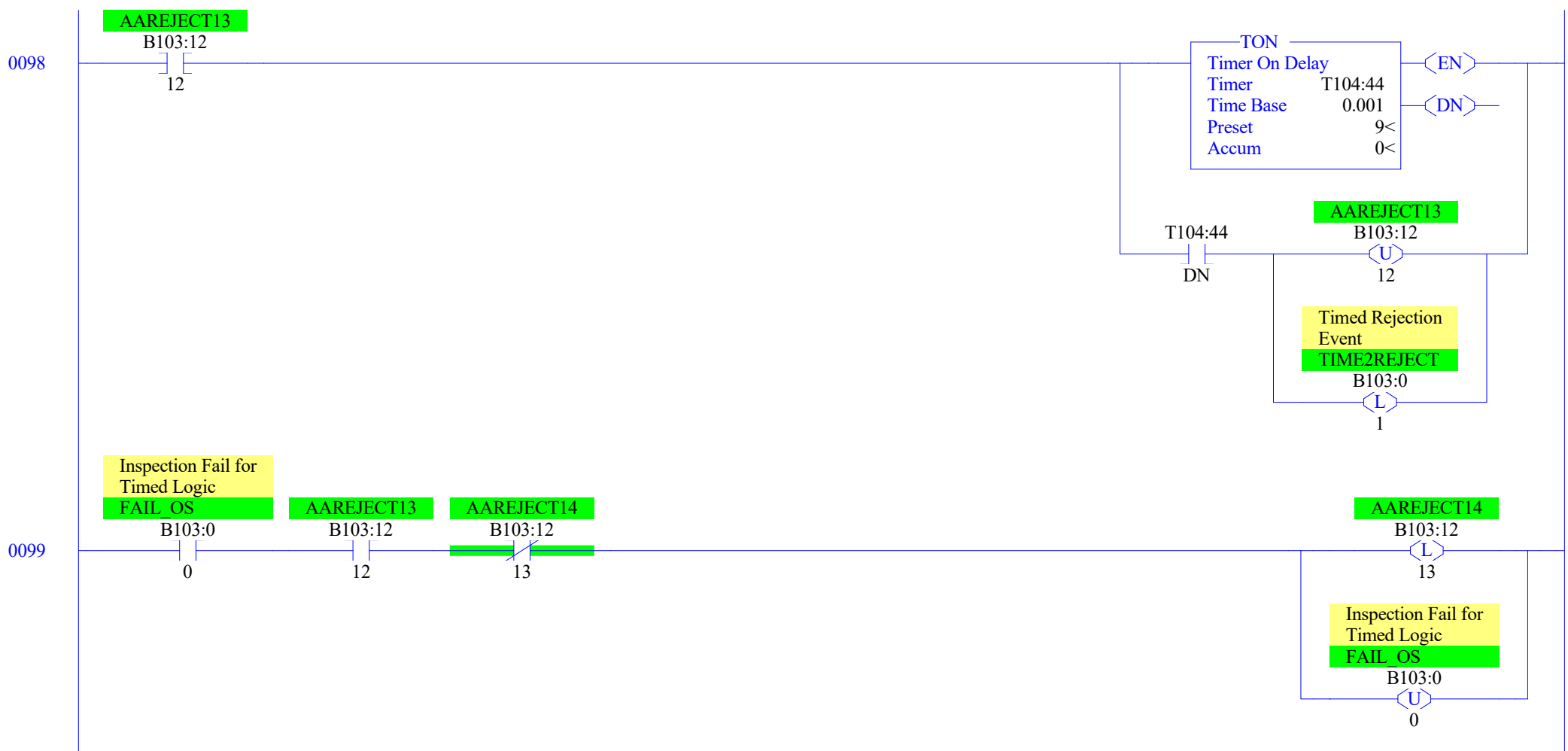


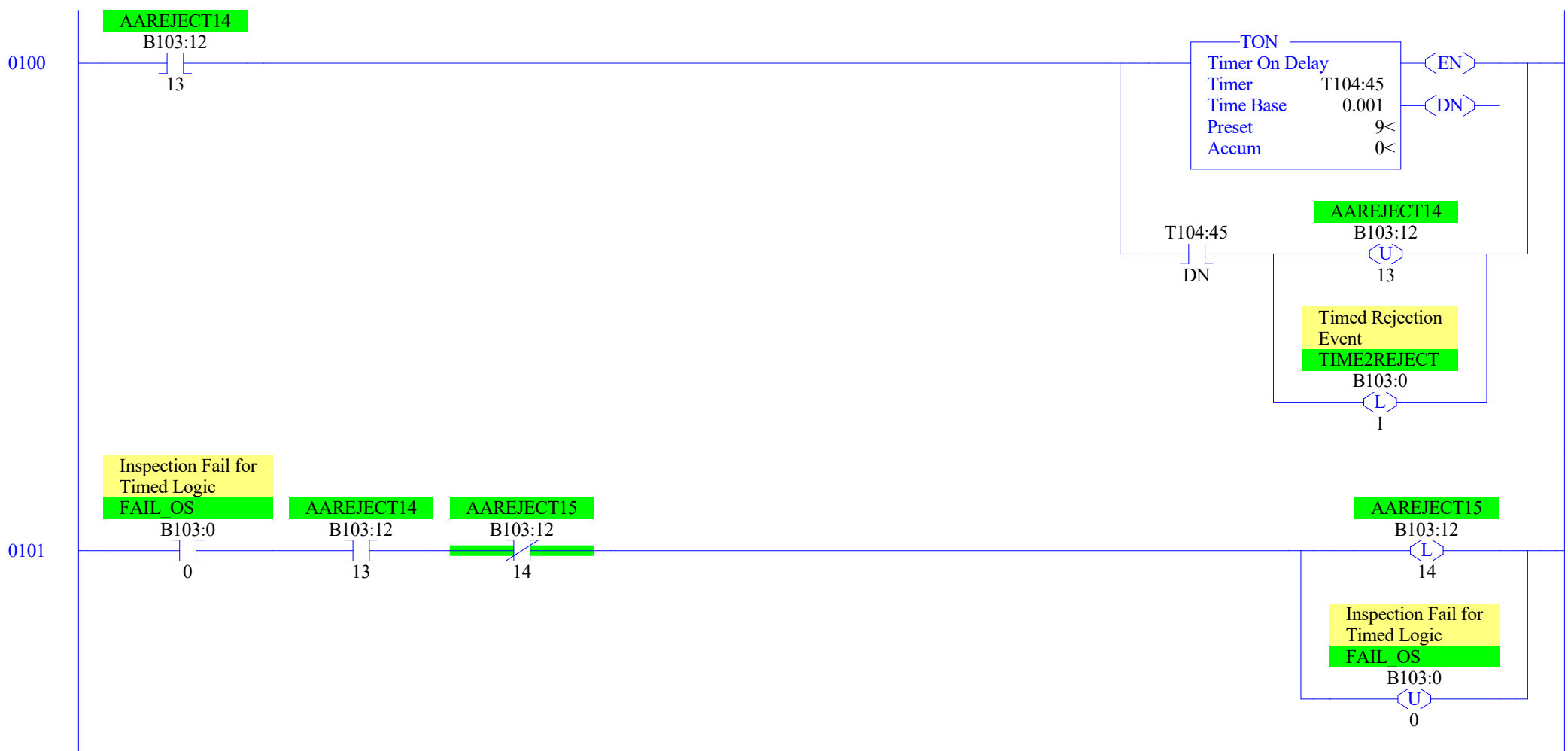


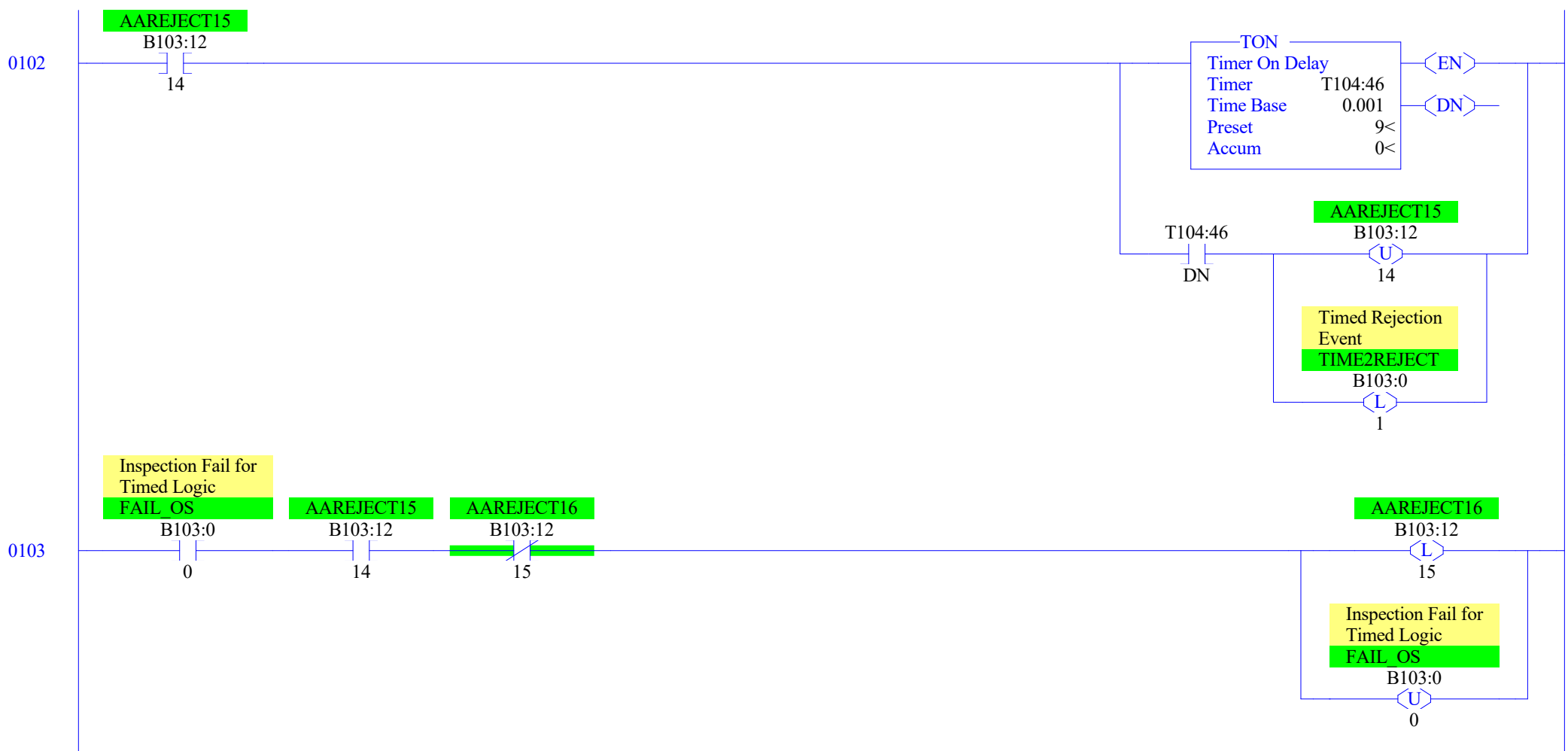


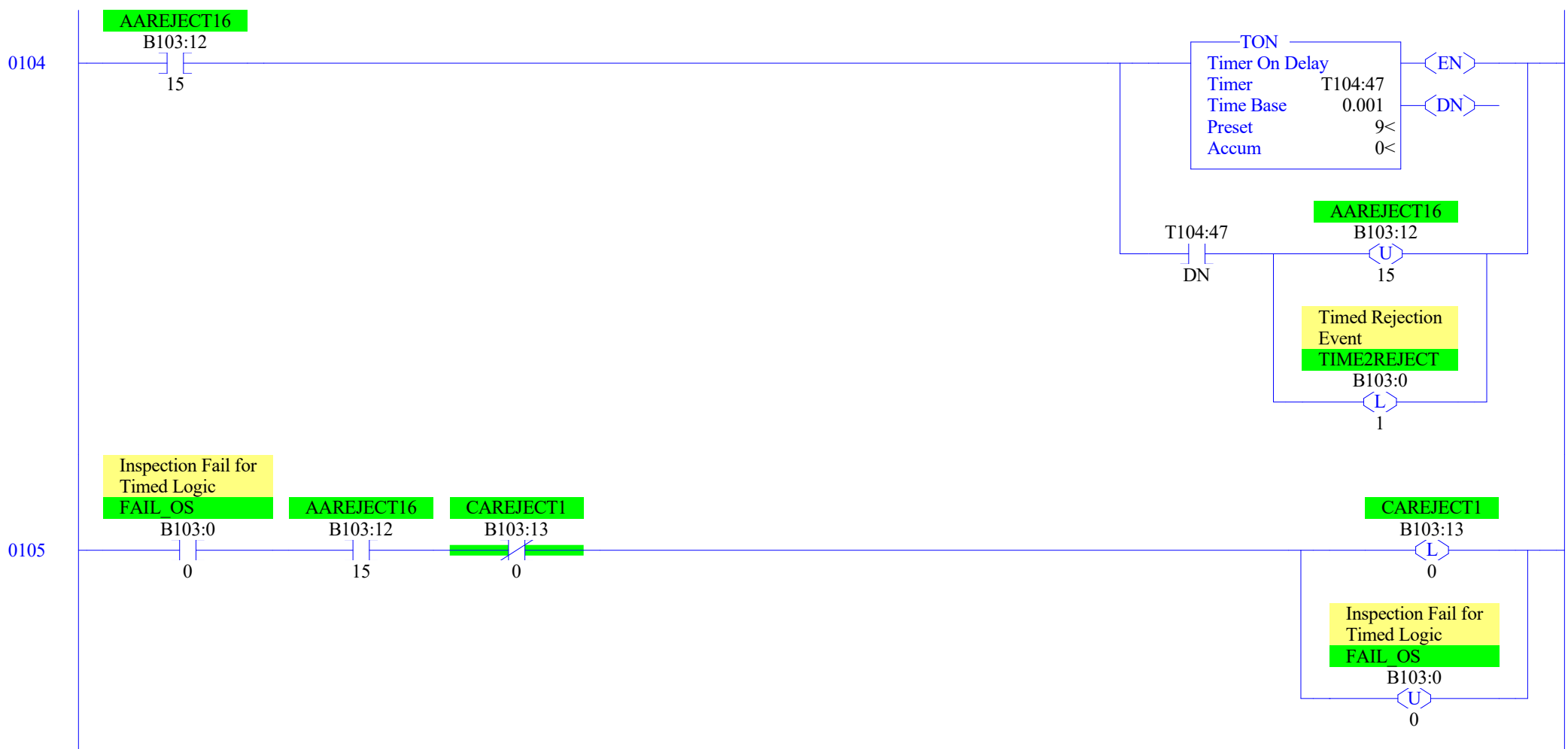


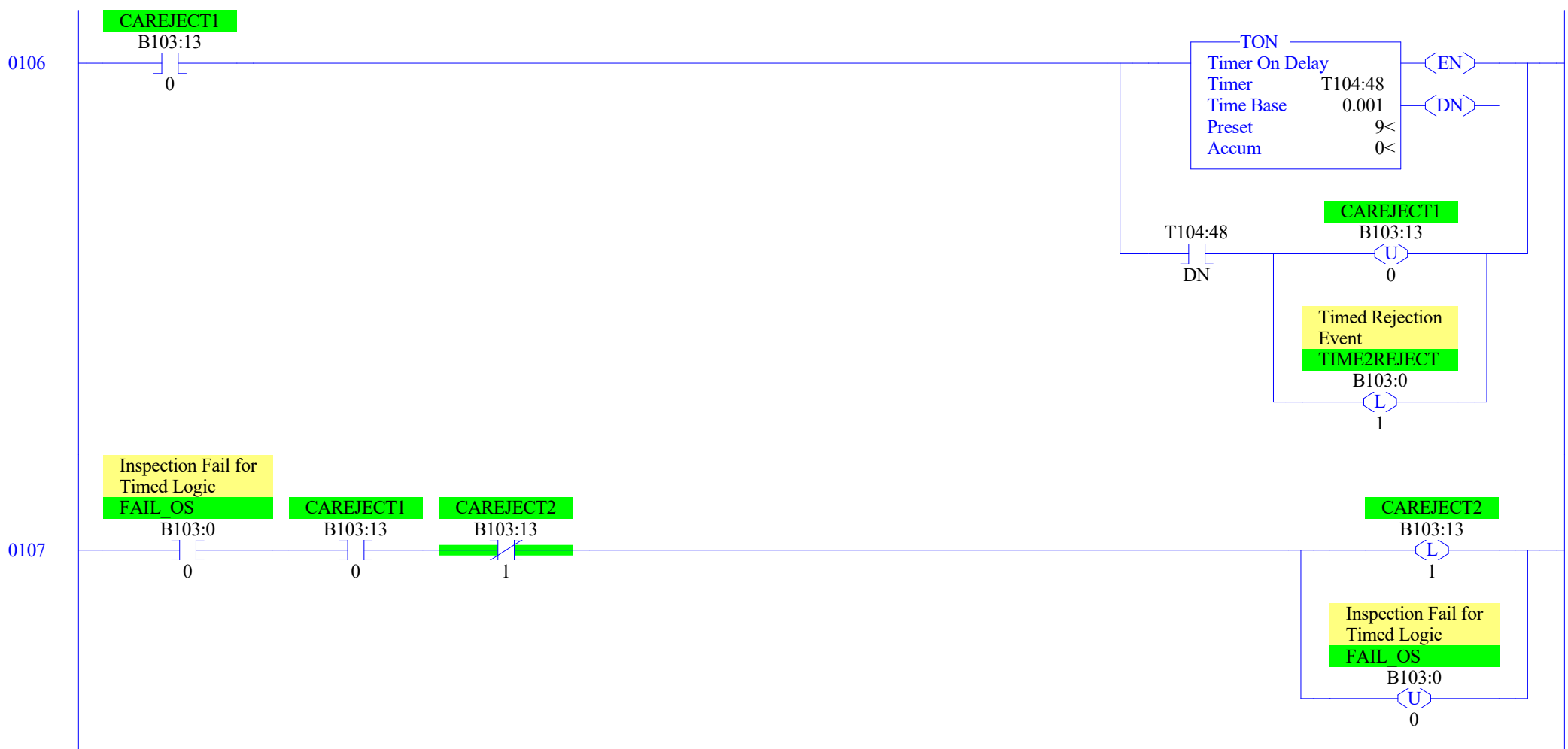


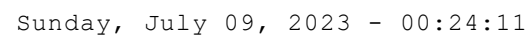


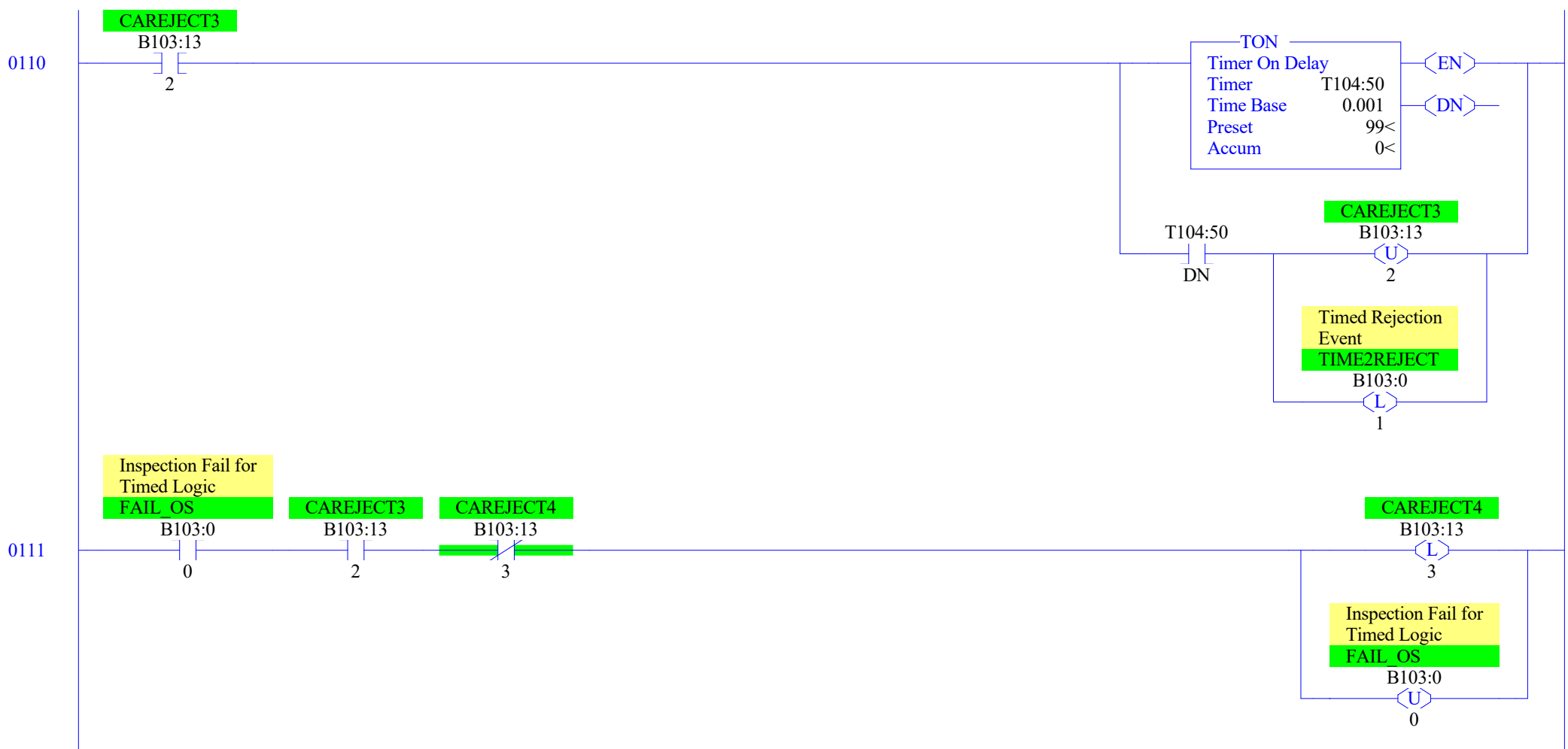


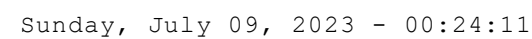


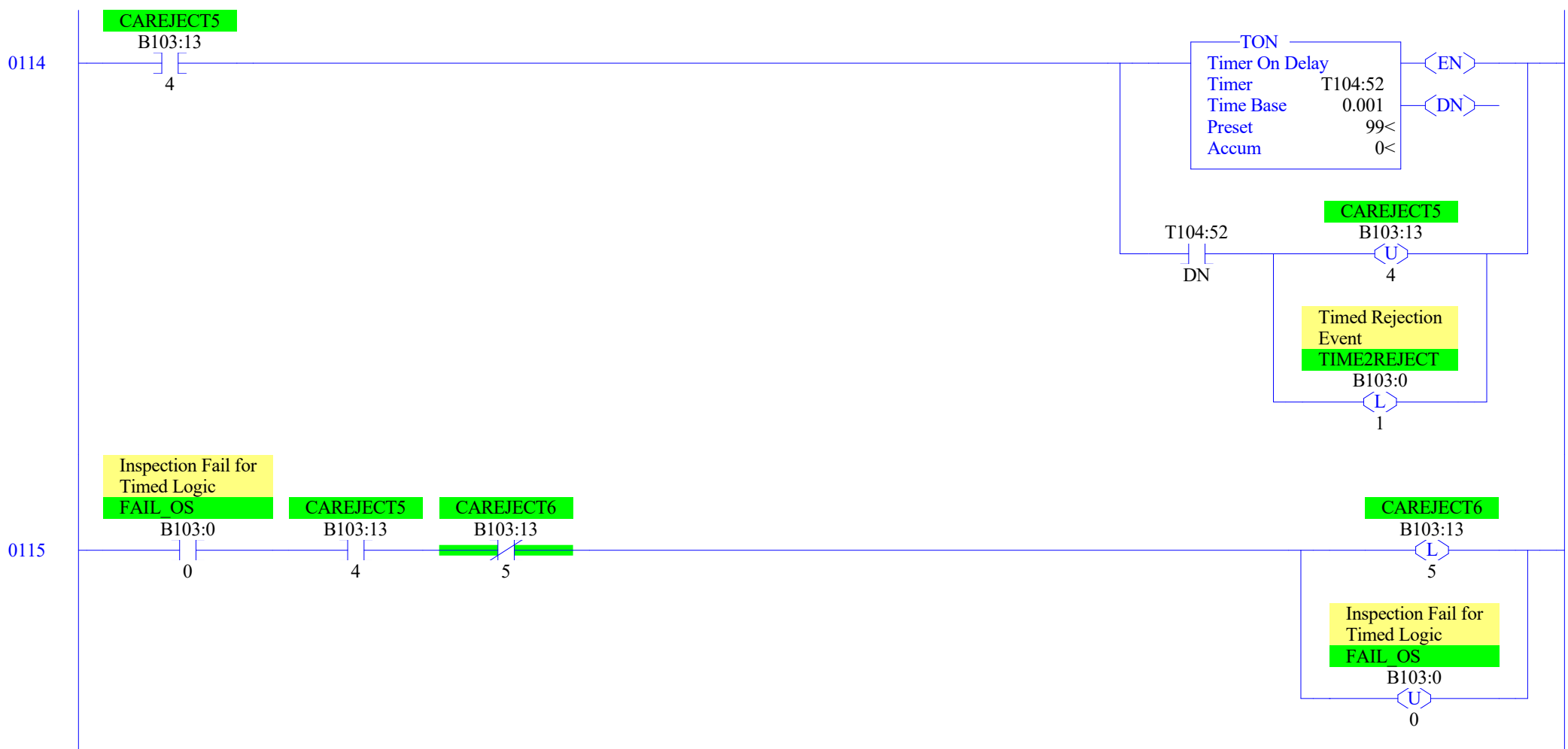


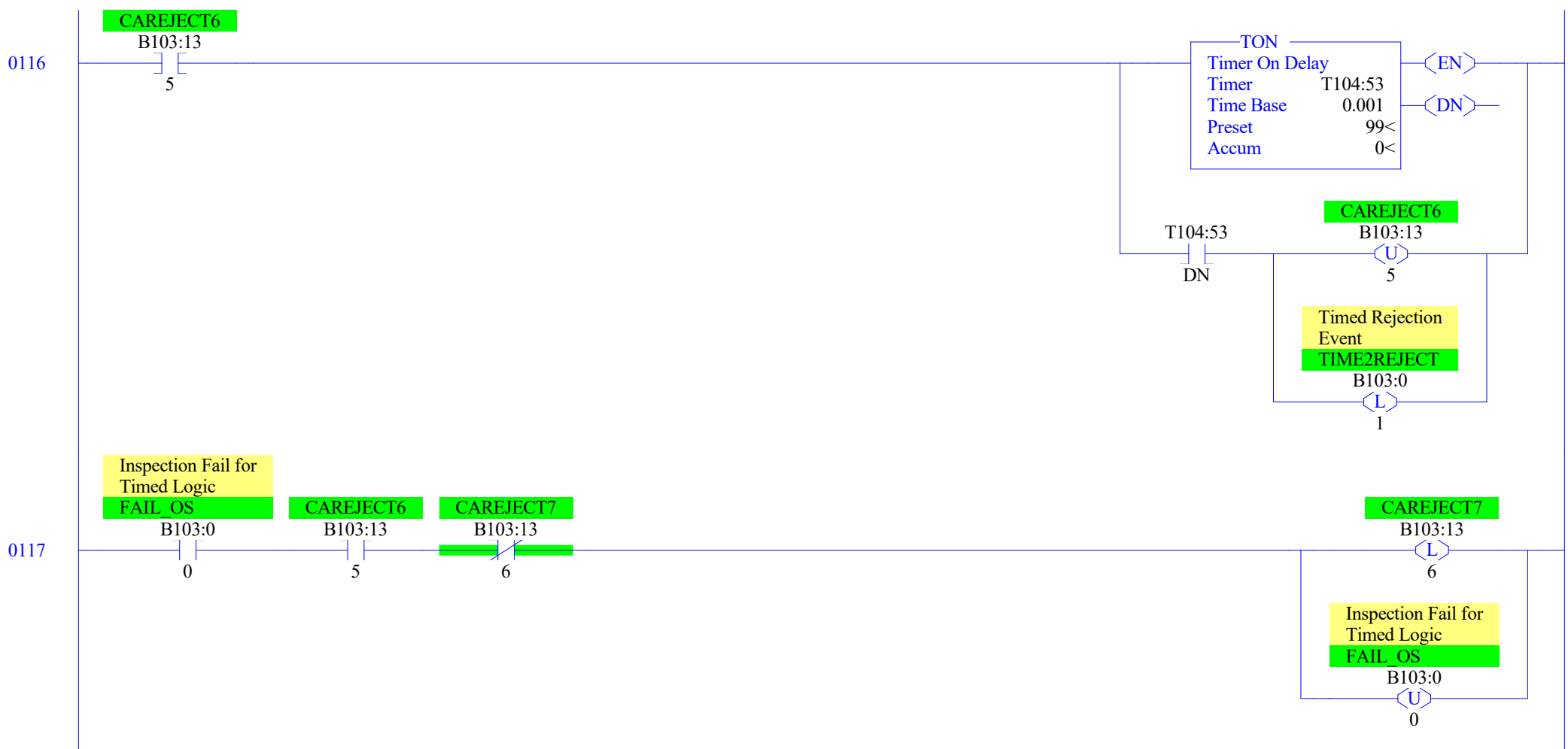


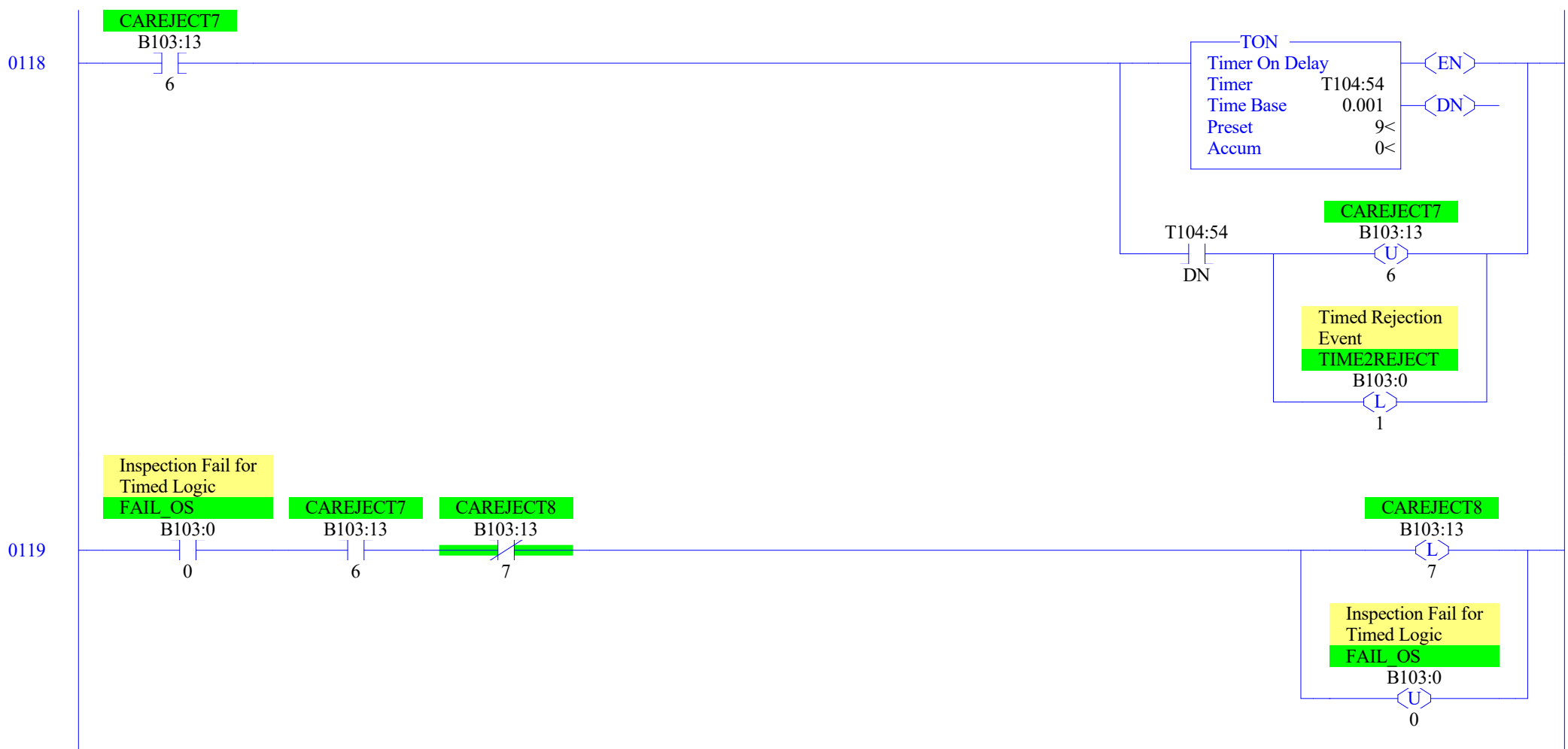


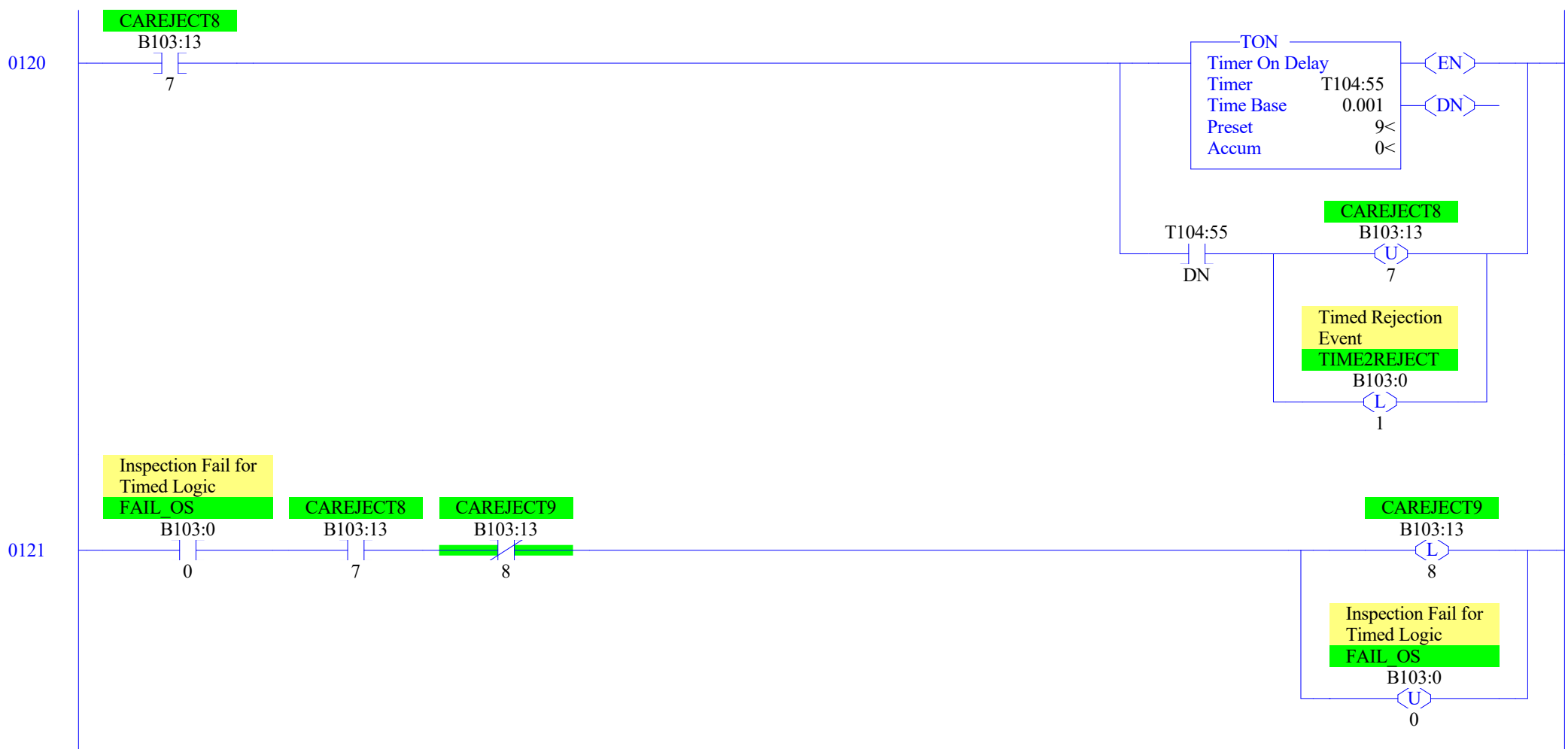


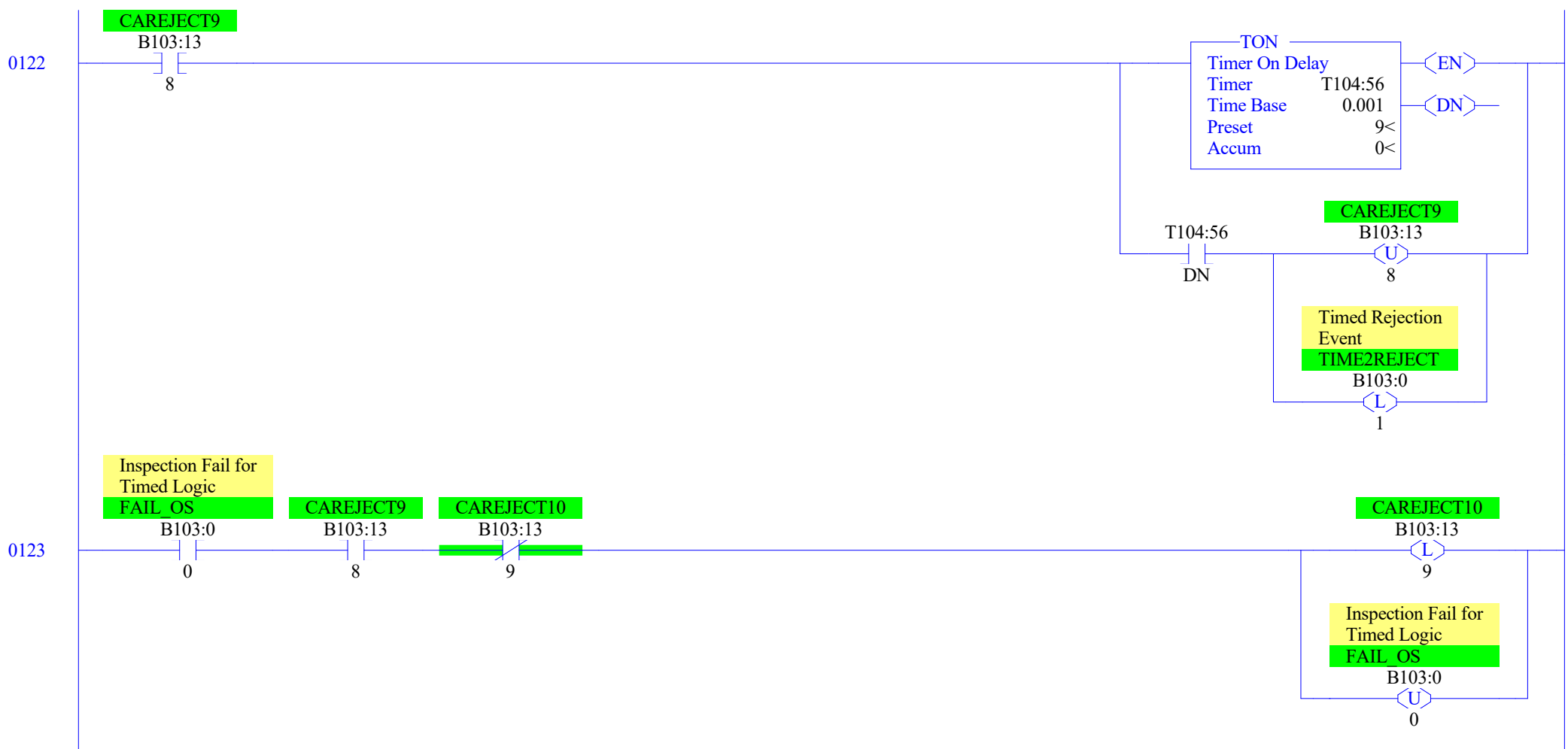


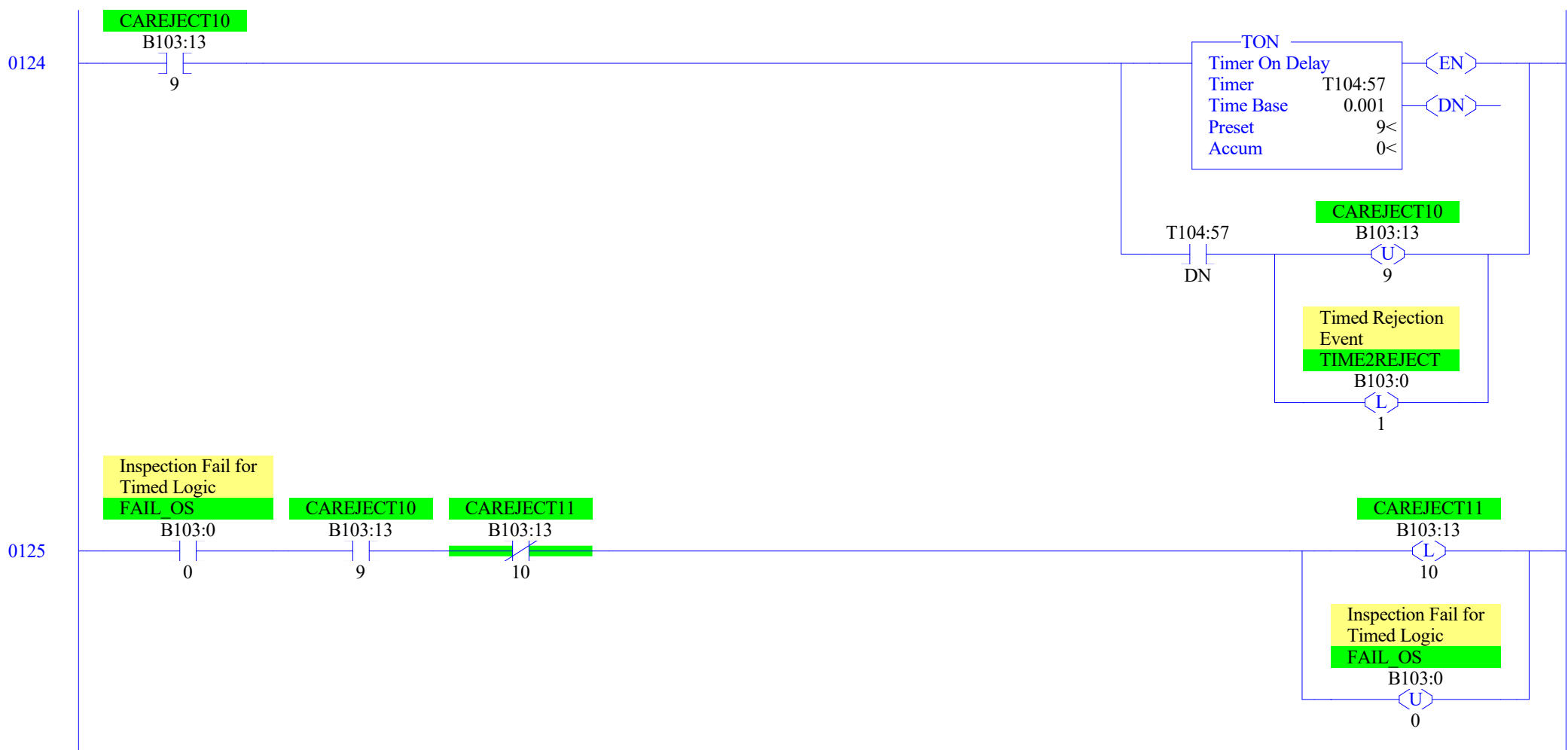


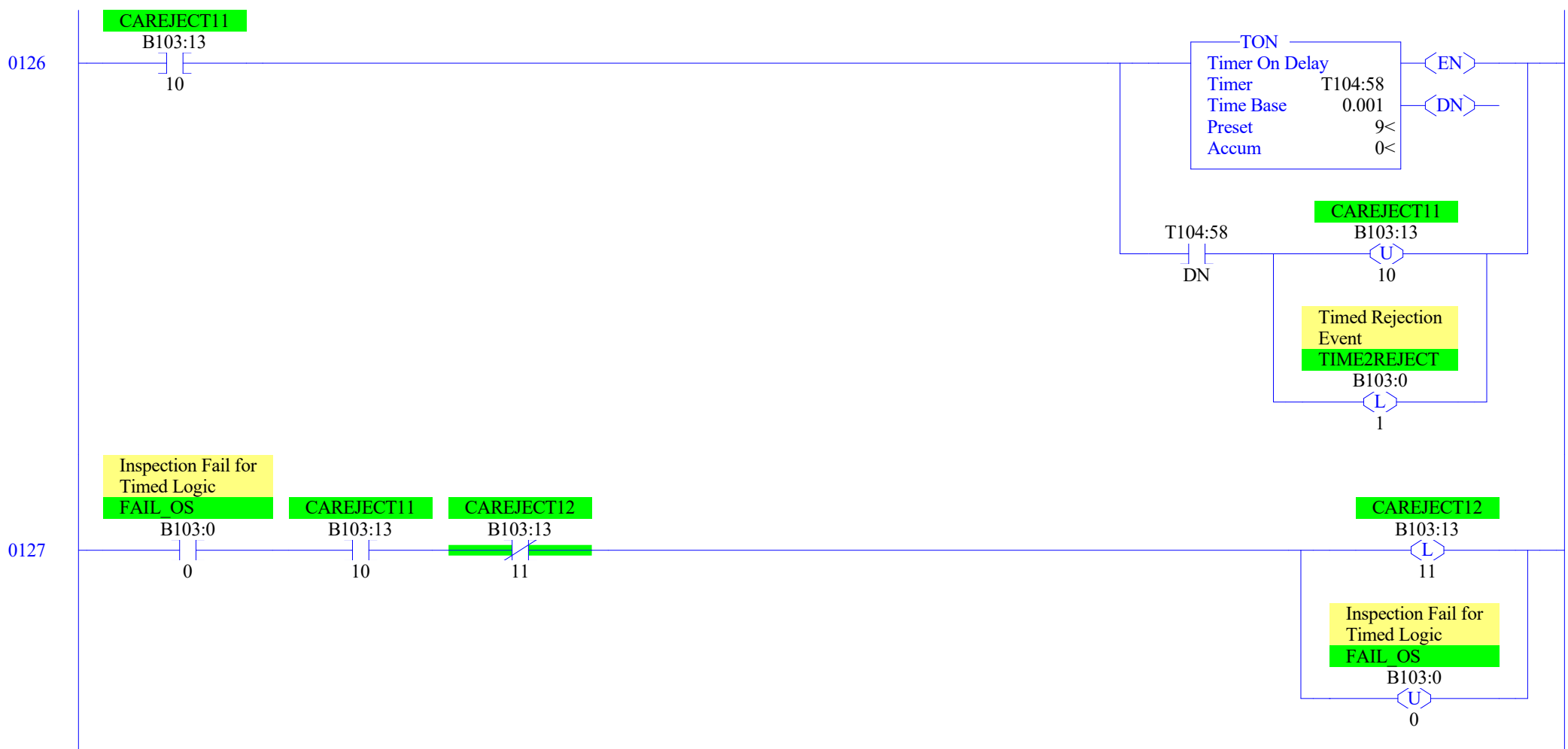


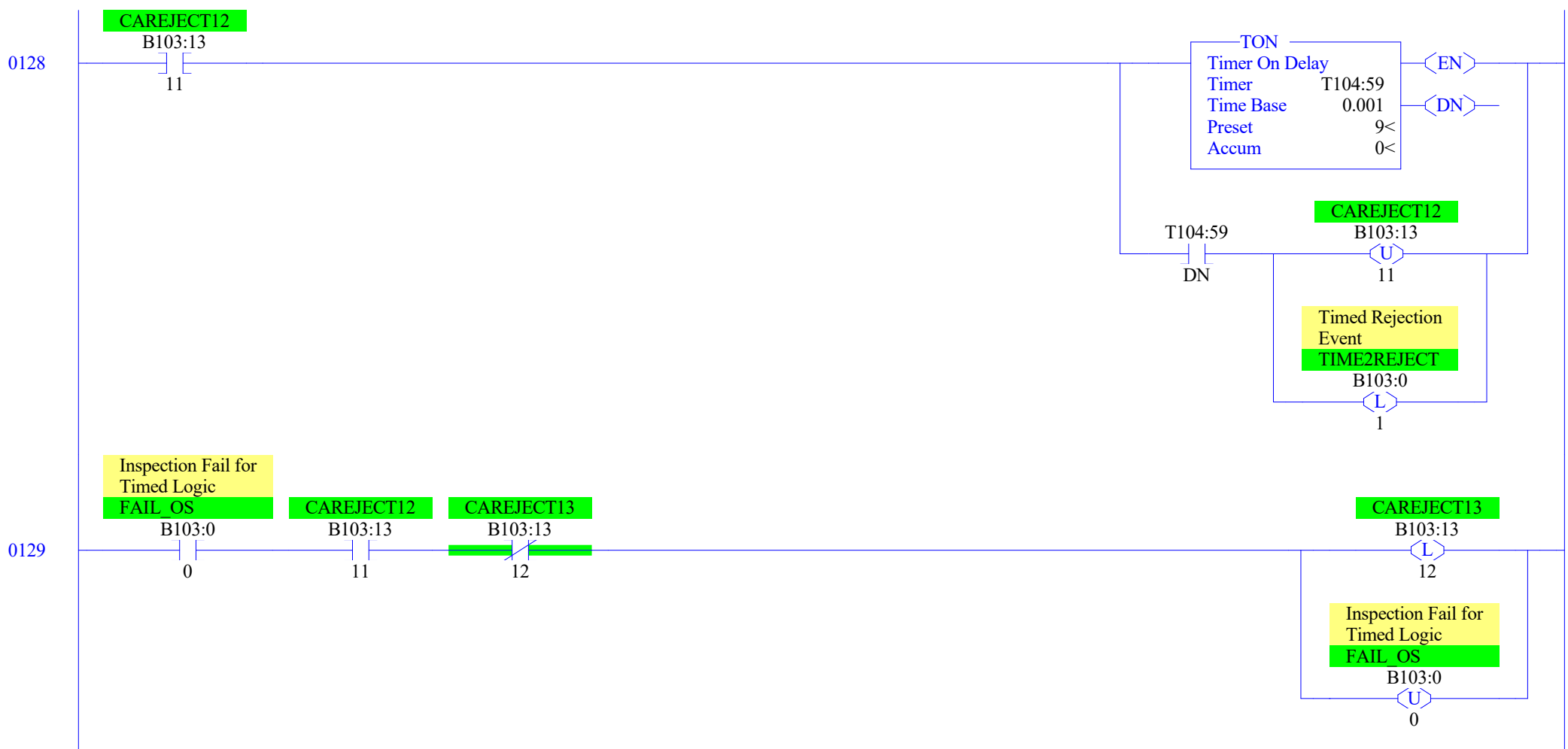


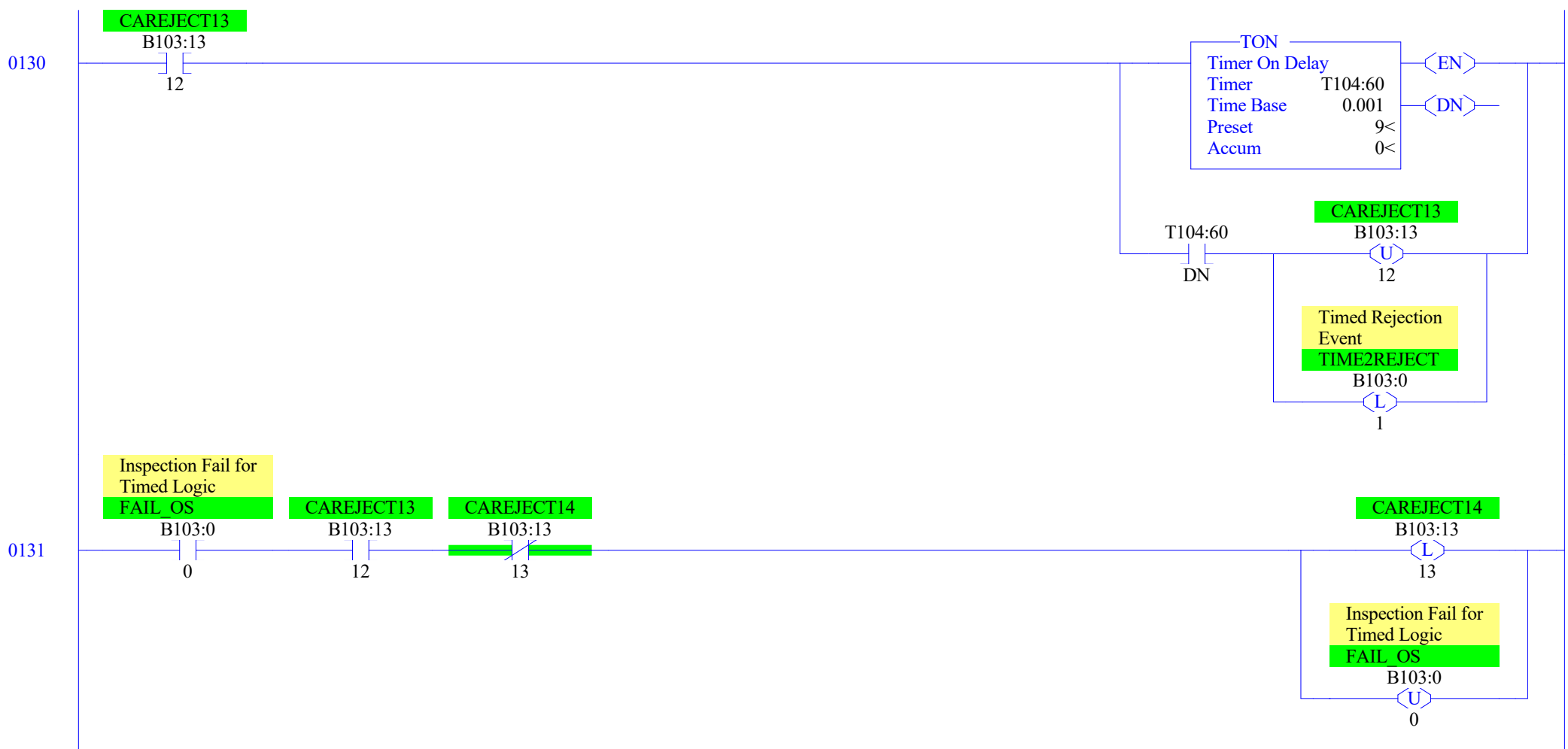


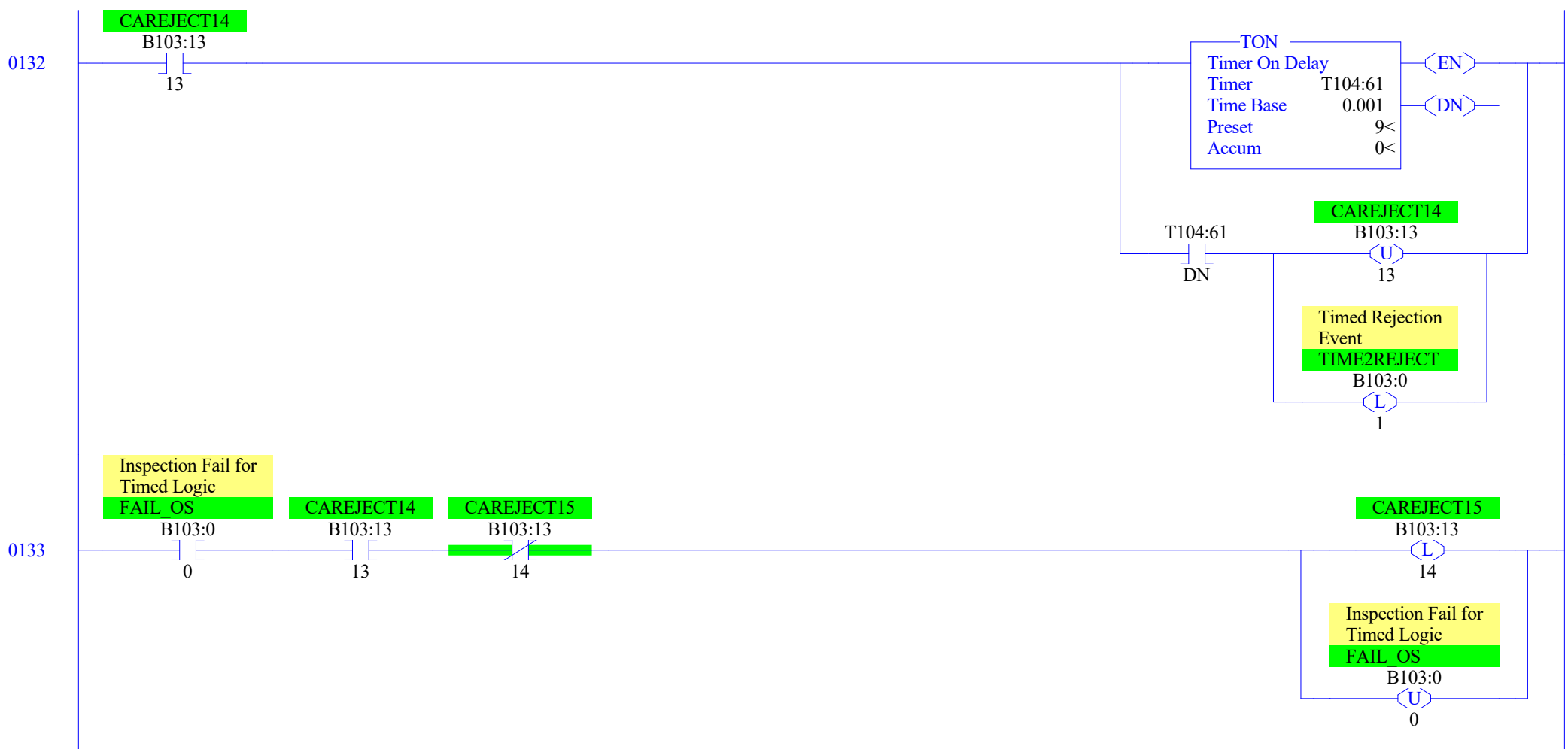


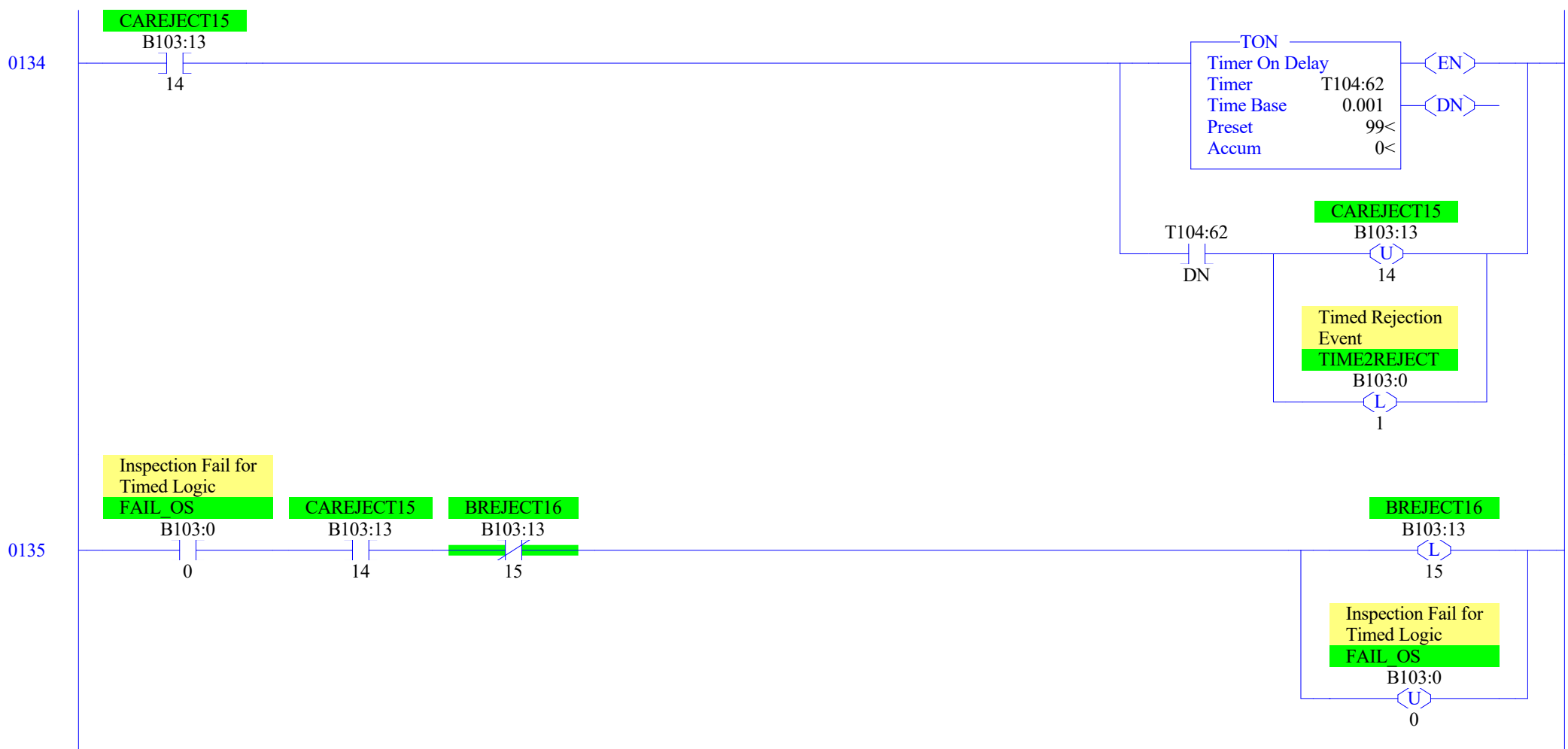


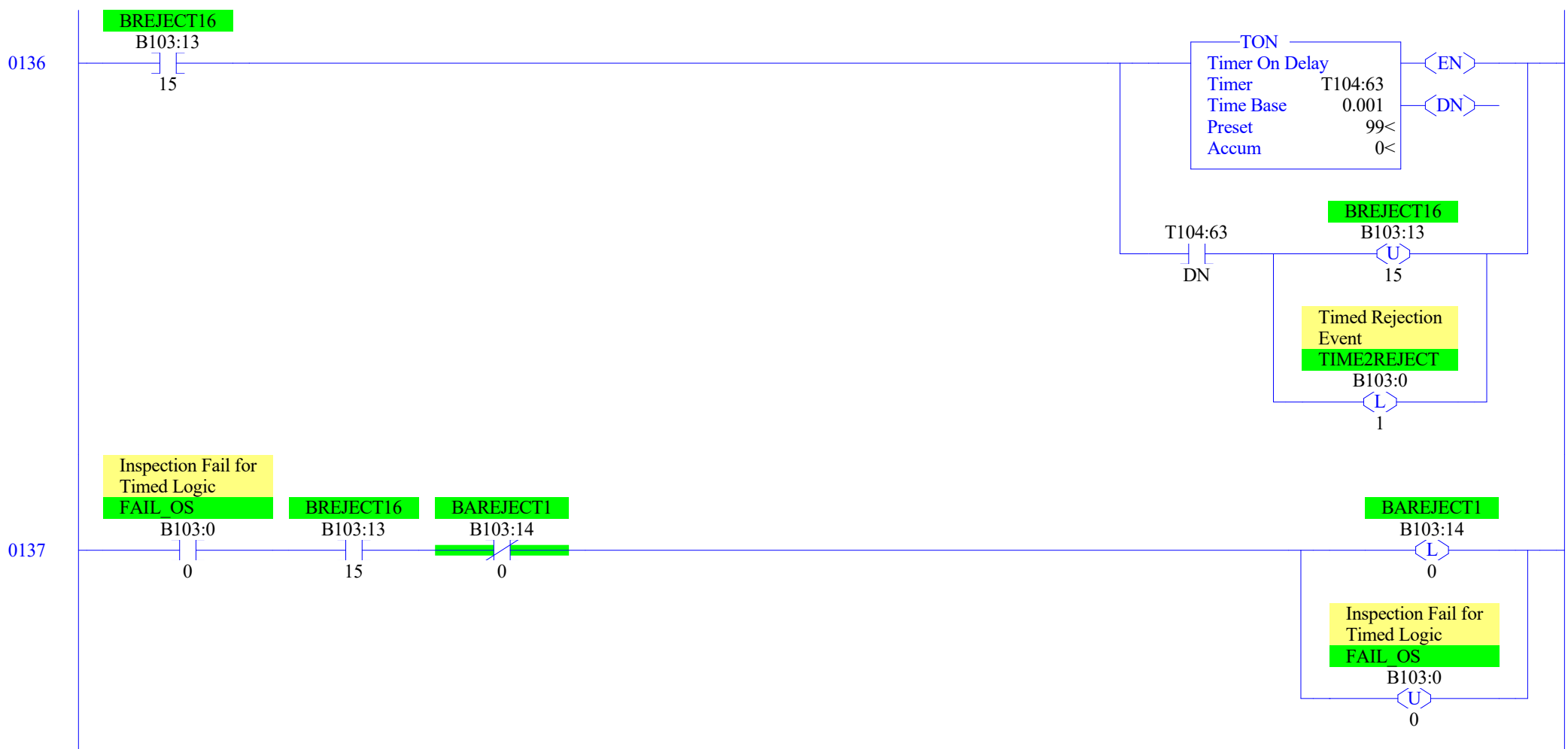


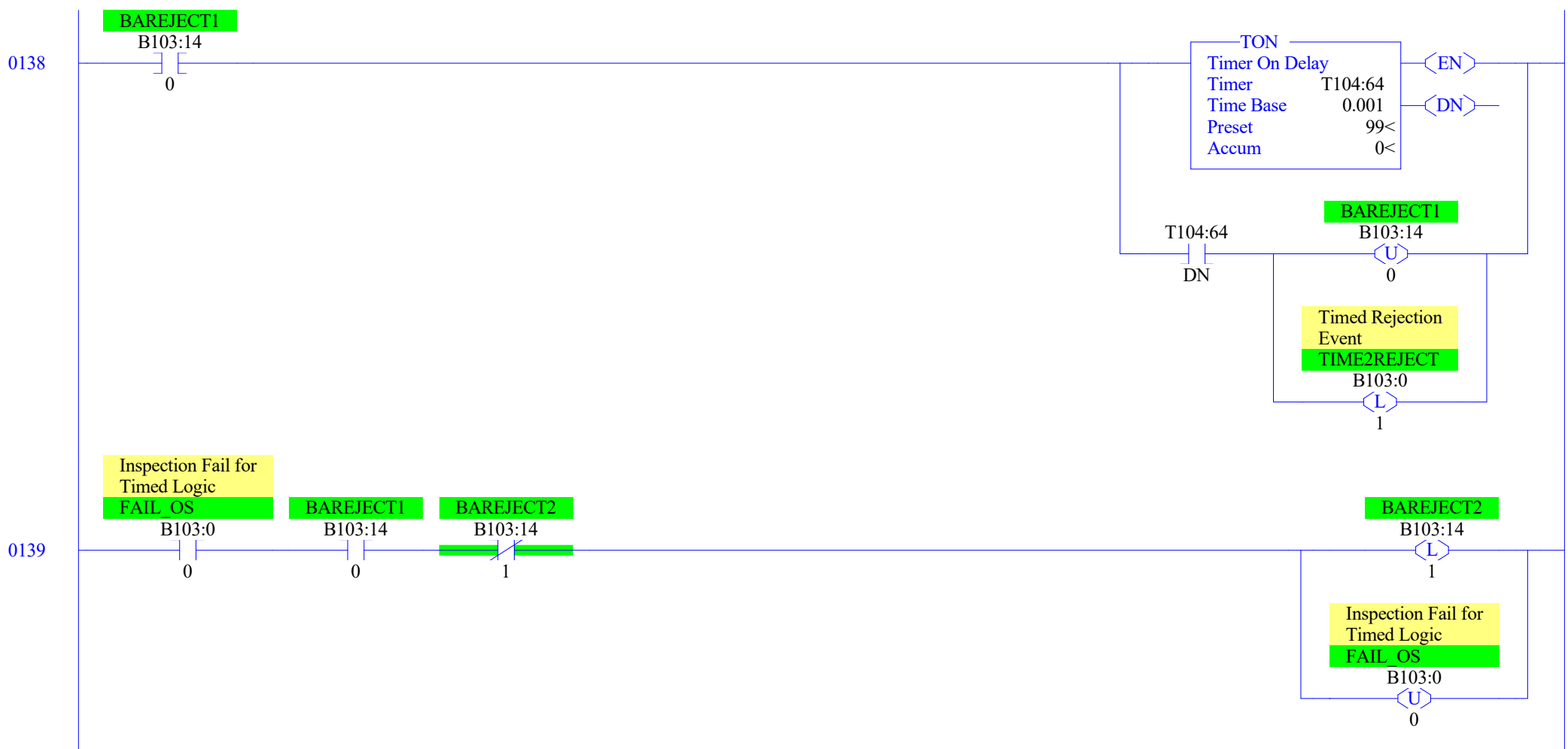


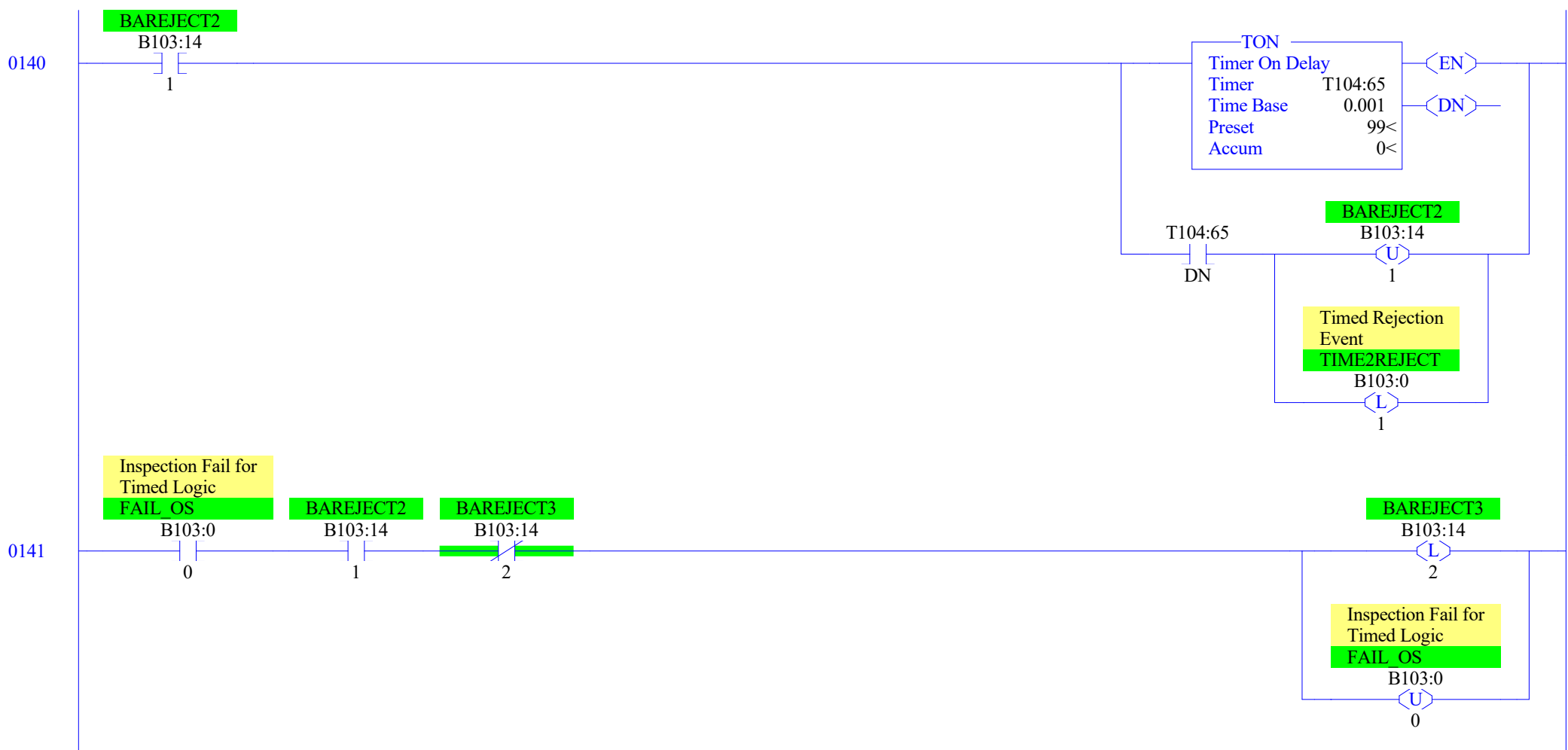


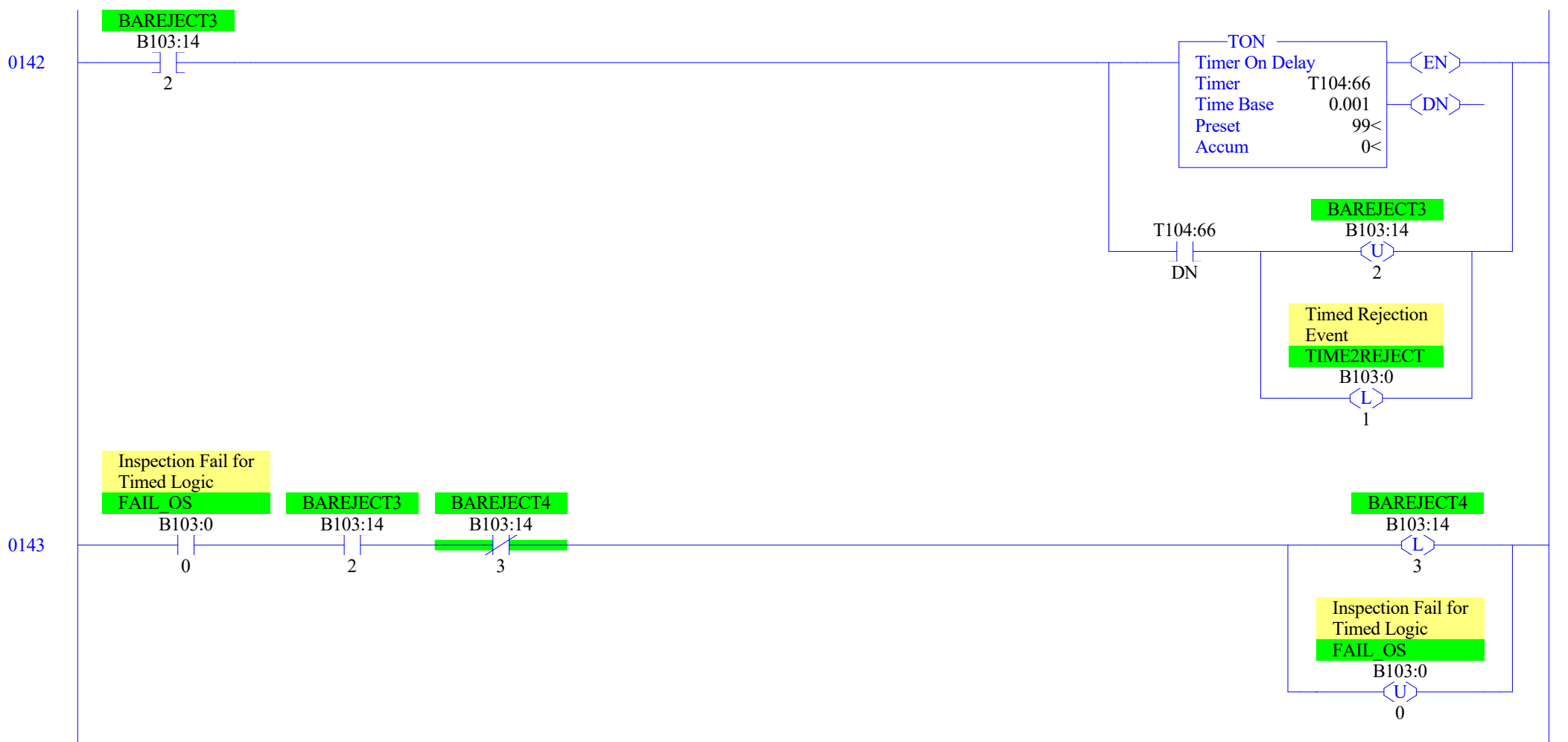


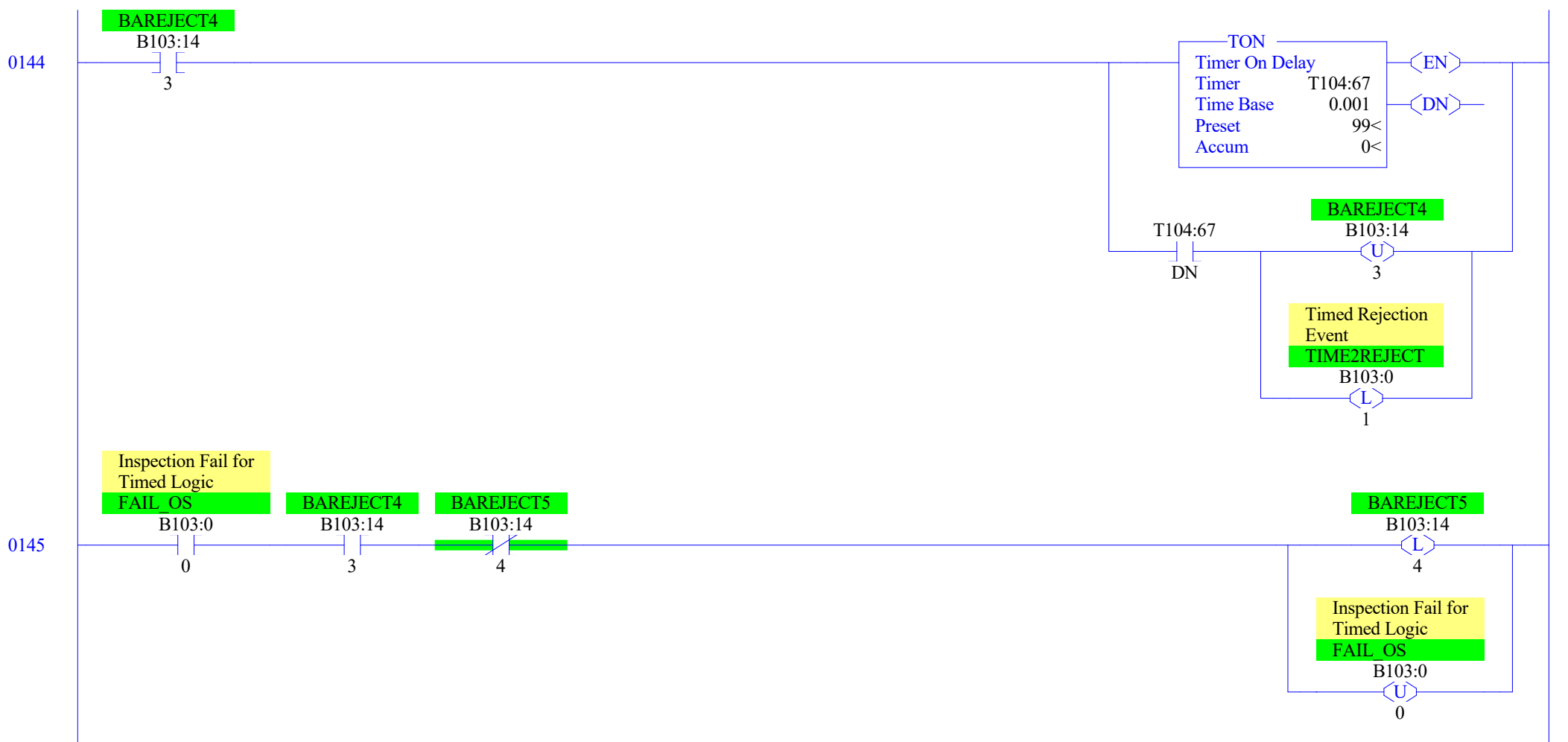


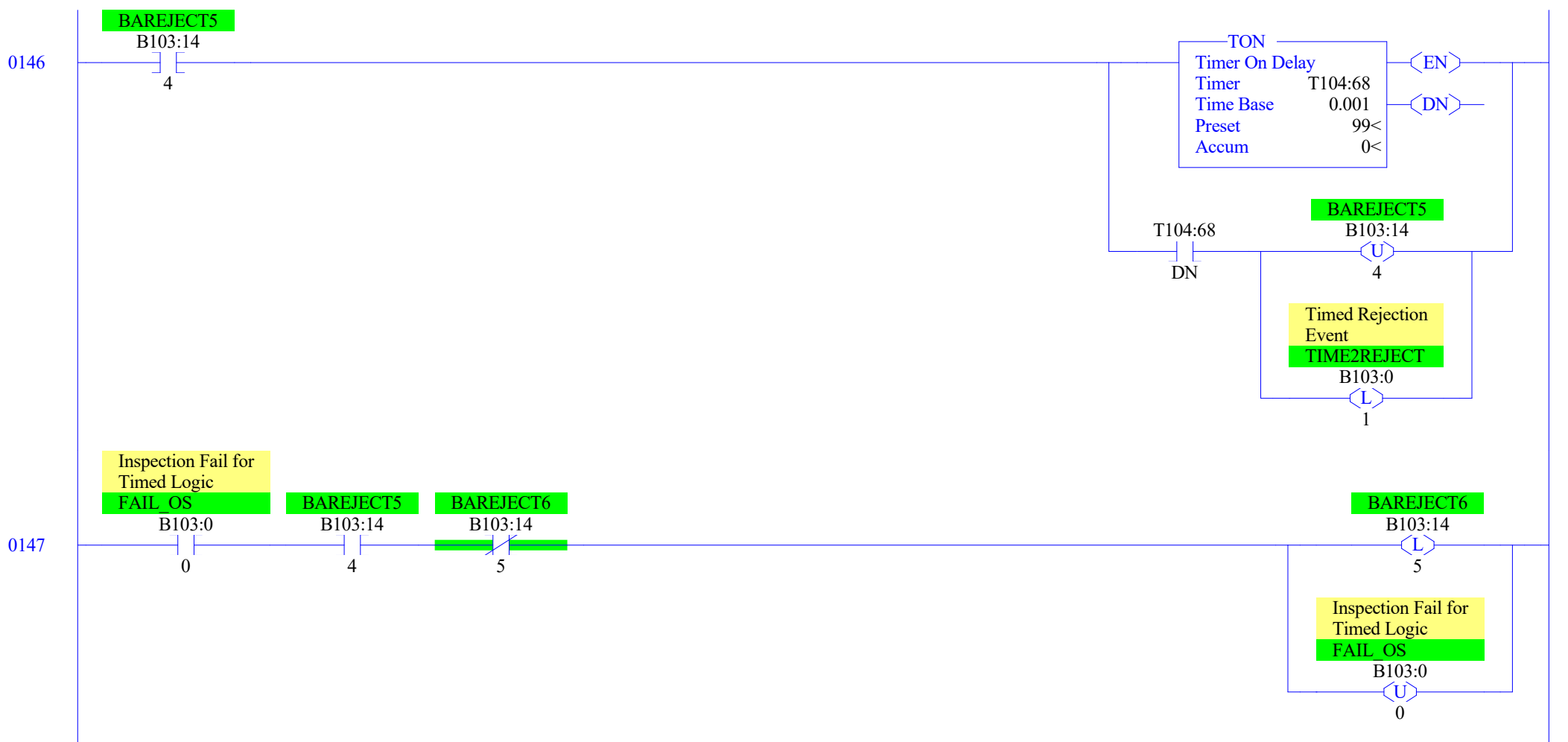


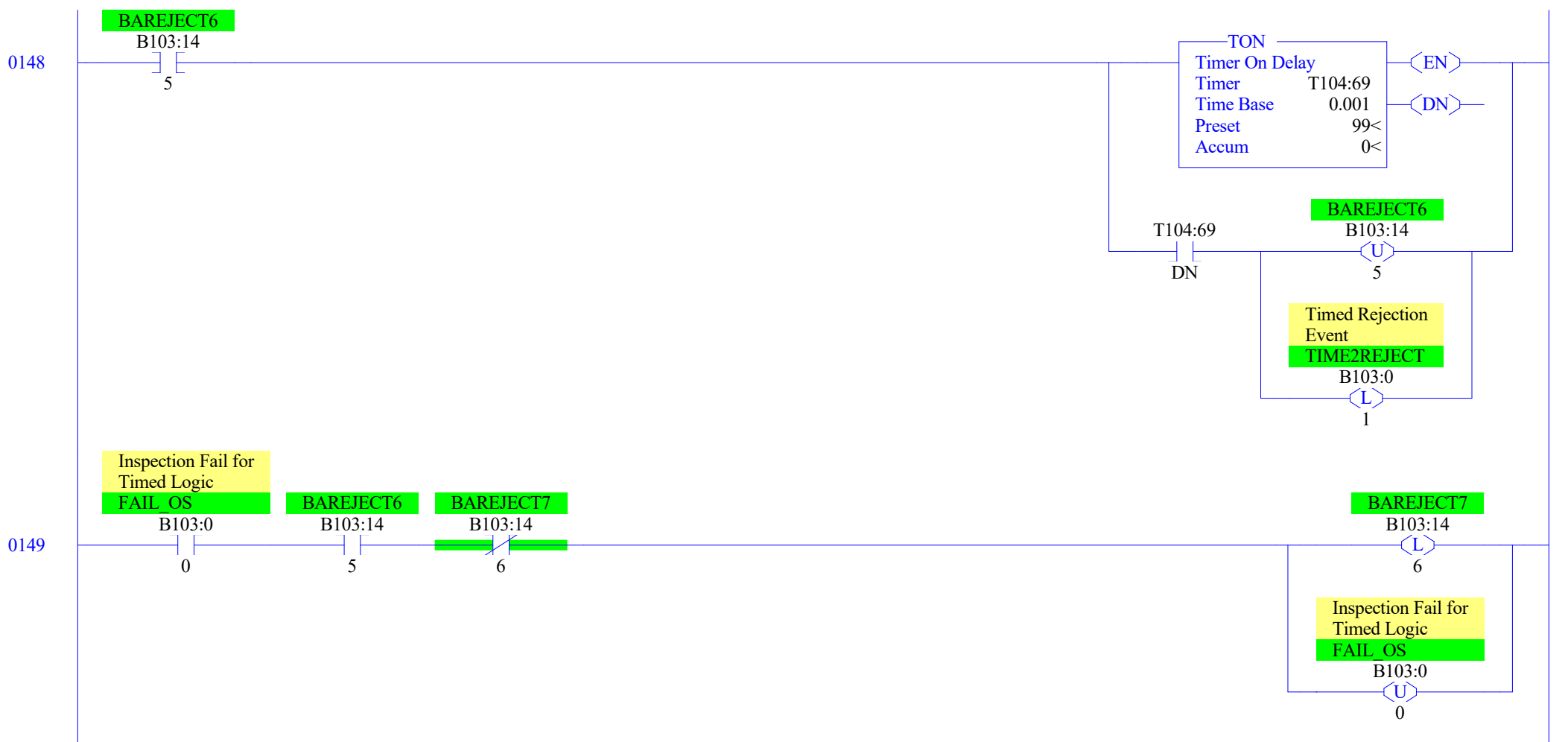


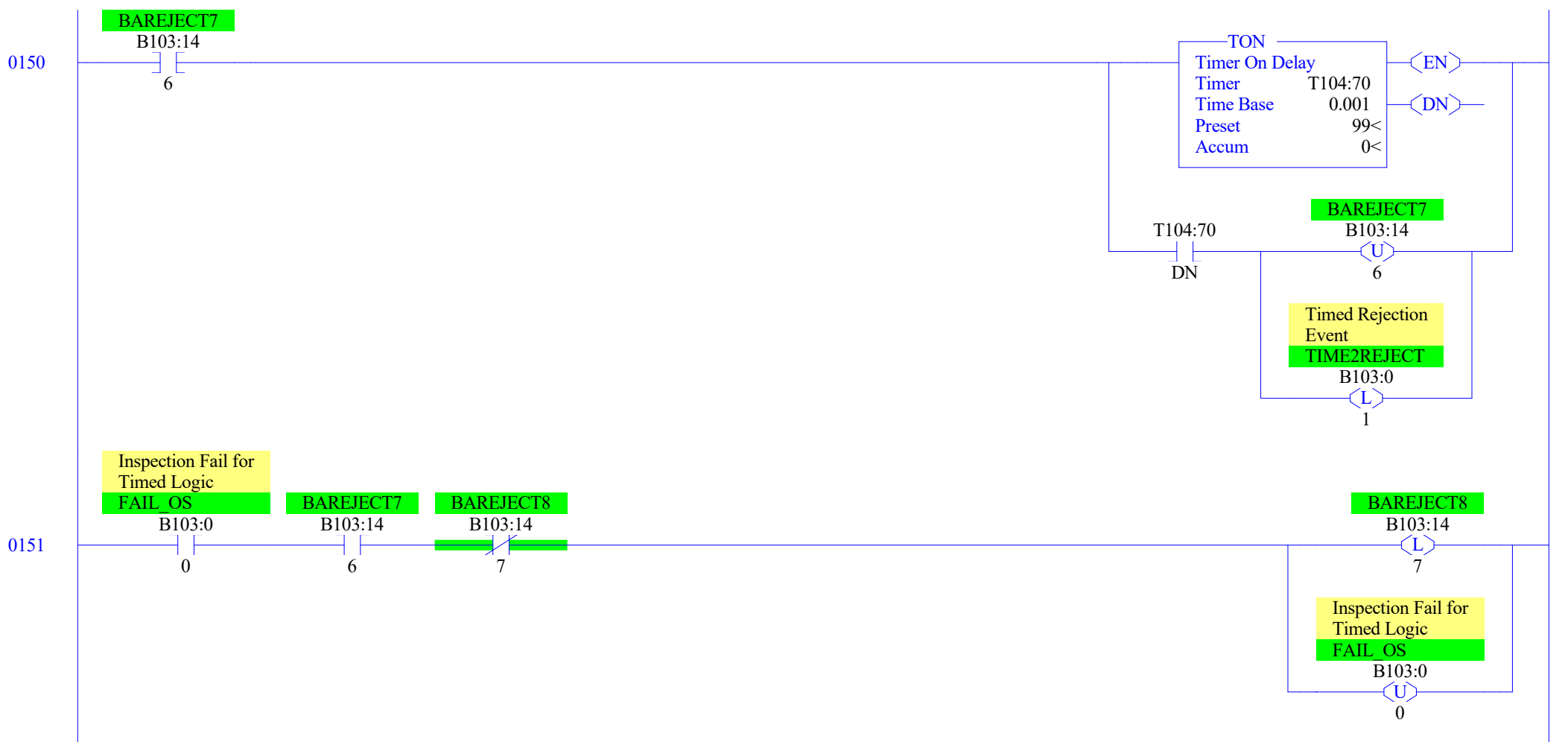


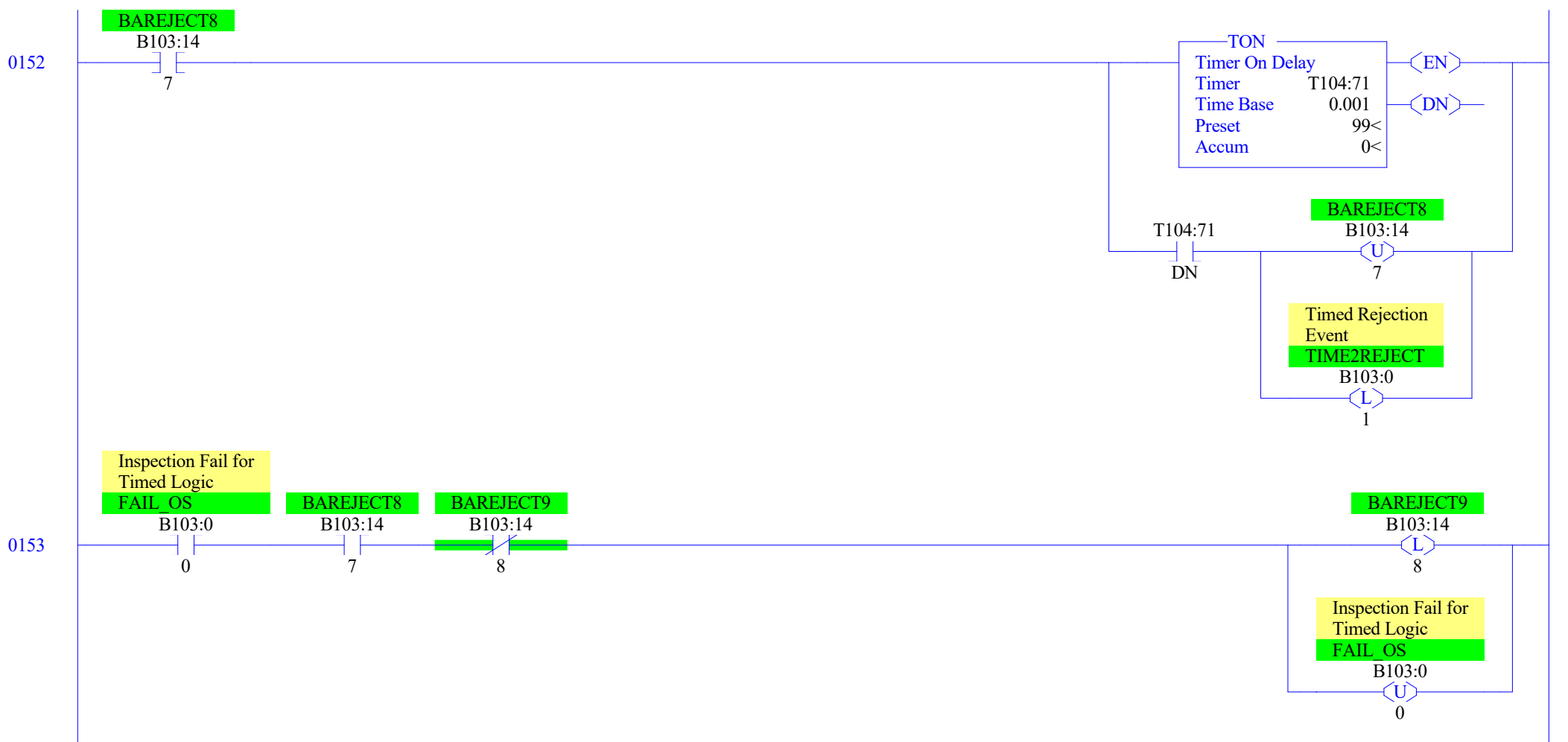


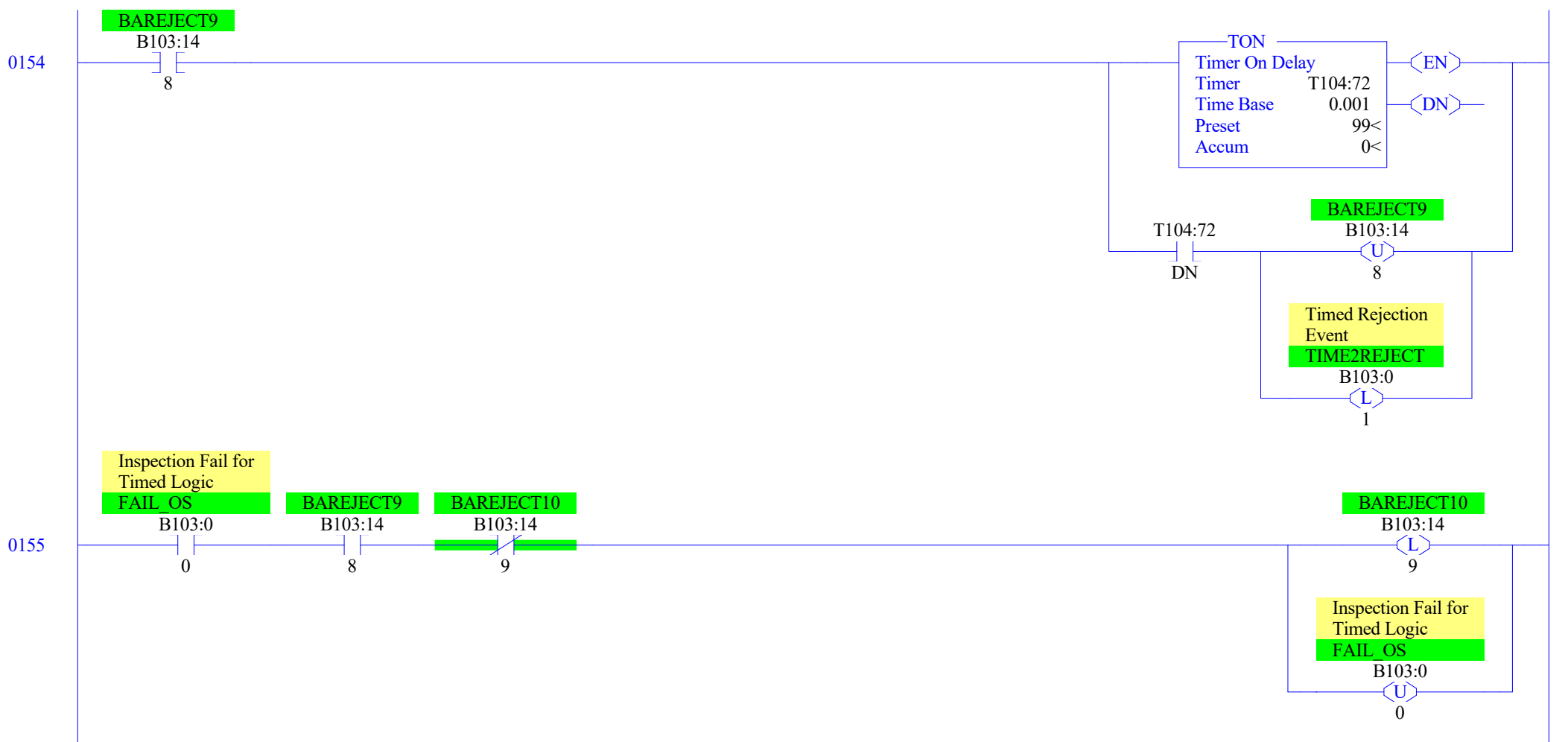


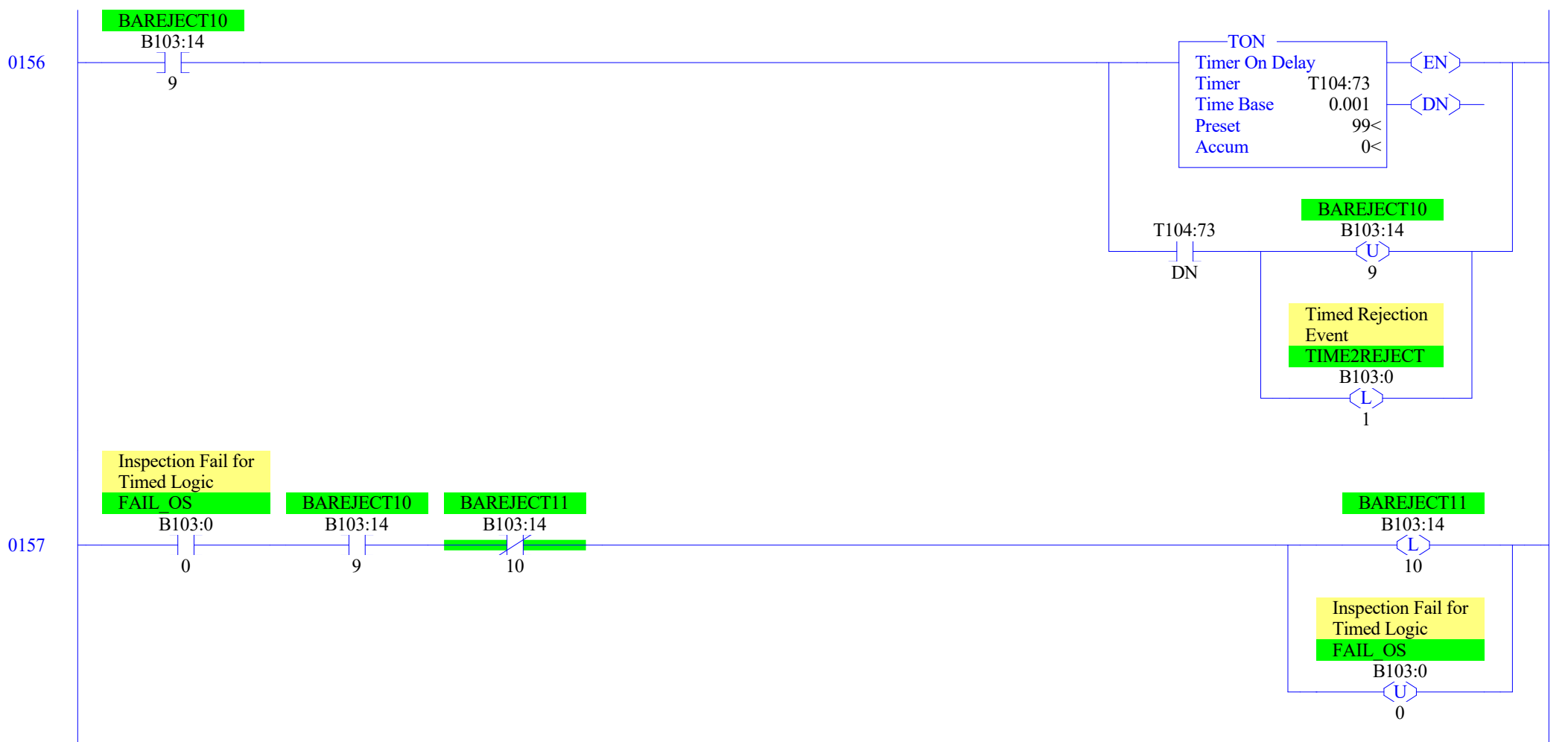


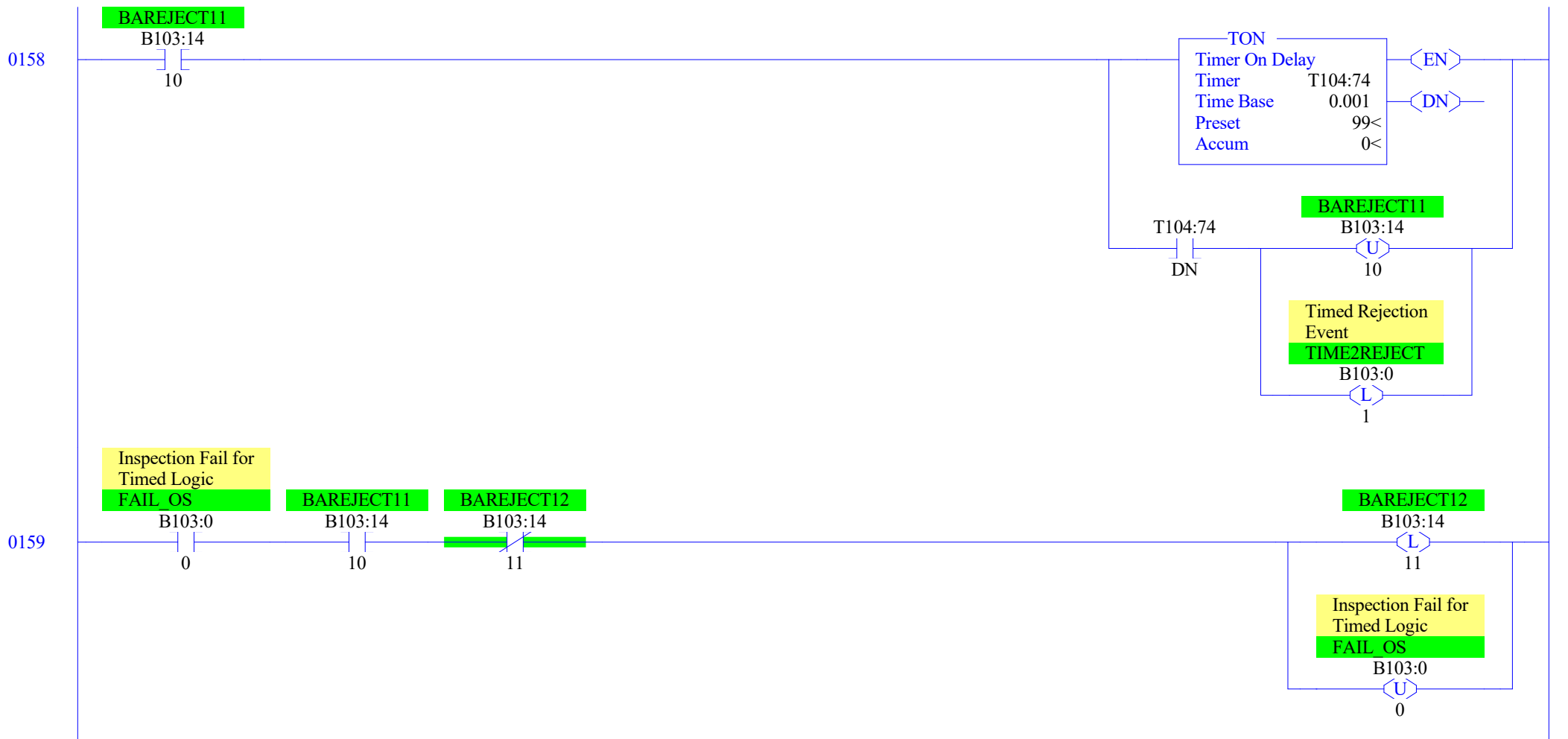


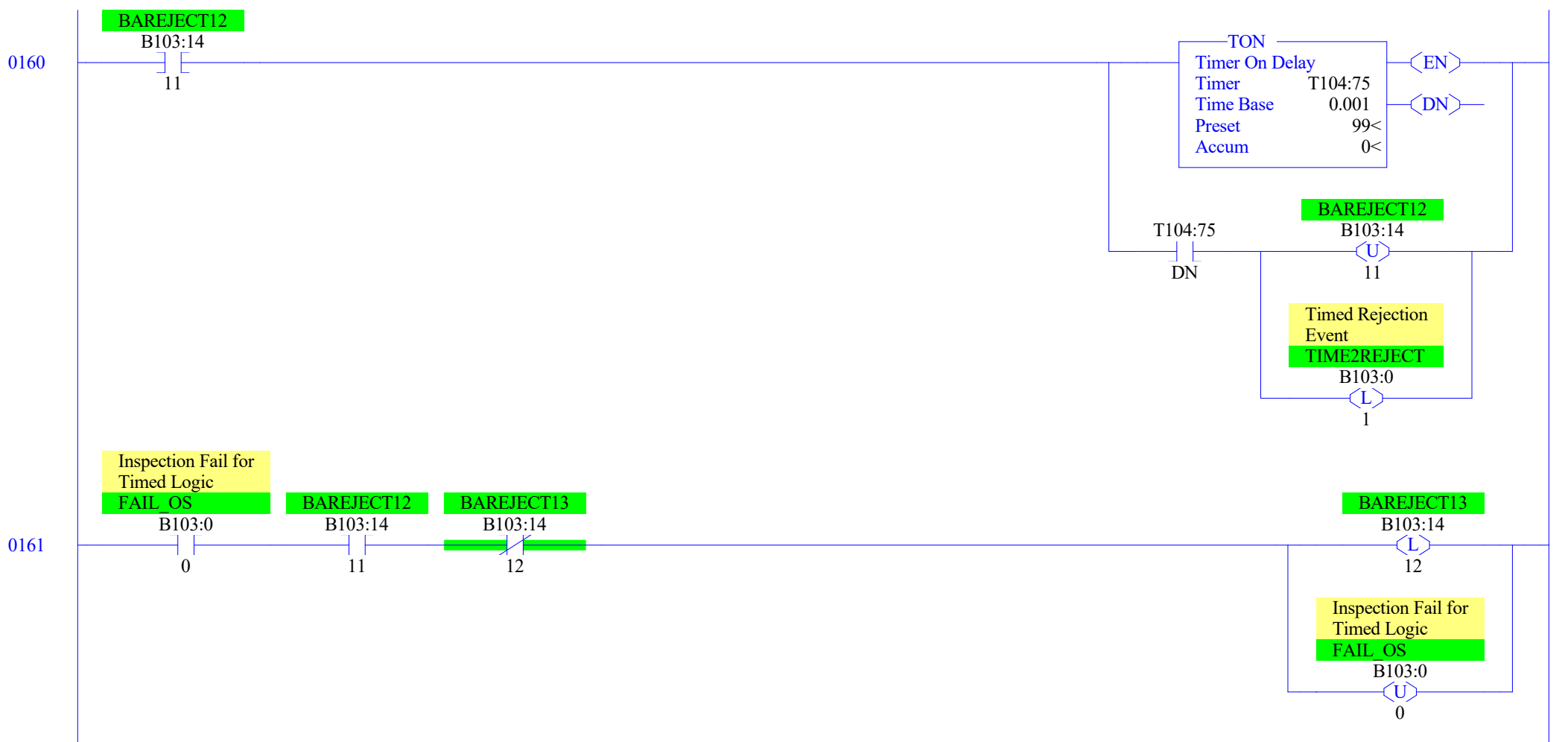


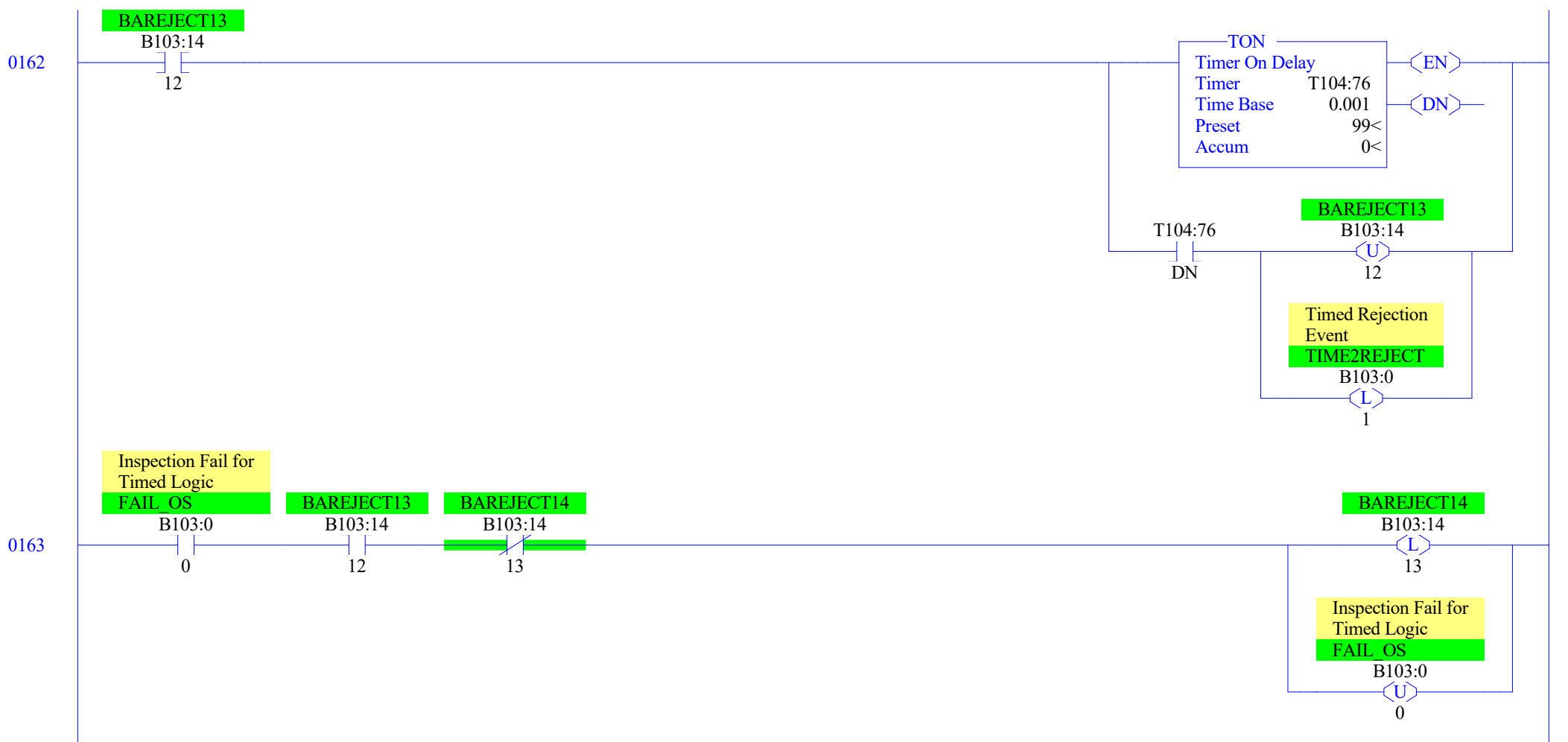


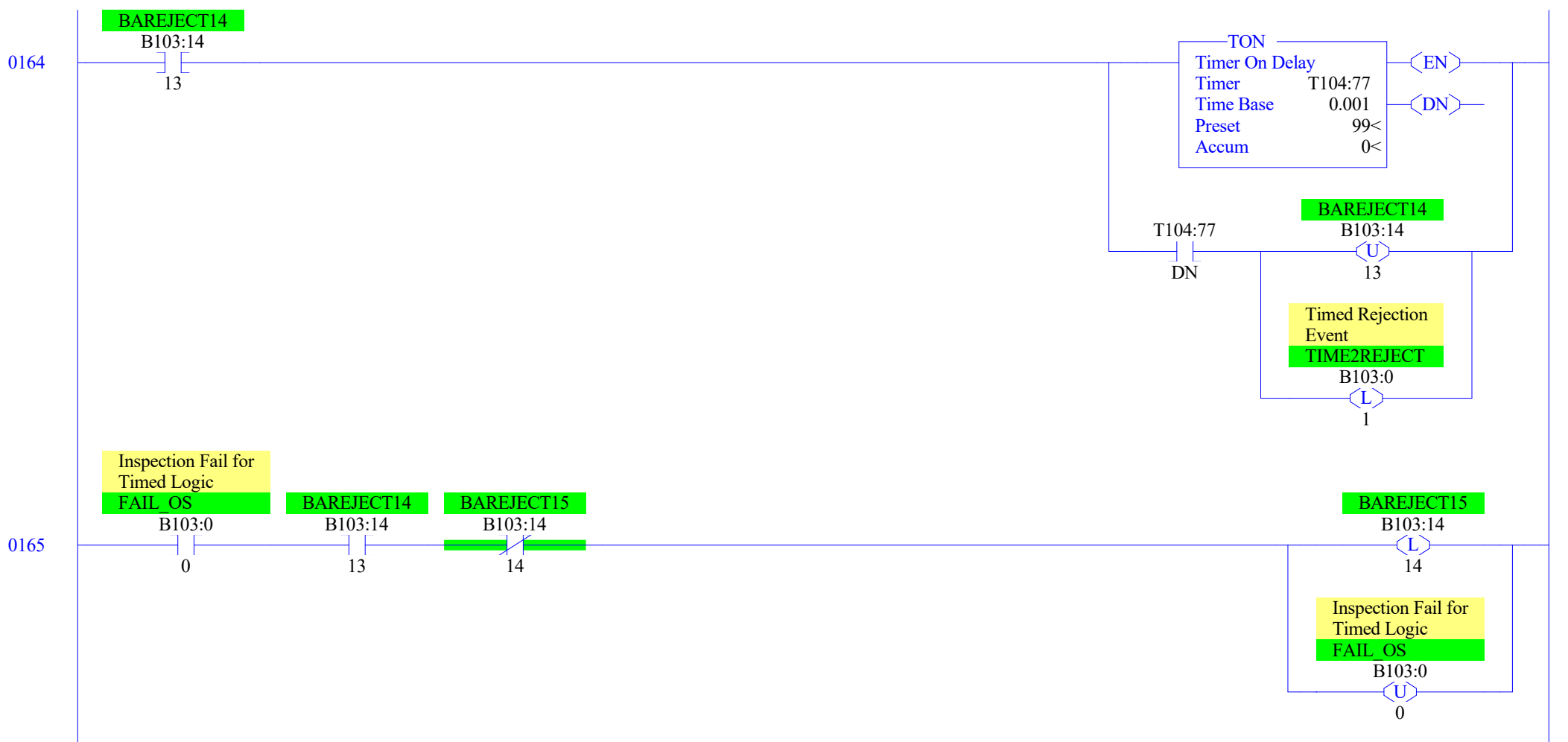


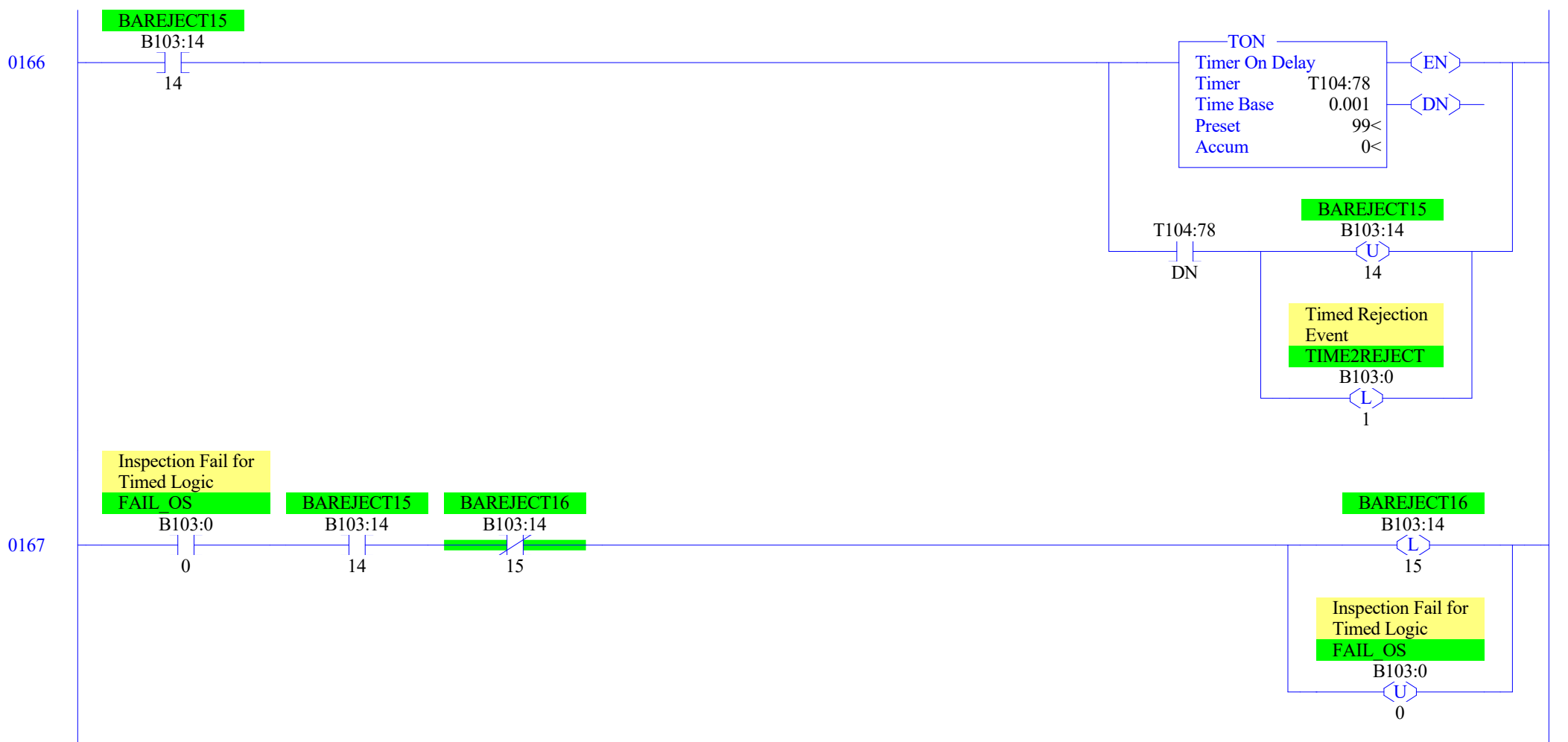


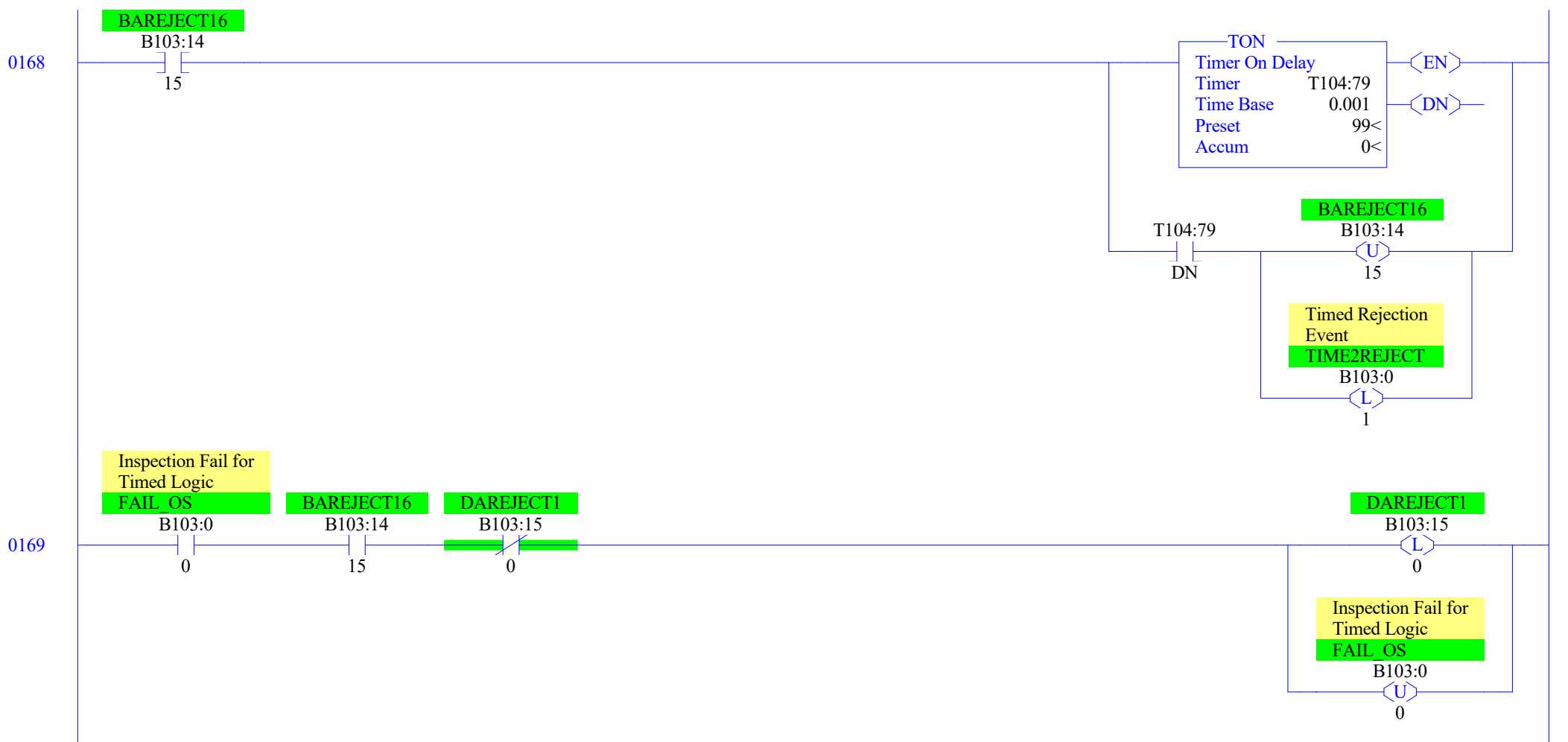


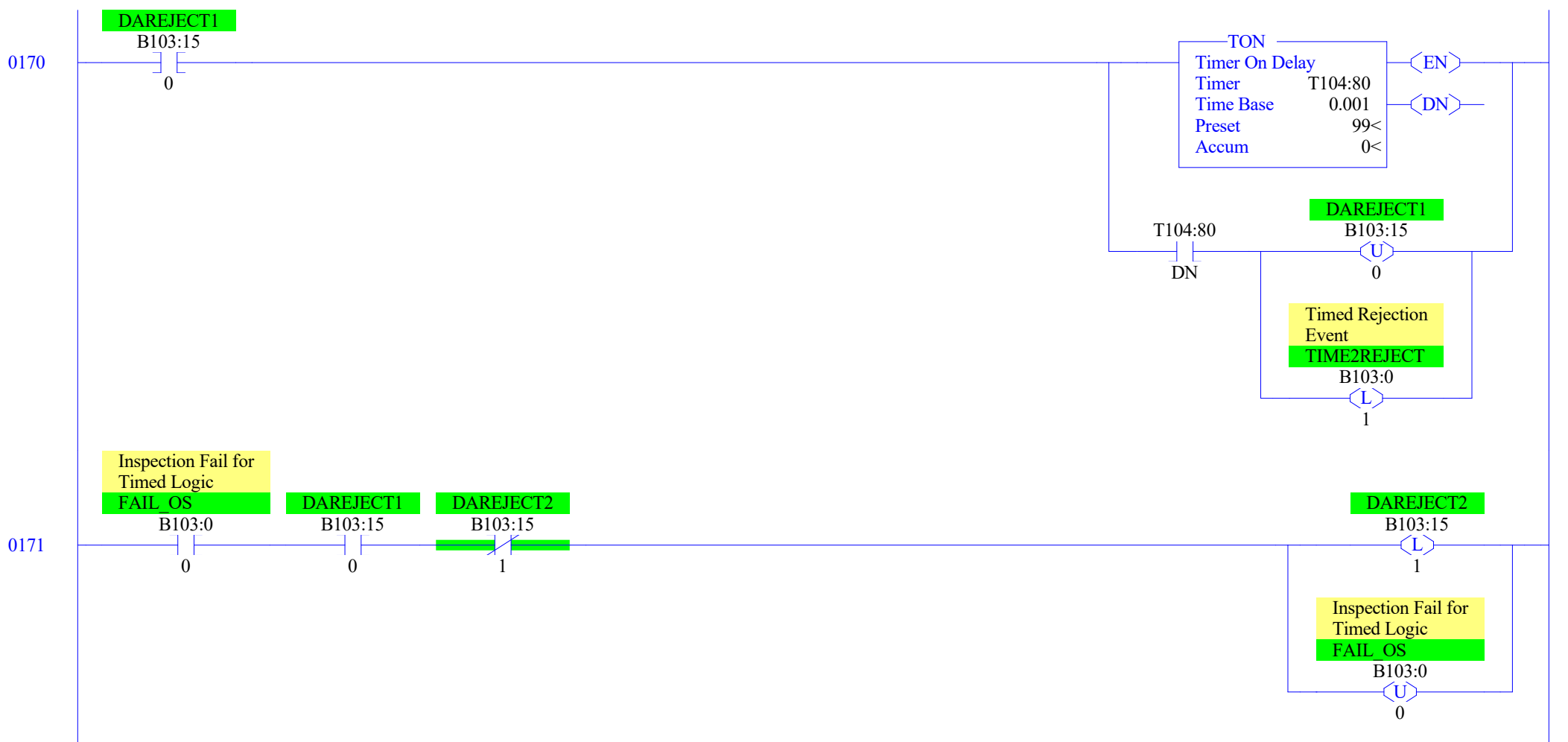


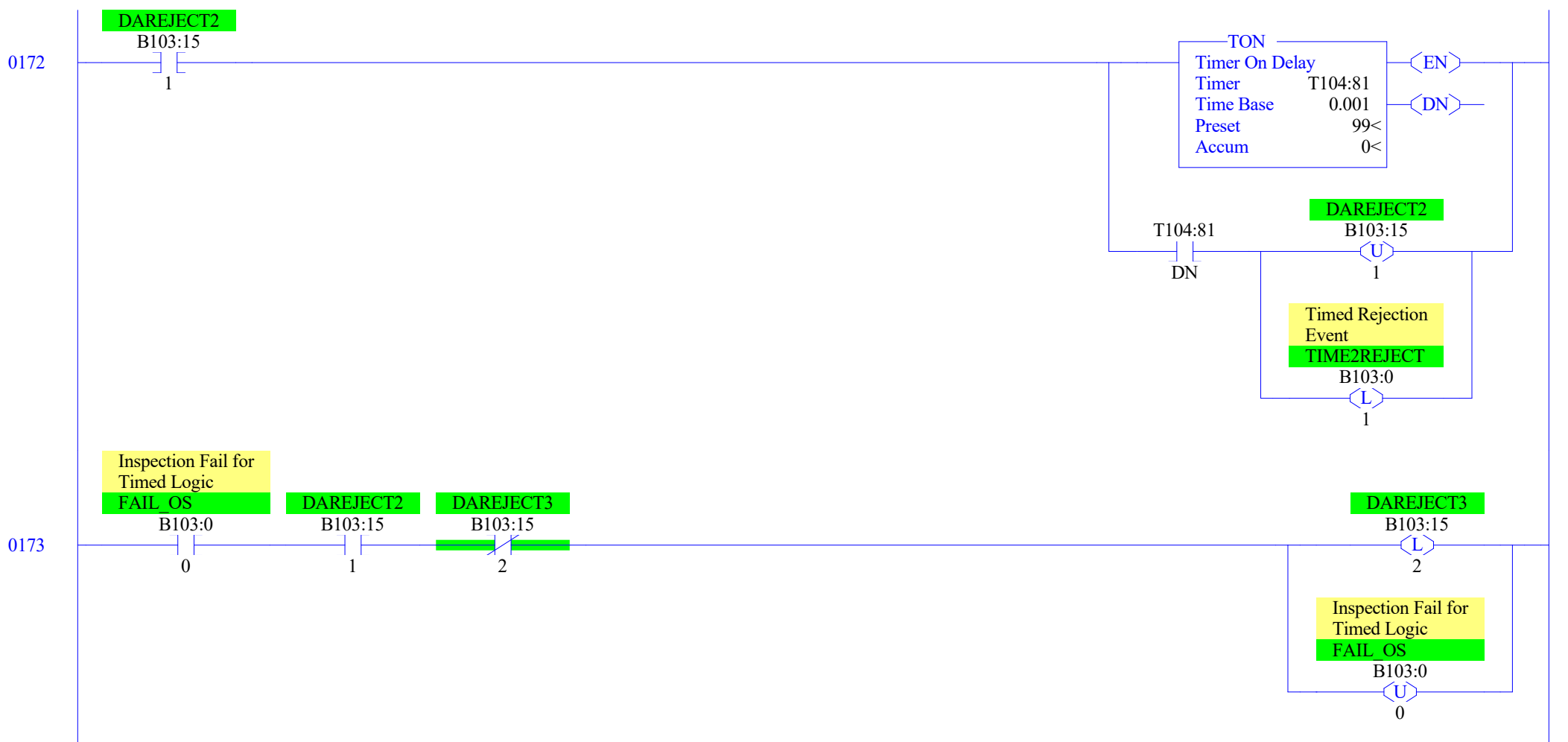


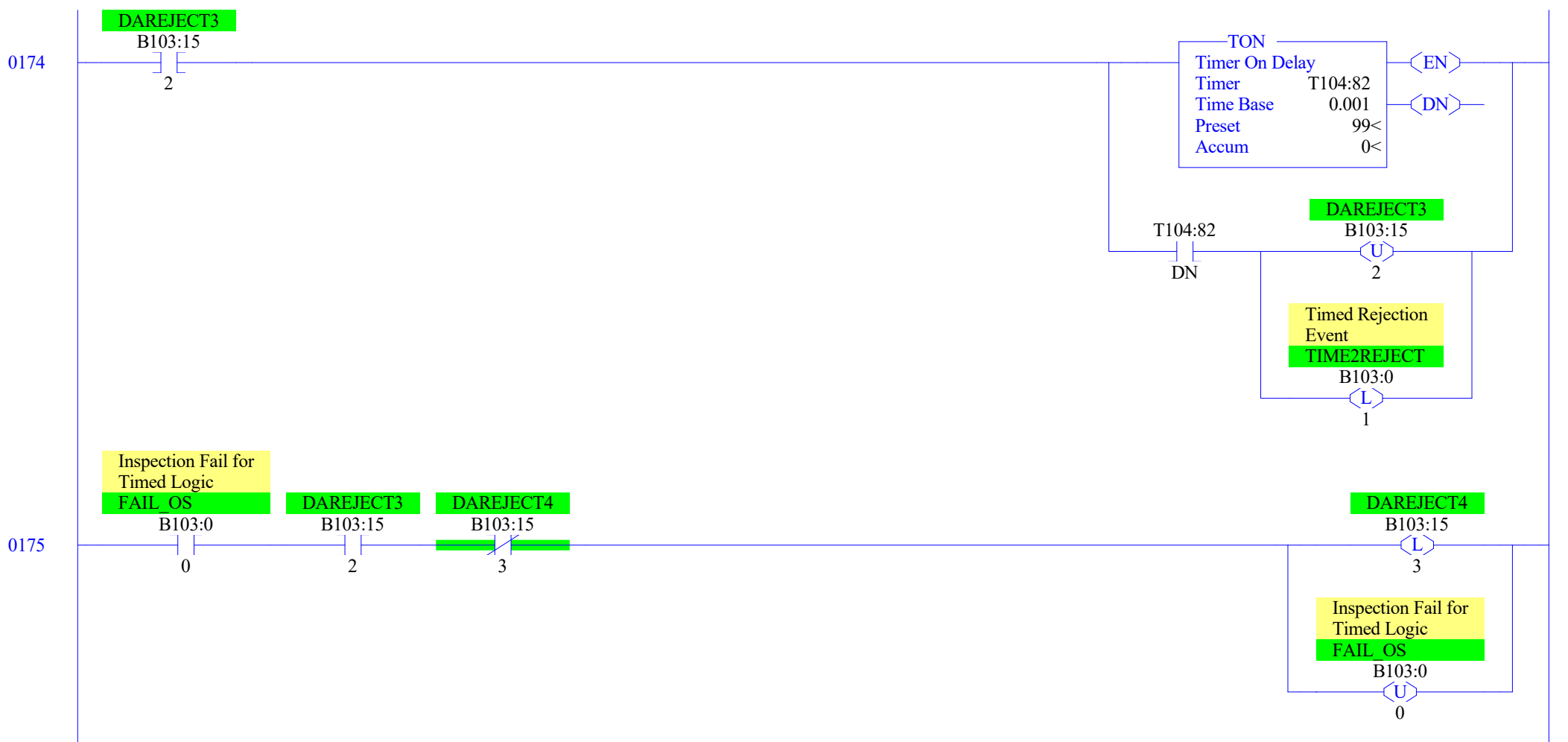


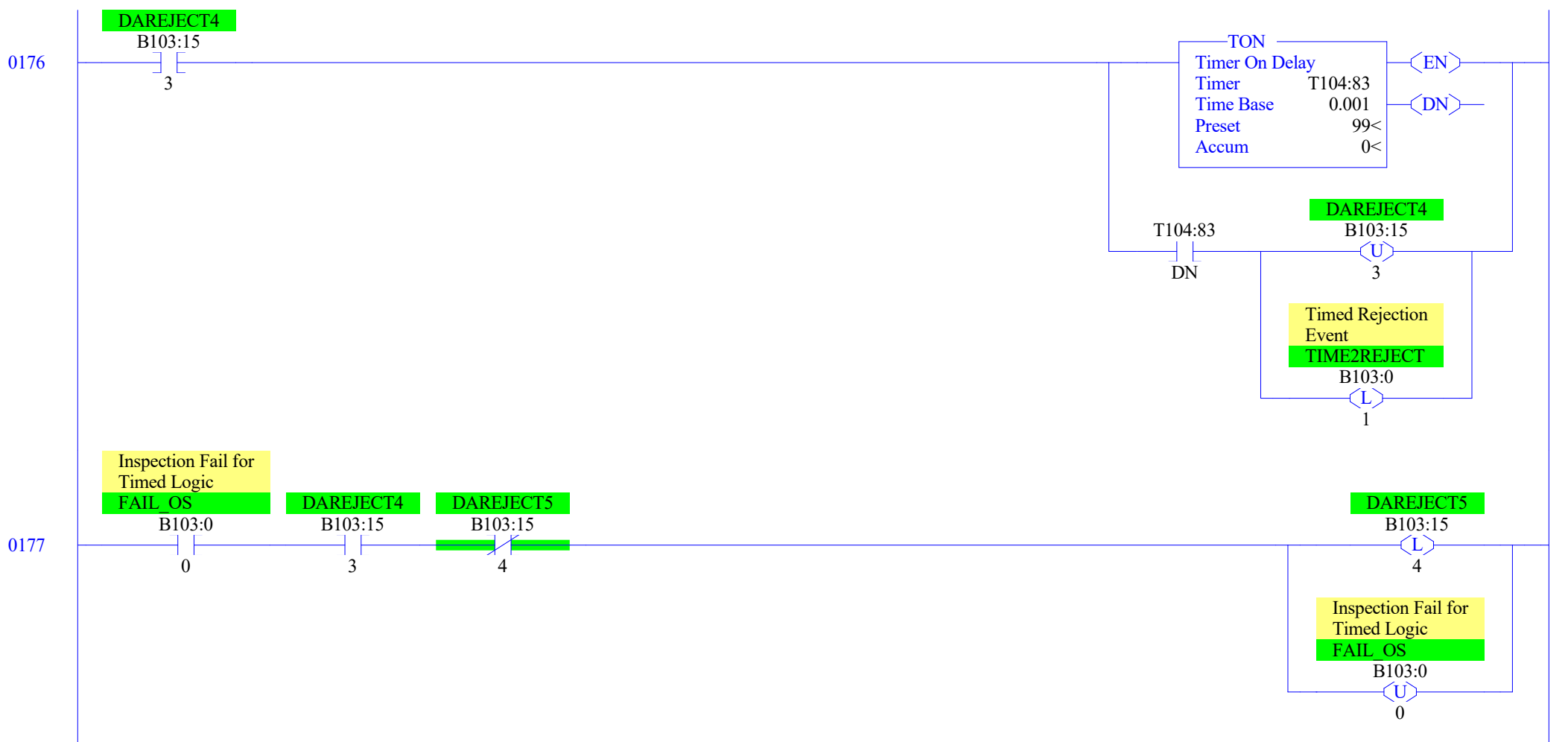


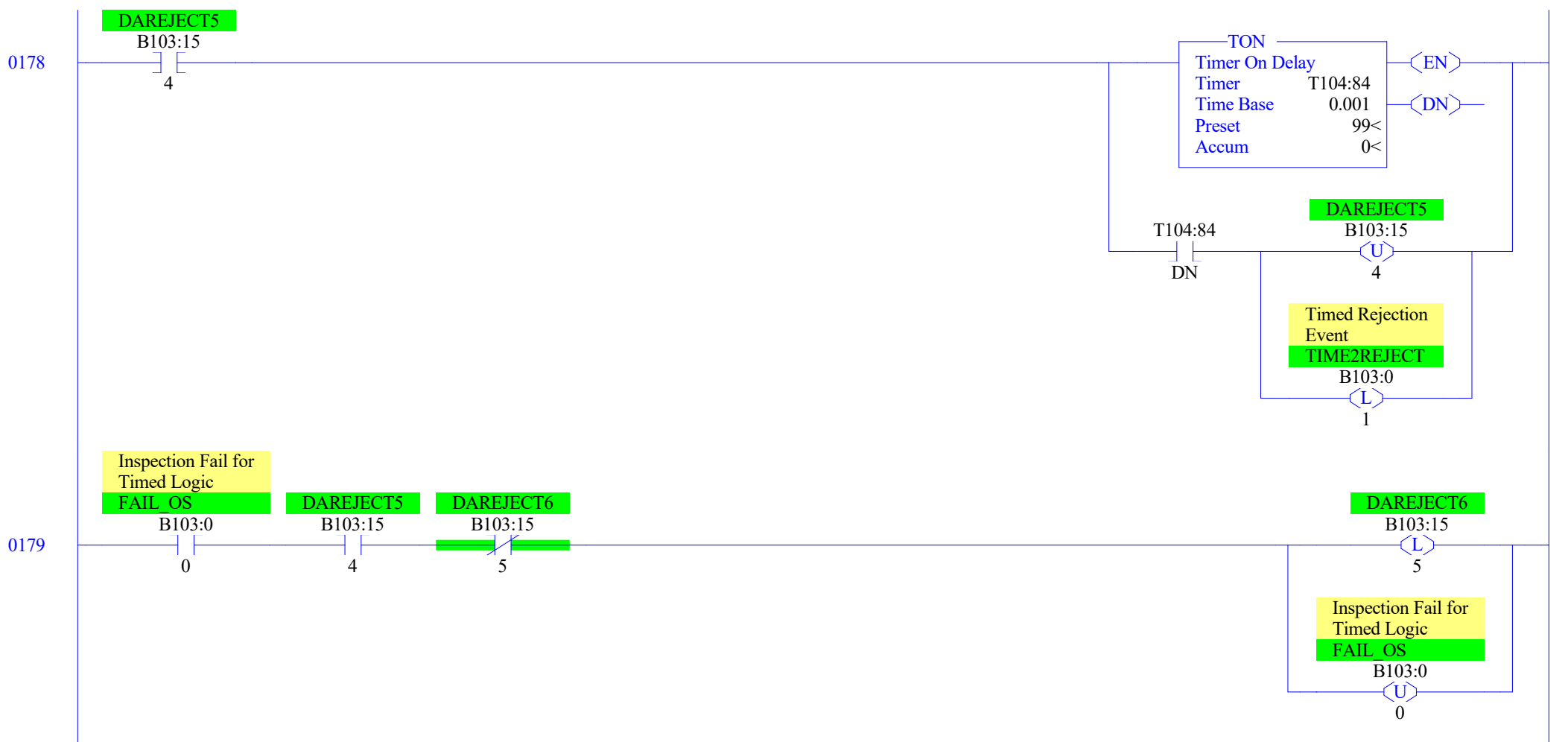


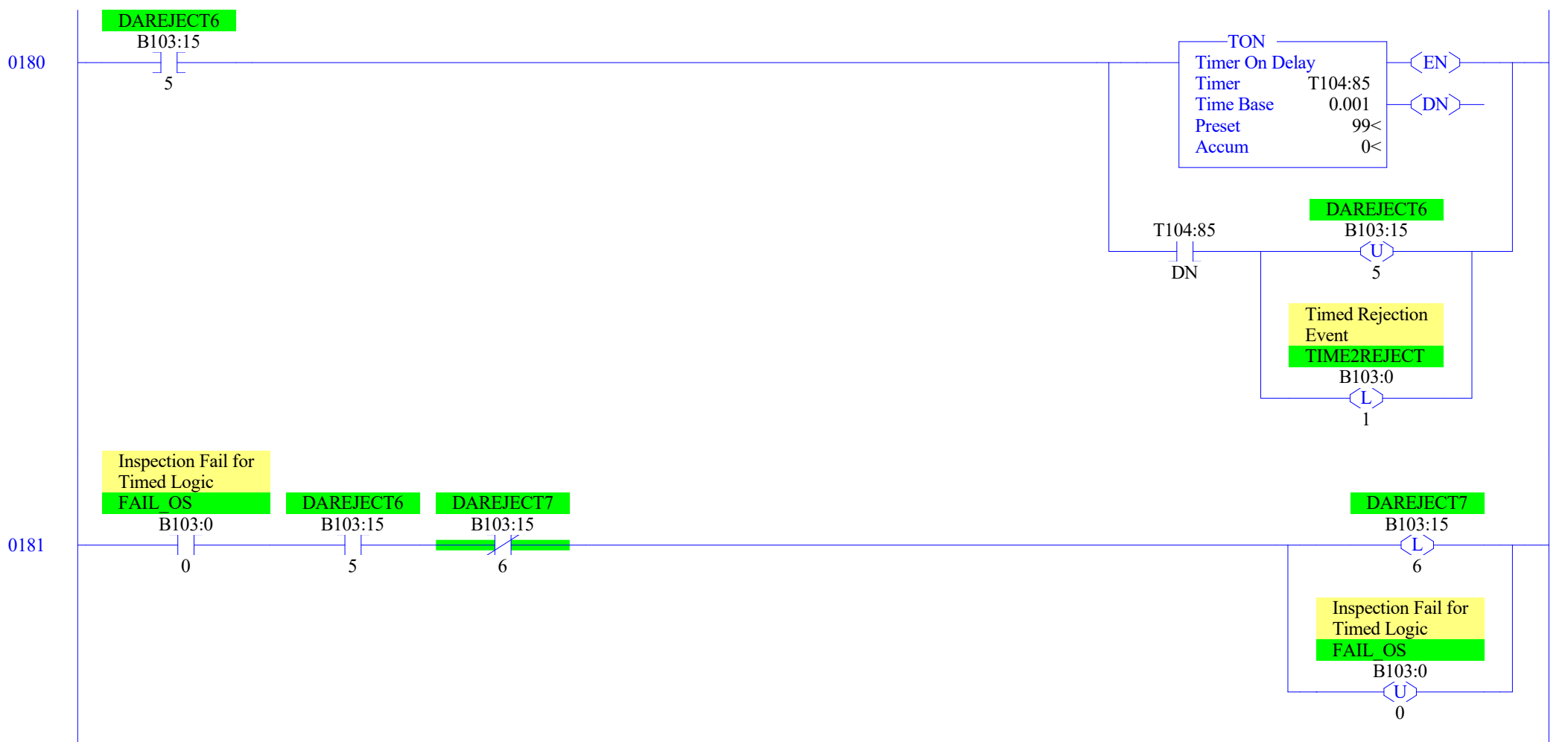


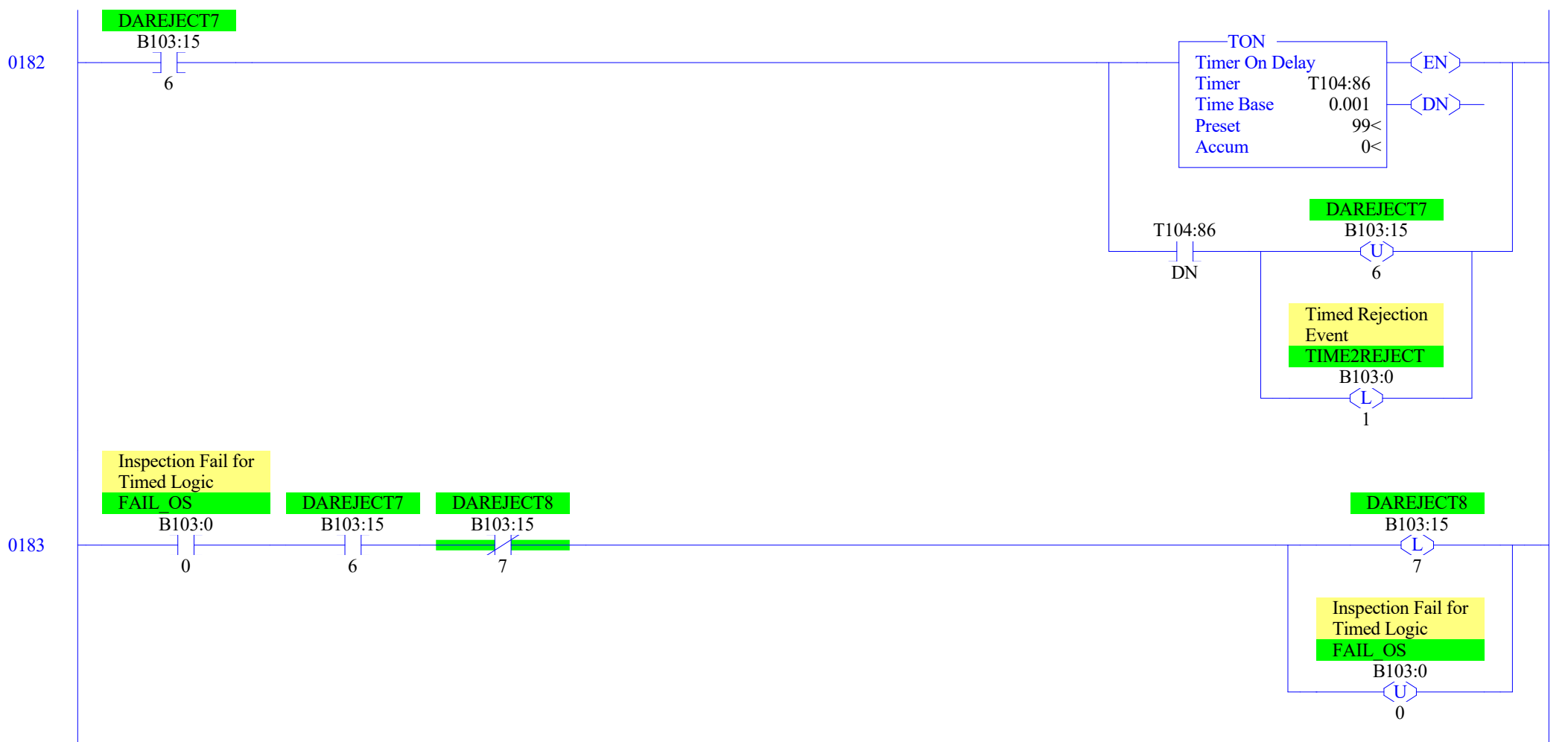


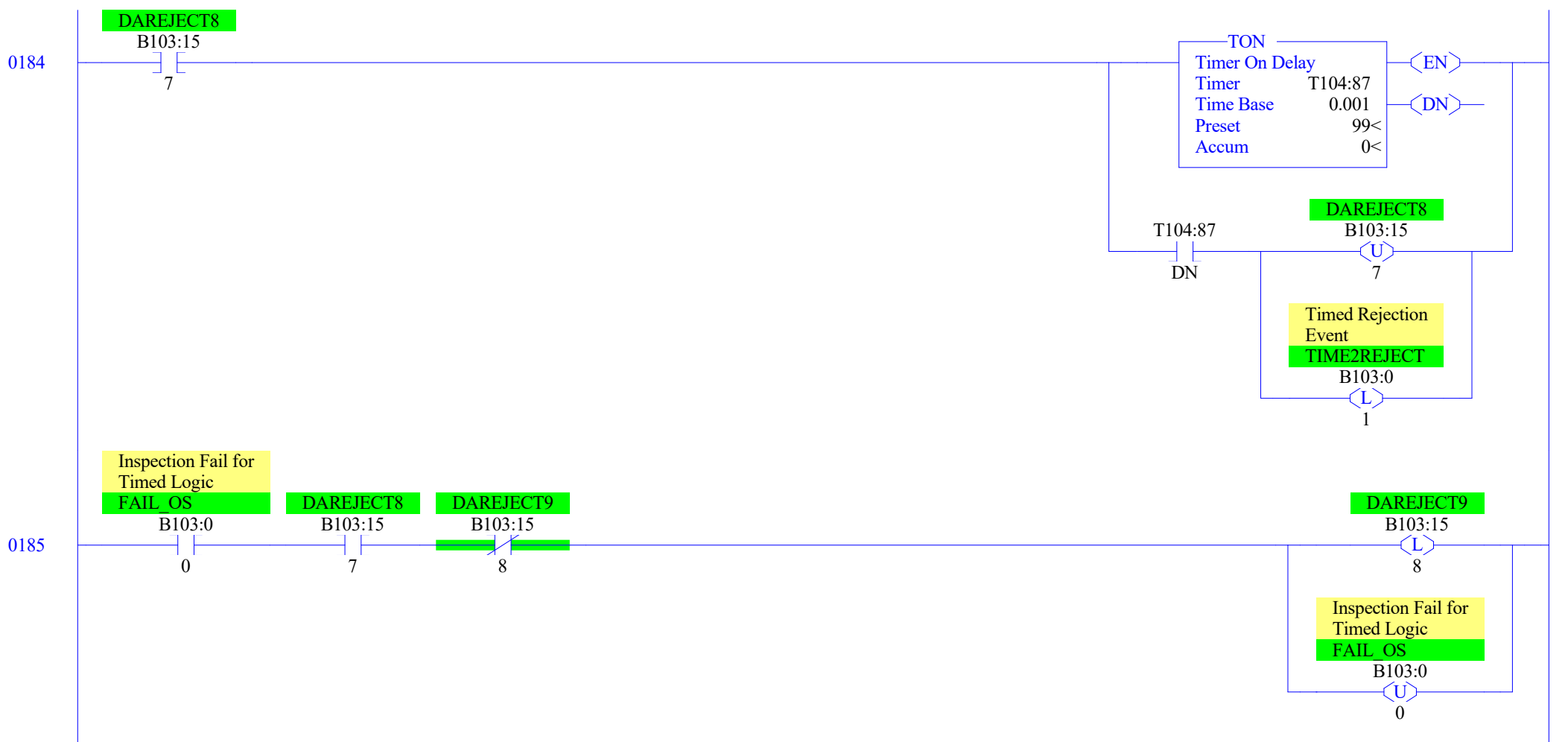


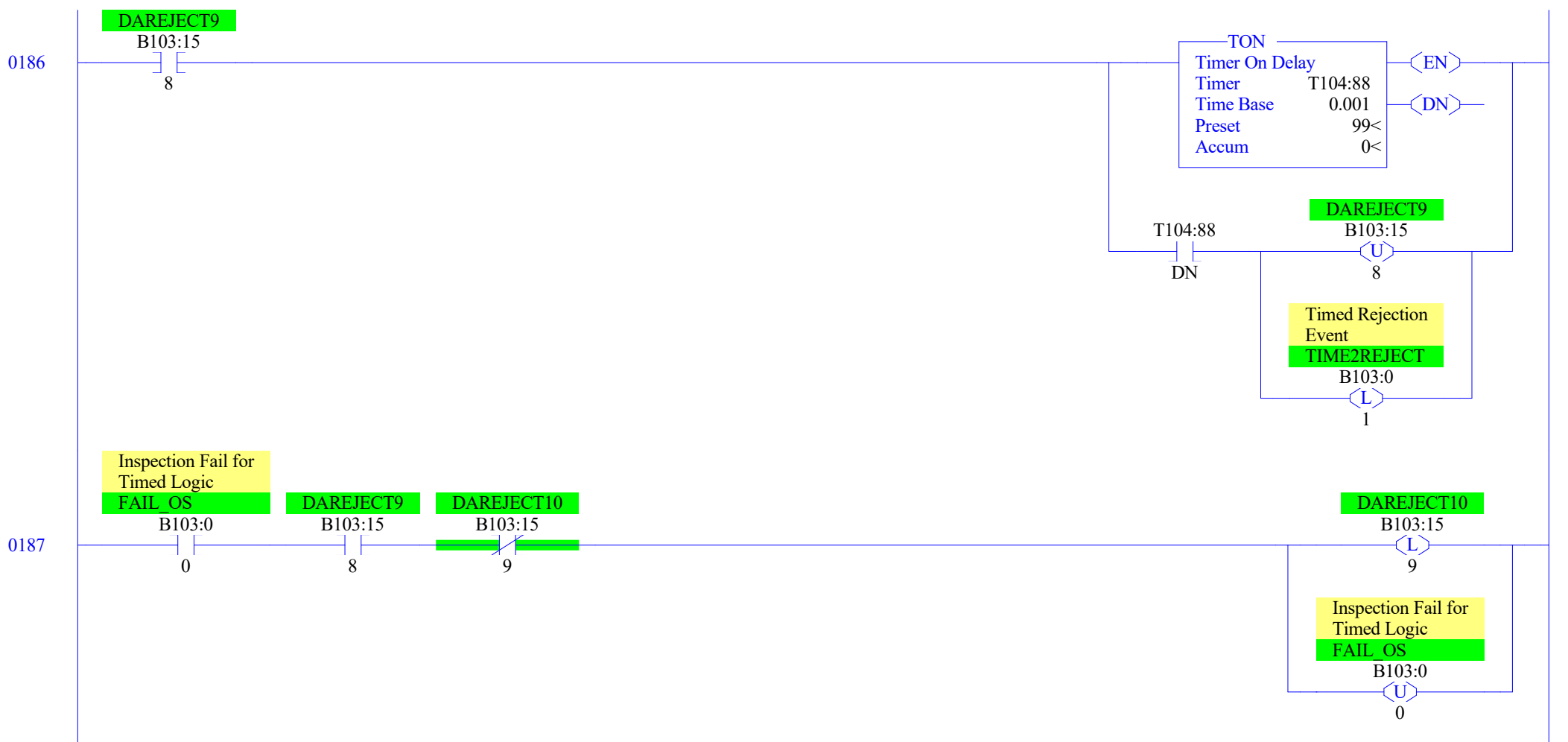


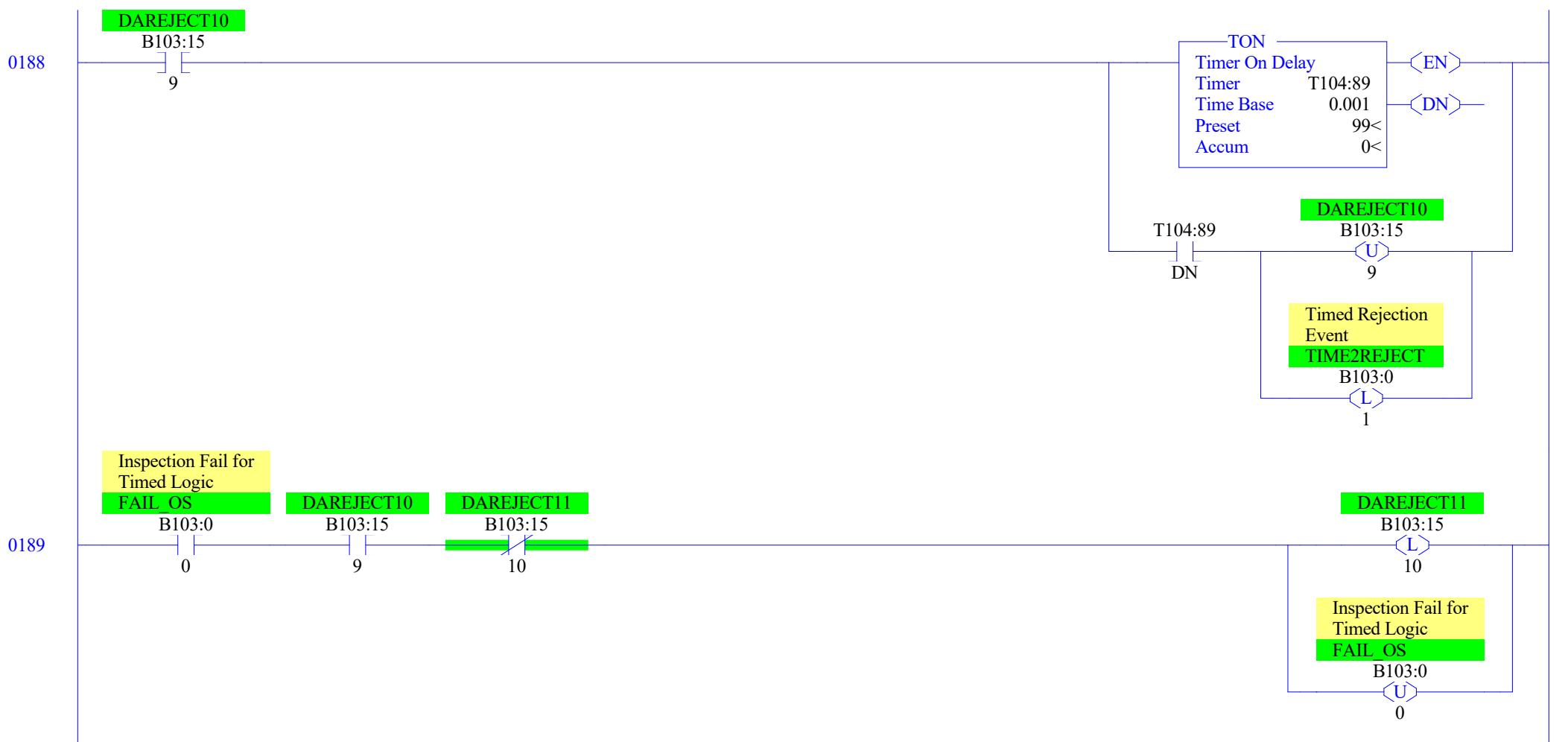


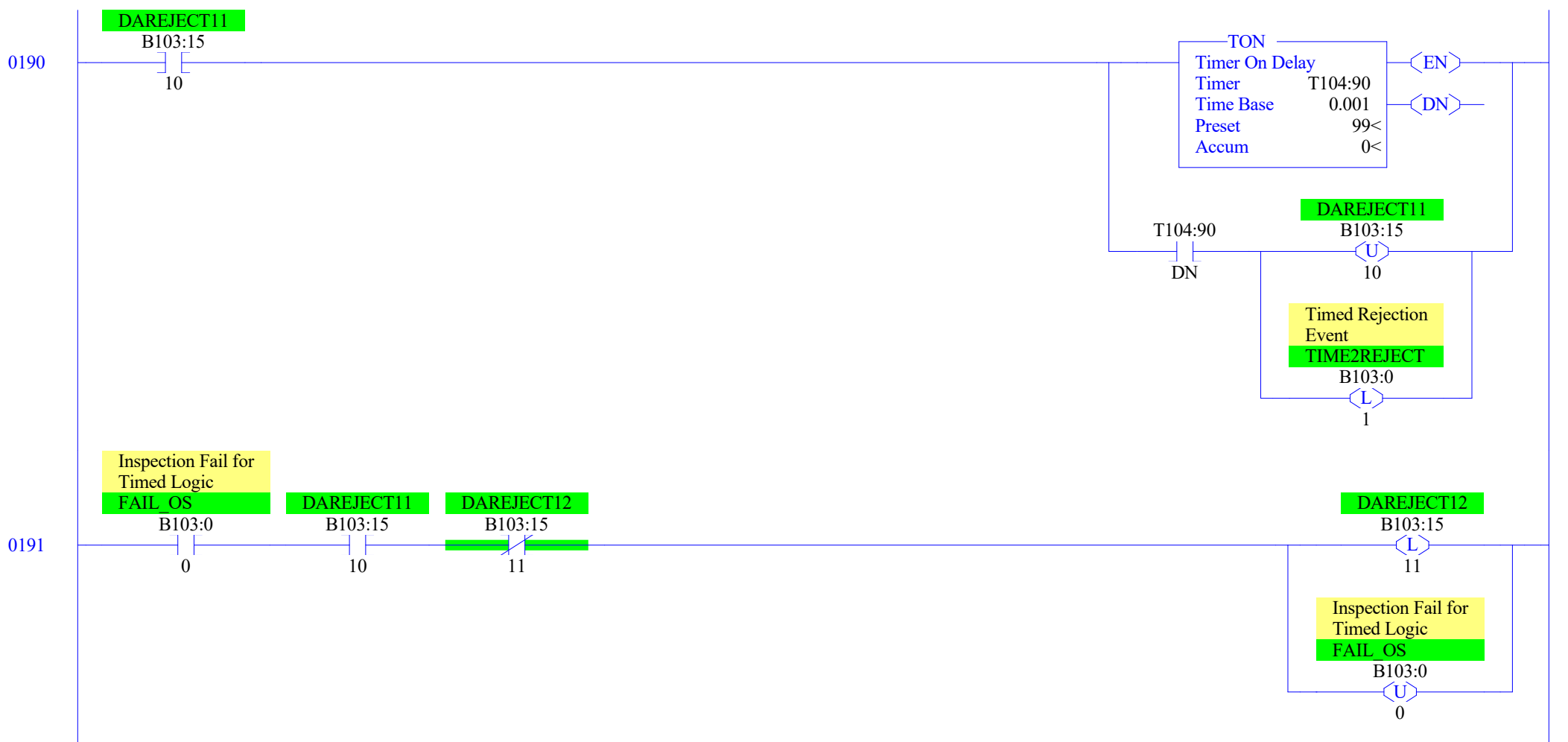


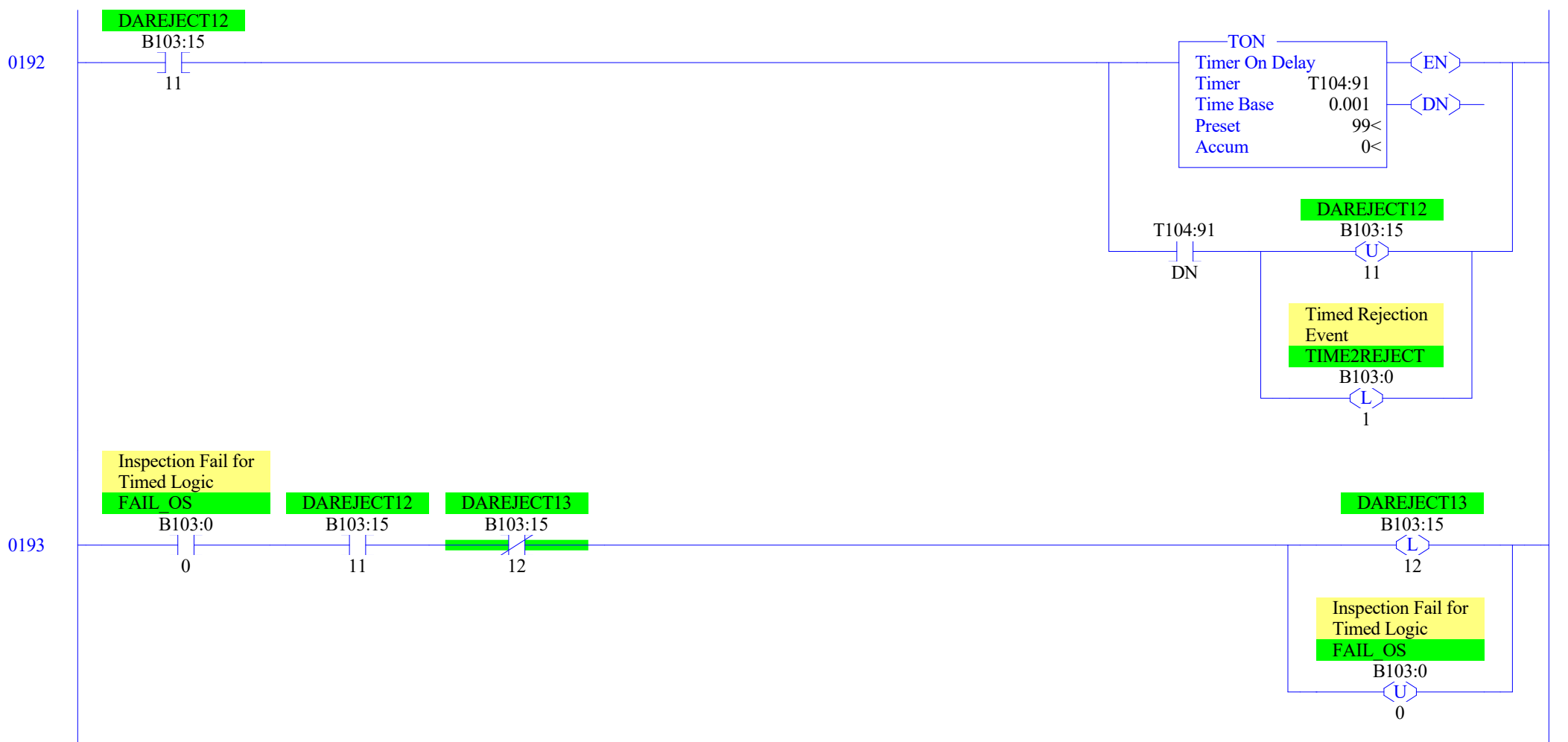


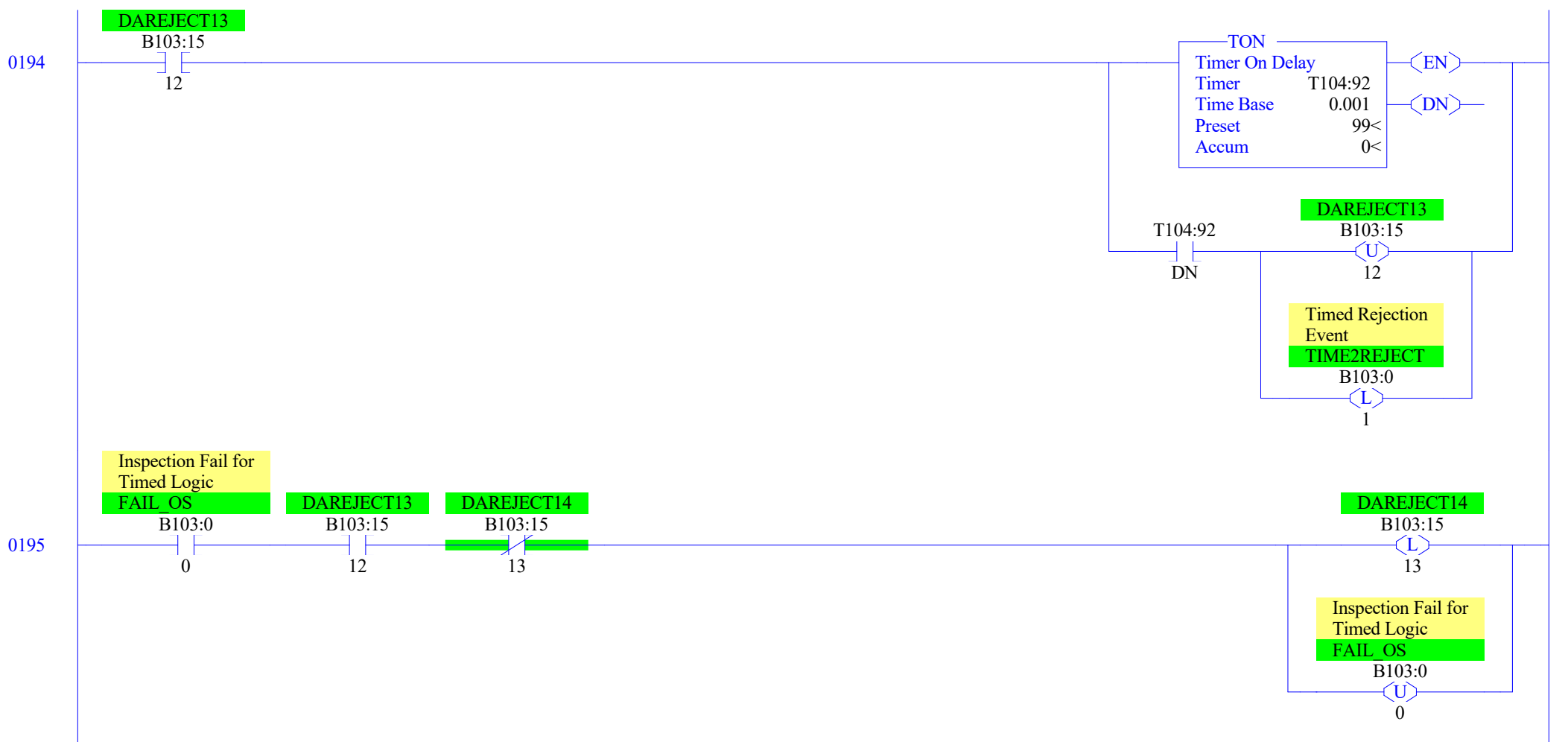


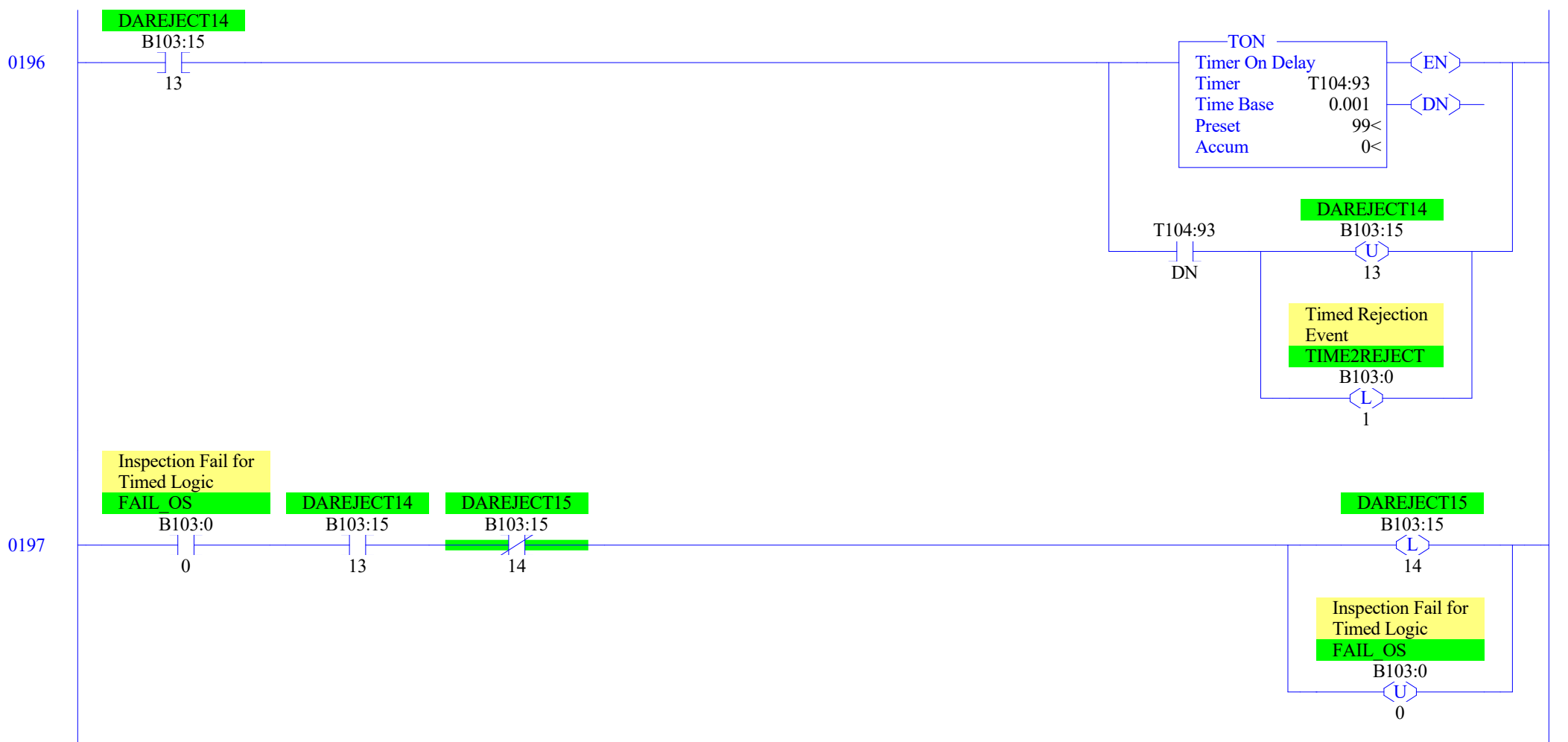


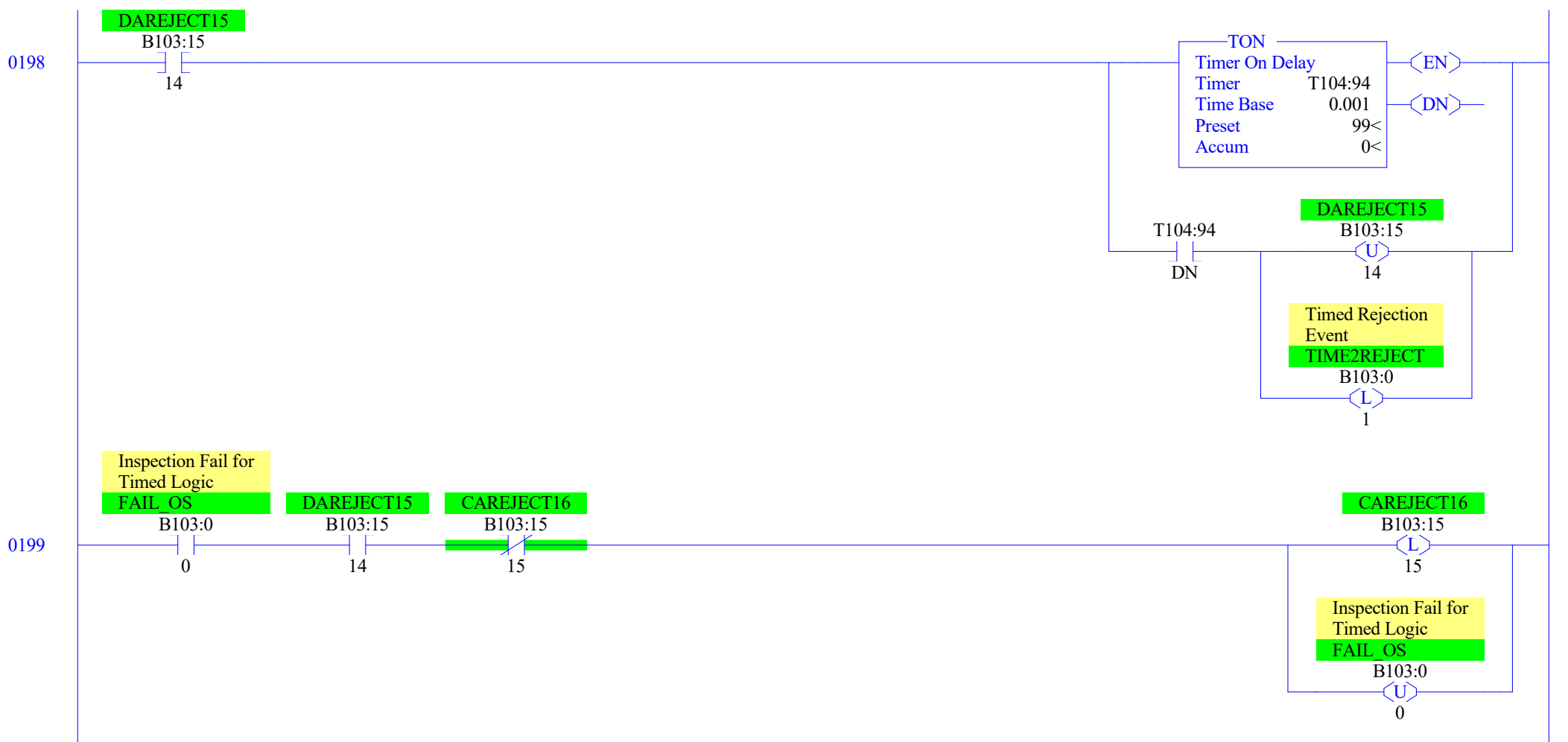


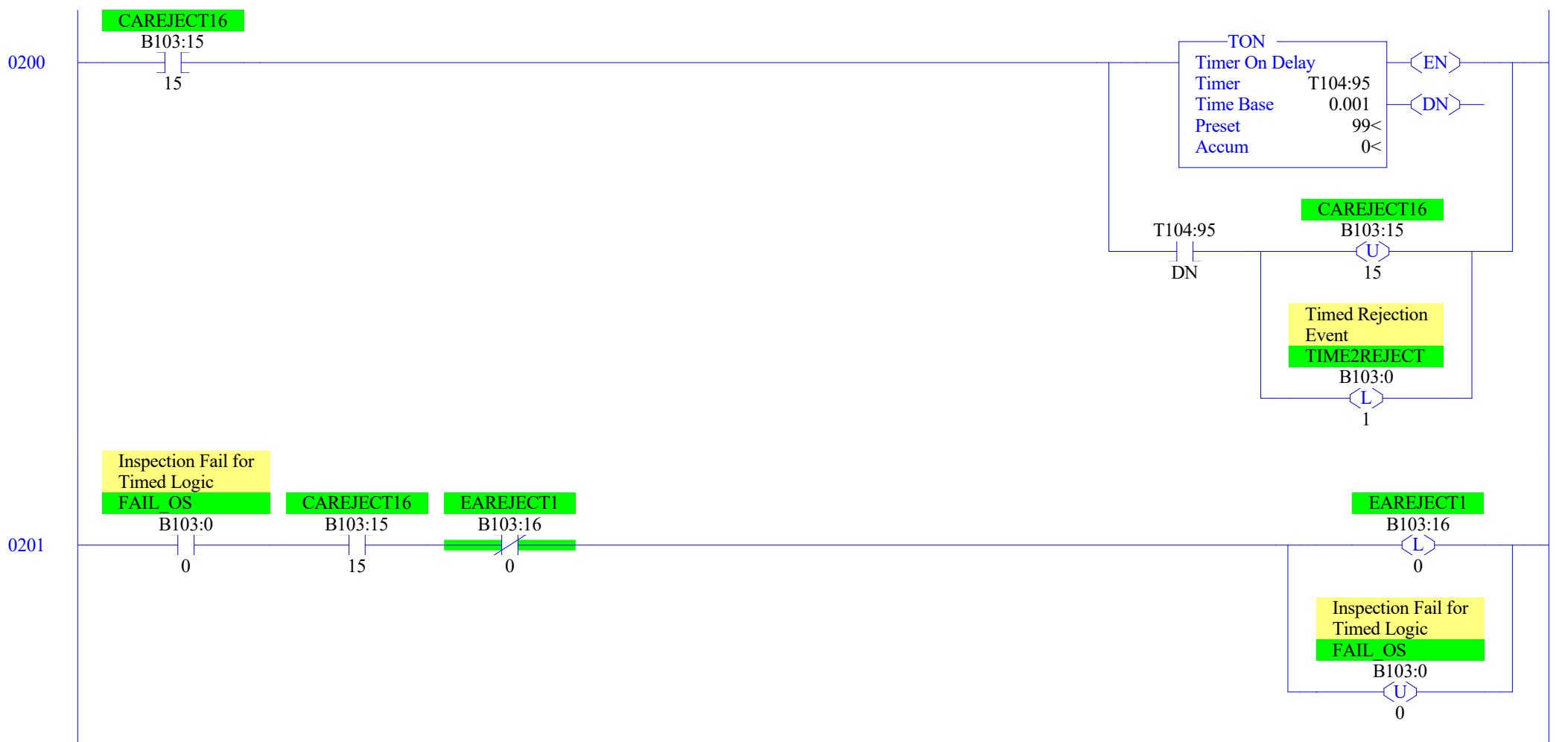


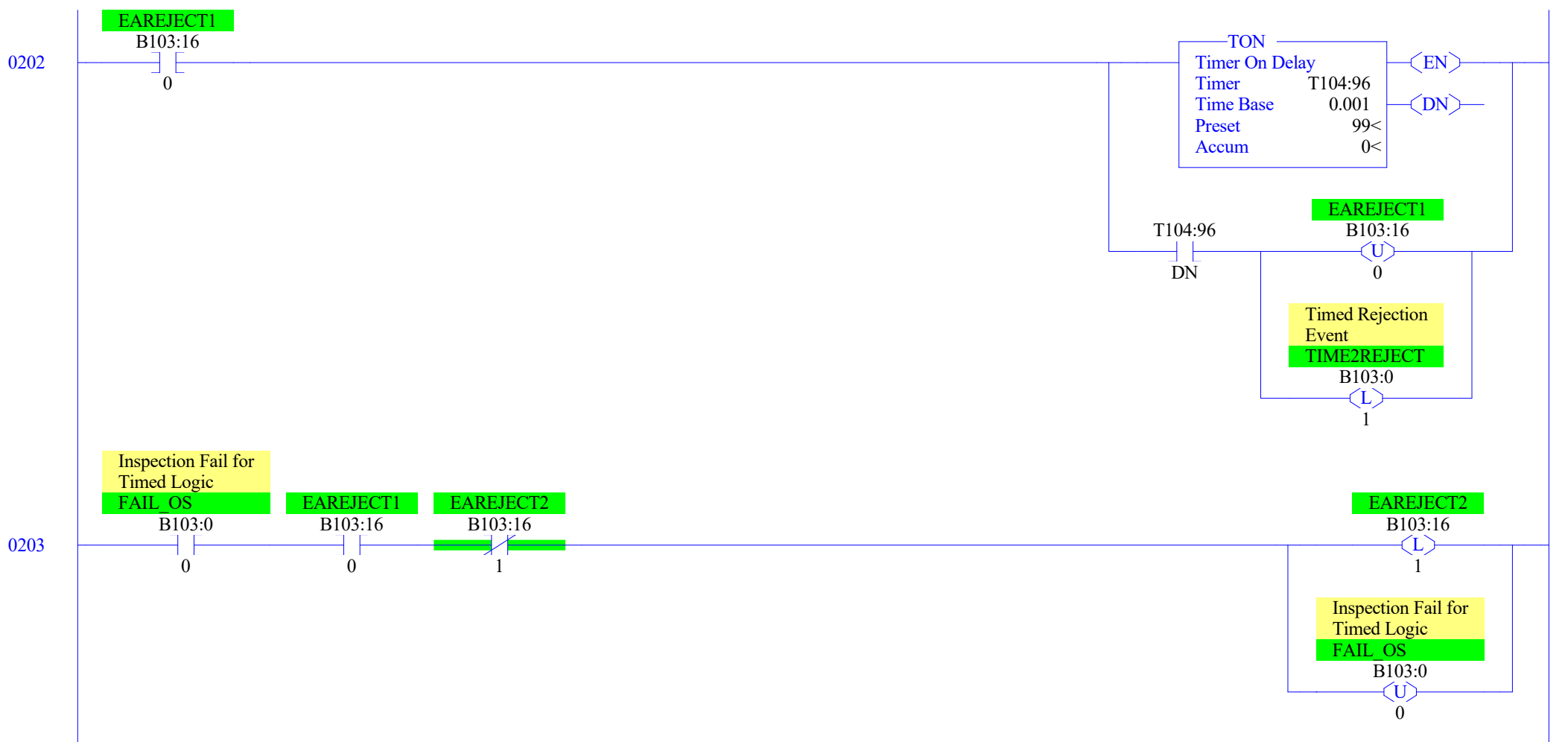


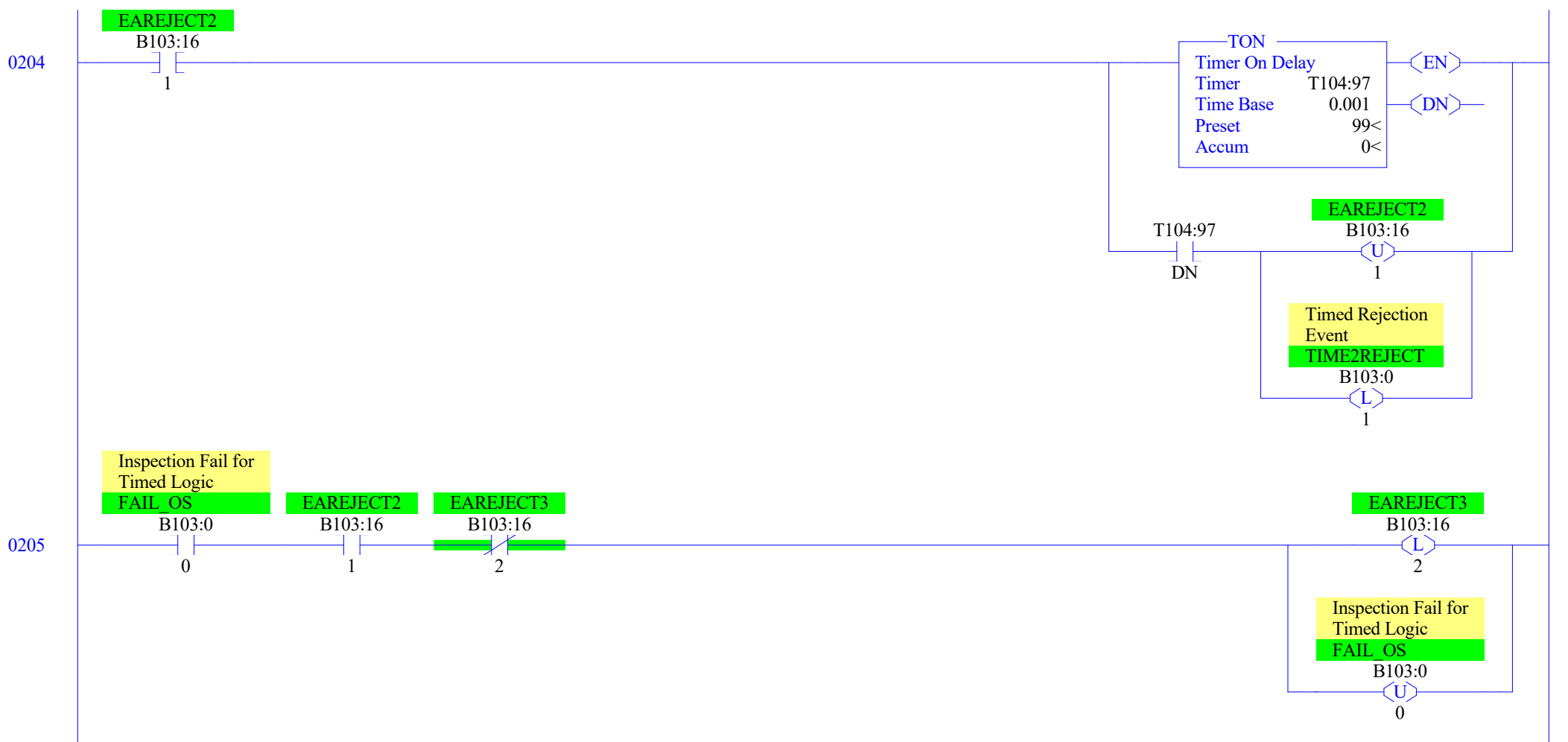


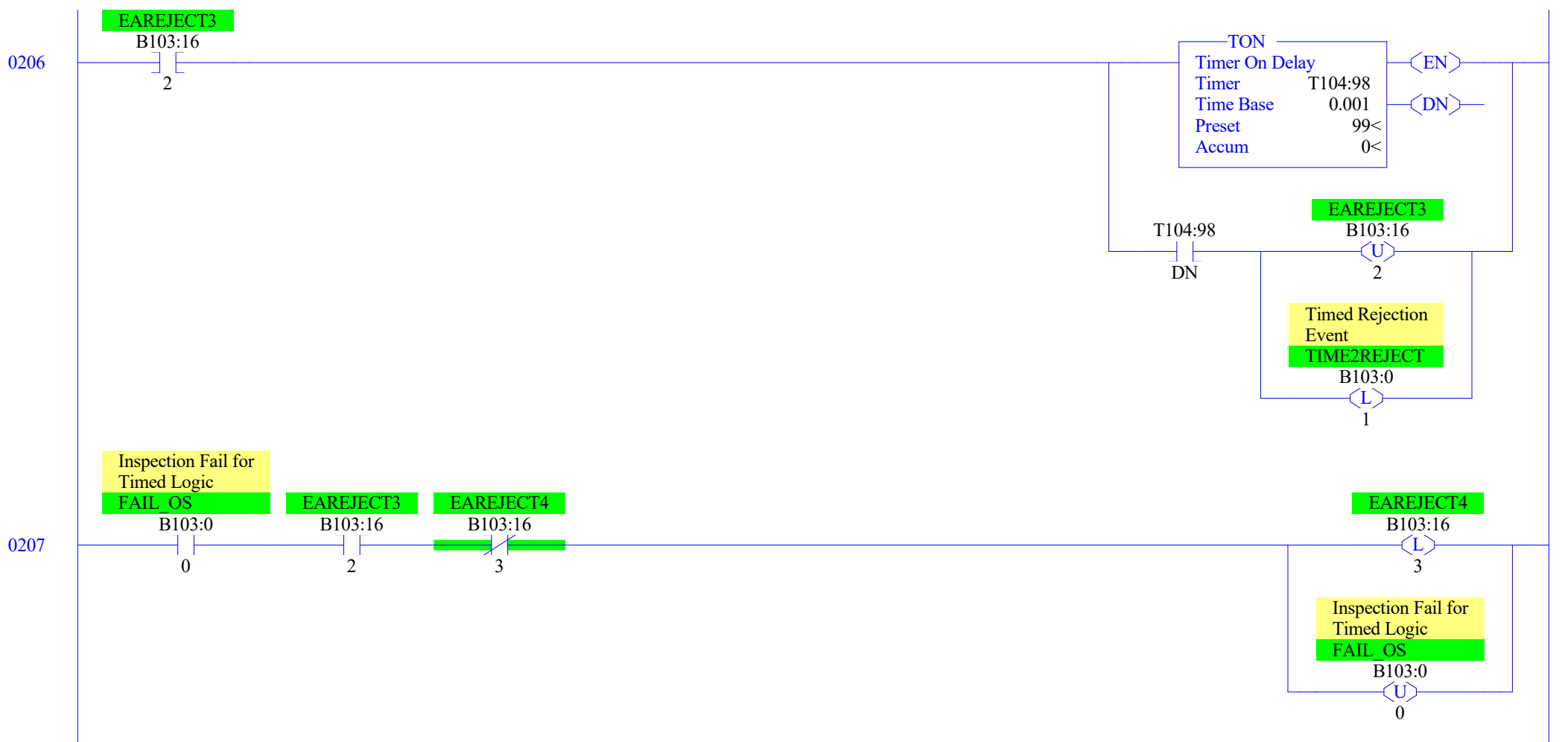


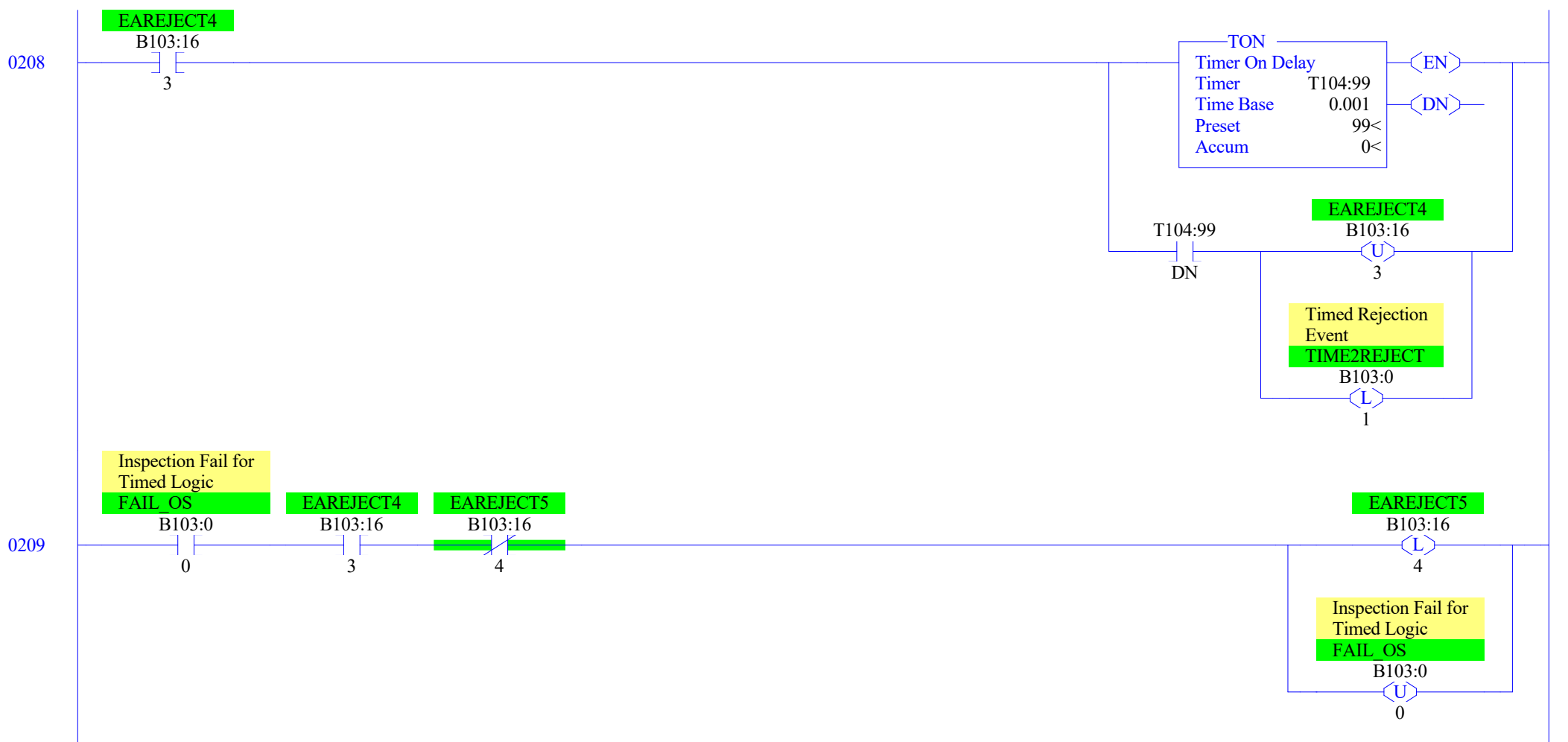


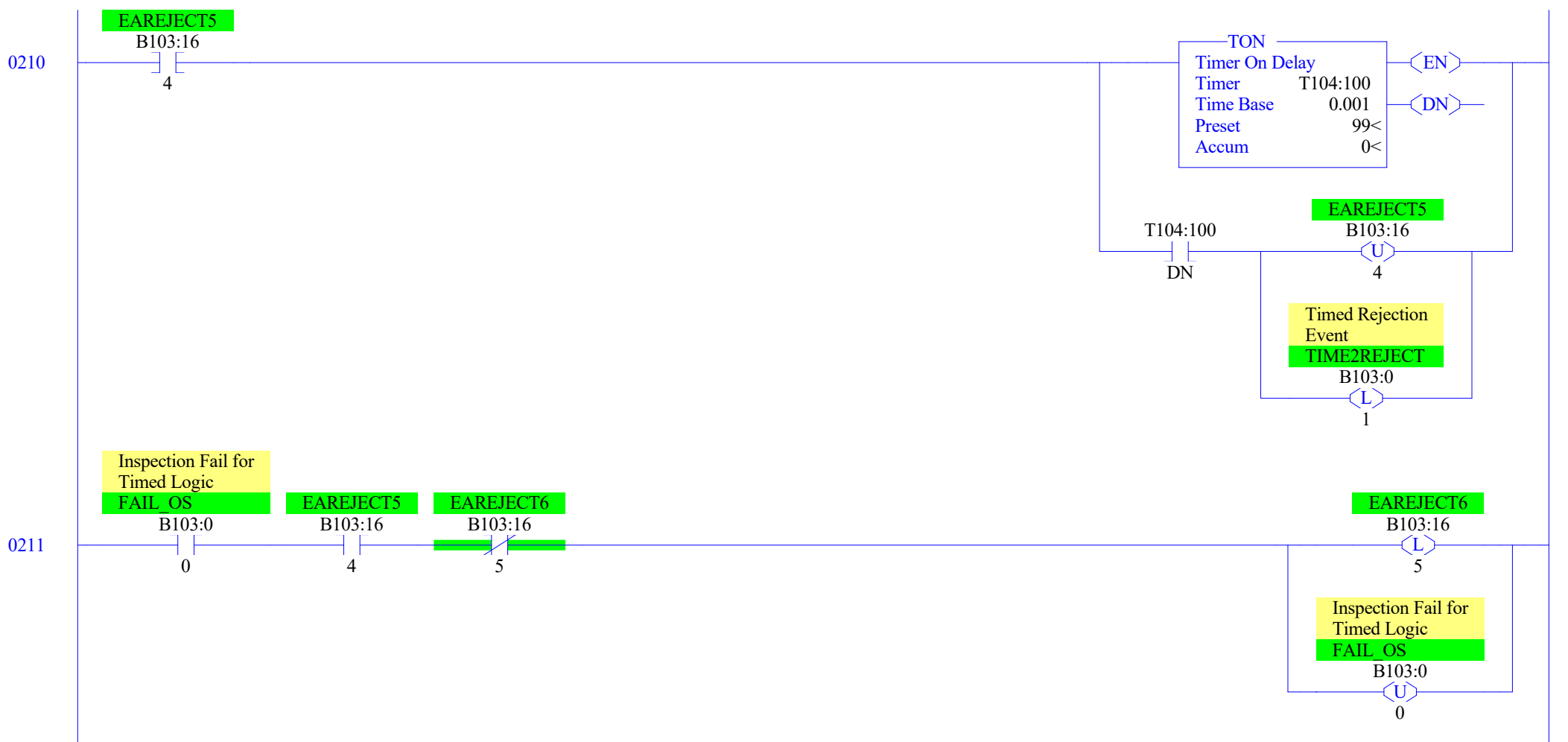


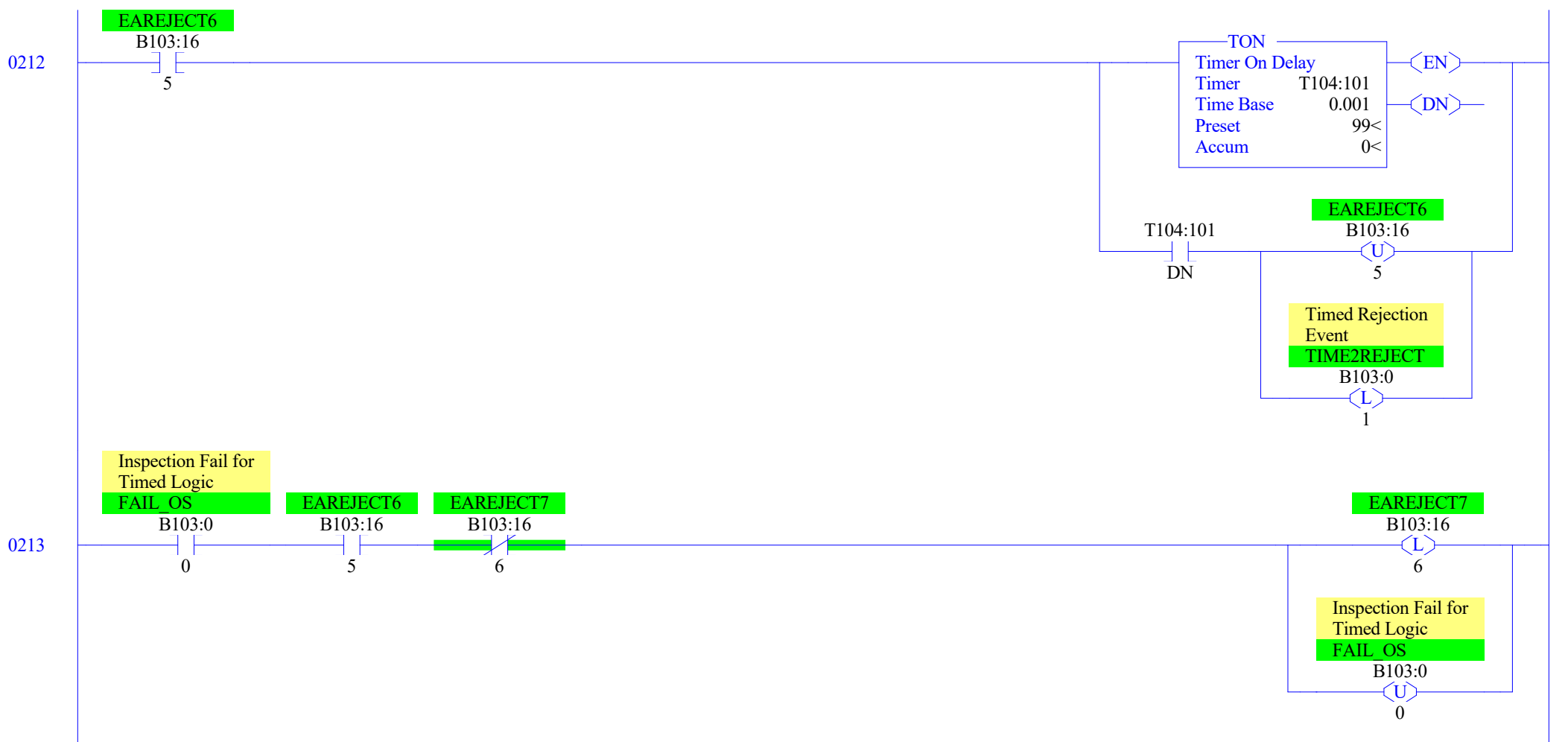


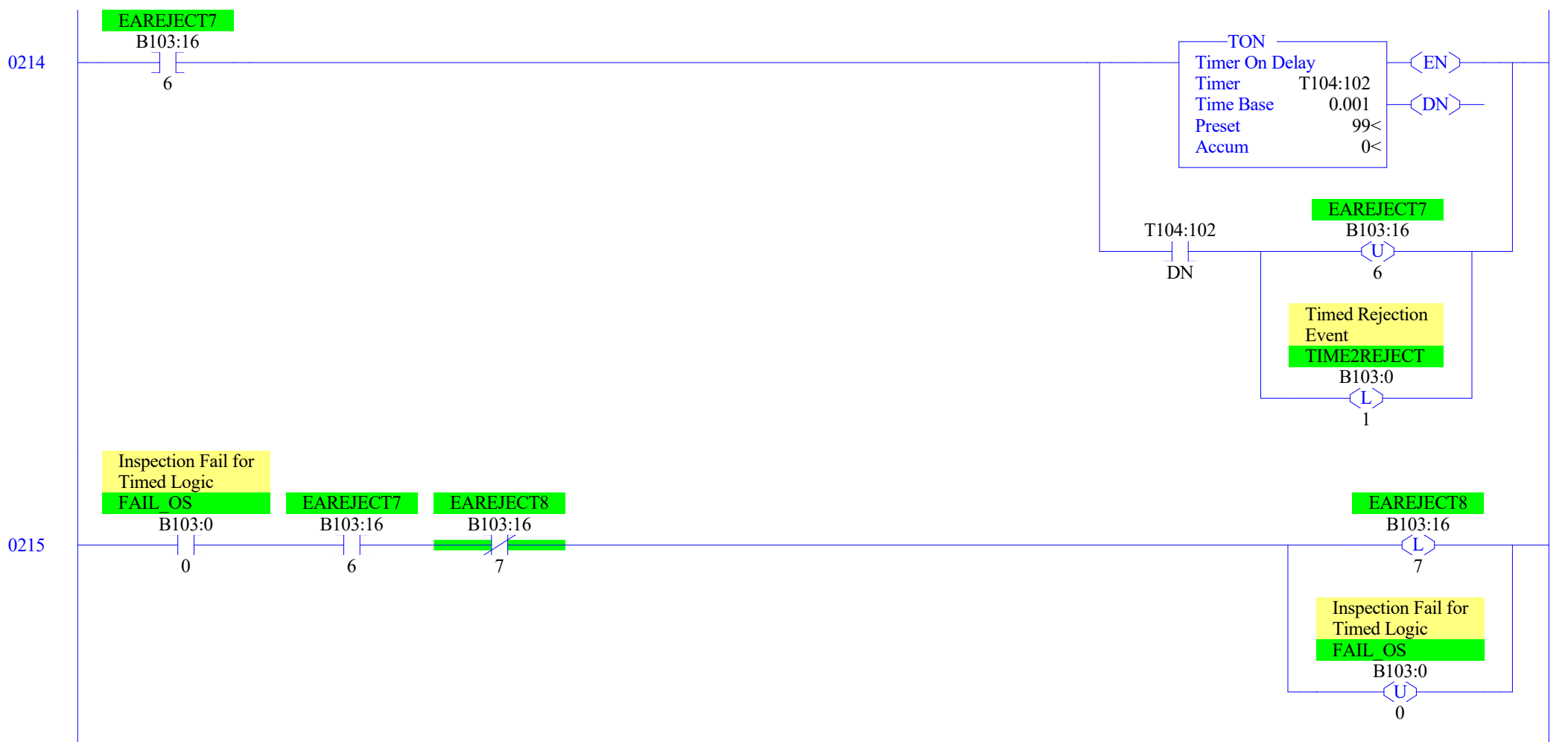


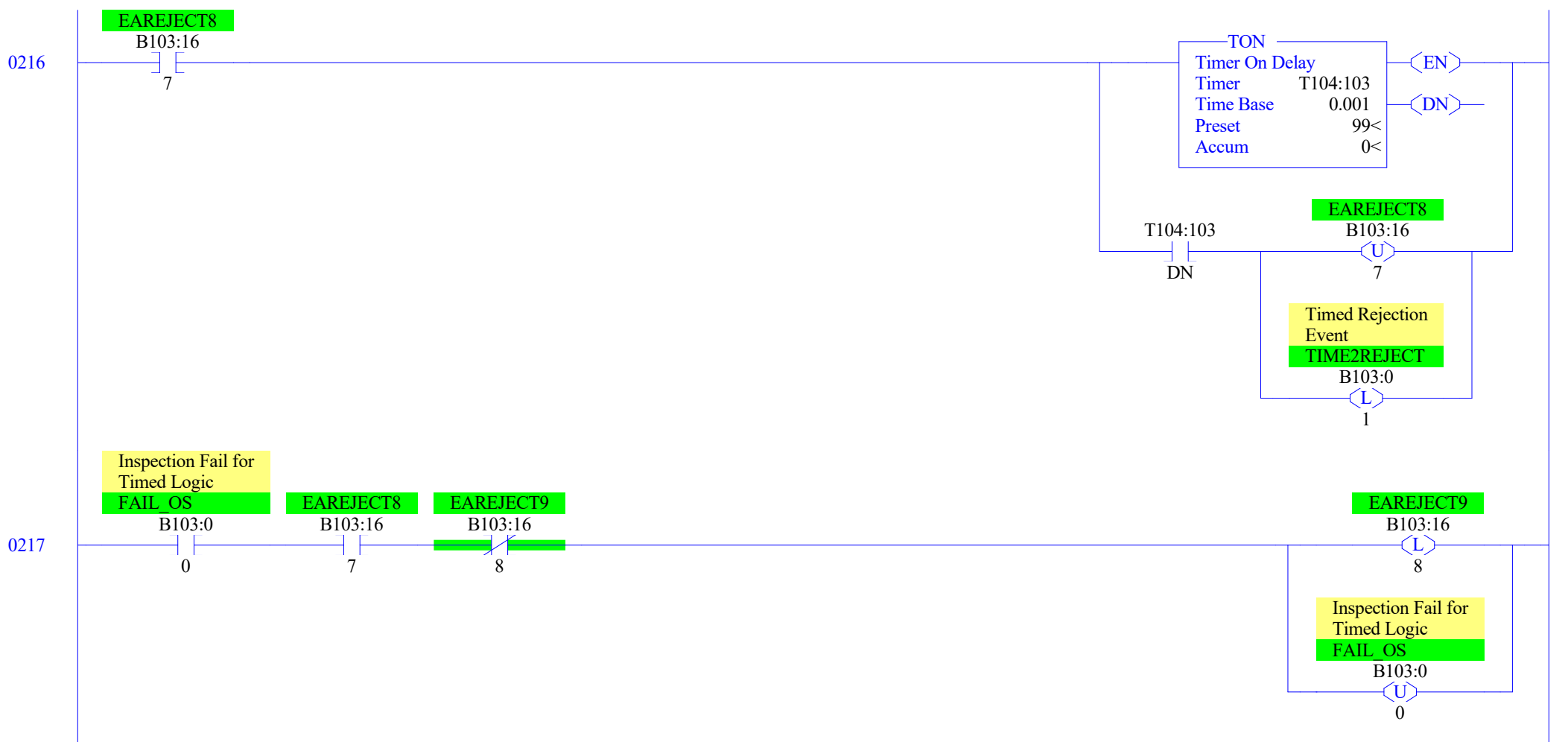


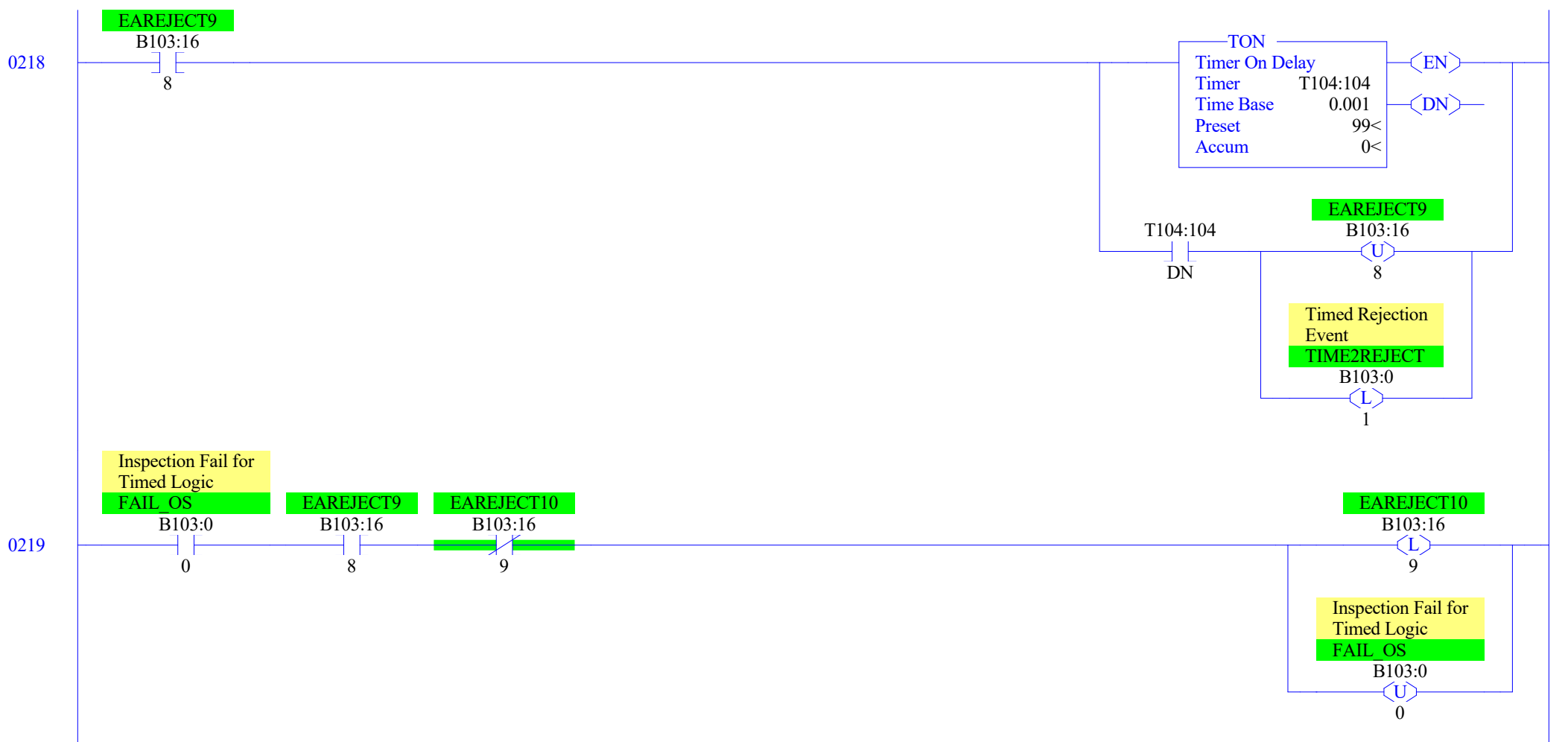


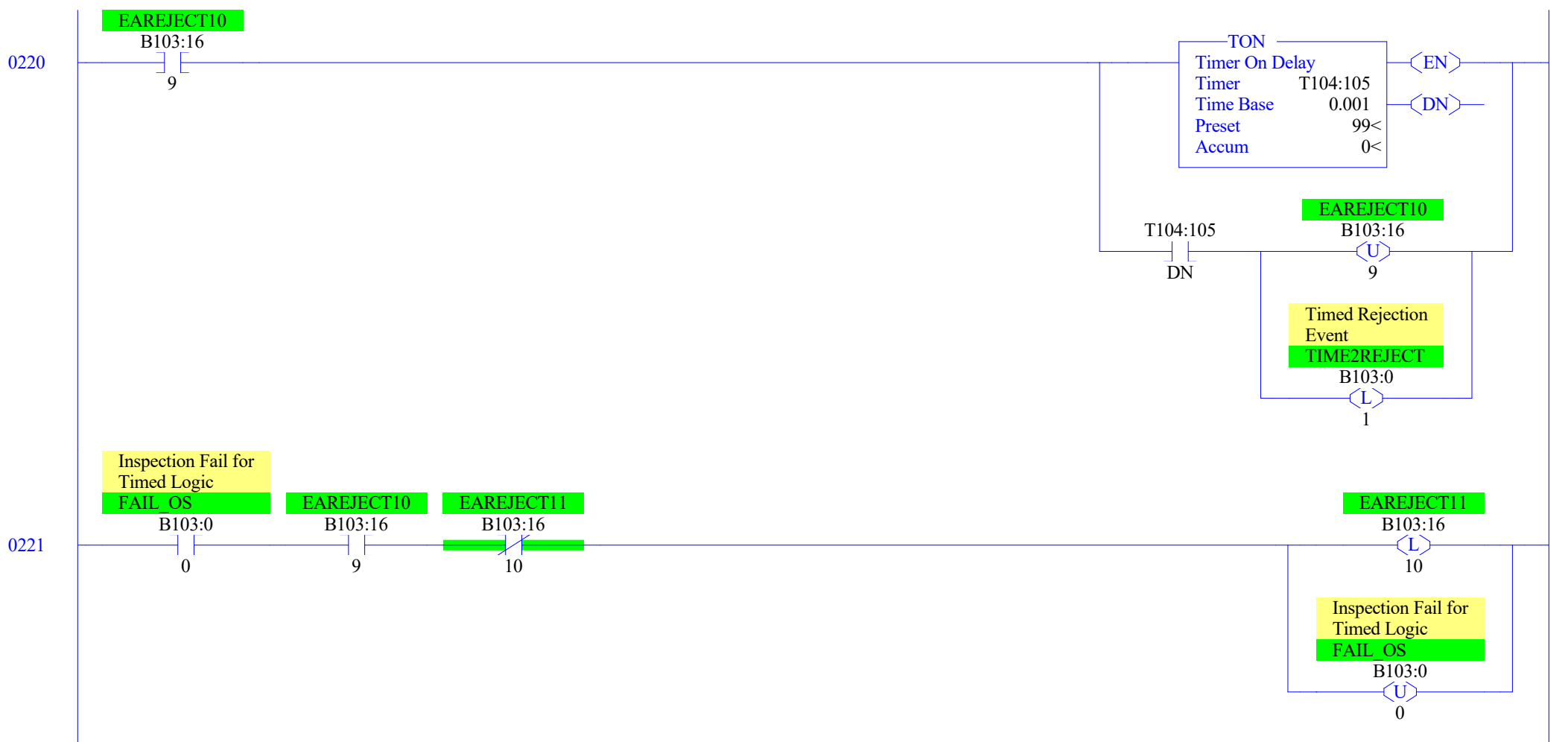


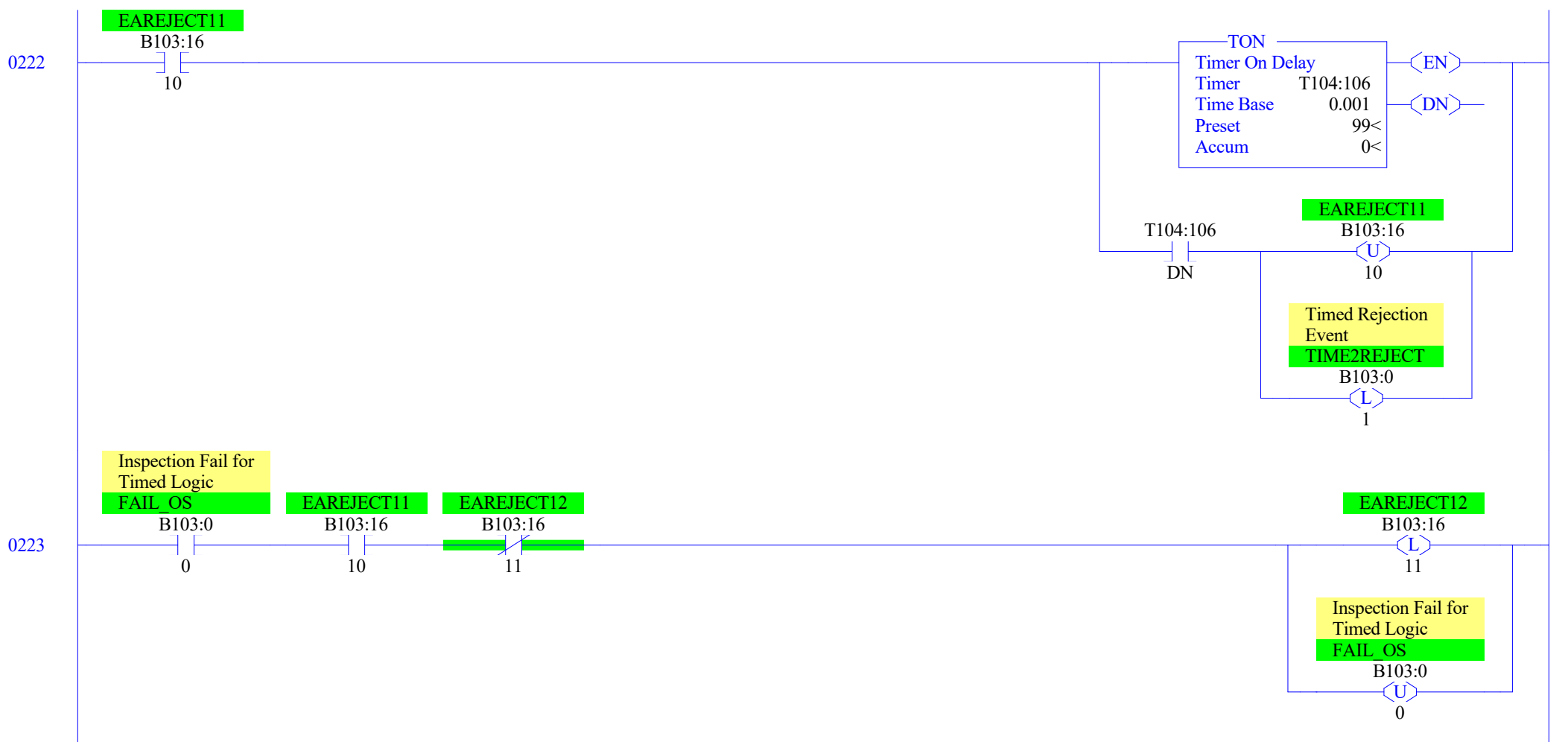


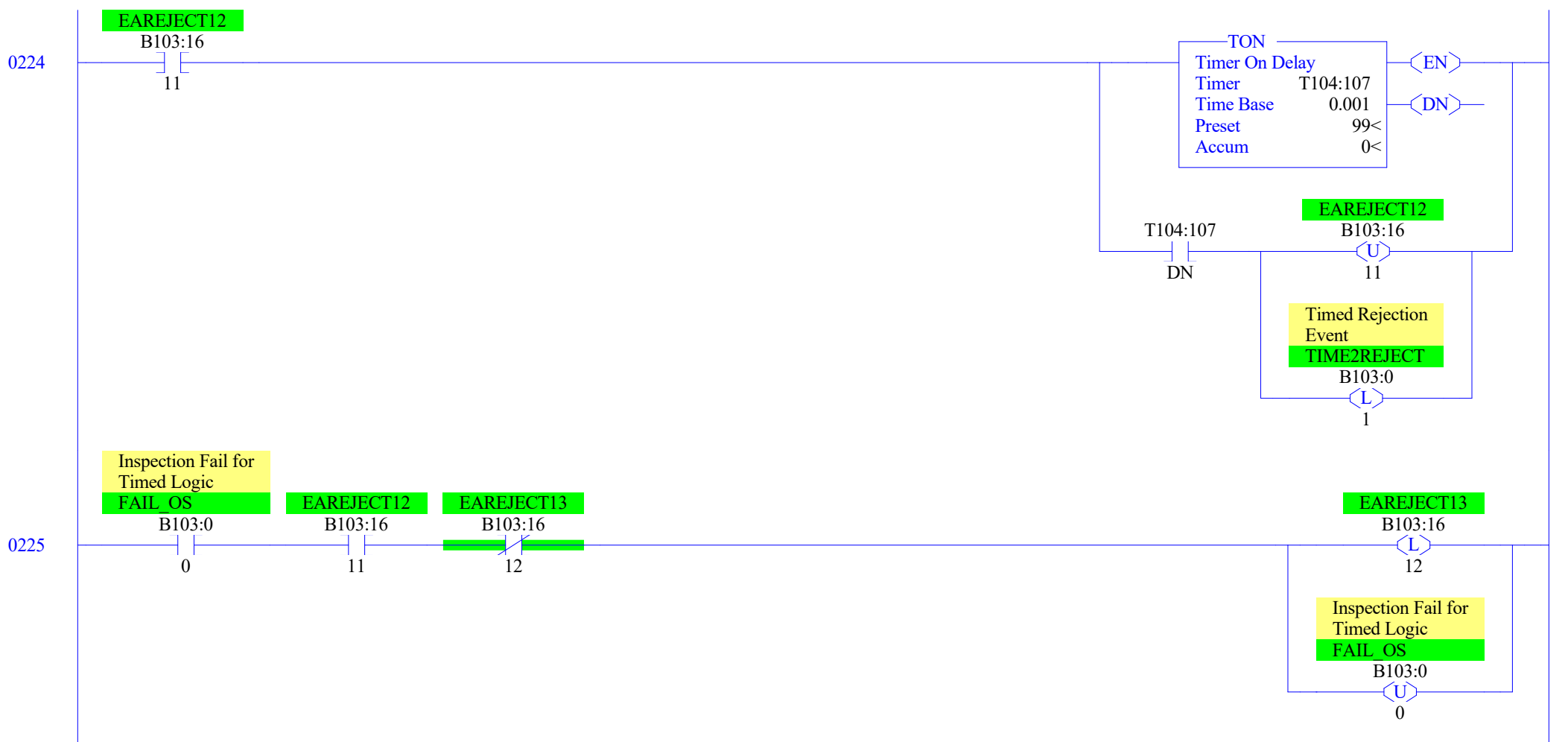


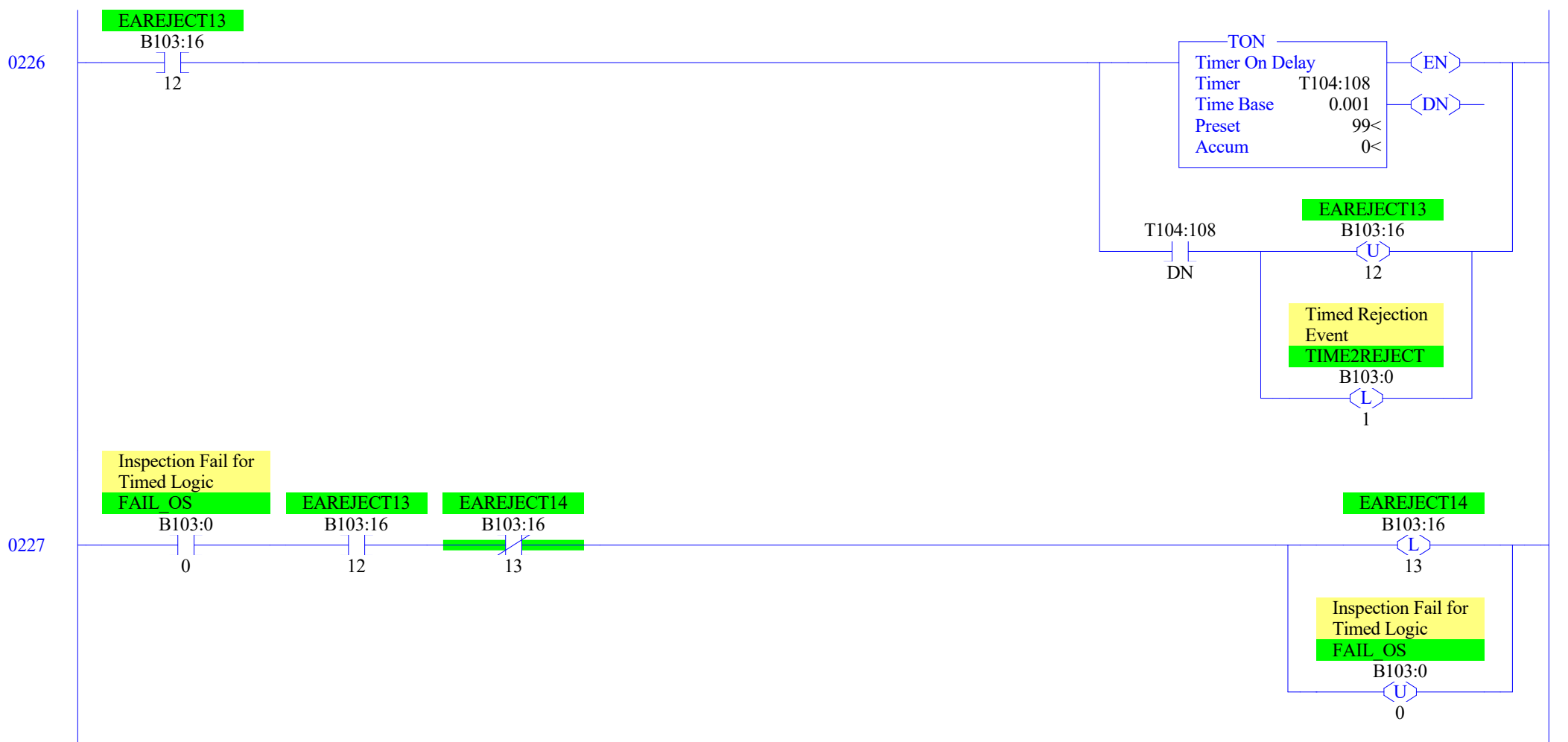


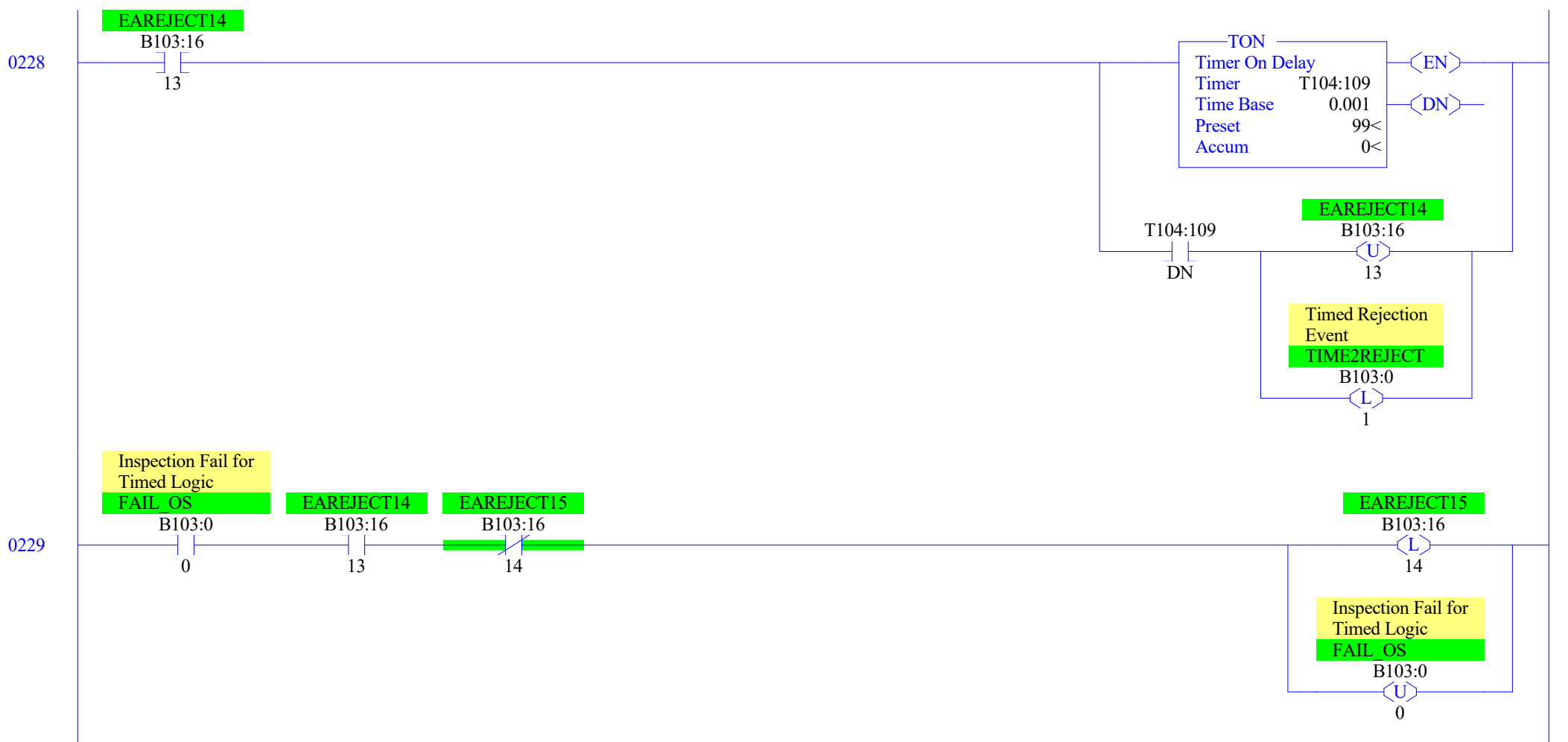


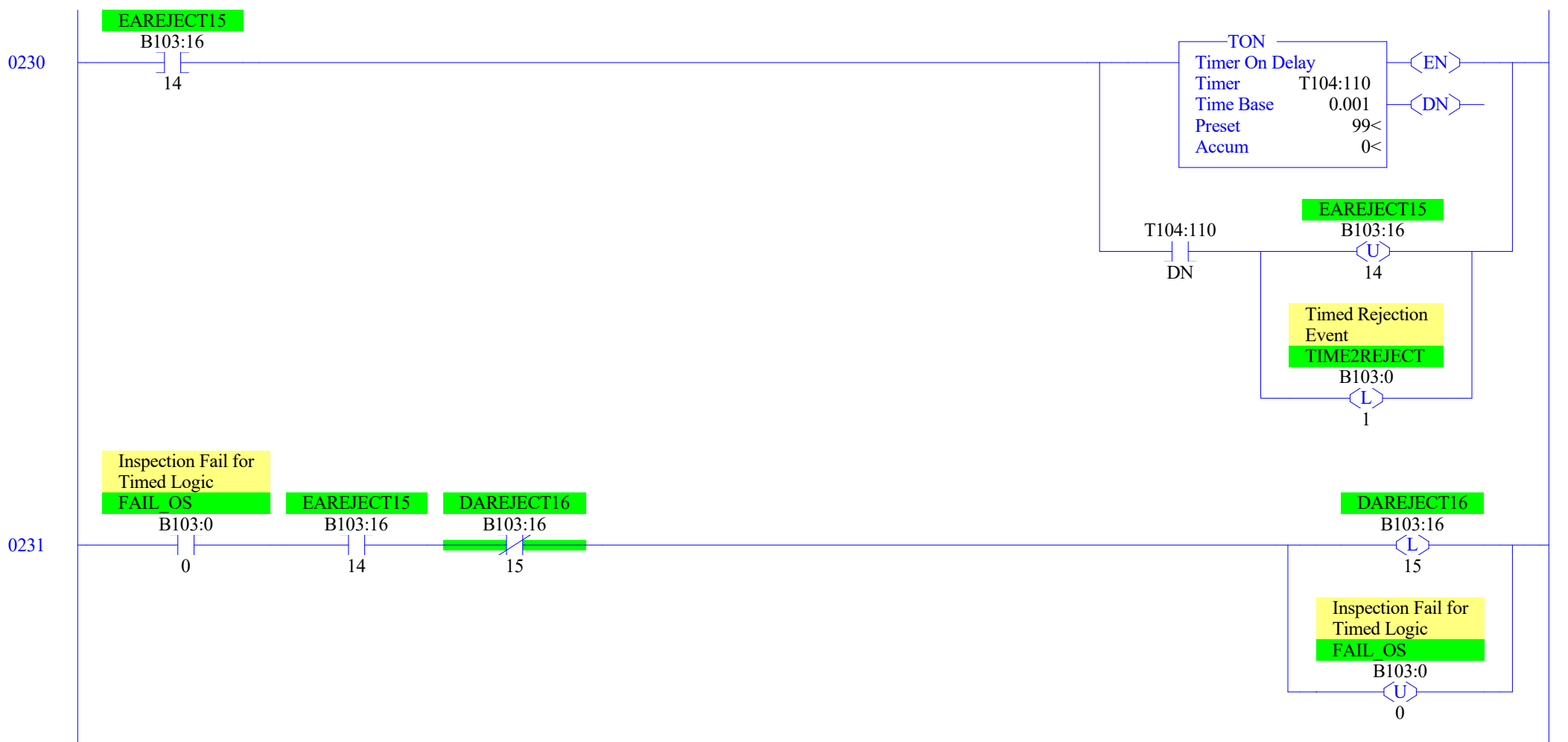






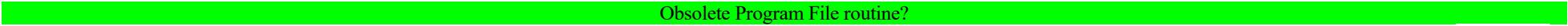








LAD 10 - 1MS_SCAN --- Total Rungs in File = 1

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Obsolete Program File routine?A horizontal blue line spanning the width of the page.
<END>

HSC0 Interrupt Routine: accumulate encoder counts; shift accept/reject bits

This Program File is executed, once, on each event when the count of encoder pulses in the value of the High-Speed Counter accumulator (HSC:0.ACC) reaches the HSC High Preset value (HSC:0.HIP). The HSC will automatically reset the HSC accumulator to 0 on each such event, because the HSC Mode (HSC:0.MOD) is 0.

A typical value for HSC:0.HIP seems to be 30, but it is assigned from the value of the integer ENCODER_HIPRESET_SP (N7:11) in the INSPECTION routine (LAD 4) at Rung 0002. whenever

- 1) the bit USE_ENCODER (B3:0/11) is 1, and
- 2) ENCODER_HIPRESET_SP differs from HSC:0.HIP.

Both USE_ENCODER and ENCODER_HIPRESET_SP originate in the GUI HMI..

The HSC function is only enabled (HSC:0/FE) when USE_ENCODER is 1, per the assignment of HSC:0/FE in MAIN_PROG routine (LAD 2) Rung 0002.

Rung 0000 adds the HSC High Preset value to the value of a working register, which register will, at regular intervals (300ms)*, be

- 1) Scaled to estimate the line speed, and
- 2) Cleared to 0.0 to initialize the estimate for the next interval

* Program File routine LAD 13 STI_SPEED, via Selectable Timed Interrupt

WORKING REGISTER**ADD**

Add	
Source A	HSC:0.HIP 30<
Source B	F18:11 0.0<
Dest	F18:11 0.0<

0000

Shift bits left in the bitstream (B11) left by one bit per interrupt

The value of the new bit (B13:1/0) loaded here (B11:0/0) is 0 i.e. we assume the can at "location" B11:0/0, which location models that of the inspection cameras, is not a reject; once that 0 is in place, on the rising edge of a reject event from a camera between now and the next HSC0 interrupt, that bit's value is changed to 1 at Rung 0005 of Program File routine LAD 4 INSPECTION.

BitShift Left 1
Control Register

BSL

Bit Shift Left	#B11:0
File	R16:0
Control	B13:1/0
Bit Address	2000<
Length	

<EN>

<DN>

Clear the /EN bit of the control register, so the BSL instruction above will "detect" a rising edge of its input rung when the next HSC0 interrupt executes this routine.

BitShift Left 1
Control Register

R16:0

U

EN

BitShift Left 1
Control Register

R16:0

U

DN

<END>

LAD 12 - EII_COUNTS - count events to determine speed --- Total Rungs in File = 1

Event Interrupt - obsolete Program File routine

See Function Files => EII:0 (Event Input Interrupt)

- EII:0.PFN (Program File Number) was probably 12 at one point
- EII:n.EIE (Event Interrupt Enable) is now 0 for all n (0-3) => all Event Input Interrupts are disabled

0000

<END>

Estimate motor speed in RPM

This Program File routine is executed at regular intervals (300ms) via Selectable Timed Interrupt (STI)

Pulses have been accumulating into the value of WORKING_REGISTER by the High-Speed Counter Interrupt 0 routine (LAD11 HSC0).

Determine number of pulses per minute.

This logic scans every 300 milliseconds so multiply the accumulated number of pulses by 200 to calculate the number of pulses per minute

CALCD_PPM

MUL

Multiply	
Source A	F18:11 0.0<
Source B	200.0 200.0<
Dest	F18:14 0.0<

Clear number of pulses in WORKING_REGISTER to start the accumulation for the next STI event

WORKING_REGISTER

CLR

Clear	
Dest	F18:11 0.0<

Move the calculated linespeed from the last STI execution of this routine (F8:15; RPM) to the previous calculated linespeed (F8:16)

PREV_LINESPEED

MOV

Move	
Source	F18:15 0.0<
Dest	F18:16 0.0<

0003

Divide pulses/minute by 100pulses/revolution to get current calculated linespeed (F8:15; RPM)

CURR_LINESPEED

DIV

Divide	
Source A	F18:14
	0.0<
Source B	100.0
	100.0<
Dest	F18:15
	0.0<

0004

Average the current and previous calculated linespeeds to use as the estimated linespeed (F8:10; RPM)

AVE_LINESPEED

ADD

Add	
Source A	F18:15
	0.0<
Source B	F18:16
	0.0<
Dest	F18:10
	0.0<

AVE_LINESPEED

DIV

Divide	
Source A	F18:10
	0.0<
Source B	2.0
	2.0<
Dest	F18:10
	0.0<

0005

<END>