```
PROGRAM Robot Drive 2
2
3
          Robot Speed Left : REAL ;
4
          Robot Speed Right : REAL ;
5
          Joystick LR : REAL ;
6
          Joystick UD : REAL ;
7
          Pendant Left: BOOL;
8
          Pendant Right : BOOL ;
9
          Pendant FWD: BOOL;
10
          Pendant REV : BOOL ;
11
          Dir State : INT ;
12
          Robot Speed Left Stopped: REAL := 2.60;
13
14
          Robot Speed Right Stopped: REAL := 2.60;
15
16
          Robot_Drive_Speed : REAL ;
17
          Dir State1 : BOOL ;
18
          Dir_State2 : BOOL ;
19
          Dir_State3 : BOOL ;
20
          Dir_State4 : BOOL ;
21
     END VAR
22
1
       //Set Speeds
2
       LTC2619 . Analog1 := Robot Speed Left;
3
       LTC2619 . Analog2 := Robot_Speed_Right;
4
5
       , 0 , 0 , xBit1 := NOT Modbus1 . MB_Inputs [ 16 ] . 1 , xBit0 := NOT Modbus1 . MB_Inputs
       [16].0,));
6
7
       CASE Dir_State OF
8
           0: //Its off
9
10
          Robot_Speed_Left := Robot_Speed_Left_Stopped;
11
          Robot_Speed_Right := Robot_Speed_Right_Stopped;
12
13
           1: //Its FWD/REV
14
          Robot_Speed_Left := Robot_Speed_Left_Stopped + Robot_Drive_Speed;
15
          Robot_Speed_Right := Robot_Speed_Right_Stopped + Robot_Drive_Speed;
16
17
           2: //Its UP/DOWN
18
           Robot_Speed_Left := Robot_Speed_Left_Stopped - Robot_Drive_Speed;
19
           Robot Speed Right := Robot Speed Right Stopped + Robot Drive Speed;
20
21
       END CASE
22
23
       Robot Drive Speed := SCALE R (X := WORD_TO_REAL (Modbus1 . MB Inputs [ 12 ] ) , I LO
       := 0.0, I HI := 1000.0, O LO := -0.5, O HI := 0.5);
24
25
```

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