- **Controller Huber_PLC**
- **Controller Fault Handler**
- **Power-Up Handler**

Tasks

- **MainTask**
  - **MainProgram**
    - **MainRoutine**
    - **Fanuc_Robot_Control**
    - **HMI_UI**
    - **Kuka_Robot_Control**
    - **Pycomm**
    - **Robotics_Control**
  - **Research**
    - **Kuka_Control**
    - **Kuka_Robot_Control**
- **Unscheduled Programs / Phases**

Motion Groups

- **Ungrouped Axes**

Add-On Instructions

Data Types

- **User-Defined**
- **Strings**
  - **STRING**
- **Add-On-Defined**
- **Module-Defined**
  - **AB:1769_DI16:I:0**
  - **AB:1769_DO16:C:0**
  - **AB:1769_DO16:I:0**
  - **AB:1769_DO16:O:0**
  - **AB:1769_IF4XOF2:C:0**
  - **AB:1769_IF4XOF2:I:0**
  - **AB:1769_IF4XOF2:O:0**
  - **AB:1769_IQ16F:C:0**
  - **AB:Embedded_IQ16F:C:0**
  - **AB:Embedded_IQ16F:I:0**
  - **AB:Embedded_OB16:C:0**
  - **AB:Embedded_OB16:I:0**
  - **AB:Embedded_OB16:O:0**
  - **FR:Standard_Robot_10Bytes:I1:0**
  - **FR:Standard_Robot_10Bytes:O1:0**
  - **FR:Standard_Robot_16Bytes:I1:0**

FR:Standard_Robot_16Bytes:O1:0
FR:Standard_Robot_8Bytes:I1:0
FR:Standard_Robot_8Bytes:O1:0
_005A:AB767879xx_F_C5D4DDB1:O:0
_005A:AB767879xx_F_D2EC9ED2:O:0
_005A:AB767879xx_F_D7BC2DEE:I:0
_005A:AB767879xx_F_E44F4328:I:0

Trends

I/O Configuration

CompactLogix5323E-QB1 System
1769-L23E-QB1 Huber_PLC
1769-L23E-QB1 Ethernet Port LocalENB

1769-L23E-QB1 Ethernet Port LocalENB

CompactBus Local

General			
Vendor:	Rockwell Automation/Allen-Bradley	Mode:	Offline
Revision:	20.14	Key Switch Position:	Offline
Chassis Type:	<none>	Created:	4/5/2019 10:48:08 AM
Slot:	0	Edited:	4/5/2019 10:50:49 AM
Serial Port			
Mode:	System	Control Line:	No Handshake
Baud Rate:	19200	RTS Send Delay:	0 (x20 ms)
Date Bits:	8	RTS Off Delay:	0 (x20 ms)
Parity:	None	DCD Wait Delay:	0 (x1 sec)
Stop Bits:	1		
System Protocol - DF1 Master			
Station Address:	0	Polling Mode:	Message Based (slave can initiate messages)
Transmit Retries:	3	Error Detection:	CRC
ACK Timeout:	50 (x20 ms)	Enable Duplicate Detection:	Yes
Relay Message Wait:	5 (x20 ms)		
System Protocol - DF1 Point to Point			
Station Address:	0	Embedded Responses:	Autodetect
NAK Receive Limit:	3	Error Detection:	CRC
ENQ Transmit Limit:	3	Enable Duplicate Detection:	Yes
ACK Timeout:	50 (x20 ms)		
System Protocol - DF1 Radio Modem			
Station Address:	0	Error Detection:	CRC
Store and Foward:	No		
System Protocol - DF1 Slave			
Station Address:	0	EOT Suppression:	No
Transmit Retries:	3	Error Detection:	CRC
Slave Poll Timeout:	3000 (x20 ms)	Enable Duplicate Detection:	Yes
System Protocol - DH485 (Current)			
Station Address:	0	Token Hold Factor:	1
Max Station Address:	2	Error Detection:	CRC
User Protocol - ASCII			
Read/Write Buffer Size:	82 bytes	Append Character 2:	'$l'
Termination Character 1:	'$r'	XON/XOFF:	No
Termination Character 2:	'$FF'	Echo Mode:	No
Append Character 1:	'$r'	Delete Mode:	Ignore
Date/Time			
Date and Time:	<offline>		
Time Zone:	<offline>		
Daylight Saving (+00:00):	<offline>		
Enable Time Synchronization:	No		
Is the system time master:	<offline>		
Is a synchronized time slave:	<offline>		
Duplicate CST Master Detected:	<offline>		
CST Mastership disabled	<offline>		
No CST Master	<offline>		
Advanced Time Sync			
CIP Sync Time Synchronization:	Disabled		

Advanced			
Controller Fault Handler:	<none>	Match Project To Controller:	No
Power-Up Handler:	<none>	Serial Number:	C01DBC37
System Overhead Time Slice:	20 %	Allow Consumed Tags to Use RPI Provided by Producer:	No
During unused System Overhead Time Slice:	Run Continuous Task		
SFC Execution			
Execution Control:	Execute current active steps only	Last Scan of Active Step:	Don't scan
Restart Position:	Restart at most recently executed step		
Memory (Estimate)			
Memory Option:	1769-L23E-QB1		
Estimated Memory			
Total Memory:	524,288 bytes	Max Used:	112,244 bytes
Free Memory:	412,044 bytes	Largest Block Free:	412,044 bytes
Used Memory:	112,244 bytes		
Security:			
Security Authority:	No Protection	Selected Slots:	
Use only the selected Security Authority for Authentication and Authorization:	No	Changes To Detect:	16#ffff_ffff_ffff_ffff
Restrict Communications Except Through Selected Slots:	No	Audit Value:	<offline>

Name	Value	Data Type	Scope
C600_Fanuc_Active	0	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		
C600_Fanuc_Active - MainProgram/HMI_UI - 1(XIC), 15(XIC), 4(XIC), 5(XIC)			
*C600_Fanuc_Active - MainProgram/Robotics_Control - *2(OTE), 0(XIC), 2(XIC), 2(XIO), 3(XIO)*			
C600_Kuka_Active	1	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		
C600_Kuka_Active - MainProgram/HMI_UI - 1(XIC), 15(XIC), 4(XIC)			
*C600_Kuka_Active - MainProgram/Robotics_Control - *3(OTE)*			
C600_Robot_Active_ONS	0	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		
*C600_Robot_Active_ONS - MainProgram/Robotics_Control - *1(OTE), 2(XIC), 2(XIO)*			
Cr35iA:I1		FR:Standard_Robot_16Bytes:I1:0	Huber_PLC
External Access:	Read/Write		
Cr35iA:I1.Input[0].0	0	BOOL	
Cr35iA:I1.Input[0].0 - MainProgram/Fanuc_Robot_Control - 5(XIC), 8(XIC)			
Cr35iA:I1.Input[0].1	0	BOOL	
Cr35iA:I1.Input[0].1 - MainProgram/Fanuc_Robot_Control - 5(XIC), 8(XIC)			
Cr35iA:I1.Input[0].2	0	BOOL	
Cr35iA:I1.Input[0].2 - MainProgram/Fanuc_Robot_Control - 5(XIC), 5(XIO), 8(XIC)			
Cr35iA:I1.Input[0].5	0	BOOL	
Cr35iA:I1.Input[0].5 - MainProgram/Fanuc_Robot_Control - 5(XIO), 8(XIO)			
Cr35iA:I1.Input[0].5 - MainProgram/HMI_UI - 6(XIC)			
Cr35iA:I1.Input[0].6	0	BOOL	
Cr35iA:I1.Input[0].6 - MainProgram/HMI_UI - 4(XIC)			
Cr35iA:I1.Input[0].7	0	BOOL	
Cr35iA:I1.Input[0].7 - MainProgram/Fanuc_Robot_Control - 0(XIC), 1(XIC), 2(XIC), 3(XIC), 5(XIO), 7(XIC), 8(XIO)			
Cr35iA:I1.Input[2].2	0	BOOL	
Cr35iA:I1.Input[2].2 - MainProgram/HMI_UI - 5(XIC)			
Cr35iA:I1.Input[4]	16#00	SINT	
Cr35iA:I1.Input[4] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[5]	16#00	SINT	
Cr35iA:I1.Input[5] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[6]	16#00	SINT	
Cr35iA:I1.Input[6] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[7]	16#00	SINT	
Cr35iA:I1.Input[7] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[8]	16#00	SINT	
Cr35iA:I1.Input[8] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[9]	16#00	SINT	
Cr35iA:I1.Input[9] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[10]	16#00	SINT	

Cr35iA:I1 (Continued)			
Cr35iA:I1.Input[10] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[11]	16#00	SINT	
Cr35iA:I1.Input[11] - MainProgram/HMI_UI - 1(MOV)			
Cr35iA:O1		FR:Standard_Robot_16Bytes:O1:0	Huber_PLC
External Access:	Read/Write		
Cr35iA:O1.Output[0].0	0	BOOL	
*Cr35iA:O1.Output[0].0 - MainProgram/Fanuc_Robot_Control - *0(OTE), 1(XIC)*			
Cr35iA:O1.Output[0].1	0	BOOL	
*Cr35iA:O1.Output[0].1 - MainProgram/Fanuc_Robot_Control - *1(OTE)*			
Cr35iA:O1.Output[0].2	0	BOOL	
*Cr35iA:O1.Output[0].2 - MainProgram/Fanuc_Robot_Control - *2(OTE)*			
Cr35iA:O1.Output[0].3	0	BOOL	
*Cr35iA:O1.Output[0].3 - MainProgram/Fanuc_Robot_Control - *3(OTE)*			
Cr35iA:O1.Output[0].4	0	BOOL	
*Cr35iA:O1.Output[0].4 - MainProgram/Fanuc_Robot_Control - *4(OTE)*			
Cr35iA:O1.Output[0].5	0	BOOL	
*Cr35iA:O1.Output[0].5 - MainProgram/Fanuc_Robot_Control - *5(OTE)*			
Cr35iA:O1.Output[0].6	0	BOOL	
*Cr35iA:O1.Output[0].6 - MainProgram/Fanuc_Robot_Control - *6(OTE)*			
Cr35iA:O1.Output[0].7	0	BOOL	
*Cr35iA:O1.Output[0].7 - MainProgram/Fanuc_Robot_Control - *7(OTE)*			
Cr35iA:O1.Output[1].0	0	BOOL	
*Cr35iA:O1.Output[1].0 - MainProgram/Fanuc_Robot_Control - *8(OTE)*			
Cr35iA:O1.Output[1].1	0	BOOL	
*Cr35iA:O1.Output[1].1 - MainProgram/Fanuc_Robot_Control - *9(OTE)*			
Cr35iA:O1.Output[1].2	0	BOOL	
*Cr35iA:O1.Output[1].2 - MainProgram/Fanuc_Robot_Control - *10(OTE)*			
Cr35iA:O1.Output[1].3	0	BOOL	
*Cr35iA:O1.Output[1].3 - MainProgram/Fanuc_Robot_Control - *11(OTE)*			
Cr35iA:O1.Output[1].4	0	BOOL	
*Cr35iA:O1.Output[1].4 - MainProgram/Fanuc_Robot_Control - *12(OTE)*			
Cr35iA:O1.Output[1].5	0	BOOL	
*Cr35iA:O1.Output[1].5 - MainProgram/Fanuc_Robot_Control - *13(OTE)*			
Cr35iA:O1.Output[1].6	0	BOOL	
*Cr35iA:O1.Output[1].6 - MainProgram/Fanuc_Robot_Control - *14(OTE)*			
Cr35iA:O1.Output[1].7	0	BOOL	
*Cr35iA:O1.Output[1].7 - MainProgram/Fanuc_Robot_Control - *15(OTE)*			
Cr35iA:O1.Output[3].0	1	BOOL	
*Cr35iA:O1.Output[3].0 - MainProgram/Fanuc_Robot_Control - *16(OTE)*			
Cr35iA:O1.Output[3].1	0	BOOL	
*Cr35iA:O1.Output[3].1 - MainProgram/Fanuc_Robot_Control - *17(OTE)*			
Cr35iA:O1.Output[3].2	0	BOOL	
*Cr35iA:O1.Output[3].2 - MainProgram/Fanuc_Robot_Control - *18(OTE)*			
Cr35iA:O1.Output[3].3	0	BOOL	
*Cr35iA:O1.Output[3].3 - MainProgram/Fanuc_Robot_Control - *19(OTE)*			
Cr35iA:O1.Output[3].4	0	BOOL	

Cr35iA:O1 (Continued)
*Cr35iA:O1.Output[3].4 - MainProgram/Fanuc_Robot_Control - *20(OTE)*
Cr35iA:O1.Output[4] 16#f4 SINT
*Cr35iA:O1.Output[4] - MainProgram/Fanuc_Robot_Control - *21(MOV)*
Cr35iA:O1.Output[5] 16#f7 SINT
*Cr35iA:O1.Output[5] - MainProgram/Fanuc_Robot_Control - *22(MOV)*
Cr35iA:O1.Output[6] 16#f4 SINT
*Cr35iA:O1.Output[6] - MainProgram/Fanuc_Robot_Control - *23(MOV)*

Debug 0 BOOL Research
Constant No
External Access: Read/Write
Debug - Research/Kuka_Robot_Control - 0(XIO)

Fanuc_Control_Stop_Timer TIMER MainProgram
Constant No
External Access: Read/Write
*Fanuc_Control_Stop_Timer - MainProgram/Fanuc_Robot_Control - *3(TON)*
Fanuc_Control_Stop_Timer.DN 0 BOOL
Fanuc_Control_Stop_Timer.DN - MainProgram/Fanuc_Robot_Control - 3(XIC)

Fanuc_Start_Prgm_Timer TIMER MainProgram
Constant No
External Access: Read/Write
*Fanuc_Start_Prgm_Timer - MainProgram/Fanuc_Robot_Control - *5(TON)*
Fanuc_Start_Prgm_Timer.DN 0 BOOL
Fanuc_Start_Prgm_Timer.DN - MainProgram/Fanuc_Robot_Control - 5(XIO)

Half_Sec_TMR_Pulse_Down TIMER Huber_PLC
Constant No
External Access: Read/Write
*Half_Sec_TMR_Pulse_Down - MainProgram/MainRoutine - *0(TON)*
Half_Sec_TMR_Pulse_Down.DN 0 BOOL
Half_Sec_TMR_Pulse_Down.DN - MainProgram/MainRoutine - 0(XIO)

Half_Sec_TMR_Pulse_Up TIMER Huber_PLC
Constant No
External Access: Read/Write
*Half_Sec_TMR_Pulse_Up - MainProgram/MainRoutine - *0(TON)*
Half_Sec_TMR_Pulse_Up.DN 0 BOOL
Half_Sec_TMR_Pulse_Up.DN - MainProgram/HMI_UI - 13(XIC)
Half_Sec_TMR_Pulse_Up.DN - MainProgram/MainRoutine - 0(XIC)
Half_Sec_TMR_Pulse_Up.DN - MainProgram/Pycomm - 1(XIC)

HMI_Robot_In_Coord_11 INT[10] Huber_PLC
Maximum Consumers: 11
Include Connection Status: n/a
Send Data State Change Event to Consumer(s): No

HMI_Robot_In_Coord_11 (Continued)
Allow Unicast Consumer Connections: n/a
Constant No
External Access: Read/Write

HMI_Robot_In_Coord_11[0]	500	INT	
HMI_Robot_In_Coord_11[0] - MainProgram/Fanuc_Robot_Control - 21(MOV)			
HMI_Robot_In_Coord_11[0] - MainProgram/Kuka_Robot_Control - 0(MOV)			
HMI_Robot_In_Coord_11[1]	500	INT	
HMI_Robot_In_Coord_11[1] - MainProgram/Fanuc_Robot_Control - 23(MOV)			
HMI_Robot_In_Coord_11[1] - MainProgram/Kuka_Robot_Control - 0(MOV)			

HMI_Robot_Out_Coord_10 INT[10] Huber_PLC
Maximum Consumers: 10
Include Connection Status: n/a
Send Data State Change Event to Consumer(s): No
Allow Unicast Consumer Connections: n/a
Constant No
External Access: Read/Write

HMI_Robot_Out_Coord_10[0]	0	INT	
*HMI_Robot_Out_Coord_10[0] - MainProgram/HMI_UI - *15(MOV)*			
HMI_Robot_Out_Coord_10[1]	0	INT	
*HMI_Robot_Out_Coord_10[1] - MainProgram/HMI_UI - *15(MOV), 13(GEQ), 13(LES)*			
HMI_Robot_Out_Coord_10[2]	0	INT	
*HMI_Robot_Out_Coord_10[2] - MainProgram/HMI_UI - *15(MOV)*			
HMI_Robot_Out_Coord_10[3]	0	INT	
*HMI_Robot_Out_Coord_10[3] - MainProgram/HMI_UI - *15(MOV)*			
HMI_Robot_Out_Coord_10[4]	0	INT	
*HMI_Robot_Out_Coord_10[4] - MainProgram/HMI_UI - *15(MOV)*			
HMI_Robot_Out_Coord_10[5]	0	INT	
*HMI_Robot_Out_Coord_10[5] - MainProgram/HMI_UI - *15(MOV)*			
HMI_Robot_Out_Coord_10[6]	0	INT	
*HMI_Robot_Out_Coord_10[6] - MainProgram/HMI_UI - *15(MOV)*			
HMI_Robot_Out_Coord_10[7]	5	INT	
*HMI_Robot_Out_Coord_10[7] - MainProgram/Pycomm - *0(MOV)*			

HMI_UI_Graph_14 INT[3] Huber_PLC
Maximum Consumers: 14
Include Connection Status: n/a
Send Data State Change Event to Consumer(s): No
Allow Unicast Consumer Connections: n/a
Constant No
External Access: Read/Write

HMI_UI_Graph_14[0]	0	INT	
*HMI_UI_Graph_14[0] - MainProgram/HMI_UI - *1(MOV)*			
HMI_UI_Graph_14[1]	0	INT	
*HMI_UI_Graph_14[1] - MainProgram/HMI_UI - *1(MOV)*			
HMI_UI_Graph_14[2]	0	INT	
*HMI_UI_Graph_14[2] - MainProgram/HMI_UI - *13(ABS)*			

HMI_UI_Graph_CNT		COUNTER	MainProgram
Constant	No		
External Access:	Read/Write		
*HMI_UI_Graph_CNT - MainProgram/HMI_UI - *13(CTD), *13(CTU)*			
HMI_UI_Graph_CNT.ACC	1	DINT	
*HMI_UI_Graph_CNT.ACC - MainProgram/HMI_UI - *13(MOV), 13(ABS), 13(GEQ), 13(LEQ)*			
HMI_UI_PB_12	0	INT	Huber_PLC
Maximum Consumers:	12		
Include Connection Status:	n/a		
Send Data State Change Event to Consumer(s):	No		
Allow Unicast Consumer Connections:	n/a		
Constant	No		
External Access:	Read/Write		
HMI_UI_PB_12.0	0	BOOL	
HMI_UI_PB_12.0 - MainProgram/HMI_UI - 2(XIC)			
HMI_UI_PB_12.1	0	BOOL	
HMI_UI_PB_12.1 - MainProgram/HMI_UI - 2(XIO)			
HMI_UI_PB_12.2	0	BOOL	
HMI_UI_PB_12.2 - MainProgram/Kuka_Robot_Control - 3(XIC)			
HMI_UI_PB_12.4	0	BOOL	
HMI_UI_PB_12.4 - MainProgram/Fanuc_Robot_Control - 4(XIC), 5(XIO), 8(XIO)			
HMI_UI_PB_12.4 - MainProgram/Pycomm - 2(XIC)			
HMI_UI_PB_12.7	0	BOOL	
HMI_UI_PB_12.7 - MainProgram/Robotics_Control - 1(XIC)			
HMI_UI_PB_12.8	0	BOOL	
HMI_UI_PB_12.8 - MainProgram/HMI_UI - 7(XIC)			
HMI_UI_PB_12.9	0	BOOL	
HMI_UI_PB_12.9 - MainProgram/HMI_UI - 8(XIC)			
HMI_UI_PB_12.10	0	BOOL	
HMI_UI_PB_12.10 - MainProgram/HMI_UI - 9(XIC)			
HMI_UI_PB_12.11	0	BOOL	
HMI_UI_PB_12.11 - MainProgram/HMI_UI - 10(XIC)			
HMI_UI_PB_12.12	0	BOOL	
HMI_UI_PB_12.12 - MainProgram/HMI_UI - 11(XIC), 12(XIO)			
HMI_UI_PB_12.13	0	BOOL	
HMI_UI_PB_12.13 - MainProgram/HMI_UI - 11(XIO), 12(XIC)			
HMI_UI_PL_13	6	INT	Huber_PLC
Maximum Consumers:	13		
Include Connection Status:	n/a		
Send Data State Change Event to Consumer(s):	No		
Allow Unicast Consumer Connections:	n/a		
Constant	No		
External Access:	Read/Write		
HMI_UI_PL_13.0	0	BOOL	
*HMI_UI_PL_13.0 - MainProgram/HMI_UI - *2(OTE), 2(XIC), 3(XIO)*			
HMI_UI_PL_13.1	1	BOOL	

HMI_UI_PL_13 (Continued)			
*HMI_UI_PL_13.1 - MainProgram/HMI_UI - *3(OTE)*			
HMI_UI_PL_13.2	1	BOOL	
*HMI_UI_PL_13.2 - MainProgram/HMI_UI - *4(OTE)*			
HMI_UI_PL_13.2 - MainProgram/Kuka_Robot_Control - 4(XIC)			
HMI_UI_PL_13.3	0	BOOL	
*HMI_UI_PL_13.3 - MainProgram/HMI_UI - *5(OTE)*			
HMI_UI_PL_13.4	0	BOOL	
*HMI_UI_PL_13.4 - MainProgram/HMI_UI - *6(OTE)*			
HMI_UI_PL_13.7	0	BOOL	
*HMI_UI_PL_13.7 - MainProgram/Robotics_Control - *0(OTE)*			
HMI_UI_PL_13.8	0	BOOL	
*HMI_UI_PL_13.8 - MainProgram/HMI_UI - *7(OTE), 7(XIC)*			
HMI_UI_PL_13.9	0	BOOL	
*HMI_UI_PL_13.9 - MainProgram/HMI_UI - *8(OTE), 8(XIC)*			
HMI_UI_PL_13.10	0	BOOL	
*HMI_UI_PL_13.10 - MainProgram/HMI_UI - *9(OTE), 9(XIC)*			
HMI_UI_PL_13.11	0	BOOL	
*HMI_UI_PL_13.11 - MainProgram/HMI_UI - *10(OTE), 10(XIC)*			
HMI_UI_PL_13.12	0	BOOL	
*HMI_UI_PL_13.12 - MainProgram/HMI_UI - *11(OTE), 11(XIC)*			
HMI_UI_PL_13.13	0	BOOL	
*HMI_UI_PL_13.13 - MainProgram/HMI_UI - *12(OTE), 12(XIC)*			
HMI_UI_Timers		TIMER[16]	Huber_PLC
Constant	No		
External Access:	Read/Write		
HMI_UI_Timers[0]		TIMER	
*HMI_UI_Timers[0] - MainProgram/HMI_UI - *7(TON)*			
HMI_UI_Timers[0].DN	0	BOOL	
HMI_UI_Timers[0].DN - MainProgram/HMI_UI - 7(XIO)			
HMI_UI_Timers[1]		TIMER	
*HMI_UI_Timers[1] - MainProgram/HMI_UI - *8(TON)*			
HMI_UI_Timers[1].DN	0	BOOL	
HMI_UI_Timers[1].DN - MainProgram/HMI_UI - 8(XIO)			
HMI_UI_Timers[2]		TIMER	
*HMI_UI_Timers[2] - MainProgram/HMI_UI - *9(TON)*			
HMI_UI_Timers[2].DN	0	BOOL	
HMI_UI_Timers[2].DN - MainProgram/HMI_UI - 9(XIO)			
HMI_UI_Timers[3]		TIMER	
*HMI_UI_Timers[3] - MainProgram/HMI_UI - *10(TON)*			
HMI_UI_Timers[3].DN	0	BOOL	
HMI_UI_Timers[3].DN - MainProgram/HMI_UI - 10(XIO)			
Home_Comp_Delay		TIMER	MainProgram
Constant	No		
External Access:	Read/Write		
*Home_Comp_Delay - MainProgram/Kuka_Robot_Control - *4(TON)*			

Home_Comp_Delay (Continued)

Home_Comp_Delay.DN	0	BOOL	
Home_Comp_Delay.DN - MainProgram/Kuka_Robot_Control - 4(XIO)			
Kuka_Home_Comp	0	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		
*Kuka_Home_Comp - MainProgram/Kuka_Robot_Control - *4(OTE), 1(XIO), 3(XIO), 4(XIC)*			
Kuka_Home_Req	0	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		
*Kuka_Home_Req - MainProgram/Kuka_Robot_Control - *3(OTE), 0(XIC), 0(XIO), 3(XIC), 4(XIC)*			
Kuka_Robot:I		_005A:AB767879xx_F_D7BC2DEE:I:0	Huber_PLC
External Access:	Read/Write		
Kuka_Robot:I.Data[0]	0	INT	
Kuka_Robot:I.Data[0] - MainProgram/HMI_UI - 15(MOV)			
Kuka_Robot:I.Data[1]	0	INT	
Kuka_Robot:I.Data[1] - MainProgram/HMI_UI - 15(MOV)			
Kuka_Robot:I.Data[2]	0	INT	
Kuka_Robot:I.Data[2] - MainProgram/HMI_UI - 15(MOV)			
Kuka_Robot:I.Data[3]	0	INT	
Kuka_Robot:I.Data[3] - MainProgram/HMI_UI - 1(MOV), 15(MOV), 4(GRT), 4(LES)			
Kuka_Robot:I.Data[4]	0	INT	
Kuka_Robot:I.Data[4] - MainProgram/HMI_UI - 15(MOV)			
Kuka_Robot:I.Data[5]	0	INT	
Kuka_Robot:I.Data[5] - MainProgram/HMI_UI - 15(MOV)			
Kuka_Robot:I.Data[6]	0	INT	
Kuka_Robot:I.Data[6] - MainProgram/HMI_UI - 15(MOV)			
Kuka_Robot:O		_005A:AB767879xx_F_D2EC9ED2:O:0	Huber_PLC
External Access:	Read/Write		
Kuka_Robot:O.Data[0]	155	INT	
*Kuka_Robot:O.Data[0] - Research/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[1]	21	INT	
*Kuka_Robot:O.Data[1] - Research/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[2]	67	INT	
*Kuka_Robot:O.Data[2] - Research/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[3].0	1	BOOL	
*Kuka_Robot:O.Data[3].0 - MainProgram/Kuka_Robot_Control - *1(OTE), 3(XIC), 4(XIO)*			
Kuka_Robot:O.Data[3].1	0	BOOL	
*Kuka_Robot:O.Data[3].1 - MainProgram/Kuka_Robot_Control - *2(OTE)*			
Kuka_Robot:O.Data[4]	500	INT	
*Kuka_Robot:O.Data[4] - MainProgram/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[5]	-9	INT	
*Kuka_Robot:O.Data[5] - MainProgram/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[6]	500	INT	

Kuka_Robot:O (Continued)
*Kuka_Robot:O.Data[6] - MainProgram/Kuka_Robot_Control - *0(MOV)*

Local:1:I AB:Embedded_IQ16F:I:0 Huber_PLC
External Access: Read/Write
Local:1:I.Data.0 1 BOOL
Local:1:I.Data.0 - MainProgram/HMI_UI - 2(XIC)
Local:1:I.Data.0 - MainProgram/Kuka_Robot_Control - 1(XIC), 1(XIO)

Local:2:O AB:Embedded_OB16:O:0 Huber_PLC
External Access: Read/Write
Local:2:O.Data.0 0 BOOL
*Local:2:O.Data.0 - MainProgram/Kuka_Robot_Control - *1(OTE)*

Null 0 BOOL MainProgram
Constant No
External Access: Read/Write
*Null - MainProgram/HMI_UI - *0(OTE), *14(OTE)*

ONS BOOL[128] Huber_PLC
Constant No
External Access: Read/Write
ONS[0] 0 BOOL
*ONS[0] - MainProgram/HMI_UI - *13(ONS)*
ONS[1] 0 BOOL
*ONS[1] - MainProgram/Robotics_Control - *1(ONS)*
ONS[2] 0 BOOL
*ONS[2] - MainProgram/Pycomm - *1(ONS)*

R_Pi_Comm_Check_New 0 SINT MainProgram
Constant No
External Access: Read/Write
*R_Pi_Comm_Check_New - MainProgram/Pycomm - *1(MOV), 1(EQU), 1(MOV), 1(NEQ)*

R_Pi_Comm_Check_Old 0 SINT MainProgram
Constant No
External Access: Read/Write
*R_Pi_Comm_Check_Old - MainProgram/Pycomm - *1(MOV)*

R_Pi_Comm_Faulted 0 BOOL MainProgram
Constant No
External Access: Read/Write
R_Pi_Comm_Faulted - MainProgram/HMI_UI - 6(XIC)
*R_Pi_Comm_Faulted - MainProgram/Pycomm - *1(OTL), *2(OTU)*

R_PI_Rand_Value 0 SINT MainProgram
Constant No
External Access: Read/Write

R_PI_Rand_Value (Continued)
R_PI_Rand_Value - MainProgram/Pycomm - 1(MOV)

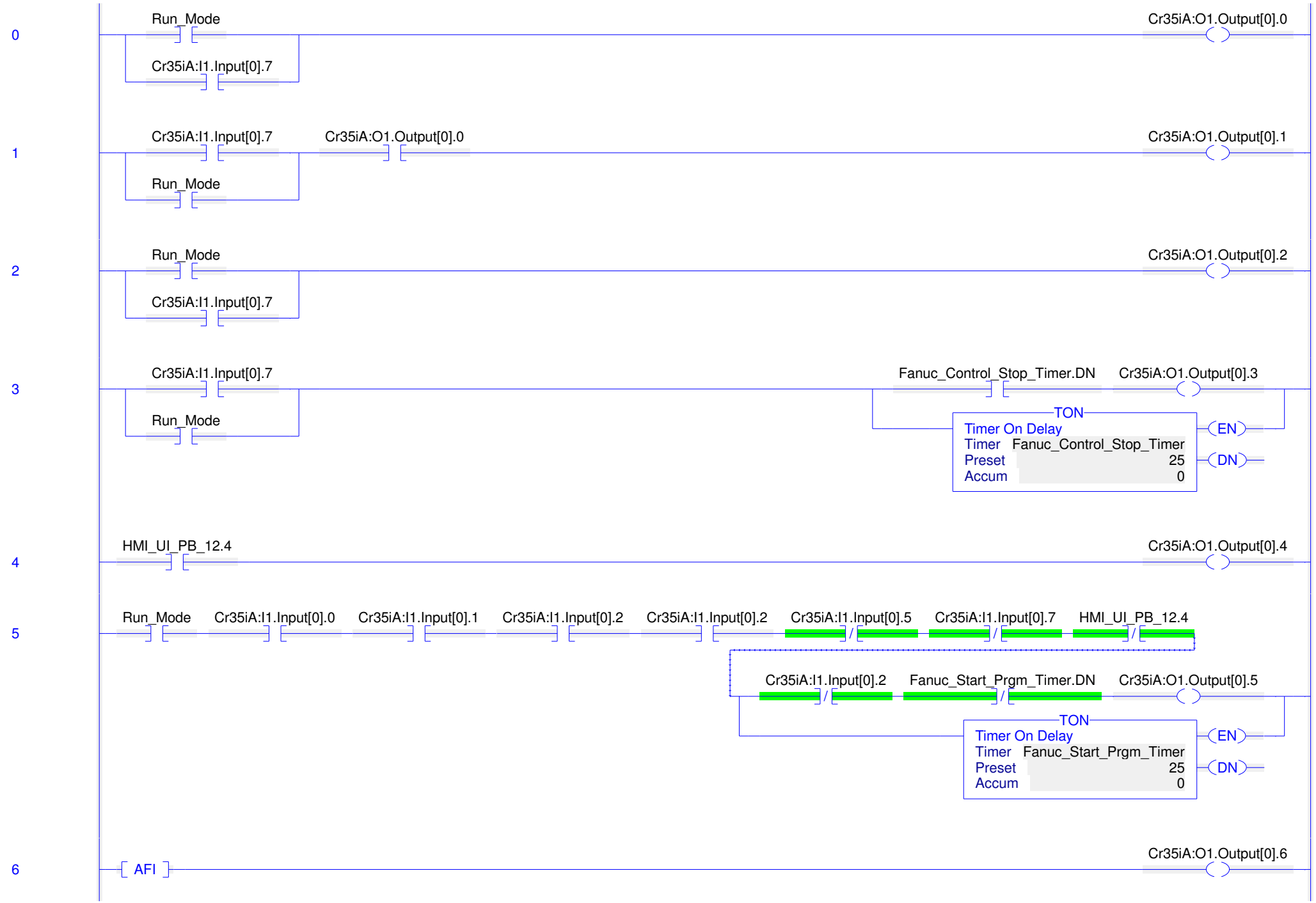
R_PI_User_Head_Angle -9 INT Huber_PLC
Constant No
External Access: Read/Write
R_PI_User_Head_Angle - MainProgram/Fanuc_Robot_Control - 22(MOV)
R_PI_User_Head_Angle - MainProgram/Kuka_Robot_Control - 0(MOV)
R_PI_User_Head_Angle - MainProgram/Pycomm - 0(MOV)

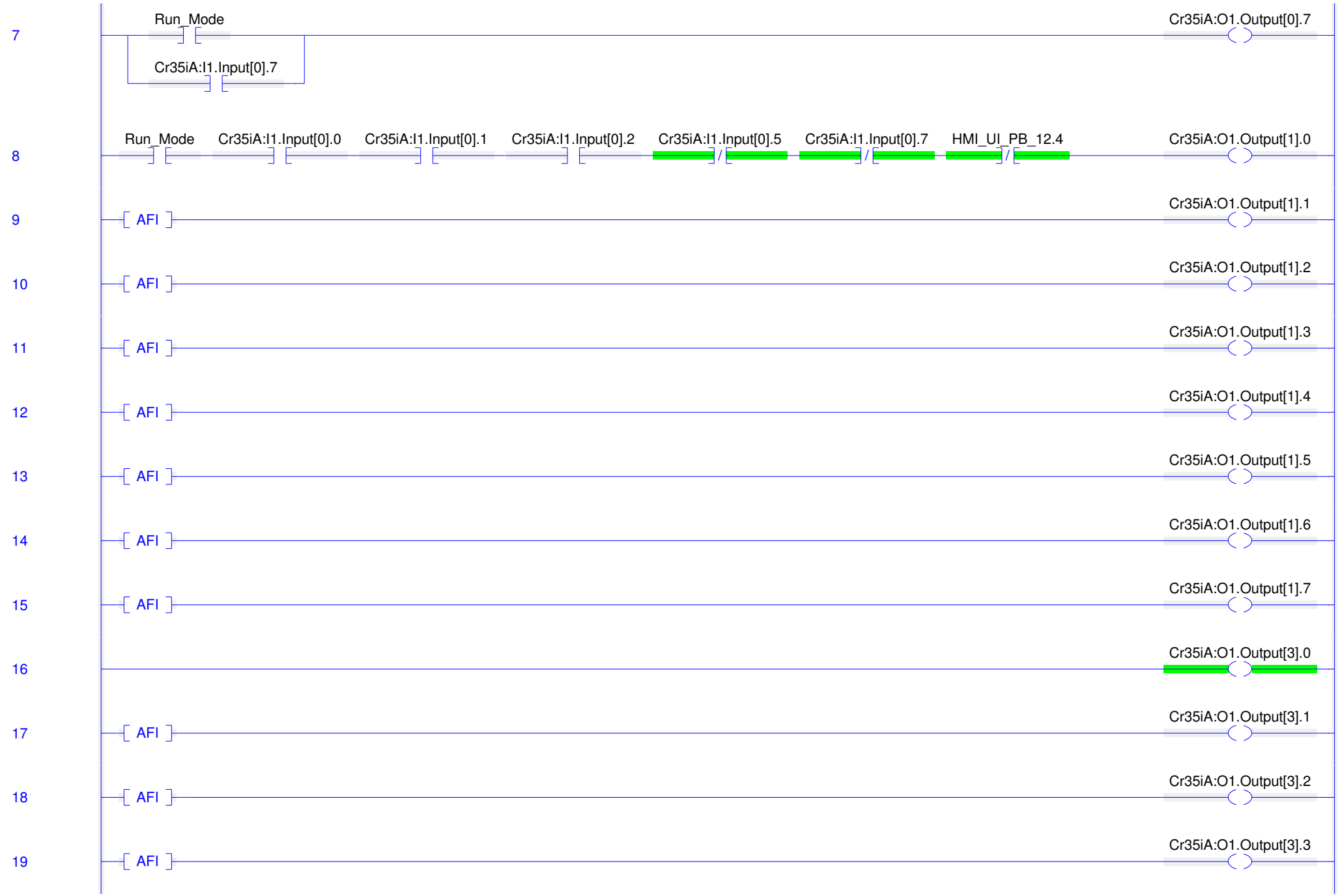
Run_Mode 0 BOOL MainProgram
Constant No
External Access: Read/Write
Run_Mode - MainProgram/Fanuc_Robot_Control - 0(XIC), 1(XIC), 2(XIC), 3(XIC), 5(XIC), 7(XIC), 8(XIC)
*Run_Mode - MainProgram/HMI_UI - *2(OTE)*
Run_Mode - MainProgram/Kuka_Robot_Control - 2(XIC)

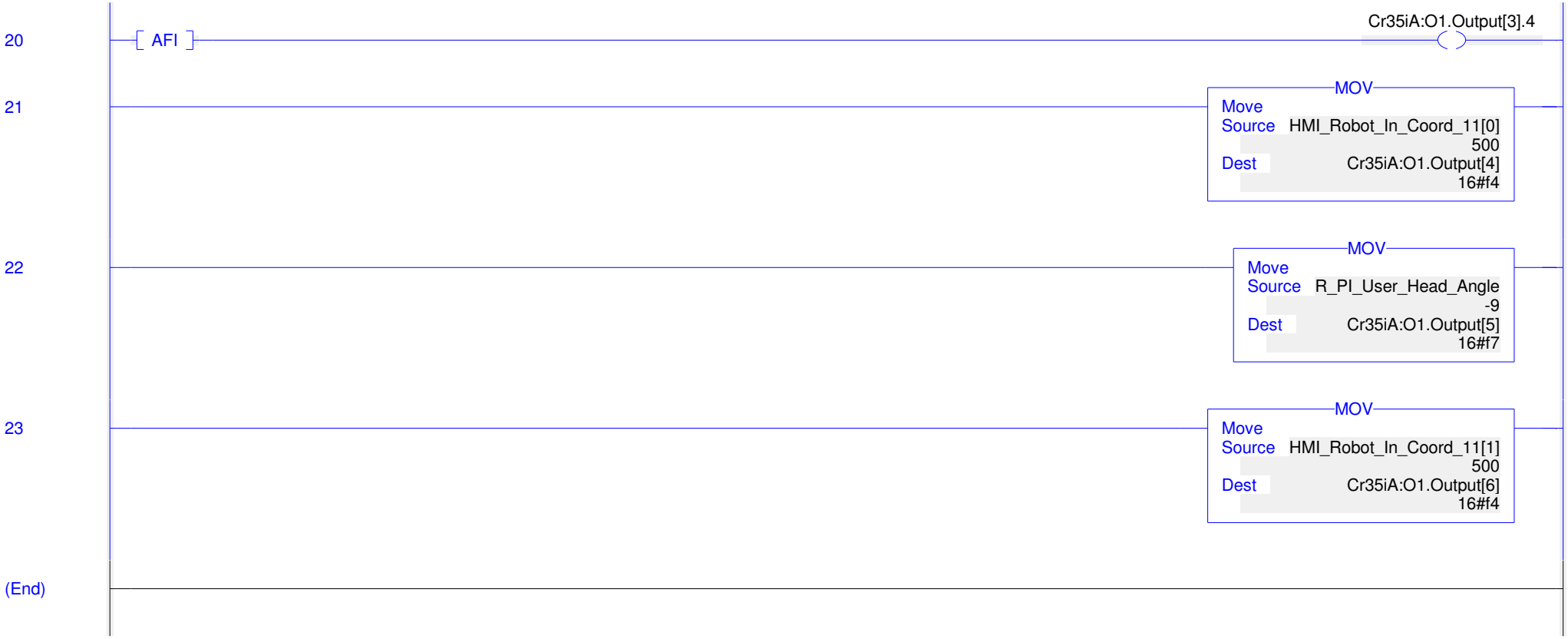
X_CAM 155 INT Huber_PLC
Constant No
External Access: Read/Write
X_CAM - Research/Kuka_Robot_Control - 0(MOV)

Y_CAM 21 INT Huber_PLC
Constant No
External Access: Read/Write
Y_CAM - Research/Kuka_Robot_Control - 0(MOV)

Z_CAM 67 INT Huber_PLC
Constant No
External Access: Read/Write
Z_CAM - Research/Kuka_Robot_Control - 0(MOV)


0
Run_Mode
Cr35iA:I1.Input[0].7
Cr35iA:O1.Output[0].0
1
Cr35iA:I1.Input[0].7
Cr35iA:O1.Output[0].0
Run_Mode
Cr35iA:O1.Output[0].1
2
Run_Mode
Cr35iA:I1.Input[0].7
Cr35iA:O1.Output[0].2
3
Cr35iA:I1.Input[0].7
Run_Mode
Fanuc_Control_Stop_Timer.DN
Cr35iA:O1.Output[0].3
TON
Timer On Delay
Timer Fanuc_Control_Stop_Timer
Preset 25
Accum 0
EN
DN
4
HMI_UI_PB_12.4
Cr35iA:O1.Output[0].4
5
Run_Mode
Cr35iA:I1.Input[0].0
Cr35iA:I1.Input[0].1
Cr35iA:I1.Input[0].2
Cr35iA:I1.Input[0].2
Cr35iA:I1.Input[0].5
Cr35iA:I1.Input[0].7
HMI_UI_PB_12.4
Cr35iA:I1.Input[0].2
Fanuc_Start_Prgm_Timer.DN
Cr35iA:O1.Output[0].5
TON
Timer On Delay
Timer Fanuc_Start_Prgm_Timer
Preset 25
Accum 0
EN
DN
6
AFI
Cr35iA:O1.Output[0].6


7
Run_Mode
Cr35iA:I1.Input[0].7
Cr35iA:O1.Output[0].7
8
Run_Mode
Cr35iA:I1.Input[0].0
Cr35iA:I1.Input[0].1
Cr35iA:I1.Input[0].2
Cr35iA:I1.Input[0].5
Cr35iA:I1.Input[0].7
HMI_UI_PB_12.4
Cr35iA:O1.Output[1].0
9
AFI
Cr35iA:O1.Output[1].1
10
AFI
Cr35iA:O1.Output[1].2
11
AFI
Cr35iA:O1.Output[1].3
12
AFI
Cr35iA:O1.Output[1].4
13
AFI
Cr35iA:O1.Output[1].5
14
AFI
Cr35iA:O1.Output[1].6
15
AFI
Cr35iA:O1.Output[1].7
16
Cr35iA:O1.Output[3].0
17
AFI
Cr35iA:O1.Output[3].1
18
AFI
Cr35iA:O1.Output[3].2
19
AFI
Cr35iA:O1.Output[3].3


20
AFI
Cr35iA:O1.Output[3].4
21
MOV
Move
Source HMI_Robot_In_Coord_11[0]
500
Dest Cr35iA:O1.Output[4]
16#f4
22
MOV
Move
Source R_PI_User_Head_Angle
-9
Dest Cr35iA:O1.Output[5]
16#f7
23
MOV
Move
Source HMI_Robot_In_Coord_11[1]
500
Dest Cr35iA:O1.Output[6]
16#f4
(End)

Name	Value	Data Type	Scope
Cr35iA:I1		FR:Standard_Robot_16Bytes:I1:0	Huber_PLC
External Access:	Read/Write		
Cr35iA:I1.Input[0].0	0	BOOL	
Cr35iA:I1.Input[0].0 - MainProgram/Fanuc_Robot_Control - 5(XIC), 8(XIC)			
Cr35iA:I1.Input[0].1	0	BOOL	
Cr35iA:I1.Input[0].1 - MainProgram/Fanuc_Robot_Control - 5(XIC), 8(XIC)			
Cr35iA:I1.Input[0].2	0	BOOL	
Cr35iA:I1.Input[0].2 - MainProgram/Fanuc_Robot_Control - 5(XIC), 5(XIO), 8(XIC)			
Cr35iA:I1.Input[0].5	0	BOOL	
Cr35iA:I1.Input[0].5 - MainProgram/Fanuc_Robot_Control - 5(XIO), 8(XIO)			
Cr35iA:I1.Input[0].5 - MainProgram/HMI_UI - 6(XIC)			
Cr35iA:I1.Input[0].6	0	BOOL	
Cr35iA:I1.Input[0].6 - MainProgram/HMI_UI - 4(XIC)			
Cr35iA:I1.Input[0].7	0	BOOL	
Cr35iA:I1.Input[0].7 - MainProgram/Fanuc_Robot_Control - 0(XIC), 1(XIC), 2(XIC), 3(XIC), 5(XIO), 7(XIC), 8(XIO)			
Cr35iA:I1.Input[2].2	0	BOOL	
Cr35iA:I1.Input[2].2 - MainProgram/HMI_UI - 5(XIC)			
Cr35iA:I1.Input[4]	16#00	SINT	
Cr35iA:I1.Input[4] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[5]	16#00	SINT	
Cr35iA:I1.Input[5] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[6]	16#00	SINT	
Cr35iA:I1.Input[6] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[7]	16#00	SINT	
Cr35iA:I1.Input[7] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[8]	16#00	SINT	
Cr35iA:I1.Input[8] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[9]	16#00	SINT	
Cr35iA:I1.Input[9] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[10]	16#00	SINT	
Cr35iA:I1.Input[10] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[11]	16#00	SINT	
Cr35iA:I1.Input[11] - MainProgram/HMI_UI - 1(MOV)			
Cr35iA:O1		FR:Standard_Robot_16Bytes:O1:0	Huber_PLC
External Access:	Read/Write		
Cr35iA:O1.Output[0].0	0	BOOL	
*Cr35iA:O1.Output[0].0 - MainProgram/Fanuc_Robot_Control - *0(OTE), 1(XIC)*			
Cr35iA:O1.Output[0].1	0	BOOL	
*Cr35iA:O1.Output[0].1 - MainProgram/Fanuc_Robot_Control - *1(OTE)*			
Cr35iA:O1.Output[0].2	0	BOOL	
*Cr35iA:O1.Output[0].2 - MainProgram/Fanuc_Robot_Control - *2(OTE)*			
Cr35iA:O1.Output[0].3	0	BOOL	
*Cr35iA:O1.Output[0].3 - MainProgram/Fanuc_Robot_Control - *3(OTE)*			
Cr35iA:O1.Output[0].4	0	BOOL	
*Cr35iA:O1.Output[0].4 - MainProgram/Fanuc_Robot_Control - *4(OTE)*			
Cr35iA:O1.Output[0].5	0	BOOL	

Cr35iA:O1 (Continued)
*Cr35iA:O1.Output[0].5 - MainProgram/Fanuc_Robot_Control - *5(OTE)*
Cr35iA:O1.Output[0].6 0 BOOL
*Cr35iA:O1.Output[0].6 - MainProgram/Fanuc_Robot_Control - *6(OTE)*
Cr35iA:O1.Output[0].7 0 BOOL
*Cr35iA:O1.Output[0].7 - MainProgram/Fanuc_Robot_Control - *7(OTE)*
Cr35iA:O1.Output[1].0 0 BOOL
*Cr35iA:O1.Output[1].0 - MainProgram/Fanuc_Robot_Control - *8(OTE)*
Cr35iA:O1.Output[1].1 0 BOOL
*Cr35iA:O1.Output[1].1 - MainProgram/Fanuc_Robot_Control - *9(OTE)*
Cr35iA:O1.Output[1].2 0 BOOL
*Cr35iA:O1.Output[1].2 - MainProgram/Fanuc_Robot_Control - *10(OTE)*
Cr35iA:O1.Output[1].3 0 BOOL
*Cr35iA:O1.Output[1].3 - MainProgram/Fanuc_Robot_Control - *11(OTE)*
Cr35iA:O1.Output[1].4 0 BOOL
*Cr35iA:O1.Output[1].4 - MainProgram/Fanuc_Robot_Control - *12(OTE)*
Cr35iA:O1.Output[1].5 0 BOOL
*Cr35iA:O1.Output[1].5 - MainProgram/Fanuc_Robot_Control - *13(OTE)*
Cr35iA:O1.Output[1].6 0 BOOL
*Cr35iA:O1.Output[1].6 - MainProgram/Fanuc_Robot_Control - *14(OTE)*
Cr35iA:O1.Output[1].7 0 BOOL
*Cr35iA:O1.Output[1].7 - MainProgram/Fanuc_Robot_Control - *15(OTE)*
Cr35iA:O1.Output[3].0 1 BOOL
*Cr35iA:O1.Output[3].0 - MainProgram/Fanuc_Robot_Control - *16(OTE)*
Cr35iA:O1.Output[3].1 0 BOOL
*Cr35iA:O1.Output[3].1 - MainProgram/Fanuc_Robot_Control - *17(OTE)*
Cr35iA:O1.Output[3].2 0 BOOL
*Cr35iA:O1.Output[3].2 - MainProgram/Fanuc_Robot_Control - *18(OTE)*
Cr35iA:O1.Output[3].3 0 BOOL
*Cr35iA:O1.Output[3].3 - MainProgram/Fanuc_Robot_Control - *19(OTE)*
Cr35iA:O1.Output[3].4 0 BOOL
*Cr35iA:O1.Output[3].4 - MainProgram/Fanuc_Robot_Control - *20(OTE)*
Cr35iA:O1.Output[4] 16#f4 SINT
*Cr35iA:O1.Output[4] - MainProgram/Fanuc_Robot_Control - *21(MOV)*
Cr35iA:O1.Output[5] 16#f7 SINT
*Cr35iA:O1.Output[5] - MainProgram/Fanuc_Robot_Control - *22(MOV)*
Cr35iA:O1.Output[6] 16#f4 SINT
*Cr35iA:O1.Output[6] - MainProgram/Fanuc_Robot_Control - *23(MOV)*

Fanuc_Control_Stop_Timer TIMER MainProgram
Constant No
External Access: Read/Write
*Fanuc_Control_Stop_Timer - MainProgram/Fanuc_Robot_Control - *3(TON)*
Fanuc_Control_Stop_Timer.DN 0 BOOL
Fanuc_Control_Stop_Timer.DN - MainProgram/Fanuc_Robot_Control - 3(XIC)

Fanuc_Start_Prgm_Timer TIMER MainProgram
Constant No

Fanuc_Start_Prgm_Timer (Continued)
External Access: Read/Write
*Fanuc_Start_Prgm_Timer - MainProgram/Fanuc_Robot_Control - *5(TON)*
Fanuc_Start_Prgm_Timer.DN 0 BOOL
Fanuc_Start_Prgm_Timer.DN - MainProgram/Fanuc_Robot_Control - 5(XIO)

HMI_Robot_In_Coord_11 INT[10] Huber_PLC
Maximum Consumers: 11
Include Connection Status: n/a
Send Data State Change Event to Consumer(s): No
Allow Unicast Consumer Connections: n/a
Constant No
External Access: Read/Write
HMI_Robot_In_Coord_11[0] 500 INT
HMI_Robot_In_Coord_11[0] - MainProgram/Fanuc_Robot_Control - 21(MOV)
HMI_Robot_In_Coord_11[0] - MainProgram/Kuka_Robot_Control - 0(MOV)
HMI_Robot_In_Coord_11[1] 500 INT
HMI_Robot_In_Coord_11[1] - MainProgram/Fanuc_Robot_Control - 23(MOV)
HMI_Robot_In_Coord_11[1] - MainProgram/Kuka_Robot_Control - 0(MOV)

HMI_UI_PB_12 0 INT Huber_PLC
Maximum Consumers: 12
Include Connection Status: n/a
Send Data State Change Event to Consumer(s): No
Allow Unicast Consumer Connections: n/a
Constant No
External Access: Read/Write
HMI_UI_PB_12.0 0 BOOL
HMI_UI_PB_12.0 - MainProgram/HMI_UI - 2(XIC)
HMI_UI_PB_12.1 0 BOOL
HMI_UI_PB_12.1 - MainProgram/HMI_UI - 2(XIO)
HMI_UI_PB_12.2 0 BOOL
HMI_UI_PB_12.2 - MainProgram/Kuka_Robot_Control - 3(XIC)
HMI_UI_PB_12.4 0 BOOL
HMI_UI_PB_12.4 - MainProgram/Fanuc_Robot_Control - 4(XIC), 5(XIO), 8(XIO)
HMI_UI_PB_12.4 - MainProgram/Pycomm - 2(XIC)
HMI_UI_PB_12.7 0 BOOL
HMI_UI_PB_12.7 - MainProgram/Robotics_Control - 1(XIC)
HMI_UI_PB_12.8 0 BOOL
HMI_UI_PB_12.8 - MainProgram/HMI_UI - 7(XIC)
HMI_UI_PB_12.9 0 BOOL
HMI_UI_PB_12.9 - MainProgram/HMI_UI - 8(XIC)
HMI_UI_PB_12.10 0 BOOL
HMI_UI_PB_12.10 - MainProgram/HMI_UI - 9(XIC)
HMI_UI_PB_12.11 0 BOOL
HMI_UI_PB_12.11 - MainProgram/HMI_UI - 10(XIC)
HMI_UI_PB_12.12 0 BOOL
HMI_UI_PB_12.12 - MainProgram/HMI_UI - 11(XIC), 12(XIO)

HMI_UI_PB_12 (Continued)

HMI_UI_PB_12.13	0	BOOL	

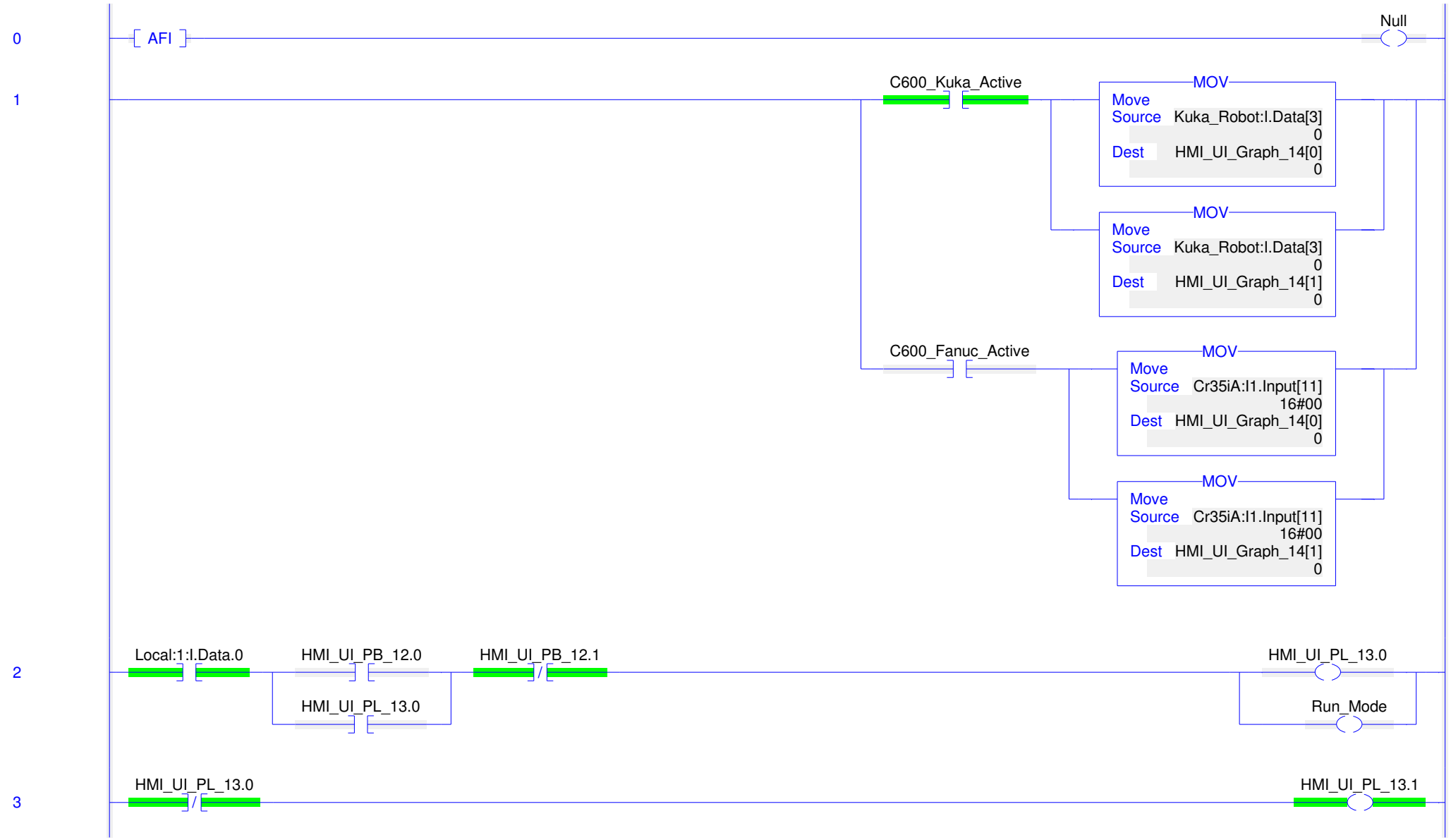
HMI_UI_PB_12.13 - MainProgram/HMI_UI - 11(XIO), 12(XIC)

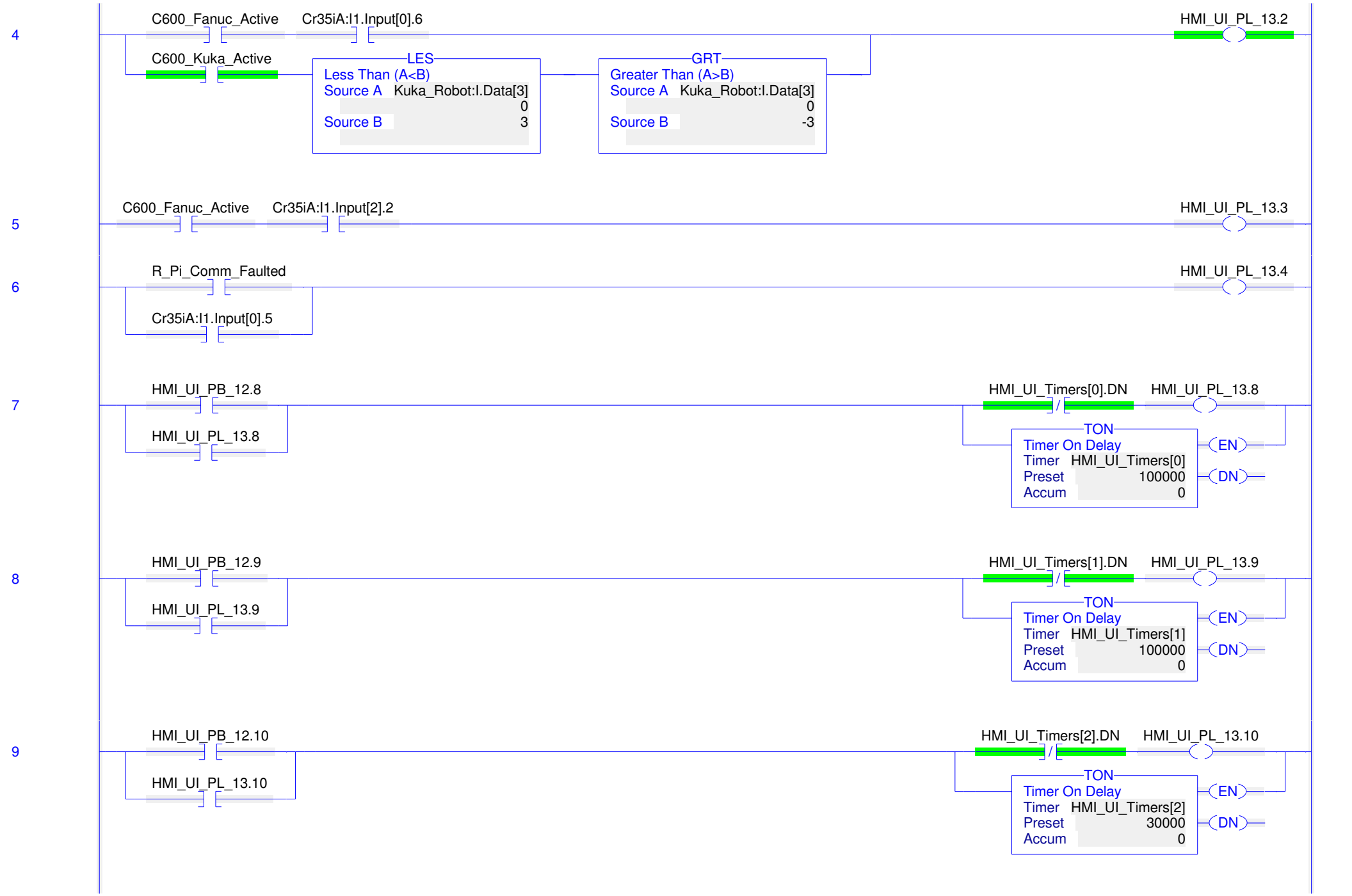
R_PI_User_Head_Angle	-9	INT	Huber_PLC
Constant	No		
External Access:	Read/Write		

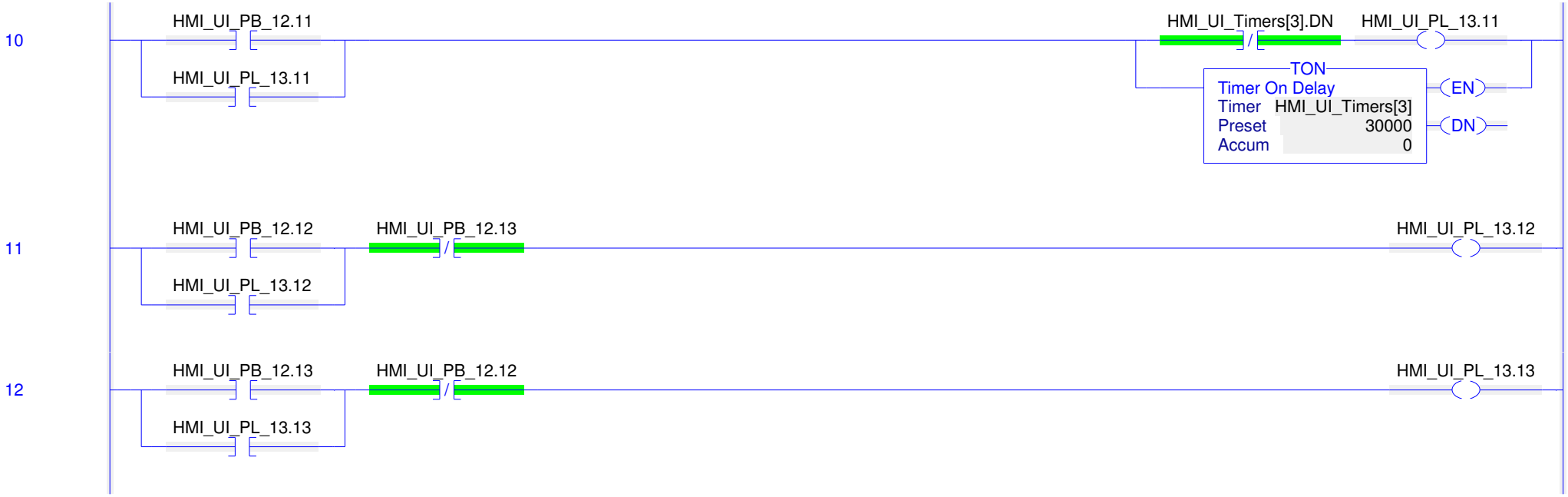
R_PI_User_Head_Angle - MainProgram/Fanuc_Robot_Control - 22(MOV)
R_PI_User_Head_Angle - MainProgram/Kuka_Robot_Control - 0(MOV)
R_PI_User_Head_Angle - MainProgram/Pycomm - 0(MOV)

Run_Mode	0	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		

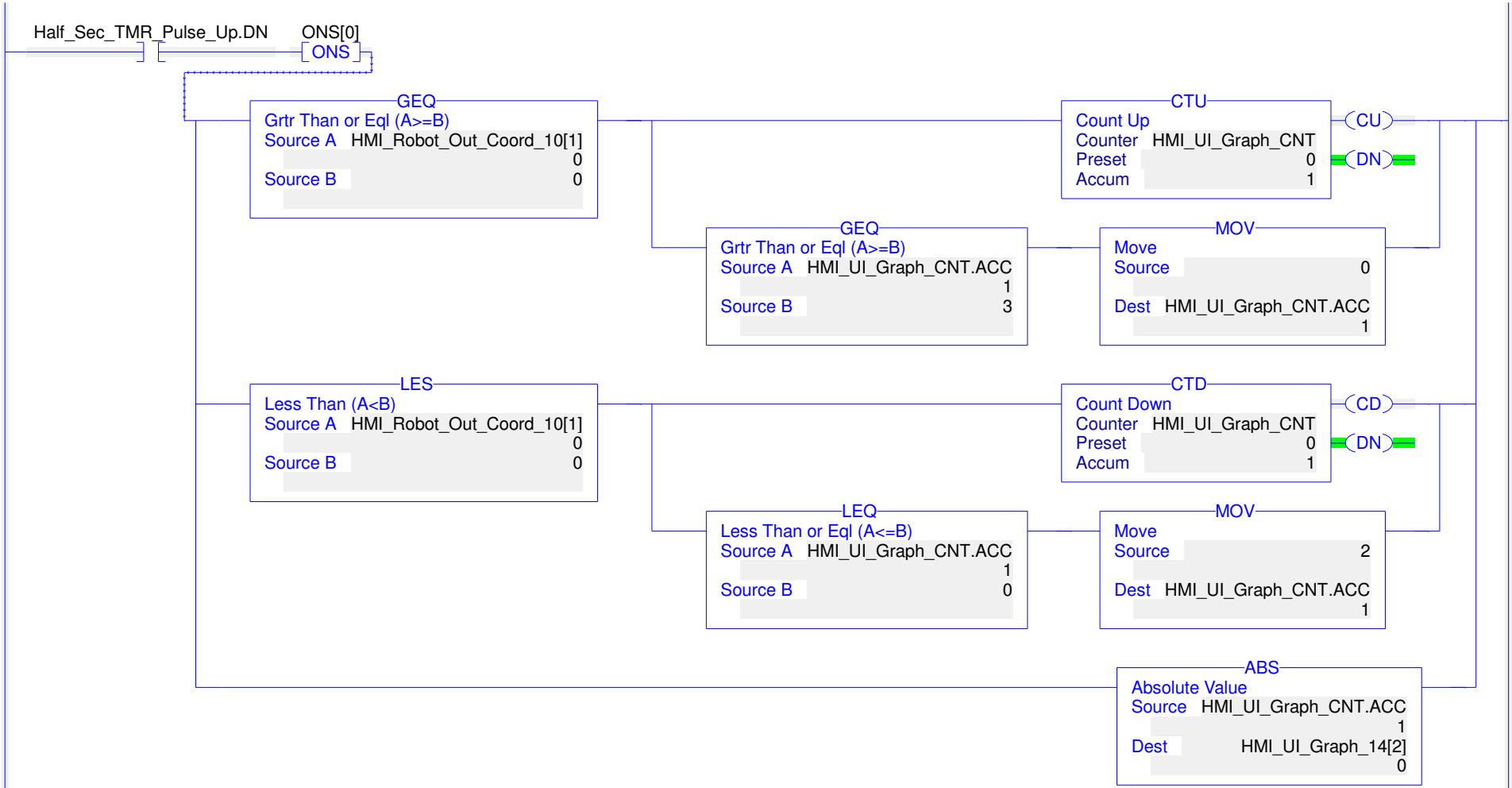
Run_Mode - MainProgram/Fanuc_Robot_Control - 0(XIC), 1(XIC), 2(XIC), 3(XIC), 5(XIC), 7(XIC), 8(XIC)
*Run_Mode - MainProgram/HMI_UI - *2(OTE)*
Run_Mode - MainProgram/Kuka_Robot_Control - 2(XIC)


0
AFI
Null
1
C600_Kuka_Active
MOV
Move
Source Kuka_Robot:I.Data[3]
0
Dest HMI_UI_Graph_14[0]
0
MOV
Move
Source Kuka_Robot:I.Data[3]
0
Dest HMI_UI_Graph_14[1]
0
C600_Fanuc_Active
MOV
Move
Source Cr35iA:I1.Input[11]
16#00
Dest HMI_UI_Graph_14[0]
0
MOV
Move
Source Cr35iA:I1.Input[11]
16#00
Dest HMI_UI_Graph_14[1]
0
2
Local:1:I.Data.0
HMI_UI_PB_12.0
HMI_UI_PB_12.1
HMI_UI_PL_13.0
HMI_UI_PL_13.0
Run_Mode
3
HMI_UI_PL_13.0
HMI_UI_PL_13.1


4
C600_Fanuc_Active
Cr35iA:I1.Input[0].6
HMI_UI_PL_13.2
C600_Kuka_Active
LES
Less Than (A<B)
Source A Kuka_Robot:I.Data[3]
0
Source B 3
GRT
Greater Than (A>B)
Source A Kuka_Robot:I.Data[3]
0
Source B -3
5
C600_Fanuc_Active
Cr35iA:I1.Input[2].2
HMI_UI_PL_13.3
6
R_Pi_Comm_Faulted
HMI_UI_PL_13.4
Cr35iA:I1.Input[0].5
7
HMI_UI_PB_12.8
HMI_UI_PL_13.8
HMI_UI_Timers[0].DN
HMI_UI_PL_13.8
TON
Timer On Delay
Timer HMI_UI_Timers[0]
Preset 100000
Accum 0
EN
DN
8
HMI_UI_PB_12.9
HMI_UI_PL_13.9
HMI_UI_Timers[1].DN
HMI_UI_PL_13.9
TON
Timer On Delay
Timer HMI_UI_Timers[1]
Preset 100000
Accum 0
EN
DN
9
HMI_UI_PB_12.10
HMI_UI_PL_13.10
HMI_UI_Timers[2].DN
HMI_UI_PL_13.10
TON
Timer On Delay
Timer HMI_UI_Timers[2]
Preset 30000
Accum 0
EN
DN


10
HMI_UI_PB_12.11
HMI_UI_PL_13.11
HMI_UI_Timers[3].DN
HMI_UI_PL_13.11
TON
Timer On Delay
Timer HMI_UI_Timers[3]
Preset 30000
Accum 0
EN
DN
11
HMI_UI_PB_12.12
HMI_UI_PL_13.12
HMI_UI_PB_12.13
HMI_UI_PL_13.12
12
HMI_UI_PB_12.13
HMI_UI_PL_13.13
HMI_UI_PB_12.12
HMI_UI_PL_13.13

13

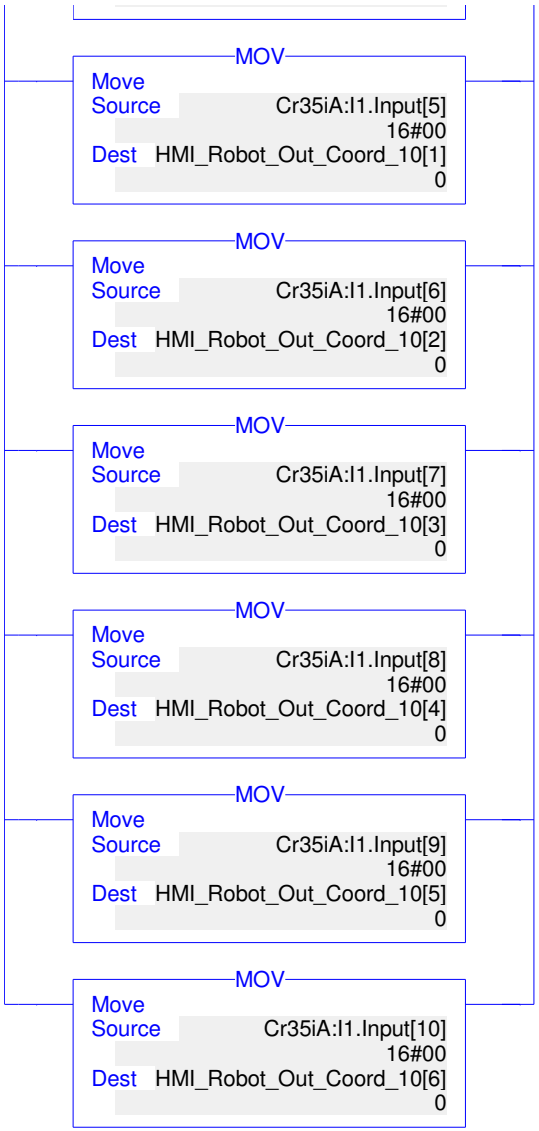

Half_Sec_TMR_Pulse_Up.DN
ONS[0]
ONS
GEQ
Grtr Than or Eql (A>=B)
Source A HMI_Robot_Out_Coord_10[1]
0
Source B
0
CTU
Count Up
Counter HMI_UI_Graph_CNT
Preset
0
Accum
1
CU
DN
GEQ
Grtr Than or Eql (A>=B)
Source A HMI_UI_Graph_CNT.ACC
1
Source B
3
MOV
Move
Source
0
Dest HMI_UI_Graph_CNT.ACC
1
LES
Less Than (A<B)
Source A HMI_Robot_Out_Coord_10[1]
0
Source B
0
CTD
Count Down
Counter HMI_UI_Graph_CNT
Preset
0
Accum
1
CD
DN
LEQ
Less Than or Eql (A<=B)
Source A HMI_UI_Graph_CNT.ACC
1
Source B
0
MOV
Move
Source
2
Dest HMI_UI_Graph_CNT.ACC
1
ABS
Absolute Value
Source HMI_UI_Graph_CNT.ACC
1
Dest HMI_UI_Graph_14[2]
0

14


AFI
Null

15


C600_Kuka_Active
MOV
Move
Source Kuka_Robot:I.Data[0]
0
Dest HMI_Robot_Out_Coord_10[0]
0
MOV
Move
Source Kuka_Robot:I.Data[1]
0
Dest HMI_Robot_Out_Coord_10[1]
0
MOV
Move
Source Kuka_Robot:I.Data[2]
0
Dest HMI_Robot_Out_Coord_10[2]
0
MOV
Move
Source Kuka_Robot:I.Data[3]
0
Dest HMI_Robot_Out_Coord_10[3]
0
MOV
Move
Source Kuka_Robot:I.Data[4]
0
Dest HMI_Robot_Out_Coord_10[4]
0
MOV
Move
Source Kuka_Robot:I.Data[5]
0
Dest HMI_Robot_Out_Coord_10[5]
0
MOV
Move
Source Kuka_Robot:I.Data[6]
0
Dest HMI_Robot_Out_Coord_10[6]
0
C600_Fanuc_Active
MOV
Move
Source Cr35iA:I1.Input[4]
16#00
Dest HMI_Robot_Out_Coord_10[0]
0


MOV
Move
Source Cr35iA:I1.Input[5]
16#00
Dest HMI_Robot_Out_Coord_10[1]
0
MOV
Move
Source Cr35iA:I1.Input[6]
16#00
Dest HMI_Robot_Out_Coord_10[2]
0
MOV
Move
Source Cr35iA:I1.Input[7]
16#00
Dest HMI_Robot_Out_Coord_10[3]
0
MOV
Move
Source Cr35iA:I1.Input[8]
16#00
Dest HMI_Robot_Out_Coord_10[4]
0
MOV
Move
Source Cr35iA:I1.Input[9]
16#00
Dest HMI_Robot_Out_Coord_10[5]
0
MOV
Move
Source Cr35iA:I1.Input[10]
16#00
Dest HMI_Robot_Out_Coord_10[6]
0

(End)

Name	Value	Data Type	Scope
C600_Fanuc_Active	0	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		
C600_Fanuc_Active - MainProgram/HMI_UI - 1(XIC), 15(XIC), 4(XIC), 5(XIC)			
*C600_Fanuc_Active - MainProgram/Robotics_Control - *2(OTE), 0(XIC), 2(XIC), 2(XIO), 3(XIO)*			
C600_Kuka_Active	1	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		
C600_Kuka_Active - MainProgram/HMI_UI - 1(XIC), 15(XIC), 4(XIC)			
*C600_Kuka_Active - MainProgram/Robotics_Control - *3(OTE)*			
Cr35iA:I1		FR:Standard_Robot_16Bytes:I1:0	Huber_PLC
External Access:	Read/Write		
Cr35iA:I1.Input[0].0	0	BOOL	
Cr35iA:I1.Input[0].0 - MainProgram/Fanuc_Robot_Control - 5(XIC), 8(XIC)			
Cr35iA:I1.Input[0].1	0	BOOL	
Cr35iA:I1.Input[0].1 - MainProgram/Fanuc_Robot_Control - 5(XIC), 8(XIC)			
Cr35iA:I1.Input[0].2	0	BOOL	
Cr35iA:I1.Input[0].2 - MainProgram/Fanuc_Robot_Control - 5(XIC), 5(XIO), 8(XIC)			
Cr35iA:I1.Input[0].5	0	BOOL	
Cr35iA:I1.Input[0].5 - MainProgram/Fanuc_Robot_Control - 5(XIO), 8(XIO)			
Cr35iA:I1.Input[0].5 - MainProgram/HMI_UI - 6(XIC)			
Cr35iA:I1.Input[0].6	0	BOOL	
Cr35iA:I1.Input[0].6 - MainProgram/HMI_UI - 4(XIC)			
Cr35iA:I1.Input[0].7	0	BOOL	
Cr35iA:I1.Input[0].7 - MainProgram/Fanuc_Robot_Control - 0(XIC), 1(XIC), 2(XIC), 3(XIC), 5(XIO), 7(XIC), 8(XIO)			
Cr35iA:I1.Input[2].2	0	BOOL	
Cr35iA:I1.Input[2].2 - MainProgram/HMI_UI - 5(XIC)			
Cr35iA:I1.Input[4]	16#00	SINT	
Cr35iA:I1.Input[4] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[5]	16#00	SINT	
Cr35iA:I1.Input[5] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[6]	16#00	SINT	
Cr35iA:I1.Input[6] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[7]	16#00	SINT	
Cr35iA:I1.Input[7] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[8]	16#00	SINT	
Cr35iA:I1.Input[8] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[9]	16#00	SINT	
Cr35iA:I1.Input[9] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[10]	16#00	SINT	
Cr35iA:I1.Input[10] - MainProgram/HMI_UI - 15(MOV)			
Cr35iA:I1.Input[11]	16#00	SINT	
Cr35iA:I1.Input[11] - MainProgram/HMI_UI - 1(MOV)			
Half_Sec_TMR_Pulse_Up		TIMER	Huber_PLC

Half_Sec_TMR_Pulse_Up (Continued)
Constant No
External Access: Read/Write
*Half_Sec_TMR_Pulse_Up - MainProgram/MainRoutine - *0(TON)*

Half_Sec_TMR_Pulse_Up.DN	0	BOOL	

Half_Sec_TMR_Pulse_Up.DN - MainProgram/HMI_UI - 13(XIC)
Half_Sec_TMR_Pulse_Up.DN - MainProgram/MainRoutine - 0(XIC)
Half_Sec_TMR_Pulse_Up.DN - MainProgram/Pycomm - 1(XIC)

HMI_Robot_Out_Coord_10		INT[10]	Huber_PLC

Maximum Consumers: 10
Include Connection Status: n/a
Send Data State Change Event to Consumer(s): No
Allow Unicast Consumer Connections: n/a
Constant No
External Access: Read/Write

HMI_Robot_Out_Coord_10[0]	0	INT	

*HMI_Robot_Out_Coord_10[0] - MainProgram/HMI_UI - *15(MOV)*

HMI_Robot_Out_Coord_10[1]	0	INT	

*HMI_Robot_Out_Coord_10[1] - MainProgram/HMI_UI - *15(MOV), 13(GEQ), 13(LES)*

HMI_Robot_Out_Coord_10[2]	0	INT	

*HMI_Robot_Out_Coord_10[2] - MainProgram/HMI_UI - *15(MOV)*

HMI_Robot_Out_Coord_10[3]	0	INT	

*HMI_Robot_Out_Coord_10[3] - MainProgram/HMI_UI - *15(MOV)*

HMI_Robot_Out_Coord_10[4]	0	INT	

*HMI_Robot_Out_Coord_10[4] - MainProgram/HMI_UI - *15(MOV)*

HMI_Robot_Out_Coord_10[5]	0	INT	

*HMI_Robot_Out_Coord_10[5] - MainProgram/HMI_UI - *15(MOV)*

HMI_Robot_Out_Coord_10[6]	0	INT	

*HMI_Robot_Out_Coord_10[6] - MainProgram/HMI_UI - *15(MOV)*

HMI_Robot_Out_Coord_10[7]	5	INT	

*HMI_Robot_Out_Coord_10[7] - MainProgram/Pycomm - *0(MOV)*

HMI_UI_Graph_14		INT[3]	Huber_PLC

Maximum Consumers: 14
Include Connection Status: n/a
Send Data State Change Event to Consumer(s): No
Allow Unicast Consumer Connections: n/a
Constant No
External Access: Read/Write

HMI_UI_Graph_14[0]	0	INT	

*HMI_UI_Graph_14[0] - MainProgram/HMI_UI - *1(MOV)*

HMI_UI_Graph_14[1]	0	INT	

*HMI_UI_Graph_14[1] - MainProgram/HMI_UI - *1(MOV)*

HMI_UI_Graph_14[2]	0	INT	

*HMI_UI_Graph_14[2] - MainProgram/HMI_UI - *13(ABS)*

HMI_UI_Graph_CNT		COUNTER	MainProgram

HMI_UI_Graph_CNT (Continued)
Constant No
External Access: Read/Write
*HMI_UI_Graph_CNT - MainProgram/HMI_UI - *13(CTD), *13(CTU)*

HMI_UI_Graph_CNT.ACC	1	DINT	

*HMI_UI_Graph_CNT.ACC - MainProgram/HMI_UI - *13(MOV), 13(ABS), 13(GEQ), 13(LEQ)*

HMI_UI_PB_12	0	INT	Huber_PLC

Maximum Consumers: 12
Include Connection Status: n/a
Send Data State Change Event to Consumer(s): No
Allow Unicast Consumer Connections: n/a
Constant No
External Access: Read/Write

HMI_UI_PB_12.0	0	BOOL

HMI_UI_PB_12.0 - MainProgram/HMI_UI - 2(XIC)

HMI_UI_PB_12.1	0	BOOL

HMI_UI_PB_12.1 - MainProgram/HMI_UI - 2(XIO)

HMI_UI_PB_12.2	0	BOOL

HMI_UI_PB_12.2 - MainProgram/Kuka_Robot_Control - 3(XIC)

HMI_UI_PB_12.4	0	BOOL

HMI_UI_PB_12.4 - MainProgram/Fanuc_Robot_Control - 4(XIC), 5(XIO), 8(XIO)
HMI_UI_PB_12.4 - MainProgram/Pycomm - 2(XIC)

HMI_UI_PB_12.7	0	BOOL

HMI_UI_PB_12.7 - MainProgram/Robotics_Control - 1(XIC)

HMI_UI_PB_12.8	0	BOOL

HMI_UI_PB_12.8 - MainProgram/HMI_UI - 7(XIC)

HMI_UI_PB_12.9	0	BOOL

HMI_UI_PB_12.9 - MainProgram/HMI_UI - 8(XIC)

HMI_UI_PB_12.10	0	BOOL

HMI_UI_PB_12.10 - MainProgram/HMI_UI - 9(XIC)

HMI_UI_PB_12.11	0	BOOL

HMI_UI_PB_12.11 - MainProgram/HMI_UI - 10(XIC)

HMI_UI_PB_12.12	0	BOOL

HMI_UI_PB_12.12 - MainProgram/HMI_UI - 11(XIC), 12(XIO)

HMI_UI_PB_12.13	0	BOOL

HMI_UI_PB_12.13 - MainProgram/HMI_UI - 11(XIO), 12(XIC)

HMI_UI_PL_13	6	INT	Huber_PLC

Maximum Consumers: 13
Include Connection Status: n/a
Send Data State Change Event to Consumer(s): No
Allow Unicast Consumer Connections: n/a
Constant No
External Access: Read/Write

HMI_UI_PL_13.0	0	BOOL

*HMI_UI_PL_13.0 - MainProgram/HMI_UI - *2(OTE), 2(XIC), 3(XIO)*

HMI_UI_PL_13.1	1	BOOL

HMI_UI_PL_13 (Continued)			
*HMI_UI_PL_13.1 - MainProgram/HMI_UI - *3(OTE)*			
HMI_UI_PL_13.2	1	BOOL	
*HMI_UI_PL_13.2 - MainProgram/HMI_UI - *4(OTE)*			
HMI_UI_PL_13.2 - MainProgram/Kuka_Robot_Control - 4(XIC)			
HMI_UI_PL_13.3	0	BOOL	
*HMI_UI_PL_13.3 - MainProgram/HMI_UI - *5(OTE)*			
HMI_UI_PL_13.4	0	BOOL	
*HMI_UI_PL_13.4 - MainProgram/HMI_UI - *6(OTE)*			
HMI_UI_PL_13.7	0	BOOL	
*HMI_UI_PL_13.7 - MainProgram/Robotics_Control - *0(OTE)*			
HMI_UI_PL_13.8	0	BOOL	
*HMI_UI_PL_13.8 - MainProgram/HMI_UI - *7(OTE), 7(XIC)*			
HMI_UI_PL_13.9	0	BOOL	
*HMI_UI_PL_13.9 - MainProgram/HMI_UI - *8(OTE), 8(XIC)*			
HMI_UI_PL_13.10	0	BOOL	
*HMI_UI_PL_13.10 - MainProgram/HMI_UI - *9(OTE), 9(XIC)*			
HMI_UI_PL_13.11	0	BOOL	
*HMI_UI_PL_13.11 - MainProgram/HMI_UI - *10(OTE), 10(XIC)*			
HMI_UI_PL_13.12	0	BOOL	
*HMI_UI_PL_13.12 - MainProgram/HMI_UI - *11(OTE), 11(XIC)*			
HMI_UI_PL_13.13	0	BOOL	
*HMI_UI_PL_13.13 - MainProgram/HMI_UI - *12(OTE), 12(XIC)*			
HMI_UI_Timers		TIMER[16]	Huber_PLC
Constant	No		
External Access:	Read/Write		
HMI_UI_Timers[0]		TIMER	
*HMI_UI_Timers[0] - MainProgram/HMI_UI - *7(TON)*			
HMI_UI_Timers[0].DN	0	BOOL	
HMI_UI_Timers[0].DN - MainProgram/HMI_UI - 7(XIO)			
HMI_UI_Timers[1]		TIMER	
*HMI_UI_Timers[1] - MainProgram/HMI_UI - *8(TON)*			
HMI_UI_Timers[1].DN	0	BOOL	
HMI_UI_Timers[1].DN - MainProgram/HMI_UI - 8(XIO)			
HMI_UI_Timers[2]		TIMER	
*HMI_UI_Timers[2] - MainProgram/HMI_UI - *9(TON)*			
HMI_UI_Timers[2].DN	0	BOOL	
HMI_UI_Timers[2].DN - MainProgram/HMI_UI - 9(XIO)			
HMI_UI_Timers[3]		TIMER	
*HMI_UI_Timers[3] - MainProgram/HMI_UI - *10(TON)*			
HMI_UI_Timers[3].DN	0	BOOL	
HMI_UI_Timers[3].DN - MainProgram/HMI_UI - 10(XIO)			
Kuka_Robot:I		_005A:AB767879xx_F_D7BC2DEE:I:0	Huber_PLC
External Access:	Read/Write		
Kuka_Robot:I.Data[0]	0	INT	
Kuka_Robot:I.Data[0] - MainProgram/HMI_UI - 15(MOV)			

Kuka_Robot:I (Continued)
Kuka_Robot:I.Data[1] 0 INT
Kuka_Robot:I.Data[1] - MainProgram/HMI_UI - 15(MOV)
Kuka_Robot:I.Data[2] 0 INT
Kuka_Robot:I.Data[2] - MainProgram/HMI_UI - 15(MOV)
Kuka_Robot:I.Data[3] 0 INT
Kuka_Robot:I.Data[3] - MainProgram/HMI_UI - 1(MOV), 15(MOV), 4(GRT), 4(LES)
Kuka_Robot:I.Data[4] 0 INT
Kuka_Robot:I.Data[4] - MainProgram/HMI_UI - 15(MOV)
Kuka_Robot:I.Data[5] 0 INT
Kuka_Robot:I.Data[5] - MainProgram/HMI_UI - 15(MOV)
Kuka_Robot:I.Data[6] 0 INT
Kuka_Robot:I.Data[6] - MainProgram/HMI_UI - 15(MOV)

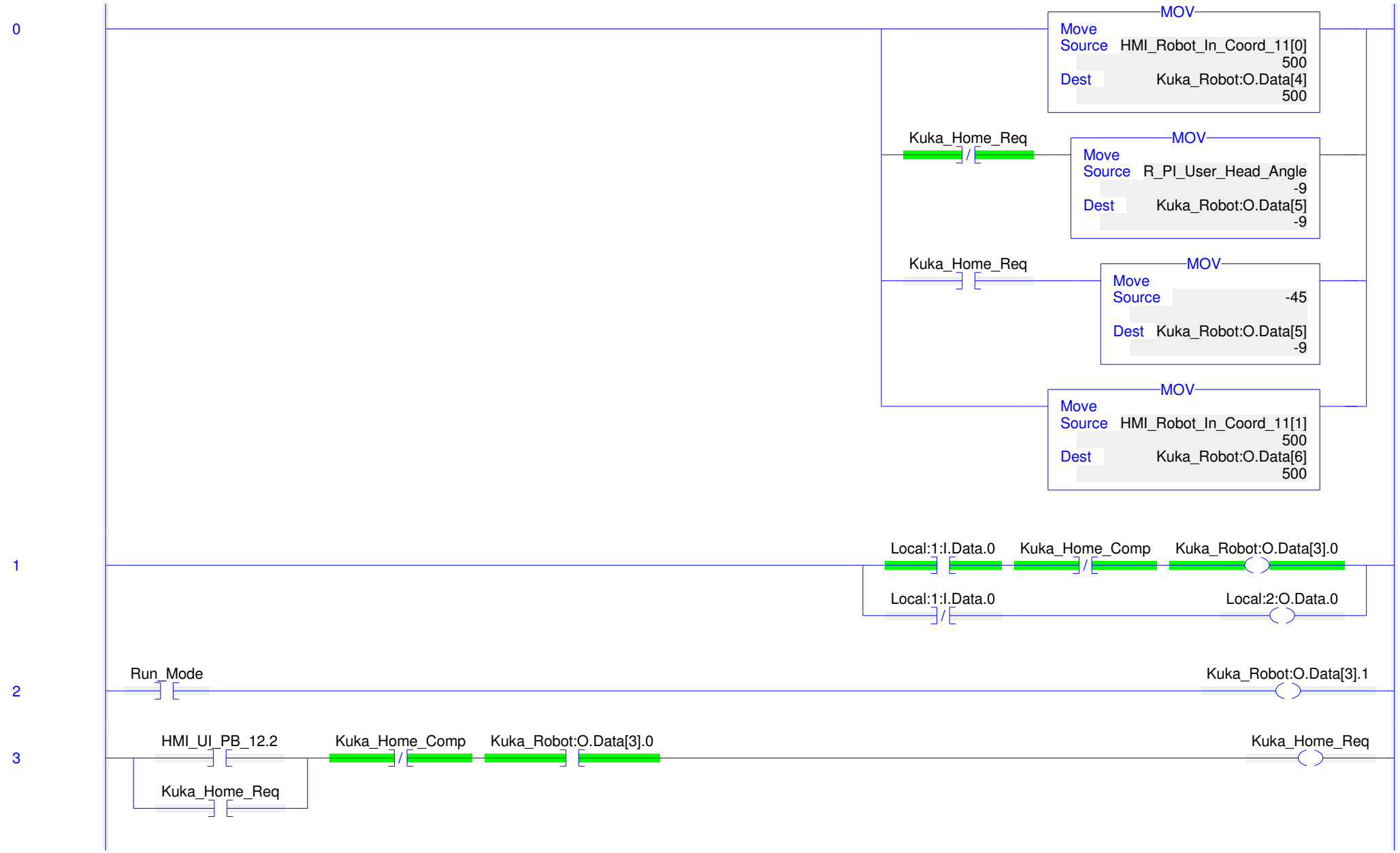
Local:1:I AB:Embedded_IQ16F:I:0 Huber_PLC
External Access: Read/Write
Local:1:I.Data.0 1 BOOL
Local:1:I.Data.0 - MainProgram/HMI_UI - 2(XIC)
Local:1:I.Data.0 - MainProgram/Kuka_Robot_Control - 1(XIC), 1(XIO)

Null 0 BOOL MainProgram
Constant No
External Access: Read/Write
*Null - MainProgram/HMI_UI - *0(OTE), *14(OTE)*

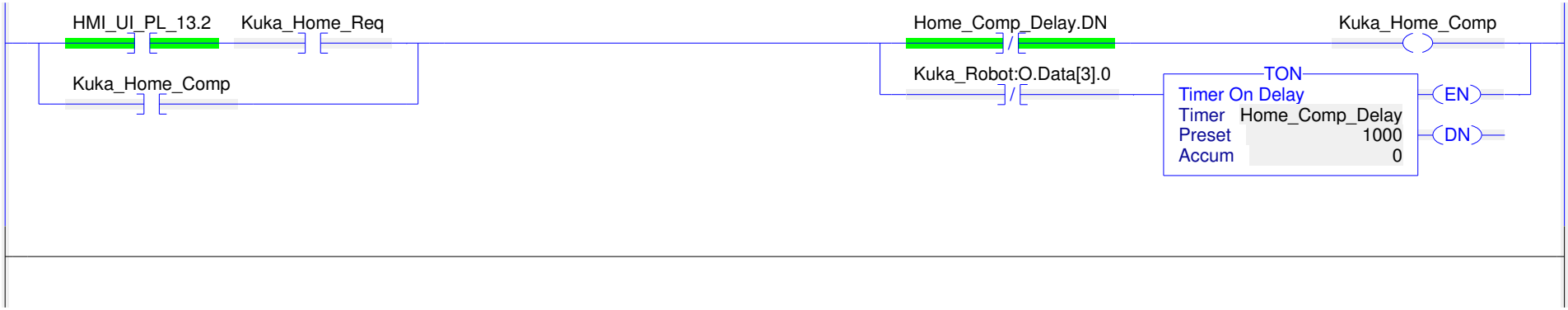
ONS BOOL[128] Huber_PLC
Constant No
External Access: Read/Write
ONS[0] 0 BOOL
*ONS[0] - MainProgram/HMI_UI - *13(ONS)*
ONS[1] 0 BOOL
*ONS[1] - MainProgram/Robotics_Control - *1(ONS)*
ONS[2] 0 BOOL
*ONS[2] - MainProgram/Pycomm - *1(ONS)*

R_Pi_Comm_Faulted 0 BOOL MainProgram
Constant No
External Access: Read/Write
R_Pi_Comm_Faulted - MainProgram/HMI_UI - 6(XIC)
*R_Pi_Comm_Faulted - MainProgram/Pycomm - *1(OTL), *2(OTU)*

Run_Mode 0 BOOL MainProgram
Constant No
External Access: Read/Write
Run_Mode - MainProgram/Fanuc_Robot_Control - 0(XIC), 1(XIC), 2(XIC), 3(XIC), 5(XIC), 7(XIC), 8(XIC)
*Run_Mode - MainProgram/HMI_UI - *2(OTE)*
Run_Mode - MainProgram/Kuka_Robot_Control - 2(XIC)


0
MOV
Move
Source HMI_Robot_In_Coord_11[0]
500
Dest Kuka_Robot:O.Data[4]
500
Kuka_Home_Req
MOV
Move
Source R_PI_User_Head_Angle
-9
Dest Kuka_Robot:O.Data[5]
-9
Kuka_Home_Req
MOV
Move
Source -45
Dest Kuka_Robot:O.Data[5]
-9
MOV
Move
Source HMI_Robot_In_Coord_11[1]
500
Dest Kuka_Robot:O.Data[6]
500
1
Local:1:I.Data.0
Kuka_Home_Comp
Kuka_Robot:O.Data[3].0
Local:1:I.Data.0
Local:2:O.Data.0
2
Run_Mode
Kuka_Robot:O.Data[3].1
3
HMI_UI_PB_12.2
Kuka_Home_Comp
Kuka_Robot:O.Data[3].0
Kuka_Home_Req
Kuka_Home_Req

4


HMI_UI_PL_13.2
Kuka_Home_Req
Kuka_Home_Comp
Home_Comp_Delay.DN
Kuka_Robot:O.Data[3].0
Kuka_Home_Comp
TON
Timer On Delay
Timer Home_Comp_Delay
Preset 1000
Accum 0
EN
DN

(End)

Name	Value	Data Type	Scope
HMI_Robot_In_Coord_11		INT[10]	Huber_PLC
Maximum Consumers:	11		
Include Connection Status:	n/a		
Send Data State Change Event to Consumer(s):	No		
Allow Unicast Consumer Connections:	n/a		
Constant	No		
External Access:	Read/Write		
HMI_Robot_In_Coord_11[0]	500	INT	
HMI_Robot_In_Coord_11[0] - MainProgram/Fanuc_Robot_Control - 21(MOV)			
HMI_Robot_In_Coord_11[0] - MainProgram/Kuka_Robot_Control - 0(MOV)			
HMI_Robot_In_Coord_11[1]	500	INT	
HMI_Robot_In_Coord_11[1] - MainProgram/Fanuc_Robot_Control - 23(MOV)			
HMI_Robot_In_Coord_11[1] - MainProgram/Kuka_Robot_Control - 0(MOV)			
HMI_UI_PB_12	0	INT	Huber_PLC
Maximum Consumers:	12		
Include Connection Status:	n/a		
Send Data State Change Event to Consumer(s):	No		
Allow Unicast Consumer Connections:	n/a		
Constant	No		
External Access:	Read/Write		
HMI_UI_PB_12.0	0	BOOL	
HMI_UI_PB_12.0 - MainProgram/HMI_UI - 2(XIC)			
HMI_UI_PB_12.1	0	BOOL	
HMI_UI_PB_12.1 - MainProgram/HMI_UI - 2(XIO)			
HMI_UI_PB_12.2	0	BOOL	
HMI_UI_PB_12.2 - MainProgram/Kuka_Robot_Control - 3(XIC)			
HMI_UI_PB_12.4	0	BOOL	
HMI_UI_PB_12.4 - MainProgram/Fanuc_Robot_Control - 4(XIC), 5(XIO), 8(XIO)			
HMI_UI_PB_12.4 - MainProgram/Pycomm - 2(XIC)			
HMI_UI_PB_12.7	0	BOOL	
HMI_UI_PB_12.7 - MainProgram/Robotics_Control - 1(XIC)			
HMI_UI_PB_12.8	0	BOOL	
HMI_UI_PB_12.8 - MainProgram/HMI_UI - 7(XIC)			
HMI_UI_PB_12.9	0	BOOL	
HMI_UI_PB_12.9 - MainProgram/HMI_UI - 8(XIC)			
HMI_UI_PB_12.10	0	BOOL	
HMI_UI_PB_12.10 - MainProgram/HMI_UI - 9(XIC)			
HMI_UI_PB_12.11	0	BOOL	
HMI_UI_PB_12.11 - MainProgram/HMI_UI - 10(XIC)			
HMI_UI_PB_12.12	0	BOOL	
HMI_UI_PB_12.12 - MainProgram/HMI_UI - 11(XIC), 12(XIO)			
HMI_UI_PB_12.13	0	BOOL	
HMI_UI_PB_12.13 - MainProgram/HMI_UI - 11(XIO), 12(XIC)			
HMI_UI_PL_13	6	INT	Huber_PLC
Maximum Consumers:	13		

HMI_UI_PL_13 (Continued)
Include Connection Status: n/a
Send Data State Change Event to Consumer(s): No
Allow Unicast Consumer Connections: n/a
Constant No
External Access: Read/Write

HMI_UI_PL_13.0 0 BOOL
*HMI_UI_PL_13.0 - MainProgram/HMI_UI - *2(OTE), 2(XIC), 3(XIO)*
HMI_UI_PL_13.1 1 BOOL
*HMI_UI_PL_13.1 - MainProgram/HMI_UI - *3(OTE)*
HMI_UI_PL_13.2 1 BOOL
*HMI_UI_PL_13.2 - MainProgram/HMI_UI - *4(OTE)*
HMI_UI_PL_13.2 - MainProgram/Kuka_Robot_Control - 4(XIC)
HMI_UI_PL_13.3 0 BOOL
*HMI_UI_PL_13.3 - MainProgram/HMI_UI - *5(OTE)*
HMI_UI_PL_13.4 0 BOOL
*HMI_UI_PL_13.4 - MainProgram/HMI_UI - *6(OTE)*
HMI_UI_PL_13.7 0 BOOL
*HMI_UI_PL_13.7 - MainProgram/Robotics_Control - *0(OTE)*
HMI_UI_PL_13.8 0 BOOL
*HMI_UI_PL_13.8 - MainProgram/HMI_UI - *7(OTE), 7(XIC)*
HMI_UI_PL_13.9 0 BOOL
*HMI_UI_PL_13.9 - MainProgram/HMI_UI - *8(OTE), 8(XIC)*
HMI_UI_PL_13.10 0 BOOL
*HMI_UI_PL_13.10 - MainProgram/HMI_UI - *9(OTE), 9(XIC)*
HMI_UI_PL_13.11 0 BOOL
*HMI_UI_PL_13.11 - MainProgram/HMI_UI - *10(OTE), 10(XIC)*
HMI_UI_PL_13.12 0 BOOL
*HMI_UI_PL_13.12 - MainProgram/HMI_UI - *11(OTE), 11(XIC)*
HMI_UI_PL_13.13 0 BOOL
*HMI_UI_PL_13.13 - MainProgram/HMI_UI - *12(OTE), 12(XIC)*

Home_Comp_Delay TIMER MainProgram
Constant No
External Access: Read/Write
*Home_Comp_Delay - MainProgram/Kuka_Robot_Control - *4(TON)*
Home_Comp_Delay.DN 0 BOOL
Home_Comp_Delay.DN - MainProgram/Kuka_Robot_Control - 4(XIO)

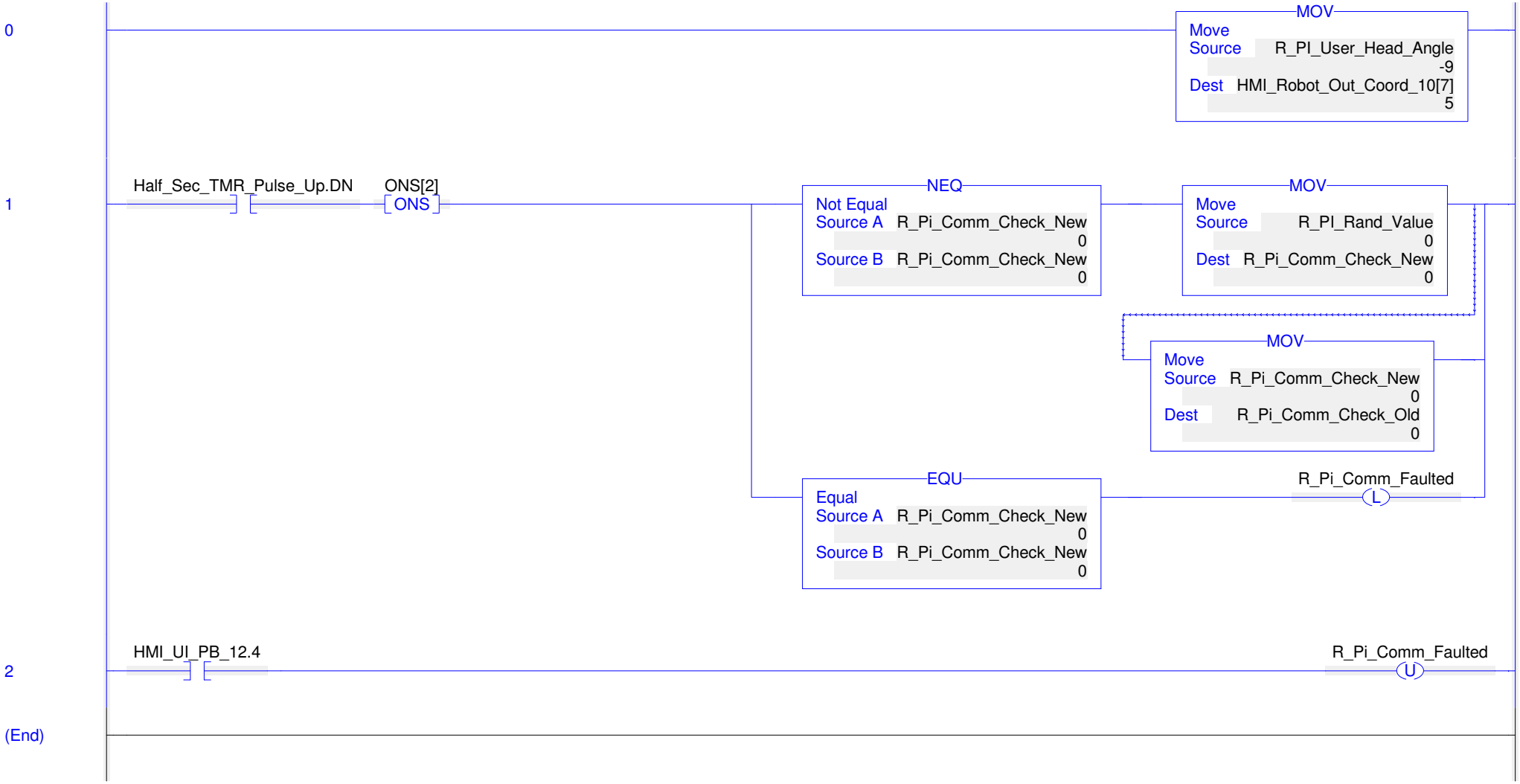
Kuka_Home_Comp 0 BOOL MainProgram
Constant No
External Access: Read/Write
*Kuka_Home_Comp - MainProgram/Kuka_Robot_Control - *4(OTE), 1(XIO), 3(XIO), 4(XIC)*

Kuka_Home_Req 0 BOOL MainProgram
Constant No
External Access: Read/Write
*Kuka_Home_Req - MainProgram/Kuka_Robot_Control - *3(OTE), 0(XIC), 0(XIO), 3(XIC), 4(XIC)*

Kuka_Robot:O		_005A:AB767879xx_F_D2EC9ED2:O:0	Huber_PLC
External Access:	Read/Write		
Kuka_Robot:O.Data[0]	155	INT	
*Kuka_Robot:O.Data[0] - Research/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[1]	21	INT	
*Kuka_Robot:O.Data[1] - Research/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[2]	67	INT	
*Kuka_Robot:O.Data[2] - Research/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[3].0	1	BOOL	
*Kuka_Robot:O.Data[3].0 - MainProgram/Kuka_Robot_Control - *1(OTE), 3(XIC), 4(XIO)*			
Kuka_Robot:O.Data[3].1	0	BOOL	
*Kuka_Robot:O.Data[3].1 - MainProgram/Kuka_Robot_Control - *2(OTE)*			
Kuka_Robot:O.Data[4]	500	INT	
*Kuka_Robot:O.Data[4] - MainProgram/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[5]	-9	INT	
*Kuka_Robot:O.Data[5] - MainProgram/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[6]	500	INT	
*Kuka_Robot:O.Data[6] - MainProgram/Kuka_Robot_Control - *0(MOV)*			
Local:1:I		AB:Embedded_IQ16F:I:0	Huber_PLC
External Access:	Read/Write		
Local:1:I.Data.0	1	BOOL	
Local:1:I.Data.0 - MainProgram/HMI_UI - 2(XIC)			
Local:1:I.Data.0 - MainProgram/Kuka_Robot_Control - 1(XIC), 1(XIO)			
Local:2:O		AB:Embedded_OB16:O:0	Huber_PLC
External Access:	Read/Write		
Local:2:O.Data.0	0	BOOL	
*Local:2:O.Data.0 - MainProgram/Kuka_Robot_Control - *1(OTE)*			
R_PI_User_Head_Angle	-9	INT	Huber_PLC
Constant	No		
External Access:	Read/Write		
R_PI_User_Head_Angle - MainProgram/Fanuc_Robot_Control - 22(MOV)			
R_PI_User_Head_Angle - MainProgram/Kuka_Robot_Control - 0(MOV)			
R_PI_User_Head_Angle - MainProgram/Pycomm - 0(MOV)			
Run_Mode	0	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		
Run_Mode - MainProgram/Fanuc_Robot_Control - 0(XIC), 1(XIC), 2(XIC), 3(XIC), 5(XIC), 7(XIC), 8(XIC)			
*Run_Mode - MainProgram/HMI_UI - *2(OTE)*			
Run_Mode - MainProgram/Kuka_Robot_Control - 2(XIC)			


0
Half_Sec_TMR_Pulse_Down.DN
TON
Timer On Delay
Timer Half_Sec_TMR_Pulse_Up
Preset 500
Accum 307
EN
DN
Half_Sec_TMR_Pulse_Up.DN
TON
Timer On Delay
Timer Half_Sec_TMR_Pulse_Down
Preset 500
Accum 0
EN
DN
1
JSR
Jump To Subroutine
Routine Name HMI_UI
2
JSR
Jump To Subroutine
Routine Name Fanuc_Robot_Control
3
JSR
Jump To Subroutine
Routine Name Robotics_Control
4
JSR
Jump To Subroutine
Routine Name Kuka_Robot_Control
(End)

Name	Value	Data Type	Scope
Half_Sec_TMR_Pulse_Down		TIMER	Huber_PLC
Constant	No		
External Access:	Read/Write		
*Half_Sec_TMR_Pulse_Down - MainProgram/MainRoutine - *0(TON)*			
Half_Sec_TMR_Pulse_Down.DN	0	BOOL	
Half_Sec_TMR_Pulse_Down.DN - MainProgram/MainRoutine - 0(XIO)			
Half_Sec_TMR_Pulse_Up		TIMER	Huber_PLC
Constant	No		
External Access:	Read/Write		
*Half_Sec_TMR_Pulse_Up - MainProgram/MainRoutine - *0(TON)*			
Half_Sec_TMR_Pulse_Up.DN	0	BOOL	
Half_Sec_TMR_Pulse_Up.DN - MainProgram/HMI_UI - 13(XIC)			
Half_Sec_TMR_Pulse_Up.DN - MainProgram/MainRoutine - 0(XIC)			
Half_Sec_TMR_Pulse_Up.DN - MainProgram/Pycomm - 1(XIC)			


0
MOV
Move
Source R_PI_User_Head_Angle
-9
Dest HMI_Robot_Out_Coord_10[7]
5
1
Half_Sec_TMR_Pulse_Up.DN
ONS[2]
ONS
NEQ
Not Equal
Source A R_Pi_Comm_Check_New
0
Source B R_Pi_Comm_Check_New
0
MOV
Move
Source R_PI_Rand_Value
0
Dest R_Pi_Comm_Check_New
0
MOV
Move
Source R_Pi_Comm_Check_New
0
Dest R_Pi_Comm_Check_Old
0
EQU
Equal
Source A R_Pi_Comm_Check_New
0
Source B R_Pi_Comm_Check_New
0
R_Pi_Comm_Faulted
L
2
HMI_UI_PB_12.4
R_Pi_Comm_Faulted
U
(End)

Name	Value	Data Type	Scope
Half_Sec_TMR_Pulse_Up		TIMER	Huber_PLC
Constant	No		
External Access:	Read/Write		
*Half_Sec_TMR_Pulse_Up - MainProgram/MainRoutine - *0(TON)*			
Half_Sec_TMR_Pulse_Up.DN	0	BOOL	
Half_Sec_TMR_Pulse_Up.DN - MainProgram/HMI_UI - 13(XIC)			
Half_Sec_TMR_Pulse_Up.DN - MainProgram/MainRoutine - 0(XIC)			
Half_Sec_TMR_Pulse_Up.DN - MainProgram/Pycomm - 1(XIC)			
HMI_Robot_Out_Coord_10		INT[10]	Huber_PLC
Maximum Consumers:	10		
Include Connection Status:	n/a		
Send Data State Change Event to Consumer(s):	No		
Allow Unicast Consumer Connections:	n/a		
Constant	No		
External Access:	Read/Write		
HMI_Robot_Out_Coord_10[0]	0	INT	
*HMI_Robot_Out_Coord_10[0] - MainProgram/HMI_UI - *15(MOV)*			
HMI_Robot_Out_Coord_10[1]	0	INT	
*HMI_Robot_Out_Coord_10[1] - MainProgram/HMI_UI - *15(MOV), 13(GEQ), 13(LES)*			
HMI_Robot_Out_Coord_10[2]	0	INT	
*HMI_Robot_Out_Coord_10[2] - MainProgram/HMI_UI - *15(MOV)*			
HMI_Robot_Out_Coord_10[3]	0	INT	
*HMI_Robot_Out_Coord_10[3] - MainProgram/HMI_UI - *15(MOV)*			
HMI_Robot_Out_Coord_10[4]	0	INT	
*HMI_Robot_Out_Coord_10[4] - MainProgram/HMI_UI - *15(MOV)*			
HMI_Robot_Out_Coord_10[5]	0	INT	
*HMI_Robot_Out_Coord_10[5] - MainProgram/HMI_UI - *15(MOV)*			
HMI_Robot_Out_Coord_10[6]	0	INT	
*HMI_Robot_Out_Coord_10[6] - MainProgram/HMI_UI - *15(MOV)*			
HMI_Robot_Out_Coord_10[7]	5	INT	
*HMI_Robot_Out_Coord_10[7] - MainProgram/Pycomm - *0(MOV)*			
HMI_UI_PB_12	0	INT	Huber_PLC
Maximum Consumers:	12		
Include Connection Status:	n/a		
Send Data State Change Event to Consumer(s):	No		
Allow Unicast Consumer Connections:	n/a		
Constant	No		
External Access:	Read/Write		
HMI_UI_PB_12.0	0	BOOL	
HMI_UI_PB_12.0 - MainProgram/HMI_UI - 2(XIC)			
HMI_UI_PB_12.1	0	BOOL	
HMI_UI_PB_12.1 - MainProgram/HMI_UI - 2(XIO)			
HMI_UI_PB_12.2	0	BOOL	
HMI_UI_PB_12.2 - MainProgram/Kuka_Robot_Control - 3(XIC)			
HMI_UI_PB_12.4	0	BOOL	

HMI_UI_PB_12 (Continued)
HMI_UI_PB_12.4 - MainProgram/Fanuc_Robot_Control - 4(XIC), 5(XIO), 8(XIO)
HMI_UI_PB_12.4 - MainProgram/Pycomm - 2(XIC)

HMI_UI_PB_12.7	0	BOOL	
HMI_UI_PB_12.7 - MainProgram/Robotics_Control - 1(XIC)			
HMI_UI_PB_12.8	0	BOOL	
HMI_UI_PB_12.8 - MainProgram/HMI_UI - 7(XIC)			
HMI_UI_PB_12.9	0	BOOL	
HMI_UI_PB_12.9 - MainProgram/HMI_UI - 8(XIC)			
HMI_UI_PB_12.10	0	BOOL	
HMI_UI_PB_12.10 - MainProgram/HMI_UI - 9(XIC)			
HMI_UI_PB_12.11	0	BOOL	
HMI_UI_PB_12.11 - MainProgram/HMI_UI - 10(XIC)			
HMI_UI_PB_12.12	0	BOOL	
HMI_UI_PB_12.12 - MainProgram/HMI_UI - 11(XIC), 12(XIO)			
HMI_UI_PB_12.13	0	BOOL	
HMI_UI_PB_12.13 - MainProgram/HMI_UI - 11(XIO), 12(XIC)			

ONS		BOOL[128]	Huber_PLC
Constant	No		
External Access:	Read/Write		
ONS[0]	0	BOOL	
*ONS[0] - MainProgram/HMI_UI - *13(ONS)*			
ONS[1]	0	BOOL	
*ONS[1] - MainProgram/Robotics_Control - *1(ONS)*			
ONS[2]	0	BOOL	
*ONS[2] - MainProgram/Pycomm - *1(ONS)*			

R_Pi_Comm_Check_New	0	SINT	MainProgram
Constant	No		
External Access:	Read/Write		
*R_Pi_Comm_Check_New - MainProgram/Pycomm - *1(MOV), 1(EQU), 1(MOV), 1(NEQ)*			

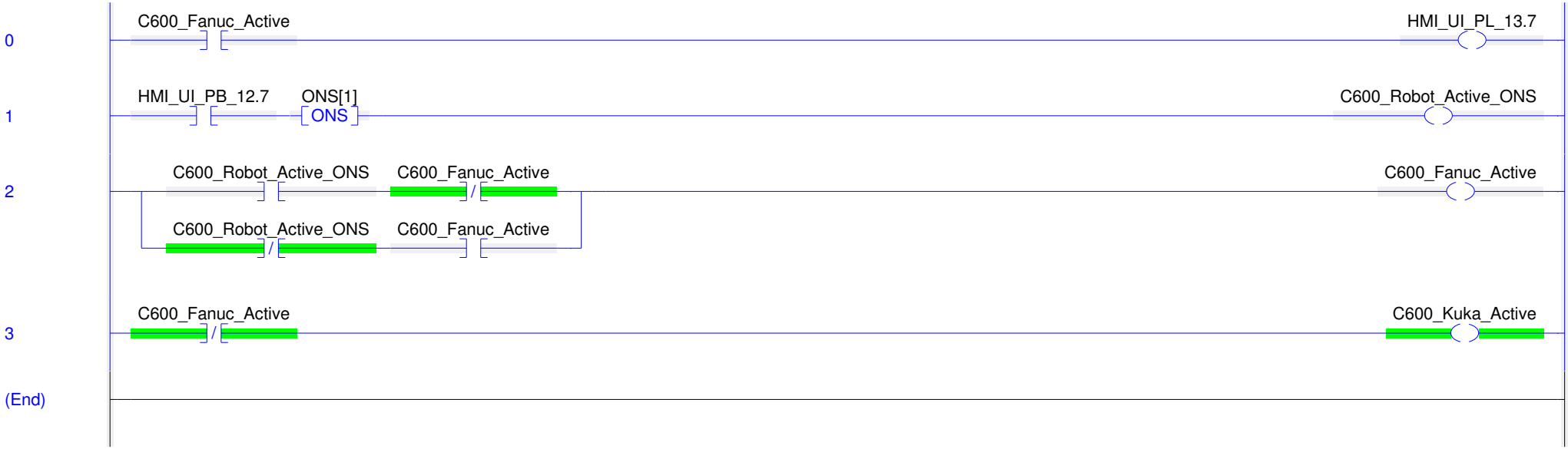
R_Pi_Comm_Check_Old	0	SINT	MainProgram
Constant	No		
External Access:	Read/Write		
*R_Pi_Comm_Check_Old - MainProgram/Pycomm - *1(MOV)*			

R_Pi_Comm_Faulted	0	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		
R_Pi_Comm_Faulted - MainProgram/HMI_UI - 6(XIC)			
*R_Pi_Comm_Faulted - MainProgram/Pycomm - *1(OTL), *2(OTU)*			

R_PI_Rand_Value	0	SINT	MainProgram
Constant	No		
External Access:	Read/Write		
R_PI_Rand_Value - MainProgram/Pycomm - 1(MOV)			

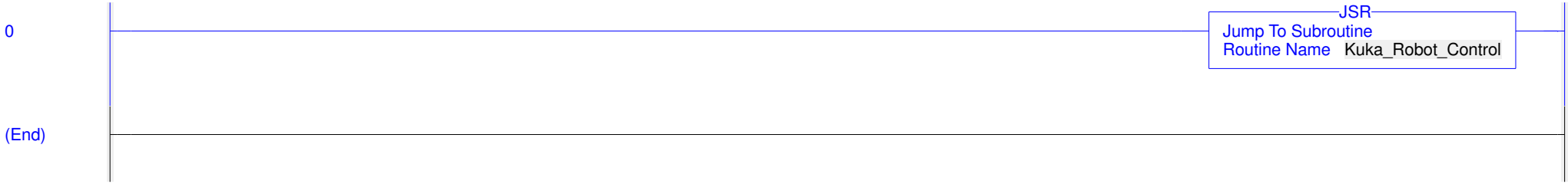
R_PI_User_Head_Angle	-9	INT	Huber_PLC
Constant	No		
External Access:	Read/Write		

R_PI_User_Head_Angle - MainProgram/Fanuc_Robot_Control - 22(MOV)
R_PI_User_Head_Angle - MainProgram/Kuka_Robot_Control - 0(MOV)
R_PI_User_Head_Angle - MainProgram/Pycomm - 0(MOV)

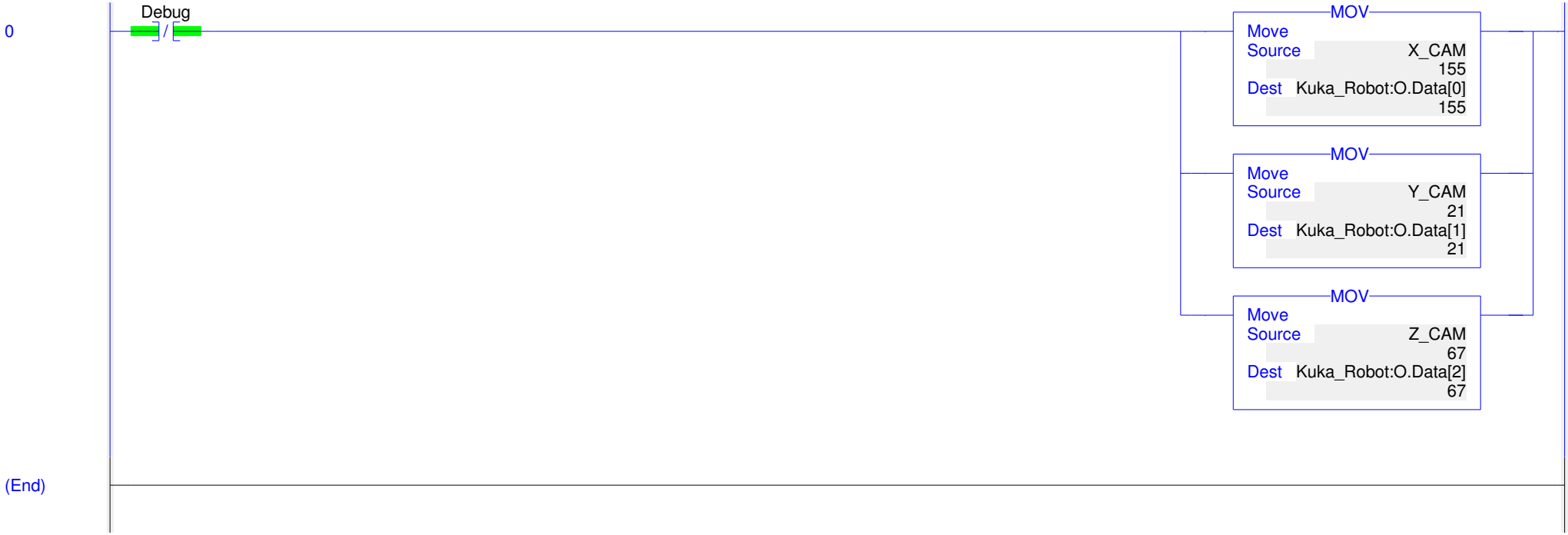

0
C600_Fanuc_Active
HMI_UI_PL_13.7
1
HMI_UI_PB_12.7
ONS[1]
ONS
C600_Robot_Active_ONS
2
C600_Robot_Active_ONS
C600_Fanuc_Active
C600_Fanuc_Active
C600_Robot_Active_ONS
C600_Fanuc_Active
3
C600_Fanuc_Active
C600_Kuka_Active
(End)

Name	Value	Data Type	Scope
C600_Fanuc_Active	0	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		
C600_Fanuc_Active - MainProgram/HMI_UI - 1(XIC), 15(XIC), 4(XIC), 5(XIC)			
*C600_Fanuc_Active - MainProgram/Robotics_Control - *2(OTE), 0(XIC), 2(XIC), 2(XIO), 3(XIO)*			
C600_Kuka_Active	1	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		
C600_Kuka_Active - MainProgram/HMI_UI - 1(XIC), 15(XIC), 4(XIC)			
*C600_Kuka_Active - MainProgram/Robotics_Control - *3(OTE)*			
C600_Robot_Active_ONS	0	BOOL	MainProgram
Constant	No		
External Access:	Read/Write		
*C600_Robot_Active_ONS - MainProgram/Robotics_Control - *1(OTE), 2(XIC), 2(XIO)*			
HMI_UI_PB_12	0	INT	Huber_PLC
Maximum Consumers:	12		
Include Connection Status:	n/a		
Send Data State Change Event to Consumer(s):	No		
Allow Unicast Consumer Connections:	n/a		
Constant	No		
External Access:	Read/Write		
HMI_UI_PB_12.0	0	BOOL	
HMI_UI_PB_12.0 - MainProgram/HMI_UI - 2(XIC)			
HMI_UI_PB_12.1	0	BOOL	
HMI_UI_PB_12.1 - MainProgram/HMI_UI - 2(XIO)			
HMI_UI_PB_12.2	0	BOOL	
HMI_UI_PB_12.2 - MainProgram/Kuka_Robot_Control - 3(XIC)			
HMI_UI_PB_12.4	0	BOOL	
HMI_UI_PB_12.4 - MainProgram/Fanuc_Robot_Control - 4(XIC), 5(XIO), 8(XIO)			
HMI_UI_PB_12.4 - MainProgram/Pycomm - 2(XIC)			
HMI_UI_PB_12.7	0	BOOL	
HMI_UI_PB_12.7 - MainProgram/Robotics_Control - 1(XIC)			
HMI_UI_PB_12.8	0	BOOL	
HMI_UI_PB_12.8 - MainProgram/HMI_UI - 7(XIC)			
HMI_UI_PB_12.9	0	BOOL	
HMI_UI_PB_12.9 - MainProgram/HMI_UI - 8(XIC)			
HMI_UI_PB_12.10	0	BOOL	
HMI_UI_PB_12.10 - MainProgram/HMI_UI - 9(XIC)			
HMI_UI_PB_12.11	0	BOOL	
HMI_UI_PB_12.11 - MainProgram/HMI_UI - 10(XIC)			
HMI_UI_PB_12.12	0	BOOL	
HMI_UI_PB_12.12 - MainProgram/HMI_UI - 11(XIC), 12(XIO)			
HMI_UI_PB_12.13	0	BOOL	
HMI_UI_PB_12.13 - MainProgram/HMI_UI - 11(XIO), 12(XIC)			

HMI_UI_PL_13	6	INT	Huber_PLC
Maximum Consumers:	13		
Include Connection Status:	n/a		
Send Data State Change Event to Consumer(s):	No		
Allow Unicast Consumer Connections:	n/a		
Constant	No		
External Access:	Read/Write		
HMI_UI_PL_13.0	0	BOOL	
*HMI_UI_PL_13.0 - MainProgram/HMI_UI - *2(OTE), 2(XIC), 3(XIO)*			
HMI_UI_PL_13.1	1	BOOL	
*HMI_UI_PL_13.1 - MainProgram/HMI_UI - *3(OTE)*			
HMI_UI_PL_13.2	1	BOOL	
*HMI_UI_PL_13.2 - MainProgram/HMI_UI - *4(OTE)*			
HMI_UI_PL_13.2 - MainProgram/Kuka_Robot_Control - 4(XIC)			
HMI_UI_PL_13.3	0	BOOL	
*HMI_UI_PL_13.3 - MainProgram/HMI_UI - *5(OTE)*			
HMI_UI_PL_13.4	0	BOOL	
*HMI_UI_PL_13.4 - MainProgram/HMI_UI - *6(OTE)*			
HMI_UI_PL_13.7	0	BOOL	
*HMI_UI_PL_13.7 - MainProgram/Robotics_Control - *0(OTE)*			
HMI_UI_PL_13.8	0	BOOL	
*HMI_UI_PL_13.8 - MainProgram/HMI_UI - *7(OTE), 7(XIC)*			
HMI_UI_PL_13.9	0	BOOL	
*HMI_UI_PL_13.9 - MainProgram/HMI_UI - *8(OTE), 8(XIC)*			
HMI_UI_PL_13.10	0	BOOL	
*HMI_UI_PL_13.10 - MainProgram/HMI_UI - *9(OTE), 9(XIC)*			
HMI_UI_PL_13.11	0	BOOL	
*HMI_UI_PL_13.11 - MainProgram/HMI_UI - *10(OTE), 10(XIC)*			
HMI_UI_PL_13.12	0	BOOL	
*HMI_UI_PL_13.12 - MainProgram/HMI_UI - *11(OTE), 11(XIC)*			
HMI_UI_PL_13.13	0	BOOL	
*HMI_UI_PL_13.13 - MainProgram/HMI_UI - *12(OTE), 12(XIC)*			
ONS		BOOL[128]	Huber_PLC
Constant	No		
External Access:	Read/Write		
ONS[0]	0	BOOL	
*ONS[0] - MainProgram/HMI_UI - *13(ONS)*			
ONS[1]	0	BOOL	
*ONS[1] - MainProgram/Robotics_Control - *1(ONS)*			
ONS[2]	0	BOOL	
*ONS[2] - MainProgram/Pycomm - *1(ONS)*			


0
JSR
Jump To Subroutine
Routine Name Kuka_Robot_Control
(End)

Name	Value	Data Type	Scope
No Tags Exist			


0
Debug
MOV
Move
Source X_CAM
155
Dest Kuka_Robot:O.Data[0]
155
MOV
Move
Source Y_CAM
21
Dest Kuka_Robot:O.Data[1]
21
MOV
Move
Source Z_CAM
67
Dest Kuka_Robot:O.Data[2]
67
(End)

Name	Value	Data Type	Scope
Debug	0	BOOL	Research
Constant	No		
External Access:	Read/Write		
Debug - Research/Kuka_Robot_Control - 0(XIO)			
Kuka_Robot:O		_005A:AB767879xx_F_D2EC9ED2:O:0	Huber_PLC
External Access:	Read/Write		
Kuka_Robot:O.Data[0]	155	INT	
*Kuka_Robot:O.Data[0] - Research/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[1]	21	INT	
*Kuka_Robot:O.Data[1] - Research/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[2]	67	INT	
*Kuka_Robot:O.Data[2] - Research/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[3].0	1	BOOL	
*Kuka_Robot:O.Data[3].0 - MainProgram/Kuka_Robot_Control - *1(OTE), 3(XIC), 4(XIO)*			
Kuka_Robot:O.Data[3].1	0	BOOL	
*Kuka_Robot:O.Data[3].1 - MainProgram/Kuka_Robot_Control - *2(OTE)*			
Kuka_Robot:O.Data[4]	500	INT	
*Kuka_Robot:O.Data[4] - MainProgram/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[5]	-9	INT	
*Kuka_Robot:O.Data[5] - MainProgram/Kuka_Robot_Control - *0(MOV)*			
Kuka_Robot:O.Data[6]	500	INT	
*Kuka_Robot:O.Data[6] - MainProgram/Kuka_Robot_Control - *0(MOV)*			
X_CAM	155	INT	Huber_PLC
Constant	No		
External Access:	Read/Write		
X_CAM - Research/Kuka_Robot_Control - 0(MOV)			
Y_CAM	21	INT	Huber_PLC
Constant	No		
External Access:	Read/Write		
Y_CAM - Research/Kuka_Robot_Control - 0(MOV)			
Z_CAM	67	INT	Huber_PLC
Constant	No		
External Access:	Read/Write		
Z_CAM - Research/Kuka_Robot_Control - 0(MOV)			

Data type Name: STRING

Description:

Size: 88 byte(s)

Name	Data Type	Style	Description	External Access
LEN	DINT	Decimal		Read/Write
DATA	SINT[82]	ASCII		Read/Write

CompactLogix5323E-QB1 System : Local Modules

Local: [0] 1769-L23E-QB1 Huber_PLC

Type:	1769-L23E-QB1 CompactLogix5323E-QB1 Controller	Parent:	Controller
Vendor:	Rockwell Automation/Allen-Bradley	Vendor ID:	1
Slot:	0	Electronic Keying:	Exact Match
Revision:	20.14	Status:	Standby
Module Fault:	Offline	Inhibit Flag	Off

Local: 1769-L23E-QB1 Ethernet Port LocalENB

Type:	1769-L23E-QB1 Ethernet Port 10/100 Mbps Ethernet Port on CompactLogix5323E-QB1	Parent:	Controller
Vendor:	Rockwell Automation/Allen-Bradley	Vendor ID:	1
Slot:	1	IP Address or Host Name:	192.168.1.150
Electronic Keying:	Disabled	Revision:	20.11
Status:	Standby	Module Fault:	Offline
Inhibit Flag	Off		

Local: CompactBus Local

Type:	CompactBus 1769 Virtual Backplane Adapter	Parent:	Controller
Vendor:	Rockwell Automation/Allen-Bradley	Vendor ID:	1
Slot:	3	Electronic Keying:	Exact Match
Revision:	20.11	Status:	Standby
Module Fault:	Offline	Inhibit Flag	Off

Ethernet : LocalENB

Path: Local: [1] LocalENB

FANUC Robot/A Cr35iA

Type:	FANUC Robot/A EtherNet/IP Robot	Parent:	LocalENB
Vendor:	FANUC Robotics America	Vendor ID:	356
IP Address or Host Name:	192.168.1.154	Electronic Keying:	Compatible Keying
Revision:	2.1	Status:	Standby
Module Fault:	Offline	Inhibit Flag	On
RPI:	32 ms	Input Type:	Unicast
Input Trigger:	Cyclic	Use Unicast:	n/a

AB76/78/79xx-F Kuka_Robot

Type:	AB76/78/79xx-F ABX EtherNet/IP(TM) Adapter	Parent:	LocalENB
Vendor:	HMS Industrial Networks AB	Vendor ID:	90

IP Address or Host Name:	192.168.1.155	Electronic Keying:	Compatible Keying
Revision:	3.28	Status:	Standby
Module Fault:	Offline	Inhibit Flag	Off
RPI:	10 ms	Input Type:	Unicast
Input Trigger:	Cyclic	Use Unicast:	n/a

Embedded I/O : Local

Path: Local: [3] Local

[1] Embedded IQ16F Discrete_Inputs

Type:	Embedded IQ16F 16 Point 24V DC High Speed Input	Parent:	Local
Vendor:	Rockwell Automation/Allen-Bradley	Vendor ID:	1
Slot:	1	Electronic Keying:	Compatible Keying
Revision:	3.1	Status:	Standby
Module Fault:	Offline	Inhibit Flag	Off
RPI:	20 ms	Use Unicast:	n/a

Module Defined Configuration Tag	Value	Data Type
Local:1:C		AB:Embedded_IQ16F:C:0
.FilterGroup0	2#0010_0010	SINT
.Filter0OffOn_0	0	BOOL
.Filter0OffOn_1	1	BOOL
.Filter0OffOn_2	0	BOOL
.Filter0OffOn_3	0	BOOL
.Filter0OnOff_4	0	BOOL
.Filter0OnOff_5	1	BOOL
.Filter0OnOff_6	0	BOOL
.Filter0OnOff_7	0	BOOL
.FilterGroup1	2#0010_0010	SINT
.Filter1OffOn_0	0	BOOL
.Filter1OffOn_1	1	BOOL
.Filter1OffOn_2	0	BOOL
.Filter1OffOn_3	0	BOOL
.Filter1OnOff_4	0	BOOL
.Filter1OnOff_5	1	BOOL
.Filter1OnOff_6	0	BOOL
.Filter1OnOff_7	0	BOOL

[2] Embedded OB16 Discrete_Outputs

Type:	Embedded OB16 16 Point 24V DC Output, Source	Parent:	Local
Vendor:	Rockwell Automation/Allen-Bradley	Vendor ID:	1
Slot:	2	Electronic Keying:	Compatible Keying
Revision:	3.1	Status:	Standby

Module Fault:	Offline	Inhibit Flag	Off
RPI:	20 ms	Use Unicast:	n/a

Module Defined Configuration Tag	Value	Data Type
Local:2:C		AB:Embedded_OB16:C:0
.Config	2#0000_0000_0000_0000	INT
.ProgToFaultEn	0	BOOL
.ProgMode	2#0000_0000_0000_0000	INT
.ProgValue	2#0000_0000_0000_0000	INT
.FaultMode	2#0000_0000_0000_0000	INT
.FaultValue	2#0000_0000_0000_0000	INT