Totally Integrated Automation Portal		
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Change Velocity of Robot [FC7]

Change Velocity of Robot Properties							
General							
Name	Change Velocity of Robot	Number	7	Туре	FC		
Language	LAD	Numbering	Automatic				
Information							
Title		Author		Comment			
Family		Version	0.1	User-defined ID			

Name	Data type	Default value	Comment
Input			
Output			
InOut			
Temp			
Constant			
▼ Return			
Change Velocity of Robot	Void		

Network 1:

Network 2:

Network 3:

```
*M3.0
"state9"

EN ENO

-70.0 IN *MD264

MOVE

EN OUT1 — "zdot"
```

Network 4:

Totally Integrated Automation Portal **M3.5 *state11" MOVE EN ENO *MD264 **OUT1 "zdot"

Network 5:

```
%M1.3
                                                                                                  %M0.5
                       "automatic or
manual(on)"
                                                                                            "position control
or velocity (on)"
   %M2.2
   "state4"
                                                                                                  ( )-
     %M2.4
   "state6"
     4 F
    %M3.0
   "state9"
   %M3.5
  "state11"
     4 F
                           %M9.0
   %M1.3
                      "position control
"automatic or
manual(on)"
                      or velocity (on)
manual"
```

Network 6:

```
%M1.3
                            %M0.5
                                                     %M1.1
                                               "velocity control on"
                                                                                                               CALCULATE
"automatic or
                       "position control
                                                                                                                                     Real
manual(on)"
                       or velocity (on)"
                              4 F
      ENO
                                                                                                   \mathsf{OUT} := \ (\mathsf{SIN}(\mathsf{IN1} + \mathsf{IN2}) / (\mathsf{IN3} * \mathsf{SI}...
    %M1.3
                            %M0.5
                      "position control
or velocity (on)"
"automatic or
manual(on)"
                                                                                                                                               %MD252
                                                                                  %MD272
                                                                                                                                              - "theta2dot"
                                                                            "actual theta 2
radian"
                                                                                                                                     OUT
                                                                                                 IN1
                                                                                  %MD276
                                                                            "actual theta 3
                                                                                    radian"
                                                                                                 IN2
                                                                                  %MD136
                                                                                        "a3"
                                                                                                 IN3
                                                                                  %MD264
                                                                                      "zdot" -
                                                                                                - IN4 😃
```

Network 7:

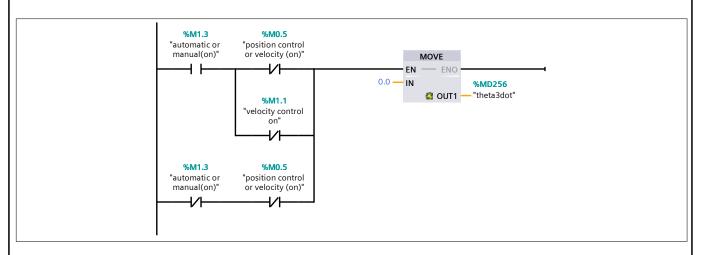
Totally Integrated Automation Portal

```
%M1.3
                       %M0.5
                                           %M1.1
                                      "velocity control on"
"automatic or
manual(on)"
                                                                                          CALCULATE
                  "position control
                                                                                                            or velocity (on)"
                                                                                             Real
                        1 F
                                                                                                            ENO
                                                                                OUT := (IN6-IN4*SIN(IN1+IN2...
                       %M0.5
   %M1.3
"automatic or
                  "position control
                                                                                                                    %MD256
                                                                  %MD272
manual(on)"
                  or velocity (on)"
                                                                                                                   - "theta3dot"
                                                             "actual theta 2
                        -| |-
                                                                    radian" -
                                                                               IN1
                                                                   %MD276
                                                             "actual theta 3
                                                                               IN2
                                                                   %MD136
                                                                       "a3"
                                                                               IN3
                                                                   %MD140
                                                                       "a4"
                                                                               IN4
                                                                  %MD264
                                                                      "zdot" -
                                                                               IN5
                                                                        0.0 — IN6 🏥
```

Network 8:

```
%M1.3
                         %M0.5
                    "position control
or velocity (on)"
"automatic or
manual(on)"
                                                                     MOVE
     1 F
                                                                 EN ·
                                                                         - ENO
                                                         0.0 — IN
                                                                                    %MD252
                                                                                   - "theta2dot"
                                                                      😃 OUT1 -
                         %M1.1
                    "velocity control on"
   %M1.3
                         %M0.5
"automatic or
                    "position control
manual(on)"
                    or velocity (on)"
```

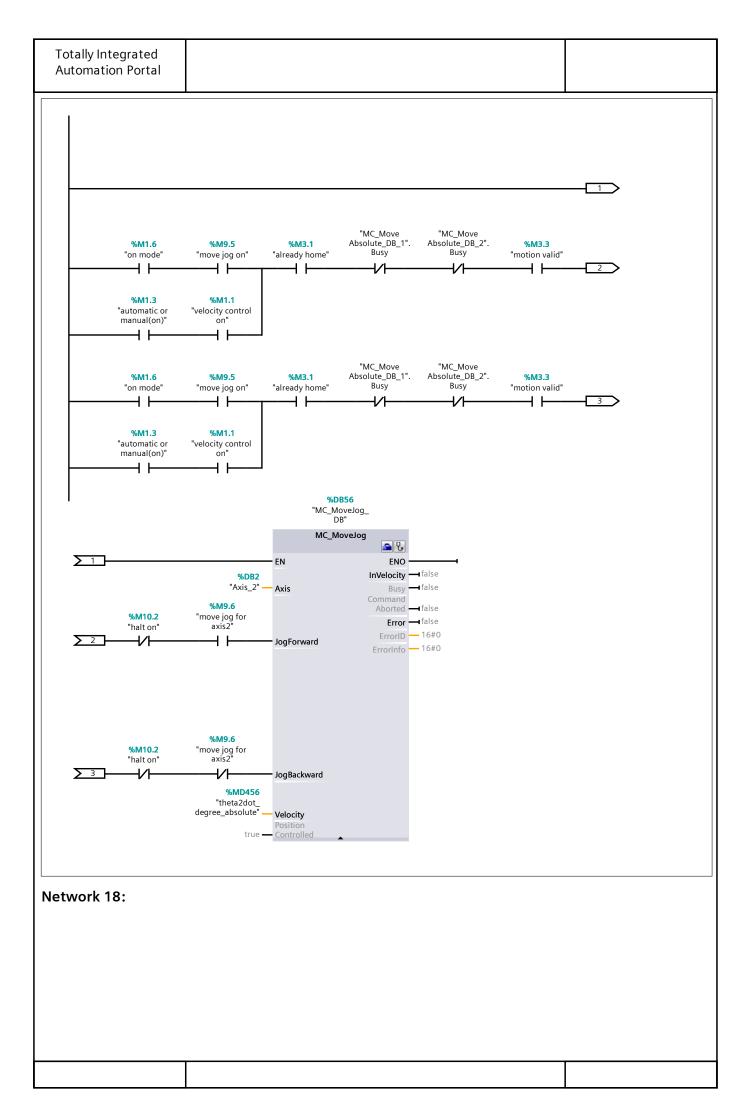
Network 9:

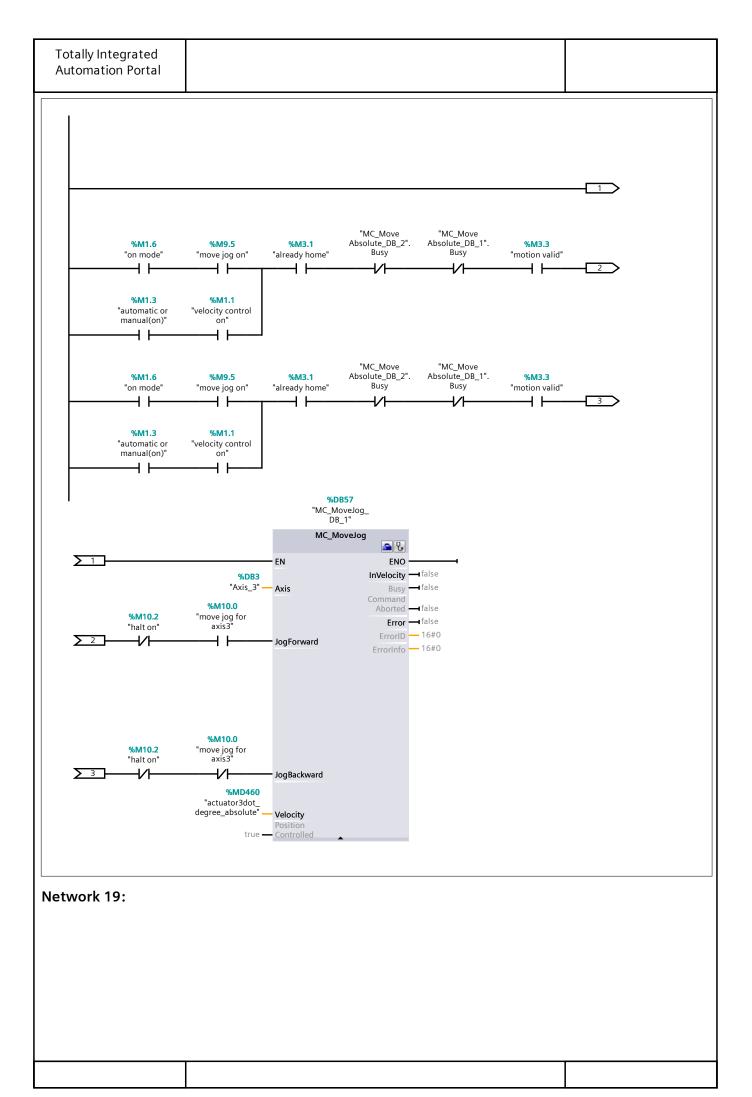


Network 10:

Totally Integrated **Automation Portal** ADD Auto (Real) EN -- ENO %MD252 %MD268 "theta2dot" -IN1 OUT — "actuator3dot" %MD256 "theta3dot" — IN2 😃 Network 11: MUL Auto (Real) EN - ENO %MD252 %MD280 57.29578 N2 OUT "theta2dot degree" "theta2dot" — IN1 Network 12: MUL Auto (Real) EN - ENO %MD268 %MD284 "actuator3dot" — IN1 "actuator3dot 57.29578 — IN2 🐫 OUT — degree" Network 13: ABS Real EN - ENO %MD280 %MD456 "theta2dot "theta2dot_ OUT — degree_absolute" degree" — IN Network 14: ABS Real EN -- ENO %MD284 %MD460 ator3dot "actuator3dot_ degree" — IN OUT — degree_absolute" "actuator3dot Network 15:

```
Totally Integrated
   Automation Portal
                                              %MD280
"theta2dot
degree"
                                                                                                                                         %M9.6
"move jog for axis2"
                                                 >=
Real
                                                                                                                                              <del>(</del> )-
                                                   0.0
Network 16:
                                            %MD284
"actuator3dot degree"
                                                                                                                                         %M10.0
"move jog for axis3"
                                                >=
Real
                                                                                                                                              <del>(</del> )-
                                                  0.0
Network 17:
```





Totally Integrated Automation Portal				
	%M0.5 "position control or velocity (on)"	%M0.2 "execute absolute position"	%M9.5 "move jog on"	-1