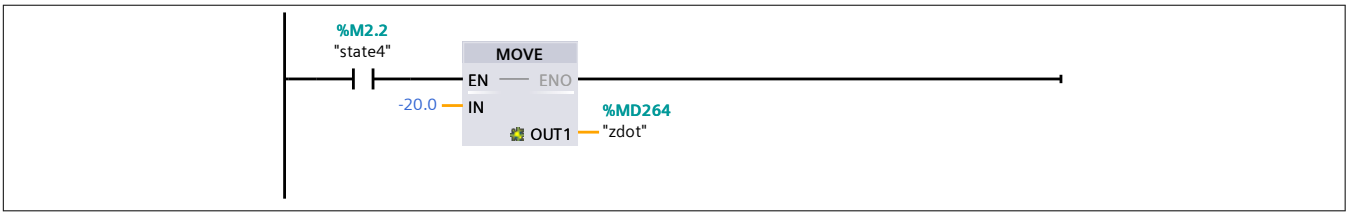
Change Velocity of Robot [FC7]

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

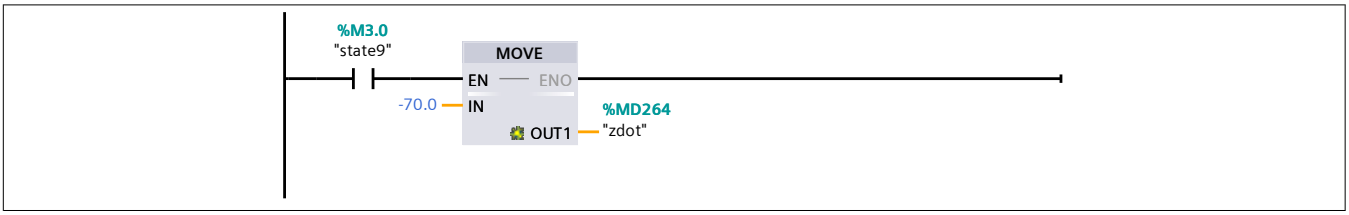
Name	Data type	Default value	Comment
Input			
Output			
InOut			
Temp			
Constant			
▼ Return			
Change Velocity of Robot	Void		

Network 1:

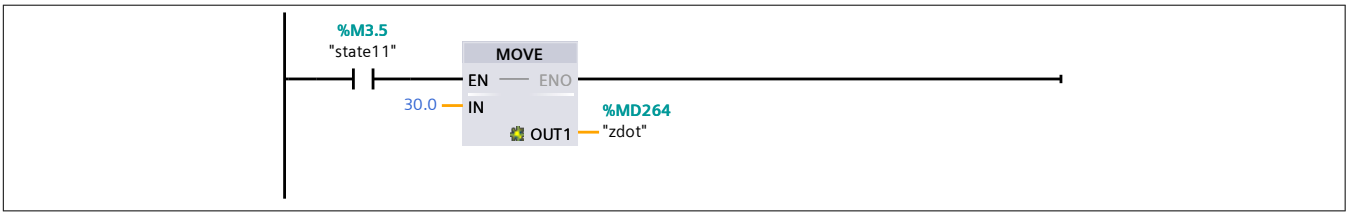


Network 2:

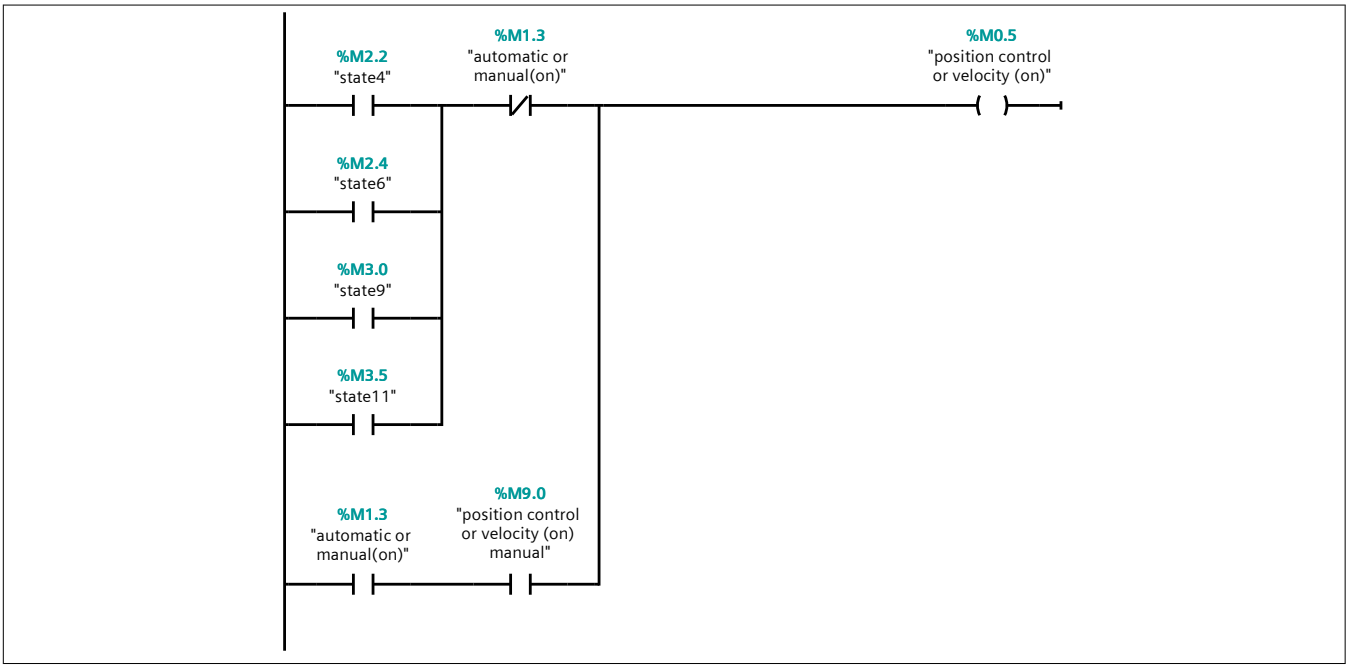
Network 3:



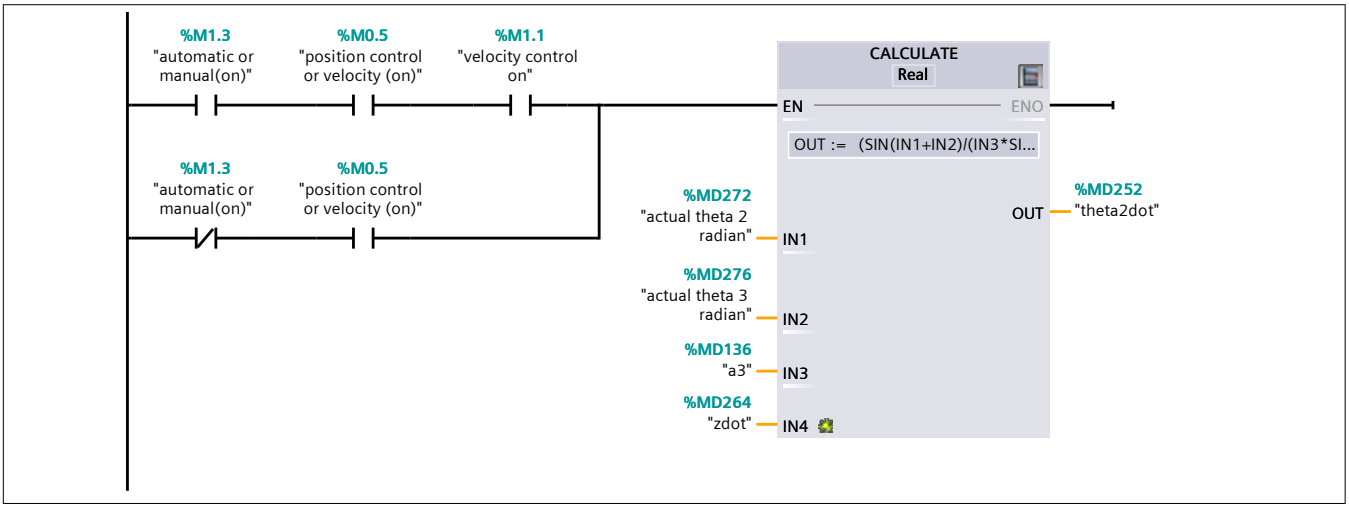
Network 4:



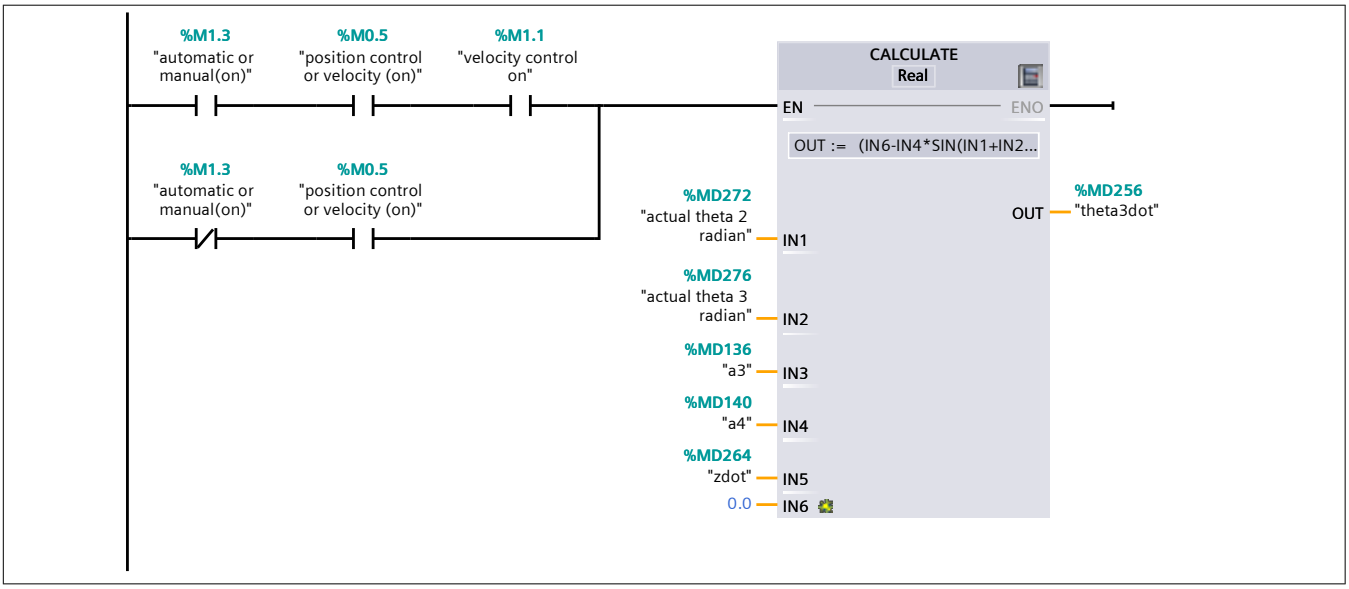
Network 5:



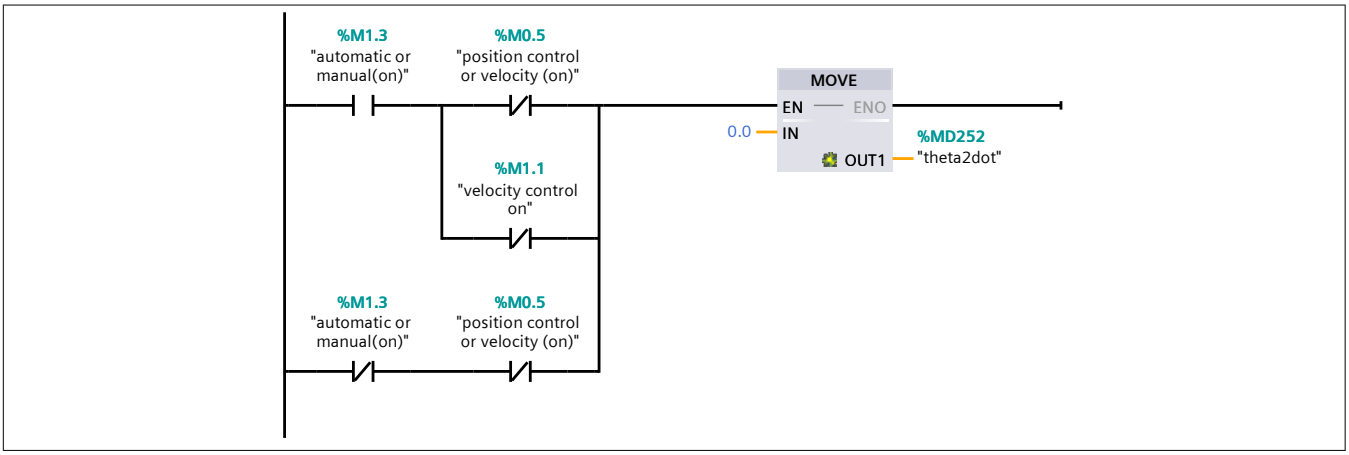
Network 6:



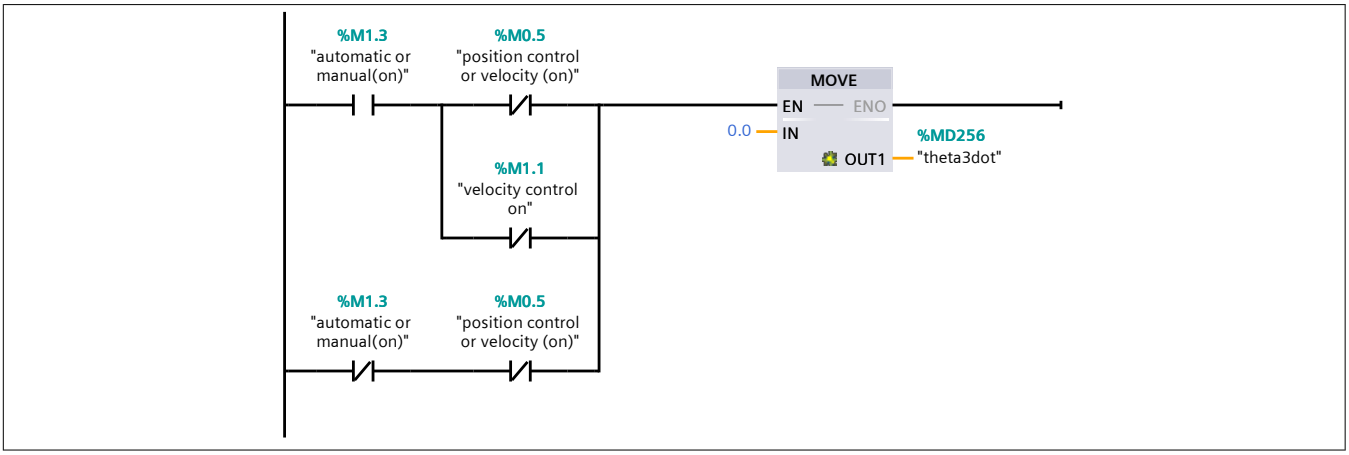
Network 7:



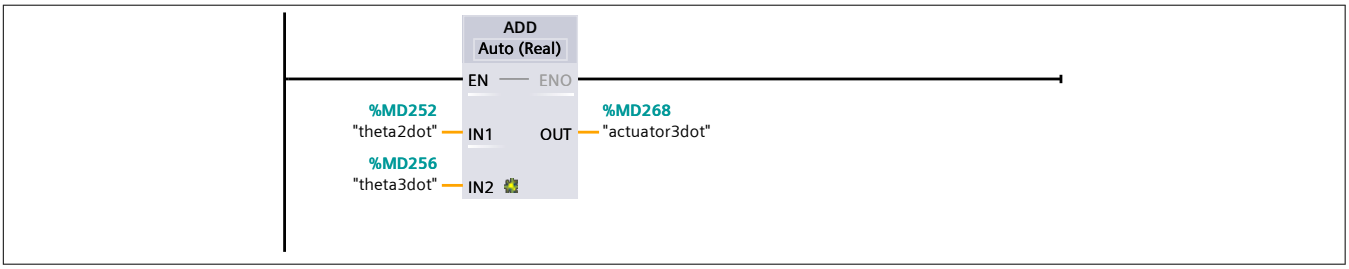
Network 8:



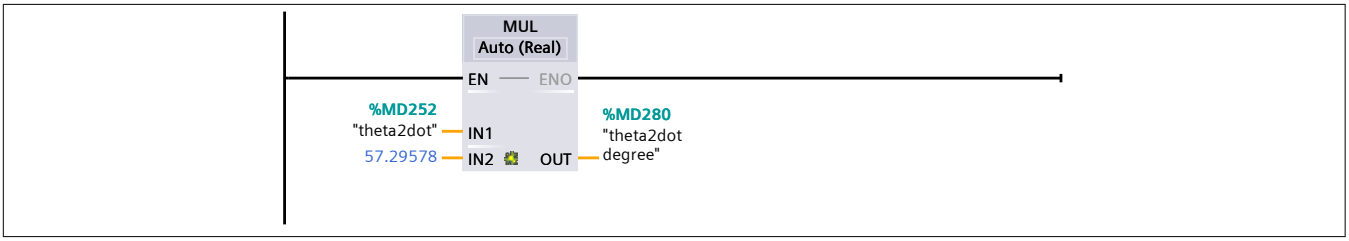
Network 9:



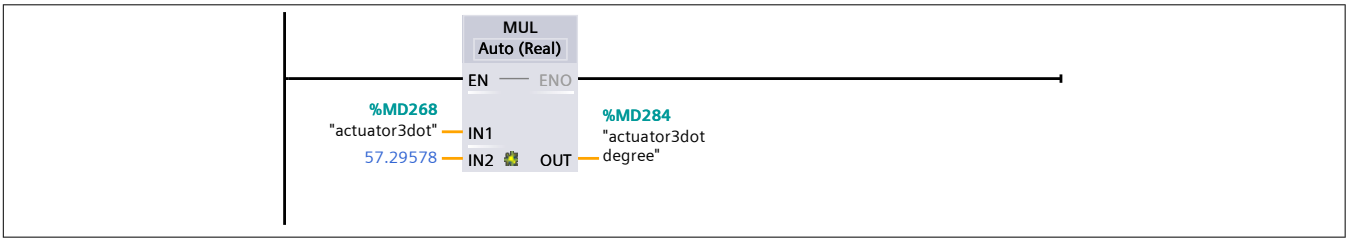
Network 10:



Network 11:



Network 12:



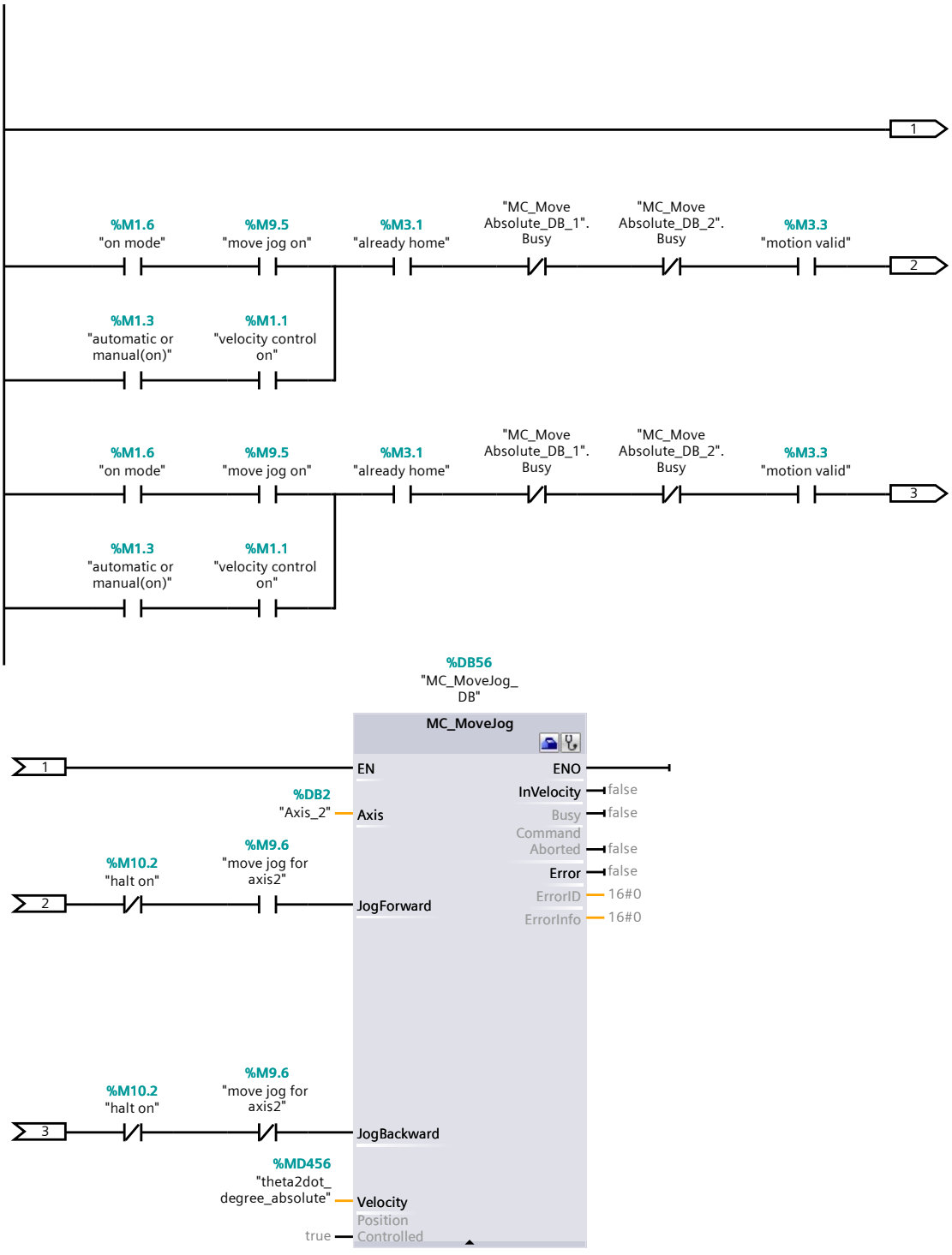
Network 13:

Network 14:

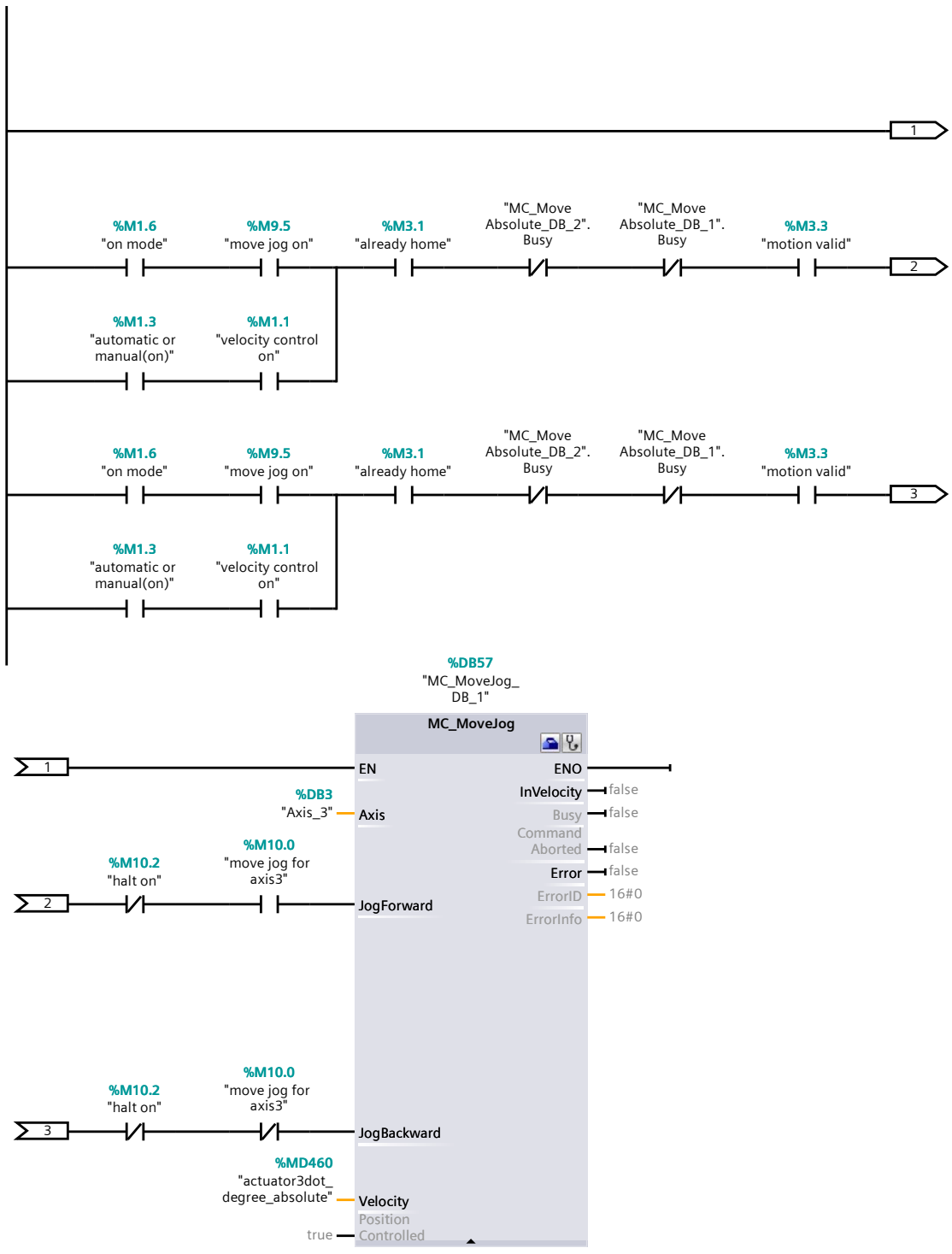
Network 15:

Network 16:

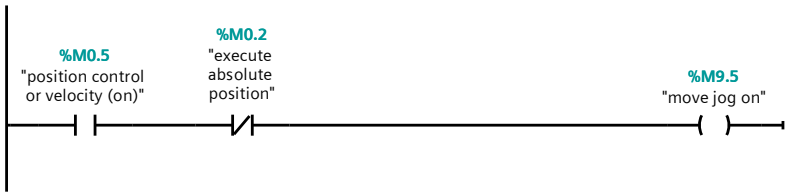
Network 17:


1
%M1.6
"on mode"
%M9.5
"move jog on"
%M3.1
"already home"
"MC_Move Absolute_DB_1". Busy
"MC_Move Absolute_DB_2". Busy
%M3.3
"motion valid"
2
%M1.3
"automatic or manual(on)"
%M1.1
"velocity control on"
%M1.6
"on mode"
%M9.5
"move jog on"
%M3.1
"already home"
"MC_Move Absolute_DB_1". Busy
"MC_Move Absolute_DB_2". Busy
%M3.3
"motion valid"
3
%M1.3
"automatic or manual(on)"
%M1.1
"velocity control on"
%DB56
"MC_MoveJog_ DB"
MC_MoveJog
1
EN
ENO
%DB2
"Axis_2"
Axis
InVelocity
false
Busy
false
Command Aborted
false
Error
false
ErrorID
16#0
ErrorInfo
16#0
%M9.6
"move jog for axis2"
%M10.2
"halt on"
2
JogForward
%M9.6
"move jog for axis2"
%M10.2
"halt on"
3
JogBackward
%MD456
"theta2dot_ degree_absolute"
Velocity
Position Controlled
true

Network 18:


1
%M1.6
"on mode"
%M9.5
"move jog on"
%M3.1
"already home"
"MC_Move Absolute_DB_2". Busy
"MC_Move Absolute_DB_1". Busy
%M3.3
"motion valid"
2
%M1.3
"automatic or manual(on)"
%M1.1
"velocity control on"
%M1.6
"on mode"
%M9.5
"move jog on"
%M3.1
"already home"
"MC_Move Absolute_DB_2". Busy
"MC_Move Absolute_DB_1". Busy
%M3.3
"motion valid"
3
%M1.3
"automatic or manual(on)"
%M1.1
"velocity control on"
%DB57
"MC_MoveJog_ DB_1"
MC_MoveJog
1
EN
ENO
%DB3
"Axis_3"
Axis
InVelocity
false
Busy
false
Command Aborted
false
Error
false
ErrorID
16#0
ErrorInfo
16#0
%M10.2
"halt on"
%M10.0
"move jog for axis3"
2
JogForward
%M10.2
"halt on"
%M10.0
"move jog for axis3"
3
JogBackward
%MD460
"actuator3dot_ degree_absolute"
Velocity
true
Position Controlled

Network 19:


%M0.5
"position control or velocity (on)"
%M0.2
"execute absolute position"
%M9.5
"move jog on"