

A VCA Protocol Based Multi-level Flexible Architecture on Embedded PLCs for Visual Servo Control

Abstract—The visual system, motion control system, and programmable logic controller (PLC) system are becoming increasingly inseparable and complex, however there are few works researching the integration of these three systems to ease the complexity. Most of them are focusing on their applications individually. We propose a flexible multi-level architecture which is based on a VCA protocol to address the integration problem. The multi-level includes flexible layer, control layer, and algorithm layer. The flexible layer is adopted to seamlessly integrate visual system and embedded PLC (ePLC) system. The VCA protocol is designed for data interaction between the layers. Correspondingly, a customized hardware, memory allocation, Petri-Net based multithreading structure are described to support the proposed flexible architecture. At last, we implement two cases using the proposed VCA protocol based flexible architecture in which the generality of the proposed flexible architecture is verified. In first case, the winding machine with visual system implements regular winding effect by the correction of θ . In the second case, the binocular catching robot uses the cameras to track the trajectory and send to ePLC. By adjusting the speed and position, the robot can catch the ball successfully.

Index Terms—motion control, visual servo control, embedded PLC, multi-level architecture, Petri Net

I. INTRODUCTION

Integration technologies are driving the industrial automation [1]. The continuously integrations of sensors, controllers, robots, tools, etc., bring the concepts of self-aware equipment, intelligent factory, CPS, etc. [2], [3]. Recent researches [4]–[6] introduce the development of integration technologies. In industrial automation, PLC system, motion control system, and visual system become more and more important and inseparable [7]–[9]. In addition, the advances of edge computing, fog computing, and edge artificial intelligence [10]–[12] put forward new challenges on edge equipment of these systems.

A. Motivations

Recently, advances in image processing and pattern recognition contribute to the thriving of visual system which has been applied in various fields. By extracting features from the image, the visual system could obtain parameters to replace human visual system to address lots of tasks; specially, the ever-growing requirements in industrial scenarios; e.g., works that should be finished in dangerous environment, tasks that human vision is difficult to satisfy, or applications in some large scale industrial production that numerous visual systems are needed.

After the visual processing, in most cases, the motion control system as the power of automation is constantly needed

to drive some actuators to finished some severe tasks, which remarkably benefits the replacement of labor force.

Furthermore, PLCs have become a base of automation owing to its high reliability and easy programming [13]. Lots of researches are focusing on it to extremely extend its applied field; for instance, [14], [15] guarantee the reliability by verifying the program of PLCs, [16], [17] improve the performance of PLCs using advanced algorithms, [18] alleviates the development complexity of PLCs with a special software structure, [19] pose methods to update PLC programs dynamically.

In addition, the visual system, motion control system, and PLC system are becoming increasingly inseparable. [20] is a typical case that describes how the three parts collaborate. The visual system analyzes the context and get error put into the motion control system. Simultaneously the PLC is analyzing the information, such as the position limitation of every axis, to make some logical judgments accordingly. Regarding the normal development of these applications, the three systems are developed individually and using the communication protocol combines them. However, this method should be always redesigned the programs in these systems because of the difference of visual algorithms, motion control algorithms and their organized logic programs. In addition, the logic and motion control are always mixed together to develop in motion-control-supported PLC, and there are also lots of communication protocols (e.g., EtherCat, Modbus, CAN, etc.). Considering the high requirements of today's applications, this becomes a cumbersome task.

Hence, how to pose a flexible structure to the integration of visual system, motion control system, and PLC system which will ease the complexity and satisfy the ever-growing requirements attracts our interest.

B. Related Works

Visual control system is combined of special motion control system and visual system which has been applied in various fields, such as transport [21], circuit detection [22], sorting system, welding [20], assembling [23], [24], robot [25], [26], unmanned aerial vehicles [27], [28], and sorting [29]. These works address their problems in relevant fields. However, all these solutions are based on special motion control system and visual system.

Additionally, the integration of logic control and motion control has variously deep researches [30]–[33]. [30], [33] realize the motion control directly in PLC. [34]–[36] use motion control module collaborated with PLC to implement

their applications. However, owing to the confusion of the development method in these works, PLCopen organization released a related standard [37] which standardizes the motion control in PLC. Based on this standardization, [38] provides an advanced implementation in distributed automation system, and companies, such as 3S [39], provide some tools for users. [18] also poses a customized real-time compilation method to reduce the development complexity.

Above works provide impressive integrations on visual servo control system and PLC with motion control functions, however there are few works researching the integration of visual system, motion control, and PLC. Most of applications are focusing on their applications with three individual systems, such as [20]. Hence, an integration structure of PLC system, motion control system, and visual system should be provided to reduce the complexity and expand the application fields.

C. Our Contributions

We propose a flexible multi-level architecture which is based on a *VCA* protocol to address the problem of integration of PLC system, motion control system, and visual system. The multi-level includes flexible layer, control layer, and algorithm layer. The *VCA* protocol is designed for data interaction between the layers. Correspondingly, customized hardware, memory allocation, and Petri-Net based multithreading structure are described to support the proposed flexible software architecture.

In the remaining paper, in Section II, the hardware and software structure and memory allocation are introduced. In Section III, the mechanism of *VCA* protocol is addressed in detail. In Section IV, we illustrate the execution process of the proposed system. Then, we implement two cases which are binocular catching robot and winding machine with visual system in Section V. In the last section, we conclude our works.

II. SYSTEM ARCHITECTURE

A. Hardware Structure

The hardware is comprised of ePLC system (*ES*) and visual system (*VS*). The *ES* is a customized structure. The number of digital input/output, analog input/output and controlled servo system could be increased according to requirements. Fig. 1 shows a typical *ES* which adopts two processor architecture. The shared memory is used to interact data between master and slave processor. The *VS* normally contains one or more cameras, and a CPU for visual tasks. The communication between *ES* and *VS* could adopt multiple protocols, such as TCP, modbus, and CAN.

B. Software Structure

The software of the proposed multi-level flexible structure is shown as in Fig. 2. To our best knowledge, the *VS* commonly contains several visual algorithms and every algorithm could extract some required parameters from pictures or videos. Meanwhile, the *ES* is comprised of modules which conclude logic part and algorithms. The algorithms here mainly donate

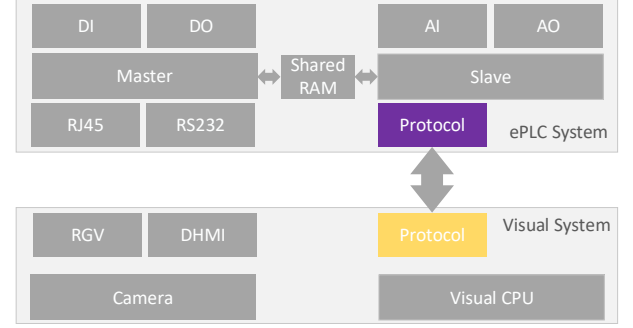


Fig. 1. Hardware architecture of typical *ES* and *VS*. The *ES* adopts two processor architecture and the *VS* contains one camera and a CUP. The communication between *ES* and *VS* adopt the CAN Bus.

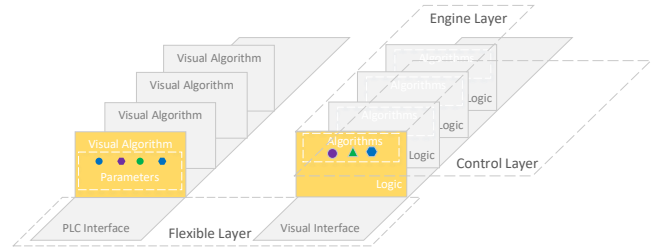


Fig. 2. Multi-level flexible architecture contains three layers: flexible layer, control layer and algorithm layer.

motion control algorithms. The structure contains three layers: flexible layer (*FL*), control layer (*CL*), and algorithm layer (*AL*).

Flexible layer: these layer is responsible for joint the *VS* and *ES*, which consists of *PLC* interface and visual interface. The parameters are framed with *VCA* protocol frame (henceforth, *VCA* protocol frame is abbreviated form of *PF*) interacted between *VS* and *ES*. Furthermore, a special protocol template (*PT*) is saved in both systems to illustrate the protocol.

Control layer: this is independent form algorithm layer to cope with the logic tasks. This make it possible to run the logic task and algorithm task in different processors.

Algorithm layer: it is mainly comprised of various types of algorithms. The independent algorithm layer makes the algorithms with high performance requirement that could be built in individual processors.

C. Memory Allocation

The dedicated storage area of *PLC* in memory is made up of bit data area (*M* area) and byte data area (*D* area). Meanwhile, we regard *M* area and *D* area as set *M* of bit and set *D* of byte. Henceforth, if \exists set *S*, we define its subscripted lowercase letter s_i as an element of *S* and the subscripted *i* is used to distinguish the elements. Fig. 3 shows the memory allocation of master processor, shared RAM and slave processor. The shared *RAM* is a special structure to fast

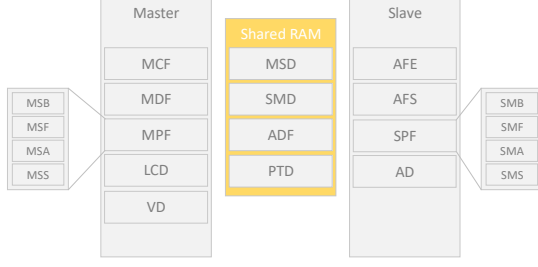


Fig. 3. Memory allocation of master processor, shared ram and slave processor.

data interaction between master and slave processors. In more general cases, the *MSD* is located in master processor, the *SMD* and *ADF* are located in slave processor and the *PT* is in both master and slave processors.

In master processor, its RAM contains the special areas: 1) Module control flag area (*MCF*) are used to start the modules. 2) Master processor data interaction flag area (*MPF*) contains begin data transfer flag from master to slave (*MSB*), transfer state of master from master to slave (*MSF*), acknowledge flag of master from master to slave (*MSA*), and transfer state of master from slave to master (*MSS*). 3) Module data saved flag area (*MDF*) denotes whether the module data are saved. 4) Logic control data area (*LCD*) are used to store the control frame. Every element lcd_i is associated with a specified module. 5) *VCA* protocol frame data area (*VD*) stores all the frames received from the *VS*.

In shared RAM, it could be read by both of master and slave processors and consists of the special areas: 1) Master processor data interaction data area (*MSD*) stores the data delivered from slave processors. 2) Slave processor data interaction data area (*SMD*) stores the data delivered from master processor. 3) Algorithm data saved flag area (*ADF*) denotes whether the algorithm data are saved. 4) Protocol template data area (*PTD*) stores the protocol template which contains *PTs* from *VS* to *ES* and from *ES* to *VS*.

In slave processor, the RAM is comprised of the special areas: 1) Algorithm flag area (*AF*) includes algorithm flag of execution (*AFE*) and algorithm flag of state (*AFS*). 2) Slave processor data interaction flag area (*SPF*) includes the begin data transfer flag from slave to master (*SMB*), transfer state of slave from slave to master (*SMF*), acknowledge flag of slave from slave to master (*SMA*), and transfer state of slave from master to slave (*SMS*). 3) Algorithm data area (*AD*) saves data which help specified algorithm executing.

We define the \mathcal{I} to interact data between master processor and slave processor. It contains two parts: transferring data from master to slave (\mathcal{I}_{mts}) and transferring data from slave to master (\mathcal{I}_{stm}), which is defined below:

$$\begin{cases} \mathcal{I}_{mts} = \mathcal{L}(msb_i, msf_i, sma_i, sms_i, smd_i) \\ \mathcal{I}_{stm} = \mathcal{L}(smb_i, smf_i, msa_i, mss_i, msd_i) \end{cases} \quad (1)$$

Where \mathcal{L} is the function to implement the process of data interaction between master and slave processors. \mathcal{I}_{mts} and \mathcal{I}_{stm} use the same function \mathcal{L} . The process of \mathcal{I}_{mts} is

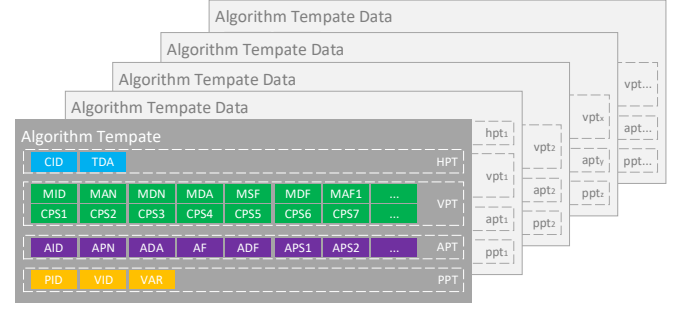


Fig. 4. A *PT* uniquely corresponds to a type of application. It contains four parts: head of protocol template, visual layer template, control layer template and algorithm layer template.

described as follows: the master processor sets msb_i one, sets msf_i one, sends data to smd_i , recovers msb_i to zero, and informs slave processor to get the data; the slave processor sets sms_i one, checks the data of smd_i , sets sma_i one, feeds back the master processor to end the transferring, recovers sms_i zero, and recovers sma_i zero; at last, the master processor recovers msf_i zero.

III. INTEGRATION OF *VS* AND *ES*

A. *VCA PT*

In cater to most applications, we propose a *VCA* protocol based multi-level flexible architecture. As shown in Fig. 4, a protocol template (*PT*) is adopted to support various types of implementations and a *PT* uniquely corresponds to a type of application. In the flexible architecture, users only need to redesign and reload the *PT* and then they can reuse the visual servo system again. The *PT* could be loaded into a stationary address of visual system and *ePLC* system. After restarting both systems, it will be put into a fixed area of *RAM*. The parsing modules from both systems will read it when parsing the *PF*. The *VCA* protocol could be used to bidirectionally transfer *PF* using the same *PT* and algorithms of framing and deframing.

The *PT* is defined below:

$$\begin{cases} PT = \{HPT, VPT, APT, PPT\} \\ HPT = \{CID, TDA\} \\ VPT = \{MID, MAN, MDN, MDA, MSF, MDF, \\ \quad \bigcup_{x=1}^i MAF_x, \bigcup_{x=1}^j CPS_x\} \\ APT = \{AID, APN, ADA, AF, ADF, \bigcup_{y=1}^i APS_y\} \\ PPT = \{PID, VID, VAR\} \end{cases} \quad (2)$$

The *PT* contains four parts: head of protocol template (*HPT*), *VCA* protocol template (*VPT*), algorithm protocol template (*APT*) and parameter protocol template (*PPT*). Every part explains as follows:

- 1) *HPT*: this part includes communication unique ID (*CID*), template data storage address (*TDA*). Every *PT* only has one *HPT*.

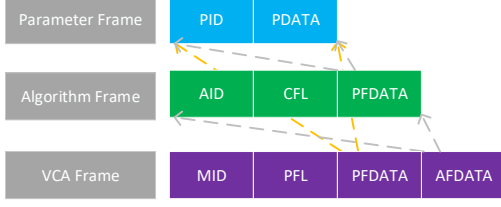


Fig. 5. VCA protocol frame contains parameter frames and algorithm frames in its data field and the algorithm protocol frame contains several parameter frames.

- 2) *VPT*: it consists of module unique ID (*MID*), module contained algorithm number (*MAN*), module contained data number (*MDN*), module data start address (*MDA*), module start flag (*MSF*), module data saved flag (*MDF*), module contained algorithm IDs (*MAS_x*). *VLT* is not \emptyset . Every *VPT* includes *MAN* algorithm IDs.
- 3) *APT*: it is comprised of algorithm unique ID (*AID*), algorithm contained parameter number (*APN*), algorithm data start address (*ADA*), algorithm data saved flag (*ADF*), algorithm contained parameter IDs (*APS_y*). *CLT* is not \emptyset . Every *APT* includes *APN* parameter IDs.
- 4) *PPT*: it contains parameter unique ID (*PID*), its relevant visual algorithm ID (*VID*) and the conversion ratio of visual algorithm parameters and motion algorithm parameters (*VAR*).

B. VCA PF

The *VCA* protocol frame (*PF*) contains parameter frames and algorithm frames in its data field and the algorithm protocol frame contains several parameter frames as shown in 5.

- 1) *PF*: it consists items of *MID*, visual frame length (*VFL*), data from parameter frames (*PFDATA*) and data from algorithm frames (*AFDATA*). The *PFDATA* and *AFDATA* contains several parameter frames and control frames, respectively. The *MIDs* both in *PT* and *PF* need one-to-one correspondence.
- 2) Algorithm frame: it is comprised of *AID*, control frame length (*CFL*) and *PFDATA*. The *AIDs* both in algorithm frame and *PF* need one-to-one correspondence.
- 3) Parameter frame: it contains *PID*, *PDATA*. *PID* is also the address of *PDATA*. The *PIDs* both in parameter frame and *PF* need one-to-one correspondence.

C. Framing of PF

The framing contains three steps: *VCA* framing, *CL* framing, and *AL* framing. Transfer data area (*TD*) saves the data to be transferred and it is indexed by the *PID*. In the *VS*, it represents the parameters obtained from the visual algorithms. In the *ES*, the data come from the *RAM*.

VCA Framing: the process is realized as the Algorithm 1. It searches the *PT* with *mid* to find the relevant *vlt_x*. Through it, we can obtain the *man* and *mdn*. According to *man* and *mdn*, the Algorithm 3 and Algorithm 2 are called to gain the *pfdata* and *afdata*. Then, it is finished after calculating the length (*vfl*).

CL Framing: Algorithm 2 illustrates the process. It seeks the *PT* to gain the *alt_y* which contains the *apn*. According to *apn*, call the Algorithm 3 to obtain the *pfdata* and then calculate the length (*cfl*) to finish the *AL* framing.

P Framing: Algorithm 3 shows the process. The *VS* obtains the *alt_z* from *FT* and then combines the *pid* and *pdata*.

Algorithm 1: VCAFraming

Input: *mid*, *TD*
Output: *PF*
 SearchPT (*mid*, *vpt_x*);
 $PF.mid \leftarrow mid$;
for $i = 0; i < vpt_x.mdn; i++$ **do**
 | ALFraming (*vpt_x.cps[i]*, *TD*, *pfdata*);
end
for $i = 0; i < vpt_x.man; i++$ **do**
 | CLFraming (*vpt_x.mas[i]*, *TD*, *afdata*);
end
 $PF.pfdata \leftarrow pfdata$;
 $PF.afdata \leftarrow afdata$;
 $PF.vfl \leftarrow (vpt_x.mdn + vpt_x.man) \times 4 + 8$;

Algorithm 2: CLFraming

Input: *aid*, *TD*, *afdata*
Output: *afdata*
 SearchPT (*aid*, *apt_y*);
 Create *clf*;
 $af.aid \leftarrow aid$;
for $i = 0; i < apt_y.apn; i++$ **do**
 | ALFraming (*apt_y.aps[i]*, *TD*, *pfdata*);
end
 $af.cfl \leftarrow apt_y.apn \times 4 + 8$;
 $af.pfdata \leftarrow pfdata$;
 $afdata \leftarrow afdata + clf$;

Algorithm 3: ALFraming

Input: *pid*, *TD*, *pfdata*
Output: *pfdata*
 SearchPT (*pid*, *ppt_z*);
 Create *pf*;
 $pf.pid \leftarrow pid$;
 $pf.pdata \leftarrow TD[pid] \times ppt_z.var$;
 $pfdata \leftarrow pfdata + pf$;

D. Deframing of PF

The process of deframing of *PF* divided into *VCA* deframing, *CL* deframing, and *AL* deframing. Received Data (*RD*)

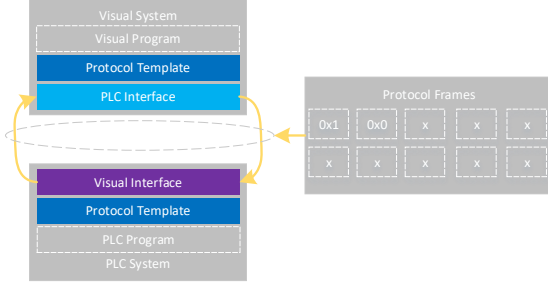


Fig. 6. *PF* interaction between *PLC* interface and visual interface.

area are used to save the deframing parameters. the *RD1*, *RD2* and *RD3* are different temporarily data stored area. In the *VS*, *RD3* are the data fed back to visual algorithms. In the *ES*, the *RD1*, *RD2* and *RD3* donate *LCD*, *MSD* and *AD*, respectively.

VCA deframing: As illustrated in Algorithm 4, obtain the *mid* and *pfl* form the start four and following four bytes data of *PDF*, respectively. Search the *PT* to gain the relevant *vpt_x*. Send the *pfl* - 8 bytes start form the eighth byte of *PDF* + 8 to the address *mda* of *vlt_x*.

CL deframing: According to *mid*, search *PT* to find the relevant *vpt_x*. Loop deal with the *mda* times of the parameter frame. In each loop, the data are sent to *RD3* with the relevant *pid*. Loop deal with the *man* times of the algorithm frame. In each loop, use the *aid* to find *apt_y* and then send the *afdata* to correlative address of *RD2*. Algorithm 5 is described the process.

AL deframing: Use *aid* to get its *apt_y*. Loop cope with the algorithm frame *apn* times. Send the parameters to *RD3* with the correlative *pid*. The process is shown in Algorithm 6.

Algorithm 4: *VLDeframing*

Input: *PDF*
 $mid \leftarrow$ four bytes form *PDF*;
 $searchPT(mid, vpt_x);$
 $pfl \leftarrow$ four bytes form *PDF* + 4;
 $RD1[vpt_x.mda] \leftarrow pfl - 8$ bytes form *PDF* + 8;
 $PDF \leftarrow PDF + pfl;$
 value of $vpt_x.mdf \leftarrow 1;$

IV. SYSTEM OPERATION MECHANISM

A. Implementation of Flexible Program and Execution

The *FL* contains *PLC* interface and visual interface, shown in Fig. 6. They interact with each other using the agreed communication protocol which is defined as *CID* in *HPT* of *PT*.

In the *ES*, the visual interface includes the following parts.

V1: communicates with *VS*, according to the *CID* in *HPT*. It has three transitions. (V1.1) donates no communication and other operations; (V1.2) donates receiving *PFs* from *VS*, and **V1.3** donates sending *PFs* to *VS*. In V1.3, the *PFs*

Algorithm 5: *CLDeframing*

Input: *mid*
 $searchPT(mid, vpt_x);$
 $mda \leftarrow vpt_x.mda;$
for $i = 0; i < vpt_x.mdn; i++$ **do**
 $RD3[RD1[mda]] \leftarrow$ 4 bytes form $mda + 4;$
 $mda \leftarrow mda + 8;$
end
for $i = 0; i < vpt_x.man; i++$ **do**
 $searchPT(vpt_x.mas[i], apt_y);$
 $cfl \leftarrow$ 4 bytes form $mda + 4;$
 $RD2[apt_y.apa] \leftarrow cfl - 8$ bytes form $mda + 8;$
 $mda \leftarrow mda + cfl;$
 value of $apt_y.adf \leftarrow 1;$
end

Algorithm 6: *ALDeframing*

Input: *aid*
 $searchPT(aid, apt_y);$
 $ada \leftarrow apt_y.ada;$
for $i = 0; i < apt_y.apn; i++$ **do**
 $RD3[RD2[ada]] \leftarrow$ 4 bytes form $ada + 4;$
 $ada \leftarrow ada + 8;$
end

will be saved in the *VD* of *ES* and there are two pointers: *PDF* and *PSP*, shown in Fig. 7. *PDF* points to the address of deframing *PF* and *PSP* points to the address of saving *PF*. After saved the *PF*, the *PSP* will point to the next new address according the *vfl* of *PF*. In V1.3, visual interface frames *TD* into *PF* with the Algorithm 1, 2 and 3. Here, the *TD* is in *RAM* of *ePLC*.

V2: Algorithm 4 will be called. The *PDF* will point to the next *PF*, if a *PF* is deframed.

In the *VS*, there are following parts.

V1: visual algorithms extracts the useful data and stores into array of data required to be transfered (*TD*) in which the parameters could be indexed by the *PID*.

V2: communicates with *ES*. It also contains three transitions. **V2.1** is no communication and other operations; **V2.1** frames *TD* into *PFs* with the Algorithm 1, 2, and 3 and sends the *PFs* to *ES*. Here, the *TD* is an array in *VS*; **V2.3** receives the *PFs* form *ES* and deframes the *PFs* with the Algorithm 4, 5, and 6.

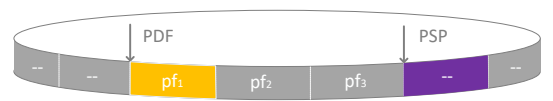


Fig. 7. *PDF* and *PSP*. *PDF* points to the address of deframing *PF* and *PSP* points to the address of saving *PF*. The *PDF* will point to the next address of *PF* if a *PF* is deframed. After saved the *PF*, the *PSP* will point to the next new address according the *vfl* of *PF*.



Fig. 8. Thread structure with three special threads: visual thread, Control thread, algorithm thread.

B. Implementation of Control Program and Execution

Control program (CP) is responsible for organizing the modules, executing the logic program, deframing the PF and interacting the data with algorithm program. The implementation of control program is described below.

C1: traverse the *MCF* and *MDF*. Its contains three transitions. **C1.1** donates that every $mc_f \in MCF$ and $md_f \in MDF$ is recovered to zero. **C1.2** means that both mc_{f_i} and md_{f_i} are checked one. **C1.3** means that mc_{f_i} are checked one while md_{f_i} is zero.

C2: executes Algorithm 5.

C3: executes logic program and checks whether there is any data required to transfer.

C4: the \mathcal{P}_{mts} is used to send data and inform the slave processor to receive parameters and start algorithms.

C5: checks the end of this module. *C5.1* donates that this module executes one time. *C5.2* donates that the logic program still requires to run.

C. Implementation and Execution of Algorithm Program

The algorithm program (AP) is in *EL*. $AP = \{\mathcal{P}_{stm}, AS, ALDP\}$, where \mathcal{P}_{stm} feeds back data to master processor, *AS* contains all algorithms and *ALDP* deframe the *AL* frame. The execution of algorithm program is introduced below.

A1: traverse the *AFS*, *ADF*, and *SMB*. *A1.1* is no program required to execute. *A1.2* donates that *PF*s needed to be deframed is checked. *A1.3* donates that data needed to feed back to master processor. *A1.4* donates that a algorithm needed to be executed is checked. *A1.5* donates that parameters of a algorithm needed to be updated is checked.

A2: *ALDP* is executed to call Algorithm 5.

A3: the \mathcal{P}_{stm} is used to feed back data to the master processor.

A4: starts a algorithm.

A5: executes the algorithm until the end.

D. Petri-Net Based Execution of Threads

We adopt the analogous thread structure in [18]. Three special threads are illustrated as follows: 1) visual thread is responsible for interaction with *VS* and drives the flexible layer; 2) control thread is mainly responsible for organizing the whole program and drives the control layer; 3) algorithm thread is used to drive the algorithm layer.

In our works, Petri Net is adopted to describe the execution of the three threads. Every thread is a Petri-Net. We define the Petri Net as three tuple:

$$PN = \{P, T, F\}, \quad (3)$$

where P is the finite set of places, T is the finite set of transitions, and F is the set of arcs. Here, $F \subset P \times T \cup T \times P$ which donates that the arcs contain form P to T and from T to P .

Then, we can define the execution of threads (ET) as follows.

$$ET = \{PN_V, PN_C, PN_A\}, \quad (4)$$

where PN_V, PN_C, PN_A are the Petri Net of visual thread, control thread, and algorithm thread, respectively.

The PN_V is donated as follows:

$$\begin{cases} PN_V = \{P_V, T_V, F_V\}, \\ P_V = \{P_{V1}, P_{V2}, P_{V3}\}, \\ T_V = \{V_1, V_2\}, \end{cases} \quad (5)$$

where P_{V1} is idle; P_{V2} is $P_{V2} = PSP$; P_{V3} is that a relevant md_f is set.

The PN_C is donated as follows:

$$\begin{cases} PN_C = \{P_C, T_C, F_C\}, \\ P_C = \{P_{C1}, P_{C2}, P_{C3}, P_{C4}, P_{C5}, P_{C6}\}, \\ T_C = \{C_1, C_2, C_3, C_4, C_5\}, \end{cases} \quad (6)$$

where P_{C1} is idle; P_{C2} donates that a model is started and the md_{f_i} is one; P_{C3} donates that a model is started and md_{f_i} is zero; P_{C4} donates that any msb_i is one; P_{C5} means the end of the data interaction in which the correlative msf is zero; P_{C6} donates that a module finishes one time execution.

The PN_V is illustrated as follows:

$$\begin{cases} PN_A = \{P_A, T_A, F_A\}, \\ P_A = \{P_{A1}, P_{A2}, P_{A3}, P_{A4}, P_{A5}, P_{A6}, P_{A7}, P_{A8}\}, \\ T_A = \{A_1, A_2, A_3, A_4, A_5\}, \end{cases} \quad (7)$$

where P_{A1} is idle; P_{A2} donates that an adf_i is one; P_{A3} donates that any adf_i is zero; P_{A4} donates that an smb_i is one; P_{A5} is that any smf_i is zero; P_{A6} is that an afe_i is one; P_{A7} is that an afs_i is one; P_{A8} is that any afe_i is zero.

The *ET* is described in Fig. 9. In the Petri Net of visual thread, if *V1.2* executes and receives a *PF* from *VS*, it transits from the initial position of P_{V1} to P_{V2} . After finished deframing of a *PF*, the state transits to P_{V3} and then visual thread back to execute *V1*. If there is any *FS* which should be sent to *VS*, it will execute *V1.2*. Apart from that, it will execute *V1.1* and back to the position of P_{V1} .

In the Petri Net of control thread, the control thread executes the *C1*. The difference between $P_{C1.2}$ and $P_{C1.3}$ is that after $P_{1.2}$, the control thread transits to P_{C2} and executes *C2*. Except that, it will back to P_{C1} . Then, the control thread runs into a module and *C3* is run. If find any data needed to transfer to slave processor, it transits to P_{C4} and executes *C4*. When finish transfer, it transits to P_{C5} . After execution of *C5*, according to *C5.1* and *C5.2*, control thread transits to P_{C3} and P_{C6} . The previous one is executed owing to that the logic program of this module is not finished.

In the Petri Net of algorithm thread, the *A1* is executed; if any *AF* needed to deframe, algorithm thread transits to P_{A2} and after the execution of *A2*, it transits to P_{A2} ; if any data

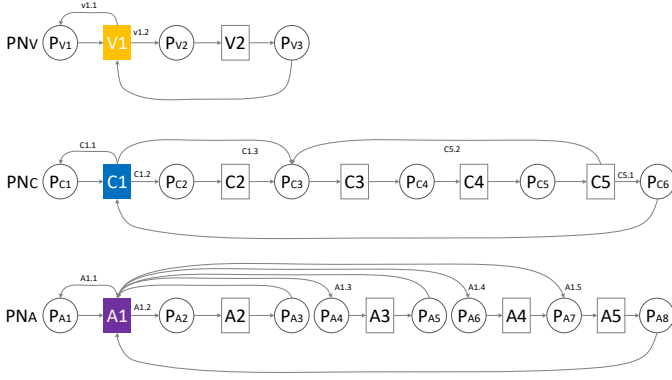


Fig. 9. Process of *ET* and it contains Petri Nets of visual thread, control thread, and algorithm thread.

required to feed back to master processor, algorithm thread transits to P_{A4} , then transfers the data, and transits to P_{A5} ; if any algorithm should be started, algorithm thread transits to P_{A6} , executes the $A4$, transits to P_{A7} , executes $A5$ to update the parameters, and then transits to P_{A8} ; if there are algorithms running and needed to updates parameters, algorithm thread transits to P_{A7} directly and after the execution of $A5$ transits to P_{A8} ; and above-mentioned transitions of $V1$ are executed in sequence.

V. CASE ANALYSIS

In this section, we introduce two scenarios of the proposed *VCA* protocol based integration method in *ePLC*. With the *VCA* protocol, users only need to code additional algorithms and change the *PT* when the scenario of visual servo system is changed.

A. Case 1: Winding Machine with Visual System

As shown in Fig. 10, (a) is the visual system, whose CUP is ARM9 based S3C2440 and which uses the CANIF interface to communicate with OV9650 CMOS Camera; (b) is the *ePLC*, CASS-PLCA149B; (c) is the winding machine with visual system which contains two axes: the U-axis and Q-axis; (d) is shown the Winding effect, the angle of the wire, Q-axis and U-axis. In winding process, the tension of the copper wire will change irregularly, especially for the thick ones. However, we use the same speed ratio of U-axis and Q-axis which always leads to irregularity of each layer of the coil. Hence, we can use the visual system to decrease or increase the speed of Q-axis to control the angle of wire.

Figure 11 is the structure of the winding machine system. The *ePLC* has two chips: a master chip and a slave chip. It uses the RS232 to receive *PFs* and could control six servo systems at most. The winding machine has two axes: the U-axis and Q-axis. The *VS* use the CMOS camera to gain winding images and transfer the digital information to ARM CUP. The ARM CUP will extract parameters from the digital information, frame *PFs* and transfer *PFs* to *ePLC* continuously.

TABLE I
PT OF WINDING MACHINE

cid_1	tda_1	xxx	xxx	xxx	xxx	xxx
0x01	0x00					
mid_1	man_1	mdn_1	mda_1	msf_1	mdf_1	mas_1
0x01	1	0	0X200	0X400	0X600	0x01
aid_1	apn_1	af_1	ada_1	$apsl_1$	xxx	xxx
0x01	0X1	0X14A	0x1F4000	0X0		
pid_1	vid_1	var_1	xxx	xxx	xxx	xxx
0X0	0X1	1000				

TABLE II
PF OF WINDING MACHINE

mid_1	pfl_1	aid_1	cfl_1	pid_1	$pdata_1$
0x01	0x14	0x01	0xE	0x01	0x400
0x01	0x14	0x01	0xE	0x01	0x200
0x01	0x14	0x01	0xE	0x01	0x000

1) *Design of PT*: In [18], we propose the customized winding machine language which only contains 13 instructions. Here, we can use the second and third instructions to control U-axis and Q-axis, respectively. In the algorithm layer, both of them use the same motion control algorithm which controls one axis with speed and position. The process of winding is mainly to control the speed ratio of U-axis and Q-axis, hence we use the *VS* to influence the speed of Q-axis only. The *PT* of winding machine is illustrated in Table I in which the pid_1 is the speed of Q-axis and the 1000 of var_1 is used to multiply by the θ .

2) *Process of PF*: Table II is shown the interacted *PF* between the *VS* and *ES*. At first, the *VS* detects that the θ is 2 degrees. Then, it sends the *PF* to inform the *ES* to increase the Q-axis speed of 2000 pulses per millisecond (p/ms). When the θ decreases to 1 degree, the increment of the Q-axis speed is changed to 1000 p/ms. Since the θ has recovered to 0, the *ES* is informed to recover the initial speed if the Q-axis.

B. Case 2: Binocular Catching Robot

As shown in Fig. 12, the binocular catching robot adopts two cameras to judge the position of the ball in the space. Through sending the continuously parameters to *ePLC*, the robot runs to the position to catch the ball. Finally, the robot will catch the ball. The cameras is xxx, the visual system is xxx. *ePLC* uses the TI F28M35 chip with two cores: ARM Cortex M3 and TI C28x, which contains a shared RAM. The servo system is adopted ASDA-B2.

1) *Design of PT*: The *ePLC* is designed to control six axes parallel. We adopt the same algorithm of Q-axis and U-axis in case one while we name three axes of the Cartesian Robot as X-axis, Y-axis and Z-axis. In this case, we have the similar module with case one however it contains three motion algorithms. pid_1 , pid_2 are the position and speed of X-axis; pid_3 , pid_4 are the position and speed of Y-axis; pid_5 , pid_6 are the position and speed of Z-axis. The *VS* use meter and

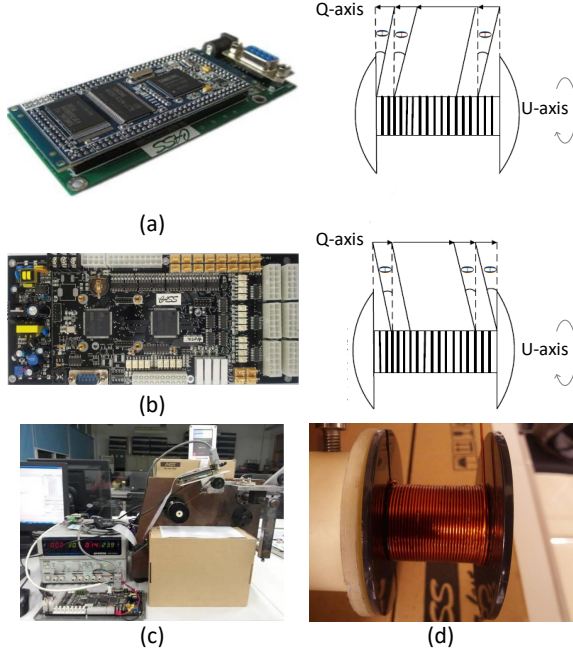


Fig. 10. (a) is the visual system, whose CUP is ARM9 based S3C2440 and which uses the CANIF interface to communicate with OV9650 CMOS Camera; (b) is the *ePLC*, CASS-PLCA149B; (c) is the winding machine with visual system which contains two axes: the U-axis and Q-axis; (d) is shown the Winding effect, the angle of the wire, Q-axis and U-axis.

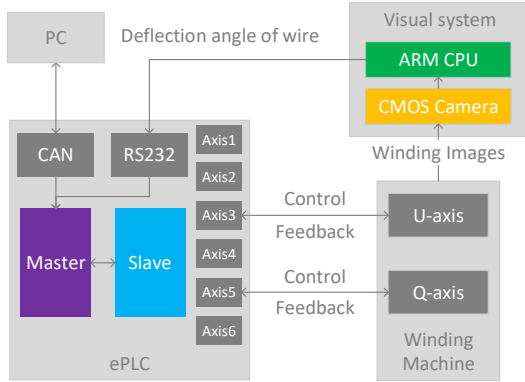


Fig. 11. Structure of the winding machine system. The *ePLC* has two chips: a master chip and a slave chip. It uses the RS232 to receive *PFs* and could control six servo systems at most. The winding machine has two axes: the U-axis and Q-axis. The *VS* use the CMOS camera to gain winding images and transfer the digital information to ARM CUP. The ARM CUP will extract parameters, frame *PFs* and transfer them to *ePLC* continuously.

meter per second (m/s) to measure the distance and speed, respectively while in the *ES*, driving every 1 cm need to output 10000 pluses. Hence, the *VAR* of position and speed are both 10000.

2) *Process of PF*: The *PFs* of a time catching the ball is shown in Table IV and the trajectory of the ball is shown in Fig. 13 which is only shown the position of X-axis and Y-axis. The *VS* sends the *PF* to *ES* to adjust the destination and speed of every axis.

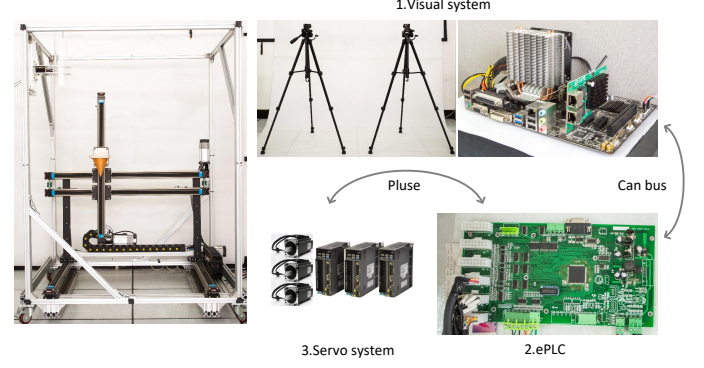


Fig. 12. Binocular Catching Robot consists of visual system, *ePLC* and servo system.

TABLE III
PT OF BINOCULAR CATCHING ROBOT

<i>cid</i> ₁	<i>tda</i> ₁	xxx	xxx	xxx	xxx	xxx	xxx	xxx
0x01	0x00							
<i>mid</i> ₁	<i>man</i> ₁	<i>mdn</i> ₁	<i>mda</i> ₁	<i>msf</i> ₁	<i>mdf</i> ₁	<i>mas</i> ₁	<i>mas</i> ₁	<i>mas</i> ₁
0x01	1	0	0X200	0X400	0X600	0x01	0x02	0x03
<i>aid</i> ₁	<i>apn</i> ₁	<i>af</i> ₁	<i>ada</i> ₁	<i>aps</i> ₁ ₁	<i>aps</i> ₂ ₁	xxx	xxx	xxx
0x01	0X2	0X14A	0x1F4000	0X0	0x4			
<i>aid</i> ₂	<i>apn</i> ₂	<i>af</i> ₂	<i>ada</i> ₂	<i>aps</i> ₁ ₂	<i>aps</i> ₂ ₂	xxx	xxx	xxx
0x02	0X2	0X14A	0x1F4000	0X8	0xA			
<i>aid</i> ₃	<i>apn</i> ₃	<i>af</i> ₃	<i>ada</i> ₃	<i>aps</i> ₁ ₃	<i>aps</i> ₂ ₃	xxx	xxx	xxx
0x03	0X2	0X14A	0x1F4000	0XE	0X10			
<i>pid</i> ₁	<i>vid</i> ₁	<i>var</i> ₁	<i>pid</i> ₂	<i>vid</i> ₂	<i>var</i> ₂	<i>pid</i> ₃	<i>vid</i> ₃	<i>var</i> ₃
0X0	0X1	10000	0X4	0X1	10000	0X8	0X1	10000
<i>pid</i> ₄	<i>vid</i> ₄	<i>var</i> ₄	<i>pid</i> ₅	<i>vid</i> ₅	<i>var</i> ₅	<i>pid</i> ₆	<i>vid</i> ₆	<i>var</i> ₆
0XA	0X1	10000	0XE	0X1	10000	0X10	0X1	10000

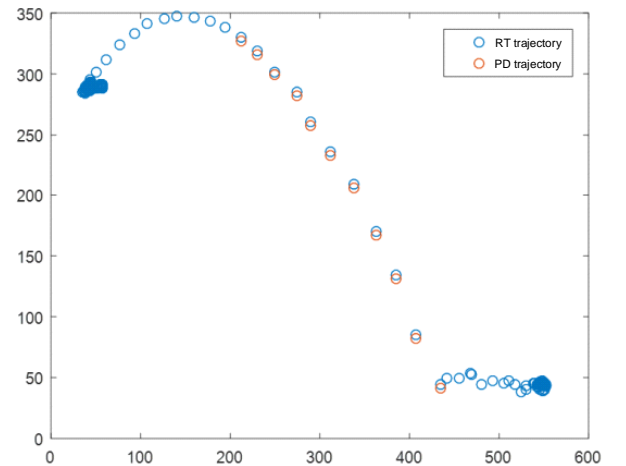


Fig. 13. Trajectory of the ball which is only shown the position of X-axis and Y-axis.

TABLE IV
PF OF BINOCULAR CATCHING ROBOT

mid_1	pfl_1	aid_1	cfl_1	pid_1	$pdata_1$	pid_2	$pdata_2$	aid_2	cfl_2	pid_3	$pdata_3$	pid_4	$pdata_4$	aid_3	cfl_3	pid_5	$pdata_5$	pid_6	$pdata_6$
0x01	0x14	0x01	0xE	0x01	0x400	0x01	0x400	0x01	0xE	0x01	0x400	0x01	0x400	0x01	0xE	0x01	0x400	0x01	0x400
0x01	0x14	0x01	0xE	0x01	0x400	0x01	0x400	0x01	0xE	0x01	0x400	0x01	0x400	0x01	0xE	0x01	0x400	0x01	0x400
0x01	0x14	0x01	0xE	0x01	0x400	0x01	0x400	0x01	0xE	0x01	0x400	0x01	0x400	0x01	0xE	0x01	0x400	0x01	0x400
0x01	0x14	0x01	0xE	0x01	0x400	0x01	0x400	0x01	0xE	0x01	0x400	0x01	0x400	0x01	0xE	0x01	0x400	0x01	0x400
0x01	0x14	0x01	0xE	0x01	0x400	0x01	0x400	0x01	0xE	0x01	0x400	0x01	0x400	0x01	0xE	0x01	0x400	0x01	0x400
0x01	0x14	0x01	0xE	0x01	0x400	0x01	0x400	0x01	0xE	0x01	0x400	0x01	0x400	0x01	0xE	0x01	0x400	0x01	0x400

C. Result

Through the analysis of two cases, the proposed *VCA* based flexible structure provides a generic method to address the visual servo control problem in *ePLC*. Based on the *VCA* protocol, the algorithms in *VS* and *ES* have a kind of normative correspondence and the existing modules and motion control algorithms could be reused without additional programming.

VI. CONCLUSION

We propose a flexible multi-level architecture which is based on a *VCA* protocol to integrate the PLC system, motion control system, and visual system to ease the complexity of the applications. The multi-level includes flexible layer, control layer, and algorithm layer. The *VCA* protocol is designed for data interaction between the layers. Correspondingly, a customized hardware, memory allocation, Petri-Net based multithreading structure are described to support the proposed flexible software architecture. We implements two cases, the winding machine with visual system and the binocular catching robot, to illustrate the proposed system which provides a generic method to develop different type applications of visual servo system in *ePLC*.

In the further research, we will implement a uniform development method of the visual servo control in *ePLC*.

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