fix_plc / PLC_1 [CPU 1214C DC/DC/DC] / Program blocks

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**					

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

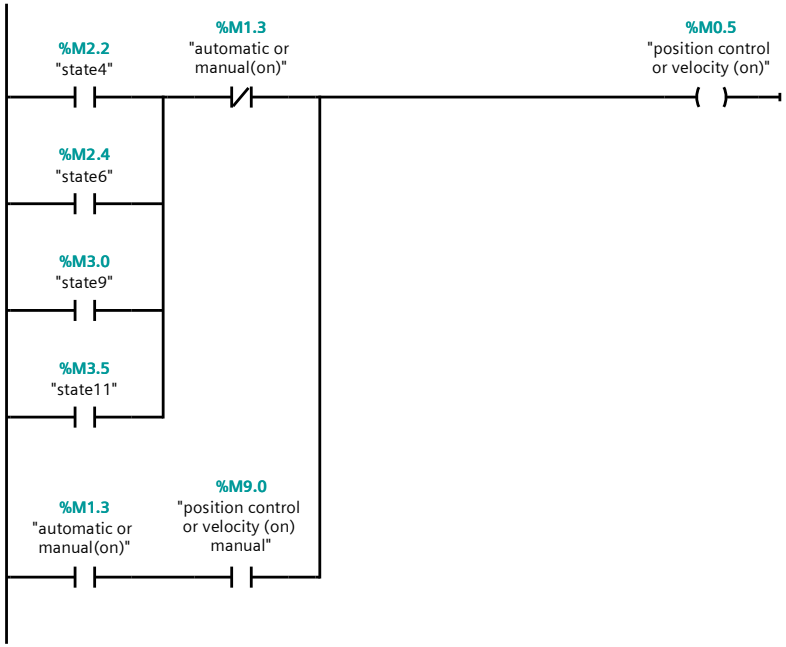
Network 1:

Network 2:

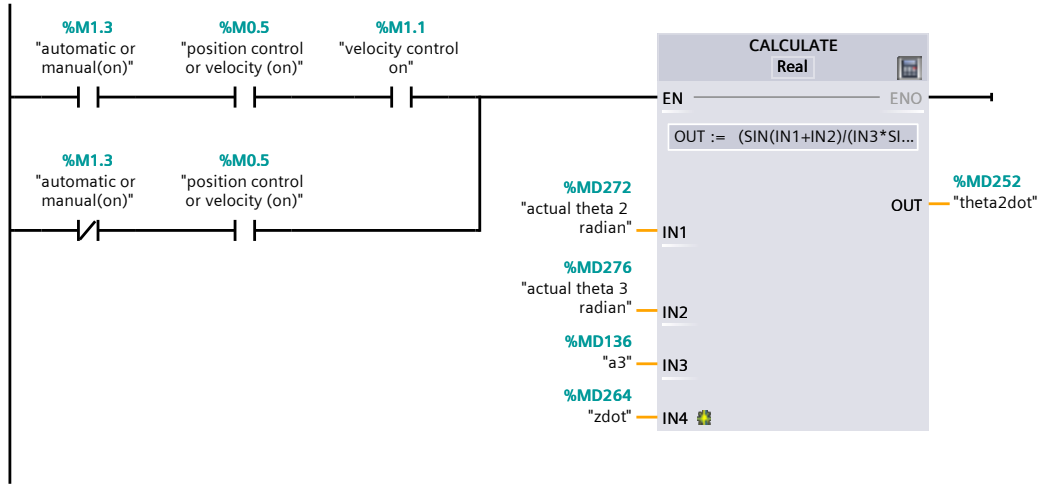
Network 3:

Network 4:

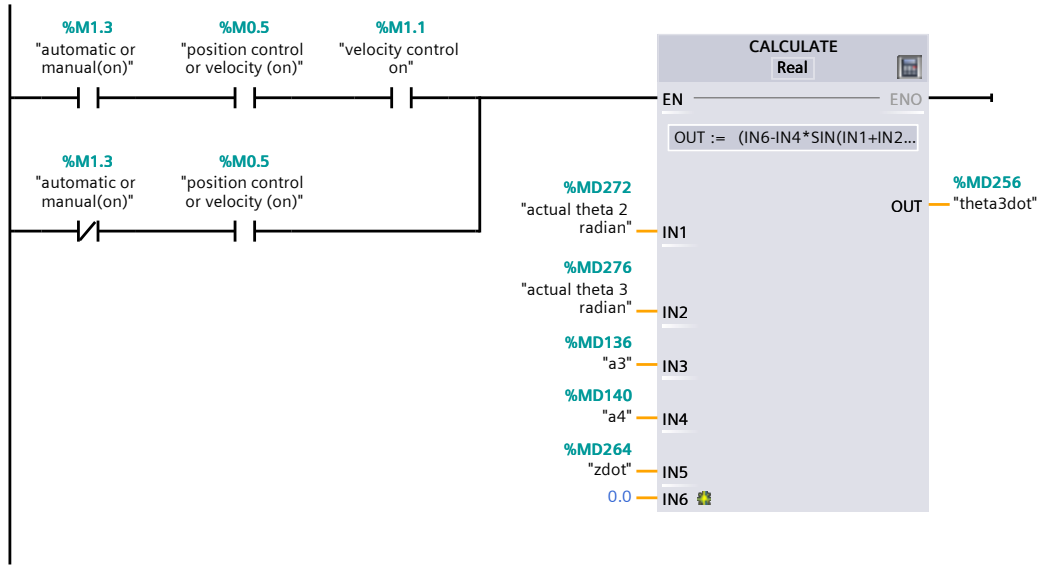
Network 5:


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

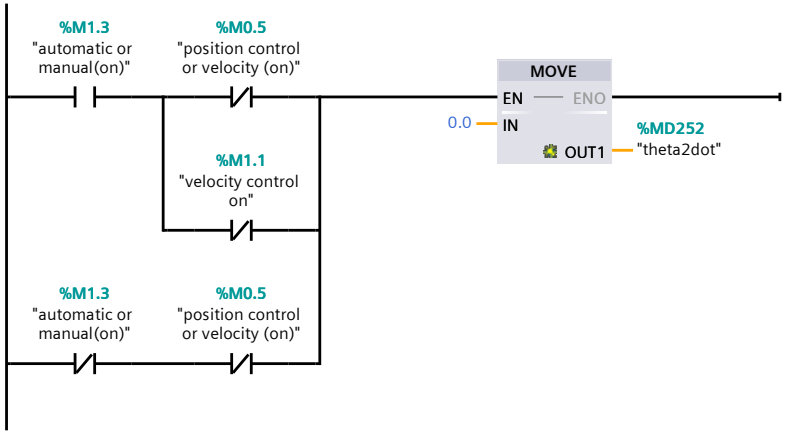
Network 6:


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

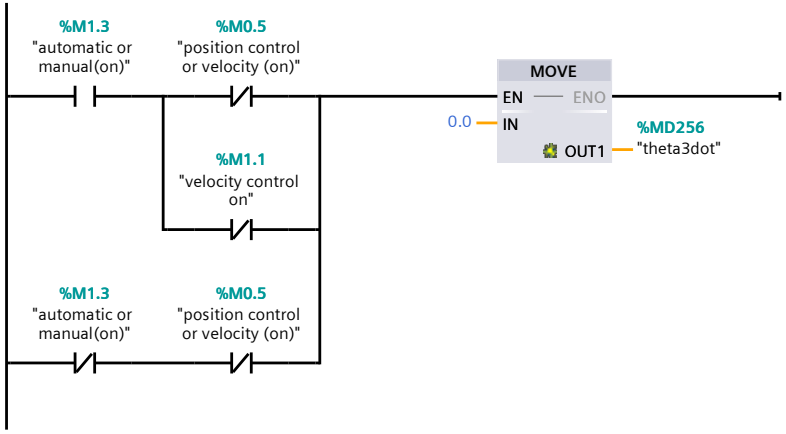
Network 7:


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

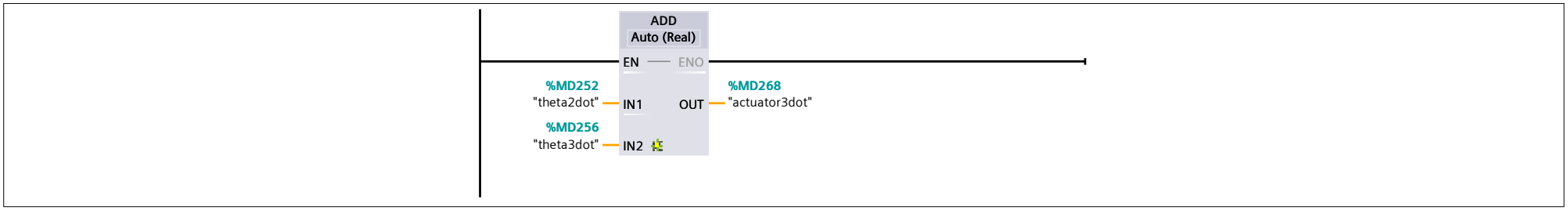
Network 8:



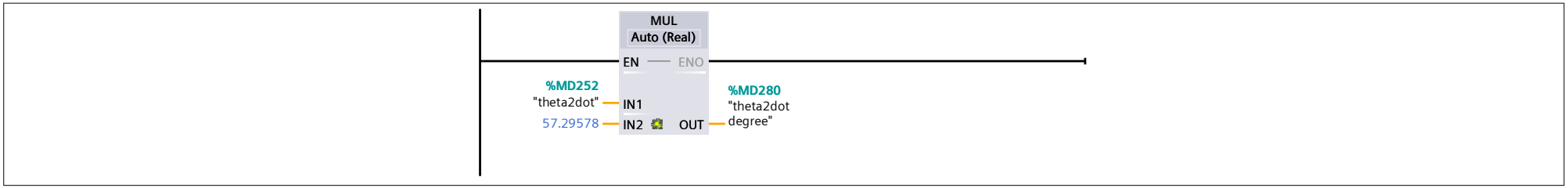
Network 9:



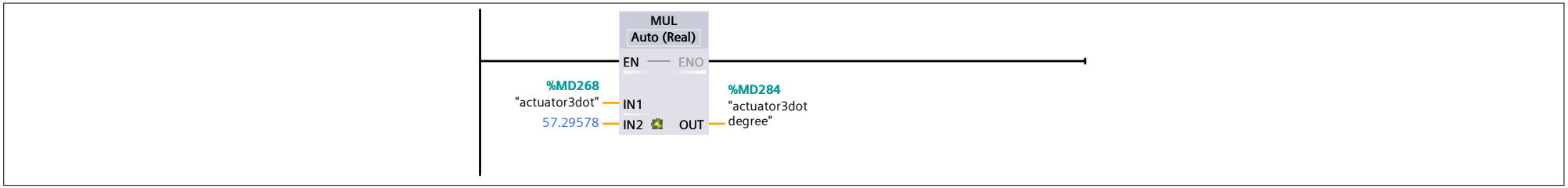
Network 10:



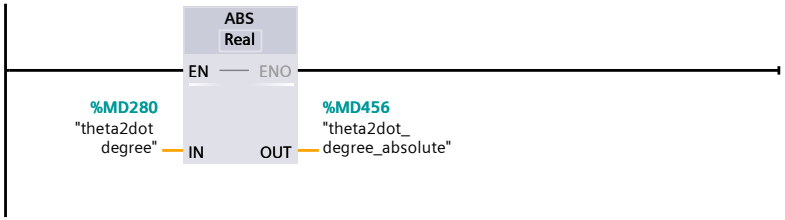
Network 11:



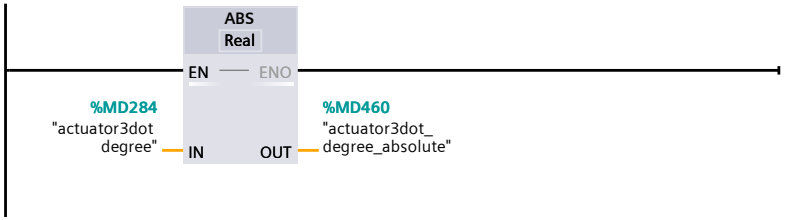
Network 12:



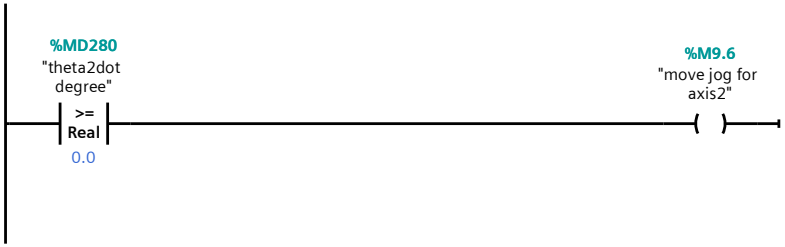
Network 13:



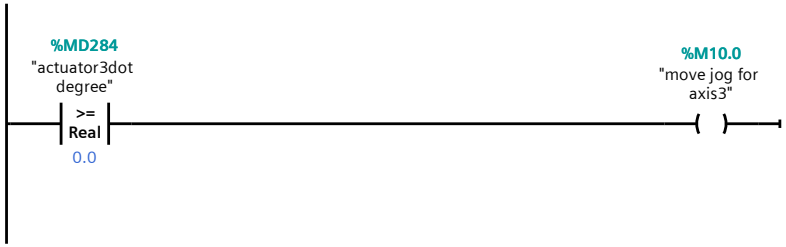
Network 14:



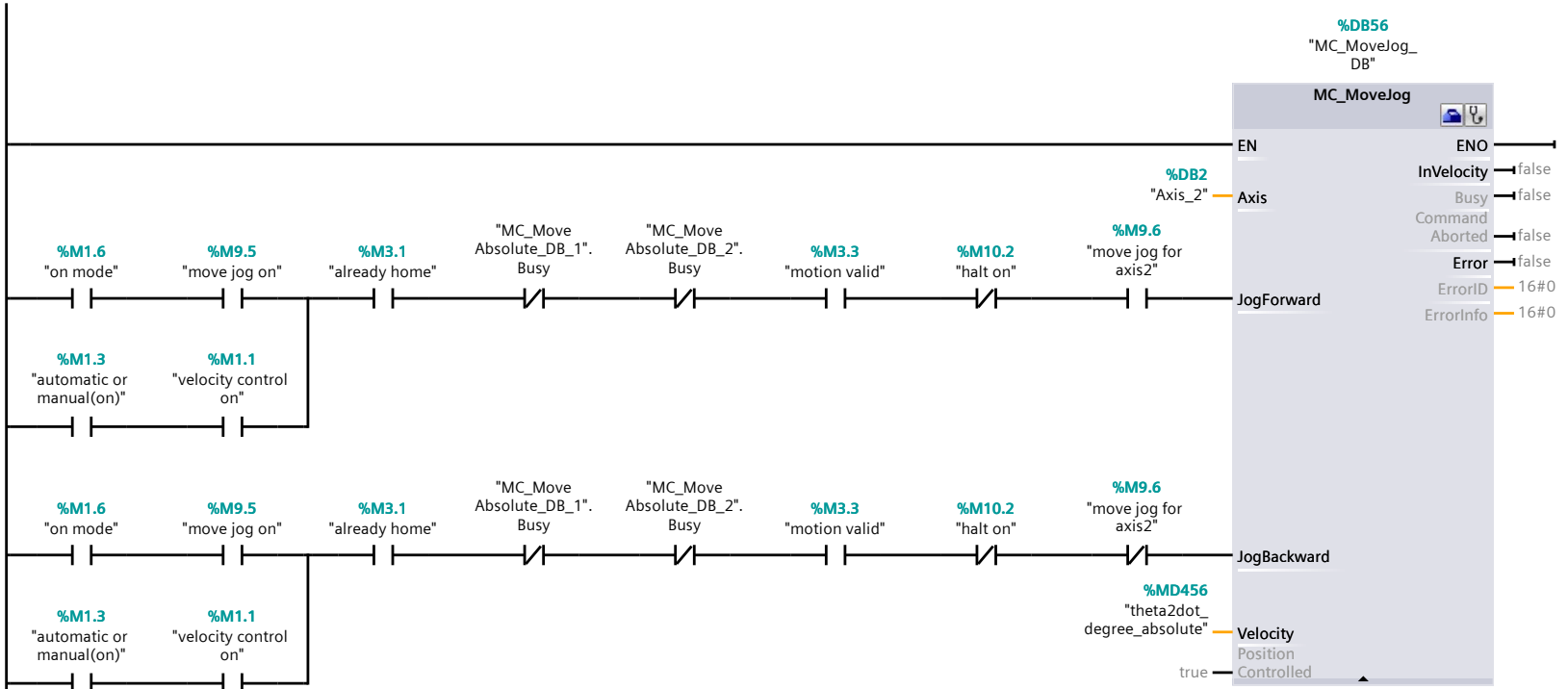
Network 15:



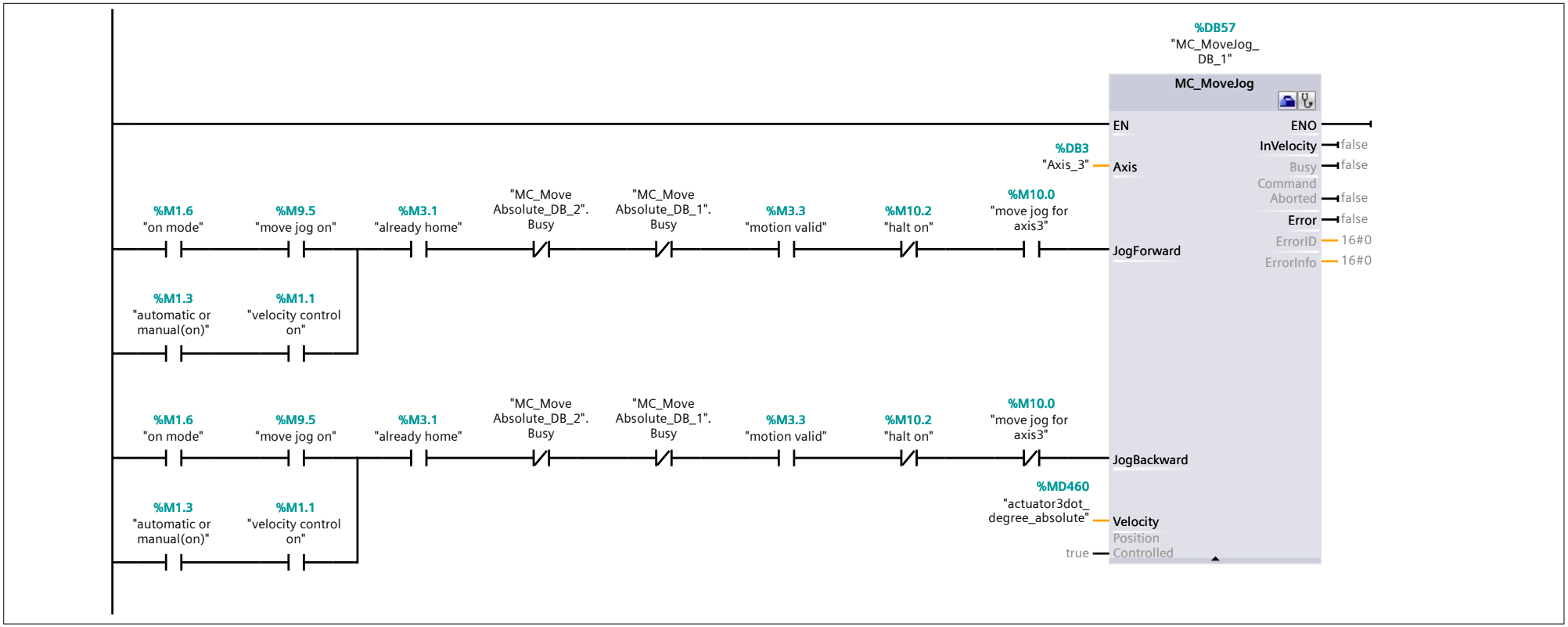
Network 16:


%MD284
"actuator3dot degree"
>= Real
0.0
%M10.0
"move jog for axis3"

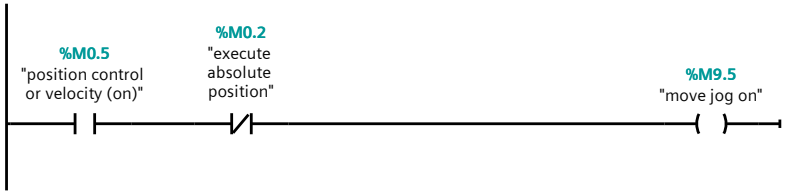
Network 17:


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

Network 18:



Network 19:


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