OB1 - <offline>

"CYCL_EXC" Cycle Execution

Name: **Family:**
Author: **Version:** 0.1
Block version: 2
Time stamp Code: 28-08-2001 14:23:52
Interface: 13-08-2001 23:52:59
Lengths (block/logic/data): 00296 00156 00020

Address	Declaration	Name	Type	Initial value	Comment
0.0	temp	OB1_EV_CLASS	BYTE		Bits 0-3 = 1 (Coming event), Bits 4-7 = 1 (Event class 1)
1.0	temp	OB1_SCAN_1	BYTE		1 (Cold restart scan 1 of OB 1), 3 (Scan 2-n of OB 1)
2.0	temp	OB1_PRIORITY	BYTE		1 (Priority of 1 is lowest)
3.0	temp	OB1_OB_NUMBR	BYTE		1 (Organization block 1, OB1)
4.0	temp	OB1_RESERVED_1	BYTE		Reserved for system
5.0	temp	OB1_RESERVED_2	BYTE		Reserved for system
6.0	temp	OB1_PREV_CYCLE	INT		Cycle time of previous OB1 scan (milliseconds)
8.0	temp	OB1_MIN_CYCLE	INT		Minimum cycle time of OB1 (milliseconds)
10.0	temp	OB1_MAX_CYCLE	INT		Maximum cycle time of OB1 (milliseconds)
12.0	temp	OB1_DATE_TIME	DATE_AND_TIME		Date and time OB1 started

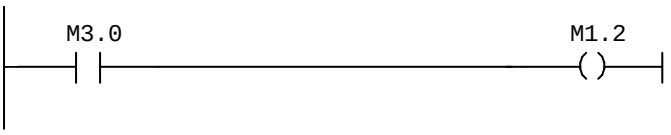
Block: OB1

```
This program demostrates how to use the FC1-blok to communicate with a FBG10
adapter connected to a JVL motor controller.
It's assumed that the address of the FBG is 10.
It's assumed that the connected controller is in MO=2 and it's possible to run
the motor with a SP command
The program is using the RS and SR command of the controller.
The program starts the motor by sending the SR=50000 command.
Then it reads the value of RS. If RS<>0 then it reads it again.
When RS=0 the program is starting the motor again by sending a new SR=50000
command.

M3.0 Start SET position
M3.1 Start GET position
M3.2 Is in position
```

Network: 1

Controls whenever the FC1 sould send a command, or request a parameter.

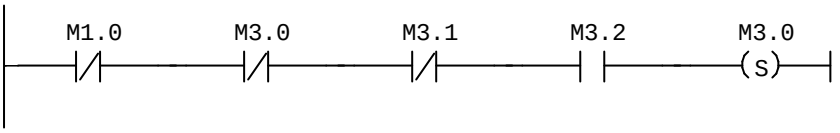


Network: 2

This network call the FC1 function block.

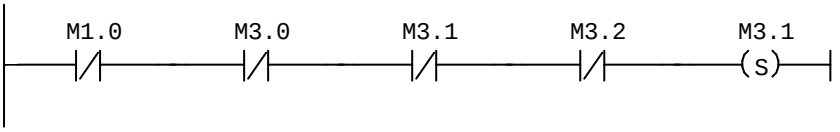
Network: 3

Set M3.0 if the motor is in position (M3.2) and nothing else is running



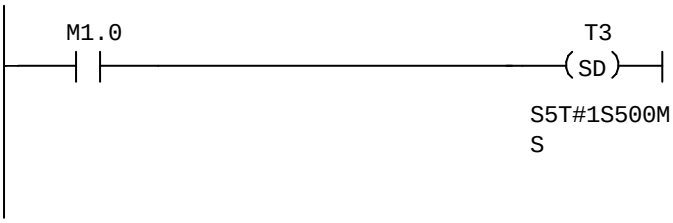
Network: 4

Set M3.1 if the motor isn't in position and nothing else is running



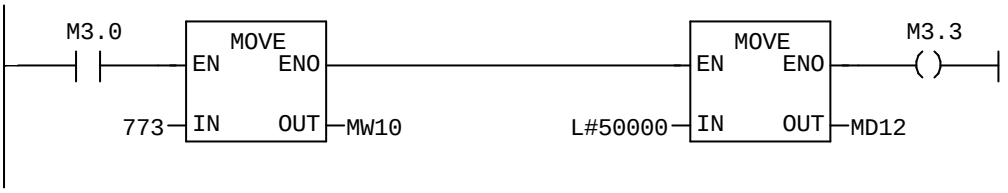
Network: 5

Starts a timer, that signals that the command is finished.



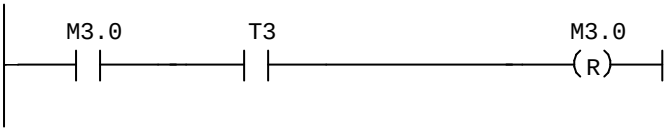
Network: 6

If M3.0 then load the command number (773 = SR) and the value 50000 into the
FBG10. Activate M3.3 wich signals that a command is ready.



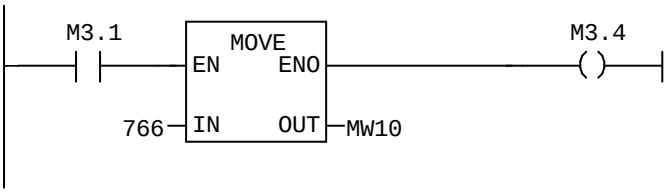
Network: 7

Resets M3.0 when the timer, that signals command executed, is fininshed.



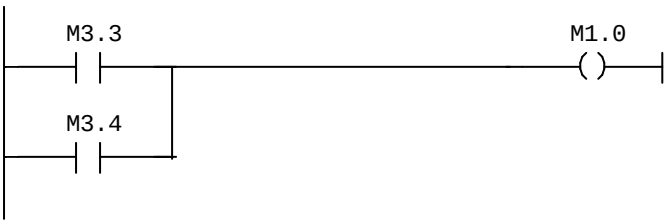
Network: 8

If M3.1 then load the command number (766 = RS) into the FBG10
Activate M3.4 wich signals that a command is ready



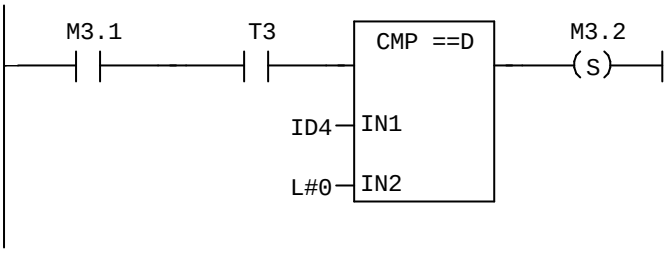
Network: 9

If there is a command ready, set M1.0. M1.0 is a signal to FC1 to start the
FBG10.



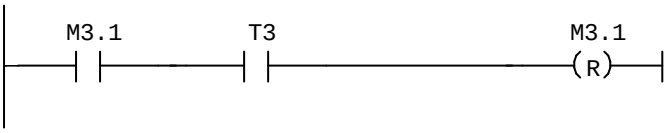
Network: 10

If the SR command has been executed, then read the result and compare it with 0.
If RS=0 then the motor has reached its position.



Network: 11

If excuting of the RS command is finish then clear the M3.1



Network: 12

Clear the in position bit (M3.2) when a new SR or RS command is initiated