

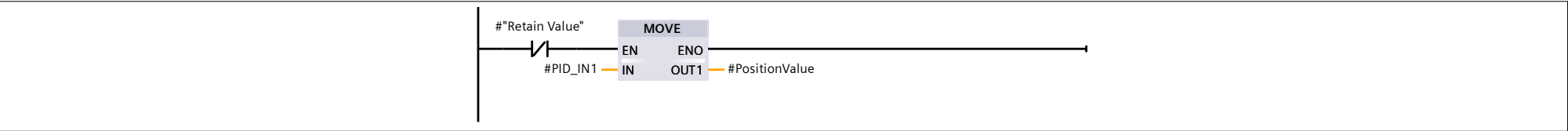
FRABA_Absolute_Encoder / PLC_1 [CPU 314C-2 PN/DP] / Program blocks

FRABA2.2Multiturn [FB2]

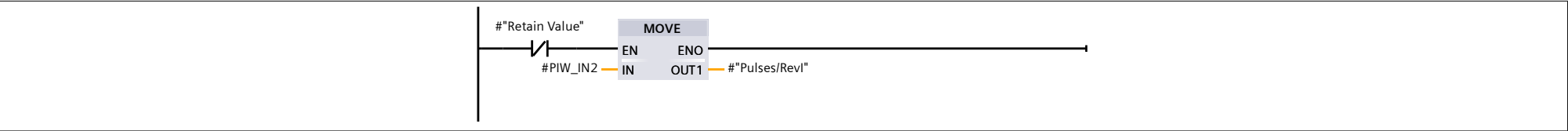
FRABA2.2Multiturn Properties							
General							
Name	FRABA2.2Multiturn	Number	2	Type	FB	Language	LAD
Numbering	Automatic						
Information							
Title		Author		Comment		Family	
Version	0.1	User-defined ID					

FRABA2.2Multiturn										
Name	Data type	Offset	Default value	Accessible from HMI/OPC UA	Writ-able from HMI/OPC UA	Visible in HMI engi-neering	Setpoint	Supervi-sion	Comment	
▼ Input										
PID_IN1	DWord	0.0	16#0	True	True	True	False			
PIW_IN2	Word	4.0	16#0	True	True	True	False			
PIW_IN3	Word	6.0	16#0	True	True	True	False			
PulleyDiameter	Real	8.0	0.0	True	True	True	False			
#Revolutions	Real	12.0	0.0	True	True	True	False			
RotationAngle	Real	16.0	0.0	True	False	False	False			
CW/CCW	Bool	20.0	false	True	True	True	False			
PresetInitial	Bool	20.1	false	True	True	True	False			
Retain Value	Bool	20.2	false	True	False	True	False			
SVEnable	Bool	20.3	false	True	True	True	False			
LoadSV	Int	22.0	0	True	True	True	False			
T10	Timer	24.0	0	True	True	True	False			
▼ Output										
PQD_OUT1	DWord	26.0	16#0	True	True	True	False			
PQW_OUT2	Word	30.0	16#0	True	True	True	False			
PositionValue	DWord	32.0	16#0	True	True	True	False			
VelocitySteps/s	Int	36.0	0	True	True	True	False			
EncoderMilimeterl	DInt	38.0	0	True	True	True	False			
▼ InOut										
Pulses/Revl	DInt	42.0	0	True	True	True	False			
Pulses/RevR	Real	46.0	0.0	True	True	True	False			
EncoderMilimeterR	Real	50.0	0.0	True	True	True	False			
CamDegree	Real	54.0	0.0	True	True	True	False			
▼ Static										
▼ P_TRIG1	Array[0..1] of Bool	58.0		True	True	True	False			
P_TRIG1[0]	Bool	58.0	false	True	True	True	False			
P_TRIG1[1]	Bool	58.1	false	True	True	True	False			
▼ Temp										
ResetDgree	Bool	0.0								
t#300ms	Bool	0.1								
PDValue	Real	2.0								
Pulses/mm	Real	6.0								
RetantiveValue	DInt	10.0								
Constant										

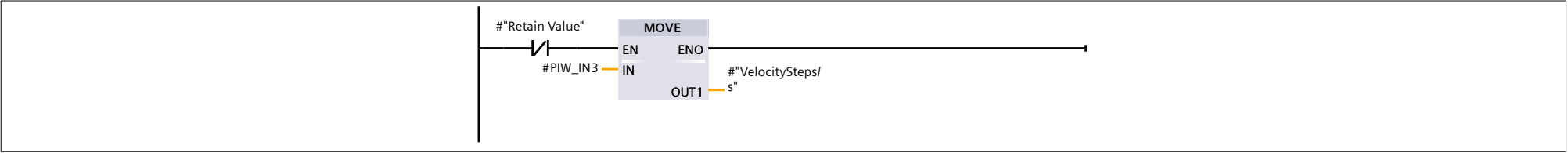
Network 1: PositionValue



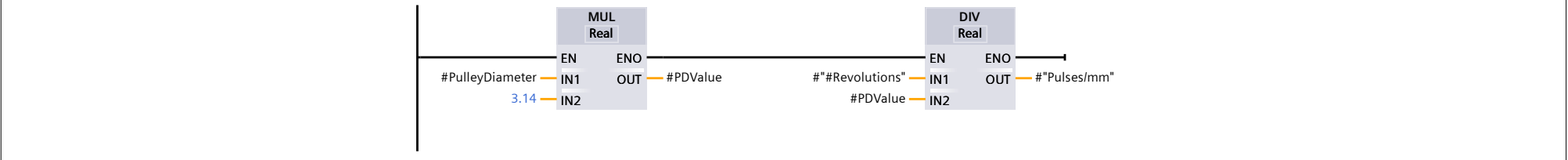
Network 2: Pulses/Revolution



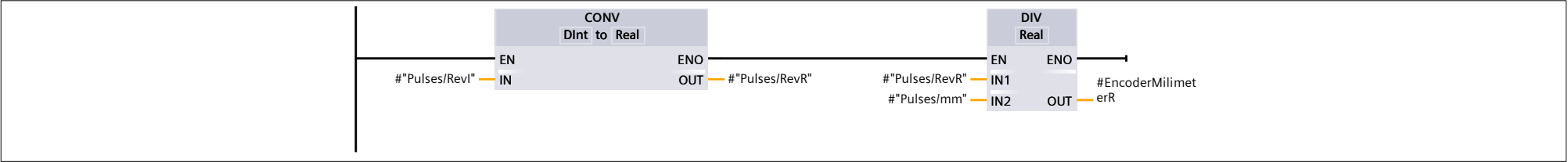
Network 3: Velocity Steps/1000ms



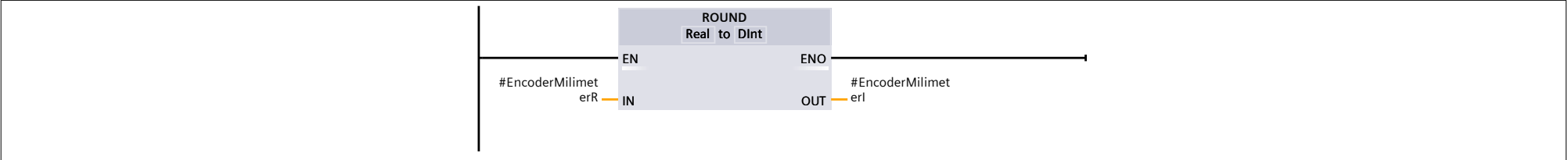
Network 4: $P=10 \times 3.14 = 31.4 = 4096 / 31.4 = 130.4$ pulses/mm



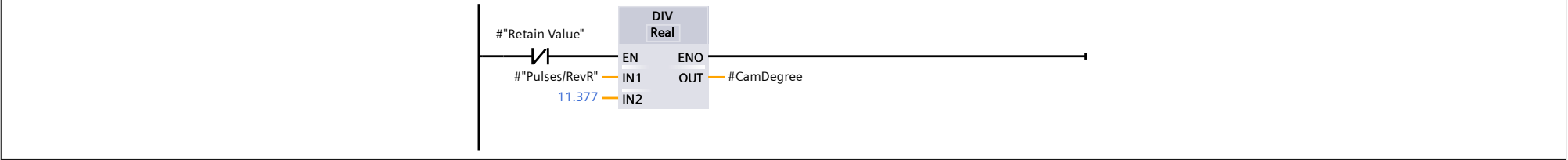
Network 5: EncoderMilimeter



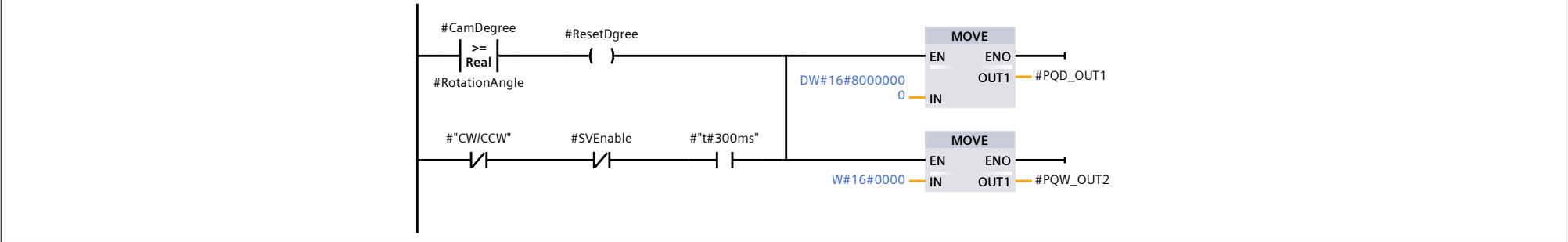
Network 6: EncoderMilimeterI



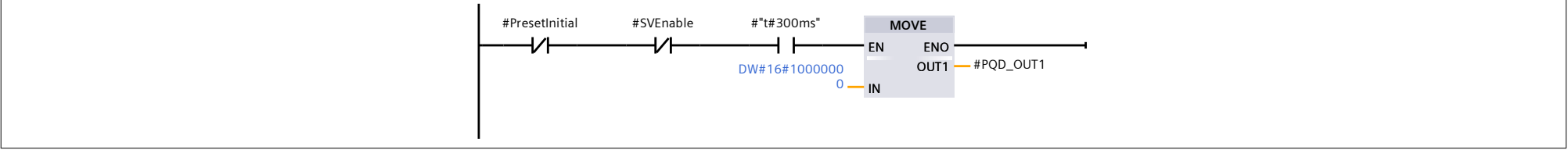
Network 7: CamDegree



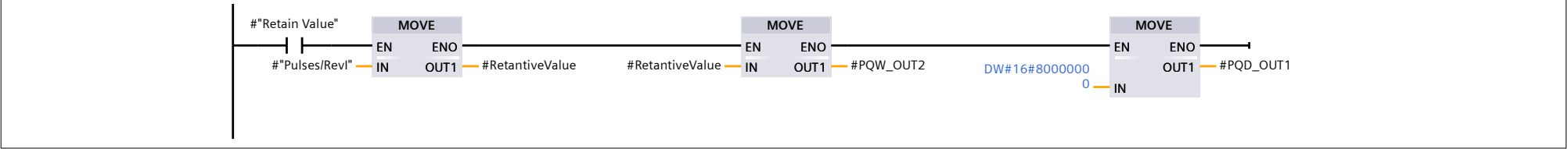
Network 8: Reset Degree and steps to 0 Cam Bit 31 (#PresetInitial)



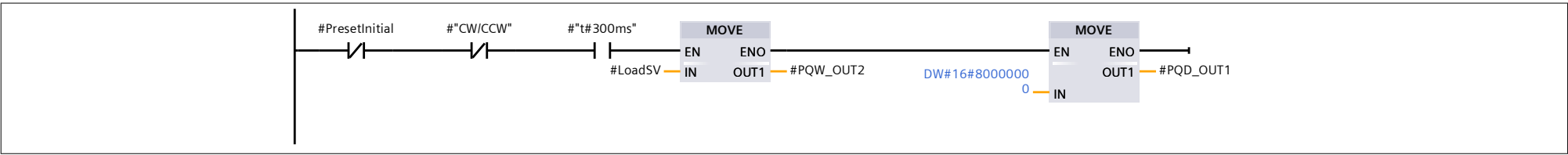
Network 9: Code Sequence Set/Reset CW/CCW Bit 28



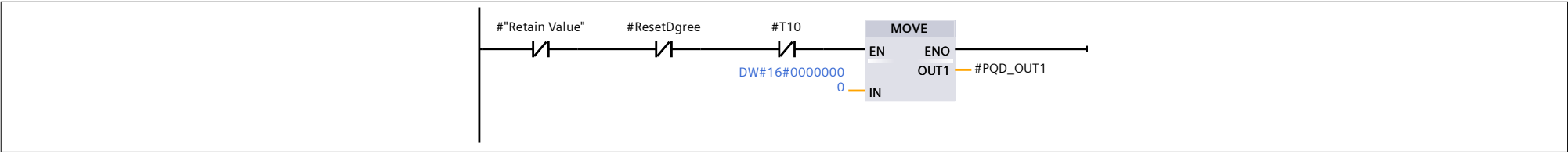
Network 10: Save Value before power recycle and transfer same after restart even encoder rotate in power failure (Set OB100 Reset PB))



Network 11: Load Set Value to Encoder (Preset Bit 31)



Network 12: Reset Data & Status Bits



Network 13:

