



**Subset of the**

**Technical Specification**

**PLCopen - Technical Committee 2 – Task Force**

**Function blocks for motion control**  
(Formerly Part 1 and Part 2)

**Version 2.0**

**Appendix B**

**Compliance Procedure and Compliance List**

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March 17, 2011.

## Appendix B. Compliance Procedure and Compliance List

Listed in this Appendix are the requirements for the compliance statement from the supplier of the Motion Control Function Blocks. The compliance statement consists of two main groups: supported data types and supported Function Blocks, in combination with the applicable inputs and outputs. The supplier is required to fill out the tables for the used data types and Function Blocks, according to their product, committing their support to the specification.

By submitting these tables to PLCopen, and after approval by PLCopen, the list will be published on the PLCopen website, [www.plcopen.org](http://www.plcopen.org) as well as a shortform overview, as specified in Appendix B 2 Supported Data types and Appendix B 3 Overview of the Function Blocks as below.

In addition to this approval, the supplier is granted access and usage rights of the PLCopen Motion Control logo, as described in Appendix B 4:

The PLCopen Motion Control Logo and Its Usage..



### Data types

The data type REAL listed in the Function Blocks and parameters (e.g. for velocity, acceleration, distance, etc.) may be exchanged to SINT, INT, DINT or LREAL without to be seen as incompliant to this standard, as long as they are consistent for the whole set of Function Blocks and parameters.

Implementation allows the extension of data types as long as the basic data type is kept. For example: WORD may be changed to DWORD, but not to REAL.

### Function Blocks and Inputs and Outputs

An implementation which claims compliance with this PLCopen specification shall offer a set of Function Blocks for motion control, meaning one or more Function Blocks, with at least the **basic** input and output variables, marked as “**B**” in the tables. These inputs and outputs have to be supported to be compliant.

For higher-level systems and future extensions any subset of the **extended** input and output variables, marked as “**E**” in the tables can be implemented.

Vendor specific additions are marked with “**V**”, and can be listed as such in the supplier documentation.

- |  |   |
|--|---|
| - <b>Basic</b> input/output variables are mandatory    | Marked in the tables with the letter “ <b>B</b> ”                 |
| - <b>Extended</b> input /output variables are optional | Marked in the tables with the letter “ <b>E</b> ”                 |
| - <b>Vendor Specific</b> additions                     | Marked in the vendor’s compliance documentation with “ <b>V</b> ” |

All the vendor specific items will not be listed in the comparison table on the PLCopen website, but in the detailed vendor specific list, which also is published.

All vendor specific in- and outputs of all FBs must be listed in the certification list of the supplier. With this, the certification listing from a supplier describes all the I/Os of the relevant FBs, including vendor-specific extensions, and thus showing the complete FBs as used by the supplier.

**Appendix B 1. Statement of Supplier**

Supplier name	Advanced Motion Controls
Supplier address	3805 Calle Tecate
City	Camarillo
Country	California 93012, USA
Telephone	805-389-1935
Fax	805-389-1165
Email address	bartasa@t-online.hu
Product Name	Click&Move (C&M)
Product version	4.2.0
Release date	12/11/2012

I hereby state that the following tables as filled out and submitted do match our product as well as the accompanying user manual, as stated above.

Name of representation (person):

Sándor Barta

CEO of Advanced Motion Controls

Date of signature (dd/mm/yyyy):

24/10/2012

Signature:



## Appendix B 2. Supported Data types

Defined datatypes with MC library:	Supported	If not supported, which datatype used
BOOL	Y	
INT		Int, Int8, Int16, Int32, Int64
WORD		UInt, UInt8, UInt16, UInt32, UInt64
REAL		Float32, Float64
ENUM	Y	
UINT		UInt, UInt8, UInt16, UInt32, UInt64

**Table 1: Supported datatypes**

Within the specification the following derived datatypes are defined. Define which of these structures are used in this system:

Derived datatypes:	Where used	Supported	Which structure
AXIS_REF	Nearly all FBs	Y	TD_AxisRefIntf
MC_DIRECTION (extended)	MC_MoveAbsolute MC_MoveVelocity MC_TorqueControl MC_MoveContinuousAbsolute	Y	EN_Direction
MC_TP_REF	MC_PositionProfile	N	
MC_TV_REF	MC_VelocityProfile	N	
MC_TA_REF	MC_AccelerationProfile	N	
MC_CAM_REF	MC_CamTableSelect	Y	CamTableRefIntf
MC_CAM_ID (extended)	MC_CamTableSelect MC_CamIn	N	
MC_START_MODE (extended)	MC_CamIn MC_CamTableSelect	N	
MC_BUFFER_MODE	Buffered FBs	Y	EN_BufferMode
MC_EXECUTION_MODE	MC_SetPosition MC_WriteParameter MC_WriteBoolParameter MC_WriteDigitalOutput MC_CamTableSelect	N	
MC_SOURCE	MC_ReadMotionState MC_CamIn MC_GearIn MC_GearInPos MC_CombineAxes MC_DigitalCamSwitch	Y	EN_SyncSource
MC_SYNC_MODE	MC_GearInPos	N	
MC_COMBINE_MODE	MC_CombineAxes	N	
MC_TRIGGER_REF	MC_TouchProbe MC_AbortTrigger	N	
MC_INPUT_REF	MC_ReadDigitalInput	N	
MC_OUTPUT_REF	MC_DigitalCamSwitch MC_ReadDigitalOutput MC_WriteDigitalOutput	N	
MC_CAMSWITCH_REF	MC_DigitalCamSwitch	N	
MC_TRACK_REF	MC_DigitalCamSwitch	N	

**Table 2: Supported derived datatypes**

### Appendix B 3. Overview of the Function Blocks

Single Axis Function Blocks	Supported as V1.0/ V1.1/ V2.0 or Not	Comments (<= 48 char.)
MC_Power	V1.1	
MC_Home	V1.1	
MC_Stop	V1.1	
MC_Halt	V2.0	
MC_MoveAbsolute	V2.0	
MC_MoveRelative	V2.0	
MC_MoveAdditive	N	
MC_MoveSuperimposed	N	
MC_HaltSuperimposed	N	
MC_MoveVelocity	V2.0	
MC_MoveContinuousAbsolute	N	
MC_MoveContinuousRelative	N	
MC_TorqueControl	N	This function supported by C&M specific FB
MC_PositionProfile	N	This function supported by C&M specific FB
MC_VelocityProfile	N	
MC_AccelerationProfile	N	
MC_SetPosition	V1.0	
MC_SetOverride	V2.0	
MC_ReadParameter & MC_ReadBoolParameter	V2.0	
MC_WriteParameter & MC_WriteBoolParameter	V2.0	
MC_ReadDigitalInput	N	Implemented in MC_ReadBoolParameter
MC_ReadDigitalOutput	N	Implemented in MC_ReadBoolParameter
MC_WriteDigitalOutput	N	Implemented in MC_ReadBoolParameter
MC_ReadActualPosition	V2.0	
MC_ReadActualVelocity	V2.0	
MC_ReadActualTorque	V2.0	
MC_ReadStatus	V1.1	
MC_ReadMotionState	N	Implemented in MC_ReadStatus
MC_ReadAxisInfo	N	
MC_ReadAxisError	V2.0	
MC_Reset	V2.0	
MC_DigitalCamSwitch	N	
MC_TouchProbe	V2.0	
MC_AbortTrigger	V2.0	
Multi-Axis Function Blocks	Supported as V1.0/ V1.1/ V2.0 or Not	Comments (<= 48 char.)
MC_CamTableSelect	V2.0	
MC_CamIn	V2.0	
MC_CamOut	N	
MC_GearIn	V2.0	
MC_GearOut	N	
MC_GearInPos	V2.0	
MC_PhasingAbsolute	N	This function supported by C&M specific FB
MC_PhasingRelative	N	This function supported by C&M specific FB
MC_CombineAxes	N	

**Table 3: Short overview of the Function Blocks**

### Appendix B 3.1 MC\_Power

If Supported	MC_Power	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Enable	Y	
E	EnablePositive	N	
E	EnableNegative	N	
V	BufferMode	Y	
VAR_OUTPUT			
B	Status	Y	
E	Valid	N	
V	Busy	Y	
V	Active	Y	
B	Error	Y	
E	ErrorID	Y	

### Appendix B 3.2 MC\_Home

If Supported	MC_Home	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Execute	Y	
B	Position	Y	
V	HomingMode	Y	
E	BufferMode	Y	
VAR_OUTPUT			
B	Done	Y	
E	Busy	Y	
E	Active	Y	
E	CommandAborted	Y	
B	Error	Y	
E	ErrorID	Y	

### Appendix B 3.3 MC\_Stop

If Supported	MC_Stop	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Execute	Y	
E	Deceleration	Y	
E	Jerk	Y	
V	BufferMode	Y	
VAR_OUTPUT			
B	Done	Y	
E	Busy	Y	
V	Active	Y	
E	CommandAborted	Y	
B	Error	Y	
E	ErrorID	Y	

**Appendix B 3.4 MC\_Halt**

If Supported	MC_Halt	Sup. Y/N	
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Execute	Y	
E	Deceleration	Y	
E	Jerk	Y	
E	BufferMode	Y	
VAR_OUTPUT			
B	Done	Y	
E	Busy	Y	
E	Active	Y	
E	CommandAborted	Y	
B	Error	Y	
E	ErrorID	Y	

**Appendix B 3.5 MC\_MoveAbsolute**

If Supported	MC_MoveAbsolute	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Execute	Y	
E	ContinuousUpdate	N	
B	Position	Y	
B	Velocity	Y	
E	Acceleration	Y	
E	Deceleration	Y	
E	Jerk	Y	
B	Direction	Y	
E	BufferMode	Y	
VAR_OUTPUT			
B	Done	Y	
E	Busy	Y	
E	Active	Y	
E	CommandAborted	Y	
B	Error	Y	
E	ErrorID	Y	

### Appendix B 3.6 MC\_MoveRelative

If Supported	MC_MoveRelative	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Execute	Y	
E	ContinuousUpdate	N	
B	Distance	Y	
E	Velocity	Y	
E	Acceleration	Y	
E	Deceleration	Y	
E	Jerk	Y	
E	BufferMode	Y	
VAR_OUTPUT			
B	Done	Y	
E	Busy	Y	
E	Active	Y	
E	CommandAborted	Y	
B	Error	Y	
E	ErrorID	Y	

### Appendix B 3.7 MC\_MoveAdditive

If Supported	MC_MoveAdditive	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis		
VAR_INPUT			
B	Execute		
E	ContinuousUpdate		
B	Distance		
E	Velocity		
E	Acceleration		
E	Deceleration		
E	Jerk		
E	BufferMode		
VAR_OUTPUT			
B	Done		
E	Busy		
E	Active		
E	CommandAborted		
B	Error		
E	ErrorID		



### Appendix B 3.8 MC\_MoveSuperimposed

If Supported	MC_MoveSuperimposed	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis		
VAR_INPUT			
B	Execute		
E	ContinuousUpdate		
B	Distance		
E	VelocityDiff		
E	Acceleration		
E	Deceleration		
E	Jerk		
VAR_OUTPUT			
B	Done		
E	Busy		
E	CommandAborted		
B	Error		
E	ErrorID		
E	CoveredDistance		

### Appendix B 3.9 MC\_HaltSuperimposed

If Supported	MC_HaltSuperimposed	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis		
VAR_INPUT			
B	Execute		
E	Deceleration		
E	Jerk		
VAR_OUTPUT			
B	Done		
E	Busy		
E	CommandAborted		
B	Error		
E	ErrorID		

### Appendix B 3.10 MC\_MoveVelocity

If Supported	MC_MoveVelocity	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Execute	Y	
E	ContinuousUpdate	N	
E	Velocity	Y	
E	Acceleration	Y	
E	Deceleration	Y	
E	Jerk	Y	
E	Direction	Y	
E	BufferMode	Y	
VAR_OUTPUT			
B	InVelocity	Y	
E	Busy	Y	
E	Active	Y	
E	CommandAborted	Y	
B	Error	Y	
E	ErrorID	Y	

### Appendix B 3.11 MC\_MoveContinuousAbsolute

If Supported	MC_MoveContinuousAbsolute	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis		
VAR_INPUT			
B	Execute		
E	ContinuousUpdate		
B	Position		
B	EndVelocity		
B	Velocity		
E	Acceleration		
E	Deceleration		
E	Jerk		
E	Direction		
E	BufferMode		
VAR_OUTPUT			
B	InEndVelocity		
E	Busy		
E	Active		
E	CommandAborted		
B	Error		
E	ErrorID		

### Appendix B 3.12 MC\_MoveContinuousRelative

If Supported	MC_MoveContinuousRelative	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis		
VAR_INPUT			
B	Execute		
E	ContinuousUpdate		
B	Distance		
B	EndVelocity		
B	Velocity		
E	Acceleration		
E	Deceleration		
E	Jerk		
E	BufferMode		
VAR_OUTPUT			
B	InEndVelocity		
E	Busy		
E	Active		
E	CommandAborted		
B	Error		
E	ErrorID		

### Appendix B 3.13 MC\_TorqueControl

If Supported	MC_TorqueControl	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis		
VAR_INPUT			
B	Execute		
E	ContinuousUpdate		
B	Torque		
E	TorqueRamp		
E	Velocity		
E	Acceleration		
E	Deceleration		
E	Jerk		
E	Direction		
E	BufferMode		
VAR_OUTPUT			
B	InTorque		
E	Busy		
E	Active		
E	CommandAborted		
B	Error		
E	ErrorID		

### Appendix B 3.14 MC\_PositionProfile

If Supported	MC_PositionProfile	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis		
B	TimePosition		
VAR_INPUT			
B	Execute		
V	TimeArray		
V	PositionArray		
E	ContinuousUpdate		
E	TimeScale		
E	PositionScale		
E	Offset		
E	BufferMode		
VAR_OUTPUT			
B	Done		
E	Busy		
E	Active		
E	CommandAborted		
B	Error		
E	ErrorID		

### Appendix B 3.15 MC\_VelocityProfile

If Supported	MC_VelocityProfile	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis		
B	TimeVelocity		
VAR_INPUT			
B	Execute		
E	ContinuousUpdate		
E	TimeScale		
E	VelocityScale		
E	Offset		
E	BufferMode		
VAR_OUTPUT			
B	ProfileCompleted		
E	Busy		
E	Active		
E	CommandAborted		
B	Error		
E	ErrorID		

**Appendix B 3.16 MC\_AccelerationProfile**

If Supported	MC_AccelerationProfile	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis		
B	TimeAcceleration		
VAR_INPUT			
B	Execute		
E	ContinuousUpdate		
E	TimeScale		
E	AccelerationScale		
E	Offset		
E	BufferMode		
VAR_OUTPUT			
B	ProfileCompleted		
E	Busy		
E	Active		
E	CommandAborted		
B	Error		
E	ErrorID		

**Appendix B 3.17 MC\_SetPosition**

If Supported	MC_SetPosition	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Execute	Y	
B	Position	Y	
E	Relative	N	
E	ExecutionMode	N	
V	Mode	Y	
VAR_OUTPUT			
B	Done	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	

**Appendix B 3.18 MC\_SetOverride**

If Supported	MC_SetOverride	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Enable	Y	
B	VelFactor	Y	
E	AccFactor	Y	
E	JerkFactor	Y	
VAR_OUTPUT			
B	Enabled	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	

### Appendix B 3.19 MC\_ReadParameter & MC\_ReadBoolParameter

If Supported	MC_ReadParameter	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Enable	Y	
B	ParameterNumber	Y	PAR_NUM
VAR_OUTPUT			
B	Valid	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	
B	Value	Y	
V	TimeStamp	Y	

If Supported	MC_ReadBoolParameter	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Enable	Y	
B	ParameterNumber	Y	PAR_NUM
VAR_OUTPUT			
B	Valid	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	
B	Value	Y	
V	TimeStamp	Y	

Name	B/E	R/W	Supp . Y/N	Comments
CommandedPosition	B	R	Y	
SWLimitPos	E	R/W	N	
SWLimitNeg	E	R/W	N	
EnableLimitPos	E	R/W	N	
EnableLimitNeg	E	R/W	N	
EnablePosLagMonitoring	E	R/W	N	
MaxPositionLag	E	R/W	N	
MaxVelocitySystem	E	R	Y	
MaxVelocityAppl	B	R/W	Y	
ActualVelocity	B	R	Y	
CommandedVelocity	B	R	Y	
MaxAccelerationSystem	E	R	Y	
MaxAccelerationAppl	E	R/W	Y	
MaxDecelerationSystem	E	R	Y	
MaxDecelerationAppl	E	R/W	Y	
MaxJerkSystem	E	R	Y	
MaxJerkAppl	E	R/W	Y	
ActualPosition	V	R	Y	
ActualLinPosition	V	R	Y	
AuxiliaryInputValue	V	R	Y	
DriveActualPosition	V	R	Y	
MaxPositionAppl	V	R/W	Y	
MinPositionAppl	V	R/W	Y	

Name	B/E	R/W	Supp . Y/N	Comments
MaxPositionSystem	V	R	Y	
MinPositionSystem	V	R	Y	
OverflowPosition	V	R	Y	
UnderflowPosition	V	R	Y	
DemandPosition	V	R	Y	
DemandLinPosition	V	R	Y	
DemandVelocity	V	R	Y	
DemandAccel	V	R	Y	
DemandJerk	V	R	Y	
LastBufferedDemandPosition	V	R	Y	
LastBufferedDemandLinPosition	V	R	Y	
LastBufferedDemandVelocity	V	R	Y	
LastBufferedDemandAccel	V	R	Y	
LastBufferedDemandJerk	V	R	Y	
OverrideVelocityFactor	V	R/W	Y	
OverrideAccelFactor	V	R/W	Y	
OverrideJerkFactor	V	R/W	Y	
AnalogInput	V	R	Y	
AnalogOutput	V	W	Y	
AxisError	V	R	Y	
DigitalInput	V	R	Y	
DigitalOutput	V	R/W	Y	

**Table 4: Parameters for MC\_Read(Bool)Parameter and MC\_Write(Bool)Parameter**

### Appendix B 3.20 MC\_WriteParameter & MC\_WriteBoolParameter

If Supported	MC_WriteParameter	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Execute	Y	
B	ParameterNumber	Y	PAR_NUM
B	Value	Y	
E	ExecutionMode	N	
VAR_OUTPUT			
B	Done	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	

If Supported	MC_WriteBoolParameter	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Execute	Y	
B	ParameterNumber	Y	PAR_NUM
B	Value	Y	
E	ExecutionMode	N	
VAR_OUTPUT			
B	Done	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	

### Appendix B 3.21 MC\_ReadDigitalInput

If Supported	MC_ReadDigitalInput	Sup. Y/N	Comments
VAR_IN_OUT			
B	Input		
VAR_INPUT			
B	Enable		
E	InputNumber		
VAR_OUTPUT			
B	Valid		
E	Busy		
B	Error		
E	ErrorID		
B	Value		



### Appendix B 3.22 MC\_ReadDigitalOutput

If Supported	MC_ReadDigitalOutput	Sup. Y/N	Comments
VAR_IN_OUT			
B	Output		
VAR_INPUT			
B	Enable		
E	OutputNumber		
VAR_OUTPUT			
B	Valid		
E	Busy		
B	Error		
E	ErrorID		
B	Value		

### Appendix B 3.23 MC\_WriteDigitalOutput

If Supported	MC_WriteDigitalOutput	Sup. Y/N	Comments
VAR_IN_OUT			
B	Output		
VAR_INPUT			
B	Execute		
E	OutputNumber		
B	Value		
E	ExecutionMode		
VAR_OUTPUT			
B	Done		
E	Busy		
B	Error		
E	ErrorID		

### Appendix B 3.24 MC\_ReadActualPosition

If Supported	MC_ReadActualPosition	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Enable	Y	
VAR_OUTPUT			
B	Valid	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	
B	Position	Y	
V	TimeStamp	Y	

### Appendix B 3.25 MC\_ReadActualVelocity

If Supported	MC_ReadActualVelocity	Sup.Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Enable	Y	
VAR_OUTPUT			
B	Valid	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	
B	Velocity	Y	
V	TimeStamp	Y	

### Appendix B 3.26 MC\_ReadActualTorque

If Supported	MC_ReadActualTorque	Sup.Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Enable	Y	
VAR_OUTPUT			
B	Valid	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	
B	Torque	Y	
V	TimeStamp	Y	

### Appendix B 3.27 MC\_ReadStatus

If Supported	MC_ReadStatus	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Enable	Y	
VAR_OUTPUT			
B	Valid	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	
B	ErrorStop	Y	
B	Disabled	Y	
B	Stopping	Y	
E	Homing	Y	
B	Standstill	Y	
E	DiscreteMotion	Y	
E	ContinuousMotion	Y	
E	SynchronizedMotion	Y	
V	ConstantVelocity	Y	
V	Accelerating	Y	
V	Decelerating	Y	
V	TimeStamp	Y	

### Appendix B 3.28 MC\_ReadMotionState

If Supported	MC_ReadMotionState	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis		
VAR_INPUT			
B	Enable		
E	Source		
VAR_OUTPUT			
B	Valid		
E	Busy		
B	Error		
E	ErrorID		
E	ConstantVelocity		
E	Accelerating		
E	Decelerating		
E	DirectionPositive		
E	DirectionNegative		

### Appendix B 3.29 MC\_ReadAxisInfo

If Supported	MC_ReadAxisInfo	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis		
VAR_INPUT			
B	Enable		
VAR_OUTPUT			
B	Valid		
E	Busy		
B	Error		
E	ErrorID		
E	HomeAbsSwitch		
E	LimitSwitchPos		
E	LimitSwitchNeg		
E	Simulation		
E	CommunicationReady		
E	ReadyForPowerOn		
E	PowerOn		
E	IsHomed		
E	AxisWarning		

### Appendix B 3.30 MC\_ReadAxisError

If Supported	MC_ReadAxisError	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Enable	Y	
VAR_OUTPUT			
B	Valid	Y	
E	Busy	Y	
B	Error	Y	
B	ErrorID	Y	
E	AxisErrorID	Y	
V	TimeStamp	Y	

### Appendix B 3.31 MC\_Reset

If Supported	MC_Reset	Sup. Y/N	Comments
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VAR_IN_OUT			
B	Axis	Y	AXIS_REF
VAR_INPUT			
B	Execute	Y	
VAR_OUTPUT			
B	Done	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	

### Appendix B 3.32 MC\_DigitalCamSwitch

If Supported	MC_DigitalCamSwitch	Sup.Y/N	Comments
VAR_IN_OUT			
B	Axis		
B	Switches		
E	Outputs		
E	TrackOptions		
VAR_INPUT			
B	Enable		
E	EnableMask		
E	ValueSource		
VAR_OUTPUT			
B	InOperation		
E	Busy		
B	Error		
E	ErrorID		

Basic elements within the array structure of MC\_CAMSWITCH\_REF

B/E	Parameter	Sup.Y/N	Comments
B	TrackNumber		
B	FirstOnPosition [u]		
B	LastOnPosition [u]		
E	AxisDirection		
E	CamSwitchMode		
E	Duration		

Basic elements within the array structure of MC\_TRACK\_REF

B/E	Parameter	Sup.Y/N	Comments
E	OnCompensation		
E	OffCompensation		
E	Hysteresis [u]		

### Appendix B 3.33 MC\_TouchProbe

If Supported	MC_TouchProbe	Sup.Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
E	TriggerInput	N	
VAR_INPUT			
B	Execute	Y	
V	RecordedPositionNumber	Y	
E	WindowOnly	Y	
E	FirstPosition	Y	
E	LastPosition	Y	
VAR_OUTPUT			
B	Done	Y	
E	Busy	Y	
E	CommandAborted	Y	
B	Error	Y	
E	ErrorID	Y	
B	RecordedPosition	Y	

### Appendix B 3.34 MC\_AbortTrigger

If Supported	MC_AbortTrigger	Sup.Y/N	Comments
VAR_IN_OUT			
B	Axis	Y	AXIS_REF
E	TriggerInput	N	
VAR_INPUT			
B	Execute	Y	
V	RecordedValueNumber	Y	
VAR_OUTPUT			
B	Done	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	

### Appendix B 3.35 MC\_CamTableSelect

If Supported	MC_CamTableSelect	Sup. Y/N	Comments
VAR_IN_OUT			
E	Master	N	
E	Slave	N	
B	CamTable	N	Implemented by CAM_TABLE_REF
VAR_INPUT			
B	Execute	Y	
V	SlavePositionArray	Y	
V	MasterPositionArray	Y	
E	Periodic	Y	
E	MasterAbsolute	N	
E	SlaveAbsolute	N	
E	ExecutionMode	N	
VAR_OUTPUT			
B	Done	Y	
E	Busy	Y	
B	Error	Y	
E	ErrorID	Y	
E	CamTableID	N	
V	CamTableRef	Y	

### Appendix B 3.36 MC\_CamIn

If Supported	MC_CamIn	Sup. Y/N	Comments
VAR_IN_OUT			
B	Master	Y	MASTER_AXIS_REF
B	Slave	Y	SLAVE_AXIS_REF
V	CamTableRef	Y	
VAR_INPUT			
B	Execute	Y	
E	ContinuousUpdate	N	
E	MasterOffset	Y	
E	SlaveOffset	Y	
E	MasterScaling	Y	
E	SlaveScaling	Y	
E	MasterStartDistance	Y	
E	MasterSyncPosition	Y	
E	StartMode	N	
E	MasterValueSource	Y	
E	CamTableID	N	
V	Velocity	Y	
V	Acceleration	Y	
V	Deceleration	Y	
V	Jerk	Y	
E	BufferMode	Y	
VAR_OUTPUT			
B	InSync	Y	
E	Busy	Y	
E	Active	Y	
E	CommandAborted	Y	
B	Error	Y	
E	ErrorID	Y	
E	EndOfProfile	Y	

### Appendix B 3.37 MC\_CamOut

If Supported	MC_CamOut	Sup. Y/N	Comments
VAR_IN_OUT			
B	Slave		
VAR_INPUT			
B	Execute		
VAR_OUTPUT			
B	Done		
E	Busy		
B	Error		
E	ErrorID		

### Appendix B 3.38 MC\_GearIn

If Supported	MC_GearIn	Sup. Y/N	Comments
VAR_IN_OUT			
B	Master	Y	MASTER_AXIS_REF
B	Slave	Y	SLAVE_AXIS_REF
VAR_INPUT			
B	Execute	Y	
E	ContinuousUpdate	N	
B	RatioNumerator	Y	
B	RatioDenominator	Y	
E	MasterValueSource	Y	
E	Acceleration	Y	
E	Deceleration	Y	
E	Jerk	Y	
E	BufferMode	Y	
VAR_OUTPUT			
B	InGear	Y	
E	Busy	Y	
E	Active	Y	
E	CommandAborted	Y	
B	Error	Y	
E	ErrorID	Y	

### Appendix B 3.39 MC\_GearOut

If Supported	MC_GearOut	Sup. Y/N	Comments
VAR_IN_OUT			
B	Slave		
VAR_INPUT			
B	Execute		
VAR_OUTPUT			
B	Done		
E	Busy		
B	Error		
E	ErrorID		

### Appendix B 3.40 MC\_GearInPos

If Supported	MC_GearInPos	Sup.Y/N	Comments
VAR_IN_OUT			
B	Master	Y	MASTER_AXIS_REF
B	Slave	Y	SLAVE_AXIS_REF
VAR_INPUT			
B	Execute	Y	
B	RatioNumerator	Y	
B	RatioDenominator	Y	
E	MasterValueSource	Y	
B	MasterSyncPosition	Y	
B	SlaveSyncPosition	Y	
E	SyncMode	N	
E	MasterStartDistance	Y	
E	Velocity	Y	
E	Acceleration	Y	
E	Deceleration	Y	
E	Jerk	Y	
E	BufferMode	Y	
VAR_OUTPUT			
E	StartSync	Y	
B	InSync	Y	
E	Busy	Y	
E	Active	Y	
E	CommandAborted	Y	
B	Error	Y	
E	ErrorID	Y	

### Appendix B 3.41 MC\_PhasingAbsolute

If Supported	MC_PhasingAbsolute	Sup. Y/N	Comments
VAR_IN_OUT			
B	Master		
B	Slave		
VAR_INPUT			
B	Execute		
V	MasterValueSource		
B	PhaseShift		
E	Velocity		
E	Acceleration		
E	Deceleration		
E	Jerk		
E	BufferMode		
VAR_OUTPUT			
B	Done		
E	Busy		
E	Active		
E	CommandAborted		
B	Error		
E	ErrorID		
E	AbsolutePhaseShift		



### Appendix B 3.42 MC\_PhasingRelative

If Supported	MC_PhasingRelative	Sup. Y/N	Comments
VAR_IN_OUT			
B	Master		
B	Slave		
VAR_INPUT			
B	Execute		
V	MasterValue_Source		
B	PhaseShift		
E	Velocity		
E	Acceleration		
E	Deceleration		
E	Jerk		
E	BufferMode		
VAR_OUTPUT			
B	Done		
E	Busy		
E	Active		
E	CommandAborted		
B	Error		
E	ErrorID		
E	CoveredPhaseShift		

### Appendix B 3.43 CombineAxes

If Supported	MC_CombineAxes	Sup. Y/N	Comments
VAR_IN_OUT			
B	Master1		
B	Master2		
B	Slave		
VAR_INPUT			
B	Execute		
E	ContinuousUpdate		
E	CombineMode		
E	GearRationNumeratorM1		
E	GearRatioDenominatorM1		
E	GearRatioNumeratorM2		
E	GearRatioDenominatorM2		
E	MasterValueSourceM1		
E	MasterValueSourceM2		
E	BufferMode		
VAR_OUTPUT			
B	InSync		
E	Busy		
E	Active		
E	CommandAborted		
B	Error		
E	ErrorID		

## Appendix B 4. The PLCopen Motion Control Logo and Its Usage

For quick identification of compliant products, PLCopen has developed a logo for the Motion Control Function Blocks:



**Figure 1: The PLCopen Motion Control Logo**

This motion control logo is owned and trademarked by PLCopen.

In order to use this logo free-of-charge, the relevant company has to fulfill all the following requirements:

1. the company has to be a voting member of PLCopen;
2. the company has to comply with the existing specification, as specified by the PLCopen Task Force Motion Control, and as published by PLCopen, and of which this statement is a part;
3. this compliance application is provided in written form by the company to PLCopen, clearly stating the applicable software package and the supporting elements of all the specified tables, as specified in the document itself;
4. in case of non-fulfillment, which has to be decided by PLCopen, the company will receive a written statement concerning this from PLCopen. The company will have a one month period to either adopt their software package in such a way that it complies, represented by the issuing of a new compliance statement, or remove all reference to the specification, including the use of the logo, from all their specification, be it technical or promotional material;
5. the logo has to be used as is - meaning the full logo. It may be altered in size providing the original scale and color setting is kept.
6. the logo has to be used in the context of Motion Control.