



Subset of the

Technical Specification

PLCopen - Technical Committee 2 – Task Force

Function blocks for motion control

Version 1.1

Appendix A :

Compliance Procedure and Compliance List

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July 2005

Appendix A. 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 (see Appendix A 2 Supported Data types) and supported Function Blocks, in combination with the applicable inputs and outputs (see Appendix A 3 Overview of the Function Blocks and its paragraphs). The supplier is required 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 , as well as a shortform overview, as specified in Appendix A 2 Supported Data types and Appendix A 3 Overview of the Function Blocks.

In addition to this approval, the supplier is granted access and usage rights of the PLCopen Motion Control logo, as described in chapter Appendix A 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.

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

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 A 1. Statement of Supplier

Supplier name	Yaskawa Electric America, Inc.
Supplier address	2121 Norman Drive South
City	Waukegan, Illinois
Country	USA
Telephone	(847) 887-7382
Fax	(847) 887-7280
Email address	jamie_solt@yaskawa.com
Product Name	MotionWorks IEC
Product version	Ver 1.50
Release date	15/01/2008

I hereby state that the following tables as filled out and submitted do match our product as well as the accompanying user manual (will be supplied at a later date), as stated above.

Name of representation (person): Jamie Solt

Date of signature (dd/mm/yyyy): 13/11/2007

Signature:



Appendix A 2. Supported Data types

Defined datatypes with MC library:	Supported	If not supported, which datatype used
BOOL	Yes	
INT	Yes	
WORD	Yes	
REAL	Yes	LREAL replaces REAL
ENUM	Yes	

Table 1: Supported datatypes

Within the specification the following derived datatypes are defined. Which structure is used in this system:

Derived datatypes:	Where used	Supported	Which structure
Axis_Ref	Nearly all FBs	Yes	
MC_Direction (extended)	MC_MoveAbsolute MC_MoveVelocity	Yes Yes	
MC_TP_REF	MC_PositionProfile	Yes	
MC_TV_REF	MC_VelocityProfile	Yes	
MC_TA_REF	MC_AccelerationProfile	Yes	
MC_CAM_REF	MC_CamTableSelect	Yes	
MC_CAM_ID (extended)	MC_CamTableSelect MC_CamIn	Yes Yes	
MC_StartMode (extended)	MC_CamIn	Yes	
MC_BufferMode	Buffered FBs	Yes	

Table 2: Supported derived datatypes

Appendix A 3. Overview of the Function Blocks

Single Axis Function Blocks	Supported Yes / No	Comments (<= 48 char.)
MC_MoveAbsolute	Yes	
MC_MoveRelative	Yes	
MC_MoveAdditive	Yes	
MC_MoveSuperimposed	Yes	
MC_MoveVelocity	Yes	
MC_Home	No	Not supported by YEA. Part V will be supported.
MC_Stop	Yes	
MC_Power	Yes	
MC_ReadStatus	Yes	
MC_ReadAxisError	Yes	
MC_Reset	Yes	
MC_ReadParameter	Yes	
MC_ReadBoolParameter	Yes	
MC_WriteParameter	Yes	
MC_WriteBoolParameter	Yes	
MC_ReadActualPosition	Yes	
MC_PositionProfile	Yes	
MC_VelocityProfile	Yes	
MC_AccelerationProfile	Yes	
Multi-Axis Function Blocks	Supported Yes / No	Comments (<= 48 char.)
MC_CamTableSelect	Yes	
MC_CamIn	Yes	
MC_CamOut	Yes	
MC_GearIn	Yes	
MC_GearOut	Yes	
MC_Phasing	No	

Table 3: Short overview of the Function Blocks

Appendix A 3.1 MoveAbsolute

If Supported	MC_MoveAbsolute	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Yes	
VAR_INPUT			
B	Execute	Yes	
B	Position	Yes	
E	Velocity	Yes	
E	Acceleration	Yes	
E	Deceleration	Yes	
E	Jerk	Yes	
E	Direction	Yes	Direction types are only valid when used with a rotary axis. None of the direction options are available for a linear axis.
E	BufferMode	Yes	
VAR_OUTPUT			
B	Done	Yes	
E	Busy	Yes	
E	Active	Yes	
E	CommandAborted	Yes	
B	Error	Yes	
E	ErrorID	Yes	

Appendix A 3.2 MoveRelative

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

Appendix A 3.3 MoveAdditive

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

Appendix A 3.4 MoveSuperimposed

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

Appendix A 3.5 MoveVelocity

If Supported	MC_MoveVelocity	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Yes	
VAR_INPUT			
B	Execute	Yes	
E	Velocity	Yes	
E	Acceleration	Yes	
E	Deceleration	Yes	
E	Jerk	Yes	
E	Direction	Yes	If current_direction and velocity = 0, then an error condition will occur
E	BufferMode	Yes	
VAR_OUTPUT			
B	InVelocity	Yes	
E	Busy	Yes	
E	Active	Yes	
E	CommandAborted	Yes	
B	Error	Yes	
E	ErrorID	Yes	

Appendix A 3.6 Home

This FB is not supported by YEA. Instead, Part 5 – Homing will be supported.

Appendix A 3.7 Stop

If Supported	MC_Stop	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Yes	
VAR_INPUT			
B	Execute	Yes	
E	Deceleration	Yes	
E	Jerk	Yes	
E	BufferMode	Yes	
V	StopTime	Yes	Technical units = mSecs
VAR_OUTPUT			
B	Done	Yes	
E	Busy	Yes	
E	Active	Yes	
E	Command- Aborted	Yes	
B	Error	Yes	
E	ErrorID	Yes	

Appendix A 3.8 Power

If Supported	MC_Power	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Yes	
VAR_INPUT			
B	Enable	Yes	
E	Enable_Positive	Yes	
E	Enable_Negative	Yes	
E	BufferMode	Yes	
VAR_OUTPUT			
B	Status	Yes	
E	Busy	Yes	
E	Active	Yes	
B	Error	Yes	
E	ErrorID	Yes	

Appendix A 3.9 ReadStatus

If Supported	MC_ReadStatus	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Yes	
VAR_INPUT			
B	Enable	Yes	
VAR_OUTPUT			
B	Valid	Yes	
E	Busy	Yes	
B	Error	Yes	
E	ErrorID	Yes	
B	Disabled	Yes	
B	Errorstop	Yes	
B	Stopping	Yes	
B	StandStill	Yes	
B	DiscreteMotion	Yes	
B	ContinuousMotion	Yes	
E	SynchronizedMotion	Yes	
E	Homing	Yes	
E	ConstantVelocity	Yes	
E	Accelerating	Yes	
E	Decelerating	Yes	

Appendix A 3.10 ReadAxisError

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

Appendix A 3.11 Reset

If Supported	MC_Reset	Sup. Y/N	Comments
VAR_IN_OUT			
B	Axis	Yes	
VAR_INPUT			
B	Execute	Yes	
VAR_OUTPUT			
B	Done	Yes	
E	Busy	Yes	
B	Error	Yes	If axis alarms are still present, then the Error bit will be FALSE.
B	ErrorID	Yes	

Appendix A 3.12 ReadParameter

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

Appendix A 3.13 ReadBoolParameter

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

Name	B/E	R/W	Supp . Y/N	Comments
CommandedPosition	B	R	Yes	
SWLimitPos	E	R/W	Yes	
SWLimitNeg	E	R/W	Yes	
EnableLimitPos	E	R/W	Yes	
EnableLimitNeg	E	R/W	Yes	
EnablePosLagMonitoring	E	R/W	No	
MaxPositionLag	E	R/W	No	
MaxVelocitySystem	E	R	Yes	
MaxVelocityAppl	B	R/W	No	
ActualVelocity	B	R	Yes	
CommandedVelocity	B	R	Yes	
MaxAccelerationSystem	E	R	No	
MaxAccelerationAppl	E	R/W	No	
MaxDecelerationSystem	E	R	No	
MaxDecelerationAppl	E	R/W	No	
MaxJerk	E	R/W	Yes	

Table 4: Parameters for ReadParameter and WriteParameter

Appendix A 3.14 WriteParameter

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

Appendix A 3.15 WriteBoolParameter

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

Appendix A 3.16 ReadActualPosition

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

Appendix A 3.17 PositionProfile

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

Appendix A 3.18 VelocityProfile

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

Appendix A 3.19 AccelerationProfile

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

Appendix A 3.20 CamTableSelect

If Supported	MC_CamTableSelect	Sup. Y/N	Comments
VAR_IN_OUT			
B	Master	Yes	
B	Slave	Yes	
B	CamTable	Yes	
VAR_INPUT			
B	Execute	Yes	
E	Periodic	Yes	
E	MasterAbsolute	No	
E	SlaveAbsolute	No	
VAR_OUTPUT			
B	Done	Yes	
E	Busy	Yes	
B	Error	Yes	
E	ErrorID	Yes	
E	CamTableID	Yes	

Appendix A 3.21 CamIn

If Supported	MC_CamIn	Sup. Y/N	Comments
VAR_IN_OUT			
B	Master	Yes	
B	Slave	Yes	
VAR_INPUT			
B	Execute	Yes	
E	MasterOffset	No	
E	SlaveOffset	No	
E	MasterScaling	No	
E	SlaveScaling	No	
E	StartMode	No	
E	CamTableID	Yes	
E	BufferMode	Yes	
V	WaitForEngage	Yes	
V	EngagePosition	Yes	
VAR_OUTPUT			
B	InSync	Yes	
E	Busy	Yes	
E	Active	Yes	
E	CommandAborted	Yes	
B	Error	Yes	
E	ErrorID	Yes	
E	EndOfProfile	Yes	

Appendix A 3.22 CamOut

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

Appendix A 3.23 GearIn

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

Appendix A 3.24 GearOut

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

Appendix A 3.25 Phasing

This FB is not supported by YEA.

Appendix A 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.