Operating instructions

PAC-Servo

231510

as of Version 3.60

Edition 05/2005
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<td>8</td>
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<td>1</td>
</tr>
</tbody>
</table>
These operating instructions contain the necessary information for the intended use of the described product.
It should be used by technically qualified personnel who are specially trained or who possess appropriate knowledge of measuring and control technology.

These operating instructions should be read carefully before installing and starting-up the control!
1.1 System concept

The PAC-Servo is a positioning and sequence controller for servo drives. The unit is 19" in size. The PAC-Servo can optionally be fitted with a complete alphanumeric keyboard and two-line LCD display or a front panel with a 7-segment status display.

Performance features:

- extensive, powerful instruction set
- 110kB battery-buffered programme storage
  In the course of further development it is possible that the available storage space may vary.
- 2 serial interfaces (RS232/RS485 or 2 x RS232)
- 16 inputs and outputs, decoupled by means of optocouplers (can be expanded up to max. 452 inputs and 452 outputs)
- Output analog voltage (±10V)
- I/O processing is possible during the positioning process

The units may be designed on the basis of the 19" system dependant upon installation specifications. The units are available with 19" or 19"/2 width in the case of the 19" design.

The units can be equipped optionally with a full-complement, alphanumeric keyboard and two-line, illuminated liquid-crystal display (2*40 characters) or a front panel with a 7-segment status display. On units with a full-complement, alphanumeric keyboard, a key-operated switch permits the system to be locked against unauthorized access.

On all units, programming can be carried out using the PROPAC program package on a PC running under MS DOS. On units with 7-segment status display, programming and commissioning are always carried out with the PROPAC program package.

The PROPAC program package permits convenient off-line program development. In addition, the PA-CONTROL can be operated fully via the PC on all units.

The descriptions of the individual menu levels, the instructions and various system messages relate to a unit equipped with front panel with keyboard and liquid-crystal display. It applies virtually analogously to using a PC in conjunction with PROPAC.

Exceptions relating to operation with the PC:

- "Key-operated switch" is always set to "Program"
- "STOP" corresponds to the space bar on the PC keyboard
- "START" corresponds to key "s" on the PC keyboard

Please refer to the PROPAC description for further information.
1.2 Conformity Declaration

IEF Werner GmbH
Wendelhofstr. 6
78120 Furtwangen

Product Range  PAC-Compact, PAC-Controller, PAC-Single
LV-Unit, PAC-Unit, LV-Single

The following standards are applicable:

89/336/EWG Electromechanical compatibility
EN 50081-1  Special standard emissive disturbances
EN 50081-2
pr EN 50082-1  Special standard resistance to jamming
pr EN 50082-2

Test procedures:

IEC 801-2/Level 3  Resistance to jamming due to electrostatic discharge (ESD)
IEC 801-3/Level 3  Resistance to jamming due to electrostatic fields
IEC 801-4/Level 3  Resistance to jamming due to fast transient disturbances
IEC 801-5/Level 3  Resistance to jamming due to voltage (Surge)
EN 55011/Class B  Limiting values and measuring methods for radio disturbances

Date  Authorised Signature (Managing Director)

This statement does not contain any assurance of features.
The safety and protection regulations of the operation instruction have to be strictly observed.
Above mentioned company places the following techn. documents at disposal for inspection:

- Operating instruction conforming to specification  User  EU-Authorities
  X  X
- User-Software  X  X
- Plans / Software-source coding  X
- Description of the methods to assure conformity  X
- Test records  X
- Other technical documentations  X
1.3 Safety Instructions

Observe the instructions and warnings contained in the operating instructions that are identified as follows:

⚠️ Failure to observe these instructions and warnings may lead to dangerous voltages.

⚠️ This sign indicates warnings and instructions referring to general danger spots.

1.3.1 Connection Instructions

⚠️ Observe the discharging time for the condenser!

- After disconnecting the control the condensers are charged with a high voltage for a short period of time. Do not handle the device until 5 minutes after switching off.
- Installation and start-up should only be carried out by qualified personnel.
- Observe the general installation regulations for assembling and operating electrical operating systems (VDE 0100, VDE 0113) (Association of German Electricians).
- Protective equipment for humans and machine should comply with local conditions and regulations.
- **Do not clamp or disconnect** power or control cable whilst the control is still connected to the mains.
- Plugs may only be connected and/or removed when inactive.
- Lay shielded and separated control and load leads at a 10 cm distance (see appendix).
- Protection Class IP20

⚠️ When carrying out assembly, disassembly and repair work, when replacing individual components and switching the operating voltage the control should be currentless.
1.3.2 Ambient Conditions

- The limit values for the ambient temperature min. 0°C to max. 40°C, must be adhered to.
- **No mist or water** should enter the control.
- **Avoid dust** entering the control.
- The control should be protected against aggressive gases and liquids.
- Ensure that air can circulate freely (air inlet and outlet ports must be kept free).

1.3.3 Operating Instructions

- **It is imperative** that the parameter values are checked in accordance with the current conditions.

- When using the programme examples contained in the operating instructions, always check whether the programme can be implemented on the machine in question.
1.4 Technical data

Ambient temperature: 0°C to 40 °C

Supply voltage: 24VDC +/- 15%, residual ripple <10%

Power consumption: approx. 30 VA

16 signal inputs (capable of extension to 452*)

- Opto-decoupled
- 24 VDC
- Typical input current 5 mA
- Low level 0 - 3 VDC
- High level 12 - 30 VDC

16 signal outputs (capable of extension to 452*)

- Opto-decoupled
- Positive-switching
- 24 V DC/0.5 A (ohmic load)
- Max. 2 A per card

Connections LR11 and LR12:

- 2 limit switch inputs per axis (PNP NC contact)
  See signal inputs for specification

- 1 additional reference switch (PNP NC contact)
  See signal inputs for specification

- 1 controller release per axis (PNP NO contact)
  24 V DC / 200 mA

- 1 input, drive booster ready
  See signal inputs for specification

- 1 output, rotational speed setpoint value
  Range: -10 V to +10 V (resolution 5 mV)
  Internal resistance 100 Ohm

Encoder (TTL push-pull signal)

- For channels A, B and zero pulse
- Phase shift A-B 90 degrees
- Encoder frequency max. 200 kHz
- Output for encoder supply 5 V DC +/-5%; max. 200 mA

*The possible maximum number of inputs and outputs may be limited due to additional control option cards.
<table>
<thead>
<tr>
<th>Data buffering</th>
<th>Lithium battery, service life minimum 5 years</th>
</tr>
</thead>
<tbody>
<tr>
<td>Protection Class</td>
<td>IP20</td>
</tr>
<tr>
<td>Weight</td>
<td></td>
</tr>
<tr>
<td>19&quot;-housing</td>
<td>4.8kg</td>
</tr>
<tr>
<td>19&quot;/2-housing</td>
<td>3.4kg</td>
</tr>
</tbody>
</table>
1.5 Outer dimensions

PA-CONTROL 19"/2 -3HE

If necessary, the unit can be incorporated in a desktop housing.
PA-CONTROL 19" -3HE

If necessary, the unit can be incorporated in a desktop housing.
1.6 Installation in a system rack

Ensure that the air can enter and exit freely.
# 2 Operator interface

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Important:

In the case of units with a 7-segment status display and also the PA-CONTROL-SC, the front panel can be simulated on the PC with the aid of the program development system PROPAC. Communication with the controller is via a serial interface. This gives the same operating possibilities as with units which have an alphanumeric keyboard and an LCD display.

2.1 The Keyboard

The PA-CONTROL has a full-complement, alphanumeric keyboard (0-9, A-Z). Certain special keys whose functions are described below are also provided.

<table>
<thead>
<tr>
<th>Special keys</th>
<th>Name</th>
<th>Function</th>
</tr>
</thead>
<tbody>
<tr>
<td>ESC</td>
<td>ESC key</td>
<td>Quit sub-menu, Abort in input field</td>
</tr>
<tr>
<td>ALT</td>
<td>ALT key</td>
<td>No function assigned as yet</td>
</tr>
<tr>
<td>CTRL</td>
<td>CTRL key</td>
<td>No function assigned as yet</td>
</tr>
<tr>
<td>SHIFT</td>
<td>SHIFT key</td>
<td>Calling dual assignment of alphanumeric keys, additional key for cursor keys</td>
</tr>
<tr>
<td>↓↓↓↓</td>
<td>Arrow down key</td>
<td>Paging in the menu to the next line (with Autorepeat)</td>
</tr>
<tr>
<td>↑↑↑↑</td>
<td>Arrow up key</td>
<td>Paging in the menu to the previous line (with Autorepeat)</td>
</tr>
<tr>
<td>→→→→</td>
<td>Move cursor one character to the right in the input field (with Autorepeat)</td>
<td></td>
</tr>
<tr>
<td>←←←←</td>
<td>Move cursor one character to the left in the input field (with Autorepeat)</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Space bar</td>
<td>Insert blanks in the editor (when programming)</td>
</tr>
<tr>
<td>ENTER</td>
<td>ENTER key</td>
<td>Terminate Enter, Terminate line in the editor</td>
</tr>
<tr>
<td>INS</td>
<td>INS key</td>
<td>No function assigned as yet</td>
</tr>
<tr>
<td>DEL</td>
<td>DEL key</td>
<td>Deletes the character at which the cursor is positioned</td>
</tr>
<tr>
<td>START</td>
<td>START key</td>
<td>Starts Automatic mode</td>
</tr>
<tr>
<td>STOP</td>
<td>STOP key</td>
<td>Stops Automatic mode</td>
</tr>
<tr>
<td>Automatik</td>
<td>KEY-operated switch</td>
<td>Access interlock for front panel (the key can be withdrawn in the position shown and then only „Automatic“ is possible).</td>
</tr>
</tbody>
</table>
2.2 General operation

Note:

Differences in menu structure may arise due to the control equipment or the different types of devices.

The basic menu is shown on the display after the PA-CONTROL is switched on.

```
PA-CONTROL Vxx.xx
1 = Automatic
```

The operator interface of the PA-CONTROL is subdivided into a menu structure. The main menu and the various sub-menus are structured and can be operated on the basis of the same principle.

Menu principle:

```
Menu title
1 = First sub-menu option
```

2 = Second sub-menu option
3 = Third sub-menu option
...
...
9 = Ninth sub-menu option

The number of menu sub-options in the individual menus has been matched to the requirements and limited to 9. Since only two lines are available on the display, only the title and one of the menu sub-options are displayed on the current menu.

Moving through the menu interface:

<table>
<thead>
<tr>
<th>Key</th>
<th>Action / Effect</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arrow down</td>
<td>Next menu sub-option is displayed</td>
</tr>
<tr>
<td>Arrow up</td>
<td>Previous menu sub-option is displayed</td>
</tr>
<tr>
<td>SHIFT + Arrow up</td>
<td>First menu sub-option is displayed</td>
</tr>
<tr>
<td>SHIFT + Arrow down</td>
<td>Last menu sub-option is displayed</td>
</tr>
<tr>
<td>ENTER</td>
<td>Activating the displayed menu sub-option</td>
</tr>
<tr>
<td>ESC</td>
<td>Quitting sub-menu and returning to the previous menu (the first menu line is displayed in the case of the main menu)</td>
</tr>
</tbody>
</table>

One other method of activating a menu option is to press the key with the number prefixed to the menu option.
2.2.1 Input field

If the operator is requested to enter a numerical value (parameter value, register value, ...), an input field is shown on the display. The input field is delimited by brackets [ ...... ]. The current value and the cursor (blinking field on the display) are located between these two brackets. The operator can update the entry by pressing the corresponding keys.

Key assignment in the input field:

<table>
<thead>
<tr>
<th>Key</th>
<th>Response / Effect</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arrow left</td>
<td>Moves cursor one character to the left</td>
</tr>
<tr>
<td>Arrow right</td>
<td>Moves cursor one character to the right</td>
</tr>
<tr>
<td>SHIFT + DEL</td>
<td>Deletes character to the left of the cursor</td>
</tr>
<tr>
<td>DEL</td>
<td>Deletes character at which the cursor is positioned</td>
</tr>
<tr>
<td>ENTER</td>
<td>Terminating an entry. The entered value is checked and, if it lies within the permit-</td>
</tr>
<tr>
<td></td>
<td>ted limits, is accepted. If the actual value lies above or below the permitted limits,</td>
</tr>
<tr>
<td></td>
<td>an error message is displayed and the system awaits entry of a new value.</td>
</tr>
<tr>
<td>ESC</td>
<td>Aborting the entry. The previous value is retained</td>
</tr>
</tbody>
</table>
2.2.2 Entering the program name

If the control awaits entry of a program name, you will see the following on the display.

```
Please enter new program name!
[ _     ]
```

The cursor (blinking field on the display) is positioned at the first position of the input field. The operator must now press the keys assigned to the letters of the required program name. Complete the entry by pressing key "ENTER" after you have entered all letters of the program name. The program name entered must comply with certain conditions (see below) and is then checked for this. The following message is displayed if the conditions are not fulfilled:

```
ERROR: Illegal program name!
Program: 5ANTON
```

You can acknowledge the error message by pressing a key and then correct the error in the input field.

The program name must comply with the following conditions:

- the first character must be a letter
- blanks are not permitted within the name
- the length is limited to 8 characters
- only "_" and "-" are practical for use as special characters
- upper-case letters

Moving the cursor in the input field:

<table>
<thead>
<tr>
<th>Key</th>
<th>Response / Effect</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arrow left</td>
<td>Moves cursor one character to the left</td>
</tr>
<tr>
<td>Arrow right</td>
<td>Moves cursor one character to the right</td>
</tr>
<tr>
<td>SHIFT + DEL</td>
<td>Deletes character to the left of the cursor</td>
</tr>
<tr>
<td>DEL</td>
<td>Deletes character at which the cursor is located</td>
</tr>
<tr>
<td>ENTER</td>
<td>Terminates an entry</td>
</tr>
</tbody>
</table>
2.2.3 Selecting a name from the program list

If you wish to access an existing program (e.g. to modify the program or to select it and define it as a start program etc.), you are offered an alphabetically sorted list of the existing programs allowing for the possible program types.

<table>
<thead>
<tr>
<th>Program list, please select!</th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>Program: 1 EXAMPLE.PNC</td>
<td></td>
</tr>
</tbody>
</table>

There are two selection options:

1. You can page in the list with keys "Arrow up" and "Arrow down" until the required program is displayed. You can then complete selection by pressing key "ENTER" and the program is then accepted for the action.

2. A blank input field ([   ]) is displayed at the end of the first display line. You can enter the name of the required program in this input field using the keyboard. The characters entered on the keyboard are accepted only if a program name with the same character string exists. The display (second display line) is corrected in accordance with the input field after each character entered.

<table>
<thead>
<tr>
<th>Program list, please select!</th>
<th>E</th>
</tr>
</thead>
<tbody>
<tr>
<td>Program: 5 EXAMPLE.PNC</td>
<td></td>
</tr>
</tbody>
</table>

You terminate selection by pressing key "ENTER", and the displayed program is then accepted from the second display line for the action.

You can delete the contents of the input field by pressing keys "Arrow down" or "Arrow up".
## 2.3 Menu structure PA-CONTROL

<table>
<thead>
<tr>
<th>main-menu</th>
<th>sub-menu</th>
</tr>
</thead>
</table>
| 1 = Automatic | - Start  
- Stop |
| 2 = Manuel | 1 = Approach reference point  
2 = Axes manual via front panel |
| 3 = Edit program | 1 = Display directory  
2 = Edit new program  
3 = Edit existing program  
4 = Copy program  
5 = Rename program  
6 = Delete program  
7 = Print program  
8 = Show memory  
9 = Transfer program * |
| 4 = Program test and diagnosis | 1 = Program test  
2 = Inputs  
3 = Outputs  
4 = Flags (Marker)  
5 = Real number register (R)  
6 = Integer number register (N)  
7 = Closed loop test  
8 = Limit switch / Standby  
9 = Counter |
| 5 = Sequence definition | 1 = Start program  
2 = Program after Stop  
3 = Program Start after Stop  
4 = Program afterFault  
5 = Labelling  
6 = Program protection |
| 6 = Parameter | 1 = Edit system parameter  
2 = Edit axis parameter  
3 = Edit ASI-BUS |
| 7 = Basic settings | 1 = Bootload system parameters  
2 = Bootload axis parameters  
3 = Clear program memory  
4 = Re-initialize PA-CONTROL |
| 8 = System diagnosis | 1 = Display PA-CONTROL-type  
2 = Keyboard test  
3 = Stop key test  
4 = Start key test  
5 = Key switch test  
6 = Test serial interface 1  
7 = Test serial interface 2  
8 = Interbus-S monitor ** |
| 9 = Communication with Modem | 1 = Communication with Modem  
2 = Edit Modem settings  
3 = Reset Modem settings |

* only with equipment PAB (option)  
** only with equipment Counter board (option, only by PAC, PAC-Compact, PAC-Servo)  
*** only with equipment Interbus-S board (option)
2.4 Automatic

In Automatic mode, the program defined as the start program is run. Other programs can be called as subroutines. A running program can be interrupted with "STOP". The program is started or an interrupted program can be continued with "START". The required input is assigned via the parameter level for functions external START and STOP (see Chapter Parameters).

Input/Key

<table>
<thead>
<tr>
<th>STOP</th>
<th>START</th>
</tr>
</thead>
<tbody>
<tr>
<td>H</td>
<td>H</td>
</tr>
<tr>
<td>L</td>
<td>L</td>
</tr>
</tbody>
</table>

- **STOP**: Stop program run
- **START**: Start program run (new start)
- **H**: High level
- **L**: Low level

Diagram:

- Start program run (new start)
- Stop program run
- Continue program run after stop
- Stop program run
- Program down
- Start program run (new start)
2.5 Manual

Overview, Manual menu

You are offered the following selection after you change to this menu option.

<table>
<thead>
<tr>
<th>Manual</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 = Approach reference point</td>
</tr>
<tr>
<td>2 = Axes manually via front panel</td>
</tr>
</tbody>
</table>

2.5.1 Reference travel

You are offered the following selection after you change to this menu option.

<table>
<thead>
<tr>
<th>Reference travel</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 = X</td>
</tr>
<tr>
<td>2 = Y</td>
</tr>
<tr>
<td>3 = Z</td>
</tr>
<tr>
<td>4 = U</td>
</tr>
</tbody>
</table>

The number of axes available for selection is dependent upon the equipment complement of the PA-CONTROL (1, 2, 4 or 8). You will see the following display after you select the axis.

| Press Start |

You can now start reference travel by pressing the "Start key", or return to the Manual menu by pressing key "ESC". The following display is shown during reference travel.

| Axis running |

Reference travel can be interrupted at any time with the "Stop key" and then aborted with key "ESC" or continued with the "Start key".
2.5.2 Axes manually via front panel

The absolute positions of the axes are displayed on the display after you change to this menu option.

\[
\begin{array}{c c c c}
\text{X : 0.000} & \text{Y : 0.000} \\
\end{array}
\]

You select manual traverse with the corresponding axis by pressing the key with the axis name (X, Y, ...). The following display is then shown (example for the X axis).

\[
\begin{array}{c c c c c c}
\text{X : 0.000} & \text{V = 500.000} \\
1 = 300.000 & 2 = 500.000 & 3 = 1000.000 \\
\end{array}
\]

The following assignment applies to the above display:

1st line:

\[
\begin{align*}
\text{X: 0.000} & : \text{Current absolute position of the axis} \\
\text{V = 500.000} & : \text{Currently selected traversing speed}
\end{align*}
\]

2nd line:

\[
\begin{align*}
1 = 300.000 & : \text{Traverse speed; this is taken from parameter Creep speed} \\
2 = 5000.000 & : \text{Traverse speed; this is taken from parameter Manual speed} \\
3 = 1000.000 & : \text{Traverse speed; this is taken from parameter Reference speed}
\end{align*}
\]

The following key assignment applies in this state:

<table>
<thead>
<tr>
<th>Key</th>
<th>Response / Effect</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arrow left</td>
<td>Traverse in negative direction (press briefly: Single-step, press for longer period: Continuous)</td>
</tr>
<tr>
<td>Arrow right</td>
<td>Traverse in positive direction (press briefly: Single-step, press for longer period: Continuous)</td>
</tr>
<tr>
<td>1</td>
<td>Set the current traverse speed to the value after 1 = ...</td>
</tr>
<tr>
<td>2</td>
<td>Set the current traverse speed to the value after 2 = ...</td>
</tr>
<tr>
<td>3</td>
<td>Set the current traverse speed to the value after 3 = ...</td>
</tr>
<tr>
<td>ESC</td>
<td>End, return to preceding menu</td>
</tr>
</tbody>
</table>
2.6 Programming

Overview, Programming menu

You are offered the following selection after you change to this menu option

<table>
<thead>
<tr>
<th>Programming</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 = Directory</td>
</tr>
<tr>
<td>2 = Edit new program</td>
</tr>
<tr>
<td>3 = Edit existing program</td>
</tr>
<tr>
<td>4 = Copy program</td>
</tr>
<tr>
<td>5 = Rename program</td>
</tr>
<tr>
<td>6 = Delete program</td>
</tr>
<tr>
<td>7 = Print program</td>
</tr>
<tr>
<td>8 = Show memory</td>
</tr>
<tr>
<td>9 = Transfer program*</td>
</tr>
</tbody>
</table>

Please note:

The user memory of the PA-CONTROL is limited due to the size of the RAM chip on the CPU3 also on the PIO-x. User memory still free can be displayed in menu option 8.

After you activate a menu sub-option of the Programming menu, the PA-CONTROL checks whether the user memory still free suffices for this action. If this is not the case, the activated function is not executed and it is aborted with the following message.

**Insufficient memory**

You can return to the menu by pressing any key.

If, for example, you nevertheless wish to create new programs, you must increase the size of the free user memory.

Options:

- Deleting programs no longer required
- Replace RAM module on CPU3 with a bigger one (contact IEF Werner beforehand)
- When equipped with PIO-x no extension is possible.
- Deleting less important comments from the programs

* only with aktiv PAB (option)
2.6.1 Display program directory

In this menu option, you can page through the current program directory. You will see the following display:

<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Type</th>
<th>Stat</th>
<th>Characters</th>
<th>Lines</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>EXAMPLE</td>
<td>PNC</td>
<td>0</td>
<td>13</td>
<td>3</td>
</tr>
</tbody>
</table>

The following assignment applies:

- **No.**: Consecutive numbering of the programs
- **Name**: Program name
- **Type**: Programme type (PN = NC - Programme, PTX = Text programme, PAB = PAB - Programme, when PAB is available)
- **Status**: Programme status (0 = write/read access possible, 1 = write-protected, 2 = transverse sum error, 3 = PAB Programme available in HOST, but not in PAB)
- **Characters**: Number of Ascii characters in the program
- **Lines**: Number of program lines

By simultaneously pressing keys "CTRL" and "DEL", you can activate the delete operation for the displayed program. Before the program is deleted, you must confirm the delete operation again.

Program: EXAMPLE PNC
Confirm delete program? 1 = yes

The program is deleted if you press key "1". Pressing any other keys aborts the delete operation and the program remains unchanged in the user memory.
2.6.2 Create new program

If you activate this menu option, you are prompted to enter a new program name (see description, entering program name).

You must then select the program type.

Program type list, please select!
1 = PNC
2 = PTX
3 = PAB

PNC program : Executable NC program with positioning and I/O instructions
PTX program : Text program for labeling inputs, outputs, ...
               (Refer to the Sections "Program test and diagnosis"
               and "Sequence definitions" for further details.)
PAB program : Executable program for parallel processing (option)

After you make the selection, you will then be in the PA-CONTROL program editor in the 1st program line.
Please refer to Chapter Instructions of the PA-CONTROL family - Programming information for a description of the program editor.

Note:

The once defined program typ can not later changed in the PAC
2.6.3 Modify existing program:

When you activate this menu option, you are offered a list of the existing programs, sorted alphabetically. You can page through the list and access the required program for programming by pressing key "ENTER".

<table>
<thead>
<tr>
<th>Program list; please select!</th>
<th>[ ]</th>
</tr>
</thead>
<tbody>
<tr>
<td>Program: 1 EXAMPLE.PNC</td>
<td></td>
</tr>
</tbody>
</table>

After you make the selection, you will be in the PA-CONTROL program editor. The first two lines of the selected program are displayed. See Chapter Instructions of the PA-CONTROL family - Programming information for a description of the program editor.

2.6.4 Copy program

With this menu option, you can copy the contents of an existing program to a new program. When you activate this menu option, you are offered a list of the existing programs, sorted alphabetically. You can page through the list and select the required program.

<table>
<thead>
<tr>
<th>Program list, please select!</th>
<th>[ ]</th>
</tr>
</thead>
<tbody>
<tr>
<td>Program: 1 EXAMPLE.PNC</td>
<td></td>
</tr>
</tbody>
</table>

After you make the selection, you are prompted to enter a new program name. If the entry is acceptable, the program is copied and is included in the directory as a further program.

Important:

The program type cannot be changed during the copy operation.
2.6.5 Rename program

In this menu option, you can change the program name of an existing program. When you activate this menu option, you are offered a list of the existing programs, sorted alphabetically. You can page through the list and select the required program.

```
Program list, please select! [ ]
Program: 1 EXAMPLE.PNC
```

After you make the selection, you are prompted to enter a new program name. After you make the entry, the program is then listed unchanged with a new name in the directory.

2.6.6 Delete program

In this menu option, you can delete an existing program (remove it from the program memory). When you activate this menu option, you are offered a list of the existing programs, sorted alphabetically. You can page through the list and select the required program.

```
Program list, please select! [ ]
Program: 1 EXAMPLE.PNC
```

After you make the selection, you are prompted once again to confirm the selection and your wish to delete this program.

```
Program: EXAMPLE PNC
Do you really want to delete program? 1 = yes
```

The program is deleted if you press key "1". Pressing any other keys aborts this selection and the program is then not deleted.
2.6.7 Print program

In this menu item the operator can create a programme printout on a serial printer connected to the serial interface 1 or 2 (the PA-CONTROL -SC and the PA-CONTROL Single only have 1 interface each).

The program is transferred (interface number, baud rate, format) under the conditions set in the system parameters (see Chapter Parameters).

The pages of the program printout are consecutively numbered and each page is provided with a header, consisting of the program name, program type, comment field and page number.

When you activate this menu option, you are offered a list of the existing programs for selection, sorted alphabetically.

Program list, please select! [ ]
Program: 1 EXAMPLE.PNC

After you make the selection, you are prompted once again to confirm the selection and your wish to print this program.

Program: EXAMPLE PNC
Print? 1 = yes

You can confirm the selection by pressing key "1". Pressing any other keys aborts this selection and returns you to the menu.

You will then see the following display after you confirm the selection.

Enter comment on printout [ ]

The second display line has an input field with a length of 38 characters. The operator can enter a text at this point, and this text is then printed out in the program printout in each header as the comment field. You can complete the entry and start the print operation by pressing key "ENTER".

Important:

You can abort the print operation by pressing key "ESC".
2.6.8 Display program memory occupancy

In this menu point, the operator can show how much of the main memory is already occupied by the existing programs or is still free. There are two different displays for this menu point for the equipment variants with and without PAB (optional).

On units without PAB (optional):

The following display, for example, appears on units without PAB after this menu point is activated:

<table>
<thead>
<tr>
<th>Memory occupied:</th>
<th>85</th>
</tr>
</thead>
<tbody>
<tr>
<td>Memory free:</td>
<td>21915</td>
</tr>
</tbody>
</table>

On units with PAB (optional):

The following display, for example, appears on units with PAB after this menu point is activated:

<table>
<thead>
<tr>
<th>Memory occupied.</th>
<th>2325</th>
<th>1269</th>
</tr>
</thead>
<tbody>
<tr>
<td>Memory free</td>
<td>17315</td>
<td>22395</td>
</tr>
</tbody>
</table>

The current figures for the memory of the host CPU are displayed on the left side (in this example: 2325, 17315) in this display. The figures on the right side (in this example: 1269, 22395) show how much memory space on the PAB is still free or is occupied.

Please note:

The value for "memory space free" differs depending on the development level and features!
2.6.9 Storing/deleting programs in a PAB

Please note:

Only active in conjunction with a PAB (optional).

The following display appears after transfer into this menu subpoint:

```
<table>
<thead>
<tr>
<th>No.</th>
<th>Name</th>
<th>Type</th>
<th>Characters</th>
<th>in PAB</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>A-Test PAB</td>
<td>PAB</td>
<td>703</td>
<td>yes</td>
</tr>
</tbody>
</table>
```

The name, type and number of characters of the program are shown. It is also shown whether the program is currently under PAB (in PAB yes) or is not present (in PAB no).

The user can scroll through the program directory with the "Arrow up" and "Arrow down" keys. If one of the programs on the PAB is to be deleted or stored, this can be done with the help of the keys "DEL" (delete) and "INS" (store) when the appropriate program is shown on the display.

This menu point can be exited with the aid of the ESC key.

Please note:

In this menu point, the programs are only deleted or stored on the PAB.
The memory of the host CPU is not affected by this.
2.7 Program test and diagnosis

Overview, Progra test and diagnosis menu

You are offered the following selection after you change to this menu option:

<table>
<thead>
<tr>
<th>Program test and diagnosis</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 = Program test</td>
</tr>
<tr>
<td>2 = Inputs</td>
</tr>
<tr>
<td>3 = Outputs</td>
</tr>
<tr>
<td>4 = Flags (Marker)</td>
</tr>
<tr>
<td>5 = Real number register (R)</td>
</tr>
<tr>
<td>6 = Integer number register (N)</td>
</tr>
<tr>
<td>7 = Save current states</td>
</tr>
<tr>
<td>8 = Limit switches / Standby</td>
</tr>
<tr>
<td>9 = Counter*</td>
</tr>
</tbody>
</table>

2.7.1 Program test

The user is offered the following selection after transfer into this menu point:

<table>
<thead>
<tr>
<th>Program test</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 = Automatic with serial diagnosis</td>
</tr>
<tr>
<td>2 = Automatic (positioning only)</td>
</tr>
<tr>
<td>3 = Automatic, individual step</td>
</tr>
</tbody>
</table>

Automatic with serial diagnosis:

The serial diagnosis is set via this menu item. The diagnosis can be activated and/or deacti-
vated using the ENTER key. The current setting is shown on the display. The diagnosis remains
active in automatic operation until it is switched off in the same manner.
If the diagnosis has been activated a serial diagnosis can be performed at all times with
PROPAC. Please refer to the operating instructions of the programme development system
PROPAC for a more detailed description.

Automatic (positioning only):

Not implemented in this version!

Automatic, individual step:

Not implemented in this version!

* Only active in conjunction with a counter board (optional).
2.7.2 Inputs, outputs, flags:

This menu sub-option is used to manually check and change the states of the inputs, outputs or flags. You will see the following display after you activate these sub-options:

e.g.: for inputs

<table>
<thead>
<tr>
<th>I 5:</th>
<th>Label text</th>
</tr>
</thead>
<tbody>
<tr>
<td>I 1 -&gt;</td>
<td>00000000000000</td>
</tr>
</tbody>
</table>

The following assignment applies:

1st line: The number after "INPUT" is the input at which the cursor field is located. The text from the program assigned in menu option "Sequence definitions -> Text assignment -> 1 = Inputs" is located at the "Label text" position. No text is displayed if no assignment has been made.

2nd line: "I 1 ->" means that, as of input 1, the states of the next 16 inputs are displayed in this line. These are followed by the logic states of the inputs (0 or 1).

0: Input not energized, output or flag reset
1: Input energized, output or flag set.

Moving and actions in the display:

<table>
<thead>
<tr>
<th>Key</th>
<th>Response / Effect</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arrow right</td>
<td>Move cursor field one position to the right (to the next element)</td>
</tr>
<tr>
<td>Arrow left</td>
<td>Move cursor field one position to the left (to the previous element)</td>
</tr>
<tr>
<td>SHIFT + Arrow right</td>
<td>Move cursor to the last cursor field of the row (last element)</td>
</tr>
<tr>
<td>SHIFT + Arrow left</td>
<td>Move cursor to the first cursor field of the row (first element)</td>
</tr>
<tr>
<td>Arrow down</td>
<td>Display next group (e.g. input 17-32)</td>
</tr>
<tr>
<td>Arrow up</td>
<td>Display previous group (e.g. input 1-16)</td>
</tr>
<tr>
<td>SHIFT + Arrow down</td>
<td>Display last group (e.g. input 497-512)</td>
</tr>
<tr>
<td>SHIFT + Arrow up</td>
<td>Display first group (e.g. input 1-16)</td>
</tr>
<tr>
<td>ENTER</td>
<td>Select element directly, enter the required element in the input field and display with ENTER</td>
</tr>
<tr>
<td>1</td>
<td>Set output or flag at which the cursor field is located</td>
</tr>
<tr>
<td>0</td>
<td>Reset the output or flag at which the cursor field is located</td>
</tr>
<tr>
<td>ESC</td>
<td>Quit sub-option</td>
</tr>
</tbody>
</table>
The following display is shown for inputs 17-32:

```
I 17: Label text
I 17 ->  0000000000000000
```

The following display is shown for outputs 1-16:

```
O 1:  Label text
O 1 ->  0000000000000000
```

The following display is shown for flags 1-16:

```
M 1: Label text
M 1 ->  0000000000000000
```

Note:

The output and flag statuses are retained when the menu is exited!
The number of inputs and outputs can vary according to the control equipment!
2.7.3 Real number register (R), integer register (N)

These menu sub-options serve to manually check and change the contents of the real number and integer registers. You will see the following display after you activate these sub-options:

e.g. for real number register:

| R 1: Label text | R 1 = 0.000 |

The following assignment applies:

1st line: The number after "REAL NUMBER REGISTER" is the number of the register displayed. The text from the program assigned in menu option "Sequence definitions -> Text assignment -> 4 = Real number register" is located at the "Label text" position.

2nd line: "R 1 = 0.000" is the contents of the displayed register (in this case, register 1 with value 0).

Moving and actions in the display:

<table>
<thead>
<tr>
<th>Key</th>
<th>Response / Effect</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arrow down</td>
<td>Display next register</td>
</tr>
<tr>
<td>Arrow up</td>
<td>Display previous register</td>
</tr>
<tr>
<td>SHIFT+Arrow down</td>
<td>Last register</td>
</tr>
<tr>
<td>SHIFT+Arrow up</td>
<td>Display first register</td>
</tr>
<tr>
<td>ESC</td>
<td>Quit sub-option</td>
</tr>
<tr>
<td>Numeric key (1..9+-)</td>
<td>Activating the input field and the character is accepted at the first position of the displayed value</td>
</tr>
<tr>
<td>Arrow right</td>
<td>Activation of the input field</td>
</tr>
<tr>
<td>ENTER</td>
<td>Terminate entry</td>
</tr>
<tr>
<td>ENTER</td>
<td>Select element directly, enter the required element in the input field and display with ENTER</td>
</tr>
<tr>
<td>ESC</td>
<td>Abort entry and previous value is retained</td>
</tr>
</tbody>
</table>

See description "Operator interface, - Input field" for the key assignment in the input field.

The entered value is transferred to the register only if the number lies within the defined value limits (+/- 8,000,000).

Example for integer register:

| N 1: Label text | N 1 = 0 |


2.7.4 Positioning control test

Note:

This submenu point is implemented only in control units with positioning control (PA-CONTROL Servo).

After choosing this submenu point there has to be an axis selection first. The operator must point out for which axes the test should be realized. An axis selection is available (only the first line are shown):

<table>
<thead>
<tr>
<th>Positioning control test axis selection</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 = X</td>
</tr>
</tbody>
</table>

If one axis is chosen the following test selection will be displayed:

<table>
<thead>
<tr>
<th>Test selection</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 = positional display</td>
</tr>
</tbody>
</table>

2 = positioning control inputs
3 = release output
4 = DA-converter test

Positional display: The position of the selected axis will be displayed. The display occurs in dependence on the gear factor and also with the chosen system of units. The release output is switched off.

Positioning control inputs:

<table>
<thead>
<tr>
<th>-X</th>
<th>+X</th>
<th>ref.</th>
<th>standby</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
</tbody>
</table>

In this submenu point the limit switch (-X, +X), the additional reference position (ref.) and standby of the output stage (standby) are displayed.

Release output:

<table>
<thead>
<tr>
<th>X release output, change, end = ESC</th>
</tr>
</thead>
<tbody>
<tr>
<td>actual state 0</td>
</tr>
</tbody>
</table>
DA-converter test:

By selection of this point another choice of submenu points is displayed.

<table>
<thead>
<tr>
<th>DA-converter test</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 = DA-zero</td>
</tr>
<tr>
<td>2 = Da-variable</td>
</tr>
<tr>
<td>3 = DA-sow tooth</td>
</tr>
<tr>
<td>4 = DA-rectangle</td>
</tr>
</tbody>
</table>

DA-zero:

<table>
<thead>
<tr>
<th>X: zero volt output</th>
</tr>
</thead>
<tbody>
<tr>
<td>end with ESC</td>
</tr>
</tbody>
</table>

DA-variable:

<table>
<thead>
<tr>
<th>X: variable voltage output</th>
</tr>
</thead>
<tbody>
<tr>
<td>end with ESC, actual state [0 ]</td>
</tr>
</tbody>
</table>

Input range: +/- 10 V, in this case „1“ is the same as 1V

DA-sow-tooth:

<table>
<thead>
<tr>
<th>X: sow-tooth +/- 10V output</th>
</tr>
</thead>
<tbody>
<tr>
<td>end with ESC</td>
</tr>
</tbody>
</table>

DA-rectangle:

<table>
<thead>
<tr>
<th>x: rectangle +/- 1V output</th>
</tr>
</thead>
<tbody>
<tr>
<td>end with ESC</td>
</tr>
</tbody>
</table>

„X“ at the beginning of the first line means that the X-axis was choosen at the beginning of the menu point positioning control test (other axis are possible).
2.7.5 Limit switches / Standby

This menu sub-option serves to check the limit switches of the individual axes and standby status of the motor power sections. The displays differ in this sub-option, dependent upon configuration of the PA-CONTROL, since only the existing motor axes are allowed for. You will see the following display after you activate the sub-option:

```
e.g.: PA-CONTROL Compact

B X+ Y-
1 10 01
```

The following assignment applies:

The elements Standby (B) and the limit switches of the axes (X+, Y+, ...) are displayed in the first line. The logical state of the corresponding inputs is displayed in the second line.

<table>
<thead>
<tr>
<th></th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Power section not ready, limit switch (NC contact) actuated</td>
</tr>
<tr>
<td>1</td>
<td>Power section ready, limit switch not actuated</td>
</tr>
</tbody>
</table>

The above display thus has the following significance:

- Power sections X- and Y- axis ready
- Limit switch X+ not actuated (input energized)
- Limit switch X- actuated (input not energized)
- Limit switch Y+ actuated (input not energized)
- Limit switch Y- not actuated (input energized)

Example PA-CONTROL (8 axes)

```
B X+ Y+ Z+ U+  B V+ W+ Q+ P-
1 10 01 11 11 1 11 11 11
```

On the PA-CONTROL with PLS5, the Standby signals of the individual power output stages (max. 4) are gated in the LV UNIT and are shown here as a general signal (AND).

**Note:**

The stand-by signal and limit switch of devices equipped with a positioning control (PA-CONTROL Servo) must be checked in the menu „Position control test“!
2.7.6 Display Counter

Please note:

This menu subpoint is active only in conjunction with a counter board (optional).

The user is offered the following selection after transfer into this menu point:

<table>
<thead>
<tr>
<th>Display counter</th>
<th>1 = Counter (1 - 8 / 13 - 20)</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>2 = 2 Phase counter (9 - 12 / 21 - 24)</td>
</tr>
</tbody>
</table>

The following display appears when the first menu subpoint is selected:

<table>
<thead>
<tr>
<th>Display counter: 1</th>
</tr>
</thead>
<tbody>
<tr>
<td>I 1 = 0</td>
</tr>
<tr>
<td>CNT 1 = 0</td>
</tr>
</tbody>
</table>

The number of the counter to which the following values apply is displayed in the first line (here: Counter No. 1). The status of the relevant input (here: I 1 = 0) and the value of the counter (here: CNT 1 = 0) are displayed in the second line.

The user has the possibility of displaying the values of the individual counters with the help of the "Arrow up" and "Arrow down" keys.

The following display appears when the second menu subpoint is selected:

<table>
<thead>
<tr>
<th>Display counter: 9</th>
</tr>
</thead>
<tbody>
<tr>
<td>A 9 = 0</td>
</tr>
<tr>
<td>B 9 = 0</td>
</tr>
<tr>
<td>CNT 9 = 0</td>
</tr>
</tbody>
</table>

The number of the counter is shown in the first line here too. The statuses of the relevant channels A and B and the value of the counter are displayed in the second line.

The user again has the possibility of choosing between the individual counters with "Arrow up" and "Arrow down" keys.
2.8 Overview, Sequence definitions menu

You are offered the following selection after you change to this menu option:

```
Sequence definitions
1 = Start program
```

- 2 = Program after stop
- 3 = Program start after stop
- 4 = Program after fault
- 5 = Labelling
- 6 = Program protection

Definitions are made for the automatic sequence of the PA-CONTROL in this menu.

**Note:**

Start programme, programme after stop, programme start and stop and programme when faults arise must be different programmes.

**Start program:** The PA-control starts the automatic sequence with this program when started. This program is, in principle, the main program.

**Program after stop:** This assignment permits special actions (e.g. closing valves, ...) to be implemented when "STOP" is detected in an automatic run. This program is executed after the axes have stopped.

**Attention:** In the programme after Stop the command block has the following restrictions:
1. This programme should not call up any further programmes as sub-routines.
2. Positioning commands are not permissible in this programme.
3. If the G210 command is active, G21 should not be used.
4. The commands „Wait for logical state of...“ inputs, outputs and flags should not be used.
5. A time monitoring that is still active is reset by the operating system without further indication and is not reactivated with a „Start“.
Program start after stop: If the PA-CONTROL was in Automatic mode and if Stop has been pressed and it is then intended to continue with Start (Automatic has not been quit), "Program start after stop" is executed before continuing with the interrupted program. This option can be used to reset actions which have been triggered on Stop.

Attention: This program may call no other programs as subroutines. Positioning instructions are not permitted

Program after fault: This assignment permits special actions (e.g. closing valves, ...) to be implemented when a fault is detected in the program run (error message, e.g.: value too high, power section not ready, —).

Attention: This program may call no other programs as subroutines. Positioning instructions are not permitted

Labels: Texts can be assigned to the inputs, outputs, flags and registers in order to simplify diagnosis during commissioning and troubleshooting. These texts are then displayed in menu option "Program test and diagnosis" in the corresponding sub-menu at the "Label text" position. In order to do this, you must create a text program, whereby the first program line is assigned to the 1st element and the second program line is assigned to the 2nd element etc. The program lines should not be longer than 20 characters in such cases since maximum 20 characters can be displayed in the diagnosis menu.

User title: The operator has the option of replacing the title in the main menu "PA-CONTROL Vxx.xx" by his own title, matched to his application. For this purpose, the operator must create a text program (type: PTX) and assign this text program under sub-menu option "User title". The first program line of this text program is then displayed as the title in the main menu.

Program protection: PA-CONTROL programs can be protected against inadvertent deletion, overwriting and modification by providing them with a program protection attribute. PA-CONTROL programs with write protection cannot be deleted. They can be displayed but not modified in the PA-CONTROL editor. If you intend to delete or modify a protected program, you must cancel the program protection attribute beforehand.
2.8.1 Start program, program after stop, program start after stop

When you activate these sub-options, you are offered a list of possible programs of type "PNC", sorted alphabetically. You can page through the list and select the required program.

Program list, please select!
Program: 1 EXAMPLE.PNC

After you make the selection, the selected program is accepted.

This assignment must be made with extreme care since it influences the entire machine sequence.

2.8.2 Text assignments

When you activate this sub-option, you are offered a further menu list.

<table>
<thead>
<tr>
<th>Label</th>
<th>Program name</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 = Inputs</td>
<td></td>
</tr>
</tbody>
</table>

2 = Outputs
3 = Flags
4 = Real number register
5 = Integer number register
6 = User title

Here as well, you are offered a list of the possible programs, sorted alphabetically, when you activate these sub-options. You can page through the list and select the required program.

Program list, please select!
Program: 1 EXAMPLE.PTX
2.8.3 Deleting assignments:

If you wish to delete an assignment (start program, ..., text program), you must display the assignment to be deleted in the second line. Press key "DEL" to tell the PA-CONTROL you wish to delete an assignment. You must confirm the action before the assignment is really deleted.

<table>
<thead>
<tr>
<th>Delete program assignment ?</th>
<th>1 = yes</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 = Start program...........:</td>
<td>EXAMPLE</td>
</tr>
</tbody>
</table>

However, if you wish to only modify an assignment, you can simply overwrite the existing assignment by reselecting.
2.9 Parameters

Overview, Parameters menu

You are offered the following selection after you change this menu option:

<table>
<thead>
<tr>
<th>Parameters</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 = System parameters</td>
</tr>
<tr>
<td>2 = Axis parameters</td>
</tr>
<tr>
<td>3 = Edit ASi-Bus</td>
</tr>
</tbody>
</table>

A distinction is made in the PA-CONTROL between two parameter types, system parameters and axis parameters.

The significance of the individual parameters and how to use them practically are explained in Chapter Parameters.

You are offered a list of the parameters, as follows, when you enter menu sub-option "System parameters".

You must first select the required axis when you enter Axis parameters.

Parameters (definitions)

| Min. value         | Actual value | Max. value |

You can now page through the list of the parameters and edit the required parameter by activating the input field by pressing a digit key or the cursor key "Arrow left". The value keyed in (modified) must lie between the min. value and the max. value. Otherwise, an error message is displayed when you terminate the entry. The entry must then be repeated or aborted by "ESC".

The submenu process ASI-BUS can only be called up when one or more AS-i cards are connected. For further information on projecting the AS-i see chapter on "Options".
2.10 Defaults

Overview, Defaults menu

You are offered the following selection when you change this menu option:

<table>
<thead>
<tr>
<th>Defaults</th>
<th>1 = Bootload system parameter</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>2 = Bootload axis parameter</td>
</tr>
<tr>
<td></td>
<td>3 = Clear memory</td>
</tr>
<tr>
<td></td>
<td>4 = Reinitialize PA-CONTROL</td>
</tr>
</tbody>
</table>

Using these functions, you can set the PA-CONTROL to a defined initial state.

Current machine parameters are overwritten or programs are deleted when you select these functions. These functions should be selected only by authorized and trained personnel.

Note: Back up your data beforehand on PROPAC or hard copy

The values to which the parameters are set are specified in Chapter Parameters.

Loading default and reinitialization have been carried out by IEF Werner prior to delivery. Reinitialization should be carried out if the CPU board is exchanged, unless otherwise directed by the servicing personnel (e.g. servicing department has made the settings).

When you select one of these options, you must confirm the operation once again by pressing digit key "1".

e.g.: Load default system parameters

You will see the following on the display:

| Confirm re-initialize PAC | 1 = Yes     /     Key = No_ |

You can now start loading default system parameters by pressing digit key "1" or you can abort the action by pressing another key.
2.11 System diagnosis

Overview, System diagnosis menu

You are offered the following selection after you change to this menu option:

<table>
<thead>
<tr>
<th>Option</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>Display PAC type</td>
</tr>
<tr>
<td>2</td>
<td>Keyboard test</td>
</tr>
<tr>
<td>3</td>
<td>Stop key test</td>
</tr>
<tr>
<td>4</td>
<td>Start key test</td>
</tr>
<tr>
<td>5</td>
<td>Key switch test</td>
</tr>
<tr>
<td>6</td>
<td>Test serial interface 1</td>
</tr>
<tr>
<td>7</td>
<td>Test serial interface 2</td>
</tr>
<tr>
<td>8</td>
<td>Interbus-S monitor</td>
</tr>
</tbody>
</table>

Note:

If the Interbus-S system (network) is in operation, you will see sub-menu option "8 = Interbus-S monitor" in the "System diagnosis" menu.
The menu item "7 = test serial interface 2" has no function when equipped with PIO-x (PA-CONTROL-SC and PA-CONTROL Single)
2.11.1 Display PA-CONTROL type

In this sub-option, you can recall the configuration of your PA-CONTROL. The information is displayed in encoded form. You can quit the display and return to the menu by pressing key ESC. You will see 13 pairs of digits on the display, separated by a hyphen.

PAC type:
00-00-00-00-00-00-00-00-00-00-00-00-000

The following allocations apply:

<table>
<thead>
<tr>
<th>Pair of Digits</th>
<th>Pos.</th>
<th>Value</th>
<th>Explanation</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.</td>
<td>1.</td>
<td>1</td>
<td>- with LC display and keyboard</td>
</tr>
<tr>
<td></td>
<td></td>
<td>2</td>
<td>- without LC display and keyboard, with 7 segment display</td>
</tr>
<tr>
<td>2.</td>
<td></td>
<td>Design</td>
<td></td>
</tr>
<tr>
<td></td>
<td>1</td>
<td>1</td>
<td>- 19&quot; control unit</td>
</tr>
<tr>
<td></td>
<td></td>
<td>2</td>
<td>- 19&quot;/2 control unit</td>
</tr>
<tr>
<td></td>
<td></td>
<td>3</td>
<td>- Compact 19&quot; - 2 axis</td>
</tr>
<tr>
<td></td>
<td></td>
<td>4</td>
<td>- Compact 19&quot; - 1 axis</td>
</tr>
<tr>
<td></td>
<td></td>
<td>5</td>
<td>- Single</td>
</tr>
<tr>
<td></td>
<td></td>
<td>6</td>
<td>- SC-Compact</td>
</tr>
<tr>
<td>2.</td>
<td></td>
<td>Positioning Process</td>
<td></td>
</tr>
<tr>
<td></td>
<td>0</td>
<td>0</td>
<td>- STEP (none)</td>
</tr>
<tr>
<td></td>
<td>1</td>
<td>1</td>
<td>- PLS4  (from V3.3 upwards no longer in production)</td>
</tr>
<tr>
<td></td>
<td>2</td>
<td>2</td>
<td>- PLS5</td>
</tr>
<tr>
<td></td>
<td>3</td>
<td>3</td>
<td>- PLS6</td>
</tr>
<tr>
<td></td>
<td>4</td>
<td>4</td>
<td>- PIO-1</td>
</tr>
<tr>
<td></td>
<td>5</td>
<td>5</td>
<td>- Positioning control</td>
</tr>
<tr>
<td>3.</td>
<td></td>
<td>Maximum number of axes (1 - 8)</td>
<td></td>
</tr>
<tr>
<td>4.</td>
<td>1.</td>
<td>Type of output stage</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>0</td>
<td>- without output stage</td>
</tr>
<tr>
<td></td>
<td></td>
<td>1</td>
<td>- 2 phase stepping motor without rotation control</td>
</tr>
<tr>
<td></td>
<td></td>
<td>2</td>
<td>- 2 phase stepping motor with rotation control</td>
</tr>
<tr>
<td></td>
<td></td>
<td>3</td>
<td>- 5 phase stepping motor without rotation control</td>
</tr>
<tr>
<td></td>
<td></td>
<td>4</td>
<td>- 5 phase stepping motor with rotation control</td>
</tr>
<tr>
<td></td>
<td></td>
<td>5</td>
<td>- 3 phase stepping motor without rotation control</td>
</tr>
<tr>
<td>2.</td>
<td></td>
<td>Supply voltage of the output stage</td>
<td></td>
</tr>
<tr>
<td></td>
<td>0</td>
<td>0</td>
<td>- none</td>
</tr>
<tr>
<td></td>
<td>1</td>
<td>1</td>
<td>- 35V</td>
</tr>
<tr>
<td></td>
<td>2</td>
<td>2</td>
<td>- 60V</td>
</tr>
<tr>
<td></td>
<td>3</td>
<td>3</td>
<td>- 90V</td>
</tr>
<tr>
<td></td>
<td>4</td>
<td>4</td>
<td>- 140V</td>
</tr>
<tr>
<td>Pair of Digits</td>
<td>Pos.</td>
<td>Value</td>
<td>Explanation</td>
</tr>
<tr>
<td>---------------</td>
<td>------</td>
<td>-------</td>
<td>-------------</td>
</tr>
<tr>
<td>5. / 6.</td>
<td></td>
<td></td>
<td>Software status PA-CONTROL CPU</td>
</tr>
<tr>
<td>7. / 8.</td>
<td></td>
<td></td>
<td>Software status positioning module</td>
</tr>
<tr>
<td>9. / 10.</td>
<td></td>
<td></td>
<td>Software status of the PAB (Option)</td>
</tr>
</tbody>
</table>

11.  
1.  
0  - no external bus coupling  
1  - InterBus-S (IBS)  
2  - one actuator sensor interface (AS-i)  
3  - two actuator sensor interfaces (AS-i)  
4  - three actuator sensor interfaces (AS-i)  
5  - IBS and one AS-i  
6  - IBS and two AS-i  
7  - IBS and three AS-i  

2.  
0  - none  
1  - CNT-1  
3  - CNT-1 and CNT-2  

12.  
1.  
0  - none  
1  - REL 9R Relay card  

2.  
Number of I/O cards (1-8)  

13.  
Size of installed RAM  

Example:

```
PAC - Type:
13-03-02-13-03-03-03-60-03-20-03-61-20-01-128
```

1. Pair of digits: - Compact 19" slide-in with 2 axes with LCD and keyboard  
2. Pair of digits: - PLS6  
3. Pair of digits: - 2 axes  
4. Pair of digits: - 2 phase stepping motor with rotation control  
- 90V output stage supply voltage  
5./6. Pair of digits: - Master software 3.60  
7./8. Pair of digits: - Positioning module software 3.20  
9./10. Pair of digits: - PAB Software status 3.61  
11. Pair of digits: - One As-i master, no CNT card  
12. Pair of digits: - no relay card, one I/O card  
13. Pair of digits: - 128kB RAM store
2.11.2 Tests

Keyboard test

You will see the following display when you select this sub-option:

```
Keyboard test, ESC = End !
```

When pressed, the keys are displayed or their functions are executed, dependent upon the described function (see Chapter Operator interface - Keyboard).
Exceptions: Arrow keys, INS, DEL, ENTER, START, STOP, ALT, CTRL

Stop key test

You will see the following display when you select this sub-option:

```
Stop key test, ESC = End !
Stop key pressed: no
```

When you press the Stop key, the display changes from "no" to "yes". The function relates to the Stop key on the front panel. The possible external Stop input can be checked via Diagnosis, Inputs.

Start key test

You will see the following display when you select this sub-option:

```
Start key test, ESC = End !
Start key pressed: no
```

When you press the Start key, the display changes from "no" to "yes". The function relates to the Start key on the front panel. The possible external Start input can be checked via Diagnosis, Inputs.
Key-operated switch test

You will see the following display when you select this sub-option:

```
Key switch test, ESC = End !
Key switch set to : Program
```

The display changes from "Program" to "Automatic" when you turn the key-operated switch.

Test serial interface 1 (2)

You will see the following on the display when you select this sub-option:

```
Serial interface 1 (2) test, ESC = End
```

All keys pressed are displayed in accordance with their function and, at the same time, the corresponding signals are transferred via the selected serial interface. Characters received via the selected serial interface are displayed immediately.

The characters of the keys now pressed (practical selection: 0-9, A-Z) are

1. shown on the display
2. transferred via the selected serial interface

At the same time, characters received from the selected interface are displayed. A jumper can be fitted between transmitter and receiver (pin 2-3) on the Sub-D connector for checking the transmit and receive modules. The character of the keys pressed is then displayed twice.

From the software version 3.20 upwards RS232/ RS485 are optional depending on the position of the jumper J11 and J12 (see chapter on "Technical Appendix -CPU 3- Card" and chapter "Commands, Text and Value Outputs via Current Data Channel").

Interbus-S Monitor

The menu item Interbus-S Monitor can only be selected when communication has been made with the Interbus-S master.
For further information see chapter “Options, Interbus-S Connection”.
2.12 Modem

Overview Modem Menu

From the Version 3.60 upwards communication between PROPAC and PAC is possible via a modem. The operator has the following possibilities when using the modem:

- Load and transfer programme
- Load and transfer parameters
- Load and transfer register values
- Diagnosis in automatic mode

For the safety reasons the following functions have not been integrated:

- Start / Stop the PAC
- Direct alteration of outputs, flags and registers in the PAC
- Manual movement of the axes of the PAC
- Simulation of the front panel

After selecting the menu item 9 the operator is given the following choice:

```
Modem
1 = Connection
2 = Edit modem setting
3 = Reset modem setting
```

Connect

The modem is connected to the PAC via the serial interface 1. This allows an operator who is not on site to have access to the PAC by calling up the sub menu Connect to the PAC. Communication between PAC and PROPAC via the modem can only be made and terminated from the PROPAC programme.

```
Modem ready for communication?
1 = yes / key = no
```

Once the modem is connected and switched on activate the key 1.

```
Modem: Wait for connection
```
If a connection has been made via the modem the display of the PAC shows communication data.

```
MODEM : CONNECT 9600MNP
```

When transferring data the characters ### are displayed in the second display line.

The user programme can be started as usual using the START key. If the automatic mode with serial diagnosis is active, diagnosis of the automatic operation in PROPAC is possible. The sub menus can be exited using the ESC key.

**Edit Modem Setting**

In this menu the operator can set the modem commands for initialization according to his modem.

```
Initialize modem
: AT&F2....... 
```

The setting can be edited using the ↧ key and the modem-specific data of the manufacturer. If PAC-supported modems are used, see „Reset modem setting“, the initialization string is generated by the PAC.
Reset Modem

For communication via a modem the basic settings for the recommended modems are filed.

**Definitely reset modem ?
1 = yes / key = no**

With key 1 a list of modems recommended by us is displayed.

**List of implemented modems**
1 = USRobotics Sportster 28.800 V.34/V.F
2 = ELSA Microlink 28.800 TQV
3 = NoName 14400bps V.42BIS/MNP
4 = ELSA Microlink ISDN/TLpro

Both analogue and ISDN modems are supported.

**Note:**

Communication can only take place from ISDN to ISDN modem or from analogue to analogue modem

**Communication Example:**

<table>
<thead>
<tr>
<th>Service person</th>
<th>Customer</th>
</tr>
</thead>
<tbody>
<tr>
<td>PC with PROPAC</td>
<td>(PA Control)</td>
</tr>
<tr>
<td>Connect PC via modem to the telephone network and switch on.</td>
<td>Connect the PAC via the modem to the telephone network. Reset modem</td>
</tr>
<tr>
<td>Select type of modem</td>
<td>&quot;1 = activate connection via modem&quot;</td>
</tr>
<tr>
<td>Edit connection data (name, telephone number)</td>
<td></td>
</tr>
<tr>
<td>Wait until the customer with the PAC is ready</td>
<td></td>
</tr>
<tr>
<td>Activate &quot;3 = select Connect&quot; and wait until until modem signals &quot;CONNECT&quot;</td>
<td>The PAC display shows the following : &quot;Modem: CONNECT...&quot;</td>
</tr>
<tr>
<td>Exit submenu &quot;Modem&quot; and implement e.g. in the submenu &quot;Data exchange&quot; the desired operation</td>
<td>When data is being transferred the characters &quot;###&quot; are visible in the second line of the PAC display</td>
</tr>
<tr>
<td>In the submenu „Modem“ menu item „4=Hang up“ terminate communication</td>
<td>The message „Modem: NO CARRIER“ appears on the PAC display</td>
</tr>
<tr>
<td></td>
<td>Exit sub menu item with ESC key</td>
</tr>
</tbody>
</table>
2.13 7-segment status display

On units equipped with the 7-segment status display, the number displayed indicates the status information of the PA-CONTROL.

<table>
<thead>
<tr>
<th>Number displayed</th>
<th>Status of the PA-CONTROL</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>PA-CONTROL is in initial state (main menu). It is possible to communicate with the PA-CONTROL with the aid of PROPAC and a PC via the serial interface (exchanging programs, editing parameters and diagnosis etc.).</td>
</tr>
<tr>
<td>1</td>
<td>The PA-CONTROL is in Automatic mode and a program is currently being executed.</td>
</tr>
<tr>
<td>2</td>
<td>The PA-CONTROL is in Automatic mode but &quot;Stop&quot; has been detected. The program run can be continued with Start or can be aborted (see Chapter Operator interface - Automatic mode).</td>
</tr>
<tr>
<td>3 - F</td>
<td>The PA-CONTROL was in Automatic mode and an error has occurred (significance of the error numbers, see Chapter Technical annex - Error messages).</td>
</tr>
</tbody>
</table>
2.14 System initialization

Important basic settings are transferred from the EPROM to the CRAM during system initialization. If this is not carried out at least once, there may be a possibility of undefined system functions.
The system parameters (see Chapter Parameters) are set to the relevant default value!

Please note:

<table>
<thead>
<tr>
<th>External Stop input No. = 0</th>
</tr>
</thead>
<tbody>
<tr>
<td>External Start input No. = 0</td>
</tr>
<tr>
<td>etc.</td>
</tr>
</tbody>
</table>

System initialization of the PA-CONTROL is absolutely essential in the following cases:
- when commissioning the CPU3 for the PA-CONTROL for the first time (carried out at IEF Werner)
- after exchanging the RAM chip on the CPU3
- after exchanging the battery on the CPU3
- after changing the EPROM (new software) on the CPU3

A distinction must be made between the units with LCD and keyboard and the units with 7-segment status display as regards the procedure for system initialization of the PA-CONTROL.
2.14.1 System initialization for units with LCD and keyboard

- Switch off the unit
- Set the key-operated switch to position "Program" (horizontal)
- Keep the "SHIFT" and "9" key pressed and switch the unit on
- You will see the following display after approx. 2 s

<table>
<thead>
<tr>
<th>Confirm bootload system parameters</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 = yes / Key = no</td>
</tr>
</tbody>
</table>

When you press digit key "1", loading of the default system parameters is started and the PA-CONTROL then responds with the main menu. Pressing any other key aborts the procedure which, in this case, may lead to a system crash.

- Select sub-option "4" = Reinitialize PA-CONTROL in menu option "7 = Defaults".

Note:

| This procedure resets all flags, sets all registers to 0, deletes all programs and loads the parameters with the default values. |
2.14.2 System initialization for units without LCD and keyboard

On these units, system initialization can be carried out only with the "PROPAC" program package and PC via the serial interface.

- Connect the PA-CONTROL and PC with the serial interface cable. Only interface 1 (socket connector) can be used on the PA-CONTROL for this purpose. The interface dependent upon the configuration must be used on the PC.
- Start "PROPAC" on the PC
- Select menu option "4 = Simulation of the PAC front panel" in PROPAC
- You will see message "Attempting to establish contact with PA-CONTROL" on the PC monitor
- Now switch on the PA-CONTROL
- Window "Simulation of the front panel PA-CONTROL" with the following message is displayed on the PC monitor after approx. 1 s

    Load default system parameters ?
    yes = SHIFT 9, no = Key

By pressing keys SHIFT and 9, you can start the default system parameter loading operation after you have confirmed the action again (see below).

    Do you really want to load default system parameters ?
    1 = yes / Key = no

You can start loading the default system parameters by pressing digit key "1", and the PA-CONTROL then responds with the main menu. Pressing any other key aborts the procedure which, in this case, may lead to a system crash.

- Select sub-option "4 = Reinitialize PA-CONTROL" in menu option "7 = Defaults".

Important:

  During this operation, all flags are reset, all registers are set to 0, all programs are deleted and the parameters are loaded with the default values.
# 3 Instructions of the PA-Control family

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### 3.1 Overview instruction set

#### 3.1.1 Positioning instructions

The positioning instructions are possible with all available axes!

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<tr>
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<tr>
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</tr>
<tr>
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</tr>
<tr>
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<tr>
<td>G100.X.50</td>
<td>Set acceleration of the X axis to 50 disb./ss</td>
<td>3-62</td>
</tr>
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<td>G120.In.m</td>
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</tr>
<tr>
<td>G123. X I12.1</td>
<td>Positioning is with the X axis as long as input 12 is energized</td>
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<tr>
<td>G140.X</td>
<td>Switch to Measuring Mode***</td>
<td>3-66</td>
</tr>
<tr>
<td>G141.X</td>
<td>Switch to Control Mode***</td>
<td>3-67</td>
</tr>
<tr>
<td>G150.X200</td>
<td>In the next positioning operation, move with the X axis the last 200 increments with the start/stop speed****</td>
<td>3-68</td>
</tr>
</tbody>
</table>

* Only use with devices with pulse generation PLS5, 2 from 8 axes!

#### 3.1.2 I/O processing

<table>
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<th>Instruction</th>
<th>Description</th>
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</tr>
</thead>
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<td>I1.0</td>
<td>Wait until input 1 is logical 0</td>
<td>3-18</td>
</tr>
<tr>
<td>I2.1</td>
<td>Wait until input 2 is logical 1</td>
<td>3-18</td>
</tr>
<tr>
<td>O12.0</td>
<td>Wait until output 12 is logical 0</td>
<td>3-19</td>
</tr>
<tr>
<td>O22.1</td>
<td>Wait until output 22 is logical 1</td>
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</tr>
<tr>
<td>M1.0</td>
<td>Wait until label 1 is logical 0</td>
<td>3-20</td>
</tr>
<tr>
<td>M2.1</td>
<td>Wait until label 2 is logical 1</td>
<td>3-20</td>
</tr>
<tr>
<td>O4:=1</td>
<td>Output 4 is set</td>
<td>3-21</td>
</tr>
<tr>
<td>O3:=0</td>
<td>Output 3 is reset</td>
<td>3-21</td>
</tr>
<tr>
<td>M41:=0</td>
<td>Label 41 is reset</td>
<td>3-22</td>
</tr>
<tr>
<td>M15:=1</td>
<td>Label 15 is set</td>
<td>3-22</td>
</tr>
</tbody>
</table>
3.1.3 Dwell and monitoring times

- **T300**: Dwell time \( T_{300} = 3 \text{ s} \), smallest increment is \( 1 = 10 \text{ ms} \) ................... 3-23
- **TN34**: Dwell time is determined by contents of N34 .................................. 3-23
- **G401.1**: Time monitoring reset............................................................ 3-87
- **G421.1.123 Label**: Start time monitoring and conditional jump if time of 1230 ms has elapsed. ...................... 3-85
- **G422.1.56 Name**: Start time monitoring and subroutine call if time of 560ms has elapsed. .......................... 3-86

3.1.4 Instructions for program organization

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- **$Label**: Jump label ........................................................................... 3-24
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- **G22 O3.1 Name**: Conditional subroutine call ........................................... 3-35
- **G22 M4.1 Name**: Conditional subroutine call ........................................... 3-35
- **DEC.N8 Label**: Check content of integer register 8. If content of register 8 is greater than 0, then decrement content by 1 and jump to label Otherwise, execute next instruction ............................ 3-44
- **CASE.JMP.N2**: Check content of integer register 2 and branch dependent upon content .......................................................... 3-36
  - **(PALET_GR)**: \( N_2 = 1 \): Jump to label "PALET_GR"
  - **(PALET_KL)**: \( N_2 = 2 \): Jump to label "PALET_KL"
  - **(PALET_14)**: \( N_2 = 3 \): Jump to label "PALET_14"
  - **(PALET_01)**: \( N_2 = 4 \): Jump to label "PALET_01"
  - **(PALET_UN)**: \( N_2 = 5 \): Jump to label "PALET_UN"
  - **(PALET_UN)**: \( N_2 = 6 \): Jump to label "PALET_UN"
  - **(PALET_37)**: \( N_2 = 7 \): Jump to label "PALET_37"

**ELSE NEUWAHL**: If \( N_2 < 1 \) or \( N_2 > 7 \) (in this case, only 7 jump labels defined), jump to label "NEUWAHL"

- **CASE.SUB.N2**: Check content of integer register 2 and branch dependent upon content .......................................................... 3-38
  - **(BIEGEN)**: \( N_2 = 1 \): Call subroutine "BIEGEN" and then continue with program line after "ELSE VONVORN"
  - **(BOHREN)**: \( N_2 = 2 \): Call subroutine "BOHREN" and then continue with program line after "ELSE VONVORN"
  - **(BIE_BOH)**: \( N_2 = 3 \): Call subroutine "BIE_BOH" and then continue with program line after "ELSE VONVORN"
  - **(WASCHEN)**: \( N_2 = 4 \): Call subroutine "WASCHEN" and then continue with program line after "ELSE VONVORN"

**ELSE VONVORN**: If \( N_2 < 1 \) or \( N_2 > 4 \) (in this case, only 4 subroutine calls defined), jump to label "VONVORN"
3-6 Instructions

PA-CONTROL system concept

BREAK

The running program is aborted. The PAC is back in the main after this command ................................................................. 3-46

3.1.5 Special functions

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<th>Function Description</th>
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</tr>
<tr>
<td>G11.1</td>
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<td>GN2.100</td>
<td>Display integer register 2 for 1 second</td>
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</tr>
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<td>GR5.200</td>
<td>Display real number register 5 for 2 seconds</td>
<td>3-27</td>
</tr>
<tr>
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<td>Storing values in PNC programmes</td>
<td>3-40</td>
</tr>
<tr>
<td>(TYPE_001)</td>
<td>N2=1: Jump to subroutine &quot;TYPE_001&quot;</td>
<td></td>
</tr>
<tr>
<td>(TYPE_002)</td>
<td>N2=2: Jump to subroutine &quot; TYPE_002&quot;</td>
<td></td>
</tr>
<tr>
<td>(TYPE_003)</td>
<td>N2=3: Jump to subroutine &quot; TYPE_003&quot;</td>
<td></td>
</tr>
<tr>
<td>ELSE NEUWAHL</td>
<td>when N2&lt;1 or N2&gt;3 (only 3 jump marks defined here) then jump to mark &quot;NEUWAHL&quot;</td>
<td></td>
</tr>
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<td>STORE Name</td>
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</tr>
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<td>G24.N12.0</td>
<td>Read in a value from keyboard and store in integer register 12</td>
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</tr>
<tr>
<td>G24.R45.0</td>
<td>Read in a value from keyboard and store in real number register 45</td>
<td>3-51</td>
</tr>
<tr>
<td>G24.R27.1.5.9.3.2</td>
<td>Read in a value by multiplexing from inputs (BCD code) and assign to a real number register</td>
<td>3-53</td>
</tr>
<tr>
<td></td>
<td>27: Target registerer</td>
<td></td>
</tr>
<tr>
<td></td>
<td>1: No sign evaluation</td>
<td></td>
</tr>
<tr>
<td></td>
<td>5: As of input number 5</td>
<td></td>
</tr>
<tr>
<td></td>
<td>9: Output 9 is the first output for multiplexing</td>
<td></td>
</tr>
<tr>
<td></td>
<td>3: Value has 3 digits before the decimal point</td>
<td></td>
</tr>
<tr>
<td></td>
<td>2: Value has 2 digits after the decimal point</td>
<td></td>
</tr>
<tr>
<td>G24.N27.1.5.9.3.0</td>
<td>Read in a value by multiplexing from inputs (BCD code) and assign to an integer register (see above for further information)</td>
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<td>Jump to label when all axes have reached their position</td>
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</tr>
<tr>
<td>G211.0.0 Label</td>
<td>Jump to label if all axes have not yet reached position</td>
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</tr>
<tr>
<td>G211.X.1 Label</td>
<td>Jump to label when the X axis has reached its position</td>
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<tr>
<td>G211.Y.0 Label</td>
<td>Jump to label when the Y axis has not yet reached position</td>
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<tr>
<td>G212.0.1 Name</td>
<td>Call subroutine when all axes have reached their position</td>
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</tr>
<tr>
<td>G212.0.0 Name</td>
<td>Call subroutine if not all axes have reached their position</td>
<td>3-75</td>
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<tr>
<td>G212.X.1 Name</td>
<td>Call subroutine when X axis has reached its position</td>
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<tr>
<td>G212.Y.0 Name</td>
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<td>G222.1.X240 Name</td>
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### 3.1.6 Value and text output via serial interface

- **G500.0**
  The LCD display on the PA-CONTROL becomes the current data channel. 3-89

- **G500.1.2.4.0**
  Initializes serial interface 1 (300 baud, 7 bit, 1 stop bit, OP, no handshake). 3-89

- **G501**
  Delete the screen and position the cursor in the upper left corner. 3-91

- **G502**
  Delete the line as from the current cursor position until the end of the line. 3-92

- **G503.4.2**
  Position the cursor in the 2nd line in the 4th column. 3-93

- **G503.N40.N32**
  Position the cursor. The line number is in N32, the position within the column in N40. 3-93

- **G510.hallo**
  Outputs text “hallo”. 3-94

- **G511.hallo**
  Outputs text “hallo” and then CR LF. 3-94

- **G512.n**
  n is a number between 0 and 255 and is transferred as a ASCII character. 3-96

- **G512.Ni**
  The contents of the integer number register Ni are sent as ASCII characters. 3-96

- **G512.N!i**
  Selection of an ASCII character using the indirect addressing. 3-96

- **G515.5.ERROR**
  Output the 5th line of the program "ERROR" on the current data channel. 3-97

- **G515.N3.ERROR**
  Fetch the content from N3 and output the corresponding line of the "ERROR" program. 3-97

- **G520.R4**
  Outputs the content of real number register 4. 3-98

- **G520.N2**
  Outputs the content of integer register 2. 3-98

- **G520.I12**
  Outputs the logical state of input 12. 3-98

- **G520.O45**
  Outputs the logical state of output 45. 3-98

- **G520.M56**
  Outputs the logical state of flag 56. 3-98

- **G521.**
  Corresponds to G520; in addition, CR LF is transferred. 3-99
3.1.7 Read in value from serial interface

**G531.R4 Label**
Waits for reception of a number and load the number in R4........3-101

**G531.N6 Label**
Waits for reception of a number and load the number in N6........3-101

**G531.07 Label**
Waits for reception of status information and assign it to O7........3-101

**G531.M1 Label**
Waits for reception of status information and assign it to M1........3-101

**G532.13 Label**
Transfer characters (max. 80) into the character buffer until "CR" is received.................................................................3-103

**G533.13**
Transfer characters (max. 80) in the background into the character buffer until "CR" is received...........................................3-104

**N1:=CHN**
Check that the character transfer in the background is completed and assign the result N1......................................................3-106

**N2:=POS.1.35**
Search as from Position 1 (Start) in the character buffer for the position of the character "#" (23 hex) and store the position in the register N2.............................................................................3-108

**N3:=COPY.2.5 FEHL**
As from the 2nd character, change the next 5 characters in the character buffer into a number and store it in the integer register 3.................................................................3-109

**R4:=COPY.2.5 FEHL**
As from the 2nd character, change the next 5 characters in the character buffer into a number and store it in the floating point number register 4..................................................................3-109

If transfer errors or invalid values are recognized, a jump occurs to the point defined by a marker.

**G540.N5**
Check that the button is (was) pressed and store the key code in N5. Otherwise, N5 is set to zero......................................................3-106

**G541.N7**
Wait until a button is pressed and store the key code in N7..........3-111

**G542.3.2.7.N1**
Allows the input of a value into register N1. The input field appears in the 3rd column in the 2nd line and is 7 characters long.................................................................3-112

**G542.2.1.4.R23**
Allows the input of a value into register R23. The input field appears in the 2nd column in the 1st line and is 4 characters long.................................................................3-112

Allows the input of a value into register N1. The position of the input field is in N41 (column) and in N54 (line). The length of the input field is in N9......................................................3-112
3.1.8 Register mapping to outputs or flags

G600.R3.2.8  
Content of R3 is output in binary code as of output 2 at 8 outputs (i.e. from O2 to O9; O2 is the least significant digit)........... 3-114

G601.R6.1.4  
Content of R6 is output in BCD code as of output 1 at 4 outputs (i.e. from O1 to O4; O1 is the least significant digit).............. 3-115

G602.R3.1.16  
Content of R3 is mapped in binary code as of flag 1 at 16 flags (i.e. from M1 to M16; M1 is the least significant digit)........... 3-116

G600.N3.2.8  
Content of N3 is output in binary code as of output 2 at 8 outputs (i.e. from O2 to O9; O2 is the least significant digit)........... 3-114

G601.N6.1.4  
Content of N6 is output in BCD code as of output 1 at 4 outputs (i.e. from O1 to O4; O1 is the least significant digit).............. 3-115

G602.N3.1.16  
Content of N3 is mapped in binary code as of flag 1 at 16 flags (i.e. from M1 to M16; M1 is the least significant digit)........... 3-116

3.1.9 Load register contents from inputs

G603.R3.1.8  
The state of inputs 1 to 8 is interpreted in binary code and the value is loaded in register R3. (I1 is the least significant digit)................................................................................................................. 3-118

G603.N3.1.8  
The state of inputs 1 to 8 is interpreted in binary code and the value is loaded in register N3. (I1 is the least significant digit)................................................................................................................. 3-118

3.1.10 Load Register Contents from Flag

G604.R5.3.32  
The flags 3 to 34 are interpreted in binary format and the value loaded in register R5 (M3 has the least-significant digit)................................................................................................................. 3-119

G604.N3.17.8  
The flags 17 to 24 are interpreted in binary format and the value loaded in register N3 (M17 has the least-significant digit)................................................................................................................. 3-119
3.1.11 Arithmetic operations

Note:

There are 512 real number registers (R1 - R512) and 512 integer number registers (N1 - N512) in the PNC programmes. The registers R1 - R128 and N1 - N128 are in the PAB!

In the examples the register numbers are identified by the letters n, m and i.

Direct addressing with real number register:
(The same operations are also available for the integer registers (Nn, Ni, Nm))
Please note: N5;=3 is possible, N5;=5.7 is not permitted

Rn;=245.73 Load register with 245.73.................................................................3-121
Rn;=-1.0 Load register with -1.0 ......................................................................3-121
Rn;=X Load register with absolute position of the X axis...............................3-121
Rn;=Rm Load register Rn with contents of Rm.............................................3-121
Rn;=Rn+56 Increment register content by 56...................................................3-123
Rn;=Rn-56 Decrement register content by 56..................................................3-124
Rn;=Rm*2 Multiply register Rm by 2 and assign results to Rn........................3-125
Rn;=Rm/2 Divide register Rm by 2 and assign results to Rn.............................3-126
Rn;=Rn+Rm Increment register content by register content of Rm................3-123
Rn;=Rn-Rm Decrement register content by register content of Rm...............3-124
Rn;=Rm*Ri Multiply register Rm by Ri and assign result to Rn.....................3-125
Rn;=Rm/Ri Divide register Rm by Ri and assign result to Rn............................3-126
Rn;=Rai Load register with axis parameter...................................................3-122

Indirect addressing:
This is identified by "!" between R and the register number. The register of n serves as the destination or source address.

Example:

R3;=5
R13;=245 Corresponds to function R5;=245

Indirect addressing is permitted for all register operations

Conversion:

R1;=N45 Load real number register 1 with the value from integer register 45 .................................................................3-121
N23;=R56 Load integer register 23 with the value from real number register 56. The real number is rounded.................................3-121
3.1.12 Compare operations

A logical state (0/1) is always assigned to the addressed flag!

M1:=R2=5  M1 is set if content of R2 is equal to 5; otherwise it is reset............ 3-128
M5:=R2>5  M5 is set if content of R2 is greater than 5; otherwise it is reset........ 3-128
M1:=R2<5  M1 is set if content of R2 is less than 5; otherwise it is reset........ 3-128
M8:=N2=R4 M8 is set if content of R2 is equal to N4; otherwise it is reset........... 3-128
M1:=R7>N5 M1 is set if content of R7 is greater than N5; otherwise it is reset..... 3-128
M1:=R5<N8 M1 is set if content of R5 is less than N8; otherwise it is reset......... 3-128
M1:=R2=5  M1 is set if content of R2 is equal to 5; otherwise it is reset............ 3-128
M5:=N2>5  M5 is set if content of N2 is greater than 5; otherwise it is reset...... 3-128
M1:=N2<5  M1 is set if content of N2 is less than 5; otherwise it is reset.......... 3-128
M8:=N2=N4 M8 is set if content of N2 is equal to N4; otherwise it is reset............ 3-128
M1:=N7>N5 M1 is set if content of N7 is greater than N5; otherwise it is reset..... 3-128
M1:=N5<N8 M1 is set if content of N5 is less than N8; otherwise it is reset........... 3-128

Indirect addressing can be used here as well for the registers. In the case of compare operations, the first operand is always a register and the second operand may be a register or a constant.

3.1.13 Instructions for logic operations

Please refer to the Operating instructions for the parallel sequential control (PAB) for a detailed description with examples further to the instructions listed below.

Two registers are used for implementing the logic operations in the PAB: The "bit accumulator" and the "bit accumulator stack". The result of a logic operation between two elements is stored in the two registers for further processing.

LD I3.1  Opens a new path for logic operations, store state of the "bit accumulator" in the "bit accumulator stack" and load the bit accumulator with logical 1 if input 3 is energized, otherwise, with logical 0. ................................................................................................... 3-133
AND I4.0 Performs an AND operation on the "bit accumulator" and the listed element and stores the result in the "bit accumulator". If the state of the element corresponds to the listed notation (in this case: input 4 not energized), the bit accumulator is AND-ed with a logical 1 (it is loaded with a logical 1). Otherwise, the bit accumulator is AND-ed with a logical 0 (loaded with a logical 0). ............... 3-133
OR M12.0 Performs an OR operation on the "bit accumulator" and the listed element and stores the result in the "bit accumulator". If the state of the element corresponds to the listed notation (in this case: flag 12 not set), the bit accumulator is OR-ed with a logical 1 (it is loaded with a logical 1). Otherwise, the bit accumulator is OR-ed with a logical 0 (it remains unchanged). .................... 3-134
OUT 05  Influences the list of elements corresponding to the contents of the "bit accumulator". "Bit accumulator" equal to "1" element is set. "Bit accumulator" equal to "0" element is reset................. 3-133
AND-LD Performs an AND operation on the "bit accumulator" and the "bit accumulator stack" and stores the result in the "bit accumulator". ........................................................................................................ 3-135
3.1.14 Communication with the parallel sequential control

Please note:

These commands can only be used in conjunction with the PAB (optional).

<table>
<thead>
<tr>
<th>Command</th>
<th>Description</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>RUN Name</td>
<td>Start program Name from the PAB or continue executing program &quot;Name&quot; (if &quot;SLEEP&quot; was active)</td>
<td>3-138</td>
</tr>
<tr>
<td>SLEEP Name</td>
<td>Stop execution of program &quot;Name&quot; on the PAB and set it to mode &quot;SLEEP&quot;</td>
<td>3-140</td>
</tr>
<tr>
<td>CANCEL Name</td>
<td>Terminate execution of program &quot;Name&quot; on the PAB</td>
<td>3-141</td>
</tr>
<tr>
<td>CASE.RUN.Ni</td>
<td>Starting PAB programmes depending on a integer number register</td>
<td>3-142</td>
</tr>
<tr>
<td>(TYPE_001)</td>
<td>Ni=1: Start PAB programme &quot;TYPE_001.PAB&quot;</td>
<td></td>
</tr>
<tr>
<td>(TYPE_002)</td>
<td>Ni=2: Start PAB programme &quot;TYPE_002.PAB&quot;</td>
<td></td>
</tr>
<tr>
<td>(TYPE_003)</td>
<td>Ni=3: Start PAB programme &quot;TYPE_003.PAB&quot;</td>
<td></td>
</tr>
<tr>
<td>ELSE NEUWAHL</td>
<td>when Ni&lt;1 or Ni&gt;3 (only 3 jump marks defined here) then jump to mark &quot;NEUWAHL&quot;</td>
<td></td>
</tr>
<tr>
<td>CASE.SLEEP.Ni</td>
<td>Stopping PAB programmes depending on a integer number register</td>
<td>3-144</td>
</tr>
<tr>
<td>(TYPE_001)</td>
<td>Ni=1: Stop the PAB programme &quot;TYPE_001.PAB&quot;</td>
<td></td>
</tr>
<tr>
<td>(TYPE_002)</td>
<td>Ni=2: Stop the PAB programme &quot;TYPE_002.PAB&quot;</td>
<td></td>
</tr>
<tr>
<td>(TYPE_003)</td>
<td>Ni=3: Stop the PAB programme &quot;TYPE_003.PAB&quot;</td>
<td></td>
</tr>
<tr>
<td>ELSE NEUWAHL</td>
<td>when Ni&lt;1 or Ni&gt;3 (only 3 jump marks defined here) then jump to mark &quot;NEUWAHL&quot;</td>
<td></td>
</tr>
<tr>
<td>CASE.CANCEL.Ni</td>
<td>Terminates the PAB programmes depending on a integer number register</td>
<td>3-146</td>
</tr>
<tr>
<td>(TYPE_001)</td>
<td>Ni=1: Terminates the PAB programme &quot;TYPE_001.PAB&quot;</td>
<td></td>
</tr>
<tr>
<td>(TYPE_002)</td>
<td>Ni=2: Terminates the PAB programme &quot;TYPE_002.PAB&quot;</td>
<td></td>
</tr>
<tr>
<td>(TYPE_003)</td>
<td>Ni=3: Terminates the PAB programme &quot;TYPE_003.PAB&quot;</td>
<td></td>
</tr>
<tr>
<td>ELSE NEUWAHL</td>
<td>when Ni&lt;1 or Ni&gt;3 (only 3 jump marks defined here) then jump to mark &quot;NEUWAHL&quot;</td>
<td></td>
</tr>
</tbody>
</table>
### 3.1.15 Commands for controlling the counters:

Please note:

<table>
<thead>
<tr>
<th>Command</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>CNT1:=10</td>
<td>Set counter 1 to the value 10</td>
</tr>
<tr>
<td>CNT2:=N10</td>
<td>Set counter 2 to the contents of the integer register 10</td>
</tr>
<tr>
<td>N1:=CNT2</td>
<td>Read counter 2 and store the read value in the integer register 2</td>
</tr>
<tr>
<td>CNT4.1.3456</td>
<td>Wait until the contents of counter 4 is greater than 3456</td>
</tr>
<tr>
<td>CNT3.1.N67</td>
<td>Wait until the contents of counter 3 is greater than the contents of</td>
</tr>
<tr>
<td></td>
<td>the integer register 67</td>
</tr>
<tr>
<td>CNT10.0.3456</td>
<td>Wait until the contents of counter 4 is less than 3456</td>
</tr>
<tr>
<td>CNT11.0.N67</td>
<td>Wait until the contents of counter 3 is less than the contents of</td>
</tr>
<tr>
<td></td>
<td>the integer register 67</td>
</tr>
</tbody>
</table>
3.2 Programming information

A program is identified by a program name and has an extension. This extension serves to indicate the type of program.

A program name consists of maximum 8 alphanumeric characters (0-9, A-Z). The 1st character must be a letter. Only the hyphen "-" and the underscored character "_" are permitted as special characters within the name. The program type consists of three letters.

The following program types are possible in the PA-CONTROL:

- **PNC**: Programs with instructions for positioning, inputs/outputs, program branching. These programs implement a program run. A syntax check is conducted in these programs when writing the program.

- **PTX**: Text programs for labelling the inputs/outputs, flags and registers and for the user title. No syntax check is conducted in the PTX programs.

- **PAB**: Program with in-, output and program branching commands. This program is intended for parallel process Control (option).

A PNC program consists of individual instructions which are executed one after the other and must be terminated with the END instruction. A PNC program may call a further PNC program with the SUB instruction as a subroutine (a nesting depth of up to 15 is permitted).

Conditional and unconditional jumps to labels may be executed within a PNC program. The label names are known only within a PNC program. It is thus possible (practical?) to use the same label names in different PCN programs.

Jump instructions from one PCN program to another PCN program are not possible.

A label name consists of maximum 8 alphanumeric characters (0-9, A-Z). The 1st character must be a letter. Only the hyphen "-" and the underscored character "_" are permitted as special characters within the name.

The label name is terminated by a blank, semicolon or end-of-line character. When defining the label, the label must be located in the first column of the line, headed by the "$" character. The label may be defined only once within a program. Of course, a jump from various positions to this one label is permitted.
An editor is provided for writing PA-CONTROL programs (see Chapter Operator interface for calling the editor).

The editor has a line-oriented organization, whereby the line number is always prefixed in front of the program line at the left on the display. A program may have a length of up to 999 lines.

The editor is always in Insert mode, i.e. new characters are inserted (appended) at the cursor position. A program line may have a length of up to 36 characters.

When you quit the program line, a syntax check is conducted on the instructions. You must confirm error messages of the syntax check (press a key) and the error must then be rectified. Otherwise, you cannot quit the program line and the program cannot be stored.

Key assignment in the program editor:

<table>
<thead>
<tr>
<th>Key</th>
<th>Response / Effect</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arrow left</td>
<td>Moves one character to the left (to the start of the program)</td>
</tr>
<tr>
<td>Arrow right</td>
<td>Moves one character to the right (max as far as the end of the program)</td>
</tr>
<tr>
<td>Arrow down</td>
<td>Moves to next program line down (max. last line)</td>
</tr>
<tr>
<td>Arrow up</td>
<td>Moves to previous program line (max. first line)</td>
</tr>
<tr>
<td>SHIFT + Arrow left</td>
<td>Moves to first column of the current program line</td>
</tr>
<tr>
<td>SHIFT + Arrow right</td>
<td>Moves to the end of the current program line</td>
</tr>
<tr>
<td>DEL</td>
<td>Deletes character at which the cursor is located (beyond line boundary)</td>
</tr>
<tr>
<td>SHIFT + DEL</td>
<td>Deletes character to the left of the cursor (beyond line boundary)</td>
</tr>
<tr>
<td>ENTER</td>
<td>Inserts a new program line at the cursor position</td>
</tr>
<tr>
<td>ESC</td>
<td>Quits the program editor and stores the program on request</td>
</tr>
</tbody>
</table>
Various elements which can be addressed during programming are available in the PA-CONTROL.

Inputs: An input can be scanned for its logical state

Outputs: Logical state 0 or 1 can be assigned to an output. In the case of conditional jumps, a logical state may be scanned.

Flags: Logical state 0 or 1 may be assigned to a flag and a logical state can be scanned.

Timers: Timers are used to generate defined waiting times.

Real number registers: Real number registers (1-512) are special memory locations for real numbers (+/- 8.000.000,000). The register contents can be used for positioning and for arithmetic and compare operations. Up to 3 positions after the decimal point are permitted.

Integer registers: Integer registers (1-512) are special memory locations for integers (+/- 8.000.000). The register contents can be used for timers and for counting, arithmetic and compare operations. No digits after the decimal point are permitted.

Axes: Axes are stepping motor axes and serve the purpose of positioning. They are addressed with names X, Y, Z, U, V, W, Q, P (only inasmuch as these names are present in the control).

Labels: Labels are orientation points and serve as destinations for conditional and unconditional jumps. Example of a label: $ROTBLAU

Comment: A comment is initiated by a semicolon (;) and serves the purpose of program documentation (see examples in the section on explanation of the instructions) and also serves the purpose of operator prompting in Automatic mode.
3.4 Explanations

Instruction abbreviations

Instruction form:

```
mmmmmm nnnnn
```

The instructions are subdivided into operand and operator or, in other words, abbreviation and a number.
The spaces between the operand and operator have been included in the "Instruction form" section for the sake of clarity and are not permitted for input in the PA-CONTROL!
There may be several instructions in one program line. Instructions of one line must be separated from each other by at least one blank.

Example:

Program: BEISPIEL
1
2

The program name for the examples has been shown in italics. The numbers in italics at the start of the line are the line numbers which are generated by the editor itself in the PA-CONTROL and which serve only the purpose of orientation in the program editor.
The examples can be keyed in directly. As in the PA-CONTROL, comments are separated with a semicolon and can be included in the program provided they do not exceed the maximum line length of 36 characters. All programs are always terminated with the END instruction.

**Important:** The examples have been written without a knowledge of the actual mechanical system and must always be checked for practical applicability.

Application:

A few words on the practical application of the respective instruction are contained in this section.

Description:

The description is explained once more in general terms in this section.

**Important:**

Here, we would like to point out special features and provide help in the form of cross references.
3.5 Wait for logical state of input

**Instruction form:**

nn.m

**Example:**

Program : BEISPIEL
1 I8.0 ;Control waits until input 8 is logical 0
2 I4.1 ;Control waits until input 4 is logical 1
3 END

**Application:**

Scanning proximity switches, pushbuttons and switches etc.

**Description:**

The control checks whether the input nn specified in the operator possesses the state m with the instruction I (input). If the scan response is not true, the control waits until the condition in the operator m is satisfied.
3.6 Wait for logical state of output

**Oi.j**

**Instruction form:**

Onn.m

**Example:**

Program: BEISPIEL

1  O8.:=1 ;Control sets output 8 (e.g. triggering for parallel sequential control)
2  O7.1 ;Control waits until output 7 is logical 1 (has been set by parallel sequential control)
3  END

**Application:**

Scanning outputs

**Description:**

In the case of instruction O (output), the control checks whether the output nn specified in the operator has the state m. If the scan is not true, the control waits until the condition in the operator m is satisfied.

**Note:**

This instruction is practical only on a PA-CONTROL equipped with a parallel sequential control (PAB). This is because only the PAB can set the output whilst the PA-CONTROL waits for the output.
3.7 Wait for logical state of flag

**Instruction form:**

Mnn.m

**Example:**

Program: BEISPIEL

1   O8:=1 ;Control sets output 8 (e.g. triggering for parallel sequential control)

2   M7.1 ;Control waits until flag 7 is logical 1 (has been set by parallel sequential control)

3   END

**Application:**

- Scanning flags

**Description:**

In the case of instruction M (flag), the control checks whether the flag nn specified in the operator has the state m. If the scan is not true, the control waits until the condition in the operator m is satisfied.

**Note:**

This instruction is practical only on a PA-CONTROL equipped with a parallel sequential control (PAB). This is because only the PAB can set the flag whilst the PA-CONTROL waits for the flag.
3.8 Set/reset output

Oi:=j

Instruction form:

On:=m

Example:

Program : BEISPIEL
1 O8:=1 ;Output 8 is set to 1
2 O7:=0 ;Output 7 is set to 0
3 END

Application:

Switching relays, signal forwarding to other electrical devices.

Description:

The available outputs can be influenced with instruction O (output). If the output nn is set to state m = 1, it switches through, i.e. the transistor is forward-biased, and remains switched on until it is reset with m = 0 and the transistor is rendered reverse-biased.
3.9 Set/reset flag

Instruction form:

\[ Mn := m \]

Example:

Program: BEISPIEL
1 I8.1 ; Control waits until input 8 is logical 1
2 M12 := 1 ; Flag 12 is set to logical 1
3 M239 := 0 ; Flag 239 is set to logical 0
4 END

Application:

Storing states, processing situations

Description:

The available flags can be influenced with instruction M. If the flag nnn is set to logical state \( m = 1 \), it remains in this state until it is reset with \( m = 0 \) (see also Instruction description, Compare operations).

Note:

The status of the flag is still retained even when the control is switched off.

The flags 240-256 are used by the system and are therefore not suitable for storing general information.

- **M250**: Is set at ’1’ after recognizing the operating voltage (Power On flag).
- **M251**: Restores the position of the key switch Automatic = ’1’, Programme = ’0’.
- **M254**: The STORE command sets the flag at ’1’. If the command has been successfully carried out the flag remains at ’1’. If an error occurs during the STORE command the flag is reset at ’0’ (See chapter 3.21 and 3.22).
- **M255**: The CASE.xxx commands set the flag at ’1’, when the jump mark is defined, otherwise with ELSE, the flag is reset at ’0’. (See chapter 3.19, 3.20 and 3.21)
- **M256**: is influenced by the G23-, G120- and G123 functions (see chapter 3.27, 3.36 and 3.37).
3.10 Dwell time

Example:

Program : BEISPIEL
1  T1 ;Dwell time 10ms
2  T300 ;Dwell time 3s
3
4  TN2 ; Dwell time corresponding to content of N2
5  END

Application:

Wait times, keeping outputs set for defined times.

Description:

Instruction T results in a control dwell time for the time specified in the operator.

Possible values:

Minimum time  n   =   1   =   10 ms
Maximum time  n   =   8.000.000   =   80.000,00 s  possible.

Important:

Any sign of the register content is suppressed. The register content remains unchanged.Instruction form:
3.11 Unconditional jump

JMP

Instruction form:

JMP Label

Example:

```
Program : BEISPIEL
1   $ENDLOS
2   I1.1 ;Wait until input 1 is energized
3   O1:=1
4   T100
5   O1:=0
6   JMP ENDLOS ;Jump to label "ENDLOS"
7   END
```

Application:

For program loops

Description:

An "Unconditional jump" is executed with function JMP.
3.12 Subroutine call

SUB

Instruction form:

```
SUB   Name
```

Example:

Program : BEISPIEL

```
1   I2.1
2   SUB LAMBLI ;Subroutine "LAMBLI" is called and executed. Further
               processing of the next instruction in the calling program
               (in this case I3.1) occurs after recognition of the END in-
               struction in the subroutine.
3   I3.1
4   I4.1
5   SUB LAMBLI ;Subroutine "LAMBLI" is called and executed. Further
               processing of the next instruction in the calling program
               (in this case I5.1) occurs when the END instruction is re-
               cognized in the subroutine
6   I5.1
7   END
```

Program : LAMBLI

```
1   O1:=1 ;Output 1 is set for 1 s, then reset
2   T100
3   O1:=0
4   END
```

Description:

Subroutine call SUB allows the user to create a well-structured program. Functions which are re-
quired more than once can thus be placed in a subroutine. The main program then remains clear
and subroutines can be tested individually.

Important:

```
A subroutine may not call itself. Subroutines must be terminated with the END instruction.
A nesting depth of up to 15 is permitted for subroutine calls.
```
Subroutine call, continued

Examples of nestings:

1.

Program : BEISPIEL
1  I2.1
2  SUB LAMBLI

Programm : LAMBLI
1  O1:=1
2  T100
3  O1:=0
4  END

3  I5.1
4  END

2.

Program : BEISPIEL
1  I2.1
2  SUB TEST

Programm : TEST
1  T10
2  SUB LAMBLI

Programm : LAMBLI
1  O1:=1
2  T100
3  O1:=0
4  END

3  I6.1
4  END

3  I5.1
4  END
3.13 Display register n

**Instruction form:**

- GRn.m
- GNn.m
- GR!n.m
- GN!n.m

**Example:**

Program: BEISPIEL

1. G24R4.0 ;Load register 4 via a keyboard
2. GR4.200 ;Display contents of register 4 for 2 s (200*10 ms) on the display
3. N35:=234 ;Load register 35 with 234
4. GN35.100 ;Display content of register N35 for 1 s (100*10 ms) on the display
5. END

**Description:**

The content of register n is displayed in the 1st display line for m*10 ms. The program stops during this display time.

The display is as follows, for instance:

```
R4 = current value
```
3.14 Linear interpolation with 2 out of 8 axes

**Instruction form:**

G01 Ai An
G01 ARi ARn

**Example:**

Program: BEISPIEL

1 G25.X G25.Y G90
2 X10 ; Traverse X axis to position 10
3 Y20 ; Traverse Y axis to position 20
4 FB1000 ; Set tool path feedrate to 1000 Hz
5 G01 X40 Y30 ; Linear interpolation with the X and Y axes from the current position to position X40 and Y30
6 END

**Application:**

Simultaneous traversing of 2 axes involving moving on a straight line between the start and destination positions.

**Description:**

With linear interpolation the target position is reached with the path speed on a straight line. Movements can be carried out axis-parallel and under a given angle. The path speed is set before the first G01 with the command FBn, can be redefined however at the beginning of a new interval (beginning with G01) with FBn. The path acceleration is set using the command G100.B.n.

**Note:**

Only possible in conjunction with PLS5-X.

If interpolation commands appear immediately one after the other in the programme (without other commands in-between), these interpolation commands are then executed together at constant path speed. The linear and circular interpolation commands can be mixed.

From Version 3.2 upwards it is possible to alter the speed at the beginning of a new interval beginning with G01, (the new V path is switched to without stopping). The transfer to the new V path is carried out with the preset path acceleration. This cannot be altered within a contour. When using this command an activation of the G2xx commands is no longer possible.
Complex example involving execution of several linear interpolation operations one after another following a contour at constant tool path feedrate. Distances "a" to "f" are moved in one continuous string owing to the fact that the G01 instructions follow consecutively one after the other (with no other instruction in between).

Program: Beispiel

1. O1: = 0 I5.1 ; Raise tool
2. G25.X G25.Y G90 ; Reference travel operations
3. X30 Y20 ; Approach workpiece edge
4. O1: = 1 ; Lower tool
5. I6.1 ; Wait until tool has been lowered
6. FB500 ; Set tool path feedrate to 500 Hz
7. G100.B.30 ; Set tool path acceleration to 300 Hz/ms
8. G01 X40 Y40 ; Move along side edge "a"
9. G01 X60 Y40 ; Move along side edge "b"
10. G01 X70 Y30 ; Move along side edge "c"
11. G01 X70 Y25 ; Move along side edge "d"
12. G01 X60 Y20 ; Move along side edge "e"
13. G01 X30 Y20 ; Move along side edge "f"
14. O1: = 0 ; Raise tool
15. X1 Y1 ; Approach initial position
16. END
3.15 Circular interpolation

**G02/G03**

**Instruction form:**

- G02 An Am CAi CAj
- G02 ARn ARm CARi CARj
- G03 An Am CAi CAj
- G03 ARn ARm CARi CARj

**Example:**

Program: BEISPIEL

2. X10 ; Traverse X axis to position 10
3. Y20 ; Traverse Y axis to position 10
4. FB1000 ; Set tool path feedrate to 1000 Hz
5. G100.B.10 ; Set tool path acceleration to 10 Hz/ms
6. G02 X20 Y30 CX10 CY0 ; Circular interpolation with X and Y axes from the current position to the end position X20 and Y30, whereby the center of the circle lies offset by 10 in the positive coordinate for the X axis and lies on the start coordinate (offset by 0) for the Y axis, when viewed from the start position.

**Application:**

Simultaneous traversing of 2 axes with movement along a circular arc (also a full circle) between start and destination positions.

**Description:**

With circular interpolation the path speed is used to move from the current position (KA) on the arc to the specified target position (KE). The centre point of the arc (KM) is specified, signed relative to the initial point by the vectors C1 and C2 (see diagram) independent of the system of measuring (G90/G91). **G02** describes a circle clockwise und **G03** anticlockwise. The path speed can be set before interpolation with the command **FBn**. The path acceleration is set using the command **G100.B.n**.

From version 3.2 upwards it is also possible to redefine the path speed at the beginning of new intervals (within a contour), beginning with **G01**, **G02** or **G03**. The new V path is switched to without stopping.
Note:

Only possible in conjunction with PLS5-X.

If interpolation commands appear immediately one after the other in the programme (without other commands in-between), these interpolation commands are then executed together at constant path speed. The linear and circular interpolation commands can be mixed.

From Version 3.2 upwards it is possible to alter the speed at the beginning of a new interval beginning with G01, (the new V path is switched to without stopping). The transfer to the new V path is carried out with the preset path acceleration. This cannot be altered within a contour. When using this command an activation of the G2xx commands is no longer possible.

Example with circular interpolation.

Program: Beispiel
1  G25.X G25.Y G90 ; Reference travel operations
2  X27 Y15 ; Approach start point of circular arc
3  FB1000 ; Set tool path feedrate to 1000 Hz
4  G100.B.30 ; Set tool path acceleration to 30 Hz/ms
5  G02 X50 Y47 CX13 CY15 ; Circular arc counterclockwise to the destination position X50 and Y47, whereby the center point of the circle for X is 13 (I) units away from the start position of the circle and the center point of the circle for Y is 15 (J) units away from the start point of the circle (in relative terms).
6  END
3.16 Switch display on/off

G11

Instruction form:

G11.n

Example:

Program : BEISPIEL
1  G11.0 ;Display switched off
2  G11.1 ;Display switched on
3  END

Application:

For sequences where speed optimization is necessary and display of the program steps is not required.
The user can assume the form of the display with the commands of the G5xx group.

Description:

Display of instructions during the program run is controlled with function G11. The instruction sequence is executed more quickly if the display is switched off with G11.0. The display can be switched back on again with G11.1. It is not possible to make an absolute statement on the time savings which are possible by using the G11 function since these savings depend on the number of characters in the display to be built up.

Important:

The instruction last executed is displayed irrespective of the program status.
The following instructions are never displayed: JMP, M1:=, etc.!
This permits a previous program line to be displayed when programming loops.
3.17 Conditional jump

**Instruction form:**

- G21 li.j Label
- G21 li,j Label
- G21 Oi.j Label
- G21 Oi,j Label
- G21 Mi.j Label
- G21 Mi,j Label

**Example:**

Program : BEISPIEL

1  G21 I1.1 EIN_5 ;If input 1 is energized, program execution is continued at label "EIN_5"; otherwise, it is continued with the next instruction
2  O1:=1 T100 O1:=0 ;Output 1 set for 1 second
3  $EIN_5
4  T10
5  G21 O5.1 MERK_31 ;If output 5 is set, the program is continued at label "MERK_31" otherwise, it is continued with the next instruction
6  O1:=1 T100 O1:=0 ;Output 1 set for 1 second
7  $MERK_31
8  T10
9  G21 M31.0 ENDE ;If flag 31 is logical 0, the program is continued at label "ENDE"; otherwise, it is continued with the next instruction
10 O1:=1 T100 O1:=0 ;Output 1 set for 1 second
11 $ENDE
12 T10
13 END

**Application:**

Program branch depending on the logical state of an input, flag or output.
Description:

A "conditional jump" is executed with function G21. The condition specified in the operand may be the logical state of an input, output or flag. A jump to the label specified in the operator is performed if the condition is satisfied, and the program is continued at this point. If the condition is not satisfied, the program is continued in the next line.

Note:

There may be no other instruction in this line after the specification of the jump destination. A comment is permitted.
3.18 Conditional subroutine call

G22

Instruction form:

G22 Ii.j   Name
G22 Oi.j  Name
G22 Mi.j  Name

Example:

Program : BEISPIEL
  1  G25.X G90 ;Reference travel X axis, absolute dimension system
  2  G22 I1.1 AUSG_2 ;Falls ;If input 1 is energized, subroutine "AUSG_2" is
     executed and execution is then continued with the next
     instruction of the calling program
  3  G22 M21.1 AUSG_2 ;If flag 21 is set, subroutine "AUSG_2" is executed and
     execution is then continued with the next instruction of the
     calling program
  4  G22 O7.1 AUSG_2 ;If output 7 is set, subroutine "AUSG_2" is executed and
     execution is then continued with the next instruction of the
     calling program
  5  END

Program : AUSG_2
  1  O2:=1 T100 O2:=0 END ;Set output 2 for 1 s

Application:

A subroutine is executed depending on the logical state of an input, flag or output.

Description:

A "conditional subroutine call" is executed with function G22. The condition specified in the oper-
and may be the logical state of an input, output or flag. The subroutine call is executed corre-
sponding to the operator if the condition is satisfied. The program is continued with the next in-
struction of the calling program as soon as the subroutine has been executed or if the condition is
not satisfied.

Note:

There may be no other instruction in this line after the specification of the subroutine
name. A comment is permitted.
3.19 Case jump

**CASE.JMP**

**Instruction form:**

```plaintext
CASE.JMP.Nn
(Label1)
(Label2)
...
(Label_i)
ELSE Label_e
```

**Example:**

Program: BEISPIEL

1 $GRAU
2 G24.N8.0 ; Read in value via keyboard
3 CASE.JMP.N8 ; Check content of N8 and branch if:
4 (ROT) ; N8 = 1: Jump to label "ROT"
5 (BLAU) ; N8 = 2: Jump to label "BLAU"
6 (GELB) ; N8 = 3: Jump to label "GELB"
7 (ROSA) ; N8 = 4: Jump to label "ROSA"
8 ELSE GRAU ; Jump to label "GRAU" if N8<1 or N8>4 (value of N8 not within the scheduled range which is 1 to 4 in this case).
9 $ROT
10 O1:=1 T100 O1:=0 ; Set output 1 for 1 s
11 JMP ENDE
12 $BLAU
13 O2:=1 T100 O2:=0 ; Set output 2 for 1 s
14 JMP ENDE
15 $GELB
16 O3:=1 T100 O3:=0 ; Set output 3 for 1 s
17 $ROSA
18 O4:=1 T100 O4:=0 ; Set output 4 for 1 s
19 $ENDE
20 END

Program: AUSG_2

1 O2:=1 T100 02:=0 END ; Set output 2 for 1 s
Application:

Program branch if there are more than two options, e.g.: Different production types, variations of traversing frequencies etc.

Description:

The CASE.JMP instruction is a program branch as a function of the content of an integer register. Case jumps can be set up simply with this instruction.

The PA checks the content of the integer register and jumps, corresponding to the value, to the labels. If the content of the integer register is less than 1 or greater than the number of elements in the label table (in the example: (ROT), (BLAU), (GELB), (ROSA), a jump is executed to the label after ELSE; otherwise, a jump is executed to the corresponding label.
3.20 Case subroutine

**CASE.SUB**

**Instruction form:**

```
CASE.SUB.Nn
(Name1)
(Name2)
...
ELSE Label_e
```

**Example:**

Program : BEISPIEL
1 $FEHLER
2 G24.N8.0 ; Read in value via keyboard
3 CASE.SUB.N8 ; Check contents of N8 and call subroutine if:
4 (KLEIN) ; N8=1 : Run subroutine "KLEIN"
5 (GROSS) ; N8=2 : Run subroutine "MITTEL"
6 (MITTEL) ; N8=3 : Run subroutine "GROSS"
7 ELSE FEHLER ; Jump to label "FEHLER" if value of N8 lies outside scheduled limits (in this case if N8<1 or N8>3)
8 O12:=0
9 I1.1
10 END

Program : KLEIN
1 O1:=1 T100 O1:=0 ; Set output 1 for 1 s
2 END

Program : GROSS
1 O2:=1 T100 O2:=0 ; Set output 2 for 1 s
2 END

Program : MITTEL
1 O3:=1 T100 O3:=0 ; Set output 3 for 1 s
2 END

**Application:**
Program branch if there are more than two options, such as: different production types, variations of traversing frequencies, ...

Description:

The CASE.SUB instruction is a program branch as a function of an integer register. Case programs can be set up simply with this instruction. The PA checks the content of the integer register and performs a subroutine call depending on the value. If the content of the integer register is less than 1 or greater than the number of elements of the name table (in this example: KLEIN, MITTEL, GROSS), a jump is made to the label defined after ELSE. Otherwise, the corresponding subroutine is called and run, and the system then continues with the program line after the ELSE branch (in the example: line 8 with O12:=0).

The following assignment applies:

<table>
<thead>
<tr>
<th>Value in register</th>
<th>Name in name table</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1st name</td>
</tr>
<tr>
<td>2</td>
<td>2nd name</td>
</tr>
<tr>
<td>...</td>
<td>...</td>
</tr>
<tr>
<td>n</td>
<td>nth name</td>
</tr>
</tbody>
</table>

Note:

The subroutines must exist. Otherwise, an error message "Subroutine not found" is issued. Subroutines may not call themselves.
3.21 Storing Values in PNC Programmes

CASE.STORE

Command form:

CASE.STORE.Ni
(Name1)
(Name2)
...
ELSE Marke_e

Example:

Programme: BEISPIEL
1 $FEHLER
2 G24.N8.0 ;Enter value via keyboard
3 CASE.STORE.N8 ;Check the contents of N8 and call up subroutine at:
4 (TYPE_001) ;N8=1 : subroutine "TYPE_001" check for allocations and update
5 (TYPE_002) ;N8=2 : subroutine "TYPE_002" check for allocations and update
7 ELSE FEHLER ;Jump to "ERROR" mark, if the value of N8 is beyond the intended limits (here when N8<1 or N8>2)
8 END

Programme: TYPE_001
1 R10:=0_ _ _ _ _ _ _ _ _ _ ;X-Collect position for product type 1
2 R11:=0_ _ _ _ _ _ _ _ _ _ ;X-Intermediate position for product type 1
3 N10:=0_ _ _ _ _ _ _ _ _ _ ;Number of products to be machined
4 M101:=0 ;Product flag for product 1
5 END

Programme TYPE_002
1 R10:=0_ _ _ _ _ _ _ _ _ _ ;X-Collect position for product type 2
2 R11:=0_ _ _ _ _ _ _ _ _ _ ;X-Intermediate position for product type 2
3 N10:=0_ _ _ _ _ _ _ _ _ _ ;Number of products to be machined
4 M102:=0 ;Product flag for product 2
5 END

Note:

In the example blanks are represented by an underline “_ _ “.

Application:
Programme branching for storing current register values in different PNC files. For different product types traversing positions (R-register) or status flags for example can be stored and called up again as required.

Description:

The **CASE.STORE** command is a programme branching that is dependant on the contents of the integer number register \( N_i \). The PA control checks the contents of the integer number register and performs a subroutine call-up in accordance with the value. If the contents of the integer number register are smaller than 1 or greater than the number of elements of the name table (here an example: TYPE_001, TYPE_002), a jump is made to the mark that is defined behind ELSE. Otherwise the respective subroutine is called up and processed and continued with the programme line after the ELSE branch.

With the command **CASE.STORE** all the current values of the N registers, R registers and flags filed in a PNC programme.

When carrying out the **CASE.STORE** command the called-up PNC programme is checked for allocations. If a register and/or flag allocation is found the current value is entered in the allocation. There must be sufficient blanks available for this purpose.

- Maximum number of space holders per register : 9 digits
- Maximum number of space holders per flag : 1 digit

**Before carrying out STORE commands**

```
1 R10:=0_ _ _ _ _ _ _ _ _ _ ;X collect position
2 R11:=0_ _ _ _ _ _ _ _ _ _ ;X intermediate position
3 N10:=0_ _ _ _ _ _ _ _ _ _ ;Number of products to be processed
4 M101:=0 ;Product flag for product 1
5 END
```

**After carrying out the STORE command**

```
1 R10:=145.345_ _ _ _ ;X collect position
2 R11:=34565.789_ _ ;X intermediate position
3 N10:=645_ _ _ _ _ _ _ _ ;Number of products to be processed
4 M101:=1 ;Product flag for product 2
5 END
```

**Note:**

> The called-up PNC programme must be available. A programme line should only contain one allocation.
> There must be sufficient zeros or blanks for overwriting after the allocation to ";" (comment) or "CR" (end of line).
> Calculation allocations are not allowed in overwrite mode.
> The **STORE** command sets the flag 254 at '1'. If the command has been carried out successfully the flag remains at '1'. If insufficient digits have been reserved for the allocations the flag is reset at '0'.

---

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3.22 Storing Values in a PNC Programme

```
STORE

Command form:
STORE Name

Example:
Programme: BEISPIEL
1 G24.R10.0 ; Enter real number register via keyboard
e.g. 4678.123
2 G24.N1.0 ; Enter integer number register via keyboard
e.g. 967
3 M25:=N1>11 ; M25 is used when contents of N1 are greater than 11.
4 STORE TYPE_001 ; Overwrite allocations in the PNC programme TYPE_001
   with current values of the registers and flags
5 END

Before carrying out the STORE command
Programme: TYPE_001
1 R10:=0_ _ _ _ _ _ _ _ ; X collect position for product type 1
2 N1:=0_ _ _ _ _ _ _ _ ; Number of products to be processed
3 M25:=0 ; Product flag for product type 1
4 END

After carrying out the STORE command
Programme: TYPE_001
1 R10:=4678.123_ _ ; X collect position for product type 1
2 N1:=967_ _ _ _ _ _ ; Number of products to be processed
3 M25:=1 ; Product flag for product 1
4 END

Note:
In the example blanks are represented by an underline " _ ".

Application:
Storing current register values in different PNC files. For different product types traversing positions (R register) or status flags for example can be stored and called up again as required.
Description:

With the command STORE the current values of N registers, R registers and flags are filed in a PNC programme.
When carrying out the STORE command the called-up PNC programme is checked for allocations. If a register and/or flag allocation is found, the current value is entered in the allocation. Sufficient blanks must be available for this purpose.

- Maximum number of space holders required for register: 9 digits
- Maximum number of space holders required for flag: 1 digit

Note:

The called-up PNC programme must be available. Only one allocation is permitted per programme line.
Sufficient zeros or blanks must be available for overwriting after the allocation to ";" (comment) or "CR" (end of line).
Calculation allocations are not permitted in the programme being overwritten.
The STORE command sets the flag 254 at ‘1’. If the command has successfully been carried out the flag remains at ‘1’. If insufficient digits have been reserved for the allocations the flag is reset at ‘0’.
3.23 Loop with conditional jump

**DEC**

**Instruction form:**

DEC.Nn Marke

**Example:**

Program: BEISPIEL

1 G24.N2.0 ;Read in number of loops
2 $ANFANG
3 O1:=1
4 T100
5 O1:=0
6 T100
7 DEC.N2 ANFANG ;All retries done? No: Jump to ANFANG
8 END

**Application:**

For setting up program loops, the number of runs of which is stored in an integer register, e.g. machine n parts, traverse n times, ...

**Description:**

The DEC instruction serves to set up program loops. It is comparable with the Pascal instruction Repeat...Until or the C instructions Do..While or While..DO. The DEC instruction checks the content of the integer register. If the content of the integer register is greater than 0, the content is decremented by 1 and a jump to the label is executed; otherwise, the system continues with the next instruction (next line).

**Note:**

The DEC instruction can be used only for integer registers. There may be no other instructions in this program line after the DEC instruction. A comment is permitted.
Examples of loops with the DEC instruction:

1. Loop program part is run through at least once (Repeat...Until, Do...While), i.e. the program part is always run, and a check is then conducted (DEC.) in order to establish whether the program part has to be run again.

Program : BEISPIEL
1  G24.N3.0
2  $MACHWAS
3  O1:=1
4  T100
5  O1:=0
6  T100
7  DEC.N3 MACHWAS
8  END

2. The loop program part is not run depending on value (While...), i.e. the register is checked first (DEC.N3) and then the program part is run, depending on the content of the register.

Program : BEISPIEL
1  G24.N3.0
2  $SCHLEIFE
3  DEC.N3 MACHWAS
4  JMP FERTIG
5  $MACHWAS
6  O1:=1
7  T100
8  O1:=0
9  T100
10 JMP SCHLEIFE
11 $FERTIG
12 END
3.24 Break Automatic Cycle

**Break**

Command form:

```
Break
```

Example:

Programme: BEISPIEL.PNC

```
1 $SCHLEIF
2 I10.1 ;Start
3 SUB HOLEN ;Subroutine for collect part
4 SUB BEARBEIT ;Subroutine for process part
5 SUB ABLEGEN ;Subroutine for deposit part
6 G21 I11.1 SCHLEIFE ;Continue producing
7 END
```

Programme: HOLEN.PNC

```
1 G421.1.100 Fehler ;Error, when part collected process is not completed in 1 s
2 O1:=1 ;Open gripper
3 I1.0 I2.1 ;Gripper open
4 O2:=1 ;Lower gripper
5 I3.0 I4.1 ;Gripper down
6 O1:=0 ;Close gripper
7 I2.0 I1.1 ;Gripper closed
8 O2:=0 ;Lift gripper
9 I4.0 I3.1 ;Gripper up
10 G401.1
11 END
12
13 §FEHLER
14 I12.1 ; ACKNOWLEDGE ERROR WHEN PART COLLECTED
15 BREAK
```

Description:

The **BREAK** command discontinues the automatic cycle of the PAC. The PAC returns to the main menu.

Application:

The **BREAK** command is for discontinuing the automatic cycle of the PAC when for example a machine error has occurred in a subroutine. Using the **BREAK** command avoids returning to the programme structure to return to the main programme from more than one subroutine level and from there to branch to the end of the programme.
3.25 Axis positioning

Instruction form:

Xnnnnn
XRn

The positioning instructions are possible with all existing axes!

Example:

Program: BEISPIEL
1  G25.X       ;Perform reference travel with X axis
2  G90        ;Absolute dimension system
3  X200       ;Axis X 200 in positive direction
4  X198       ;Axis X by 2 in negative direction to absolute position 198
5  R3=678
6  XR3       ;Axis X 678 in positive direction
7  G91       ;Incremental dimension system
8  R3=-500
9  X-10      ;Axis X in negative direction
10 XR3       ;Axis X in negative direction
11 END

Application:

Positioning

Description:

The positioning instruction traverses the axes in positive or negative direction, viewed from the datum. The value entered in the operator is the traverse system in the incremental dimension system (G91).

Note:

The end point of the movement is dependent upon the programmed dimension system, either in absolute dimensions (G90) or in incremental dimensions (G91).
3.26 Traversing speed

Instruction form:

- FA nnnnn
- FA Rn
- FB nnnn ; speed for the interpolation
- FB Rn

Example:

Program: BEISPIEL
1  G25.X ;Perform reference travel with X axis
2  G91 ;Set absolute dimension system
3  FX200 ;Traversing speed X axis 200 Div./s
4  X1000
5  R4:=500
6  FXR4 ;Traversing speed X axis 500 Div./s
7  X10
8  END

Application:

Different speeds for traversing and moving axes.

Description:

With the F command the control is instructed to move at the speed specified in the operator for the rest of the programme. All axes that are addressed with the operand F can be moved at different speeds.
If the traversing speed is determined by the contents of a register, the signs and the digits after the comma of the register contents are not taken into account.
The axis parameter determined in the parameter list can also be loaded via a register (see Chapter 0).
FB is for setting the path speed for the interpolation (FBmin = 50Hz, FBmax = 5000HZ).

Note::
If speed F has not been programmed during the programme run then all traversing commands are carried out at the speed defined in the parameter field. A speed setting that is higher than the one set in the parameter field leads to the fault signal „Value too great“ A speed that is lower than the minimum one set in the parameters leads to the fault signal „Value too small“ A value smaller than 10Hz leads to the fault signal ”Value too small “.

Special feature of the PAC-Servo:

With this type of control the speed can be altered during an active positioning process.

Example: Speed profile

Programme :BEISPIEL
1   G90 ;Positioning performed in absolute system of measuring
2   G25.X ;Return to datum
3   G100.X.100 ;Determine acceleration of X axis
4   G210 ;Processed commands beyond the line limit
5   FX1000 ;Traversing speed X axis v₁ : 1000AE/s
6   X1500 ;Positioning of the X axis
7   G230.1.X200 ;Wait until the current absolute position of the X axis is greater than 200
8   FX500 ;Traversing speed X axis v₂ : 500AE/s
9   G230.1.X350
10  FX150 ;Traversing speed X axis v₃ : 150AE/s
11  G230.1.X600
12  FX1200 ;Traversing speed X axis v₄ : 1200AE/s
13  G213
14  END

Note:
The selected speeds must be reachable in the target interval. The acceleration cannot be altered during this process It must be defined beforehand.
3.27 Travel until condition is satisfied

G23

Instruction form:

G23 n.m

Example:

Program : BEISPIEL
1  G25.X G91 ;Perform reference travel with X axis, switch over to absolute dimension system
2  G23 I3.1 ;The next positioning operation is executed (in this case X100) provided input 3 is set; otherwise, the instruction after this is executed
3  X100 ;Traverse axis X 100 in positive direction
4  SUB LOCHBOHR
5  END

Application:

A workpiece is traversed under a recognition device until it is recognized. The recognition device then sends a signal back to the PA so that the program can be continued.

Description:

With the function G23, the next traversing instruction is executed as long as the condition n.m of the operand is valid. If the condition is not satisfied, the traversing instruction is aborted and the next instruction is executed.

Note:

The current absolute position is taken into account for subsequent positioning if the movement commands are aborted.
The command G23 resets the marker 256. If the positioning command is carried out after G23 and if the event (change of the input state) occurs during positioning, the marker 256 is set.
This allows the user to interrogate the marker 256 to determine whether the positioning process has been completed by the state change or end of travel.
3.28 Load register via keyboard

**Instruction form:**

G24.Rn.0  
G24.Nn.0

**Example:**

Program : BEISPIEL
1   G25.X G91 ;Reference travel, incremental dimension system}
2   G24.R1.0 ;Read in a value via keyboard to register R1, in this case as a traversing distance
3   G24.N1.0 ;Read in a value via keyboard to register N1, in this case as a number of travel operations
4 $FAHR_1
5   XR1 ;Travel with X axis, distance in R1
6   DEC.N1 FAHR_1 ;All travel operations completed? If not, then jump to label "FAHR_1"
7   END

**Applikation:**

During execution of a PA program, it is possible to influence the program sequence by entering values via the keyboard. The entered values may be a timer, a repeat factor or for positioning.

**Description:**

The program waits for an operator entry via the PA keyboard after instruction G24.Rn.0 is called. The operator is requested to make an input on the display by output of the program line and current register content.

**Display:**

<table>
<thead>
<tr>
<th>BEISPEL</th>
<th>0</th>
<th>R1 [current value]</th>
</tr>
</thead>
<tbody>
<tr>
<td>G24.R1.0</td>
<td>;Program comment</td>
<td></td>
</tr>
</tbody>
</table>

The displayed current register content can be overwritten with the numeric keys of the keyboard. The old value is retained if only key ESC is pressed.

**Note:**

PA-CONTROL system concept  Instructions  3-51
The maximum number of digits/characters is 7.

No limit value check is performed for the entered value. This must be done by the user in conjunction with the compare operations.

A program abort occurs if the Stop key is pressed during input. This is indicated by "*" and message "Program abort during value input".
3.29 Load register via inputs

**Instruction form:**

G24.Rn.S, NrE.NrA.AzV.AzN
G24.Nn.S, NrE.NrA.AzV.AzN

**Example:**

Program: Beispiel

1 G24.N5.1.3.2.2.0 ; The value to be read in has no digits after the decimal point
2 $SCHLEIFE
3 O1:=1 T5 O1:=0 T5
4 DEC.N5 SCHLEIFE
5 END

**Description:**

Instruction G24.Nn.S.NrE.NrA.AzV.AzN (G24.Rn) results in reading in of a value into a register with the number n (n=1 - 128). The real number with a maximum of 8 digits is supplied via inputs of the PA. Reading takes place in multiplex mode in order to limit the number of required inputs. 4 inputs and one output for each decade to be read are always occupied.

S may have the numeric value 1 or 2. A 1 identifies the number as being without a sign, while a 2 indicates that there is a sign in the highest-order decade. For this reason, the maximum number is 7 for a value with a sign in the highest-order decade. The number is negative if the highest-order bit of the decade is set to 1.

The number of outputs for multiplex mode correspond to the total of digits before and after the decimal point.
Note:

A "0" must be entered at the corresponding positions in the instruction if no digits are required before or after the decimal point. The number of digits must not exceed 8.

A time of approx. 2 ms is required for each decade for reading in. This fact must be taken into account in applications where time is critical and the read-in procedure must be performed in advance where appropriate. Register contents are retained even in the event of a mains power failure. The inputs are read in as a BCD value (0-9). The required outputs cannot be used as flags since they assume the value "0" after reading in.

Assignments of inputs and outputs:

Example: G24.R1.1.4.2.2.1

- No sign evaluation
- Input 4 is the first input for reading
- Output 2 is the first output for multiplex mode
- 2 digits before the decimal point
- 1 digit after the decimal point, i.e. 3 digits!

States of the inputs E4 to E7 for the number 34.5 (with the corresponding control in multiplex operation):

<table>
<thead>
<tr>
<th></th>
<th>E4</th>
<th>E5</th>
<th>E6</th>
<th>E7</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>1</td>
<td>1</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>4</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>5</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>0</td>
</tr>
</tbody>
</table>
Assignment of inputs and outputs:

Example: G24.R1.2.3.4.2.1

- Sign evaluation
- Input 3 is the first input for reading
- Output 4 is the first output for multiplex mode
- 2 digits before the decimal point
- 1 digit after the decimal point, i.e. 3 digits!

States of the inputs E3 to E6 for the number +24.8 (with the corresponding control in multiplex operation):

<table>
<thead>
<tr>
<th></th>
<th>E3</th>
<th>E4</th>
<th>E5</th>
<th>E6</th>
</tr>
</thead>
<tbody>
<tr>
<td>+</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>0</td>
</tr>
<tr>
<td>2</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>4</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>8</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>1</td>
</tr>
</tbody>
</table>
Assignment of inputs and outputs:

Example: G24.N1.2.3.4.3.0

- Sign evaluation
- Input 3 is the first input for reading
- Output 4 is the first output for multiplex mode
- 3 digits before the decimal point
- 0 digit after the decimal point

States of the inputs E3 to E6 for the number -906 (with the corresponding control in multiplex operation):

<table>
<thead>
<tr>
<th></th>
<th>E3</th>
<th>E4</th>
<th>E5</th>
<th>E6</th>
</tr>
</thead>
<tbody>
<tr>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>1</td>
</tr>
<tr>
<td>9</td>
<td>1</td>
<td>0</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>6</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>0</td>
</tr>
</tbody>
</table>
### 3.30 Reference travel

**G25**

**Instruction form:**

G25.A

**Example:**

Program : BEISPIEL
1 G25.X ;Reference travel is performed for the X axis
2 G25.Y ;Reference travel is performed for the Y axis
3 END

Programm : BEISPIEL
1 G90
2 G21 I5.0 REFEREN ;Reference condition for Y axis satisfied?
3 G25.0 G91
4 X100 ;Satisfy reference condition for Y axis!
5 G90
6 $REFEREN
7 G25.Y
8 G25.X
9 END

**Applikation:**

Reference travel must be performed after every restart, i.e. after a power failure or after the PA has been switched off. This is the only way of guaranteeing that the control executes its program in a defined manner.

**Description:**

The PA-CONTROL performs reference travel with the corresponding axis after start of instruction G25.A. The position reached after reference travel is considered as the datum for the axis.

**Note:**

The reference flag must be set by a reference travel (G25.X, G25.Y,...) or by instruction G25.0 before positioning can be performed with an axis. Instruction G25.0 does not change the position values of the axes. The speed is taken from the parameters (reference speed) for the reference travel. The parameter setting for the reference speed and the acceleration must be adapted to the overtravel (distance between reference switch and mechanical stop).
3.31 Set position to zero

G26

Instruction form:

G26.A

Example:

Program : BEISPIEL
1  G26.X ;Set absolute position of the X axis to zero
2  G26.Y ;Set absolute position of the Y axis to zero
3   END

Applikation:

A sensible application for this PA instruction is for continuous movements, e.g. use of the rotary table DT140 in only one direction.

Description:

The absolute position counter of each axis can be set to zero with function G26.A. The variable A of the operand indicates the selected axis.

Note:

The software limit switches defined by way of the range on the parameter level are taken over unchanged. If this instruction is repeated correspondingly, it is thus theoretically possible to perform infinite positioning in one direction, since no counter overflow and no transgression of the range limits is possible. The remainder values for gear factors with digits after the decimal point not equal to zero are also cleared, i.e. they cannot be taken into account in subsequent positioning.
3.32 Set position to dimension

**G29**

**Instruction form:**

G29.Ai  
G29.ARn

**Example:**

Program: BEISPIEL  
1   G25.X  ;Reference travel X axis  
2   G90   ;Absolute dimension system  
3   X700  ;Position to position +700 of X axis  
4   G29.X0 ;Set current position of the X axis to zero, datum position of workpiece and axis system is the same  
5   END

**Application:**

When using dimensions from drawings, it is possible to define a datum which corresponds to the drawing origin.

![Diagram](image)

**Description:**

The position counter of each axis can be set to a new value with function G29. The operator must enter the selected axis. The software switches are automatically changed as well.
3.33 Absolute dimension system

G90

Instruction form:

G90

Example:

Program : Beispiel
1  G25.X ;Reference travel
2  G90 ;Following position instructions are executed in the absolute dimension system
3  X10 ;Position 10 is approached with the X axis, travel = 10 mm
4  X450 ;Position 450 is approached with the X axis, travel = 440 mm
5  X30 ;Position 30 is approached with the X axis, travel = -420 mm
6  END

Application:

For dimensions which are all measured from a datum.

Description:

All subsequent positioning operations are performed in the absolute dimension system after instruction G90 is called until the system is switched over to incremental dimension system with instruction G91.
3.34 Incremental dimension system

G91

Instruction form:
G91

Example:

Programm : Beispiel
1 G25.X ;Reference travel
2 G91 ;Following position instructions are executed in the incremental dimension system
3 X10 ;Position 10 is approached with the X axis, travel = 10 mm
4 X450 ;Position 460 is approached with the X axis, travel = 450 mm
5 X30 ;Position 490 is approached with the X axis, travel = 30 mm
6 END

Application:
- For dimensions which are not referred to a datum.
- For dimension intervals which occur several times in succession and can be repeated with a program loop (DEC.Ni).

Description:
All subsequent positioning operations are performed in the incremental dimension system after instruction G91 is called until the system is switched over to absolute dimension system with instruction G90.
3.35 Define acceleration

G100

Instruction form:

G100.A.i
G100.A.Rn
G100.B.i
G100.B.Rn

Example:

Program : Beispiel
1  G25.X ;Reference travel X axis
2  G91 ;Incremental dimension system
3  FX250
4  G100.X.15 ;Definition of acceleration for the X axis
5  X250 ;Traversing instruction for the X axis
6  G100.X.20 ;Definition of acceleration for the X axis
7  X250 ;Traversing instruction for the X axis
8  END

Application:

Using instruction G100, it is possible to obtain an acceleration value which differs from the values defined in the parameter values and which is adapted to the particular situation. The definition made here is valid until the next G100 instruction or until a restart. The stored parameter values are valid if instruction G100 is not used.

Description:

A stands for the axis designation and can have a value between 1 and the maximum number of axes in multi-axis systems. G100.B serves the employment for the track acceleration of interpolation.

Note:

An error message "Value too high" is issued for instruction G100.A.i if i is greater than the parameter value.
3.36 Residual Distance Positioning

G120

Command form

G120 In.m +Am
G120 In.m +ARI

Example:

Programm: BEISPIEL

1  G25.X G90 ;Return to datum with X axis and switch to absolute measurement system
2  G120 I3.1 X200 ;Activate residual distance positioning, as long as the entry 3 is set the X axis will move at the next positioning. If the entry is reset the residual distance will be positioned..
3  X3000 ;Positioning when the residual distance positioning is active
4  ...
7  ...
8  R15:=25 ;File residual distance in register 15
9  G120 I5.0 XR15 ;Activate residual distance positioning, as long as the entry 5 has not been set, the X axis will move at the next positioning. If the entry is set, the residual distance of 25 is positioned.
10 X300
11 G22 M256.0 SONDER ;The entry did not change during the positioning, subroutine is called up
12 ...
13 END

Programme: SONDER

1 ...
2 ...
3 END

Application:

A part has to be aligned when depositing. It is turned (rotation axis) and when an input signal is given (light barrier, sensor,..) it is turned a given number of degrees further (residual distance).

Description:

This command takes into consideration the defined input with the subsequent positioning process. If this input alters its status, the residual distance is then positioned.
Condition:
- The positioning has not yet reached the braking stage
- The residual distance must be greater than the braking distance

Note:
Command is only available in the PAC-Single and/or PAC-SC compact!
The commands G23, G123 or G210 should not be simultaneously active. The command G120 resets the flag 256. If all requirements have been met and if „altering the input status“ occurs during the positioning process, the flag 256 is set.
3.37 Traverse axis provided condition is fulfilled

**G123**

Instruction form:

- G123.A In.m
- G123.A Mn.m
- G123.A On.m

Example:

Program: BEISPIEL
1  G25.X G90 ; Reference travel is performed with the X axis, switch over to absolute dimension system
2  G123.X I3.1 ; The X axis is traversed during the next positioning operation provided input 3 is set. Otherwise, the current positioning operation is aborted.
3   X100 ; Traverse axis X 100 in positive direction
4  SUB LOCHBOHR
5   END

Application:

A workpiece is traversed beneath a detection device until it is detected. The detection device then returns a signal to the PA so that the program can be continued.

Description:

With function G123, the next traverse instruction of the corresponding axis is executed provided condition n.m of the operand is valid. If the condition is not fulfilled, the traverse instruction is aborted and the next instruction is executed. G123 acts only on the axis defined in the command.

Note:

- If traverse commands are aborted, the current absolute position for the subsequent positioning operation is taken into consideration.
- The instruction group G210 (process beyond line limit) is permitted together with instruction G123.
- Only one G123 may be active per axis. Logic operations involving several conditions can be implemented via the instructions for logic operations.
- G23 and G123 may not be active simultaneously.
- Operators O and M are practical only in conjunction with the PAB.
3.38 Switch to Measuring Mode

G140

Command form:

G140.A

Example:

Programme: BEISPIEL
1  G25.X  ;Return to datum with X axis
2   X100  ;Move to position 100
3    I5.1 ;Wait until set-up mode is active, guard circuit bridged
4   G140.X ;Switch X axis to measuring mode, axis can be moved manually.
5    I5.0 ;Guard circuit is reactivated, set-up mode is blocked
6   G141.X ;Switch X axis back to control mode
7    X1000  ;Move X axis to position 1000
8    END

Application:

During set-up mode make the axis currentless.

A stands for axis name.

A = 0 : all axes
A = X : X axis
A = Y : Y axis
etc.

Description:

The command G140 gives the programmer the opportunity to make the servo axes currentless during the set-up mode. The measuring mode however remains active so that the positions of the axes are not lost. After switching on control operation again it is not necessary to repeat a return to datum as the position measuring remains active.

Note:

This command is only available for the PAC-Servo. When switching a vertical axis to the measuring mode this may slip down. Risk of collision!

3.39 Switch to Control Mode

G141

Command form:

G141.A

Example:

Programme: BEISPIEL
1 G25.X ;Return to datum with X axis
2 X100 ;Move to position 100
3 I5.1 ;Wait until set-up mode is active, guard circuit bridged
4 G140.X ;Switch X axis to measuring mode, axis can be moved manually.
5 I5.0 ;Guard circuit is reactivated, set-up mode is blocked
6 G141.X ;Switch X axis to control mode again
7 X1000 ;Move X axis to position 1000
8 END

Application:

Make the axis currentless during the set-up mode.

A stands for axis name.

A = 0 : all axes
A = X : X axis
A = Y : Y axis
etc.

Description:

The command G141 gives the programmer the opportunity of switching a servo axis that has been made currentless with G140 back to control operation. The position altered in measuring mode is however retained. A repeat return to datum is not necessary after switching on control operation again.

Note:

This command is only available for the PAC-Servo.
When switching on control operation again there is a risk of collision due to a possible change in position!
3.40 Traverse part-distance with Start-Stop

G150

Instruction form:

G150. An
G150. ARi

Example:

Program: BEISPIEL
1  G25.X G91 ; Perform reference travel with X axis, switch over to incremental dimension system
2  G150.X200 ; Traverse the last 200 increments at Start-Stop speed during the next positioning operation with the X axis.
3  X1000 ; Position 1000 increments with the X axis. The deceleration process is started so that Start-Stop speed is reached 200 increments before the destination position. The last 200 increments are then positioned at the Start-Stop speed.
4  END

Application:

For positioning operations in which the last part-distance is positioned in Start-Stop mode.

Examples: Joining operation faster response to G23 or G123 instructions

Description:

Instruction G150 provides the programmer with the option of starting the deceleration operation at an earlier point during the next positioning operation with the corresponding axis and positioning the distance defined with G150 using the Start-Stop speed. The transmission from the deceleration ramp to the Start-Stop speed (distance) is performed continuously.

Note:

This command is not available with the positioning control version.
Positioning course without G150 or G150 with value = 0

Note:

- The number after the axis name in instruction G150 is a distance and is interpreted as an unsigned quantity and direction-independently.
- The instruction is allowed for only during the next positioning operation for this axis.
- If the distance to be traversed during the next positioning operation is less than the distance from instruction G150, instruction G150 is ignored and the positioning operation runs as normal.
3.41 Commands of the G2?? - Group

Introduction

With the commands of this group complex machine functions are possible as parallel cycles can be realised easily.

Without the commands of the G2?? - group the following applies:

The programmes are processed in lines, command on command. With positioning processes the execution of the programme is only continued when the process has been completed.

Example 1:
1 G90 ;Absolute system of measuring
2 G25.X ;Return to datum of X axis
3 X1000 ;Positioning process
4 O1:=1 ;Set output 1
5 I1.1 ;Wait until input 1 at 1
6 O1:=0 ;Reset output 1
7 END

In example 1 the cycle in line 3 remains stationary for the period of the positioning process. The output 1 is set upon completion of the positioning process when input 1 is set.

Using the G2?? commands

Example 2:
1 G90 ;Absolute system of measuring
2 G25.X ;Return to datum of X axis
3 G210 ;Processed commands beyond the line limit, do not wait until the end of the positioning processes
4 X1000 ;Positioning process
5 O1:=1 ;Set output 1
6 I1.1 ;Wait until input 1 at "1"
7 O1:=0 ;Reset output 1
8 G213 ;Wait until all positioning processes are completed, Re-cancel G210 function
9 END

Output 1 is set immediately after starting the positioning process. Line 6 is then processed although the positioning process has not yet been completed and input signals can be reacted to for example during the positioning process. Virtually all commands initiated by the command G210 are permissible in this operating status. „Restarting“ an axis that is already undergoing positioning is not possible but another axis or axes can be started that have completed the previous positioning process. The commands of the G2?? group also offer simple inquiry possibilities as regards the positioning processes.
3.41.1 Process instruction beyond line limit

G210

Instruktion form:

G210

Example:

See the next few instructions

Application:

Program parts in which input and output functions are to be operated during positioning.

Description:

Instruction **G210** starts a so-called "process beyond line limits" in the PA-CONTROL.

This means:

- if several positioning tasks of different axes are to be executed in several lines in direct succession (with no other instructions in between), these positioning instructions are all started simultaneously.

- The positioning tasks are only started and the processing of the following commands is continued (until G213 has been reached).

This means that further commands (I/O processing) can be carried out whilst the axes are being positioned.
3.41.2 Position-related jump

G211

Instruction form:

G211.A.j  Label

Application:

Execution of a jump dependent on whether the selected axis or all axes has/have reached its/their end position.

A stands for the axis number and j stands for the condition.

The following applies:

A = 0   : all axes,
A = 1  : X axis,
A = 2   : Y axis,
A = 3   : Z axis,
usw.

j = 0  : Jump if position of selected axes has not yet been reached
j = 1  : Jump if position of selected axes has been reached

Note:

The instruction evaluates only the end position
No further instruction may be contained in this line after G211.A.j
Example 1:

Program: BEISPIEL
1  G25.X G25.Y  ;Reference travel of the X and Y axes
2  G90          ;Absolute dimension system
3  G210         ;Process instructions beyond line limit start
4  X10000 Y6000 ;Axes start
5  $SETZE
6  O1:=1 T50 O1:=0 ;Set output 1 for 500 ms
7  G211.0.0 SETZE ;Jump to label "SETZEN" if all axes have not yet reached their position
8  G213         ;Wait until all axes are in position (cancel the G210 function)
9  O2:=1
10 END

Example 2:

Program: BEISPIEL
1  G25.X G25.Y  ;Reference travel of the X and Y axes
2  G90          ;Absolute dimension system
3  G210         ;Process instructions beyond line limit start
4  X10000 Y6000 ;Axes start
5  $SCHLEIFE
6  O1:=1 T50 O1:=0 ;Set output 1 for 500 ms
7  T50          ;Wait 500 ms
8  G211.0.1 FERTIG ;Jump to label "FERTIG" if all axes have reached their position
9  JMP SCHLEIFE ;Jump to "SCHLEIFE"
10 $FERTIG
11 G213         ;Wait until all axes are in position (cancel the G210 function)
12 O2:=1
13 END
Example 3:

Program : BEISPIEL
1 G25.X G25.Y ;Reference travel of the X and Y axes
2 G90 ;Absolute dimension system
3 G210 ;Process instructions beyond line limit start
4 X10000 Y6000 ;Axes start
5 $SCHLEIFE
6 O1:=1 T50 O1:=0 ;Set output 1 for 500 ms
7 T50 ;Wait 500 ms
8 G211.Y.1 FERTIG ;Jump to label "FERTIG" if the Y axis has reached its position
9 JMP SCHLEIFE ;Jump to "SCHLEIFE"
10 $FERTIG
11 G213 ;Wait until all axes are in position (cancel the G210 function)
12 O2:=1
13 END

Example 4:

Program : BEISPIEL
1 G25.X G25.Y ;Reference travel of the X and Y axes
2 G90 ;Absolute dimension system
3 G210 ;Process instructions beyond line limit start
4 X10000 Y6000 ;Axes start
5 $SCHLEIFE
6 O1:=1 T50 O1:=0 ;Set output 1 for 500 ms
7 T50 ;Wait 500 ms
8 G211.X.0 SCHLEIFE ;Jump to label "SCHLEIFE" if the X axis has not yet reached its position
9 G213 ;Wait until all axes are in position (cancel the G210 function)
10 O2:=1
11 END
3.41.3 Position-related subroutine call

**G212**

**Instruction form:**

G212.A.j Name

**Description:**

Execution of a subroutine call depending on whether the selected axis or all axes has/have reached its/their end position.

A stands for the axis name and j stands for the condition.

The following applies:

- **A = 0**: all axes,
- **A = X**: X axis,
- **A = Y**: Y axis,
- **A = Z**: Z axis,
  etc.
- **j = 0**: Jump to subroutine if position of selected axes has not yet been reached
- **j = 1**: Jump to subroutine if position of selected axis has been reached

**Note:**

The instruction evaluates only the end position

No further instruction may be contained in this line after G212.A.j
Example 1.

Program : BEISPIEL
1  G25.X G25.Y ;Reference travel of the X and Y axes
2  G90 ;Absolute dimension system
3  G210 ;Process instructions beyond line limit start
4  X10000 Y6000 ;Axes start
5  T100 ;1 s waiting time
6  G212.0.0 AUSGSET ;Jump to subroutine if all axes have not yet reached their position
7  G213 ;Wait until all axes are in position (cancel the G210 function)
8  O2:=1
9  END

Program : AUSGSET
1  O9:=1 T50 O9:=0
2  END

Example 2:

Program : BEISPIEL
1  G25.X G25.Y ;Reference travel of the X and Y axes
2  G90 ;Absolute dimension system
3  G210 ;Process instructions beyond line limit start
4  X10000 Y6000 ;Axes start
5  T100 ;1 s waiting time
6  G212.0.1 AUSGSET ;Jump to subroutine when all axes have reached their position
7  G213 ;Wait until all axes are in position (cancel the G210 function)
8  O2:=1
9  END

Program : AUSGSET
1  O9:=1 I7.1 T50 O9:=0
2  END
Example 3:

Program : BEISPIEL
1  G25.X G25.Y ;Reference travel of the X and Y axes
2  G90 ;Absolute dimension system
3  G210 ;Process instructions beyond line limit start
4  X10000 Y6000 ;Axes start
5  T100 ;1 s waiting time
6  G212.X.0 AUSGSET ;Jump to subroutine if the X axis has not yet reached its position
7  G213 ;Wait until all axes are in position (cancel the G210 function)
8    O2:=1
9    END

Program : AUSGSET
1    O9:=1 I7.1 T50 O9:=0
2    END

Example 4:

Program : BEISPIEL
1  G25.X G25.Y ;Reference travel of the X and Y axes
2  G90 ;Absolute dimension system
3  G210 ;Process instructions beyond line limit start
4  X10000 Y6000 ;Axes start
5  T100 ;1 s waiting time
6  G212.Y.1 AUSGSET ;Jump to subroutine when the Y axis has reached its position
7  G213 ;Wait until all axes are in position (cancel the G210 function)
8    O2:=1
9    END

Program : AUSGSET
1    O9:=1 I7.1 T50 O9:=0
2    END
3.41.4 Wait until all axes in position

Instruction form:

G213

Example:

Program : BEISPIEL
1  G210 ;Process beyond line limit,
2  X1234.56 Y399.10 ;Start positioning for X and Y axes
3  O1:=2 T10 O1:=0
4  G213 ;Wait until all axes are in position, reset function of instruction G210
5  END

Application:

There are two reasons for using instruction G213:

- Cancellation of instruction G210
- Waiting until all moving axes have reached their destination position

Description:

Processing of instructions is cancelled during positioning with instruction G213 ( G213 = Reset G210. In order to achieve this, the system waits, when instruction G213 is reached, until all moving axes have reached their destination position.
3.41.5 Position-related jump (current position)

### G221

**Instruction form:**

G221.j.An.Label  
G221.j.ARn.Name

**Application:**

A conditional jump can be realized as a function of a current axis position by using instruction G221.0.

$j$ stands for jump condition, $An$ stands for the axis and the position and label stands for the destination to which the jump is to take place.

The following applies:

- $j = 0$: Jump if the position $(An)$ is less than the current axis position
- $j = 1$: Jump if the position $(An)$ is greater than the current axis position

**Note:**

This instruction acts on the absolute position of the specific axis irrespective of selected dimension system (G90/G91).  
This line may not contain any further instruction after G221.

**Example 1:**

Program: BEISPIEL

```
1 G25.X G25.Y ;Reference travel of the X and Y axes
2 G90 ;Absolute dimension system
3 G210 ;Process instructions beyond line limit start
4 X10000 Y6000 ;Axes start
5 $SCHLEIFE
6 O1:=1 T50 O1:=0 T50
7 G221.1.X8000 ROT ;Jump "ROT" if the X position is greater than 8000
8 O2:=1 T10 O2:=0
9 $ROT
10 G221.0.0 SCHLEIFE ;Jump to "SCHLEIFE" if all axes are not yet in position
11 G213
12 END
```
Example 2:

Program : BEISPIEL
1  G25.X G25.Y ;Reference travel of the X and Y axes
2  G90 ;Absolute dimension system
3  G210 ;Process instructions beyond line limit start
4  X10000 Y6000 ; Axes start
5  $SCHLEIFE
6  O1:=1 T50 O1:=0 T50 ;Jump to "ROT" if the Y position is greater than 2000
7  G221.1.Y2000 ROT
8  O2:=1 T10 O2:=0
9  $ROT
10 G211.0.0 SCHLEIFE ;Jump to "SCHLEIFE" if all axes are not yet in position
11 G213
12 END

Example 3:

Program : BEISPIEL
1  G25.X G25.Y ;Reference travel of the X and Y axes
2  G90 ;Absolute dimension system
3  G210 ;Process instructions beyond line limit start
4  X10000 Y6000 ; Axes start
5  $SCHLEIFE
6  O1:=1 T50 O1:=0 T50 ;Jump to "ROT" if the X position is smaller than 8000
7  G221.0.X8000 ROT
8  O2:=1 T10 O2:=0
9  $ROT
10 G211.0.0 SCHLEIFE ;Jump to "SCHLEIFE" if all axes are not yet in position
11 G213
12 END
3.41.6 Position-related subroutine call (current position)

G222

Instruction form:

G222.j.An Name

Applikation:

A conditional subroutine call can be realized as a function of a current axis position by using instruction G222.

j stands for the jump condition, An stands for the position of the axis and Name stands for the subroutine to be called.

The following applies:

\[
\begin{align*}
  j &= 0 & \text{Jump if the position (An) is less than the current axis position.} \\
  j &= 1 & \text{Jump if the position (An) is greater than the current axis position.}
\end{align*}
\]

Note:

This instruction acts on the absolute position of the specific axis irrespective of selected dimension system (G90/G91)

Example 1:

Programm : BEISPIEL
1  G25.X G25.Y ;Reference travel of the X and Y axes
2  G90 ;Absolute dimension system
3  G210 ;Process instructions beyond line limit start
4  X10000 Y6000 ;Axes start
5  $SCHLEIFE
6  O1:=1 T50 O1:=0 T50
7  G221.1.X8000 ROT ;Call subroutine "ROT" if the X position is greater than 8000
8  G211.0.0 SCHLEIFE ;Jump "SCHLEIFE" if all axes have not yet reached their position
9  G213
10  END

Programm : ROT
1  O2:=1 T10 O2:=0
2  END
Example 2:

Program : BEISPIEL
1 G25.X G25.Y ;Reference travel of the X and Y axes
2 G90 ;Absolute dimension system
3 G210 ;Process instructions beyond line limit start
4 X10000 Y6000 ; Axes start
5 $SCHLEIFE
6 O1:=1 T50 O1:=0 T50
7 G221.1.Y1000 ROT ;Call subroutine "ROT" if the Y position is greater than 1000
8 G211.0.0 SCHLEIFE ;Jump to "SCHLEIFE" if all axes have not yet reached their position
9 G213
10 END

Program : ROT
1 O2:=1 T10 O2:=0
2 END

Example 3:

Program : BEISPIEL
1 G25.X G25.Y ;Reference travel of the X and Y axes
2 G90 ;Absolute dimension system
3 G210 ;Process instructions beyond line limit start
4 X10000 Y6000 ; Axes start
5 $SCHLEIFE
6 O1:=1 T50 O1:=0 T50
7 G221.0.X4000 ROT ;Call subroutine "ROT" if the X position is smaller than 4000
8 G211.0.0 SCHLEIFE ;Jump to "SCHLEIFE" if all axes have not yet reached their position
9 G213
10 END

Program : ROT
1 O2:=1 T10 O2:=0
2 END
3.41.7 Wait until current position < / > as value

**G230**

**Instruction form:**

G230.j.An

**Example:**

Program : BEISPIEL
1  G25.X ;Reference travel of the X axe
2  G90 ;Absolute dimension system
3  G210 ;Process instructions beyond line limit start
4  X10000 ;Start der Achse
5  O1:=1 T10 O1:=0
6  G230.1.X3000 O2:=1 ;Output 2 is set from X3000 to X5000
7  G230.1.X5000 O2:=0
8  O1:=1 T10 O1:=0
9  G213
10 G210 ;Process instructions beyond line limit start
11  X0
12  O1:=1
13  G230.0.X3000 ;Output 1 is set from X10000 to X3000
14  O1:=0
15  G213
16  END

**Application:**

By using instruction G230, it is possible to suspend further execution of the PA program until a certain position is reached.

j stands for the condition and An stands for the axis and the position.

The following applies:

\[
\begin{align*}
    j &= 0 & \text{Wait until position is less than current position} \\
    j &= 1 & \text{Wait until position is greater than current position}
\end{align*}
\]

**Note:**

This instruction acts on the absolute position of the specific axis irrespective of the selected dimension system (G90/G91)
3.42 Time monitoring instructions

Introduction

Time monitoring instructions of the PA family

The instructions described below are primarily suitable if operations have to be monitored with respect to a defined end and if auxiliary programs have to be started to remedy or record errors in the event of irregularities. These situations can always occur if sequences are started by the controls, e.g. soldering programs, which are executed in parallel and independently of the programs of the PA.

After the corresponding time has elapsed, a conditional jump or subroutine call can take place, depending on the respective instruction. Set time conditions can be reset or aborted. The time condition is checked before each instruction executed by the PA and a reaction initiated where appropriate.

Note:

With „Programme after Stop“ a time monitoring that is still active is reset by the operating system without further signalization and not reactivated with a start (see also Chapter 2.8 Cycle Definitions).
3.42.1 with conditional jump

**G421.1.**

**Instruction form:**

G421.1.nnn  Marke

**Example:**

Program : BEISPIEL
1  $ANFANG
2   O1:=1 ;Set output 1
3  G421.1.200 FEHLER_1 ;Jump to label ‹FEHLER_1” if 2 seconds have elapsed and the time condition has not been reset
4   I1.1 O1:=0 ;Wait for input 1 = 1 and reset output 1
5   G401.1 ;Reset the time condition
6  END
7
8  $FEHLER_1
9   O2:=1 ;Set fault signal
10   I2.1 ;Wait for error acknowledgment signal
11   O1:=0 O2:=0 ;Reset output 1 and fault signal
12  JMP  ANFANG

**Description:**

The monitoring time is started with instruction G421.1.200 Label. The monitoring function is reset if the reset instruction G401.1 is recognized before expiry of the 2-second monitoring time (200*10 ms). If this does not occur, the program is continued at the specified label.

A G421 running in the program is aborted by a further G421 or G422 and, at the same time, the new time monitoring instruction is started. The remaining time of the first monitoring task is not further processed.
3.42.2 with conditional subroutine call

G422.1

Instruction form:

G422.i.nnn  Name

Example:

Program : BEISPIEL
1  O1:=1 ;Set output 1
2 G422.1.200 FEHLER ;Subroutine call if 2 seconds have elapsed and the time
condition has not been reset.
3  I1.1 I1.1 O1:=0 ;Wait for input 1 = 1 and reset output 1
4  G401.1
5  END

Program : FEHLER
1  O3:=1 ;Fault at ...
2  I5.1 ;Acknowledgment by operator
3  END

Description:

The monitoring time is started with instruction G422.1.200 Name. The monitoring function is reset
if the reset instruction G401.1 is recognized before expiry of the
2-second monitoring time (200*10 ms). If this does not occur, the jump is made to the specified
subroutine.

Important:

In the example, instruction "I1.1" has been written twice intentionally (3rd program line:
I1.1 I1.1 01:=0). The reason is that the return from the time monitoring subroutine does not
occur as the result of the PA instruction (when the time had elapsed) which was inter-
rupted by time monitoring but in response to the following instruction.

Example:

The PAC is in the 3rd program line at the first I1.1 instruction and waits for the input, time monitor-
ing is activated, subroutine "FEHLER" is called and is run. The return from the subroutine then
occurs at the second I1.1 instruction in the 3rd program line.
3.42.3 Reset time condition

G401.1

Instruction form:

G401.1

Example:

Example, see instruction G421 or G422

Description:

The time monitoring function which was started by instructions G421 or G422 is stopped by this instruction. The time monitoring function is then no longer active.
3.43 Text and value output, value transfer

Introduction:

This command group enables texts, register contents, input, output and marker states to be output via the current data channel during the program sequence (automatic operation).

The following data channels are possible:

- LCD display on the PA-Control front panel
- Serial interface 1 and 2

The current data channel can be selected with the command "G500.".
Initialization (baud rate, number of data bits, parity, ...) of the selected serial interface also takes place via the command "G500.".

Please note:

The desired data channel (with initialization in the case of a serial interface) should be defined with the command "G500." at the start of every program in which the commands of the G5xx group are used. Otherwise, it cannot be guaranteed that all operations take place via the data channel currently defined in the parameters.

The following applies only to the equipment with CPU3:

From the software version 3.20 upwards the RS485 channel at interface 2 can be used as an alternative to the RS232 channel. For this purpose the jumper on the CPU3 at J12 should be removed and inserted at J11 (see chapter "Technical Appendix" -> "CPU3").

The RS485 signals are on PIN8 = B and PIN9 = A. After running through the switch-on functions of the PAC the transmitter operates at high resistance. A programme example for the coupling of several PACs based on the master-slave-principle can be found on the demo disk.

Note:

All PACs used must be equipped at least with the system software 3.2.
3.43.1 Interface initialization

**G500**

Instruction form.

G500.0

Example:

Program:BEISPIEL
See examples of the following commands

Description:

G500. switches between the two serial interfaces and the LC display of the PA-Control front panel
Only the No.: 0 is necessary after the command G500. when the LC display is selected. All other
parameters are omitted.
If a serial interface is selected as a data channel, it is initialized in accordance with the transferred
parameters [refer to the list for the meaning of the transfer parameters].

Please note:

The desired data channel should be defined at the start of every program!
Only details without CR-LF are meaningful for output on the LC display of the PA-Control.
Significance of the transfer parameters:

No:

0 : LC-Display is activated
1 : Interface 1 is activated
2 : Interface 2 is activated*

Baud rate:

1 : 110 baud
2 : 300 baud
3 : 1200 baud
4 : 2400 baud
5 : 4800 baud
6 : 9600 baud
7 : 19200 baud
8 : 38400 baud  (currently not yet available)

Data format:

1 : 8 data bits, 1 stop bit, no parity
2 : 7 data bits, 1 stop bit, no parity*
3 : 7 data bits, 1 stop bit, even parity
4 : 7 data bits, 1 stop bit, odd parity

Handshake:

0 : Hardware handshake (CTS) inactive
1 : Hardware handshake (CTS) active

* Not possible with the PAC-SC Compact and the PAC-Single
3.43.2 Delete the display

G501

Instruction form:

G501

Example:

Program: EXAMPLE
1   G11.0 ;Switch off sequence displays
2   G500.0 ;Switches the G500 commands to the current display medium (LC display or, in the case of "Simulation of the front panel", the serial interface)
3   G501 ;Deletes the display and sets the cursor in the top left corner (1st column, 1st line)
4   G510.Hello ;Outputs the text "Hello" on the current display medium.
5   END

Description:

The command G501 deletes the display of the current display medium and sets the cursor in the top left corner.

Note:

Before the command G501 is used, switchover to the current display medium should be performed with the command "G500.".
3.43.3 Delete up to line end

G502

Instruction form:

G502

Example:

Program : EXAMPLE
1  G11.0 ;Switch off sequence displays
2  G500.0 ;Switches the G500 commands to the current display medium (LC display or, in the case of "Simulation of the front panel", the serial interface)
3  G501 ;Deletes the display and sets the cursor in the top left corner (1st column, 1st line).
4  N1:=234
5  $LOOP
6  G503.1.2 ;Position the cursor in the first column of the 2nd line
7  G510.VALUE N1
8  G503.11.2 ;Position the cursor in the 11th column of the 2nd line
9  G502 ;Delete as from the cursor position up to the end of the line
10 G520.N1 ;Output the value of N1 at the display (flush left)
11 T100
12 DEC.N1 LOOP
13 END

Description:

The command G502 deletes the display on the display medium from the current cursor position to the end of the line. The position of the cursor remains unchanged.

The command can be used to delete the previously displayed value when register values are output so as to then output the new register value.

Please note:

Before using the command G502, switchover to the current display medium should be performed with the command "G500.".
3.43.4 Position the cursor

**G503**

Instruction form:

- G503.n.m
- G503.Nn.m
- G503.n.Nm
- G503.Nn.Nm

Example

Program: EXAMPLE

```
1 G11.0 ;Switch off sequence displays
2 G500.0 ;Switches the G500 commands to the current display medium (LC display or, in the case of "Simulation of the front panel", the serial interface)
3 N23:=5
4 N35:=2
5 G501 ;Deletes the display and sets the cursor in the top left corner (1st column, 1st line)
6 G503.4.1 ;Sets the cursor in the 4th column of the 1st line
7 G510.HELLO ;Outputs the text "HELLO" at the current cursor position on the current display medium
8 G503.N23.N35 ;Sets the cursor in the 5th column of the 2nd line. See values of N23 and N35
9 G510.OPERATOR ;Outputs the text "OPERATOR" at the current cursor position on the current display medium
10 END
```

Description:

The command G503 serves to position the cursor on the display.

The LCD display is divided up into 40 columns and 2 lines.

Please note:

Before using the command G503, switchover to the current display medium should be carried out with the command "G500.".
3.43.5 Text output

**G510.**

**Instruction form:**

G510.  text

**Example:**

Program: BEISPIEL

```plaintext
1  G500.2.6.1.0  ;Initializes the selected interface
2  G510.Maschinenfehler !  ;Outputs the text "Machine error!" via the serial interface
3  END
```

**Description:**

G510. outputs the text via the selected serial interface.

**Note:**

No CR and no LF are sent at the end of the text.
There may be no other instruction in this line after G510. The text starts after "G510." and ends at the end of the line (terminate entry with ENTER in the program editor)
3.43.6 Text output

**G511.**

**Instruction form:**

G511.  text

**Example:**

Program : BEISPIEL
1   G500.2.6.1.0 ;Initializes the selected interface
2   G511.Maschinenfehler ! ;Outputs the text "Machine error!" via the serial interface
   and terminates the transmission with CR and LF
3   END

**Description:**

G511. outputs the text via the selected serial interface and sends a CR and LF after the text.

**Note:**

The transmission is terminated with CR and LF.
There may be no other instruction in this line after G511. The text starts after "G511" and
ends at the end of the line (terminate entry with ENTER in the program editor)
3.43.7 Control character output

**G512.**

**Instruction form:**

\[ \text{G512. } n \]

**Example:**

Program: BEISPIEL
1. G500.2.6.1.0 ;Initializes the selected interface
2. G512.7 ;Outputs command "BEL" via serial interface.
3. G511.36 ;Outputs character "$" via serial interface.
4. G511.4 ;Outputs 04Hex (EOT) via serial interface.
5. END

**Description:**

G512. interprets \( n \) as the \( n \)th character (ordinal) of the ASCII table and outputs the character via the serial interface.

All numbers between 0 and 255 are permitted.

**Application:**

Output of control characters to printer. Please refer to your printer's ASCII table for the significance of the individual characters.

**Note:**

**No CR and no LF are sent after the character.**
3.43.8 Text Output

G515.

Command form:

G515.i.Name
G515.Ni.Name

Example:

Programme : MELDUNG.PTX
1 Machine ready
2 Fault at the part feed conveyor
3 Part magazine empty
4 Text not defined

Programme : BEISPIEL : PNC
1 G500.0 ; Initialization, LC-Display is current data channel
2 G515.2.MELDUNG ; outputs the second line of the programme
"MELDUNG.PTX" on the current data channel
3 N5:=3
4 G515.N5.MELDUNG ; outputs the third line of the programme
"MELDUNG.PTX" on the current data channel
5 END

Description:

G515 outputs a text (line) that is filed in a programme file (*.PTX) on the current data channel. With this function different control sequences can be output to the printer and similar devices that otherwise require several G512 commands each.

Note:

The file must be a *.PTX type file and available when the programme is running. If the respective text line cannot be found (number is greater than the number of lines in the file) the last programme line is specified.
3.43.9 Value output

G520.

Instruction form:

G520. Rn
G520. Nn
G520. In
G520. On
G520. Mn

Example:

Program : BEISPIEL
1 G500.2,6,1.0 ;Initializes the selected interface
2 G520.R2 ;Outputs the contents of R2 via the current serial interface
3 G520.N5 ;Outputs the contents of N5 via the current serial interface
4 G520.I7 ;Outputs the state of input 7 via the current serial interface
5 G520.O12 ;Outputs the state of output 12 via the current serial interface
6 G520.M25 ;Outputs the state of flag 25 via the current serial interface
7 END

Description:

G520. determines the state of the operand (register, input, output, flag) and outputs the corresponding value via the current serial interface.

<table>
<thead>
<tr>
<th>Operand</th>
<th>State</th>
<th>Output(ASCII character)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Input</td>
<td>Energized</td>
<td>1</td>
</tr>
<tr>
<td>Input</td>
<td>Not energized</td>
<td>0</td>
</tr>
<tr>
<td>Output</td>
<td>Set</td>
<td>1</td>
</tr>
<tr>
<td>Flag</td>
<td>Set</td>
<td>1</td>
</tr>
<tr>
<td>Flag</td>
<td>Reset</td>
<td>0</td>
</tr>
<tr>
<td>Real number register</td>
<td>546.06</td>
<td>546.06</td>
</tr>
<tr>
<td>Integer register</td>
<td>34</td>
<td>34</td>
</tr>
</tbody>
</table>

Note:

No CR and no LF are sent via output.
3.43.10 Value output

G521.

Instruction form:

G521. Rn
G521. Nn
G521. In
G521. On
G521. Mn

Example:

Program: BEISPIEL
1 G500.2.6.1.0 ;Initializes the selected interface
2 G521.R2 ;Outputs the contents of R2 via the current serial interface
3 G521.N5 ;Outputs the contents of N5 via the current serial interface
4 G521.I7 ;Outputs the state of input 7 via the current serial interface
5 G521.O12 ;Outputs the state of output 12 via the current serial interface
6 G520.M25 ;Outputs the state of flag 25 via the current serial interface
7 END

Description:

G521. determines the state of the operand (register, input, output, flag) and outputs the corresponding value via the current serial interface.

<table>
<thead>
<tr>
<th>Operand</th>
<th>State</th>
<th>Output(ASCII character)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Input</td>
<td>Energized</td>
<td>1</td>
</tr>
<tr>
<td>Input</td>
<td>Not energized</td>
<td>0</td>
</tr>
<tr>
<td>Output</td>
<td>Set</td>
<td>1</td>
</tr>
<tr>
<td>Flag</td>
<td>Set</td>
<td>1</td>
</tr>
<tr>
<td>Flag</td>
<td>Reset</td>
<td>0</td>
</tr>
<tr>
<td>Real number register</td>
<td>546.09</td>
<td>546.09</td>
</tr>
<tr>
<td>Integer register</td>
<td>34</td>
<td>34</td>
</tr>
</tbody>
</table>

Note:

CR and LF are also sent, besides the actual value.
3.44 Value acceptance from the current data channel

G5??,...

Introduction:

This command group allows registers, output states and marker states to be read in via the current data channel during the program sequence (automatic operation).

The following data channels are possible:

- Keyboard on the PA-Control front panel
- Serial interfaces 1 and 2

The current data channel can be selected with the command "G500.".

In addition, the selected serial interface is initialized (baud rate, number of data bits, parity, ...) via the command "G500.".

Please note:

The desired data channel (with initialization in the case of a serial interface) should be defined with the command "G500." at the start of every program. Otherwise, it cannot be guaranteed that all operations take place via the data channel defined in the parameters as current.
### 3.44.1 Value transfer

**Instruction form:**

- `G531.Rn`  
- `G531.Nn`  
- `G531.On`  
- `G531.Mn`  

**Example.**

Program : BEISPIEL

1. `G500.2.6.1.0 ; Initializes the selected interface`
2. `G531.R2 FEHLER ; Waits for reception of a message at the current serial interface and assigns the information to register R2; the program is continued at label "FEHLER" in the event of a transmission error`
3. `G531.M3 FEHLER ; Waits for reception of a message at the current serial interface and sets flag 31 on the basis of the information`
4. `JMP ENDE`
5. `$FEHLER ; Error message program part`
6. `...`
7. `$ENDE`
8. `END`

**Description:**

G531. waits for reception of characters at the current serial interface. When CR is received, transmission is considered as having been completed and the received characters are further processed in accordance with the operand.

A time monitoring function is not implemented in the G531 instruction and can be realized with instructions G401, G421 and G422, if required.

The program is continued in the label if a transmission error (parity error, ...) is established during reception or if an invalid character string is received.

The program is aborted and the corresponding message is shown on the display if the "Stop key" is recognized.

<table>
<thead>
<tr>
<th>Operand</th>
<th>Received ASCII characters</th>
<th>Action/State</th>
</tr>
</thead>
<tbody>
<tr>
<td>Output</td>
<td>1</td>
<td>Set output</td>
</tr>
<tr>
<td>Output</td>
<td>0</td>
<td>Reset output</td>
</tr>
<tr>
<td>Flag</td>
<td>1</td>
<td>Set flag</td>
</tr>
<tr>
<td>Flag</td>
<td>0</td>
<td>Reset flag</td>
</tr>
<tr>
<td>Real number register</td>
<td>546.33</td>
<td>546.33</td>
</tr>
<tr>
<td>Integer register</td>
<td>25</td>
<td>25</td>
</tr>
</tbody>
</table>
Please note:

No further command may be in this line after G531.

Output of a log on a printer:

Preconditions:

- Printer connected to serial interface 2 with setting: 300 baud, 7 data bits, 1 stop bit, even parity, no hardware handshake
- Integer register 10 number of good parts
- Integer register 11 number of defective parts

Program: PROTOKO
1  G500.2.2.3.0 ; Initialization of interface
2  G511. Production log ; Output title
3  G512.10 ; Insert blank line
4  G510. Machine group: 1234
5  G511. System: Test
6  G512.10 ; Insert blank line
7  G510. Number of good parts:
8  G521. R10
9  G510. Number of defective parts:
10  G521. R11
11  G512.10
12  END
3.44.2 Character transfer in the buffer

G532.

Instruction form:

G532.n Label

Example:

Program : EXAMPLE
1  G500.2.6.1.0 ; Initialization of serial interface 2
2  G532.13 U_ERROR ; Receives characters at the serial interface and stores them in the character buffer until the end criterion 13 = 0D hex = CR is received
3  N3:=COPY.2.5 C_ERROR ; As from the 2nd character, convert the next 5 characters from the character buffer into a number and store this number in the integer register 3.
4  JMP END
5  $U_ERROR
6  G24.N1.0; TRANSFER ERROR
7  JMP END
8  $C_ERROR
9  G24.N1.0; CONVERSION ERROR
10 $END
11 END

Description:

The command G532.n takes characters (max. 80) from the current serial interface until the end criterion "n" has been received or until a fault occurs, and stores these characters in the character buffer. The end criterion "n" is a number greater than 0 and less than 255 and represents the corresponding ASCII character. If an error occurs during transfer of the characters, the transfer is aborted and the program is continued at the marker.

Error possibilities:

- Parity error, Overrun error, Framing error in character transfer
- Character buffer full

Please note:

The program remains in line 2 until the end criterion is recognized or until a transfer error occurs.
3.44.3 Character transfer in the background into the buffer

**G533.**

**Instruction form:**

G533.n

**Example**

Program: EXAMPLE

```
1  G500.2.6.1.0 ;Initialization of the serial interface 2
2  G533.13  ;Receives characters in the background at the serial interface and stores them in the character buffer until the end criterion 13 = 0D hex = CR is received

3  $LOOP
4  SUB WORK
5  N1:=CHN ;Character string completely received ?
6  CASE.JMP.N1 ;Evaluation of the transfer
7  (ZEI_DA) ;End criterion was received
8  (U_ERROR) ;Error during transfer of a character
9  (P_FULL) ;Character buffer is full and the end criterion was not yet received
10 ELSE LOOP ;End criterion was not yet received
11 $ZEI_DA
12 N3:=COPY.2.5 C_ERROR ;From the 2nd character, convert the next 5 characters from the character buffer into a number and store this number in the integer register 3

13 JMP END
14 $U_ERROR
15 G24.N2.0; TRANSFER ERROR
16 JMP END
17 $P_FULL
18 G24.N2.0; BUFFER FULL
19 $END
20 END
```
Description:

The command G533.n accepts characters in the background (max. 80) from the current serial interface until the end criterion n" is received or until an error has occurred, and stores these characters in the character buffer.

The end criterion "n" is a number greater than 0 and less than 255 and represents the corresponding ASCII character.

The addition "in the background" means that the PA-CONTROL starts a system routine which accepts characters and the next command of the PNC program is then executed.

The command Ni:=CHN allows you to check whether the character string was completely received.

If an error occurs during transfer of the characters, the transfer is aborted and the program is continued at the marker.

Error possibilities:

- Parity error, Overrun error, Framing error during character transfer
- Character buffer full

Note:

When making communication via the serial interface a loss of information can occur under certain circumstances.

G510. Please send! 
... ;Attention: Send to communications partner immediately
... 
G533.13 ;From now on the PAC is already ready to receive

Better solution:

G533.13 ;From now on the PAC is ready to receive
...
G510. Please send! ;PAC is already ready to receive
3.44.4 Check whether character transfer in the background has been completed

**Instruction form:**

\[ Nn:=\text{CHN} \]

**Example:**

Program: EXAMPLE

1. \[ \text{G500.2.6.1.0} \] ; Initialization of serial interface 2
2. \[ \text{G533.13} \] ; Receives characters in the background at the serial interface and stores them in the character buffer until the end criterion 13 = 0D hex = CR is received
3. \[ \$\text{LOOP} \]
4. \[ \text{SUB WORK} \]
5. \[ N1:=\text{CHN} \] ; Character string completely received?
6. \[ \text{CASE.JMP.N1} \] ; Evaluation of the transfer
7. \[ \text{(ZEI\_DA)} \] ; End criterion was received
8. \[ \text{(U\_ERROR)} \] ; Error during transfer of a character
9. \[ \text{(P\_FULL)} \] ; Character buffer is full and the end criterion has not yet been received
10. \[ \text{ELSE LOOP} \] ; End criterion has not yet been received
11. \[ \$\text{ZEI\_DA} \]
12. \[ N3:=\text{COPY.2.5 C\_ERROR} \] ; From the 2nd character, convert the next 5 characters from the character buffer into a number and store this number in the integer register 3.
13. \[ \text{JMP END} \]
14. \[ \$\text{U\_ERROR} \]
15. \[ \text{G24.N2.0; TRANSFER ERROR} \]
16. \[ \text{JMP END} \]
17. \[ \$\text{P\_FULL} \]
18. \[ \text{G24.N2.0; BUFFER FULL} \]
19. \[ \$\text{END} \]
20. \[ \text{END} \]
Description:

The command \( \text{Nn}:=\text{CHN} \) checks whether reception of a character string in the background has been completed (whether the end character was received). The result of the CHN function is stored in the integer register.

The result in the integer register is interpreted as follows:

<table>
<thead>
<tr>
<th>Contents of Ni</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>End criterion not yet received</td>
</tr>
<tr>
<td>1</td>
<td>End criterion received</td>
</tr>
<tr>
<td>2</td>
<td>Transfer error at the serial interface (parity,...)</td>
</tr>
<tr>
<td>3</td>
<td>Receive buffer full but end criterion not yet received</td>
</tr>
</tbody>
</table>

If the end criterion was recognized (in example \( \text{Nn}=1 \)), the character buffer is copied into a processing buffer. The commands "POS" and "Copy" act on this processing buffer. This allows a further character string to be received with a renewed G533 command during execution of the commands "POS" and "Copy".

Note:

The function \( \text{Nn}:=\text{CHN} \) may only be used several times with \( \text{Nn}=0 \).
3.44.5 Search for the position of a character in the buffer

**POS.**

**Instruction form:**

\[ Ni:=\text{POS}.n.m \]
\[ Ni:=\text{POS}.Nn.m \]

**Example:**

Program : EXAMPLE
1  G500.2.6.1.0 ;Initialization of serial interface 2
2  G532.13 U_ERROR ;Receives characters at the serial interface and stores them in the processing buffer until the end criterion 13 = 0D hex = CR is received
3  N2:=POS.1.35 ;Search in processing buffer for character 35= 23 hex = # and store the item in N2
4  M1:=N2<1 ;Character found ?
5  G21 M1.1 Z_NO ;No!
6  N3:=COPY.N2.5 C_ERROR ;As from the value of N2, convert the next 5 characters from the processing buffer into a number and store them in the integer register 3
7  JMP END
8  $U_ERROR
9  G24.N1.0; TRANSFER ERROR
10 JMP END
11 $C_ERROR
12 G24.N1.0; CONVERSION ERROR
13 JMP END
14 Z_NO
15 G24.N1.0; CHARACTER NOT FOUND
16 END
17 END

**Description:**

With the command, it is possible to search in the processing buffer with the criterion to determine whether a particular character ("m") occurs. "m" is a number greater than 0 and less than 255 and represents the corresponding ASCII character. The search in the processing buffer commences as from the position "n".

If the character is found, the item is stored in the integer register. If the character was not found, the value "0" is stored in the integer register.
3.44.6 Convert character into number

COPY.

Instruction form:

Ni:=COPY.n.m Label
Ri:=Copy.n.m Label
Ni:=COPY.Nn.Nm Label
Ri:=COPY.Nn.Nm Label

Example:

Program : EXAMPLE
1 G500.2.6.1.0 ;Initialization of the serial interface
2 G532.13 U_ERROR ;Receives characters at the serial interface and stores
them in the processing buffer until the end criterion 13 =
0D hex = CR is received
3 N3:=COPY.2.5 C_ERROR ;As from the 2nd character, convert the next 5 characters
from the processing buffer into a number and store this
number in the integer register 3
4 JMP END
5 $U_ERROR
6 G24.N1.0; TRANSFER ERROR
7 JMP END
8 $C_ERROR
9 G24.N1.0; CONVERSION ERROR
10 $END
11 END

Description:

The command COPY allows characters from the processing buffer to be converted into a number
and stored in an integer or real number register.

COPY starts as from the "n"th character and takes the next "m" characters, provided that charac-
ters are contained in the processing buffer. If less than "m" characters are available, the conver-
sion process is ended without an error.

If an error occurs, the conversion process is aborted. The register remains unchanged and the
program is continued at the marker.

Possible errors:

- "n" is less than 1 or greater than 80
- "m" is less than 1 or greater than 10
- Not a single character from the quantity 0 to 9 was found during the conversion proc-
  ess.
3.44.7 Check whether a key is actuated

Instruction form:

G540.Nn

Example:

Program : Example
1  G11.0 ;Switch off sequence displays
2  G500.0 ;Switches the G500 commands to the current display medium (LC display or, in the case of "Simulation of the front panel" the serial interface)
3  G501 ;Delete display
4  N1:=0
5  $LOOP
6  O1:=1 T10
7  O1:=0 T10
8  G540.N1 ;Checks whether a key is pressed and stores the key code in N1. Otherwise N1 becomes 0
9  M1:=N1>0 ;Was a key pressed ?
10  G21 M1.0 LOOP ;No !
11  G503.4.1 ;Position cursor in the 4th column of the 1st line
12  G502 ;Delete up to the end of the line
13  G510.N1
14  G512.32
15  G520.N1
16  JMP LOOP
17  END

Description:

The command G540 checks whether a key on the PAC front panel has been pressed. If so, the key code is stored in the N register. If no key has been pressed, the N register is set to 0.

The command serves to interrogate the keyboard whilst a program part is being processed in order to react to possible requests of the operator.

Please note:

The command works only with the front panel of the PA-CONTROL (LCD display, membrane keyboard). Refer to the table "PAC key code" in the "Technical appendix" section for the key codes.
3.44.8 Fetch a character from the keyboard

G541.

Instruction form:

G541.Nn

Example:

Program : Example
1  G11.0 ;Switch off sequence displays
2  G500.0 ;Switches the G500 commands to the current display medium (LC display or, in the case of "Simulation of the front panel", the serial interface)
3  G501 ;Delete display
4  N1:=0
5  $LOOP
6  G541.N1 ;Waits until a key is pressed and stores the key code in N1
7  G503.4.1 ;Position cursor in the 4th column of the 1st line
8  G502 ;Delete up to the end of the line
9  G510.N1
10  G512.32
11  G520.N1
12  JMP LOOP
13  END

Description:

The command G541 waits until a key on the PAC front panel has been pressed and stores the key code in the N register.

The command G541 can be used to realize internal menus in the PA-CONTROL.

Please note:

The command works only with the front panel of the PA-CONTROL (LCD display, membrane keyboard).
Refer to the table "PCA key code" in the "Technical appendix" section for the key codes.
3.44.9 Input a register value

G542.

Instruction form:

- G542.s.z.l.Ni
- G542.s.z.l.Ri

Example:

Program : Example
1  G11.0 ;Switch off sequence displays
2  G500.0 ;Switches the G500 commands to the current display
3       medium (LC display or, in the case of "Simulation of the
4       front panel", the serial interface)
5  G501 ;Delete display
6  $LOOP
7  G503.1.1
8  G510.Input time
9  G542.30.1.3.N1 ;Input of the N register 1 via the front panel

The input field appears in the 30th column in the
1st line and is 3 characters long
10 G501
11 G503.1.2
12 G510.Time for output 1 is
13 G512.32
14 G512.32
15 G510. * 10ms
16 O1:=1 TN1 O1:=0
17 JMP LOOP
18 END

Description:

The command G542.s.z.l.Ni allows the operator to enter a register value during the program sequence.
The command opens an input field (see Chapter "User interface"). The length and position of the input field is defined by the operators (parameters) of the command.

The following applies:

- s : stands for column
- z : stands for line
- l : stands for length of the input field
- Ni : register worked with (storage)
3.45 Map to register / Map from register

G60?.

Introduction:

This instruction group permits register contents to be mapped to outputs or flags during automatic operation or to load the image of inputs to a register.

General instruction format:

G60?.Rn.m.i
G60?.Nn.m.i

Rn / Nn: Source/destination
m: First element of the destination/source address (corresponds to the least significant bit)
i: Number of elements to which/from which mapping is to occur (1 ≤ i ≤ 32)

Note:

m + i must be equal to or less than the maximum number of elements used.

The register content is used as follows:

- Digits after the decimal point are truncated
- Negative number becomes positive number
- Maximum 32 bits are mapped.

Different formats are available:

- Binary image
- BCD image
3.45.1 Binary format to outputs

**G600.**

**Instruction form:**

G600.Rn.m.i
G600.Nn.m.i

**Example 1:**

Program : BEISPIEL
1  R3:=10.7
2  G600.R3.5.8 ;Content of R3 represented in binary code as of output 5
   with 8 bits
3  END

**States of the outputs after execution of the above instructions:**

- Output 5       Reset (0)
- Output 6       Set (1)
- Output 7       Reset (0)
- Output 8       Set (1)
- Output 9       Reset (0)
- Output 10      Reset (0)
- Output 11      Reset (0)
- Output 12      Reset (0)

**Example 2:**

Program : BEISPIEL
1  N3:=18
2  G600.N3.2.4 ;Content of N3 represented in binary code as of output 2
    with 4 bits
3  END

**States of the outputs after execution of the above instructions:**

- Output 2       Reset (0)
- Output 3       Set (1)
- Output 4       Reset (0)
- Output 5       Reset (0)

**Note:**

In example 1 the digits after the comma are omitted.
In example 2 only the 4 least-significant digits of the binary number are represented
(The contents of the integer number register are nevertheless interpreted correctly!).
3.45.2 BCD format to outputs

**Instruction form:**

G601.Rn.m.i  
G601.Nn.m.i

**Example 1:**

Program : BEISPIEL  
1    R3:=10.7  
2    G601.R3.5.8  ;Content of R3 represented in BCD code as of output 5 with 8 bits  
3    END

**States of the outputs after execution of the above instructions:**

- Output 5 Reset (0)  
- Output 6 Reset (0)  
- Output 7 Reset (0)  
- Output 8 Reset (0)  
- Output 9 Set (1)  
- Output 10 Reset (0)  
- Output 11 Reset (0)  
- Output 12 Reset (0)

**Example 2:**

Program : BEISPIEL  
1    N3:=12  
2    G601.N3.2.4  ;Content of N3 represented in BCD code as of output 2 with 4 bits  
3    END

**States of the outputs after execution of the above instructions:**

- Output 2 Reset (0)  
- Output 3 Set (1)  
- Output 4 Reset (0)  
- Output 5 Reset (0)

**Note:**

The digits after the decimal point are truncated in example 1.  
Only the lowest-order digit of the BCD number is represented in example 2.
3.45.3 Binary format to flags

Instruction form:

G602.Rn.m.i
G602.Nn.m.i

Example 1

Program: BEISPIEL
1  R3:=11.3
2  G602.R3.4.8 ;Content of R3 represented in binary code as of flag 4 with 8 bits
3  END

States of the flags after execution of the above instructions:

- Flag 4  Set (1)
- Flag 5  Set (1)
- Flag 6  Reset (0)
- Flag 7  Set (1)
- Flag 8  Reset (0)
- Flag 9  Reset (0)
- Flag 10 Reset (0)
- Flag 11 Reset (0)

Example 2:

Program: BEISPIEL
1  R3:=65535
2  G602.R3.17.32 ;Content of R3 represented in binary code as of flag 1 with 32 bits
3  END

State of flags 17 to 49 after execution of the above instructions:

- Flags 17 - 31 are set
- Flags 32 - 49 are reset
Example 3:

Program : BEISPIEL
1    N3:=11
2    G602.N3.1.4 ;Content of N3 represented in binary code as of flag 1
               with 4 bits
3    END

States of the flags after execution of the above instructions:

-Flag 1    Set (1)
-Flag 2    Set (1)
-Flag 3    Reset (0)
-Flag 4    Set (1)
3.45.4 Inputs in binary format to register

**G603**

Instruction form:

G603.Rn.m.i
G603.Nn.m.i

Example 1:

Program : BEISPIEL

1 G603.R3.2.8 ;Inputs 2 to 9 (2 = least-significant bit) are interpreted as a binary number and the value is transferred to register 3

2 END

States of the inputs on execution of the above instructions:

-Input 2 Not energized (0) Value = 1
-Input 3 Energized (1) Value = 2
-Input 4 Not energized (0) Value = 4
-Input 5 Energized (1) Value = 8
-Input 6 Not energized (0) Value = 16
-Input 7 Not energized (0) Value = 32
-Input 8 Not energized (0) Value = 64
-Input 9 Energized (1) Value = 128

In binary code, this results in the following number "10001010" and, in register 3, value 138 (8AHex).

Example 2:

Program : BEISPIEL

1 G603.N3.5.4 ;Inputs 5 to 8 (5 = LSB) are interpreted as a binary number and the value is transferred to integer register 3

2 END

States of the inputs on execution of the above instruction:

-Input 5 Not energized (0)
-Input 6 Energized (1)
-Input 7 Not energized (0)
-Input 8 Energized (1)

In binary code, this results in the following number "1010" and, in register 3, value 10 (0AHex).
3.45.5 Flag in Binary Format in Register

**G604.**

**Command form:**

G604.Rn.m.i  
G604.Nn.m.i

**Example 1:**

Programme: BEISPIEL

1  G604.R3.2.8  ;The flags 2 to 9 (2= lowest-significant bit) are interpreted as a binary number and the value transferred to the R3 register

2  END

Input statuses when carrying out the above command:

- Flag 2 (0)  Value= 1
- Flag 3 (1)  Value= 2
- Flag 4 (0)  Value= 4
- Flag 5 (1)  Value= 8
- Flag 6 (0)  Value= 16
- Flag 7 (0)  Value= 32
- Flag 8 (0)  Value= 64
- Flag 9 (1)  Value= 128

In the binary code this is equivalent to the number "10001010" and in register 3 the value 138 (8AHex).

**Example 2:**

Programme: BEISPIEL

1  G604.N3.5.4  ;The flags 5 to 8 (5=LSB) are interpreted as binary numbers and the value transferred to the integer number register 3

2  END

Input statuses when carrying out the above command:

- Flag 5 (0)  
- Flag 6 (1)  
- Flag 7 (0)  
- Flag 8 (1)  

In the binary code this is equivalent to the number "1010" and in register 3 the value 10 (0ahex).
3.46 Arithmetic operation

+ - * /

The following applies generally to assignments:

<table>
<thead>
<tr>
<th>Destination operand</th>
<th>Source operand 1</th>
<th>Operand</th>
<th>Source operand 2</th>
</tr>
</thead>
<tbody>
<tr>
<td>- Register</td>
<td>- Register</td>
<td>+ - * /</td>
<td>- Unsigned constant</td>
</tr>
</tbody>
</table>

Note:

The result is dependent upon the operation and the sign of the register contents. K (constant) is also used as a real number in the description for integer. In the real application, only permitted type of number may be used. The source operands remain unchanged. One exception is if the destination operand is also the source operand.

Example:

R1:=5
R2:=3
R3:=R1+R2 ; the registers then have the following values: R1=5, R2=3, R3=8
R1:=R1+R2 ; the registers then have the following values: R1=8, R2=3

Note:

Registers can be addressed directly and indirectly in value assignments and for basic arithmetic operations.

Direct addressing:

The letter R(N) is followed by a number (1-512) which identifies the desired register

Indirect addressing:

The letter R(N) is followed by "!" and then by a number (1-512) which refers to the register whose content identifies the desired register.
3.46.1 Load register

\[
\begin{align*}
Rn: &= K \\
Nn: &= K \\
R!n: &= A \\
N!n: &= Nm \\
Rn: &= A \\
Nn: &= Nm \\
Rn: &= Rm \\
Nn: &= Rm \\
R!n: &= Rm \\
N!n: &= Nm
\end{align*}
\]

Instruction form:

<table>
<thead>
<tr>
<th>Rn:=</th>
<th>K</th>
<th>Nn:=</th>
<th>K</th>
</tr>
</thead>
<tbody>
<tr>
<td>R!n:=</td>
<td>K</td>
<td>N!n:=</td>
<td>K</td>
</tr>
<tr>
<td>Rn:=</td>
<td>A</td>
<td>Nn:=</td>
<td>Nm</td>
</tr>
<tr>
<td>R!n:=</td>
<td>A</td>
<td>N!n:=</td>
<td>Nm</td>
</tr>
<tr>
<td>Rn:=</td>
<td>Rm</td>
<td>Nn:=</td>
<td>Rm</td>
</tr>
<tr>
<td>R!n:=</td>
<td>Rm</td>
<td>N!n:=</td>
<td>Nm</td>
</tr>
</tbody>
</table>

Example:

Program: BEISPIEL
1. R2:=45 ; Load real number register 2 with 45
2. R3:=R2 ; Load real number register 3 with value of real number register 2
3. R!2:=100.79 ; Load real number register 45 with 100.79
4. R21:=R!2 ; Load real number register 21 with value 100.79 from register 45
5. R5:=X ; Load real number register 5 with absolute position of the X axis
6. N7:=87 ; Load integer register 7 with value 87
7. N65:=N7 ; Load integer register 65 with value from integer register 7
8. N1:=R45 ; Load integer register 1 with value from real number register 45, value is rounded
9. R25:=N65 ; Load real number register 25 with value from integer register 65
10. N2:=4
11. N!2:=17 ; Load integer register 4 (N2=4) with 17

Description:

Values can be loaded into the registers using these instructions.

Note:

No spaces (blanks) are permitted within the instruction.
3.46.2 Load Register with Axis Parameter

\[ Rn:= \]

Command form:

\[ Rn:= RAi \]

Example:

```
Programme: BEISPIEL
1  G90
2  G25.X ;Return to datum X axis
3  FX1000 ;Set traversing speed to 1000Hz
4  X100 ;Move to position X100
5  R34:=RX1 ;Load real number register 34 with the traversing speed of the X axis
6  FXR34 ;Set traversing speed at the preset parameter
7  X10 ;Move to position X10
8  END
```

Description:

With the aid of this command the axis parameters can be loaded in the register.

The following applies:

\[ RX : X \text{ axis} \]
\[ RY : Y \text{ axis} \]
\[ ... \]
\[ RP : P \text{ axis} \]

The parameter is selected by the digit:

1 : Traversing speed
2 : Return to datum speed
3 : Manual speed
4 : Slow traverse
5 : Start/stop speed
6 : Acceleration
7 : Gear factor
8 : Min. traversing range
9 : Max. traversing range

Note:

Blanks are not permitted in the command.
3.46.3 Addition

Instruction form:

\[
\begin{align*}
R_n &= R_m + K \\
R_{!n} &= R_m + K \\
R_n &= R_m + R_i \\
R_{!n} &= R_{!m} + R_i \\
N_n &= N_m + K \\
N_n &= N_i + N_m \\
N_{!n} &= N_m + K \\
N_{!n} &= N_{!m} + N_i
\end{align*}
\]

Example:

Program : BEISPIEL
1  R2:=R2+57 ; Add content of R2 by 57
2  R2:=R4+R3 ; Add the content of R4 and the content of R3 and assign result R2
3  R1:=5
4  R5:=100
5  R24:=R1+R2 ; Add content of R5 and content of R2 and assign result to register R24. Content of R1=5. The content of R5 is thus accessed owing to indirect addressing. The content of R5 and R2 is added and the result is assigned to R24. R1, R5 and R2 remain unchanged.
6  N3:=N3+87 ; Add content of N3 by 87
7  N3:=N3+N5 ; Add content of N5 to content of N3
8  END
3.46.4 Subtraction

Instruction form:

- \( R_n := R_m - K \)
- \( R!n := R_m - K \)
- \( R_n := R!m - Ri \)
- \( R!n := R!m - Ri \)
- \( N_n := N_m - K \)
- \( N!n := N_m - Ni \)
- \( N!n := N!m - Ni \)

Example:

Program : BEISPIEL
1  R2 := R2 - 57 ; Subtract content of R2 by 57
2  R2 := R2 - R3 ; Subtract the content of R3 from content of R2
3  R1 := 5
4  R5 := 100
5  R24 := R1 - R2 ; Subtract content of R2 from content of R5 and assign result to register R24. Content of R2 is now subtracted from this value and the result is assigned to R24. R1, R5 and R2 remain unchanged.
6  N23 := N23 - 99 ; Subtract content of N23 by 99
7  N23 := N23 - N4 ; Subtract content of N4 from content of N23
8  END
3.46.5 Multiplication

Instruction form:

\[
\begin{align*}
R_n &= R_m \times K \\
R_n &= R_m \times R_i \\
N_n &= N_m \times K \\
N_n &= N_m \times N_i \\
N_n &= N_l \times N_i
\end{align*}
\]

Example:

Programm : BEISPIEL
\begin{align*}
1 & \quad R_2 := R_2 \times 4 \quad ; \text{Multiply content of } R_2 \text{ by } 4 \text{ and assign result to } R_2 \\
2 & \quad R_4 := R_2 \times R_3 \quad ; \text{Multiply content of } R_2 \text{ by content of } R_3 \text{ and assign result to } R_4 \\
3 & \quad R_1 := 5 \\
4 & \quad R_5 := 100 \\
5 & \quad R_24 := R_1 \times R_2 \quad ; \text{Multiply content of } R_5 \text{ by content of } R_2 \text{ and assign result to register } R_24 \\
6 & \quad N_2 := N_2 \times 4 \quad ; \text{Multiply content of } N_2 \text{ by } 4 \text{ and assign result to } N_2 \\
7 & \quad N_2 := N_3 \times N_6 \quad ; \text{Multiply content of } N_3 \text{ by content of } N_6 \text{ and assign result to } N_2 \\
8 & \quad \text{END}
\end{align*}
3.46.6 Division

Instruction form:

\[
\begin{align*}
R_n &= R_m / K \\
R!_n &= R_m / K \\
R_n &= R_m / R_i \\
R_n &= R!_m / R_i \\
N_n &= N_m / K \\
N!_n &= N_m / K \\
N_n &= N_m / N_i \\
N_n &= N!m / N_i
\end{align*}
\]

Example:

Program : BEISPIEL
1. R2:=R2/3 ;Divide register content of R2 by 3 and assign result to R2
2. R4:=R2/R3 ;Divide register content of R2 by register content of R3 and assign result to R4
3. R1:=5
4. R5:=100
5. R24=R!1/R2 ;Divide register content of R5 by register content of R2 and assign result to register R24
6. N34:=N34/2 ;Divide content of N34 by 2 and assign result to N34. The result is rounded (if necessary)
7. N25:=N67/N88 ;Divide content of N67 by content of N88 and assign result to N25. The result is rounded (if necessary)
8. END

Note:

A system error occurs if dividing by 0. This is indicated by message "SE5" on the display.
3.46.7 Compare operations

Compare operations can take place between registers and between registers and constants. The result of compare operations (logical 0 or 1) is assigned to a flag. The flag is always processed dependent upon the result.

Result true (logical 1) : Flag is set (logical 1)
Result false (logical 0) : Flag is reset (logical 0)

The following applies in general:

<table>
<thead>
<tr>
<th>Destination</th>
<th>:</th>
<th>Operand 1</th>
<th>Operation</th>
<th>Operand 2</th>
</tr>
</thead>
<tbody>
<tr>
<td>- Flag</td>
<td>-</td>
<td>Register</td>
<td>&lt;= &gt;</td>
<td>Register</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>- Constant</td>
</tr>
</tbody>
</table>

Note:

Operation "=" must be used with extreme care. If it is intended to check the limits of inputs or loop conditions, operations ">" or "<" are more reliable since they supply a clear and unequivocal result even if rounding problems occur!
3.46.8 Compare

> = <

Instruction form:

\[ \begin{align*}
M_n &= R_m = K \\
M_n &= R_m > K \\
M_n &= R_m < K \\
M_n &= R_m = R_i \\
M_n &= R_m > R_i \\
M_n &= R_m < R_i \\
M_n &= R_m = R_i \\
M_n &= N_m = K \\
M_n &= N_m > K \\
M_n &= N_m < K \\
M_n &= N_m = N_i \\
M_n &= N_m > N_i \\
M_n &= N_m < N_i \\
M_n &= N_m = N_i
\end{align*} \]

Example:

Programm : BEISPIEL
1  \( M_{34} := R_1 = 56.77 \); Flag 34 is set if the content of R1 is equal to 56.77; otherwise, flag 34 is reset
2  \( M_{35} := R_1 > 56.34 \); Flag 35 is set if the content of R1 is greater than 56.34 otherwise, flag 35 is reset
3  \( M_{36} := R_1 < 56 \); Flag 36 is set if the content of R1 is less than 56; otherwise, flag 36 is reset
4  \( R_2 := 10 \)
5  \( M_{12} := R_{10} = 0 \); Flag 12 is set if the content of R10 is equal to 0; otherwise, flag 12 is reset
6  \( M_{34} := N_1 = 56 \); Flag 34 is set if the content of N1 is equal to 56; otherwise, flag 34 is reset
7  \( M_{35} := N_1 > 56 \); Flag 35 is set if the content of N1 is greater than 56; otherwise, flag 35 is reset
8  \( M_{36} := N_1 < 56 \); Flag 36 is set if the content of N1 is less than 56; otherwise, flag 36 is reset
9  END
3.46.9 Complex examples

1. Load real number registers 10 to 20 with 0 at program start (reset counters)

Program: BEISPIEL
1  R1:=10 ;R1 serves the purpose of indirect addressing
2  $SCHLEIFE
3  R!1:=0.0 ;Assign value to register to which the content of R1 points
4  R1:=R1+1 ;Next register
5  M1:=R1<20 ;Load all 10 registers (R10-R20) with value?
6  G21 M1.1 SCHLEIFE ;Jump if not all registers have yet been loaded
7  END

2. Production sequence of pallet with uneven distances

Program: PALETT_1
1  R11:=1
2  $EINLESEN
3  G24.R!11.0 ;Entry of the pallet positions
4  R11:=R11+1 ;Pointer to next pallet position
5  M1:=R11>5 ;All pallet positions read in?
6  G21 M1.0 EINLESEN ;No!
7  R11:=1 ;Position pointer for processing to 1st position
8  $NAECHST
9  +X100 ;Approach fetch position
10 SUB TEILHOLE ;Pick up part
11  +XR!11 ;Approach deposit position
12 SUB TEILABLE ;Deposit part
13 R11:=R11+1 ;Position pointer to next pallet position
14 M1:=R1>6 ;All pallet positions occupied?
15 G21 M1.0 NAECHST ;No!

Program: TEILHOLE
1  I1.1 ;Wait until part is in fetch position
... ;Start sequence for part

Program: TEILABLE
1  I7.1 ;Pallet present
... ;Sequence for depositing part

...
3.47 Logic operations

A logic operation must always start with a LD command and end with an OUT command. Only commands of the logic operations may be used within a logic string (starting with LD, ending with OUT).

Logic operations are processed on the basis of the following functional mechanism.

In order to also use with logic operations the writing method from the commands "Wait for the state of an element" (e.g. I3.1, M12.0), not only the element and the number such as input, marker or output, but also the desired state of the element was also assigned to the LD, AND and OR commands. If the current state of the element (I, M, O) corresponds to the state of the element with the logic command, a logic "1" is used for further work on converting the command (LD, AND, OR). Otherwise, further work is carried out with a logic "0".

The result of the logic operations LD, AND and OR is stored in the bit accumulator. The state of the bit accumulator is first transferred into the bit accumulator stack with an LD command and only then is the result of the element check stored in the bit accumulator.

The logic operations AND-LD and OR-LD carry out a logic operation between the bit accumulator and bit accumulator stack and store the result in the bit accumulator.

The OUT command sends the state of the bit accumulator to the addressed element. If the bit accumulator is set to logic "1", the output or marker is set. Otherwise, it is reset. Several OUT commands can follow directly one after the other.

In the case of the PAB, every parallel sequence has its own bit accumulator and bit accumulator stack.
Command: LD

Functional mechanism for logic operations

Check status of the elements

State of the elements is as noted in the command

Yes | No
--- | ---
1   | 0

Example: LD I3.1

Linker
"AND" "OR"

Output OM

Command: AND or OR

Functional mechanism for logic operations

Check status of the elements

State of the elements is as noted in the command

Yes | No
--- | ---
1   | 0

Example: AND M6.0

Linker
"AND" "OR"

Output OM

Command: AND-LD or OR-LD
Functional mechanism for logic operations

Check status of the elements

<table>
<thead>
<tr>
<th>State of the elements is as noted in the command?</th>
</tr>
</thead>
<tbody>
<tr>
<td>YES</td>
</tr>
<tr>
<td>1</td>
</tr>
</tbody>
</table>

Example: AND-LD OR-LD

---

Command: OUT

Functional mechanism for logic operations

Check status of the elements

<table>
<thead>
<tr>
<th>State of the elements is as noted in the command?</th>
</tr>
</thead>
<tbody>
<tr>
<td>YES</td>
</tr>
<tr>
<td>1</td>
</tr>
</tbody>
</table>

Example: LD I3.1
3.47.1 Logic AND operation

**LD, AND, OUT**

Instruction form:

- AND li.n
- AND Oi.n
- AND Mi.n

Example:

Program : EXAMPLE

1  LD I3.1 ;Begin the logic operation and load the bit accumulator with logic "1", if input 3 is set. Otherwise load bit accumulator with logic "0".

2  AND I4.0 ;If the input 4 is not set, make an AND logic operation with logic "1" and the bit accumulator and store the result in the bit accumulator

3  OUT O6 ;If the bit accumulator is set to logic "1", the output 6 is set. Otherwise, output 6 is reset.

4  END

Application:

Building up logic AND operations between inputs, markers and outputs. The result of the logic operation can be assigned to a marker or to an output.

Schematic circuit diagram to above example:

```
+U
   /
  I3
   |
  I4
   |
   O6
```
3.47.2 Logic OR operation

**LD, OR, OUT**

Instruction form:

- OR Ii.n
- OR Oi.n
- OR Mi.n

Example:

Program: EXAMPLE

1. LD I3.1 ;Begin logic operation and load bit accumulator with logic "1" if input 3 is set. Otherwise, load bit accumulator with logic "0".
2. OR I4.0 ;If input 4 is not set, make an OR logic operation with logic "1" and the bit accumulator and store the result in the bit accumulator.
3. OUT O6 ;If the bit accumulator is at logic "1", output 6 is set. Otherwise, output 6 is reset.
4. END

Application:

Establishing logic OR operations between inputs, markers and outputs. The result of the logic operation can be assigned to a marker or to an output.

Schematic circuit diagram to above example:

```
+U
 / \\
I3  I4
|   |
|   |
|   |
|   |
|   |
|   |
|   |
O6   
```
3.47.3 Multi-stage logic AND operation

AND-LD

Instruction form:

AND-LD

Example:

Program : EXAMPLE
1 LD I3.1 ;Start logic operation and load bit accumulator with logic "1" if input 3 is set. Otherwise, load bit accumulator with logic "0".
2 OR I4.0 ;If input 4 is not set, make an OR logic operation with logic "1", and with the bit accumulator and store the result in the bit accumulator
3 LD I5.1 ;Begin logic operation and load the bit accumulator with logic "1" if input 5 is set. Otherwise, load it with logic "0".
4 OR I6.1 ;If input 6 is set, make an OR logic operation with logic "1", and the bit accumulator and store the result in the bit accumulator
5 AND-LD ;Make an AND logic operation with the bit accumulator and with the bit accumulator stack and store the result in the bit accumulator
6 OUT O6 ;If the bit accumulator is set to logic "1", output 6 is set. Otherwise, output 6 is reset
7 END

Application:

Establishing complex (multi-stage) logic AND operations between inputs, markers and outputs. The results of the logic operation can be assigned to a marker or to an output.

Schematic circuit diagram to above example:

```
+U
/I3   I4
|     |
|     |
/I5   I6
|     |
|     |
I4
```

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3.47.4 Multi-stage logic OR operation

OR-LD

Instruction form:

OR-LD

Example:

Program: EXAMPLE
1 LD I3.1 ;Begin logic operation and load bit accumulator with logic "1" if input 3 is set. Otherwise, load it with logic "0".
2 AND I4.0 ;If input 4 is not set, make an AND logic operation with logic "1" and with the bit accumulator and store the result in the bit accumulator.
3 LD I5.1 ;Begin logic operation and load the bit accumulator with logic "1" if input 5 is set. Otherwise, load it with logic "0".
4 AND I6.1 ;If input 6 is set, make an AND logic operation with logic "1" and with the bit accumulator and store the result in the bit accumulator.
5 OR-LD ;Make an OR logic operation with the bit accumulator and with the bit accumulator stack and store the result in the bit accumulator.
6 OUT O6 ;If the bit accumulator is set to logic "1", the output 6 is set. Otherwise, output 6 is reset.
7 END

Application:

Establishing complex (multi-stage) logic OR operations between inputs, markers and outputs. The result of the logic operation can be assigned to a marker or to an output.

Schematic circuit diagram to above example:

```
+U
  |   |
  |   |
  |I3  |
  |I4  |
  |I5  |
     |
     |I6
     |
     |
     O6
```
3.47.5 Complex Logic Operations

If a multi-step logic operation is carried out, the result of a logic operation must be temporarily stored as the logic operation result is repeatedly overwritten in the Bit-accu-stack. The example shows a multi-step logic operation. If the programming is carried out without temporary storage in flag 82, the Bit-accu-stack will be overwritten after the second LD command and logic operation result will be incorrect.

Example:

Programme: EXAMPLE

<table>
<thead>
<tr>
<th>False</th>
<th>Right</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 LD M4.1</td>
<td>1 LD M4.1</td>
</tr>
<tr>
<td>2 OR M5.0</td>
<td>2 OR M5.0</td>
</tr>
<tr>
<td>3 LD M14.1</td>
<td>3 OUT M82</td>
</tr>
<tr>
<td>4 OR M15.0</td>
<td>4 ;</td>
</tr>
<tr>
<td>5 LD M24.1</td>
<td>5 LD M14.1</td>
</tr>
<tr>
<td>6 OR M25.0</td>
<td>6 OR M15.0</td>
</tr>
<tr>
<td>7 LD M34.1</td>
<td>7 AND M82.1</td>
</tr>
<tr>
<td>8 AND M35.0</td>
<td>8 OUT M82</td>
</tr>
<tr>
<td>9 AND-LD</td>
<td>9 ;</td>
</tr>
<tr>
<td>11 OUT M82</td>
<td>10 LD M24.1</td>
</tr>
<tr>
<td>12 END</td>
<td>11 OR M25.0</td>
</tr>
</tbody>
</table>

Circuit diagram:

```
+U

M5

M4

M15

M14

M25

M24

M35

M34

M82

BILD056A
```
3.48 Communication with the parallel sequence controller

Please note:

This commands can only be used in conjunction with the PAB board (optional).

3.48.1 Starting a parallel sequence

<table>
<thead>
<tr>
<th>RUN</th>
</tr>
</thead>
</table>

Instruction form:

RUN Name

Example:

Program : EXAMPLE.PNC
1 M1:=0 ;Reset marker 1
2 M2:=0 ;Reset marker 2
3 RUN OUT1 ;Start the program "OUT1"
4 RUN OUT2 ;Start the program "OUT2"
5 M1.1 ;Wait until marker 1 is set to logic "1"
6 M2.1 ;Wait until marker 2 is set to logic "1"
7 O3:=1 ;Set the output 1
8 END ;End program "EXAMPLE".

Program : OUT1.PAB
1 O1:=1 ;Set the output 1
2 T10 ;Waiting time of 100 ms
3 O1:=0 ;Reset output 1
4 M2:=1 ;Set marker 2
5 END ;End program "OUT1"; it is removed from the parallel sequence interpreter

Program : OUT2.PAB
1 O2:=1 ;Set output 2
2 T20 ;Waiting time of 200 ms
3 O2:=0 ;Reset output 2
4 M1:=1 ;Set marker 1
5 END ;End program "OUT2"; it is removed from the parallel sequence interpreter
Application:

Starting sequence programs.

Description:

The RUN command allows sequence programs (programs of the type "PAB") to be started on the parallel sequence controller. The programs are taken into the sequence interpreter of the PAB where they are processed.

Please note:

The programs must be present in the memory of the PAB.
A program can only be entered once into the sequence interpreter.
Up to 32 programs can be processed simultaneously in the sequence interpreter.
3.48.2 Stopping a parallel sequence

### SLEEP

**Instruction form:**

Sleep Name

**Example:**

Program: EXAMPLE.PNC

```plaintext
1 M1:=0  ;Reset marker 1
2 M2:=0  ;Reset marker 2
3 RUN OUT1 ;Start program "OUT1"
5 M1.1 ;Wait until marker 1 is set to logic "1"
6 SLEEP OUT1 ;Stop the program "OUT1"
7 M1:=0 ;Reset marker 1
8 I1.1 ;Wait until input 1 is set to logic "1"
9 RUN OUT1 ;Continue the program "OUT1"
10 M2.1 ;Wait until marker 2 is set to logic "1";
11 O3:=1 ;Set output 1
12 END ;End program "EXAMPLE"
```

Program: OUT1.PAB

```plaintext
1 O1:=1 ;Set output 1
2 M1:=1 ;Set marker 1
3 M1.0 ;Wait until marker 1 is set to logic "0"
4 T10 ;Waiting time of 100 ms
5 O1:=0 ;Reset output 1
6 M2:=1 ;Set marker 2
7 END ;End program "OUT1"
```

**Application:**

Stopping sequence programs, e.g. when a safety door is opened.

**Description:**

Sequence programs (programs of the type "PAB") can be stopped on the parallel sequence controller with the SLEEP command. The program is put into SLEEP mode by the SLEEP command in the sequence interpreter of the PAB, i.e. it is not processed further. It remains at the current command. This program can then be continued as from the current command with the RUN command.

**Please note:**

The SLEEP command can only be used on programs which are in the RUN mode. Dwell and monitoring time commands are also stopped.
### 3.48.3 Ending a parallel sequence

**CANCEL**

**Instruction form:**

- Cancel Name

**Example:**

Program : EXAMPLE.PNC

1  M1:=0 ;Reset marker 1
2  M2:=0 ;Reset marker 2
3  RUN OUT1 ;Start program "OUT1"
4  I7.1 ;Wait until input 7 is energized
5  CANCEL OUT1 ;End program "OUT1"
6  END ;End "EXAMPLE" program

Program : OUT1.PAB

1  $START
2  O1:=1 ;Set output 1
3  T10 ;Waiting time of 100ms
4  O1:=0 ;Reset output 1
5  T10 ;Waiting time of 100ms
6  JMP START ;Jump to "START" marker
7  END

**Application:**

Immediate ending of sequence programs. This makes space in the sequence interpreter for a new program to be started, e.g. operating mode change of a production system.

**Description:**

The CANCEL command allows sequence programs (programs of the type "PAB") to be ended on the parallel sequence controller. The program is removed from the sequence interpreter of the PAB by the CANCEL command and is no longer further processed.

**Please note:**

The CANCEL command can only be used on programs which are in RUN mode or SLEEP mode.
The program is aborted at the command currently being processed, i.e. elements which are still influenced are supplied (marker, outputs, register).
### 3.48.4 Starting parallel sequences

**CASE.RUN**

#### Command form:

```
CASE.RUN.Ni
(Name1)
(Name2)
...
ELSE Marke_e
```

#### Example:

Programme: BEISPIEL.PNC

```
1 $FEHLER
2 G24.N8.0 ;Enter value via keyboard
3 CASE.RUN.N8 ;Check contents of N8 and start PAB programme at:
4 (PROG-1) ;N8=1 : start programme PROG-1
5 (PROG-2) ;N8=2 : start programme PROG-2
6 (PROG-3) ;N8=3 : start programme PROG-3
7 ELSE FEHLER ;Jump to "ERROR" mark, if the value of N8 is beyond the intended limits (here when N8<1 or N8>3)
8 O12:=0
9 I1.1
10 END
```

Programme: PROG-1.PAB

```
1 O1:=1 T100 O1:=0 ;Set output 1 for 1 s
2 END
```

Programme: PROG-2.PAB

```
1 O2:=1 T100 O2:=0 ;Set output 2 for 1 s
2 END
```

Programme: PROG-3.PAB

```
1 O3:=1 T100 O3:=0 ;Set output 3 for 1 s
2 END
```

**Application:**

Depending on e.g. different types of manufacturing, different types of processing operations can be executed in parallel to other operations. These operations can be initiated variable with CASE.RUN.
Description:

With the command CASE.RUN parallel sequences where startet depending on a integer number register. Programme distributors can be easily created using this command. The PA-CONTROL checks the contents of the integer number register and starts a parallel sequence in accordance with the value. If the contents of the integer number register are smaller than 1 or greater than the number of elements of the name table (in the example given: PROG-1, PROG-2, PROG-3), a jump is made to the mark that is defined after ELSE. Otherwise the respective PAB programme is called up and continued with the programme line after the ELSE branch (in the example given: Line 8 with O12:= 0).

The following allocations apply:

<table>
<thead>
<tr>
<th>Value in register</th>
<th>Name in name table</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1. Name</td>
</tr>
<tr>
<td>2</td>
<td>2. Name</td>
</tr>
<tr>
<td>...</td>
<td>...</td>
</tr>
<tr>
<td>n</td>
<td>n. Name</td>
</tr>
</tbody>
</table>

Note:

The PAB programmes have to be available, otherwise the error message „programme not available“ will be displayed. If a parallel sequence has already been startet it cannot be startet again. Otherwise the error message “programme already running“ will be displayed. If the command is set in a PAB programme, a maximum of 24 CASE branches is possible. Otherwise the error message „PAB: in CASE too much (...) switches“.
3.48.5 Stopping parallel sequences

**CASE.SLEEP**

**Command form:**

```
CASE.SLEEP.Ni
(Name1)
(Name2)
...
ELSE Marke_e
```

**Example:**

Programme: BEISPIEL.PNC
1 RUN PROG-1 ;Starting the programme PROG-1
2 RUN PROG-2 ;Starting the programme PROG-2
3 $ANFANG
...
25 G24.N10.0 ;Enter value via keyboard
26 CASE.SLEEP.N10 ;checks the contents of N10 and stops the corresponding PAB programme at N10:
27 (PROG-1) ;N10=1: stops the programme PROG-1.PAB
28 (PROG-2) ;N10=2: stops the programme PROG-2.PAB
29 ELSE FEHLER ;Jump to mark "FEHLER", if the value of N10 is beyond the intended limits (here when N10<1 or N10>2).
...
90 $FEHLER
100 END

Programme: PROG-1.PNC
1 $ANFANG ;Jump mark
2 O1:=1 ;Set output 1
3 T100 ;wait 1s
4 O1:=0 ;reset output 1
5 T100 ;wait 1s
6 JMP ANFANG ;go to mark ANFANG
7 END

Programme: PROG-2.PAB
1 $ANFANG ;Jump mark
2 O2:=1 ;set output 2
3 T50 ;wait 0.5s
4 O2:=0 ;reset output 2
5 T50 ;wait 0.5s
6 JMP ANFANG ;go to mark ANFANG
7 END

**Application:**

Depending on e.g. different types of manufacturing, different types of processing operations can be executed in parallel to other operations. They can be stopped variable with CASE.SLEEP.
Description:

With the command CASE.SLEEP parallel sequences can be stopped depending on a integer number register. Programme distributors can be easily created using this command. The PA-CONTROL checks the contents of the integer number register and starts a parallel sequence in accordance with the value. If the contents of the integer number register are smaller than 1 or greater than the number of elements of the name table (in the example given: PROG-1, PROG-2), a jump is made to the mark that is defined after ELSE. Otherwise the respective PAB programme is called up and continued with the programme line after the ELSE branch.

The following allocations apply:

<table>
<thead>
<tr>
<th>Value in register</th>
<th>Name in name table</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1. Name</td>
</tr>
<tr>
<td>2</td>
<td>2. Name</td>
</tr>
<tr>
<td>...</td>
<td>...</td>
</tr>
<tr>
<td>n</td>
<td>n. Name</td>
</tr>
</tbody>
</table>

Note:

The PAB programmes have to be available, otherwise the error message „programme not available“ will be displayed.
If a parallel sequence has already been stopped it cannot be stopped again. Otherwise the error message “programme already in Sleep” will be displayed.
If the command is set in a PAB programme, a maximum of 24 CASE branches is possible. Otherwise the error message „PAB: in CASE too much (...) switches“.
3.48.6 Terminating parallel sequences

**CASE.CANCEL**

**Command form:**

```
CASE.CANCEL.Ni
(Name1)
(Name2)
...
ELSE Marke_e
```

**Example:**

Programme: BEISPIEL.PNC

```
1 RUN PROG-1 ;Starting the programme PROG-1
2 RUN PROG-2 ;Starting the programme PROG-2
3 $ANFANG
...
25 G24.N10.0 ;Enter value via keyboard
26 CASE.CANCEL.N10 ;checks the contents of N10 and terminates the corresponding PAB programme at N10:
27 (PROG-1) ;N10=1: terminates programme PROG-1.PAB
28 (PROG-2) ;N10=2: terminates programme PROG-2.PAB
29 ELSE FEHLER ;Jump to mark "FEHLER", if the value of N10 is beyond the intended limits (here when N10<1 or N10>2).
...
90 $FEHLER
100 END
```

Programme: PROG-1.PNC

```
1 $ANFANG ;Jump mark
2 O1:=1 ;Set output 1
3 T100 ;wait 1s
4 O1:=0 ;reset output 1
5 T100 ;wait 1s
6 JMP ANFANG ;go to mark ANFANG
7 END
```

Programme: PROG-2.PAB

```
1 $ANFANG ;Jump mark
2 O2:=1 ;set output 2
3 T50 ;wait 0.5s
4 O2:=0 ;reset output 2
5 T50 ;wait 0.5s
6 JMP ANFANG ;go to mark ANFANG
7 END
```

**Application:**
Depending on e.g. different types of manufacturing, different types of processing operations can be executed in parallel to other operations. These operations can be terminated variable with CASE.CANCEL.

Description:

With the command CASE.CANCEL parallel sequences can be terminated depending on a integer number register. Programme distributors can be easily created using this command.

The PA-CONTROL checks the contents of the integer number register and starts a parallel sequence in accordance with the value. If the contents of the integer number register are smaller than 1 or greater than the number of elements of the name table (in the example given: PROG-1, PROG-2), a jump is made to the mark that is defined after ELSE. Otherwise the respective PAB programme is called up and continued with the programme line after the ELSE branch.

The following allocations apply:

<table>
<thead>
<tr>
<th>Value in register</th>
<th>Name in name table</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1. Name</td>
</tr>
<tr>
<td>2</td>
<td>2. Name</td>
</tr>
<tr>
<td>...</td>
<td>...</td>
</tr>
<tr>
<td>n</td>
<td>n. Name</td>
</tr>
</tbody>
</table>

Note:

If the command is set in a PAB programme, a maximum of 24 CASE branches is possible. Otherwise the error message „PAB: in CASE too much (...) switches“.
4 Commissioning

Contents

4.1 Installation of a PAC Servo ................................................................. 4-2
4.2 Wiring the connections................................................................. 4-2
4.3 Adjusting the position controller .................................................. 4-3
4.4 Function and status check of the inputs and outputs.................. 4-3
4.5 Setting the parameters................................................................. 4-3
4.6 PNC programming ................................................................. 4-4
4.7 Defining the start program........................................................... 4-5
4.8 Running the program created..................................................... 4-5
4.1 Installation of a PAC Servo

Ambient conditions, such as temperature, soiling or humidity, influence operation of a positioning and sequential control and may cause errors. This fact must be taken in consideration as early as the installation stage. The PAC-Servo may not be installed in the area of a strong electrical or magnetic field (e.g. welding transformer) and may not be mechanically stressed (e.g. by vibration). Ensure that the fan inlet and the fan outlet openings are unobstructed.

4.2 Wiring the connections

Important:

Plugs and connectors may be connected and disconnected only with the power supply switched off!

Please refer to Chapter "Technical annex" for the pin assignments of the individual plugs and connectors with connection examples.

- Limit switches of all available axes
- Servo motors
- Inputs
- Outputs
- External start (if used)
- External stop (if used)

Note:

Always connect the housing to the PE wire!

The Stop switch must be closed before the Start switch is closed (external start/stop) in order to guarantee proper functioning of the start and stop.
Please refer to the function schematic in Chapter Operator interface ⇒ Automatic.
4.3 Adjusting the position controller

Please refer to the section "Putting position controller into operation" for details about commissioning and adjusting the position controller.

4.4 Function and status check of the inputs and outputs

The inputs and outputs of the PA-CONTROL can be checked in menu sub-option "Program test and diagnosis" (see Chapter Operator interface - program test and diagnosis for a description).

- Checking the function of the limit switches
- Checking the function of the connected inputs
- Checking the function of the connected outputs

4.5 Setting the parameters

Please refer to Chapter Parameters for setting the parameters.

Note:

The parameter values must be checked to ensure that they are correct for the application!
4.6 PNC programming

In order to create a new PNC program, you must access the PA-CONTROL program editor from the main menu by selecting menu options "Programming - Create new program" and by entering the program name "BEISPIEL" with type "PNC".

Note:

Please always check that the program can be executed on the available machine.

The PCN program is to perform the following functions:

- Reference travel with the X axis
- Set absolute dimension system
- Set positioning speed to 50 mm/s
- Move X axis to position 100
- Wait 2 seconds
- Move X axis to position 10
- Wait 1 second

Press the following keys in the program editor to create this program.

Program : BEISPIEL

<table>
<thead>
<tr>
<th>Program</th>
<th>Enter by pressing keys</th>
</tr>
</thead>
<tbody>
<tr>
<td>G90</td>
<td>G 9 0 ENTER</td>
</tr>
<tr>
<td>G25.X</td>
<td>G 2 5 . X ENTER</td>
</tr>
<tr>
<td>FX50</td>
<td>F X 5 0 ENTER</td>
</tr>
<tr>
<td>X100</td>
<td>X 1 0 0 ENTER</td>
</tr>
<tr>
<td>T200</td>
<td>T 2 0 0 ENTER</td>
</tr>
<tr>
<td>X10</td>
<td>X 1 0 ENTER</td>
</tr>
<tr>
<td>T100</td>
<td>T 1 0 0 ENTER</td>
</tr>
<tr>
<td>END</td>
<td>END ENTER</td>
</tr>
</tbody>
</table>

Program entry can be terminated and quit by pressing key "ESC“ and answering the prompt to save the program.

ESC
1
1

If errors have been made when entering the program or if incorrect instructions have been entered, these errors must be rectified. Otherwise, it is not possible to save the program.
4.7 Defining the start program

Before the program which you have created can be run, the PAC-Servo must be informed of the particular PNC program with which the automatic sequence is to commence. This is defined in menu sub-option Sequence definitions (see Chapter Operator interface - Sequence definitions).

4.8 Running the program created

In order to run the program, the PA-CONTROL must be switched to Automatic mode (main menu 1st line). When you press the Start key, the program runs. The program run can be interrupted by pressing the Stop key.

The following is displayed during the program run:

1st line: Program name and subroutine nesting depth
2nd line: Program line number with the instructions

e.g.:

Beispiel 0
1 G90

The program performs the following steps.

<table>
<thead>
<tr>
<th>Display (2nd line)</th>
<th>Step executed by the PA-CONTROL</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 G90</td>
<td>Positioning is switched over to absolute dimension system</td>
</tr>
<tr>
<td>2 G25.X</td>
<td>The PA-CONTROL performs reference travel with the X axis</td>
</tr>
<tr>
<td>3 FX50</td>
<td>The traversing speed for the X axis is set to 50 mm/s</td>
</tr>
<tr>
<td>4 X100</td>
<td>The PA-CONTROL moves the X axis to position 100</td>
</tr>
<tr>
<td>5 T200</td>
<td>Waiting time 1 second</td>
</tr>
<tr>
<td>6 X10</td>
<td>The PA-CONTROL moves to position 10</td>
</tr>
<tr>
<td>7 T100</td>
<td>Waiting time 1 second</td>
</tr>
<tr>
<td>8 END</td>
<td>Automatic sequence is terminated.</td>
</tr>
</tbody>
</table>

The PAC-Servo returns to the main menu.
5 Parameters

Contents

5.1 General information on parameters .............................................................. 5-2
5.2 System parameters ....................................................................................... 5-3
5.3 Axis parameters .......................................................................................... 5-6
5.1 General information on parameters

We make a distinction between two parameters types on a PA-CONTROL.

- **System parameters**: Parameters which relate to the general system, such as operator language and serial interface, ...
- **Axis parameters**: Parameters relating to the axes, such as traversing speed and acceleration, ...

Various basic settings must be made before the program can be run feasibly. This means that differently dimensioned and differently loaded axes must be moved under different conditions as regards acceleration, maximum speed or gear factor.

All parameters can be loaded with default values and checked individually and, if necessary, modified (see Chapter Operator interface).
## 5.2 System parameters

**List of system parameters:**

<table>
<thead>
<tr>
<th>Parameter name</th>
<th>Min. value</th>
<th>Actual value</th>
<th>Max. value</th>
</tr>
</thead>
<tbody>
<tr>
<td>Operator language</td>
<td>1</td>
<td>1</td>
<td>2</td>
</tr>
<tr>
<td>Number of axes</td>
<td>0</td>
<td>2</td>
<td>6</td>
</tr>
<tr>
<td>External start input No.</td>
<td>0</td>
<td>0</td>
<td>128*</td>
</tr>
<tr>
<td>External stop input No.</td>
<td>0</td>
<td>0</td>
<td>128*</td>
</tr>
<tr>
<td>Manual enable input No.</td>
<td>0</td>
<td>0</td>
<td>128*</td>
</tr>
<tr>
<td>Standby output No.</td>
<td>0</td>
<td>0</td>
<td>128*</td>
</tr>
<tr>
<td>Fault output No.</td>
<td>0</td>
<td>0</td>
<td>128*</td>
</tr>
<tr>
<td>Autostart</td>
<td>0</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>Front panel</td>
<td>0</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>Serial interface No.</td>
<td>1</td>
<td>1</td>
<td>2</td>
</tr>
<tr>
<td>Baud rate of the serial interface</td>
<td>1</td>
<td>6</td>
<td>7</td>
</tr>
<tr>
<td>Format of the serial interface</td>
<td>1</td>
<td>1</td>
<td>4</td>
</tr>
<tr>
<td>Handshake of the serial interface</td>
<td>0</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>PA-CONTROL address</td>
<td>1</td>
<td>1</td>
<td>31</td>
</tr>
</tbody>
</table>

* A maximum of 112 inputs and 112 outputs are available with PAC-Servo.

**Operator language**

This parameter is used to switch over to the various operator languages.

1 = German
2 = English
3 = French (Not yet implemented in this version)

**Number of axes**

The number of axes available to the operator will differ, dependent upon device configuration. This maximum number of axes depends upon the positioning method and is stored in parameter "Maximum number of axes". Dependent upon application, the operator can now set the current number of axes which must, however, always be equal to or less than the maximum number of axes of the system. This set current number of axes is assumed as the maximum limit for the operator in the case of axis-related actions (positioning, processing parameters, ...).

**External start input No.**

Any input can be defined for the external start signal on the PA-CONTROL. If 0 is entered, corresponding to the default value, there is no external start option.

The following applies to start:

Transition from not energized to energized triggers the start (NO contact function, positive edge evaluation, see Operator interface - automatic).
External stop input No.

Any input of the PA-CONTROL can be defined for the external stop signal. If 0 is entered, corresponding to the default value, there is no external stop option.

The following applies to stop:

| If the external stop is defined, the selected input must be energized. Automatic mode is interrupted if the input is de-energized (NC contact function, level-operated, see Operator interface - automatic). |

Manual enable input No.

On the PA-CONTROL, any input can be defined for enabling the manual functions. If "0" is entered, corresponding to the default value, the manual function is freely accessible. If a value greater than 0 is entered, the input of the corresponding number must be energized so as to permit access to the manual functions.

Not yet activated in this version.

Standby output No.

Any output can be defined for output of standby (PA-CONTROL OK) on the PA-CONTROL.

Fault output No.

Any output can be defined for output of a fault which has occurred in the automatic sequence (e.g.: limit switch actuated, value too high etc.) on the PA-CONTROL. If a fault occurs in Automatic mode, the output is set. If the automatic sequence is then aborted and you return to the menu, the output is then reset.

Autostart

If the Autostart parameter is set to 1, the PA-CONTROL starts execution of the program after switching on (Reset), i.e. it automatically changes to Automatic mode.

Preconditions:
- Start program must be defined
- An input must be defined as external stop and must be energized
- An input must be defined as external start

Important:

The Autostart function is executed once only after switching on (Reset). If the program is to be executed several times, either an endless loop must be programmed or it must be executed again with "Start".
Front panel

Not yet implemented in this version

Serial interface number

The PA-CONTROL has 2 serial interfaces for communication (transfer of programs and parameters) with other systems. The serial interface number defines whether the first or second interface is used for this task.

Baud (baud rate)

The Baud parameter defines the baud rate for transfer of programs and parameters.

<table>
<thead>
<tr>
<th>Parameter value</th>
<th>Transfer rate</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>110 baud</td>
</tr>
<tr>
<td>2</td>
<td>300 baud</td>
</tr>
<tr>
<td>3</td>
<td>1200 baud</td>
</tr>
<tr>
<td>4</td>
<td>2400 baud</td>
</tr>
<tr>
<td>5</td>
<td>4800 baud</td>
</tr>
<tr>
<td>6</td>
<td>9600 baud</td>
</tr>
<tr>
<td>7</td>
<td>38800 baud</td>
</tr>
</tbody>
</table>

Format

The Format parameter defines the transfer format for transfer of programs and parameters via the serial interface.

<table>
<thead>
<tr>
<th>Parameter value</th>
<th>Transfer format</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>8 bits, no parity</td>
</tr>
<tr>
<td>2</td>
<td>7 bits, no parity</td>
</tr>
<tr>
<td>3</td>
<td>7 bits, even parity</td>
</tr>
<tr>
<td>4</td>
<td>7 bits, odd parity</td>
</tr>
</tbody>
</table>

Handshake

The Handshake parameter defines what handshake procedure is used when transferring programs and parameters via the serial interface.

<table>
<thead>
<tr>
<th>Parameter value</th>
<th>Handshake</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>No handshake</td>
</tr>
<tr>
<td>1</td>
<td>Hardware handshake</td>
</tr>
</tbody>
</table>

PA-CONTROL address

The PA-CONTROL address parameter defines the number of the PA-CONTROL if it is operated in a network. The possible value lies between 0 and 31. Not yet activated in this version.
5.3 Axis parameters

List of axis parameters

<table>
<thead>
<tr>
<th>Parameter name</th>
<th>Min. value</th>
<th>Actual value</th>
<th>Max. value</th>
</tr>
</thead>
<tbody>
<tr>
<td>Max. autospeed</td>
<td>10</td>
<td>5000</td>
<td>50000</td>
</tr>
<tr>
<td>Reference speed</td>
<td>10</td>
<td>1000</td>
<td>50000</td>
</tr>
<tr>
<td>Manual speed</td>
<td>10</td>
<td>500</td>
<td>2000</td>
</tr>
<tr>
<td>Slow manual speed</td>
<td>10</td>
<td>300</td>
<td>1000</td>
</tr>
<tr>
<td>Start/stop speed</td>
<td>10</td>
<td>400</td>
<td>1000</td>
</tr>
<tr>
<td>Acceleration</td>
<td>1</td>
<td>20</td>
<td>500</td>
</tr>
<tr>
<td>Transmission factor</td>
<td>0.001</td>
<td>1</td>
<td>1000</td>
</tr>
<tr>
<td>Traversing range, minimum</td>
<td>-8000000</td>
<td>0</td>
<td>+8000000</td>
</tr>
<tr>
<td>Traversing range, maximum</td>
<td>-8000000</td>
<td>10000</td>
<td>+8000000</td>
</tr>
<tr>
<td>Reserve field 1</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>Reserve field 2</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>P section</td>
<td>0</td>
<td>1.0</td>
<td>200</td>
</tr>
<tr>
<td>Reserve field 2</td>
<td>0</td>
<td>0.5</td>
<td>200</td>
</tr>
<tr>
<td>D section</td>
<td>0</td>
<td>0</td>
<td>200</td>
</tr>
<tr>
<td>Encoder resolution</td>
<td>1</td>
<td>1024</td>
<td>100000</td>
</tr>
<tr>
<td>Exact positioning</td>
<td>1</td>
<td>10</td>
<td>1000</td>
</tr>
<tr>
<td>Contouring error</td>
<td>1</td>
<td>1000</td>
<td>10000</td>
</tr>
<tr>
<td>Clearance, limit switch from zero pulse</td>
<td>50</td>
<td>2200</td>
<td>10500</td>
</tr>
<tr>
<td>Nominal speed</td>
<td>1</td>
<td>3000</td>
<td>10000</td>
</tr>
<tr>
<td>P current controller</td>
<td>0</td>
<td>0</td>
<td>200</td>
</tr>
<tr>
<td>I current controller</td>
<td>0</td>
<td>0</td>
<td>200</td>
</tr>
<tr>
<td>Controller type</td>
<td>0</td>
<td>0</td>
<td>2</td>
</tr>
<tr>
<td>Reference travel sequence</td>
<td>1</td>
<td>2</td>
<td>4</td>
</tr>
<tr>
<td>Reserve 3</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>Reserve 4</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
</tbody>
</table>

Max. autospeed

This parameter value is used by the control as the traversing speed in Automatic mode if no other value has been preset in the program, e.g. with instruction FAn. It is also the limit value for value input within a program.

Reference speed

Reference travel, i.e. the travel to the limit switch, is executed at this speed.

Important:

This speed must be adapted to the available overtravel distance. The overtravel distance is the distance between the limit switch and the mechanical stop. When the limit switch is detected, the motor is decelerated to stop with the preset acceleration ramp.
**Manual speed**

Positioning in Manual mode is performed at this speed unless set otherwise.

**Slow manual speed**

The distance from the limit switch to leaving the limit switch is travelled at this speed during reference travel.

**Start/stop speed**

This is the speed at which the positioning operation is commenced and terminated again (see sketch).

**Acceleration**

All positioning operations are executed on the basis of a ramp function. A low value for the acceleration corresponds to a gentle ramp, e.g. a low acceleration. A high value leads to a high acceleration with a steep ramp. (Acceleration in indication unit \((\text{AE} / \text{s}^2)\))
Transmission factor

This parameter makes it possible to perform program input in mm, inches or degrees etc. The following formula is used to determine this parameter:

\[
\text{Transmission factor (GF)} = \frac{\text{Increments per revolution}}{\text{Feed per motor revolution}} \times \text{Unit of measurement}
\]

Example 1:
No gear unit
Encoder with 500 increments per revolution
Spindle lead 5 mm
Input in mm

\[
\text{GF} = \frac{500}{5\text{ mm}} = 100
\]

If a gear unit is used between motor and driven shaft, the above calculation formula for the gear factor changes as follows:

\[
\text{Transmission factor (GF)} = \frac{\text{Increments per revolution} \times \text{gear ratio}}{\text{Feed per encoder revolution}} \times \text{Unit of measurement}
\]

Example 2:
with gear unit
Encoder with 500 increments per revolution
Feed per Encoder revolution 300 mm
Gear reduction ratio 15:1
Input in mm

\[
\text{GF} = \frac{500 \times 15}{300\text{ mm}} = 25
\]
Table for transmission factor calculation

This table makes it possible to determine the gear factor simply by reading it off.

Increments per encoder revolution and feed per motor revolution must be selected. The gear factor can be read off at the intersection point.

<table>
<thead>
<tr>
<th>Increments per revolution</th>
<th>2</th>
<th>4</th>
<th>5</th>
<th>10</th>
<th>20</th>
<th>40</th>
<th>80</th>
</tr>
</thead>
<tbody>
<tr>
<td>200</td>
<td>100</td>
<td>50</td>
<td>40</td>
<td>20</td>
<td>10</td>
<td>5</td>
<td>2.5</td>
</tr>
<tr>
<td>400</td>
<td>200</td>
<td>100</td>
<td>80</td>
<td>40</td>
<td>20</td>
<td>10</td>
<td>5</td>
</tr>
<tr>
<td>500</td>
<td>250</td>
<td>125</td>
<td>100</td>
<td>50</td>
<td>25</td>
<td>12.5</td>
<td>6.25</td>
</tr>
<tr>
<td>1000</td>
<td>500</td>
<td>250</td>
<td>200</td>
<td>100</td>
<td>50</td>
<td>25</td>
<td>12.5</td>
</tr>
</tbody>
</table>

Traversing range minimum/Traversing range maximum

These parameters serve as software limit switches. The positioning range can be restricted by defining the values for maximum and minimum traversing range. The check is conducted before each positioning operation. If necessary, an error message is issued and the program is aborted.
P section:

The amplification factor of the position controller is designated as the P section. The value 10 is entered for the P section after the standard parameter is loaded.

P control units work quickly but very inaccurately. If the P section is too large, a great position deviation is part of a certain control deviation. This means that there is a hard engagement. This hard engagement can mean that a control deviation to the other side occurs as a result, and this in turn must be compensated for. The system behaves in an unstable manner.

Please note:

If too great a value is selected for the P section, the result is drive oscillation.
If the P section value is too small, permanent control deviation occurs. The desired value is never achieved.

I section:

The integral section of the position controller is designated as the I section. The value 0.5 is entered for the I section after the standard parameter is loaded.

In contrast to the P controller, with which a position deviation is immediately assigned to every control deviation, a particular positioning speed is associated with every control deviation in the case of the I controller. Over a certain time, this results in a position deviation. The I controller works slowly but accurately and has no permanent control deviation. If the setting for the adjustment speed is set too high, the controller adjusts too quickly and the checkback signal of the control system arrives too late, particularly if it is too slow. The control system can make hardly any contact under such conditions.

Please note:

The I section must not be selected too high, otherwise the system becomes unstable. However, the value for the I section must also not be too small, otherwise the controller reacts too slowly.
D section:

The differential section at the control factor of the position controller is designated as the D section. The standard value is set to "0".

Pure D control units do not occur in practice. The D section of a controller is an addition to other, i.e. proportionally or integrally acting, parts of engagement. A controller with a D component engages strongly if the control deviation changes rapidly. This occurs so that a rapid lowering or rise in the control deviation is countered. In practice, this property means that the controller works "with foresight". The controller possesses a so-called derivative. This allows any occurring control deviation to be remedied quickly and as completely as possible.

Please note:

Knowledge of the section delay is of great significance for using the D section of the controller. Without this knowledge, modification of this parameter can quickly reduce the control quality, the exact opposite.

Increments per encoder revolution:

This parameter can be entered directly. The quadrupling of the pulse undertaken by the position controller is taken into account automatically by the system.

Example:

Encoder with 1000 increments per revolution

=> Enter the value 1000.

Exact positioning:

Entering this value determines the range (also known as the tolerance window) in which the controller recognizes "Position reached" following positioning.

Please note:

This value is entered in encoder increments.

If the values for the P and I sections are too small, definition of the value 1 can result in the desired position not being reached until after a very long period. Fluctuation by one to two increments corresponds to the principle method of operation of a controller. This fact, based on the desired accuracy, must be taken into account when selecting the encoder.
Contouring error:

In position control mode, the LR11/12 constantly monitors the drive and ensures that the setpoint position is reached and maintained if it is deviated from. If the actual position deviates from the setpoint position by the contouring error amount, there is a fault in the system. The position controller automatically switches off the controller release. This statement applies both to standstill and to positioning operation.

When high demands are placed on the dynamics, the value for the contouring error should not be selected too small, otherwise, this error will respond too frequently, thereby switching off the controller release.

The standard entry should correspond to the number of encoder increments referred to 1/4 motor revolution.

Please note:

| This value is entered in encoder increments. |

Distance between limit switch and zero pulse:

The reference travel always starts with travel towards the limit switch. When this is reached, the direction is reversed and the speed is changed. Travel is now at creep speed until the zero pulse is recognized. The value stored in this parameter gives the number of increments by which the zero pulse must occur at the latest. If the zero pulse is not recognized in the stipulated range, an abort occurs.

Nominal speed:

The corresponding nominal speed must be entered here in revolutions / minutes, the maximum value being defined as 10000 revolutions / minute.

P current controller:

The parameter describes the amplification factor for operation without a tacho and is set to 0 as standard.

I controller:

The parameter describes the integral component for operation without a tacho.

The standard value is 0.
Controller type:

The connection to the tacho is defined in this parameter:

0 = Operation with tacho (normal operation).
1 = Operation without tacho (position controller takes over speed control loop)

Reference travel sequence:

The PAC-Servo offers four possibilities for a reference travel which are described with the numbers 1-4 and which are stored as parameters.

1 = Reference travel to the right limit switch
2 = Reference travel to the left limit switch (STANDARD)
3 = Reference travel to additional reference switch, search direction right
4 = Reference travel to additional reference switch, search direction left

Example 1: Reference travel to the left limit switch

Travel with reference speed
Travel at creep speed

Example 2: Search direction left, axis is ahead of G25.X, left of additional reference point

Travel with reference speed
Travel at creep speed
Example 3: Search direction left, axis is ahead of G25.X, right of additional reference point

- Travel with reference speed
- Travel at creep speed

Example 4: Search direction right, axis is ahead of G25.X, right of additional reference point

- Travel with reference speed
- Travel at creep speed

Example 5: Search direction right, axis is ahead of G25.X, left of additional reference point

- Travel with reference speed
- Travel at creep speed
6 Options

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6.1 RAM-Expansion

Note:

RAM expansion with the PA-CONTROL SC and PA-CONTROL Single (equipped with PIO) is not possible.

If the programme storage does not suffice for complex programmes the programme storage of the PA-CONTROL* can be expanded. Contact IEF Werner before exchanging the RAM module.

⚠️ The control should be currentless before exchanging the RAM module on the CPU3 and the condenser discharged. All programmes and parameters should be saved with PROPAC. When switching on the PA-CONTROL again after exchanging the RAM module a system initialization of the PA-CONTROL is absolutely necessary (see Chapter User Interface, System Initialization).

* In the course of further development the available storage space may vary.
6.2 Parallel sequence control (PAB)

6.2.1 The extended control concept

A slave CPU (PAB, option) allows PA-CONTROL units to be extended to form multitasking controllers. The many years of experience of IEF Werner GmbH, involving several hundred applications in the automation sector and several thousand controllers of the PA range, go into realizing this extension.

The application-oriented instruction set of the PA-CONTROL was extended by the functions (RUN, SLEEP and CANCEL) which are absolutely essential to a clear and easy-to-operate multitasking system. Apart from these new commands, the user actually "sees" nothing of the 32 (in the PAB) programs (tasks) which are being processed simultaneously and can therefore realize the task to be solved effectively.

The idea behind this simple but effective method is to divide up the individual functions of the system into clear subtasks. Every subtask can be represented as a sequential step chain and can therefore be programmed and realized directly using the PA-CONTROL control instruction set.

The special feature of the PAB is that it can process several (max. 32) sequences on the slave CPU at the same time. The multitasking system developed at IEF Werner largely removes the responsibility of synchronizing the individual programs (tasks, step chains) from the user. The access control to shared data (markers, registers) is, of course, reliably monitored by the operating system.

In practice, the user first compiles a main program which runs in the foreground. Up to 8 axes are managed in the PNC type program and the background programs are started (RUN), stopped (SLEEP) and ended (CANCEL). A PAB program can also use the functions RUN, SLEEP and CANCEL on other PAB programs. Up to 32 PAB programs can be active simultaneously. If necessary, individual PAB programs can be ended (CANCEL) and additional functions can be activated via the start (RUN) of other PAB programs.

The instruction set and the syntax of the PAB programs is identical to the PNC programs, apart from the positioning commands, and therefore requires no additional working-in time.

The instruction set contains the following functions:

- Interrogations of logic statuses of inputs, markers and outputs
- Sets of markers and outputs
- Setting and reading integer and real number registers
- Logic operations between inputs, markers and outputs
- Conditional and unconditional jumps within programs
- Calculation operations (+,-,*,/) for integer and real numbers
- Comparison operations
- Dwell and monitoring time functions
- Control commands for PAB (RUN, SLEEP, CANCEL)

The PAB programs use the inputs, outputs, markers and registers existing in the system together with the PNC programs.
6.2.2 Schematic representation of a PA-CONTROL with PAB

**PA-CONTROL** (Host CPU)

- **Display**
- **Keyboard**
- **Serial interface 1**
- **Serial interface 2**

**Program organisation**

- Program memory
  - *.PNC
  - *.PTX
  - *.PAB

**PAC**

- **Sequentia program interpreter**
- **Register**
  - R129 - R512
  - N129 - N512

**Common**

- **Registers**
  - R1 - R128
  - N1 - N128
- **Flags**
  - M1 - M256
- **Inputs**
  - I1 - I512
- **Outputs**
  - O1 - O512
- **Motors**
  - X, Y, ...

**PAB** (Slave CPU)

- **Program memory**
  - *.PAB

**PAC-Serial interface 1**

**PAB-Serial interface 2**
6.3 AS-i Connection

Due to the use of the optional Actuator-Sensor-Interface card in the devices of the PA-Control family maximum 124 additional inputs/outputs can be managed per AS-i card. It is also possible to connect up to 3 AS-i master cards in the PA-Control. The bus system comprises a two-wire line for the data and power supply of the bus participants (slaves). Due to this wiring principle the wiring is reduced to a minimum of the conventional wiring.

6.3.1 AS-i Technical Data

<p>| | |</p>
<table>
<thead>
<tr>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>Topology</td>
<td>Tree structure</td>
</tr>
<tr>
<td>Bus medium</td>
<td>Unshielded two-wire line for data and power</td>
</tr>
<tr>
<td>Line length</td>
<td>100m, expansion via repeater possible</td>
</tr>
<tr>
<td>Number of slaves</td>
<td>Up to 31 per AS-i string</td>
</tr>
<tr>
<td>Number of AS-i strings</td>
<td>Up to 3 cards with the PA-CONTROL</td>
</tr>
<tr>
<td>Number of participants</td>
<td>Combination of 31 intelligent or 124 binary participants per AS-i Bus string (max. 124 inputs and 124 outputs)</td>
</tr>
<tr>
<td>Current supply</td>
<td>One AS-i power unit per string</td>
</tr>
<tr>
<td>Cycle time</td>
<td>max. 5ms</td>
</tr>
<tr>
<td>Addressing</td>
<td>Fixed unique address in slave (E²PROM), addressing possible via master</td>
</tr>
</tbody>
</table>
1. ASI-string with up to 31 Slave

ASI-master 1
Input range: I133 - I256
Output range: O133 - O256

ASI-master 2
Input range: I261 - I384
Output range: O261 - O384

ASI-master 3
Input range: I389 - I512
Output range: O389 - O512

ASI-master 4
Input range: I517 - I640
Output range: O517 - O640

2. ASI-string with up to 31 Slave

ASI-power unit

3. ASI-string with up to 31 Slave

ASI-power unit

4. ASI-string with up to 31 Slave

ASI-power unit
6.3.2 Application Example

**ASI master card**

1. **ASI-string**
   - I133 - I256
   - O133 - O256

**ASI-Slave**
- Adress: 1

**ASI-Slave**
- Adress: 2

**ASI-Slave**
- Adress: 5

- **Sensoractuator module**
  - 2 inputs and 2 outputs

- **CP-valve island with ASI island activation**
  - (FESTO)

- **Up to 4 standard sensors on one ASI slave**
  - (2 or 3 conductor technique)

- **24V-power unit**
  - for outputs

- **ASI power unit**
6.3.3 Addressing the AS-i Master Card

**Diagram:**
- DIP switch settings for addressing the AS-i card

**Procedure for loading the PA-CONTROL with AS-i Master**

- Addressing the AS-i Master Cards

<table>
<thead>
<tr>
<th>Number AS-i Master in the PAC</th>
<th>AS-i Master 1 DIP 1</th>
<th>AS-i Master 1 DIP 2</th>
<th>AS-i Master 2 DIP 1</th>
<th>AS-i Master 2 DIP 2</th>
<th>AS-i Master 3 DIP 1</th>
<th>AS-i Master 3 DIP 2</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>ON</td>
<td>ON</td>
<td>-</td>
<td>-</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>2</td>
<td>ON</td>
<td>ON</td>
<td>ON</td>
<td>OFF</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>3</td>
<td>ON</td>
<td>ON</td>
<td>ON</td>
<td>OFF</td>
<td>OFF</td>
<td>ON</td>
</tr>
</tbody>
</table>

- Insert the AS-i Master in the PA-CONTROL
- Supply the AS-i Master cards via the bus line with the AS-i supply voltage
- Re-initialize the PA-CONTROL

**Note:**

If the connected AS-i Master are not correctly addressed, they will not be recognized when the PA-CONTROL is re-initialized.
If a connected AS-i Master has no AS-i supply voltage, the PA-CONTROL indicates a configuration error when the programme starts.
For automatic operation of the PA-CONTROL at least one AS-i participant must be at the bus otherwise the PA-CONTROL signals a fault.
6.3.4 Addressing the AS-i Slave Participants

The addressing of the Slave participants at the AS-i Bus is performed individually before installation. This can be performed either with a special programming device (e.g. from Festo) or directly with the PA-CONTROL together with PROPAC. A detailed description can be found in the operating instructions of PROPAC from V3.6 upwards.

6.3.5 Operating the AS-i at the PA-CONTROL

Expansion of the PAC-Menu:

6 = Parameter
  1 = System parameter
  2 = Axis parameter
  3 = Process ASI-BUS

1 = Adopt actual configuration
2 = Display status
3 = Activate automatic programming
4 = Change operating mode

Only the respective submenus for the existing AS-i cards are displayed.

Adopt Actual Configuration

| 1 = yes / key = no |

When this function is called up the AS-i Master checks all slaves connected to the string and stores the configuration. If the configuration is altered but not adopted (e.g. a slave is removed or added) the stored and the connected configuration data will no longer correspond. In the status display the configuration bit OK is equal to '0'.

Display Status

<table>
<thead>
<tr>
<th>OFL</th>
<th>APF</th>
<th>NORM</th>
<th>PROJ</th>
<th>Aavai</th>
<th>Aakti</th>
<th>LDS.0</th>
<th>OK</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>1</td>
</tr>
</tbody>
</table>

OFL: OFFLINE Mode
0: AS-i Master is ready and waits for communication with the CPU
1: AS-i Master works internally, no communication with CPU possible

APF: Error AS-i Supply voltage
0: Supply voltage is O.K.
1: No supply voltage for the AS-i
NORM: Normal operating display
0: Normal operation not active
1: Normal operation active (protected mode)

PROJ: Projecting Mode
0: Not active
1: Active

Aavai: Automatic programming of the slave address is possible
0: No
1: Yes
If a programmed AS-i module fails during operation it can be replaced without renewed
programming. Replace the defect module with a similar AS-i module with the bus address 0 and activate
the option Aakti. The AS-i Master recognizes the new AS-i module at the address 0 and
automatically addresses the new AS-i module with the projected address.
If the new module is not identical no addressing takes place.
Aavai becomes 0.

Aakti: Automatic Programming of the Slave Address
0: Not active
1: Active

LDS.0: Slave with Address 0
0: Exists
1: Not existing

OK: Configuration of the AS-i
0: Not OK
1: OK

Activate Automatic Programming

| AS-i BUS Automatic Programming | Activated: yes (ENTER/ESC) |

Change Operating Mode

| Protected operating mode (Automatic) | Activated: yes (ENTER/ESC) |
6.4 Interbus-S connection

Installation of the optional Interbus-S board in the units of the PA-CONTROL family opens up new and expanded application capabilities for the PA-CONTROL.
The PA-CONTROL is integrated as the slave in the 2-wire remote bus user in the Interbus-S system. The PA-CONTROL uses 64 bits or data points in the Interbus-S. Various significances are assigned to the 64 bits in order to fully utilize the diverse capabilities and fully comply with the requirements in respect of the PAC.

The PAC can be addressed in two operating modes via the Interbus-S:

- **Program and parameter transfer between host and PAC in both directions.**
  These capabilities are also implemented in the PROPAC programming environment.

- **Execution of individual commands whilst the PAC is running its program.** In this case, a host (PC or PLC) can exchange individual data with a PAC simply via the Interbus-S.

An overview of the functions available is shown below. IEF has developed driver functions in the Turbo Pascal and Microsoft C languages for a PC as master.

### 6.4.1 Instructions for the PA-CONTROL via Interbus-S:

<table>
<thead>
<tr>
<th>Instruction</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>cmd_stop</td>
<td>Stop Automatic, stop positioning (corresponds to the STOP key)</td>
</tr>
<tr>
<td>cmd_abort</td>
<td>Abort Automatic mode (halt positioning) and change to initial state</td>
</tr>
<tr>
<td>cmd_start</td>
<td>Change from initial state to Automatic mode and process programs as of the &quot;Start program&quot;</td>
</tr>
<tr>
<td>cmd_data_transmission</td>
<td>Start data transmission; the mode and direction of data transmission are defined in the instruction parameter</td>
</tr>
<tr>
<td>cmd_get_aktual_posaktuelle</td>
<td>Fetch position of an axis</td>
</tr>
<tr>
<td>cmd_put_single_reminder</td>
<td>Change flag</td>
</tr>
<tr>
<td>cmd_get_reminder_word</td>
<td>Read flag word (marker)</td>
</tr>
<tr>
<td>cmd_put_int_reg</td>
<td>Write to integer register</td>
</tr>
<tr>
<td>cmd_get_int_reg</td>
<td>Read integer register</td>
</tr>
<tr>
<td>cmd_put_float_reg</td>
<td>Write to floating point register</td>
</tr>
<tr>
<td>cmd_get_float_reg</td>
<td>Read floating point register</td>
</tr>
<tr>
<td>cmd_put_single_output</td>
<td>Change output</td>
</tr>
<tr>
<td>cmd_get_output_word</td>
<td>Read output word</td>
</tr>
<tr>
<td>cmd_get_input_word</td>
<td>Read input word (input)</td>
</tr>
<tr>
<td>cmd_put_reminder_refresh</td>
<td>Change flag and with consecutive updating</td>
</tr>
<tr>
<td>cmd_get_reminder_refresh</td>
<td>Read double-flag word (marker) with consecutive updating</td>
</tr>
<tr>
<td>cmd_get_int_reg_refresh</td>
<td>Read integer register with consecutive updating</td>
</tr>
<tr>
<td>cmd_get_float_reg_refresh</td>
<td>Read floating point register with consecutive updating</td>
</tr>
<tr>
<td>cmd_put_output_refresh</td>
<td>Change output with consecutive updating</td>
</tr>
<tr>
<td>cmd_get_output_refresh</td>
<td>Read output word with consecutive updating</td>
</tr>
<tr>
<td>cmd_get_input_refresh</td>
<td>Read input word with consecutive updating</td>
</tr>
</tbody>
</table>
6.4.2 Interbus-S remote bus slave board for PA-CONTROL

Use the remote bus cable complying with the specifications of Messrs. Phoenix Contact.
6.4.3 Interbus-S monitor:

If the Interbus-S system (network) is in operation, you will see sub-menu option "8 = Interbus-S monitor" in the "System diagnosis" menu.

The Interbus-S monitor serves to test communication with the PA-CONTROL via Interbus-S.

You will see the following display after you switch to this menu option:

| IBS-IN    | : 00 00 00 00 00 00 00 |
| IBS-OUT   | : 49 45 46 20 00 00 3F 00 |

The current 64 bit (8 bytes) PA control input data and PA-CONTROL output data are shown on the display. This data is displayed byte-serially in hexadecimal notation. The instruction interpreter for Automatic mode is active on the PA-CONTROL, i.e. all instructions permitted in Automatic mode of the PA-CONTROL can be executed. This permits the Interbus-S operator to check the protocol running on the Interbus-S network between Master and PA-CONTROL.

You can quit the Interbus-S monitor by pressing the "ESC key".
6.5 Counter board

The use of the counter board "CNT" makes available additional possible uses of the PA-CONTROL as from software version 3.xx. Up to 2 counter boards can be used in one PAC. In the case of the PAC servo, the CNT board can only be used if max. 4 servo axes are controlled (2 x LR12 => 4 axes).

The counter board is automatically recognized when "Reinitialized PA-CONTROL" is carried out (menu point "Reinitialize basic settings - PA-Control").

Please note:

This initialization must always be carried out when counter board(s) is/are retrofitted.

The counter board has 8 opto-decoupled signal inputs with a joint ground potential at a 9-pole Sub-D socket. The input signal levels are designed for 24 V DC, type 6 mA. With input frequencies above 1 kHz, signal sources (rotary transducers, proximity switches) with push-pull output driver stages must be used in order to ensure correct switching behavior of the optocoupler inputs.

12 counters are present on the hardware side on the counter board. One input is permanently assigned to every counter CNT1 to CNT8. CNT1 to CNT8 are incrementers. At the same time, 2 inputs are assigned to each counter CNT9 to CNT12 (incrementers/decrementers). CNT9 to CNT12 are incrementers/decrementers with channel A and B (90° phase angle) for evaluating incremental transducers.

CNT13 to CNT24 are on the second counter board. (CNT13 to CNT20 are incrementers, CNT21 to CNT24 are incrementers/decrementers).

SUB-D-pin socket

| 1 | CNT1 (13) | CNT9 (21) Channal-A |
| 2 | CNT2 (14) | CNT9 (21) Channal-B |
| 3 | CNT3 (15) | CNT10 (22) Channal-A |
| 4 | CNT4 (16) | CNT10 (22) Channal-B |
| 5 | CNT5 (17) | CNT11 (23) Channal-B |
| 6 | CNT6 (18) | CNT11 (23) Channal-B |
| 7 | CNT7 (19) | CNT12 (24) Channal-A |
| 8 | CNT8 (20) | CNT12 (24) Channal-B |

BILD122E
6.5.1 Function CNT1 to CNT8 (CNT13 to CNT20)

The counter range of the incrementers (CNT1 to CNT8 / CNT13 to CNT20) is between 0 and 65,535. The positive switching edges (0V after plus) initiate the counting procedure. The following situation arises when the counting range is exceeded:

Starting point of the examples: Counter reading = zero

<table>
<thead>
<tr>
<th>Number of input pulses</th>
<th>Counter reading</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>10</td>
<td>10</td>
</tr>
<tr>
<td>65,535</td>
<td>65,535</td>
</tr>
<tr>
<td>65,536</td>
<td>0</td>
</tr>
<tr>
<td>65,537</td>
<td>1</td>
</tr>
<tr>
<td>65,538</td>
<td>2</td>
</tr>
</tbody>
</table>

6.5.2 Function CNT9 to CNT12 (CNT21 to CNT24)

The counting range of the incrementers/decrementers (CNT9 to CNT12 / CNT21 to CNT24) is between -32,766 and +32,767. There is 4-fold evaluation of the two channels A and B. This gives a counter reading of 2,000 after one revolution with a transducer with 500 pulses/revolution.

- The counting direction is defined by the allocation of the switching edges of the inputs used as channel A and channel B and can therefore be adjusted by interchanging A and B.
6.5.3 Commands for operating the counters

- **CNT1:=10**: Set counter 1 to the value 10
- **CNT2:=N10**: Set counter 2 to the contents of the integer register 10
- **N1:=CNT2**: Read counter 2 and store the read value in the integer register 2
- **CNT4.1.3456**: Wait until the contents of counter 4 is greater than 3.456
- **CNT3.1.N67**: Wait until the contents of counter 3 is greater than the contents of the integer register 67
- **CNT10.0.3456**: Wait until the contents of counter 4 is less than 3.456
- **CNT11.0.N67**: Wait until the contents of counter 3 is less than the contents of the integer register 67

The counter commands are also possible in PAB programs. When using in the PAB, please pay attention to the update time of 10 ms, i.e. make comparisons not to "=" but with ">" and "<".

6.5.4 Electrical data

**Input level**

- **Low level**: 0 - 3 V DC
- **High level**: 10 - 30 V DC
- **Typical current**: 5 mA
- **Maximum input frequency**: 20 kHz, duty factor 1:1, (required with the signal source as from 1 kHz push-pull driver)
6.5.5 CNT board, view from the front

6.5.6 Assignment of the signal connector

<p>| | | | | | | | | | |</p>
<table>
<thead>
<tr>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>A1</td>
<td>Counter 1 phase - A</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>2</td>
<td>B1</td>
<td>Counter 1 phase - B</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>3</td>
<td>A2</td>
<td>Counter 2 phase - A</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>4</td>
<td>B2</td>
<td>Counter 2 phase - B</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>5</td>
<td>A3</td>
<td>Counter 3 phase - A</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>6</td>
<td>B3</td>
<td>Counter 3 phase - B</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>7</td>
<td>A4</td>
<td>Counter 4 phase - A</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>8</td>
<td>B4</td>
<td>Counter 4 phase - B</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>9</td>
<td>GND</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
6.5.7 Addressing the counter board

Counter board

J3

CNT1 - CNT12

J3

CNT13 - CNT24

Counter input connector
6.5.8 Connection examples for the counter board

**Initiator plus-switching**

- +24VDC
- GND

**Initiator with push-pull output**

- +24VDC
- GND

**Incremental transducer**

- +24VDC
- Channel A
- Channel B
- GND
6.6 I/O Card

The I/O card is used as an option for the PAC-SC Compact and PAC-Single control. All other versions are already equipped with an I/O card as part of the standard equipment although expansions are also possible (see also chapter “Technical Appendix -> Basic Equipment”).

Refer to the Chapter „Technical Appendix -> I/O Card“ for a detailed description of the I/O card.“
7 Technical annex

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7.1 Error message of the PA-Control

7.1.1 Error messages in the automatic sequence and during manual traversing

<table>
<thead>
<tr>
<th>Error text:</th>
<th>Number:</th>
<th>Possible cause of error:</th>
</tr>
</thead>
<tbody>
<tr>
<td>Power section not ready</td>
<td>3</td>
<td>Power section not connected, power sections defective, motor not connected, rotation monitoring tripped, ...</td>
</tr>
<tr>
<td>Limit switch defective</td>
<td>4</td>
<td>Limit switch approached during positioning</td>
</tr>
<tr>
<td>Value too high</td>
<td>5</td>
<td>Value for speed higher than parameter value, Parameter value, value for indirect addressing greater than largest register number</td>
</tr>
<tr>
<td>Value too low</td>
<td>6</td>
<td>Value for speed less than parameter value, Parameter value, value for indirect addressing smaller than the smallest register number</td>
</tr>
<tr>
<td>Overflow, arithmetic operation</td>
<td>7</td>
<td>Numbers out of range</td>
</tr>
<tr>
<td>Program does not exist</td>
<td>8</td>
<td>Program does not exist in PA-CONTROL when subroutine is called</td>
</tr>
<tr>
<td>End of program does not exist</td>
<td>9</td>
<td>No END</td>
</tr>
<tr>
<td>Excessive nesting depth</td>
<td>A</td>
<td>Too many subroutines called</td>
</tr>
<tr>
<td>Limit switch not reached</td>
<td>B</td>
<td>Limit switch not reached during reference travel, limit switch damaged, limit switch not being actuated (mechanical fault), ...</td>
</tr>
<tr>
<td>Range transgression</td>
<td>C</td>
<td>Parameter value for the traversing range has been exceeded when positioning</td>
</tr>
<tr>
<td>Illegal instruction</td>
<td>D</td>
<td>Instruction unknown or illegal for this configuration</td>
</tr>
<tr>
<td>Positioning module defective</td>
<td>E</td>
<td>Hardware fault</td>
</tr>
<tr>
<td>No reference point</td>
<td>F</td>
<td>A positioning instruction has been called without prior reference travel or G25.0</td>
</tr>
<tr>
<td>No positioning module</td>
<td>-</td>
<td>Jumper for positioning module selection not set correctly on the CPU</td>
</tr>
<tr>
<td>Illegal axis selection</td>
<td>-</td>
<td>Axis name not enabled in system parameter (number of axes)</td>
</tr>
<tr>
<td>programme does not exist</td>
<td>-</td>
<td>subroutine isn’t stored after call in, subroutine name is written wrong, stop the parallel runoff as programme is not activ, start programme is not defined.</td>
</tr>
<tr>
<td>Error text:</td>
<td>Number:</td>
<td>Possible cause of error:</td>
</tr>
<tr>
<td>----------------------------------</td>
<td>---------</td>
<td>-----------------------------------------------------------------------------------------</td>
</tr>
<tr>
<td>to much runoff started</td>
<td>-</td>
<td>to much PAB programmes will be started through RUN</td>
</tr>
<tr>
<td>programme runs</td>
<td>-</td>
<td>PAB-programme is activ, is not possible to start twice</td>
</tr>
<tr>
<td>programme is in SLEEP</td>
<td>-</td>
<td>PAB-programme is already stopped with SLEEP</td>
</tr>
<tr>
<td>unknown command</td>
<td>-</td>
<td>Command is not allowed for this programme</td>
</tr>
<tr>
<td>PAB-module incorrect</td>
<td>-</td>
<td>communication between CPU and PAB is halted</td>
</tr>
<tr>
<td>G02/03 end point incorrect</td>
<td>-</td>
<td>end point is not at the segment of a circle, check coordinates</td>
</tr>
<tr>
<td>G02/03 radius is zero</td>
<td>-</td>
<td>wrong coordinates, check coordinates</td>
</tr>
<tr>
<td>1. ASi wrong configuration</td>
<td>-</td>
<td>Ist-configuration of the 1. Asi Masters is not the same like in the project</td>
</tr>
<tr>
<td>1. ASi distribution voltage missed</td>
<td>-</td>
<td>signal line 1. Asi Masters is not connected with power supply, power supply not ready.</td>
</tr>
<tr>
<td>1. ASi Slave 0</td>
<td>-</td>
<td>Slave with address 0 at the 1. AS-1 lane, addressing is not made.</td>
</tr>
<tr>
<td>2. ASi configuration wrong</td>
<td>-</td>
<td>Ist-configuration of the 2. AS-1 Masters is not the same like the project</td>
</tr>
<tr>
<td>2. ASi distribution voltage missed</td>
<td>-</td>
<td>signal line 2. AS-i Master is not connected with the power supply, power supply is not ready.</td>
</tr>
<tr>
<td>2. ASi Slave 0 existing</td>
<td>-</td>
<td>Slave with address 0 at 2. AS-i lane, addressing is not made.</td>
</tr>
<tr>
<td>3. ASi configuration wrong</td>
<td>-</td>
<td>Ist-configuration of the 3. AS-i Masters is not the same like the project</td>
</tr>
<tr>
<td>3. ASi configuration missed</td>
<td>-</td>
<td>signal line 3. AS-i Master is not connected with the power supply, power supply not ready</td>
</tr>
<tr>
<td>3. ASi Slave 0 existing</td>
<td>-</td>
<td>Slave with address 0 at 3. AS-i lane, addressing is not made.</td>
</tr>
<tr>
<td>Interbus-S access not ok</td>
<td>-</td>
<td>communication through interbus-s unpossible</td>
</tr>
<tr>
<td>Emergency-stop from Interbus-S</td>
<td>-</td>
<td>Emergency-stop from interbus activated.(Master datas WORT 3 = 00 00hex)</td>
</tr>
<tr>
<td>Transfer target not found, G421</td>
<td>-</td>
<td>time monitoring expired during a subroutine is still open. Time monitoring does not find the defined jump mark.</td>
</tr>
</tbody>
</table>
### 7.1.2 In the automatic sequence and with manual shift (with position controller)

<table>
<thead>
<tr>
<th>Error text:</th>
<th>Description / Explanation:</th>
</tr>
</thead>
<tbody>
<tr>
<td>150 LR bus error</td>
<td>System error on the position controller</td>
</tr>
<tr>
<td>151 LR supply</td>
<td>Undervoltage recognition on the LR board, check 5V power supply unit to the system</td>
</tr>
<tr>
<td>152 LR interrupt</td>
<td>LR was incorrectly addressed by CPU3</td>
</tr>
<tr>
<td>153 LR emergency stop</td>
<td>Several errors simultaneously</td>
</tr>
<tr>
<td>155 LR machine data invalid</td>
<td>Check parameters</td>
</tr>
<tr>
<td>156 LR operating mode invalid</td>
<td>Problems with G2xx commands</td>
</tr>
<tr>
<td>157 LR pos. data invalid</td>
<td>Invalid data was transfered with Xnn, FXn or G100.n</td>
</tr>
<tr>
<td>158 LR limit switch active</td>
<td>Limit switch is overchived</td>
</tr>
<tr>
<td>159 LR software limit switch</td>
<td>LR outside the defined range</td>
</tr>
<tr>
<td>162 LR zero pulse/cam missing</td>
<td>Zero pulse was found within the definitions during the reference travel:</td>
</tr>
<tr>
<td></td>
<td>- Range too small (max. 1.1 rev)</td>
</tr>
<tr>
<td></td>
<td>- Adjustment of the zero pulse referred to the limit switch axis critical, pulse should be in the range 1/4U&lt;zero pulse &gt; 3/4U</td>
</tr>
<tr>
<td>169 LR V_curr.&gt;Vmax</td>
<td>The maximum permissible speed was exceeded</td>
</tr>
<tr>
<td>182 LR control deviation (overflow regulation)</td>
<td>Drive cannot follow setpoint position stipulations. Acceleration or control parameters possible too great (not optimized)</td>
</tr>
</tbody>
</table>
### 7.1.3 Error messages in the program editor during the syn. check

<table>
<thead>
<tr>
<th>Error text</th>
<th>Description/Explanation</th>
</tr>
</thead>
<tbody>
<tr>
<td>Illegal axis name</td>
<td>Axis name lies outside the range permitted in system parameter Number of axes</td>
</tr>
<tr>
<td>Instruction not known</td>
<td>Incorrect character</td>
</tr>
<tr>
<td>Instruction not possible</td>
<td>This instruction is not possible in this program type or with this configuration</td>
</tr>
<tr>
<td>CASE instruction, incorrect character</td>
<td>Incorrect characters in the CASE statement</td>
</tr>
<tr>
<td>CASE instruction, no Else branch</td>
<td>CASE statement has not been terminated with the ELSE instruction</td>
</tr>
<tr>
<td>CASE instruction, no open</td>
<td>Instructions of a CASE statement have been found with no CASE open (e.g.: CASE.JMP.N4)</td>
</tr>
<tr>
<td>Input instruction expected</td>
<td>An input instruction must follow in this instruction at this point</td>
</tr>
<tr>
<td>No end instruction in program</td>
<td>The program is not terminated with an &quot;END&quot;</td>
</tr>
<tr>
<td>Integer expected</td>
<td>An integer must follow in this instruction at this point</td>
</tr>
<tr>
<td>Identical axes names expected</td>
<td>Identical axes names must follow in this instruction</td>
</tr>
<tr>
<td>No subsequent instruction in this line</td>
<td>There may be no further instruction in this program line after this instruction</td>
</tr>
<tr>
<td>Status invalid</td>
<td>Only status '0' or status '1' are permitted when assigning or scanning inputs, flags or outputs</td>
</tr>
<tr>
<td>Blank expected</td>
<td>A blank must follow at this point in this instruction (or instruction strings)</td>
</tr>
<tr>
<td>N expected</td>
<td>An 'N' must follow at this point in this instruction</td>
</tr>
<tr>
<td>Name expected</td>
<td>A valid name (program or jump label) must follow in this instruction at this point</td>
</tr>
<tr>
<td>Positive number expected</td>
<td>A positive number must follow in this instruction at this point</td>
</tr>
<tr>
<td>Program write-protected</td>
<td>The program has the write-protected attribute and cannot be modified (cancel write-protected attribute)</td>
</tr>
<tr>
<td>Period expected</td>
<td>There must a period in this instruction at this point</td>
</tr>
<tr>
<td>Checksum error</td>
<td>A checksum error has been established when loading the program into the program editor. The program cannot be loaded correctly and must be deleted</td>
</tr>
<tr>
<td>R expected</td>
<td>There must an &quot;R&quot; for register in this instruction at this point</td>
</tr>
<tr>
<td>Error text:</td>
<td>Description/Explanation:</td>
</tr>
<tr>
<td>-------------------------------</td>
<td>------------------------------------------------------------------------------------------</td>
</tr>
<tr>
<td>R, I, O or M expected</td>
<td>There must be an 'R', 'I', 'O' or 'M' in this instruction at this point</td>
</tr>
<tr>
<td>Real number expected</td>
<td>There must be a real number in this instruction at this point, but this real number may not exceed the range in the parameter value</td>
</tr>
<tr>
<td>Double jump label</td>
<td>This jump label occurs several times in this program</td>
</tr>
<tr>
<td>Jump label not first character</td>
<td>The jump label must be at the first position of a program line</td>
</tr>
<tr>
<td>Jump label not found</td>
<td>This jump label does not exist in this program</td>
</tr>
<tr>
<td>Number out of range</td>
<td>The number lies outside of the scheduled range (parameter value, maximum numerical value limit)</td>
</tr>
<tr>
<td>Number expected</td>
<td>There must be a number in this instruction at this point</td>
</tr>
<tr>
<td>Line too long</td>
<td>The program line may not be longer than 35 characters</td>
</tr>
</tbody>
</table>
### 7.1.4 Status messages from the operating system

The operating system may output the following messages "SE=n". The error message can be reset only by switching the unit off.

<table>
<thead>
<tr>
<th>Error type</th>
<th>n = Error No.:</th>
<th>Cause of error</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bus error</td>
<td>2</td>
<td>Address does not respond during asynchronous access</td>
</tr>
<tr>
<td>Address error</td>
<td>3</td>
<td>Access to odd addresses may occur during arithmetic operations</td>
</tr>
<tr>
<td>Illegal instruction</td>
<td>4</td>
<td>Defective EPROM or problem relating to subroutine return</td>
</tr>
<tr>
<td>Division by 0</td>
<td>5</td>
<td>Register values out of range</td>
</tr>
<tr>
<td>CHK</td>
<td>6</td>
<td>Not in PA-CONTROL</td>
</tr>
<tr>
<td>Trapv</td>
<td>7</td>
<td>Not in PA-CONTROL</td>
</tr>
<tr>
<td>PRIV</td>
<td>8</td>
<td>Not in PA-CONTROL</td>
</tr>
<tr>
<td>Trace</td>
<td>9</td>
<td>Not in PA-CONTROL</td>
</tr>
<tr>
<td>Instruction not implemented</td>
<td>A-D</td>
<td>May occur as a consequence of error number 3</td>
</tr>
<tr>
<td>Illegal format</td>
<td>E</td>
<td>Not in PA-CONTROL</td>
</tr>
<tr>
<td>Interrupt not initialized</td>
<td>F</td>
<td>Not in PA-CONTROL</td>
</tr>
<tr>
<td>Interrupt error</td>
<td>G</td>
<td>Not in PA-CONTROL</td>
</tr>
<tr>
<td>Autovector not initialized</td>
<td>H-N</td>
<td>Not in PA-CONTROL</td>
</tr>
<tr>
<td>Non-autovector not initialized</td>
<td>O</td>
<td>Not in PA-CONTROL</td>
</tr>
</tbody>
</table>
7.2 Basic equipment, PA-Control Servo

A basic equipment variant of the PA-Control Servo (rear view shown here) consists of the following components:

<table>
<thead>
<tr>
<th>for 1 axis (see Figure 19&quot;/2 – Width):</th>
<th>for 2 axis (see Figure 19&quot; – Width):</th>
</tr>
</thead>
<tbody>
<tr>
<td>- 1 Power supply unit board (NT)</td>
<td>- 1 Power supply unit board (NT)</td>
</tr>
<tr>
<td>- 1 I/O board</td>
<td>- 1 I/O board</td>
</tr>
<tr>
<td>- 1 LR11 board</td>
<td>- 1 LR12 board</td>
</tr>
<tr>
<td>- 1 CPU3 board</td>
<td>- 1 CPU3 board</td>
</tr>
<tr>
<td>- 6 free plug-in stations</td>
<td>- 5 free plug-in stations</td>
</tr>
</tbody>
</table>

The free plug-in stations are available for additional I/O boards and other options (see Section "Options") for further details.

The PA-CONTROL Servo is available in two different widths, 19"/2 and 19" width.
7.3 CPU 3 - Board

Important:

The guaranteed battery service life is 5 years. The battery should be renewed within this period in order to avoid data loss (replacement CPU from IEF Werner).

PA-CONTROL type setting:

Jumper: 1 = Jumper inserted,
0 = Jumper not inserted

<table>
<thead>
<tr>
<th>PA-Control Typ</th>
<th>J 7</th>
<th>J 8</th>
<th>J 9</th>
<th>J 10</th>
</tr>
</thead>
<tbody>
<tr>
<td>PAC-Step</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>PAC-Step with PAB</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>PAC-Compact with PLS4</td>
<td>1</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>PAC / PAC-Compact with PLS 5</td>
<td>0</td>
<td>1</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>PAC / PAC-Compact with PLS 6</td>
<td>1</td>
<td>1</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>PAC / PAC-Compact with PLS 5 and PAB</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>PAC / PAC-Compact with PLS 6 and PAB</td>
<td>1</td>
<td>1</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>PAC-Servo (with Lageregler)</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>PAC-Servo with PAB</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
</tr>
</tbody>
</table>

From the software versions 3.20 upwards the RS485 channel at interface 2 can be used as an alternative to the RS232 channel (see also Chapter 3 “Text and Value Output via Current Data Channel”). For this purpose remove the jumper J12 on the CPU 3 and insert on J11.
The RS485 signals are at Pin8 = B and at Pin9 = A. After running through the switch-on function of the PAC the transmitter operates at high resistance. Programming example for the coupling of several PACs according to the master-slave-principle can be found on the disk.

All used PACs must be equipped at least with the system software 3.20.
7.3.1 Connector pin assignment, serial interface 1 (top)

X7.1

<table>
<thead>
<tr>
<th>Pin</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>Not used</td>
</tr>
<tr>
<td>2</td>
<td>Transmit Data</td>
</tr>
<tr>
<td>3</td>
<td>Receive Data</td>
</tr>
<tr>
<td>4</td>
<td>Ready to send</td>
</tr>
<tr>
<td>5</td>
<td>Clear to send</td>
</tr>
<tr>
<td>6</td>
<td>Not used</td>
</tr>
<tr>
<td>7</td>
<td>Ground</td>
</tr>
<tr>
<td>8</td>
<td>Not used</td>
</tr>
<tr>
<td>9</td>
<td>Not used</td>
</tr>
</tbody>
</table>

Sub-D 9-pin, socket

Important:

Assignment does not correspond to standard RS232!

Example:

Connection cable between PA and PC (COM1 or COM2):

<table>
<thead>
<tr>
<th>PAC</th>
<th>PC (25-polig)</th>
<th>PC (9-polig)</th>
</tr>
</thead>
<tbody>
<tr>
<td>TXD(2)</td>
<td>RXD(3)</td>
<td>RXD(2)</td>
</tr>
<tr>
<td>RXD(3)</td>
<td>TXD(2)</td>
<td>TXD(3)</td>
</tr>
<tr>
<td>GND(7)</td>
<td>GND(7)</td>
<td>GND(5)</td>
</tr>
</tbody>
</table>

7.3.2 Connector serial interface 2 (bottom)

X7.2

<table>
<thead>
<tr>
<th>Pin</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>Not used</td>
</tr>
<tr>
<td>2</td>
<td>Transmit Data</td>
</tr>
<tr>
<td>3</td>
<td>Receive Data</td>
</tr>
<tr>
<td>4</td>
<td>Ready to send</td>
</tr>
<tr>
<td>5</td>
<td>Clear to send</td>
</tr>
<tr>
<td>6</td>
<td>Internally occupied</td>
</tr>
<tr>
<td>7</td>
<td>Ground</td>
</tr>
<tr>
<td>8</td>
<td>Internally occupied (until V3.20 RS485 B)*</td>
</tr>
<tr>
<td>9</td>
<td>Internally occupied (until V3.20 RS485 A)*</td>
</tr>
</tbody>
</table>

Important:

Assignment does not correspond to standard RS232!

*) From the software version 3.20 upwards optional RS232/RS485, depending on the position of the jumper J11 and J12 (see Chapter „Technical Appendix - CPU 3 Card“ and chapter „3 Commands, 3.38 Text and Value Output via Current Data Channel“).
7.4 I/O board 16/16

7.4.1 I/O board addressing

Fuses for Outputs 1 - 16
### Connector pin assignment I/O board

<table>
<thead>
<tr>
<th>Sub-D 37-pin socket</th>
<th>1</th>
<th>2</th>
<th>3</th>
<th>4</th>
<th>5</th>
<th>6</th>
<th>7</th>
<th>8</th>
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</tbody>
</table>

**Signal input:**
- Opto-decoupled
- 24VDC
- Typical input current 5mA
- Low level 0 - 3VDC
- High level 10 - 30VDC

**Signal output:**
- Opto-decoupled
- Positiv switching
- 24VDC / 0,5A (ohmic load)
- Max. 2A per board
7.4.3 Connection example

I/O-16/16

24VDC/IN

Input 1

Input 4

Output 1

Output 2

GND

24VDC

BILD0111E
7.5 Positioning controller board LR11 / LR12

7.5.1 Positioning controller board LR11 (for one axis)

7.5.2 Positioning controller board LR12 (for two axis)
### 7.5.3 Jumper assignment J3

Particular motor axis designations which are shown in the table below are obtained for the LR11 and LR12 in accordance with the jumper assignments.

**Jumper:**
- 1 = Jumper connected
- 0 = Jumper not connected

<table>
<thead>
<tr>
<th>MR</th>
<th>S0</th>
<th>S1</th>
<th>S2</th>
<th>LR11</th>
<th>LR12</th>
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<tr>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>X-axis</td>
<td>X-axis, Y-axis</td>
</tr>
<tr>
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<td>1</td>
<td>0</td>
<td>0</td>
<td>Z-axis</td>
<td>Z-axis, U-axis</td>
</tr>
<tr>
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<td>1</td>
<td>0</td>
<td>V-axis</td>
<td>V-axis, W-axis</td>
</tr>
</tbody>
</table>

**Please note:**

When the controller is fitted with the position controller boards, keep to the sequence X, Y, Z, U, V and W when selecting the axes. It is not possible to operate a controller with only a Z or a Z and U axis.

The following tables are obtained:

<table>
<thead>
<tr>
<th>Number of axis</th>
<th>Axis designation</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>X</td>
</tr>
<tr>
<td>2</td>
<td>X, Y</td>
</tr>
<tr>
<td>3</td>
<td>X, Y, Z</td>
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<tr>
<td>4</td>
<td>X, Y, Z, U</td>
</tr>
<tr>
<td>5</td>
<td>X, Y, Z, U, V</td>
</tr>
<tr>
<td>6</td>
<td>X, Y, Z, U, V, W</td>
</tr>
</tbody>
</table>
7.5.4 Connector assignment

DA output

X8 / X8.1 / X8.2

1  +24V - IN
2 „Ready“ input of the output stage - IN
3  not occupied
4  not occupied
5  GND (of the an. setp. value)
6  GND (of the 24V voltage) - IN
7 release sign. for control (+24V) - OUT
8  not occupied
9  an. setp. value (Defin. +/- 10V) for controller

Limit switch

X3 / X3.1 / X3.2

1  +24VDC (internally connected with PIN1 of X8.1 or X8.2)
2  Limit switch -
3  Additional reference switch
4  not occupied
5  not occupied
6  GND (of +24VDC)
7  Limit switch +
8  not occupied
9  not occupied

Incremental encoder

X9 / X9.1 / X9.2

1  Chan. A
2  +5VDC-OUT for encod.
3  Chan. B (negated)
4  Chan. C (reference sig.)
5  GND (+5VDC) – OUT for encod.
6  Chan. A (negated)
7  Chan. B
8  not occupied
9  Chan. C (negated)
7.6 NT1-5V power supply for μP-System

The following status signals can appear on the 7-segment status display:

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<thead>
<tr>
<th>Number</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Initial position, Control is waiting for start</td>
</tr>
<tr>
<td>1</td>
<td>Automatic programme is running</td>
</tr>
<tr>
<td>2</td>
<td>Automatic, stop recognized, continue with start</td>
</tr>
</tbody>
</table>

=> All the following numbers denote faults, see Chapter: Fault Signals of the PA-CONTROL
   In automatic mode and when moved manually
7.7 Connection between the PC and the PAC

The connection between the PC and the unit of a PA-CONTROL range is necessary, for example when using the program development system PROPAC. The data exchange and the transfer of programs and parameters (in both directions) is via a serial interface. The PC must therefore be equipped with this interface (COM1 or COM2). The units of the PA-CONTROL range are prepared as standard for this task.

The cable used must meet the following conditions:

<table>
<thead>
<tr>
<th>PA-Control (socket = interface)</th>
<th>PC (9-pole or 25-pole)</th>
</tr>
</thead>
<tbody>
<tr>
<td>(9-pole, Sub-D)</td>
<td>(9-pole, Sub-D) / 25-pole, Sub-D</td>
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<tr>
<td>TXD (2)</td>
<td>RXD (2) / RXD (3)</td>
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<tr>
<td>RXD (3)</td>
<td>TXD (3) / TXD (2)</td>
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<tr>
<td>GND (7)</td>
<td>GND (5) / GND (7)</td>
</tr>
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</table>

Please note:

Assignment does not correspond to standard RS232!
### 7.8 PAC-keycode (+extended ASCII-character set)

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<th>Sign</th>
<th>PAC Keyboard</th>
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<td>329</td>
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<tr>
<td>333</td>
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<td>335</td>
<td>14F</td>
<td>Shift+Arrow right</td>
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<td>336</td>
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<td>337</td>
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<td>338</td>
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<td>153</td>
<td>DEL / Alt+DEL</td>
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<td>371</td>
<td>173</td>
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<td>372</td>
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<td>Ctrl+ Arrow right</td>
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<td>397</td>
<td>18D</td>
<td>Ctrl+DEL</td>
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7.9 Servicing

7.9.1 Exchanging the battery on the CPU board:

The fitted battery has a guaranteed service life of 5 years. The battery should be renewed before this period expires in order to prevent data loss.

Procedure:
- Procure a replacement CPU board from IEF Werner (new battery)
- Back up your data with PROPAC on PC (programs and parameters)
- Switch off the unit and disconnect the mains plug
- Exchange the CPU board
- Load the default parameters in the unit when switching on
- Transfer the programs and parameters with PROPAC from PC

7.10 Pro - Demo

Example programs for the PA-Control controls:

The demonstration diskette with the examples is included with all PA-CONTROL operating instructions.
Please refer to the directory on the diskette for the list of demonstration programs.

7.11 Accessory list

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<tr>
<th>Order number</th>
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<td>Original version PROPAC (3,5&quot; &amp; 5,25&quot; Disk) including manual</td>
<td>#230850</td>
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<td>Connection cable PC-XT for the PA (length 3m)</td>
<td>#230929</td>
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<tr>
<td>Connection cable PC-AT for the PA (length 3m)</td>
<td>#230920</td>
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