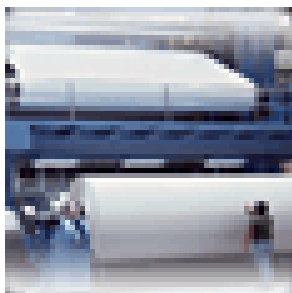


Rockwell Automation Application Content

Rockwell Automation Robotics Libraries



Reference Manual

Set Feedrate - Robot

raM_Robot_Opr_Feedrate

V2.0

January, 2024

Important User Information

Solid-state equipment has operational characteristics differing from those of electromechanical equipment. Safety Guidelines for the Application, Installation and Maintenance of Solid State Controls (publication SGI-1.1 available from your local Rockwell Automation sales office or online at <http://literature.rockwellautomation.com>) describes some important differences between solid-state equipment and hard-wired electromechanical devices. Because of this difference, and because of the wide variety of uses for solid-state equipment, all persons responsible for applying this equipment must satisfy themselves that each intended application of this equipment is acceptable.

In no event will Rockwell Automation, Inc. be responsible or liable for indirect or consequential damages resulting from the use or application of this equipment.

The examples and diagrams in this manual are included solely for illustrative purposes. Because of the many variables and requirements associated with any particular installation, Rockwell Automation, Inc. cannot assume responsibility or liability for actual use based on the examples and diagrams.

No patent liability is assumed by Rockwell Automation, Inc. with respect to use of information, circuits, equipment, or software described in this manual.

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Throughout this manual, when necessary, we use notes to make you aware of safety considerations.

WARNING



Identifies information about practices or circumstances that can cause an explosion in a hazardous environment, which may lead to personal injury or death, property damage, or economic loss.

IMPORTANT

Identifies information that is critical for successful application and understanding of the product.

ATTENTION



Identifies information about practices or circumstances or death, property damage, or economic loss. Attentions avoid a hazard, and recognize the consequence.

SHOCK HAZARD



Labels may be on or inside the equipment, that dangerous voltage may be present.

BURN HAZARD



Labels may be on or inside the equipment, for example, a drive or motor, to alert people that surfaces may reach dangerous temperatures.

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1 Overview

raM_Robot_Opr_Feedrate:

- Sets the feedrate for a robot. This instruction executes immediately and affects the rate of the path planning.

Use when:

- Using a Device Handler for Robot Management

Do NOT use when:

- Not using a Device Handler for Robot Management

1.1 Prerequisites

- Device Handler for Robot
 - Rockwell Automation Robotics Libraries v2.0 →
- Studio 5000 – Logix Designer
 - v35.0 →
- Studio 5000 – Application Code Manager
 - v4.03.00 →

Sets a feedrate for the robot path master

raM_Robot_Opr_Feedrate			
raM_Robot_Opr_Feedra...	InstanceName	Sts_ERR	0
Ref_Handle	\RobotName_DH.Hndlr	Sts_MtdID	49042
Cfg_FeedRate	0.0		
Cfg_ChangeTime	0.0		

Method Instance ID

Instruction Backing Tag

Data Handle

Desired feed rate of Robot Master

Duration to accel/decel path master

(Sts_EO)

(Sts_EN)

(Sts_ER)

(Sts_IP)

(Sts_PC)

Note: Status bits not shown on the output side of the instruction are not used and will not exist in the instruction backing tag.

5

1.3 Execution

- Level

1.3.1 Overview

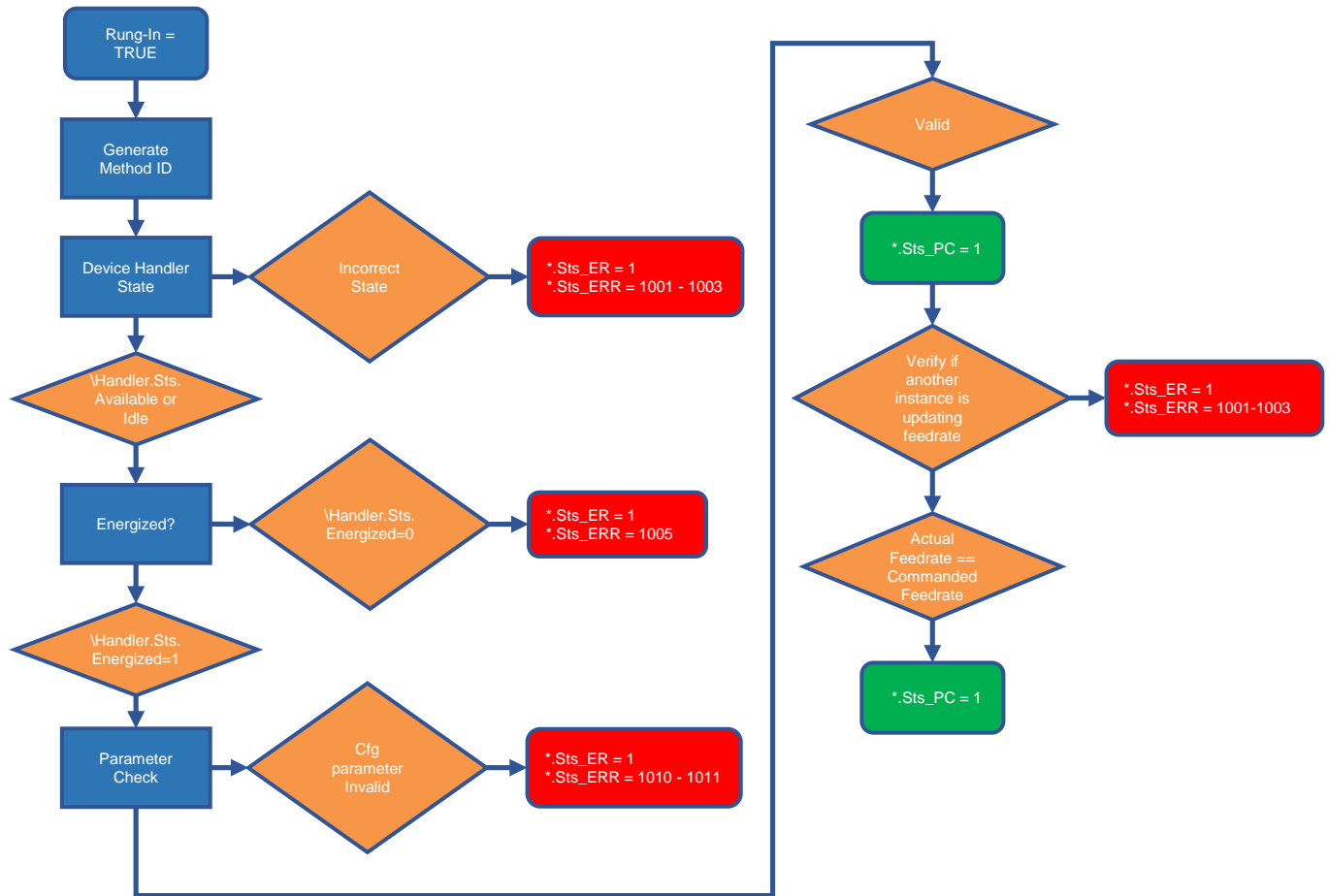
Rung in condition transition response:

- False → True
 - Initialization
 - *.Sts_EO = 0
 - *.Sts_ER = 0
 - *.Sts_PC = 0
 - *.Sts_IP = 0
 - Running
 - *.Sts_EO = 1
 - *.Sts_EN = 1
 - *.Sts_IP = 1
 - Operation
 - IF: Method completes
 - THEN: *.Sts_PC = 1 and *.Sts_IP = 0
 - IF: Error
 - THEN: *.Sts_IP = 0 and *.Sts_PC = 0 and *.Sts_ER = 1
- True → False
 - *.Sts_EO = 0
 - *.Sts_EN = 0
 - *.Sts_IP = 0
 - IF: Error
 - THEN: *.Sts_ER = 1

1.3.2 Affected Device Handler Status

Status	Value
*.Sts.FeedrateActual	0...125 %
*.Sts.FeedrateSetpoint	0...125 %
*.fFeedrateSetpoint	
*.fLoadProtectionFeedrateTarget	100.0
*.fFeedrateChangeTime	Cfg_ChangeTime
*.bStartPathMaster	1

1.3.3 Execution Table



2 Instruction

2.1 Input Data

Input	Function / Description	DataType
Ref_Handle	Device Handler Data Structure	raM_UDT_Robot_Dvc_DataHndl
Cfg_FeedRate	Set feed rate of the path master [0.0..125.0 %]	REAL
Cfg_ChangeTime	Duration to accelerate or decelerate the path master [seconds]	REAL

2.2 Output Data

Output	Function / Description	DataType
Sts_EO	Instruction has enabled the rung output. Provides a visible indicator of the EnableOut system parameter for use during ladder instantiation	BOOL
Sts_EN	Instruction is Being Scanned - Rung In Condition = TRUE	BOOL
Sts_ER	Instruction is in Error - See Sts_ERR / Sts_EXERR for Additional Error Information	BOOL
Sts_ERR	Instruction Error Code - See Instruction Help for Code Definition	DINT
Sts_EXERR	Instruction Extended Error Code - See Instruction Help for Code Definition	DINT
Sts_MtdID	Method ID	DINT
Sts_IP	Instruction is 'In Process'	BOOL
Sts_PC	Instruction Process is Complete	BOOL

2.3 Error Codes

Sts_ERR	Description
0	No errors present
1001	Device Handler is not in a running state. Commands to the device cannot be processed.
1002	Device Handler is faulted. Clear faults to apply commands
1003	Device Handler is not in a supported state.
1005	Robot is not energized
1006	Transform has not been enabled, cannot start robot master
1010	Feedrate out of range 0.0..125.0
1011	Change time out of range >0.0
1012	Concurrent feed rate command send during execution
1013	Stop on Path command during execution
1014	Master is not started in configured acceleration/deceleration time

3 Application Code Manager

3.1 Definition Object: raM_Robot_Opr_Feedrate

This object contains the AOI definition and used as linked library to implement object. This gives flexibility to choose to instantiate only definition and create custom implement code. User may also create their own implement library and link with this definition library object.

3.2 Implementation Object: raM_LD_Robot_Feedrate

Implementation Language: Ladder

Content Type: Routine

This implement contains only a rung with an instance of the raM_Robot_Opr_Feedrate object.

Parameter Name	Default Value	Instance Name	Definition	Description
RoutineName	_{ObjectName}	{RoutineName}	Routine	Name of the routine where the object will be placed
TagName	{ObjectName}	{TagName}	Tag	Instruction backing tag
StartBitTagName	Cmd_{ObjectName}		Local Tag	Tag name for start command enabling bit

Linked Library

Link Name	Catalog Number	Revision	Solution	Category
RobotHandler	raM_Robot_Dvc_DeviceHandler	2	(RA-LIB) Robotics	Robot Handler
raM_Robot_Opr_Feedrate	raM_Robot_Opr_Feedrate	2	(RA-LIB) Robotics	Asset-Control

3.3 Attachments

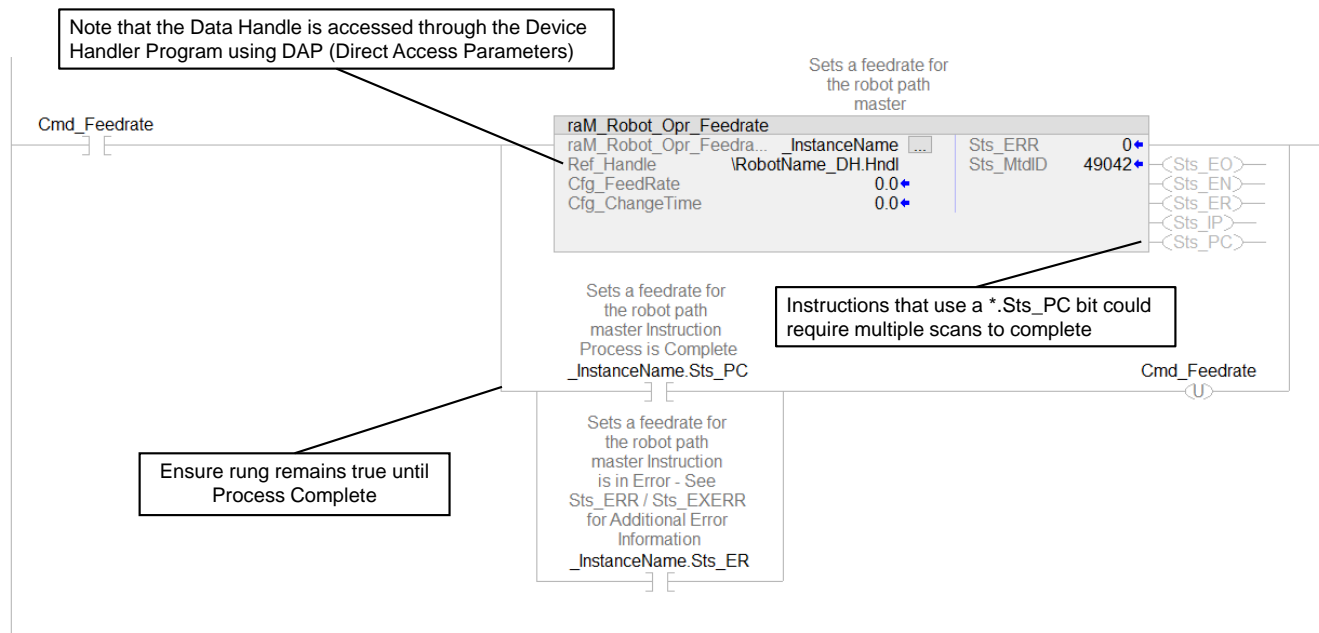
Name	Description	File Name	Extraction path
V2_{LibraryName}	Reference Manual	RM-{LibraryName}.pdf	{ProjectName}\Documentation

4 Application

4.1 Using raM_Robot_Opr_Feedrate

Applies a feedrate for the robot path planner. The feedrate is applied to the robot master and can speed up, slow down, or stop a robot on path.

Note that the Load Protection may reduce the overall feedrate of the system and cause this instruction to not achieve its setpoint. If Load Protection is reducing the maximum capable feedrate, the instruction will still set the Sts_PC bit and complete even then the setpoint was not reached.



5 Appendix

General

This document provides a programmer with details on this OEM Building Block instruction for a Logix-based controller. You should already be familiar with how the Logix-based controller stores and processes data.

Novice programmers should read all the details about an instruction before using the instruction. Experienced programmers can refer to the instruction information to verify details.

IMPORTANT

This OEM Building Block Instruction includes an Add-On Instruction for use with Version 24 or later of Studio 5000 Logix Designer.

Common Information for All Instructions

Rockwell Automation Building Blocks contain many common attributes or objects. Refer to the following reference materials for more information:

- Foundations of Modular Programming, **IA-RM001C-EN-P**

Conventions and Related Terms

Data - Set and Clear

This manual uses set and clear to define the status of bits (Booleans) and values (non-Booleans):

This Term:	Means:
Set	The bit is set to 1 (ON) A value is set to any non-zero number
Clear	The bit is cleared to 0 (OFF) All the bits in a value are cleared to 0

Signal Processing - Edge and Level

This manual uses Edge and Level to describe how bit (BOOL) Commands, Settings, Configurations and Inputs to this instruction are sent by other logic and processed by this instruction.

Send/Receive Method:	Description:
Edge	<ul style="list-style-type: none">Action is triggered by "rising edge" transition of input (0-1)Separate inputs are provided for complementary functions (such as "enable" and "disable")Sending logic SETS the bit (writes a 1) to initiate the action; this instruction CLEARS the bit (to 0) immediately, then acts on the request if possibleLD: use conditioned OTL (Latch) to sendST: use conditional assignment [if (condition) then bit:=1;] to sendFBD: OREF writes a 1 or 0 every scan, should use Level, not Edge <p>Edge triggering allows multiple senders per Command, Setting, Configuration or Input (many-to-one relationship)</p> <input type="checkbox"/>
Level	<ul style="list-style-type: none">Action ("enable") is triggered by input being at a level (in a state, usually 1)Opposite action ("disable") is triggered by input being in opposite state (0)Sending logic SETS the bit (writes a 1) or CLEARS the bit (writes a 0); this instruction does not change the bitLD: use OTE (Energize) to sendST: use unconditional assignment [bit:= expression_resulting_in_1_or_0;] or "if-then-else" logic [if (condition) then bit:= 1; else bit:= 0;]FBD: use OREF to the input bit <p>Level triggering allows only one sender can drive each Level</p>

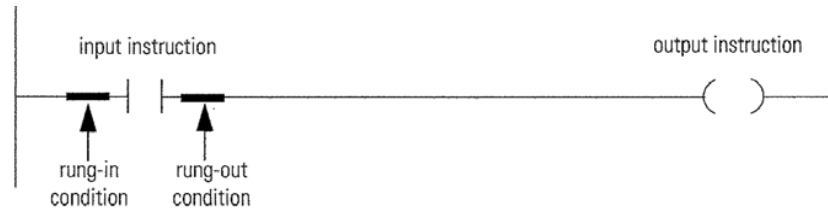
Instruction Execution - Edge and Continuous

This manual uses Edge and Continuous to describe how an instruction is designed to be executed.

Method:	Description:
Edge	<ul style="list-style-type: none">• Instruction Action is triggered by "rising edge" transition of the rung-in-condition
□	
Continuous	<ul style="list-style-type: none">• Instruction Action is triggered by input being at a level (in a state, usually 1)• Opposite action is triggered by input being in opposite state (0)• Instructions designed for continuous execution should typically be used on rungs without input conditions present allowing the instruction to be continuously scanned

Relay Ladder Rung Condition

The controller evaluates ladder instructions based on the rung condition preceding the instruction (rung-in condition). Based on the rung-in condition and the instruction, the controller sets the rung condition following the instruction (rung-out condition), which in turn, affects any subsequent instruction.



If the rung-in condition to an input instruction is true, the controller evaluates the instruction and sets the rung-out condition based on the results of the instruction. If the instruction evaluates to true, the rung-out condition is true; if the instruction evaluates to false, the rung-out condition is false.

IMPORTANT

The rung-in condition is reflected in the EnableIn parameter and determines how the system performs each Add-On Instruction. If the EnableIn signal is TRUE, the system performs the instruction's main logic routine. Conversely, if the EnableIn signal is FALSE, the system performs the instruction's EnableInFalse routine.

The instruction's main logic routine sets/clears the EnableOut parameter, which then determines the rung-out condition. The EnableInFalse routine cannot set the EnableOut parameter. If the rung-in condition is FALSE, then the EnableOut parameter and the rung-out condition will also be FALSE.

Pre-scan

On transition into RUN, the controller performs a pre-scan before the first scan. Pre-scan is a special scan of all routines in the controller. The controller scans all main routines and subroutines during pre-scan, but ignores jumps that could skip the execution of instructions. The controller performs all FOR loops and subroutine calls. If a subroutine is called more than once, it is performed each time it is called. The controller uses pre-scan of relay ladder instructions to reset non-retentive I/O and internal values.

During pre-scan, input values are not current and outputs are not written. The following conditions generate pre-scan:

- Transition from Program to Run mode.
- Automatically enter Run mode from a power-up condition.

Pre-scan does not occur for a program when:

- Program becomes scheduled while the controller is running.
- Program is unscheduled when the controller enters Run mode.

IMPORTANT

The Pre-scan process performs the Process Add-On Instruction's logic routine as FALSE and then performs its Pre-scan routine as TRUE.
