



Эта страница пока что не переведена полностью. Пожалуйста, помогите завершить перевод.

(Сотрите это сообщение по окончании перевода.)

Примеры использования PLC

- [Управление шпинделем, подключенным через PULSE-DIR](#)
- [Работа с расширителями портов Modbus через Hardware PLC](#)
- [M07 Mist Coolant ON](#)
- [M03 Simple Spindle ON procedure](#)
- [Getting a Height Map](#)

Spindle Speed control for DAC

[SPN.plc](#)

```
#define command      var00
#define parameter    var01
//set Spindle speed control via DAC channel #1
//Spindle Speed is given in **eparam** register

main()
{
    value=eparam;
    if (value>0xFFFF) {value=0xFFFF;};
    //fix if given value is out of range 0...0xffff
    if (value<0) {value=0;};

    dac01=value;    //setup DAC value

    /**Set Spindle Speed** is asynchronous operation.
    //It's better to inform myCNC Software New Spindle Speed applied.
    //Send information about new Spindle Speed to myCNC Software
    message=PLCCMD_REPLY_TO_MYCNC;
    //Command code to send to myCNC software
    command=PLC_MESSAGE_SPINDLE_SPEED_CHANGED;
    //Message code
    parameter=eparam;    //New Spindle Speed information
    timeout=timer+10; do { timer++; } while (timer<timeout);
    //Delay to push the Message to myCNC Software

    gvarset(7371,eparam);
    //myCNC register #7371 contains actual Spindle Speed.
    //Another way to inform myCNC software about new Spindle Speed
    //(to display on it DRO for example)

    exit(99);    //normal exit.
```

```
};
```

Spindle Speed control for ET10_DAC

SPN.plc

```
#define command    var00
#define parameter  var01
//set Spindle speed control via ET10 DAC channel #1
//Spindle Speed is given in **eparam** register

main()
{
    command=0x32;
    //EXT_ET10_DAC_OFFSET; set ADC offset register address
    parameter=0x800-(eparam/2)+(1<<12);
    //0x800 - is the middle of 12bits range - represents 0V
    //Eparam contains 12bits DAC value in 0V range, ET10 DAC setup in
    +10V...-10V range, so need to /2
    //Encoder channel number is given in high 12 bits of 16bit word.

    message=PLCCMD_SET_CNC_EXTVAR;
    //setup Message register with command for access to [[External CNC
    Variables]]
    textit=timer+2;do{timer++;}while(timer<textit);
    //2ms delay to push the command from PLC to myCNC Core

    /**Set Spindle Speed** is asynchronous operation.
    //It's better to inform myCNC Software New Spindle Speed applied.
    //Send information about new Spindle Speed to myCNC Software
    message=PLCCMD_REPLY_TO_MYCNC;           //Command code to
    send to myCNC software
    command=PLC_MESSAGE_SPINDLE_SPEED_CHANGED; //Message code
    parameter=eparam;                         //New Spindle Speed
    information
    timeout=timer+10; do { timer++; } while (timer<timeout); //Delay to
    push the Message to myCNC Software

    gvarset(7371,eparam);
    //myCNC register #7371 contains actual Spindle Speed.
    //Another way to inform myCNC software about new Spindle Speed (to
    display on it DRO for example)

    exit(99); //normal exit.
};
```

M03, Spindle On, Relay and ET10 DAC

M03.plc

```
//Turn on Spindle clockwise
//set Spindle speed control ET10 DAC channel #2
#include pins.h //defines for pins numbers
#include vars.h //defines for variable names

main()
{
    timer=0;
    value=eparam;

    command=0x32;//EXT_ET5_DAC_OFFSET
    parameter=0x800-(eparam/2)+(2<<12);//channel #2
    message=PLCCMD_SET_CNC_EXTVAR;
    texit=timer+2;do{timer++;}while(timer<texit);

    portclr(OUTPUT_CCW_SPINDLE);
    portset(OUTPUT_SPINDLE);

    gvarset(7370,1);
    //Global Register #7370 shown actual Spindle state (0=OFF, 1=ON).
    //Set Register value when Spindle is ON
    gvarset(7371,eparam);
    //myCNC register #7371 contains actual Spindle Speed.
    //Another way to inform myCNC software about new Spindle Speed (to
    display on it DRO for example)

    /**Set Spindle Speed** is asynchronous operation.
    //It's better to inform myCNC Software New Spindle Speed applied.
    //Send information about new Spindle Speed to myCNC Software
    message=PLCCMD_REPLY_TO_MYCNC; //Command code to
    send to myCNC software
    command=PLC_MESSAGE_SPINDLE_SPEED_CHANGED; //Message code
    parameter=eparam; //New Spindle Speed
    information
    timeout=timer+10; do { timer++; } while (timer<timeout); //Delay to
    push the Message to myCNC Software

    //Wait till Spindle Rotation Speed comes to good values before next
    motion started
    timeout=timeout_on_delay+timer;
    do{timer++;}while (timer<timeout); //delay for Spindle
    reach given speed
```

```
exit(99);                                     //normal exit.
};
```

Water Fill and Drain control

Procedure M240 is used in [some plasma cutting machines to control Water Table Fill & Drain](#).

Running procedure with parameter "1" toggles Water Filling, running with parameter "0" toggles Water Draining. If try to ON both Fill & Drain, the procedure will turn off the previous relay to prevent conflicts.

M240.plc

```
#define OUTPUT_FILL      13
#define OUTPUT_DRAIN     12

main()
{
    o=gvarget(7184); //read OUTPUT PORT 0 state (pins 0...31)
    drain_state=o&(1<<OUTPUT_DRAIN);
    fill_state=o&(1<<13);

    if (eparam==0) //toggle drain
    {
        if (drain_state==0)
        {
            portset(OUTPUT_DRAIN);
            portclr(OUTPUT_FILL);    //to prevent both are open
        }else
        {
            portclr(OUTPUT_DRAIN);
        };
    }else //toggle fill
    {
        if (fill_state==0)
        {
            portset(OUTPUT_FILL);
            portclr(OUTPUT_DRAIN);    //to prevent both are open
        }else
        {
            portclr(OUTPUT_FILL);
        };
    };
    exit(99);
};
```

Gantry Alignment Procedure (with Homing)

M132

```
G10 L80 P5521 Q1
G10 L80 P5525 Q1

M146 P0 L1028
M88 L0 P5(Soft stop when sensor triggered)
G91 G0 Y -300.0000 F 600.00
G04 P0.1
M89 L1 P5(Quick stop when sensor triggered)
G91 G0 Y 300.0000 F 30.00
G04 P0.1
M135
```

M135

```
G10 L80 P5521 Q1
G10 L80 P5525 Q1

M146 P0 L1028

M144
G91 G0 Y100 F30
G04 P0.1

G90 G10 L70 P0 Y0
G04 P0.1
M145 P0 L1028
G90 G10 L193 P97 Q5531

debug #98
G90 G10 L192 P98 Q7525
debug #98
debug #97
G90 G10 L190 P97 Q98
debug #97

G90 G28.9 Y97 F200

M146 P0 L1028

G90 G10 L70 P0 Y0

G90 G10 L80 P5521 Q0
G90 G10 L80 P5525 Q0
G90 G10 L80 P7395 Q0 (Homing Flag)
```

[M144.plc](#)

```
//Look after input1 & input2 sensors, remember position, when triggered

main()
{

timer=0;

message=PLCCMD_MOTION_CONTINUE;
texit=timer+2;do{timer++;}while(timer<texit);

ready=0;

state1=0;
state2=0;

e9000=portget(13);//gvarget(9000);
e9001=portget(14);//gvarget(9001);

state0=0;

m1=0;
m2=0;

do
{
    timer++;

    if (state0==0)
    {
        a=portget(13);//gvarget(9000);
        if (a!=e9000)
        {
            m1=1;
            position1=gvarget(5021+1);    //Machine Y
            state0=1;
        };
        a=portget(14);//gvarget(9100);
        if (a!=e9001)
        {
            m1=2;
            position1=gvarget(5021+1);    //Machine Y
            state0=1;
        };
    }else
    {
        if (m1==2)
        {
            a=portget(13);//gvarget(9000);
            if (a!=e9000)
```

```
{
    m2=1;
    position2=gvarget(5021+1);    //Machine Y
state0=2;
};
}else
{
    a=portget(14);//gvarget(9100);
    if (a!=e9001)
    {
        m2=2;
        position2=gvarget(5021+1);    //Machine Y
state0=2;
    };
};
};

}while(state0<2);

b=position1-position2;

if (b>25000)
{
    b=50000-b;
};
c=0-25000;
if (b<c)
{
    b=50000+b;
};

gvarset(97,b);
texit=timer+30;do{timer++;}while(timer<texit);

gvarset(7230,m1);
if (m1==1) { gvarset(98,1);}
else { x=0-1; gvarset(98,x)};

message=PLCCMD_MOTION_SKIP;
//message=PLCCMD_MOTION_SOFT_SKIP;
texit=timer+2;do{timer++;}while(timer<texit);

exit(99);
};
```

M145.plc

```
#define var_address var00
#define var_value    var01

main()
{
    timer=0;

    lparam=eparam>>16;

    axis=1;    //
    n=gvarget(7230);

    channel=0xff;
    if (n==1) {channel=0;};
    if (n==2) {channel=1;};
    if (n==4) {channel=2;};
    if (n==8) {channel=3;};

    if (channel>8)
    {
        message=PLCCMD_MOTION_ABORT;
        texit=timer+2;do{timer++;}while(timer<texit);
        exit(99);
    };

    var_value=15;
    var_address=112+channel;//channel turn off
    message=PLCCMD_SET_CNC_VAR;
    texit=timer+2;do{timer++;}while(timer<texit);

    exit(99);

};
```

M146.plc

```
#define var_address var00
#define var_value    var01

main()
{
    timer=0;

    dir=0;

    axis=1;
    channel=0;
```



```
var_address=112+channel;//channel 0 set up
var_value=axis;
if (dir!=0) { var_value=16+axis; };
message=PLCCMD_SET_CNC_VAR;
texit=timer+10;do{timer++;}while(timer<texit);

channel=1;

var_address=112+channel;//channel 0 set up
var_value=axis;
if (dir!=0) { var_value=16+axis; };
message=PLCCMD_SET_CNC_VAR;
texit=timer+10;do{timer++;}while(timer<texit);

gvarset(7230,1);

exit(99);
};
```

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http://cnc42.com/ru/plc/plc_examples

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