TOSHIBA

6F8C0928

Integrated Controller V series

MENU

Sequence Controller S2T
User's Manual - Function -

This manual is prepared for users of Toshiba's Programmable Controller S2T.
Read this manual thoroughly before using the S2T. Also, keep this manual and related manuals so that you can read them anytime while the S2T is in operation.

General Information

1. The S2T has been designed and manufactured for use in an industrial environment. However, the S2T is not intended to be used for systems which may endanger human life. Consult Toshiba if you intend to use the S2T for a special application, such as transportation machines, medical apparatus, aviation and space systems, nuclear controls, submarine systems, etc.

2. The S2T has been manufactured under strict quality control. However, to keep safety of overall automated system, fail-safe systems should be considered outside the S2T.

3. In installation, wiring, operation and maintenance of the S2T, it is assumed that the users have general knowledge of industrial electric control systems. If this product is handled or operated improperly, electrical shock, fire or damage to this product could result.

4. This manual has been written for users who are familiar with Programmable Controllers and industrial control equipment. Contact Toshiba if you have any questions about this manual.

5. Sample programs and circuits described in this manual are provided for explaining the operations and applications of the S2T. You should test completely if you use them as a part of your application system.

Hazard Classifications

In this manual, the following two hazard classifications are used to explain the safety precautions.

⚠ WARNING	Indicates a potentially hazardous situation which, if not avoided, could result in death or serious injury.
⚠ CAUTION	Indicates a potentially hazardous situation which, if not avoided, may result in minor or moderate injury. It may also be used to alert against unsafe practices.

Even a precaution is classified as CAUTION, it may cause serious results depending on the situation. Observe all the safety precautions described on this manual.

Safety Precautions

Installation:

⚠ CAUTION

1. Excess temperature, humidity, vibration, shocks, or dusty and corrosive gas environment can cause electrical shock, fire or malfunction. Install and use the S2T and in the environment described in the S2T User's Manual - Hardware.

2. Improper installation directions or insufficient installation can cause fire or the units to drop. Install the S2T in accordance with the instructions described in the S2T User's Manual - Hardware -.

3. Turn off power before installing or removing any units, modules or terminal blocks. Failure to do so can cause electrical shock or damage to the S2T and related equipment.

4. Entering wire scraps or other foreign debris into to the S2T and related equipment can cause fire or malfunction. Pay attention to prevent entering them into the S2T and related equipment during installation and wiring.

Wiring:

⚠ CAUTION

1. Turn off power before wiring to minimize the risk of electrical shock.

2. Exposed conductive parts of wire can cause electrical shock. Use crimp-style terminals with insulating sheath or insulating tape to cover the conductive parts. Also close the terminal covers securely on the terminal blocks when wiring has been completed.

3. Operation without grounding may cause electrical shock or malfunction. Connect the ground terminal on the S2T to the system ground.

4. Applying excess power voltage to the S2T can cause explosion or fire. Apply power of the specified ratings described in the S2T User's Manual - Hardware.

5. Improper wiring can cause fire, electrical shock or malfunction. Observe local regulations on wiring and grounding.

Operation:

⚠ WARNING

1. Configure emergency stop and safety interlocking circuits outside the S2T. Otherwise, malfunction of the S2T can cause injury or serious accidents.

⚠ CAUTION

2. Operate the S2T and the related modules with closing the terminal covers. Keep hands away from terminals while power on, to avoid the risk of electrical shock.

3. When you attempt to perform force outputs, RUN/HALT controls, etc. during operation, carefully check for safety.

4. Turn on power to the S2T before turning on power to the loads. Failure to do so may cause unexpected behavior of the loads.

5. Set operation mode switches of the S2T and I/O modules. Improper switch settings may cause malfunction of the S2T and related equipment.

6. Do not use any modules of the S2T for the purpose other than specified. This can cause electrical shock or injury.

7. Configure the external circuit so that the external power required for output modules and power to the loads are switched on/off simultaneously. Also, turn off power to the loads before turning off power to the S2T.

8. Install fuses appropriate to the load current in the external circuits for the relay output modules. Failure to do so can cause fire in case of load over-current.

9. Check for proper connections on wires, connectors and modules. Insufficient contact can cause malfunction or damage to the S2T and related equipment.

10. Turn off power immediately if the S2T is emitting smoke or odor. Operation under such condition can cause fire or electrical shock. Also unauthorized repairing will cause fire or serious accidents. Do not attempt to repair. Contact Toshiba for repairing.

Maintenance:

⚠ CAUTION

1. Do not charge, disassemble, dispose in a fire nor short-circuit the batteries, It can cause explosion or fire. Observe local regulations for disposal of them.

2. Turn off power before removing or replacing units, terminal blocks or wires. Failure to do so can cause electrical shock or damage to the S2T and related equipment.

3. Replace a blown fuse with a specified one. Failure to do so can cause fire or damage to the S2T.

4. Perform daily checks, periodical checks and cleaning to maintain the system in normal condition and to prevent unnecessary troubles.

5. Check by referring “Troubleshooting” section of the S2T User’s Manual - Hardware, when operating improperly. Contact Toshiba for repairing if the S2T or related equipment is failed. Toshiba will not guarantee proper operation nor safety for unauthorized repairing.

6. The contact reliability of the relays used in the relay output module will reduce if the switching exceeds the specified life. Replace the module if exceeded.

7. Replace the battery every 2 years to maintain the S2T’s program and data normally.

8. Do not modify the S2T and related equipment in hardware nor software. This can cause fire, electrical shock or injury.

9. Pay special attention for safety if you attempt to measure circuit voltage at the S2T’s terminal.

10. Turn off power before replacing modules. Failure to do so can cause electrical shock or damage to the S2T and related equipment.
    If you attempt to replace an I/O module while power on (by using on-line I/O replacement function), carefully check for safety.

Before reading this manual

Purpose of this manual

This manual describes the functions (those functions which can be achieved by the CPU and the basic hardware) of the Programmable Controller S2T. This manual also provides the necessary information for designing application programs and operating the S2T.
Read this manual carefully to use the S2T with it's maximum performance.

Inside of this manual

This manual is divided into the following 3 Parts.

Part 1. Basic Programming ..... Gives the basic information for programming, and shows how to write a program into the S2T with a simple example.

Part 2. Functions..... For the full understanding of the S2T functions, first explains the internal operation of the S2T CPU, and then explains the detailed functions of the S2T.

Part 3. Programming Information .... Explains the information for designing a program which will fully use the functions of the S2T. Also explains Ladder diagram and SFC as programming languages for the S2T. Explains in the detailed information summarized in Part 1.

Those who are using the S2T for the first time should first read Part 1 in order to understand the basics of programming.
When Parts 2 and 3 are read in addition, the advanced control functions of the S2T will be understood without difficulty.

Those experienced in using the S2T may skip Part 1, but refer to Parts 2 and 3 as necessary so as to fully use performance. An index is provided at the end of this manual for that purpose.

When it comes to the configuration, some of the contents of Parts 1 and 3 are duplicated. However, please note that some portions of the explanation in Part 1 are summarized for ease of understanding.

Related manuals

The following related manuals are available for the S2T.

S2T User's Manual-Hardware
This manual covers the S2T's main body and basic I/O-their specifications, handling, maintenance and services.

S2T User's Manual-Functions
This document explains the functions of the S2T and how to use them. The necessary information to create user programs is covered in this volume.

T-series Instruction Set
This manual provides the detailed specifications of instructions for Toshiba's T-series Programmable Controllers.

T-PDS Basic Operation Manual
This manual explains how to install the T-series program development system (T-PDS) into your personal computer and provides basic programming operations.

T-PDS Command Reference Manual
This manual explains all the commands of the T-series program development system (T-PDS) in detail.

T-series Computer Link Function
This manual explains the specification and handling method of the T-series Programmable Controller's Computer Link function.

Before reading this manual

Note and caution symbols

Users of this manual should pay special attention to information preceded by the following symbols.

Calls the reader's attention to information considered important for full understandings of programming procedures and/or operation of the equipment.

Calls the reader's attention to conditions or practices that could damage the equipment or render it temporarily inoperative.

Terminology

AWG	American Wire Gage
ASCII	American Standard Code for Information Interchange
CPU	Central Processing Unit
EEPROM	Electrically Erasable Programmable Read Only Memory
IF	Interface
I/O	Input/Output
LED	Light-Emitting Diode
ms	millisecond
NEMA	National Electrical Manufacture's Association
PLC	Programmable Controller
PS	Power Supply
RAM	Random Access Memory
ROM	Read Only Memory
µs	microsecond
Vac	ac voltage
Vdc	dc voltage

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BASIC PROGRAMMING

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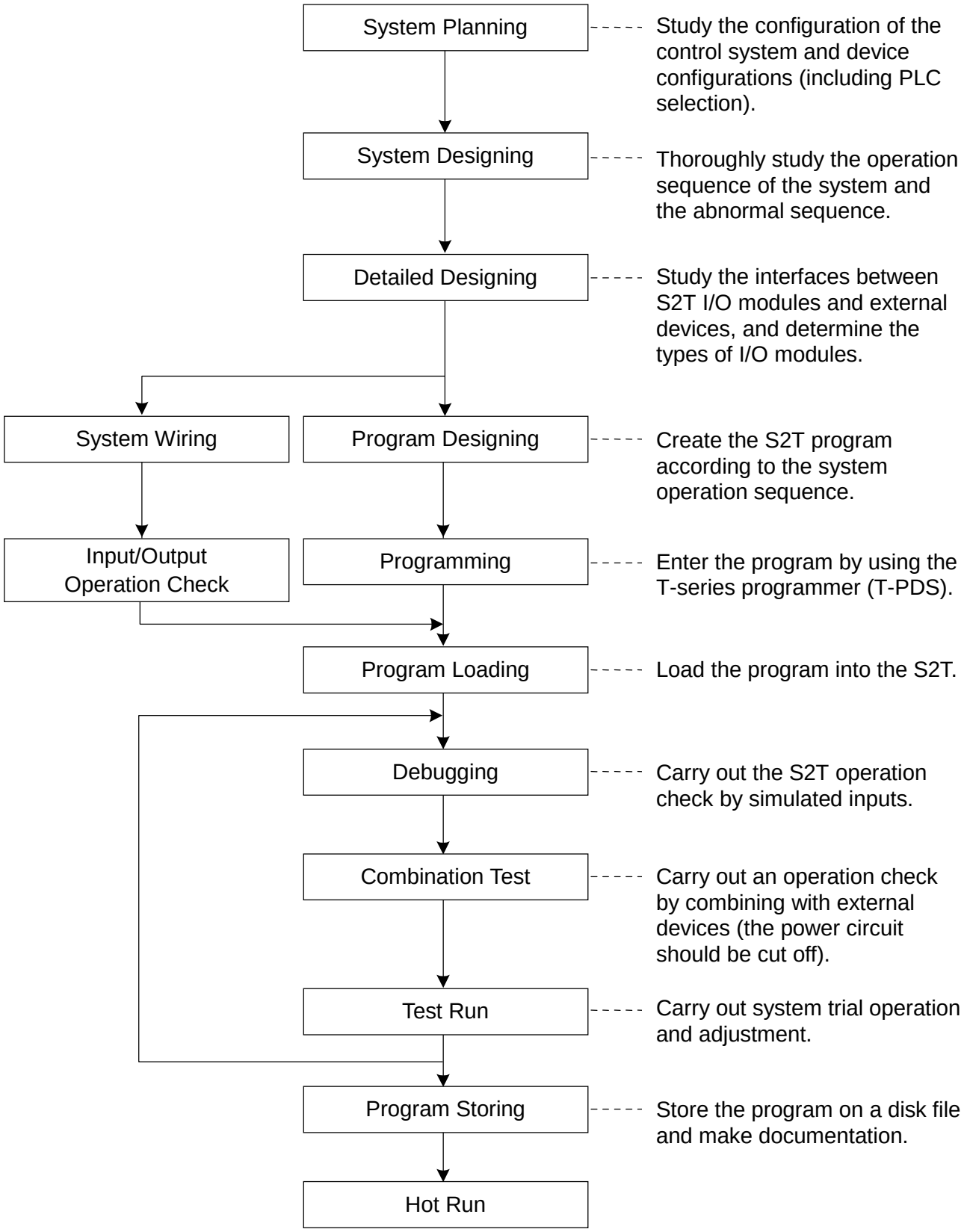
PART 1

BASIC PROGRAMMING

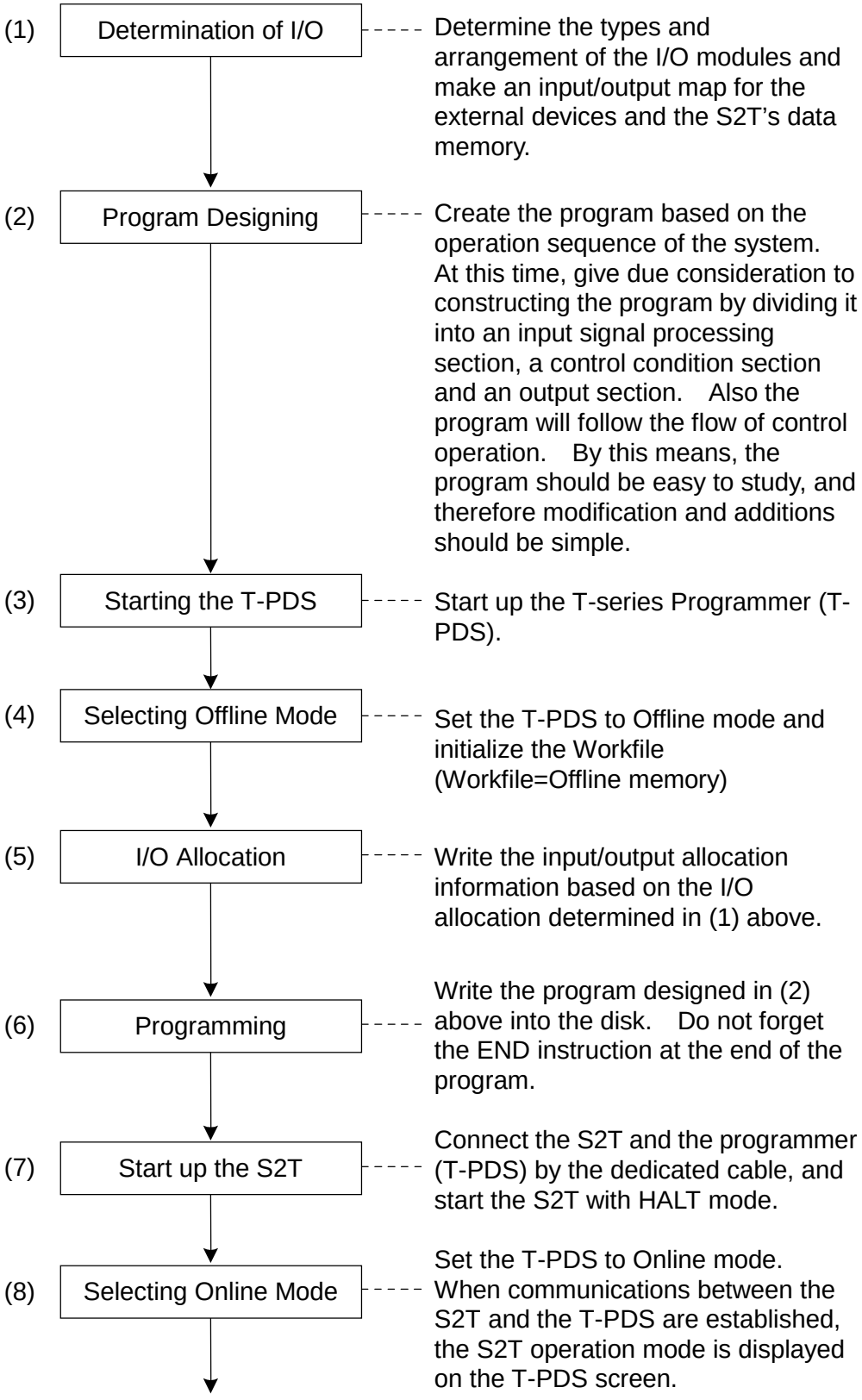
1.1 System design procedures

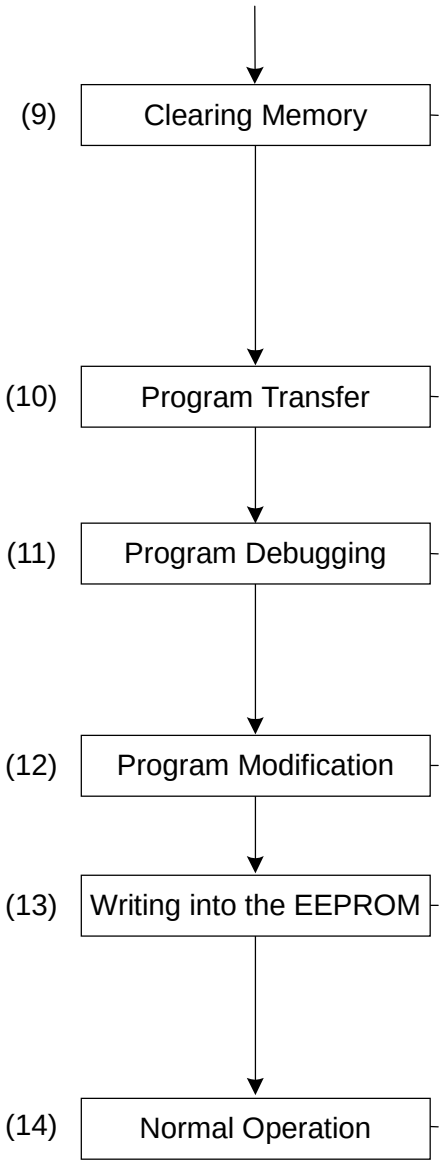
Normally, the design of a control system to which the S2T is applied is carried out by the following procedure.



1.2 Basic programming procedures

The basic procedures for creating a S2T program and loading the program into the S2T are as follows.





Clear the S2T's memory by issuing the Clear Memory command from the T-PDS. If the S2T is in ERROR mode, issue the Error Reset command, then issue the Clear Memory command.

Transfer the program created in offline mode to the S2T.

Put the S2T into RUN mode and check the operation. When the I/O modules are not all mounted, use the Forced RUN (RUN-F) function.

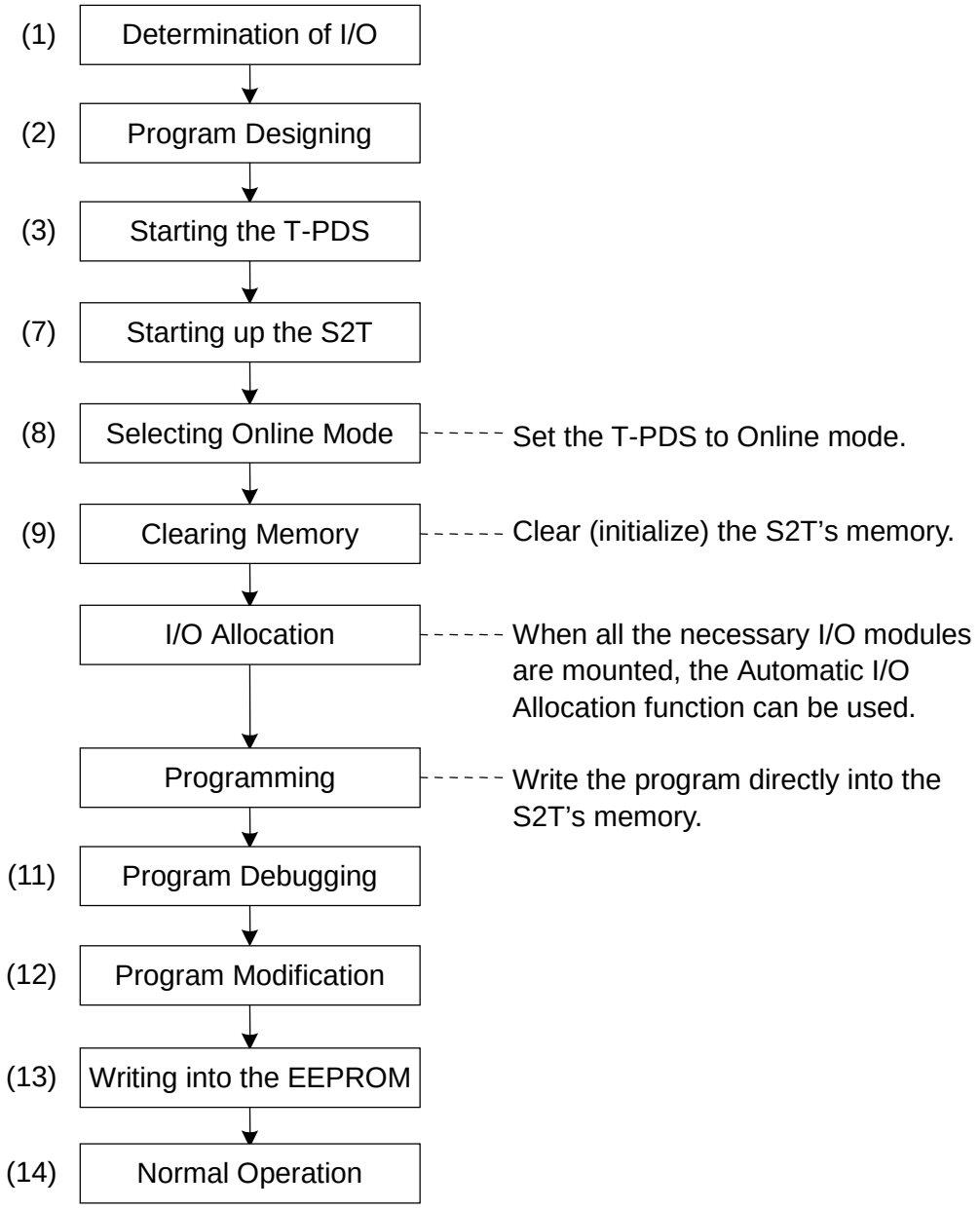
Carry out any required modifications to the program.

When the S2T CPU has built-in flash memory (PU662T/PU672T), write the program into the flash memory.

Put the RAM/ROM switch to ROM, and the operation mode switch to RUN. Operation will then start automatically the next time when power is switched ON.

The above procedure is called 'Offline mode programming'.
In the Offline mode programming, after the user program is developed without the S2T hardware, it will be loaded into the S2T at a time.

On the other hand, the method of connecting the programmer (T-PDS) to the S2T and writing the program directly into the S2T is called 'Online mode programming'. The procedure of Online mode programming is as follows.



NOTE

(1) Take special care for Safety during program debugging and test run.
(2) If power is switched on when the RAM/ROM switch is in RAM, the S2T will not enter RUN mode automatically even if the Operation mode switch is in RUN. (See Section 2.2)

2.1 Operation modes and functions

There are 3 modes of RUN, HALT and ERROR as basic operation modes of the S2T. Also, as a variation of the RUN mode, the RUN-F mode is available for debugging.

RUN Mode: This is the program execution mode. The S2T repeats the reading of external inputs, execution of the user program and the determination of external output states. (One cycle of this operation is called a 'scan'). Monitoring of the program execution state and forced input/output can be performed using the programmer.

RUN-F Mode: This is a mode to force the program execution even when the I/O modules are not mounted. (In the normal RUN mode, this would give an I/O no answer error). This is used for program debugging.

HALT Mode: This is the operation stop mode. The S2T switches OFF all outputs and stops user program execution. Normally, programming is carried out in this mode. Also, writing the program into the flash memory (in the case of the PU662T/PU672T) is available in this mode only.

ERROR Mode: This is the 'Error Down' state. When the S2T detects an error by self-diagnosis which renders continuation of operation impossible, it will switch OFF all outputs, stop the use program execution and enter the ERROR mode. In the ERROR mode, all writing operations to the S2T are prohibited. In order to escape from this mode, it is necessary either execute 'Error Reset' from the programmer, or to switch the power supply OFF and ON again.

NOTE

1. Programs can be changed in both the RUN mode and the RUN-F mode (this is called the 'online program changing function'). However, only normal programming in the HALT mode is described in Part 1. See Part 2 for the online program changing function.
2. Apart from the above 4 modes, there are actually the HOLD mode and the DEBUG mode as well. These are described in Part 2.

2.2 Modes transition conditions

To determine/change the operation mode of the S2T, the operation mode switch on the CPU module, programmer PLC control commands and S2T self-diagnosis are available. Also, the RAM/ROM switch on the CPU module controls the operation mode at power up. These are described below.

* Operation Mode Switch...HALT/RUN

Switch Position	Operation Mode
HALT	When the mode switch is shifted from RUN or P-RUN to HALT, the operation mode will turn to the HALT mode. Also, when power is switched ON with the mode switch at HALT, the S2T will start up in the HALT mode.
RUN	When the mode switch is shifted from HALT to RUN, the operation mode will turn to the RUN mode. The mode when power is switched ON in the RUN position will be determined by the RAM/ROM switch.

* Auto-RUN/Standby selection

Switch Position	Operation Mode
Auto-RUN	The S2T's initial operation mode is determined by the mode control switch (HALT / RUN). When this switch is in RUN, the S2T moves into RUN mode automatically.
Standby	The S2T stays in HALT mode regardless of the mode control switch (HALT / RUN) after power on. Then the operation mode can be changed manually, i.e. by programmer command or by changing the mode control switch.

* RAM/ROM switch:

Switch Position	Operation Mode
RAM	User program stored in RAM is used. (Program transfer from Flash Memory to RAM is not executed)
ROM	At the beginning of RUN mode, user program stored in flash memory is transferred to RAM. (It is called Initial load)

* Mode control switch:

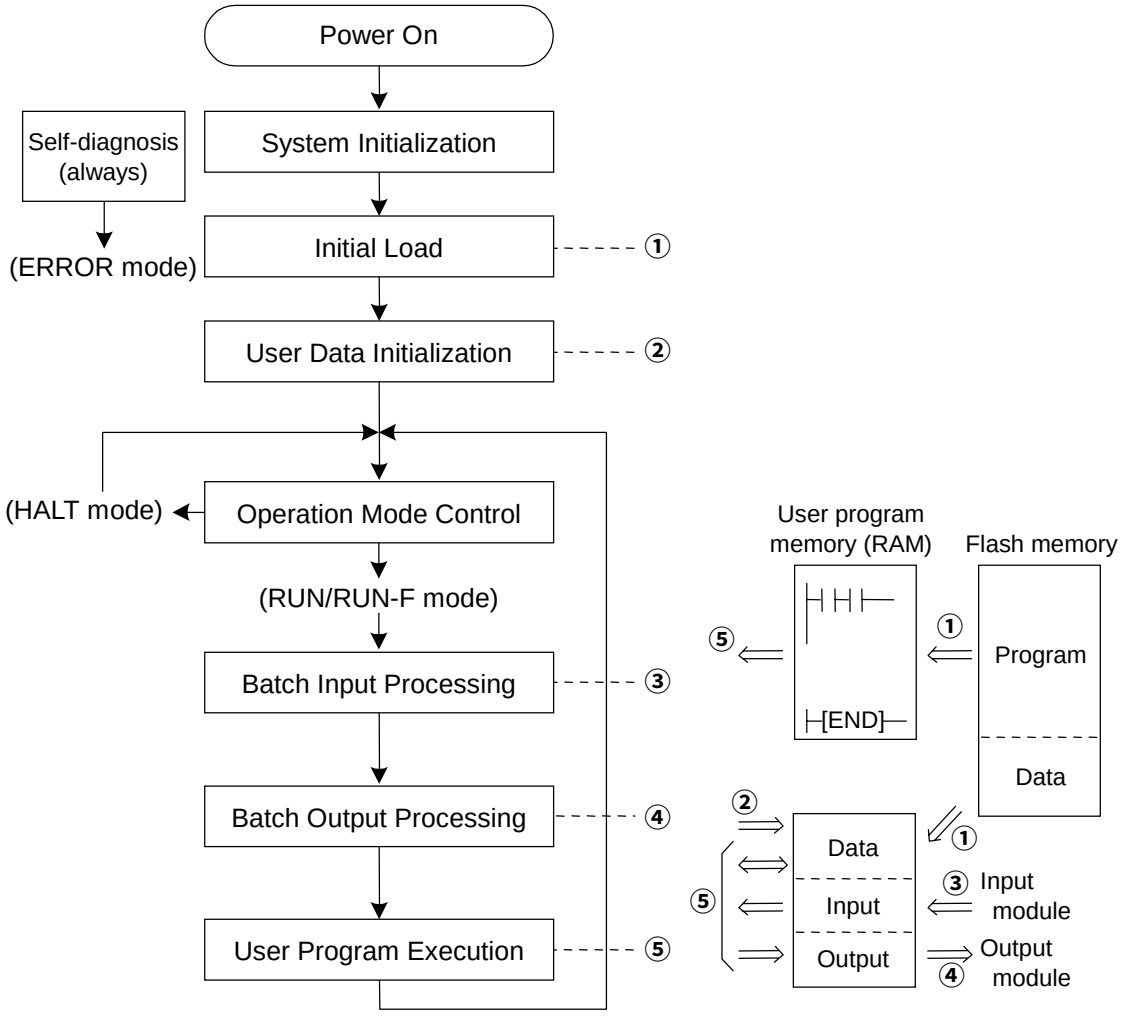
Switch Position	Operation Mode
HALT	User program execution is stopped. (HALT mode) Normally, programming is performed in the HALT mode. S2T operation mode control by programmer is not allowed.
RUN	S2T executes user program cyclically. (RUN mode) It is the normal switch position under operation. Even in the RUN mode, program changes are possible. However, saving into the flash memory is available only in the HALT mode. S2T operation mode control by programmer is possible.

Previous state			OP mode transition factor		OP mode after transition	Remarks
OP mode	RAM/ROM	Mode SW				
— (Power OFF)	RAM	HALT	Power ON		HALT	No Initial Load
		RUN	Power ON	Auto-RUN	RUN	No Initial Load
				Standby	HALT	
	ROM	HALT	Power ON		HALT	Initial Load execution
		RUN	Power ON	Auto-RUN	RUN	Initial Load execution → RUN
				Standby		
	—	—	Error detection at power ON		ERROR	
HALT	RAM	HALT	Mode SW	→RUN	RUN	No Initial Load
		RUN	Command	RUN	RUN	
			Command	Force RUN	RUN-F	
	ROM	HALT	Mode SW	→RUN	RUN	Initial Load execution → RUN
		RUN	Command	RUN	RUN	
			Command	Force RUN	RUN-F	Initial Load execution → RUN-F
	—	RUN	Mode SW	→HALT	HALT	Mode unchange
		HALT	Command (any)		HALT	Command invalid (Mode unchange)
		RUN	Command	HALT	HALT	
		—	Error detection		ERROR	
RUN	—	RUN	Mode SW	→HALT	HALT	
		RUN	Command	HALT	HALT	
			Command	RUN	RUN	Command invalid (Mode unchange)
			Command	Force RUN	RUN	
			Error detection		ERROR	
RUN-F	—	RUN	Mode SW	→HALT	HALT	
		RUN	Command	HALT	HALT	
			Command	RUN	RUN-F	Command invalid (Mode unchange)
			Command	Force RUN	RUN-F	
			Error detection		ERROR	
ERROR	—	—	Mode SW (HALT/RUN)		ERROR	Invalid
			Command (except Error Reset)		ERROR	
			Command	Error Reset	HALT	Recovery to HALT mode

1) In this table, OP mode, RAM/ROM and Mode SW mean Operation mode, RAM/ROM switch and Operation Mode switch, respectively.
2) — means the switch status is not related to.
3) See next page for the Initial Load.

2.3 Operation flow chart

User programs can be produced without fully understanding the internal processes of the S2T. However, understanding the outline of the internal processes will be effective in producing more efficient programs and in carrying out appropriate debugging. The following drawing gives a S2T internal process overview.



① Initial Load

When the RAM/ROM switch is in ROM and the operation mode switch is in RUN, the following contents stored in the flash memory will be transferred to the S2T RAM at power up and at transiting from the HALT mode to the RUN mode.

(1) Whole user program
(2) Leading 4k words of data register (D0000 to D4095)

② User Data Initialization
User data (data register, timer, counter, input register, output register, etc.) are initialized. User data is explained in Section 5.

③ Batch Input Processing
The status of external input signals will be read from input modules and stored in the input registers. (The input register is sometimes called the 'input image table'.)

④ Batch Output Processing
The status of output registers is written to the output modules. The output module determines the ON/OFF state of output based on this. (The output register is sometimes called the 'output image table'.)

⑤ User Program Execution
The instructions stored in the user program memory are read one by one, and the contents of the output register are updated while referring to the contents of the user data. This is an essential function of the S2T.

One cycle from operation mode control to user program execution is called 'one scan'. The time required for 1 scan is called the 'scan cycle' (or the 'scan time').

Generally, the shorter the scan cycle, the faster the output response to a change in input signal.

NOTE

The important items related to the S2T operation mode and the switches are summarized below.

(1) When power is turned on with the RAM/ROM switch at RAM position, the S2T starts up in HALT mode. Therefore, use the RAM position during debug and test run, and set to ROM in normal operation, regardless of the type of the S2T CPU.

(2) The object of the Initial Load is whole program and the leading 4k words of data register (D0000 to D4095).
Therefore, even if the range of D0000 to D4095 is specified as retentive, these data will be initialized by the data of the flash memory.

3.1 I/O allocation

As described in Section 2.3, communication between input modules or output modules and the user program is executed via the input registers and the output registers.

I/O allocation is the determination of which address of the I/O registers shall be assigned to which I/O module. Basically, this is determined by the mounting order of the modules. Therefore, informing the CPU of the module mounting order is called 'I/O allocation'.

The following two methods are available for performing I/O allocation. Either method requires that the S2T is in the HALT mode and that the operation mode switch is in a position RUN.

(1) Automatic I/O Allocation
Execute the automatic I/O allocation command to the S2T from the programmer. The S2T CPU reads the module types of I/O modules mounted (see the table on the next page) and stores this in the user program memory as I/O allocation information.

(2) Manual I/O Allocation
Set the mounting positions and the module types of I/O modules on the I/O allocation screen of the programmer, and write this information to the S2T.
Manual I/O allocation is used when performing programming in a state in which not all the I/O modules have been mounted, or when using the unit base address settings described in Section 3.4.
Manual I/O allocation is also used for offline mode programming.

When the I/O allocation information is stored in the S2T memory by these methods, the correspondence between the I/O modules and the I/O register is automatically determined by the rules described in Section 3.3.

*) In practice, special allocation of module types other than those shown in the table on the next page can be executed by manual I/O allocation. However, the description is omitted here. The details are described in Part 3.

The module type of I/O module is expressed in the following table by a combination of a functional classification (X: lnput, Y: Output, X+Y: I/O mixed) and the number of registers occupied (W).

Module	Description	Module Type
DI632D/652	8 points DC input	X 1W
DI633	16 points DC input	X 1W
DI634	32 points DC input	X 2W
DI635/635H	64 points DC input	X 4W
IN653/663	16 points AC input	X 1W
DO633/633P/653	16 points DC output	Y 1W
DO634	32 points DC output	Y 2W
DO635	64 points DC output	Y 4W
AC663	16 points AC output	Y 1W
RO663	16 points Relay output	Y 2W
RO662S	8 points Relay output (isolated)	Y 1W
AD624L/634L AD624/634 RT614	4 channels analog input	X 4W
AD668/TC618	8 channels analog input	X 8W
DA632L DA662/672	4 channels analog output	Y 4W
DA664	4 channels analog output	Y 4W
PI632	2 channels pulse input	iX+Y 2W
CF611	ASCII module	iX+Y 4W
SN621/622/625/626/627	TOSLINE-S20 data transmission	TL-S
UM611/612	TOSLINE-F10 data transmission	TL-F

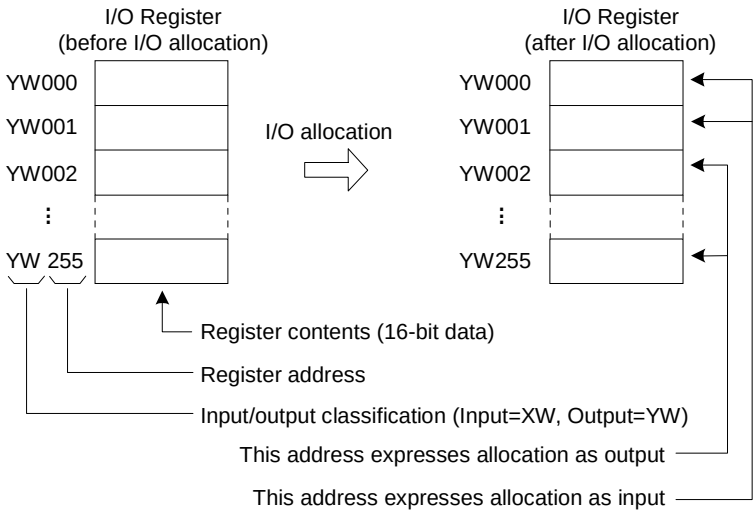
3.2 Input and output registers

In the previous Section, I/O allocation is the performance of correspondence between I/O modules and input/output registers. Here, the configurations of input registers and output registers, and methods of address expression are described.

In descriptions hitherto, input registers and output registers have been treated as separate entities. However, from the viewpoint of memory configuration, this is not correct.

In practice, the input register and the output register use the same memory area which is called the 'I/O register'. In other words, before performing I/O allocation, the I/O register is not colour-divided for input and output. Colour-division of input and output in register units (16-bit units) is performed by carrying out I/O allocation. (Before allocation, internally, all are regarded as output registers).

This idea can be conveyed by the following drawing.



The I/O register is a 16-bit register, and 256 registers are available. ('16-bit' signifies that it stores the ON/OFF information for 16 points.)

The I/O register used in the user program is expressed as follows.

When an input register ...XW □□□
When an output register ...YW □□□

The above □□□ expresses the register address (also called the 'register number'), a decimal number from 000 to 255.

Also, each bit (called a 'device') in the I/O register is expressed as follows.

When a bit in an input register (input device) ...X □□□★
When a bit in an output register (output device) ...Y □□□★

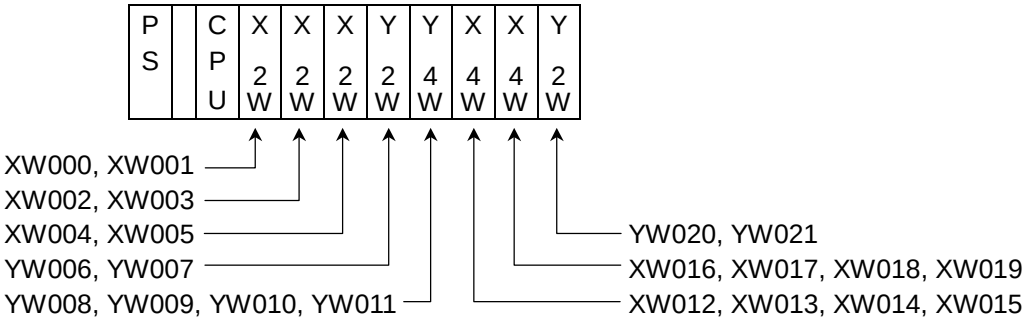
The above □□□ expresses the register address and the ★ expresses the bit position in the register.

As bit positions, 16 positions of 0,1, ..., 9, A, B, C, D, E, F are available.

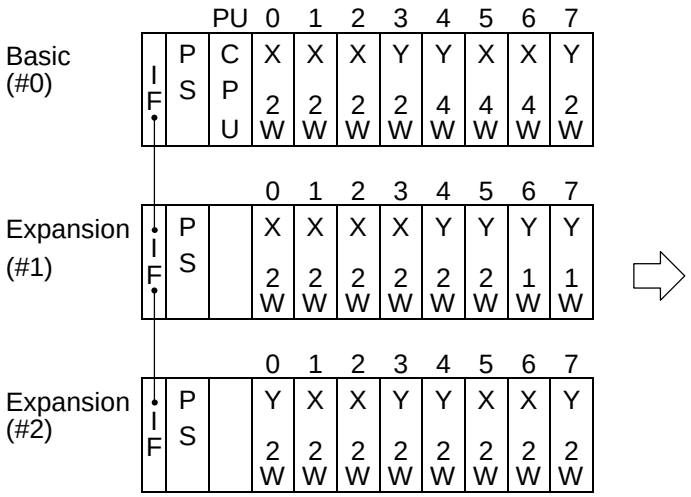
3.3 Rules for I/O allocation

When I/O allocation is performed either by the automatic I/O allocation or the manual I/O allocation method, the I/O allocation information (information on which type of module is mounted in which position) is produced in the user program memory. The coordination between the registers and the I/O modules is decided according to the following rules.

(1) In the basic unit, allocation is carried out from the module immediately to the right of the CPU in sequence from the lowest register address.



(2) In the case of expansion units, allocations are given following on from the previous stage unit in sequence from the left end module to the right end module.

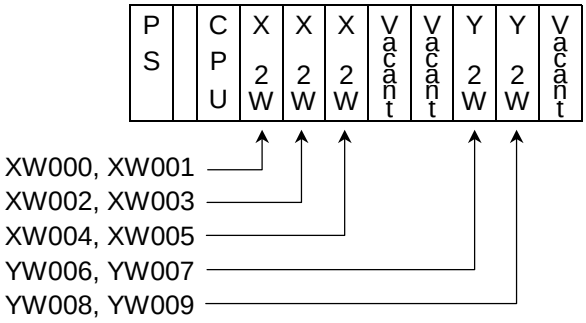


Register allocation table

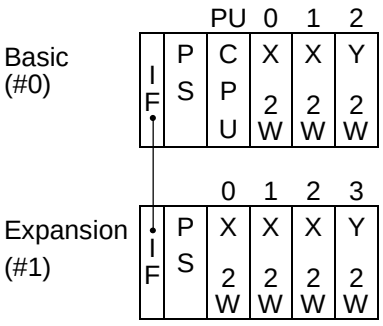
Unit	Slot	Type	Register
0	0	X 2W	XW000, XW001
	≀	≀	≀
	7	Y 2W	YW020
1	0	Y 2W	XW022, XW023
	1	X 2W	XW024, XW025
	2	X 2W	XW026, XW027
	3	X 2W	XW028, XW029
	4	Y 2W	XW030, XW031
	5	Y 2W	XW032, XW033
	6	Y 2W	XW034
	7	Y 2W	XW035
2	0	Y 2W	XW036, XW037
	≀	≀	≀

*) In the I/O allocation, for convenience, the module mounting position is expressed by a combination of the unit number and the slot number.
Unit number: #0, #1, #2, #3 in sequence from the basic unit
Slot number: 0,1, 2, ...7 in sequence from the module mounting position at the left end.

(3) Slots in which no module is mounted (in manual I/O allocation, slots for which no type is set) do not occupy registers. These are called 'vacant' slots.



(4) In case of the 4-slot basic rack (BU643D), slots 4 to 7 are regarded as vacant. Similarly, in case of the 6-slot expansion rack (BU666), slots 6 to 7 are regarded as vacant.

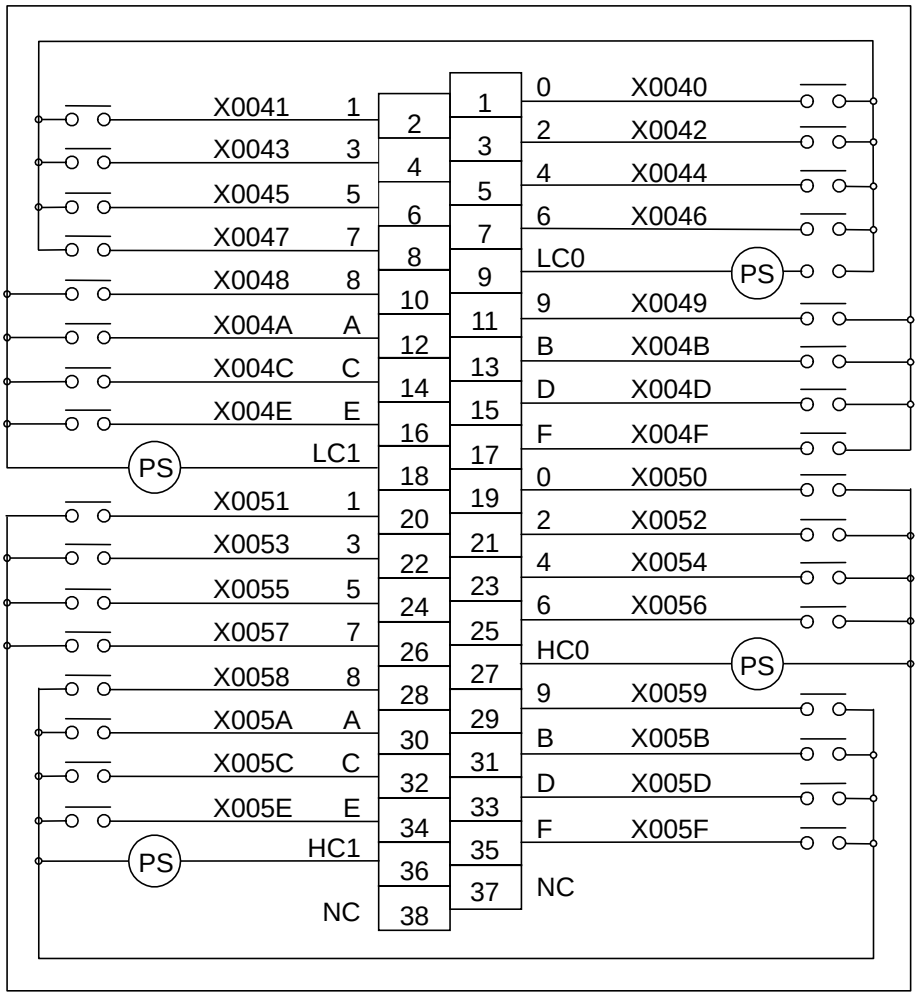


Register allocation table

Unit	Slot	Type	Register
0	0	X 2W	XW000, XW001
	1	X 2W	XW002, XW003
	2	Y 2W	XW004, XW005
	3	Vacant	—
	≀	≀	≀
	7	Vacant	—
1	0	Y 2W	XW006, XW007
	1	X 2W	XW008, XW009
	2	X 2W	XW010, XW011
	3	X 2W	XW012, XW013
	4	Vacant	—
	≀	≀	≀
	7	Vacant	—

(5) After an input/output register is allocated to an I/O module, the individual external signals on the module are allocated to each bit (device) on the register. At this time, in modules to which multiple registers are allocated, lower register address is allocated to the lower common (LC) side.

(Example)
The following is the input signal and input device coordination when XW004 and XW005 are allocated to a 32-point input module (X2W).



(6) Special modules (modules which are not designated by X, Y, X+Y, iX, iY, iX+Y as module types) such as data transmission modules do not occupy input/output registers.

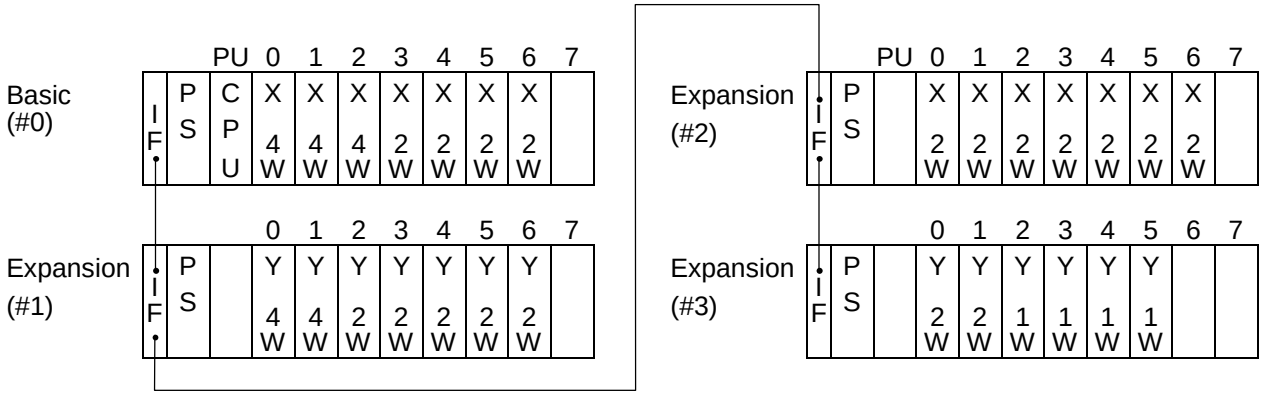
(7) Input/output registers which are not allocated, internally become output registers, and can be used in the same way as auxiliary registers/relays in the program.

3.4 Unit base address setting functions

As a special function for input/output allocation, there is a function which can set the base register address of each unit.

This function is achieved by the manual I/O allocation.

If this function is used, the register address does not shift even when module additions are carried out in the future.



Register allocation table

Unit	Unit base address	Slot	Type	Register
0	00	PU		—
		0	X 4W	XW000〜XW003
		1	X 4W	XW004〜XW007
		2	X 4W	XW008〜XW011
		3	X 2W	XW012, XW013
		4	X 2W	XW014, XW015
		5	X 2W	XW016, XW017
		6	X 2W	XW018, XW019
		7		—
1	30	0	Y 4W	YW030〜YW033
		1	Y 4W	YW034〜YW037
		2	Y 2W	YW038, YW039
		3	Y 2W	YW040, YW041
		4	Y 2W	YW042, YW043
		5	Y 2W	YW044, YW045
		6	Y 2W	YW046, YW047
		7		—
2	60	0	X 2W	XW060, XW061
		1	X 2W	XW062, XW063
		2	X 2W	XW064, XW065
		3	X 2W	XW066, XW067
		4	X 2W	XW068, XW069
		5	X 2W	XW070, XW071
		6	X 2W	XW072, XW073
		7		—
3	90	0	Y 2W	YW090, YW091
		1	Y 2W	YW092, YW093
		2	Y 1W	YW094
		3	Y 1W	YW095
		4	Y 1W	YW096
		5	Y 1W	YW097
		6		—
		7		—

NOTE

(1) Apart from register address skipping between units, when the unit base address setting function is used, it follows the I/O allocation rules described in Section 3.3.

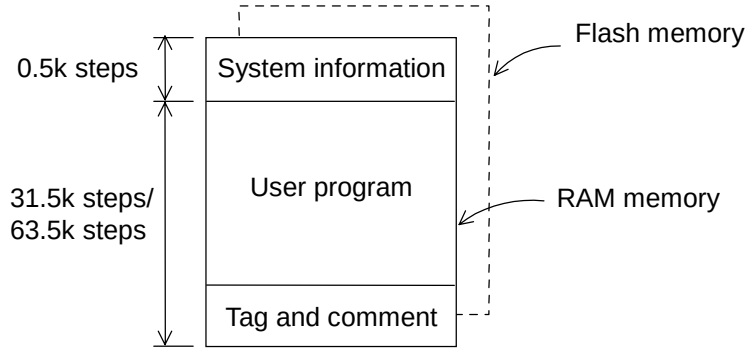
(2) A setting which gives a latter stage unit a low register address cannot be performed. For example, a setting by which the base address of Unit #1 is 50 and the base address of Unit #2 is 30 cannot be performed.

(3) When automatic I/O allocation is performed, there is no base address designation for any unit. The registers are allocated in succession. (As described in Section 3.3).

4.1 User program configuration

A group of instructions for executing control is called a ‘user program’. This is also called an ‘application program’, a ‘sequence program’ or a ‘logic circuit’. In this manual it will be called a ‘user program’.

The memory area which stores the user program is called the ‘user program memory’, and in the S2T it has a capacity of 32k steps. (PU662T)/64k steps (PU672T)
However, out of this, 0.5k steps are used to store the user program ancillary information (this is called ‘system information’). Therefore, the actual user program capacity will be 31.5k/63.5k steps. Also, if Tags and Comments are stored in the S2T, a part of this area is used.
A ‘step’ is the minimum unit which composes an instruction and, depending on the type of instruction, there will be 1-10 steps per instruction.



NOTE

(1) For the conditions for transfer from the flash memory to the RAM (the Initial Load), see Section 2.3.
(2) Tag and Comment are explained in Part 3.

4.2 System information

'System information' is the area which stores execution control parameters and user program control information for executing the user program, and occupies 0.5k steps. The following contents are included in the system information.

(1) Machine parameters (model type, memory capacity)
(2) User program information (program ID, system comments, number of steps used, etc.)
(3) Execution control parameters (scanning mode, sub-program and interrupt program execution conditions)
(4) Retentive memory area information
(5) I/O allocation information
(6) I/O interrupt assignment information
(7) Network assignment information
(8) Computer link parameters
(9) System diagnosis function execution conditions

Out of these, the CPU automatically performs the setting/updating of the machine parameters of (1) and the number of steps used of (2). Items apart from these are set by the user from the programmer. Here, only the retentive memory area information of (4) and the I/O allocation information of (5) are described. The other items are described in Part 2 and Part 3.

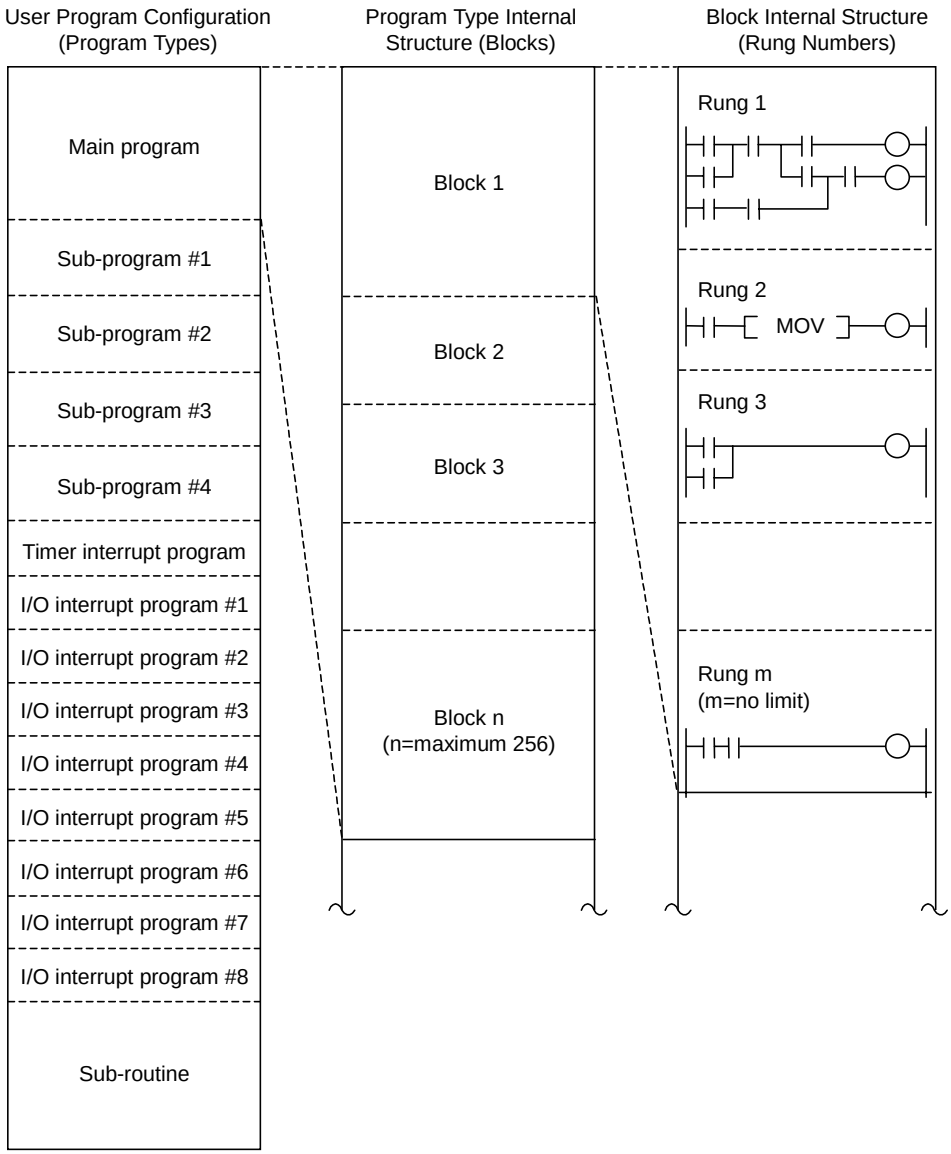
* Retentive memory area
  The ranges for retaining the data during power off can be set for the auxiliary register (RW), the timer register (T), the counter register (C) and the data register (D). Data other than within these set ranges will be 0-cleared (device is OFF) in the data initialization process at power up. This setting is performed in a way to designate from the first address (0) to a designated address for each of the above registers. (See Section 5.2 for details)

* I/O allocation information
  As described in Section 3,I/O allocation information is stored here by executing automatic I/O allocation or manual I/O allocation. The CPU determines input/output register allocation based on this information. Also, as self-diagnosis, the CPU executes a check as to whether the modules in the allocation information are correctly mounted.

4.3 User program

The user program is a group of instructions for executing control, and has a capacity of 31.5k/63.5k steps. The function which executes the user program is the main function of the programmable controller S2T.

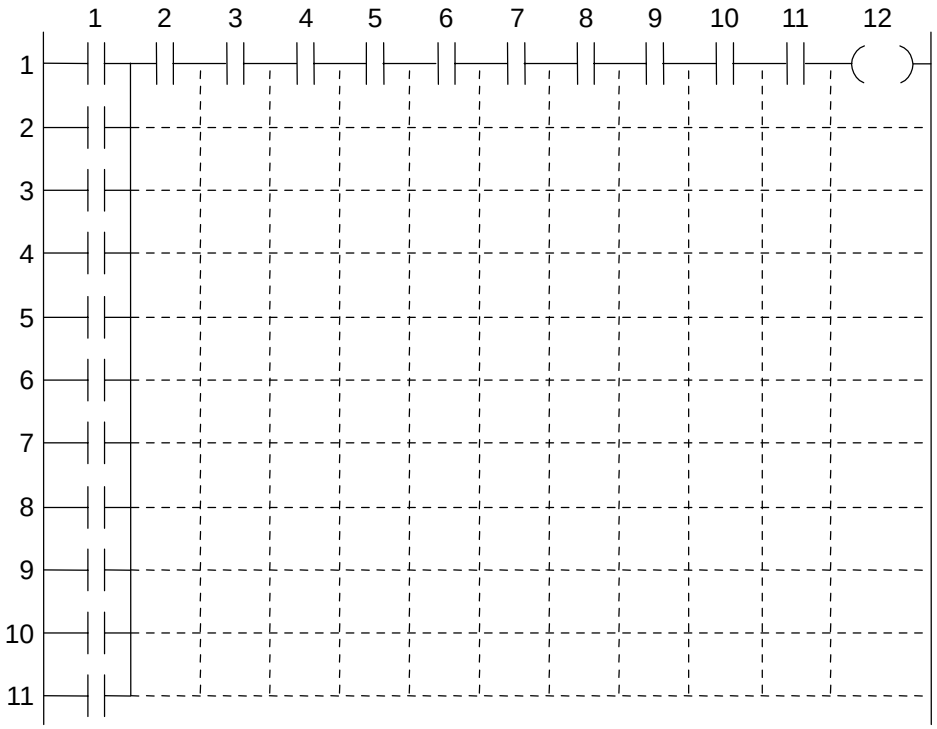
The user program is stored by each program type as shown in the following diagram, and it is managed by units called 'blocks' in each program type. Also, in 1 block, the user program is managed by a rung number (in the case of ladder diagram). Therefore, in the monitoring/editing the user program, a specified rung can be called by designating the program type, block number and rung number.



* Program Types
  As program types, the main program, sub-programs (#1-#4), the timer interrupt program, I/O interrupt programs (#1-#8) and the sub-routines are available. Although there is a capacity limit of within a total of 31.5K/63.5k steps, there is no capacity limit on any of the program types.

* Blocks
  From 1 to 256 are effective as block numbers. Every block has no capacity limit. In the S2T, apart from the Ladder diagram, the SEC language can be used. However multiple languages cannot be used in one block. In other words, when multiple languages are used, it is necessary to separate blocks. In the case of using the ladder diagram only, there is no need to divide the block.

* Rungs
  Within the block, the user program is managed by the rung number. (In the case of the Ladder diagram). A 'rung' signifies one grouping which is linked by lines other than right and left power rails. There is no limit to the number of rungs which can be programmed within one block. The size of one rung is limited to 11 lines × 12 rows (maximum 132 steps), as shown in the following diagram.



4.4 Program execution sequence

The main program is the main body of the user program which executes every scan, and must have at least one END instruction. Here, the program execution sequence is described in the case of the main program only. The operation of other program types is described in Part 2.

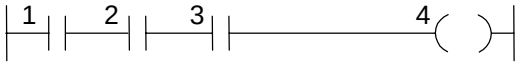
The user program is executed in the following sequence.

① The main program is .executed in sequence from the first block (the lowest number block) to the block which contains the END instruction.

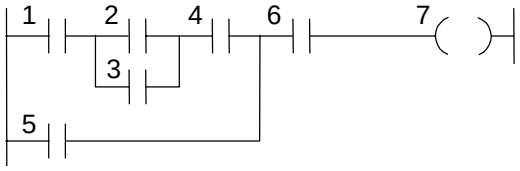
② Within one block, it is executed in sequence from the first rung (Rung 1) to the last rung (in the case of the block containing the END instruction, to the rung which has the END instruction).

③ Within one rung, it is executed in accordance with the following rules.

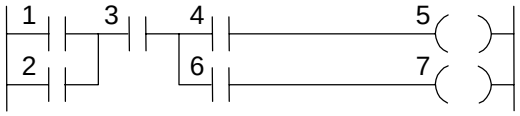
(1) When there is no vertical connection, execution is carried out from left to right.



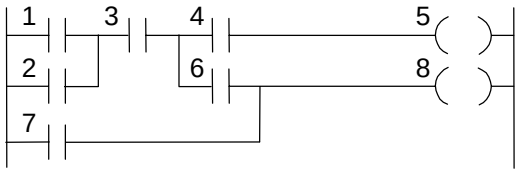
(2) When there are OR connections the OR logic path is executed first.



(3) When there are branches, execution is carried out from the upper line to the lower line.



(4) A combination of (2) and (3) above.



NOTE

1. The block numbers need not be consecutive. In other words, there may be vacant blocks in the middle.
2. The rung numbers must be consecutive. In other words, vacant rungs cannot be programmed in the middle.

5.1 User data types and functions

Data stored in the RAM memory of the CPU and which can be referred directly in a user program, such as the states of input/output signals, control parameters and arithmetical results during execution of the user program are called 'user data'.

From the viewpoint of treatment, user data can be considered as divided into registers and devices.

Registers are locations which store 16-bit data. The following types are available according to their functions.

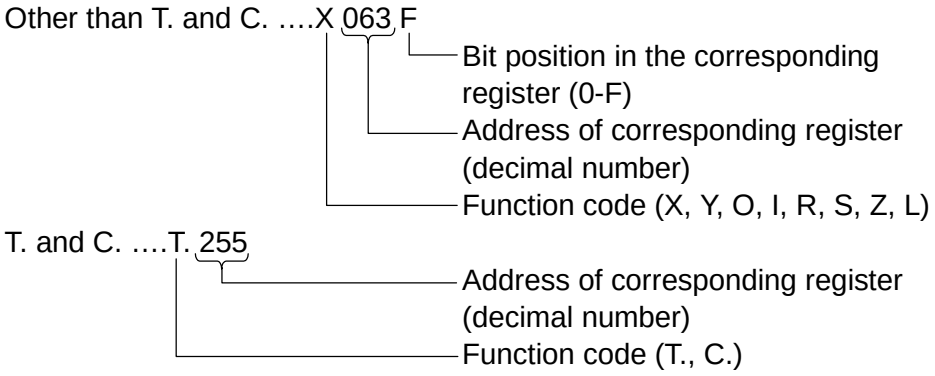
Code	Name	Function	Number	Address Range
XW	Input register	Stores input data from the input module (batch input)	Total 512 words	XW000-XW511
YW	Output register	Stores output data to the output module (batch output)		YW000-YW511
IW	Direct input register	Direct input data from the input module (direct input)		IW000-IW511
OW	Direct output register	Direct output data to the output module(direct output)		OW000-OW511
RW	Auxiliary register	Used as a temporary memory for results during execution of the user program	1000 words	RW000-RW999
SW	Special register	Stores error flags, execution control flags, clock-calendar data timing clocks, etc.	256 words	SW000-SW255
T	Timer register	Stores elapsed time during timer instruction execution	1000 words	T000-T999
C	Counter register	Stores current count value during counter instruction execution	512 words	C000-C511
D	Data register	Used for storing control parameters and as a temporary memory for execution results	8192 words	D0000-D8191
W	Link register	Data exchange area with data transmission module (TOSLINE-S20)	2048 words	W0000-W2047
LW	Link relay register	Data exchange area with data transmission module (TOSLINE-F10)	256 words	LW000-LW255
F	File register	Used for storing control parameters and for storing accumulated data	32768 words	F0000-F32767
I	Index register	Used for indirect addressing for register designation of instructions	1 word	I (No address)
J			1 word	J (No address)
K			1 word	K (No address)

*1) In the S2T system, 1 word is treated as equal to 16 bits and units called words are used as numbers of registers.
*2) All register addresses are decimal numbers.
*3) In the timer register T000-T063 increase in 0.01 second units (0.01 second timer) and T064-T999 increase in 0.1 second units (0.1 second timer).

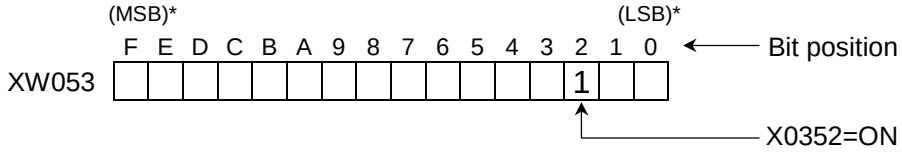
On the other hand, 'devices' are locations which store 1-bit data (ON/OFF information). The following types are available according to their functions.

Code	Name	Function	Number	Address Range
X	Input device	Stores input data from the input module (batch input) Corresponds to 1 bit in the XW register	Total 8192 points	X0000-X511F
Y	Output device	Stores output data to the output module (batch output) Corresponds to 1 bit in the YW register		Y0000-Y511F
I	Direct input device	Direct input data from the input module (direct input)		I0000-I511F
O	Direct output device	Direct output data to the output module (direct output)		O000-O511F
R	Auxiliary relay device	Used for internal relay. Corresponds to 1 bit in the RW register	16000 points	R000-R999F
S	Special device	Stores error flags, execution control flags, timing relays, etc. Corresponds to 1 bit in the SW register	4096 points	S0000-S255F
T.	Timer relay device	Reflects the execution result of the timer instruction Corresponds to the T register operation of the same address	1000 points	T.000-T.999
C.	Counter relay device	Reflects the execution result of the counter instruction Corresponds to the C register operation of the same address	512 points	C.000-C.511
Z	Link device	Data exchange area with data transmission module (TOSLINE-S20) Corresponds to 1 bit in the leading 512 words of the W register	16000 points	Z0000-Z999F
L	Link relay device	Data exchange area with data transmission module (TOSLINE-F10)	4096 points	L0000-L255F

The address expressions for devices are as shown below.



Therefore, for example, device X0352 expresses bit 2 of register XW035, and if X0352 is ON, it means that bit 2 of XW035 is 1.



NOTE

(1) The least significant bit (LSB) is bit 0 when numerical values are handled in the register.
(2) When the direct input register/device (IW/I) are used in an instruction, input data will be read directly from the input module when that instruction is executed. (This system is called the 'direct input system'). As opposed to this, in the input register (XW), input data will be read from the corresponding input module in a batch before user program execution. (This system is called the 'batch input system'). In the input/output allocation. an IW and XW of the same address correspond to the same input module.
(3) When the direct output register/device (OW/O) are used in an instruction, those data will be outputted directly to the output module when that instruction is executed. (This system is called the 'direct output system'). As opposed to this, the contents of the output register (YW) will be outputted to the corresponding output module in a batch before user program execution. (This system is called the 'batch output system'). In the input/output allocation, an OW and YW of the same address correspond to the same output module.
Note that, in the case of direct output by device O, the other 15 bits in the same register (OW) are also directly outputted.
(4) See Part 3 for details of registers/devices.

* LSB : Least significant bit
MSB: Most significant bit

5.2 Conditions for data initialization

The user data are initialized according to the conditions in the following table at power up and at transiting the RUN mode.
Also, the leading 4k words of the data register (D0000 to D4095), are the subjects of the Initial Load. Therefore, when the Initial Load conditions are established, initialization will be carried out in the sequence Initial Load → data initialization. (See Section 2.3 for Initial Load)

Register/Device	Initialization
Input registers/devices (XW/X)	For forced input devices the previous state is maintained, the others are 0-cleared.
Output registers/devices (YW/Y)	For coil forced output devices the previous state is maintained, the others are 0-cleared.
Auxiliary registers/devices (RW/R)	For registers designated as retentive and coil forced devices the previous state is maintained, the others are 0-cleared.
Special registers/devices (SW/S)	CPU setting part is initialized and the user setting part is maintained.
Timer registers/relays (T/T.)	For registers designated as retentive and the devices which correspond to them the previous state is maintained, the others are 0-cleared.
Counter registers/relays (C/C.)	
Data registers (D)	For registers designated as retentive the previous state is maintained, the others are 0-cleared.
Link registers/relays (W/Z)	For forced link devices the previous state is maintained, the others are 0-cleared.
Link relays (LW/L)	For forced link relays the previous state is maintained, the others are 0-cleared.
File registers (F)	All maintained
Index registers (I,J,K)	All 0-cleared

*) The retentive memory area designation is available for the RW, T, C and D registers.
These areas are designated by the system information setting function of the programmer. For each register the area from the first address (0) to the designated address becomes the retentive memory area.

T-PDS's Retentive Memory Area Designation Screen

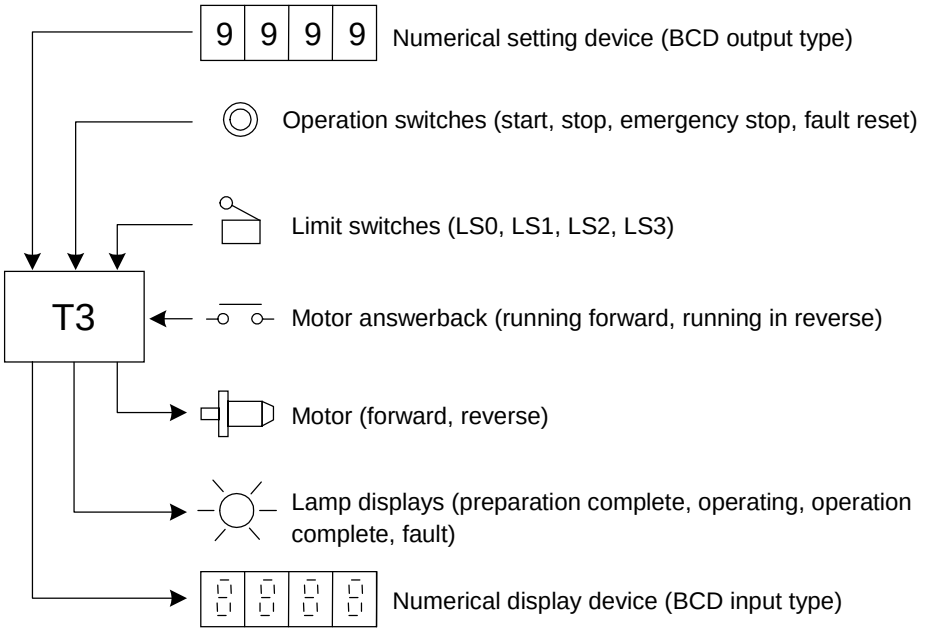
13. Retentive memory area
RW000 ~ [ ]
T000 ~ [ ]
C000 ~ [ ]
D0000 ~ [ ]

6. Programming Example

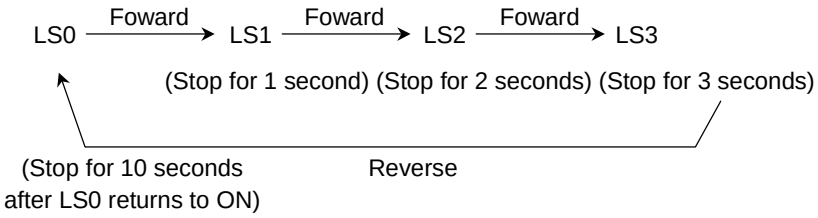
6.1 Sample system

In this section, simple sequences as examples, input/output allocation, program designing and also the procedures for the actual programming operation are shown. Refer to them when using the S2T.

Let us consider the sequence in the following diagram as an example



① When the 'Start' switch is pressed with LS0 in the ON state, the following operation is executed.



② The above operation is repeated only for the number of times set by the numerical setting device. During the operation, the 'Operating' lamp is lit and, at the same time, the actual number of executions at that time is displayed on the numerical display device.

When the operation is completed, the 'Operating' lamp will go out, and the 'Operation complete' lamp will be lit.

③ If the 'Stop' switch is pressed during the operation, the motor is stopped at that position and, after 1 second, starts in reverse. When the LS0 becomes ON, the motor is stopped and, after 1 second, the 'Preparation complete' lamp is lit.

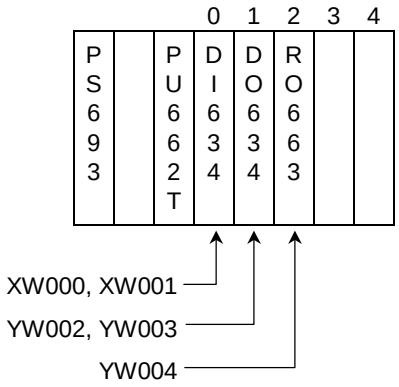
④ When LS0 is ON in states other than during operation, the 'Preparation complete' lamp is lit. The 'Start' switch is only effective when the 'Preparation complete' lamp is lit.

⑤ When the 'Emergency stop' switch has been pressed, the motor is stopped in that position and the 'Fault' lamp is lit. In that state, if the 'Fault reset' switch is pressed, the 'Fault' lamp will go out.

6.2 Input/output allocation

First decide the module configuration and make a Map of Correspondence between external signals and registers/devices. Here, the allocation is made for modules with the configuration shown below.

* Module configuration and register allocation



Rack : BU643D (for Basic, 3 I/O slots)
PS : PS693 (100-120/200-240 Vac)
CPU : PU662T (Standard)
Input : DI634 (32 points DC input)
Output : DO634 (32 points DC output)
RO663 (16 points isolated Relay output)

* Input/Output Map

XW000 (Numerical Setting Device)		XW001 (Switches)	
X0000	×10⁰	X0010	Emergency stop (normally ON)
01		11	Fault reset
02		12	Start
03		13	Stop
04	×10¹	14	
05		15	
06		16	
07		17	
08	×10²	18	LS0
09		19	LS1
0A		1A	LS2
0B		1B	LS3
0C	×10³	1C	Answerback forward
0D		1D	Answerback reverse
0E		1E	
0F		1F	

YW002 (Numerical Display Device)		YW003 (Lamps)		YW004 (Motor)	
Y0020	$\times 10^0$	Y0030	Fault	Y0040	Forward
21		31	Preparation complete	41	Reverse
22		32	Operating	42	
23		33	Operation complete	43	
24	$\times 10^1$	34		44	
25		35		45	
26		36		46	
27		37		47	
28	$\times 10^2$	38		48	
29		39		49	
2A		3A		4A	
2B		3B		4B	
2C	$\times 10^3$	3C		4C	
2D		3D		4D	
2E		3E		4E	
2F		3F		4F	

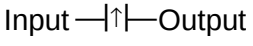
6.3 Sample program

A sample program of this sequence are shown on the following pages. When designing a program, arrange the conditions, and give them careful thought so that the program will follow the flow of operations as far as possible.

Here, the program is composed using basic instructions only. The following is a simple explanation of the instructions used in this program.

NO contact
Put output ON when the input is ON and the state of device Ⓐ is ON.

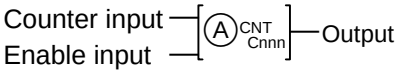
NC contact
Put output ON when the input is ON and the state of device Ⓐ is OFF.



Transitional contact (rising)
Put output ON only when the input at the previous scan was OFF and the input at the present scan is ON.

Coil
Put device Ⓐ ON when the input is ON, and put device Ⓐ OFF when the input is OFF.

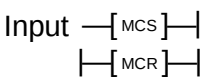
ON-delay timer
After the input has changed from OFF to ON, put output ON after the elapse of the time specified by Ⓐ. Also, at this time put the corresponding timer relay ON. (the 0.1 second timer in the example on the next page)



Counter
With the enable input in the ON state, count the number of times the count input is ON and store in counter register Cnnn. When the values of Ⓐ and Cnnn become equal, put output ON. When the enable input is OFF, clear Cnnn and put output OFF.

Binary conversion
When the input is ON, convert the value of BCD which has been stored in Ⓐ to a binary number and store in Ⓑ.

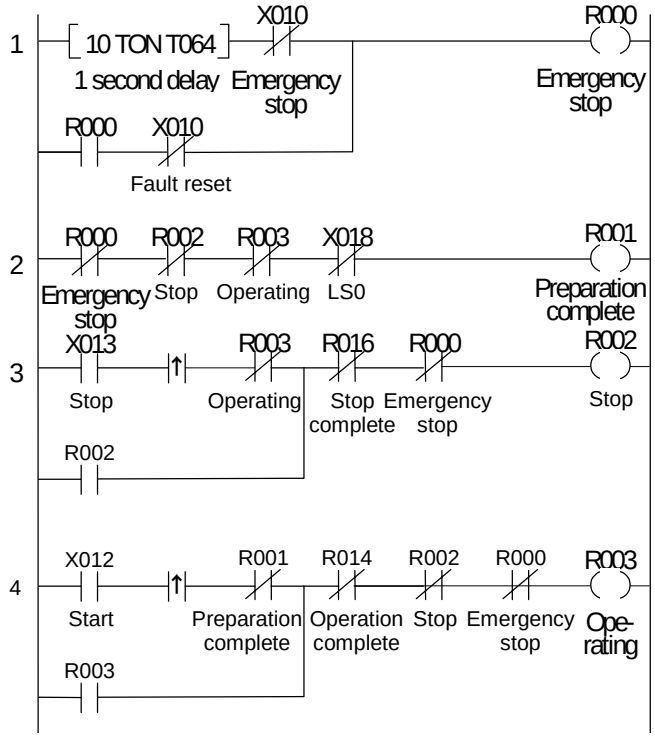
BCD conversion
When the input is ON, convert the value of Ⓐ to BCD and is store in Ⓑ.



Master control set/reset
Put the power rail between MCS and MCR ON only when the input of MCS is ON.

6. Programming Example

Operation Mode Setting Part



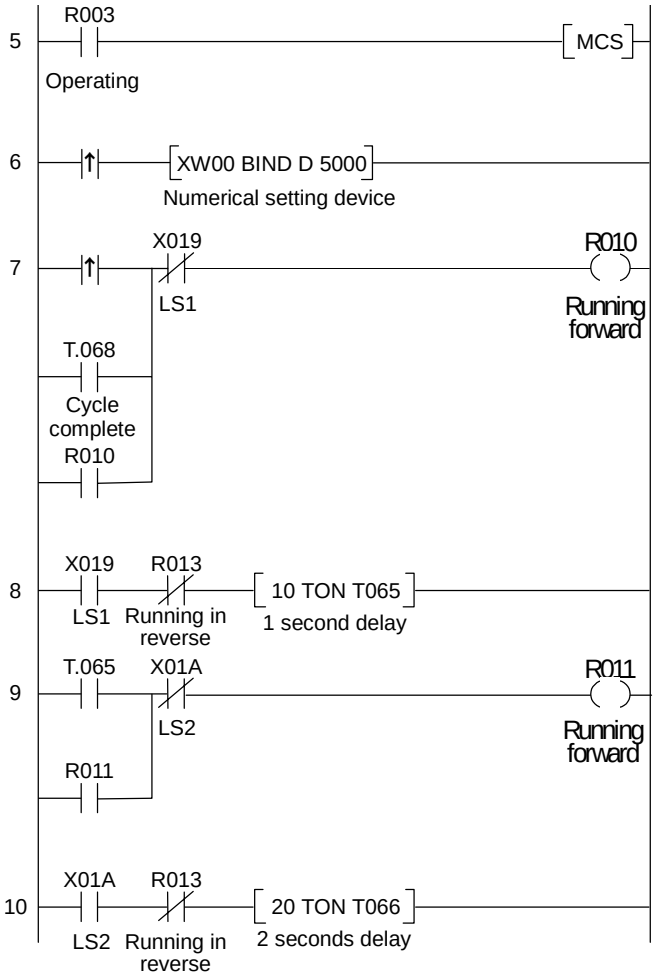
When 'Emergency stop' (X010: normally ON) is OFF, maintains R000 ON. R000 is reset by 'Fault reset' (X011) ON.

ON delay timer is to wait the establishment of the emergency stop signal.

When 'operating' (R003) is ON and 'Stop' (X013) is ON, the stop mode (R002) is ON. When 'Stop complete' (R016) is ON, R002 is put to reset.

When 'Preparation complete' (R001) is ON and 'Start' (X012) is ON, the operation mode (R003) is put ON. When 'Operation complete' (R014) is ON, R003 is put to reset.

Operating Sequence



When the operation mode (R003) is ON, the MCS-MCR is executed.

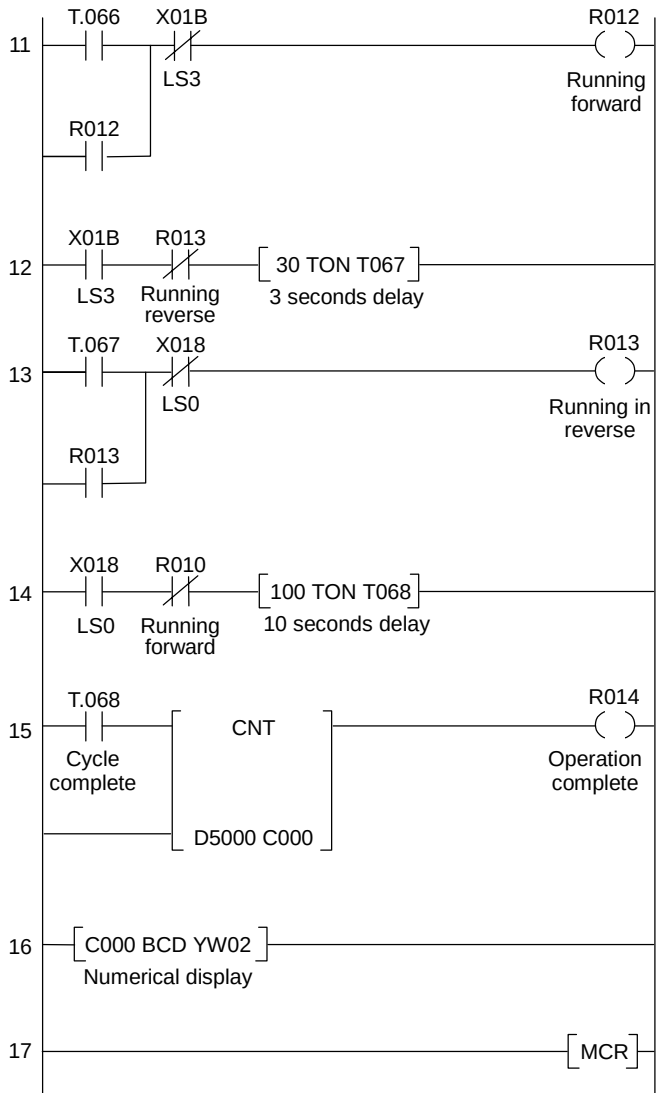
The value of the numerical setting device is binary-converted at the beginning of the operation, and is substituted in D5000.

R010 is put ON at the beginning of the operation. R010 is reset by LS1 (X019) being ON. When 'Cycle complete' (T.068) is ON also, in the same way, R010 is put ON.

T.065 is put ON after LS1 (X019) has been ON for 1 second.

When T.065 is ON, R011 is put ON and held. R011 is reset by LS2 (X01A) being ON.

T.066 is put ON after LS2 (X01A) has been ON for 2 seconds.



When T.066 is ON, R012 is put ON and held. When LS3 (X01B) is ON, R012 is reset.

T.067 is put ON after LS3 (X01B) has been ON for 3 seconds.

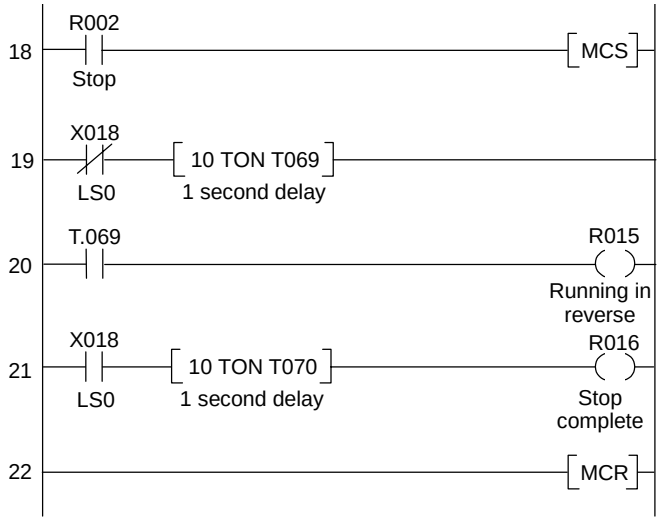
When T.067 is ON, R013 is put ON and held. When LS0 (X018) is ON, R013 is reset.

'Cycle complete' (T.068) is put ON after LS0 (X018) has been ON for 10 seconds.

The number of completed cycles are counted. When they equal the value (D5000) on the numerical setting device, 'Operation complete' (R014) is put ON.

The count value (C000) is converted to BCD and is outputted to the numerical display.

Stop Sequence

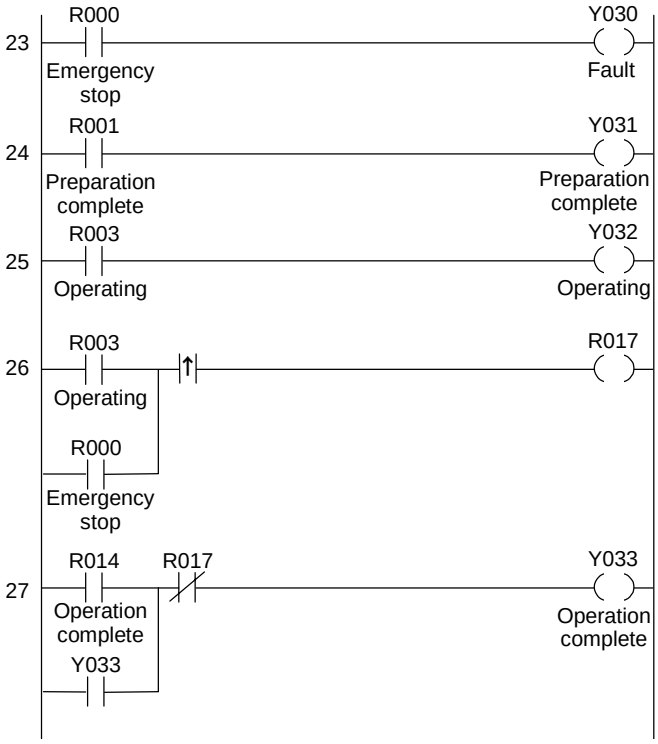


When the stop mode (R002) is ON, the MCS-MCR is executed.

When LS0 (X018) is OFF, T.069 and R015 are put ON after 1 second. If LS0 (X018) is put ON, T.069 and R015 are reset.

'Stop complete' (R016) is put ON after LS0 (X018) har 1 second.

Lamp Circuit



When 'Emergency stop' (R000) is ON, the 'Fault' lamp (Y030) is put ON.

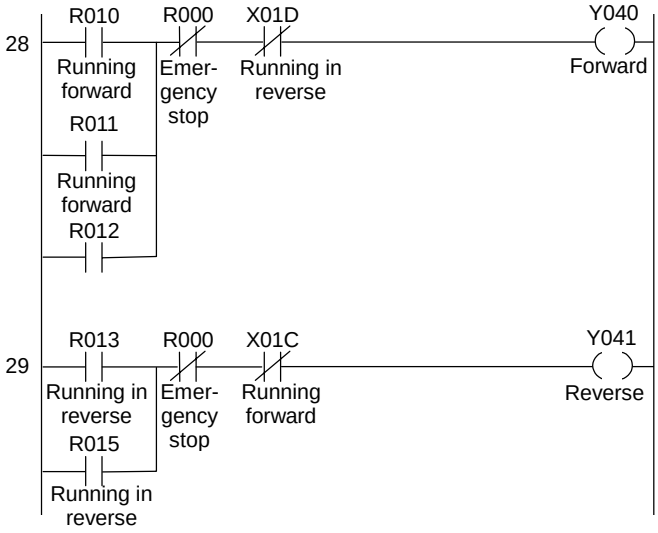
When 'Preparation complete' (R001) is ON, the 'Preparation complete' lamp (Y031) is put ON.

When 'Operating' (R003) is ON, the 'Operating' lamp (Y032) is put ON.

R017 becomes ON immediately the operation mode (R003) or 'Emergency stop' (R000) is put ON.

When 'Operation complete' (R014) is ON, the 'Operation complete' lamp (Y033) is put ON. When R017 is on, Y033 is reset.

Motor Circuit



When R010, R011, or R012 is ON, 'Forward' (Y040) is put ON. This is interlocked by the 'Running in reverse' answerback (X01D).

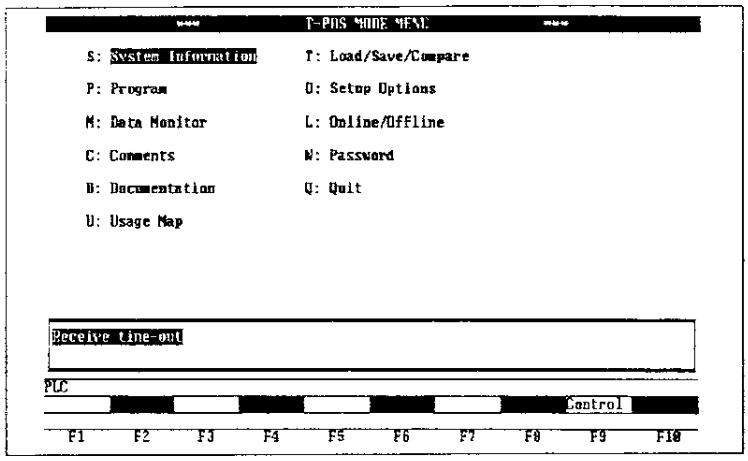
When R013 or R014 is ON, 'Reverse' (Y041) is put ON. This is interlocked by the 'Running forward' answerback (X01C).

Program End

6.4 Programming procedure

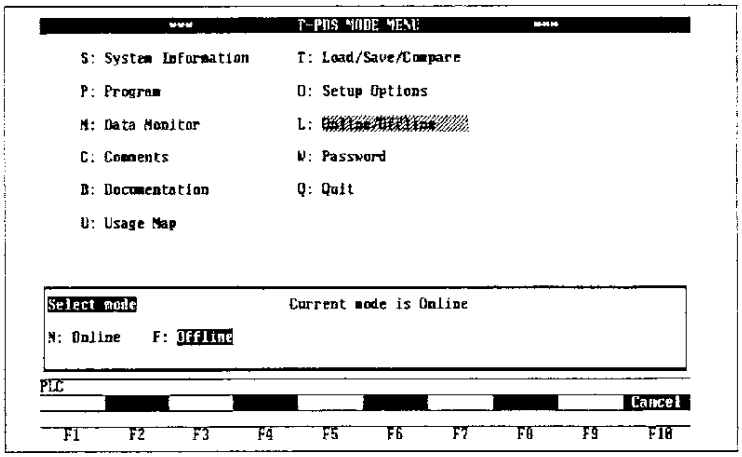
Here, the procedures for actually writing this program to the S2T using the programmer (T-PDS) are shown. (An operational example of T-PDS version 2.0)

(1) Turn the programmer power ON, startup the T-PDS by keying in TPDS [Enter].
(T-PDS initial Menu Screen)

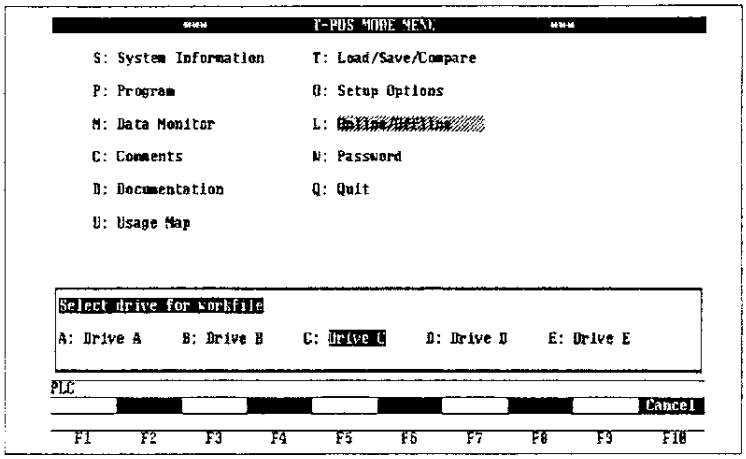


In the initial state, the T-PDS starts up in the communication mode with the PLC (S2T). Therefore, in the state when it is not connected to the S2T, “Receive time-out” is displayed on the screen.

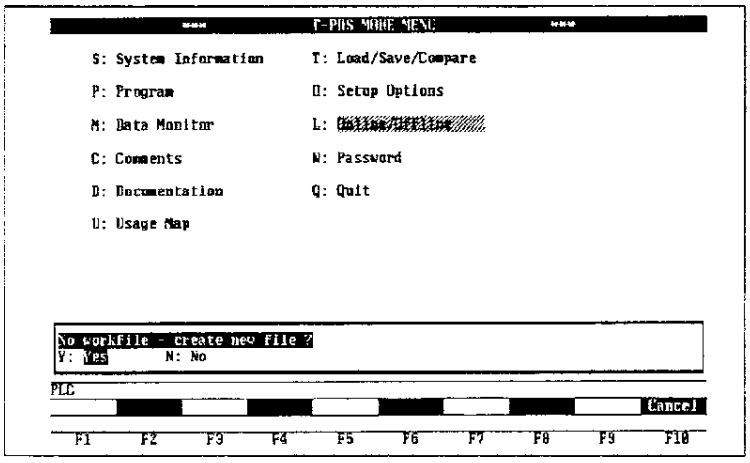
(2) In order to carry out off-line programming, change to off line mode. Select “L: Online/Offline”, key-in L.



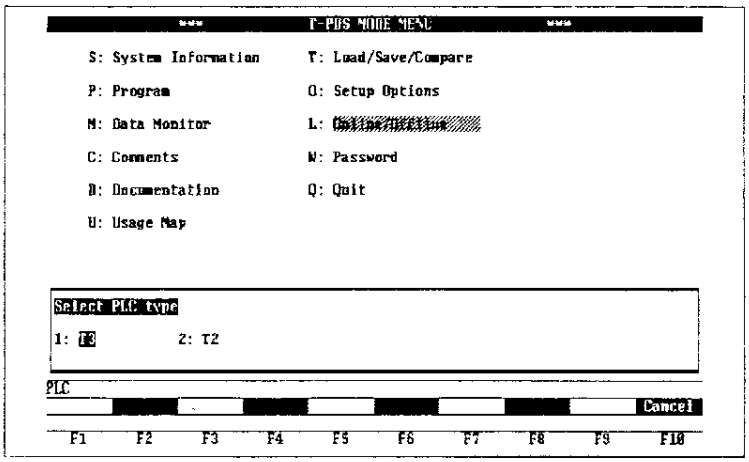
Here, select “F: Offline”.
Key-in F.



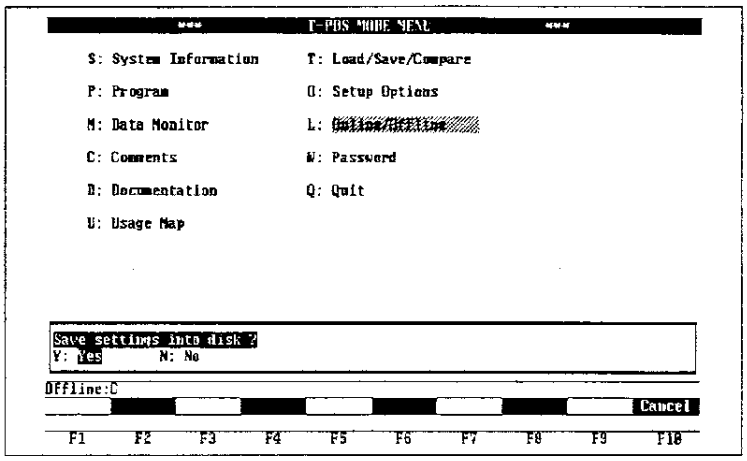
This sets the selection mode for the disk drive in which to create the off-line work file. Here, select “C: drive C” by keying-in C.



The programmer is now waiting for confirmation the creation of a work file. Key-in Y.

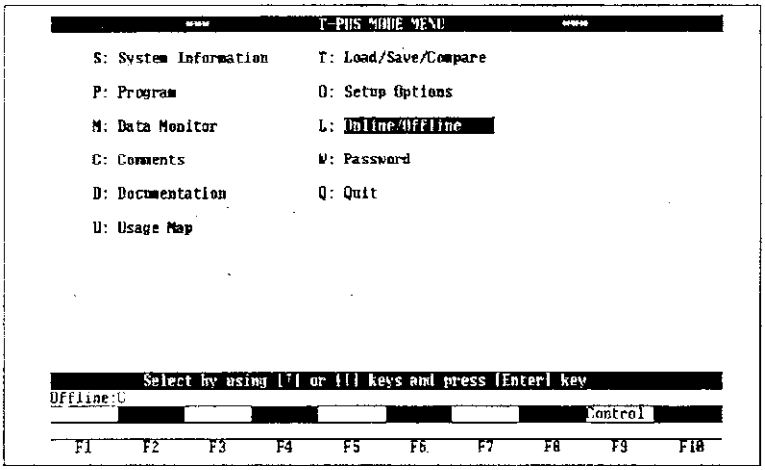


Next, the PLC model will be requested. Select “6: T3H” by keying-in 1.

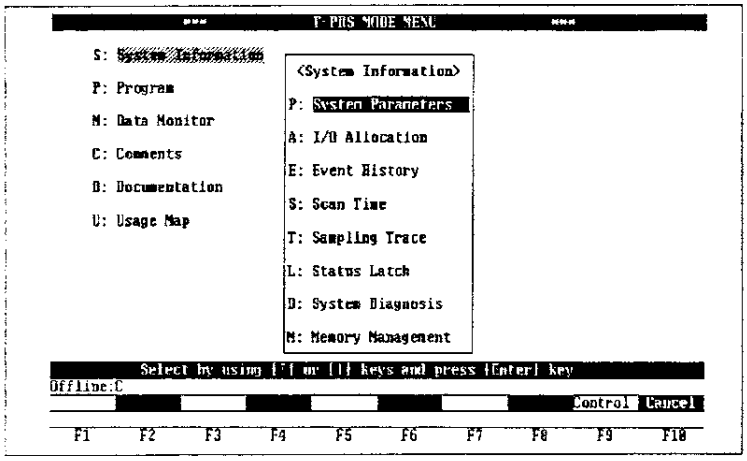


The T-PDS mode is changed to offline mode.
“Offline C: ” is displayed at the bottom left of the screen.

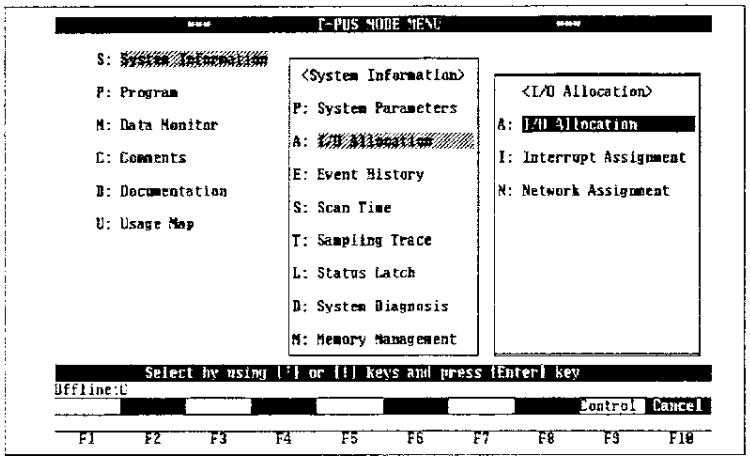
Since you are asked whether to record the settings, select “Y: Yes”. By this means, the next time the T-PDS starts up, it will start up with the work file in drive C as the target.



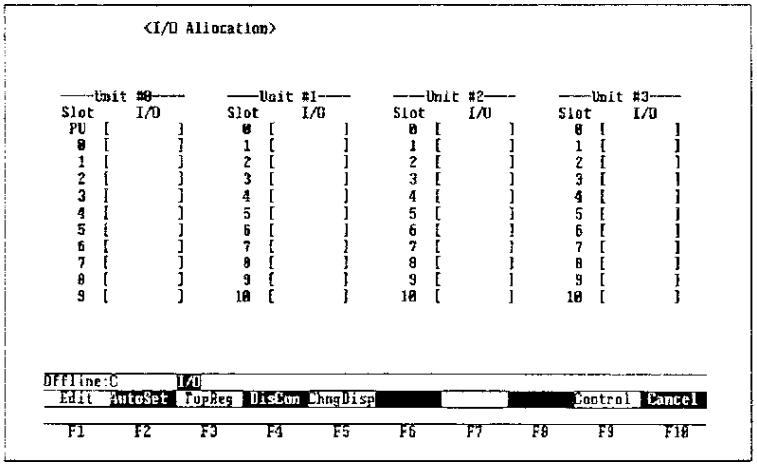
(3) Next carry out the I/O allocation. From the initial menu state, select "S: System information". Key-in S.



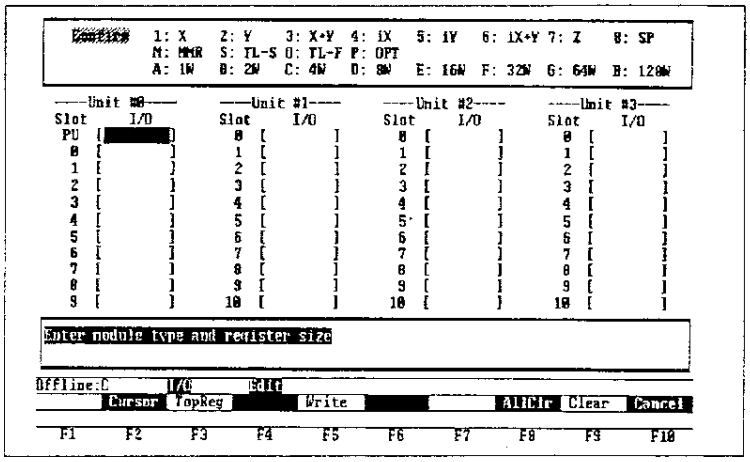
Here, select "A: I/O allocation information". Key-in A.



Then, key-in A to select "A: I/O allocation".



In offline programming, manual I/O allocation is carried out. Therefore, select F1 (Edit) on the command line. A cursor will appear on the screen.



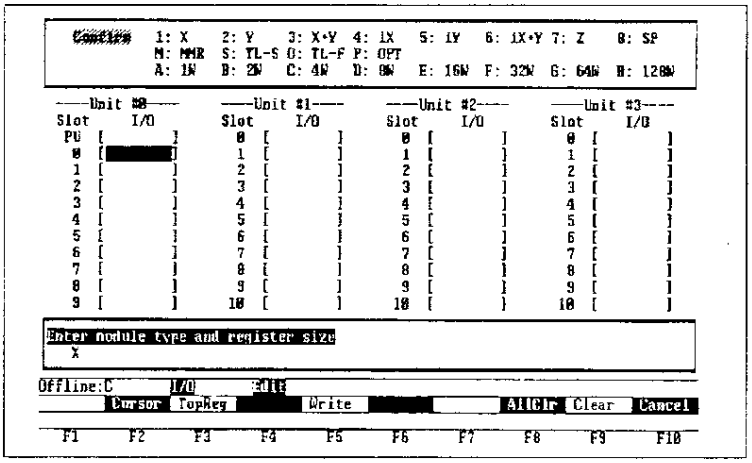
Because the module configuration has been decided in Section 6.2, carry out the following settings as the input/output allocation.

---- Unit #0 ----

Slot	I/O
PU	[ ]
0	[X 2W] ← DI634 (32 pts input)
1	[Y 2W] ← DO634 (32 pts output)
2	[Y 1W] ← RO663 (16 pts output)

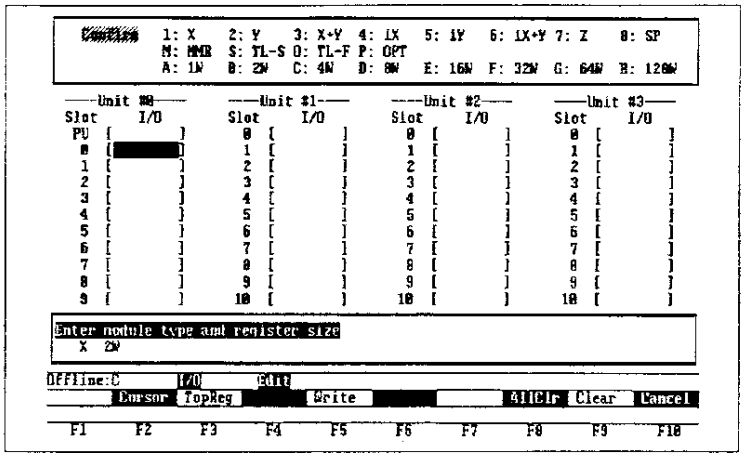
To set the module type, move the cursor to the specified slot position. Then designate by combining a function division (X, Y, etc.) and the number of the register occupied (1W, 2W, etc.) from the selection list displayed in the upper part of the screen.

First, move the cursor to Unit #0, Slot 0, using the cursor keys. Then, key-in 1 to designate “1: X”.



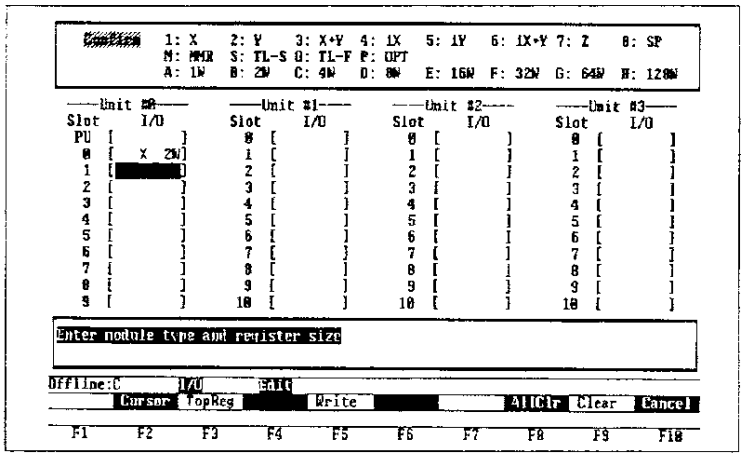
6. Programming Example

Next, key-in B to designate “B: 2W”.



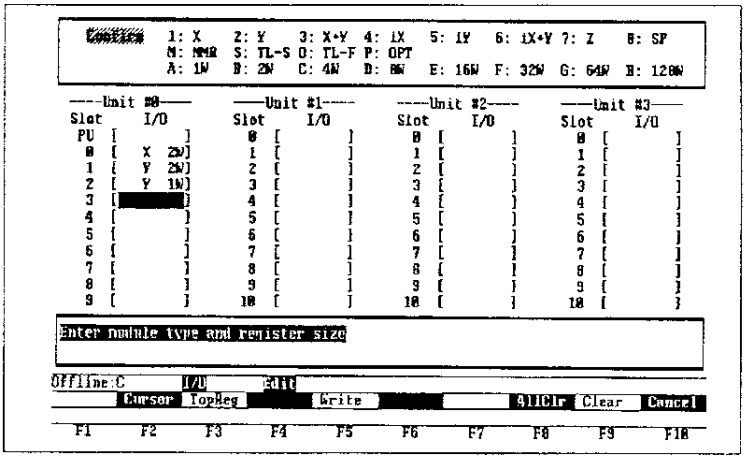
“X 2W” is displayed as the module type at the bottom of the screen.

Set the module type into the slot at the cursor position. Key-in [Enter].

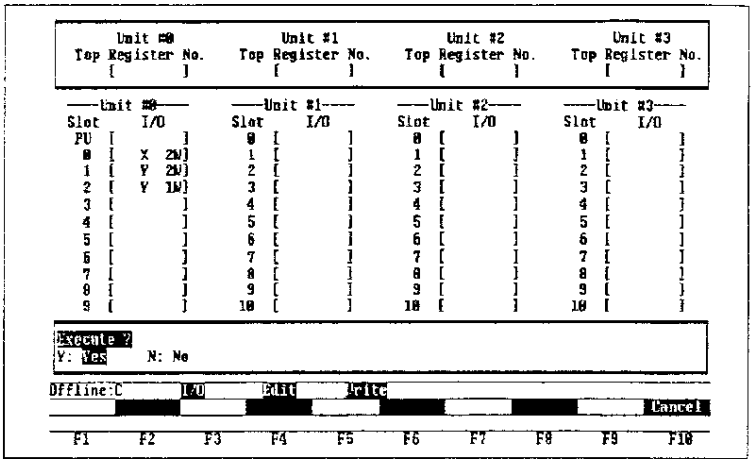


“X 2W” is displayed at the Unit #0, Slot 0 position, and the cursor moves to the next slot.

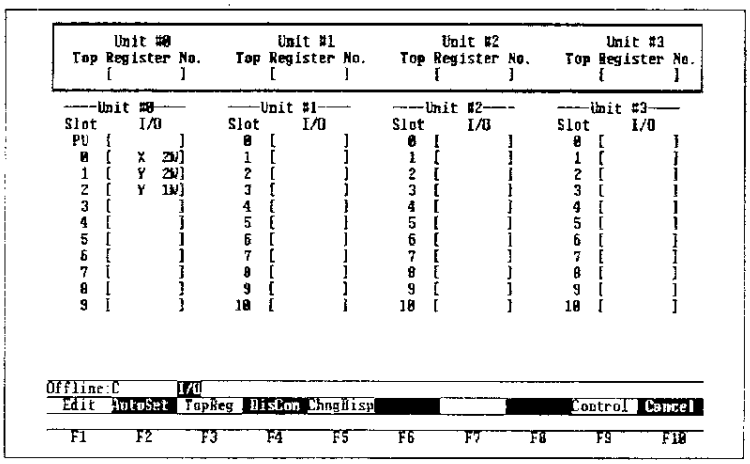
Hereafter, carry out the required settings using the same procedure.



After completing required settings, write this information in the work file. Select F5 (Write) from the command line.

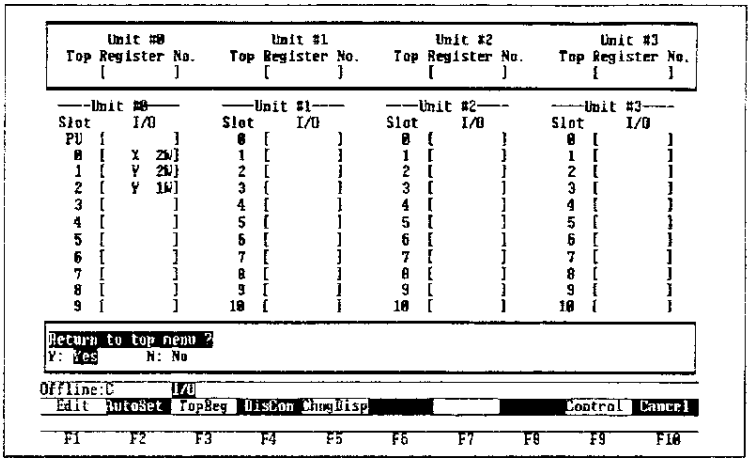


The programmer will wait for confirmation. Key-in Y.

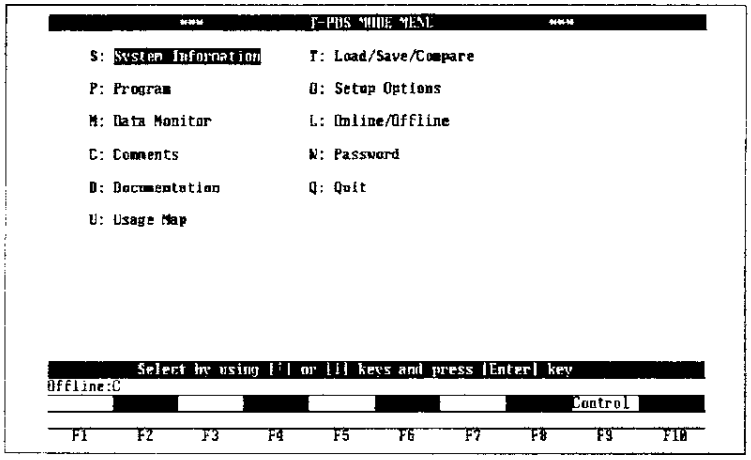


This completes the I/O allocation.

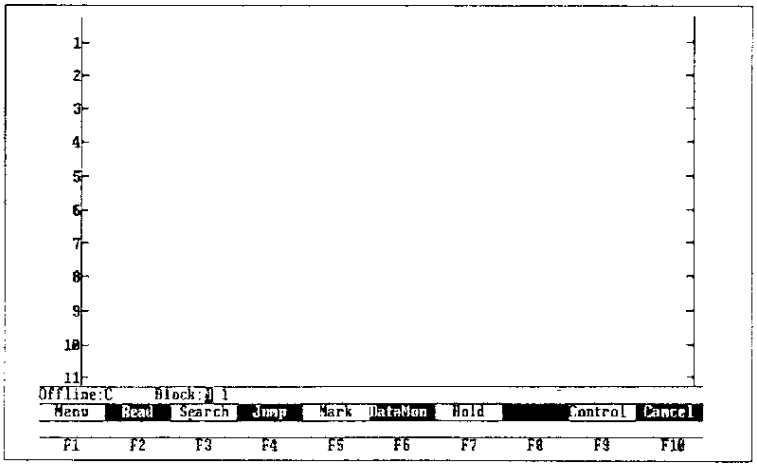
(4) Now we enter the program typing phase. First, press the [Esc] key to return to the initial menu.



The programmer will wait for confirmation. Key-in Y.

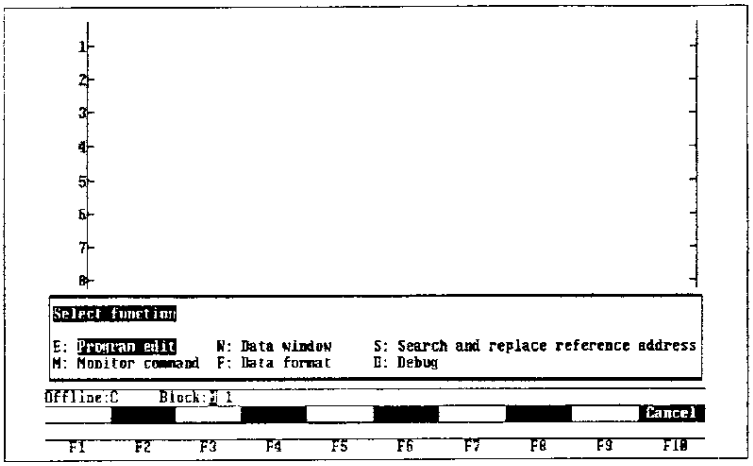


Here, select “P: Program”. Key-in P.

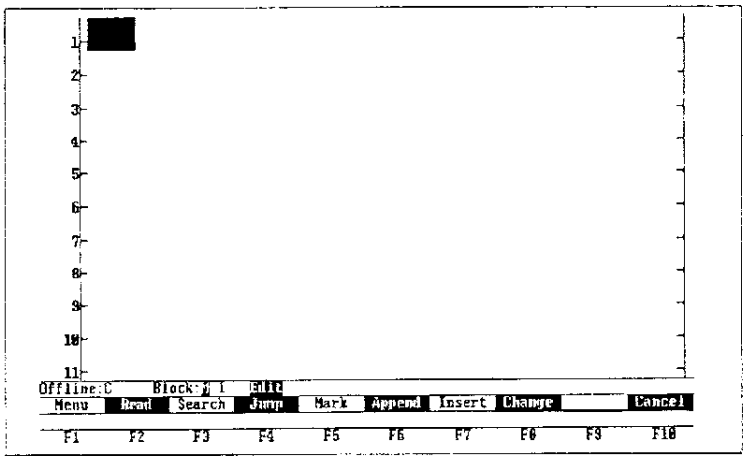


Block 1 of the main program is automatically selected, and “Block: M1” will be displayed on the screen.

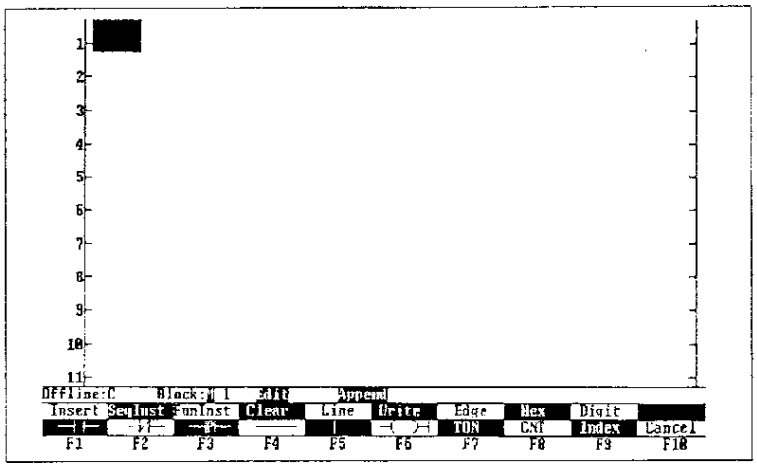
Here, select F1 (Menu) from the command line.



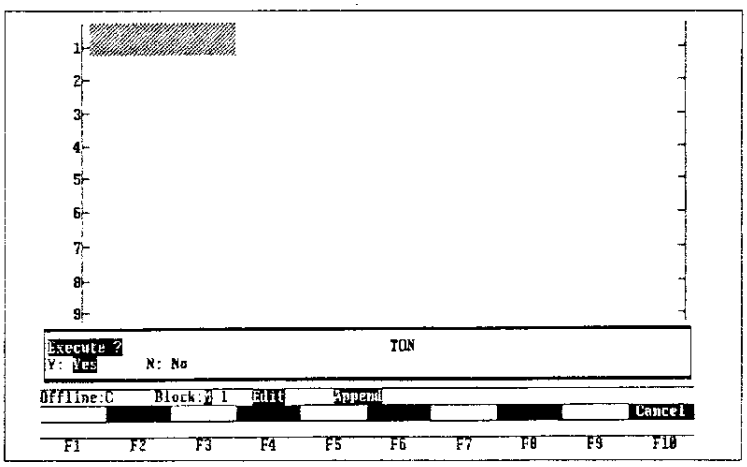
Then, select “E: Program Edit” from the menu window and key-in E. A cursor will appear on the screen.



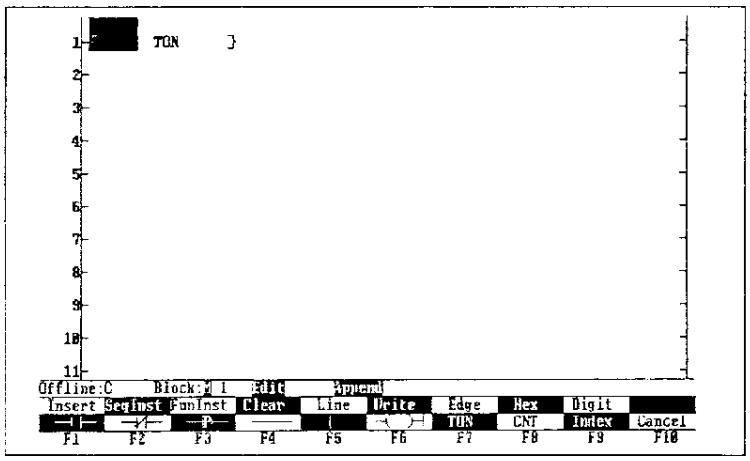
Here, select F6 (Append) from the command line. Then, instruction symbols will appear on the command line.



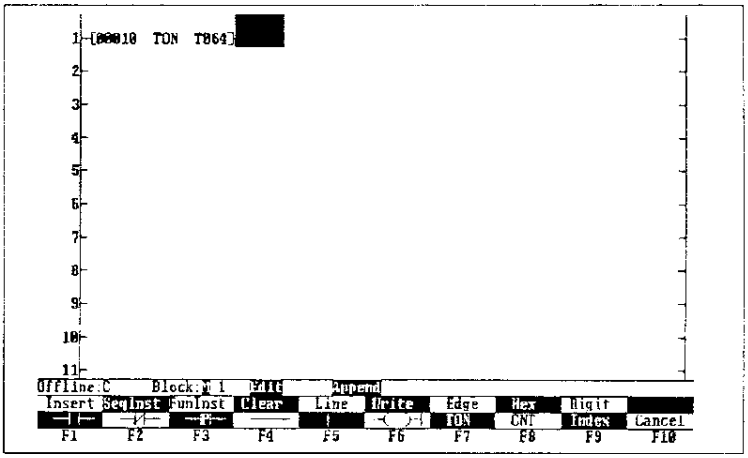
Here, start typing in the program in Section 6.3.
First, press F7 (TON).



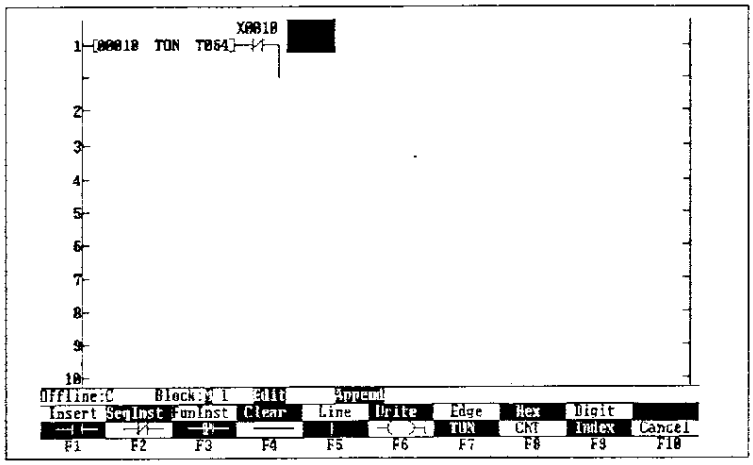
Since the programmer is waiting confirmation, key-in Y.



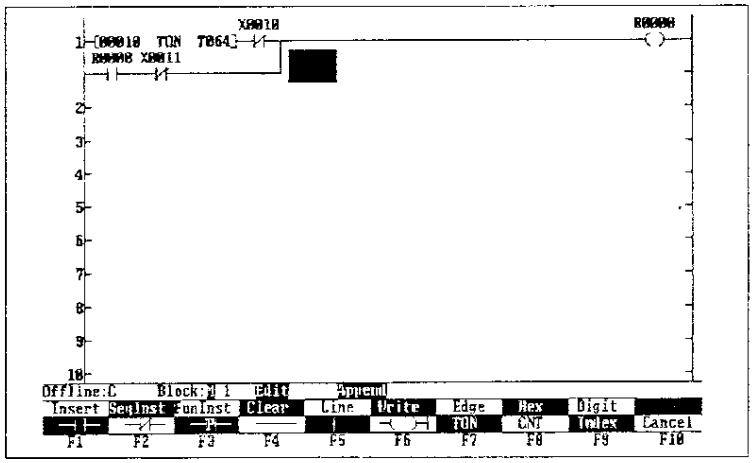
Input the operands (setting value and timer register).
Key-in
10 [Enter]
T64 [Enter]
If you make a mistake, cancel it with the Space key and re-input.



Next, input the NC contact of X010 (with vertical connection).
Key-in
F2 (—|/|—)
F5 (I)
X10 [Enter]



Complete the 1st rung using the same procedure, as follows.
Key-in
F6 (—( )—|) R0 [Enter]
F1 (—| |—) R0 [Enter]
F2 (—|/|—) X11 [Enter]
F4 (-) [Enter]
F4 (-) [Enter]

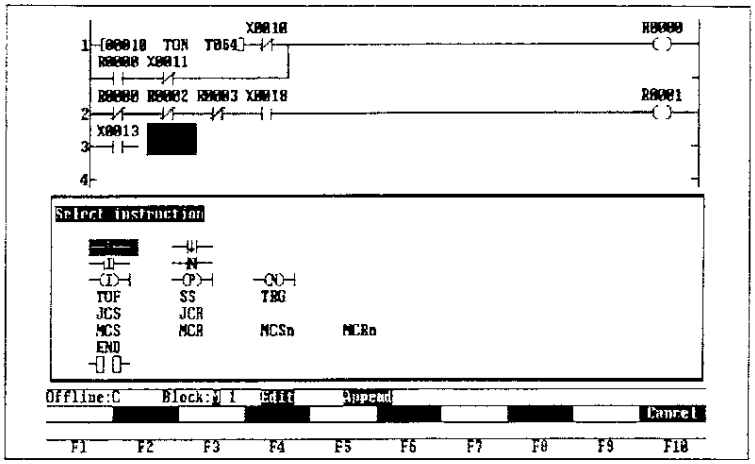


Next, move to the head of the 2nd rung using the cursor keys, and input the 2nd rung using the same procedure as for the 1st rung. Then input the 3rd and 4th rungs.

6. Programming Example

While doing this, when an instruction for which the symbol is not displayed on the command line such as a transitional contact, display the Menu Window by pressing Shift + F2 (Seq Inst), and then select.

(Screen state when Shift + F2 (Seq Inst) has been pressed)



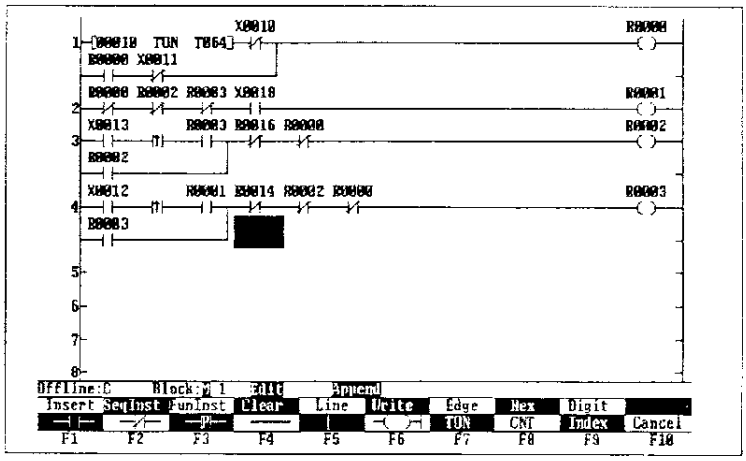
When input has been completed as far as the 4th rung, write the 1st to 4th rungs into the work file.

In other words, the size of program which is writable to the work file at any one time is one screen size (11 lines by 12 columns). Therefore, this means writing to the work file at convenient divisions of rungs.

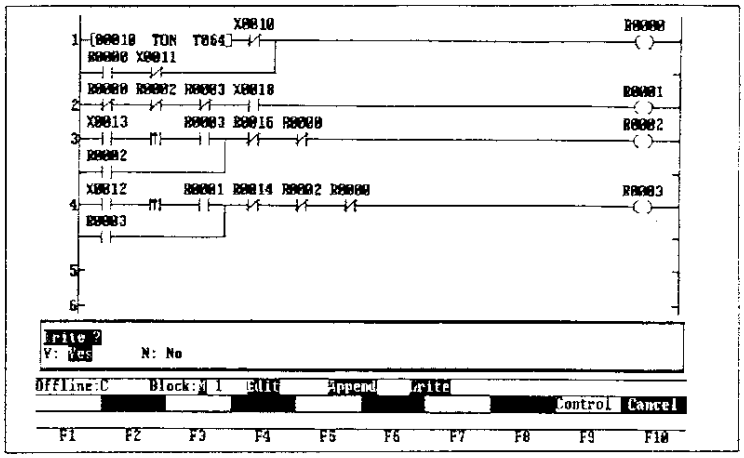
(The cursor also will move within the screen limits in the Edit mode).

Carry out the operation of writing to the work file as follows:

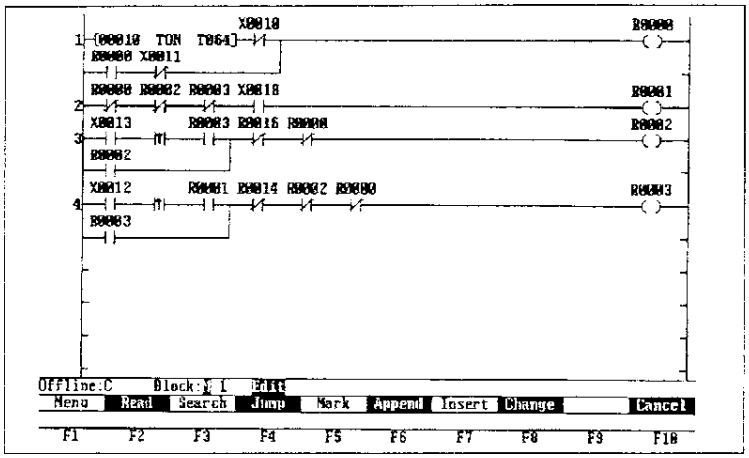
(State with input up to the 4th rung complete)



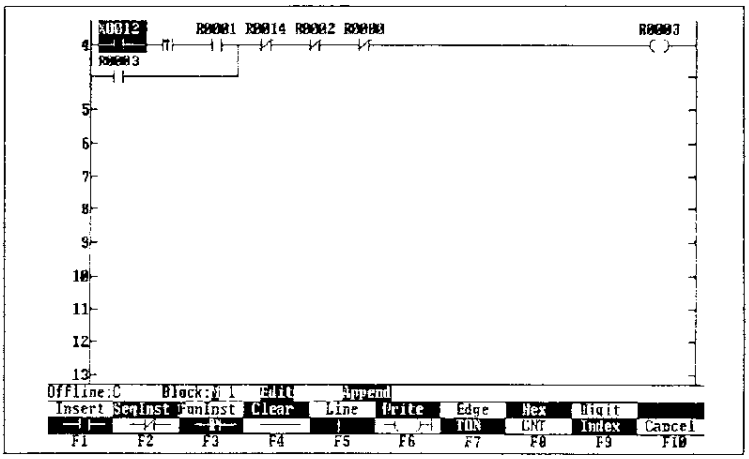
Key-in Shift + F6 (Write).



Because the programmer is awaiting confirmation, key-in Y.



In this way, the 1st to 4th rungs have been written to the work file. Next, input the 5th rung onward. Move the cursor onto the 4th rung using the cursor keys (the cursor can move over existing rungs only), and press F6 (Append). The screen will then turn to an edit screen with the 4th rung leading.

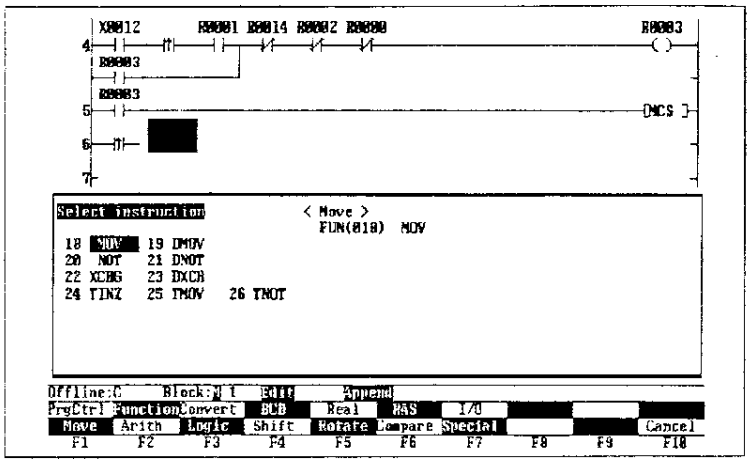


6. Programming Example

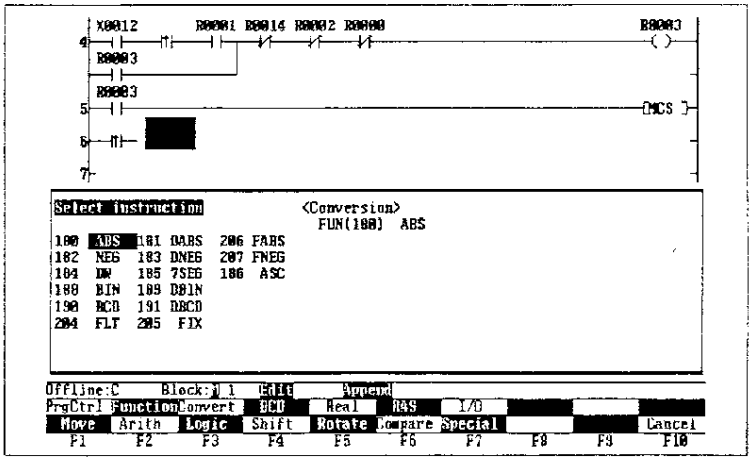
Move the cursor to the head of the 5th rung, and start entering the program from there onward.

To input the Function instructions such as BIN, key-in Shift + F3 (Fun Inst) to display Function instructions, then select the instruction group which contains the desired instruction.

(Screen state when Shift + F3 (Fun Inst) has been pressed)



(State when Shift + F3 (Convert) is pressed on the above screen)



Hereafter, write the whole program using the same procedure.

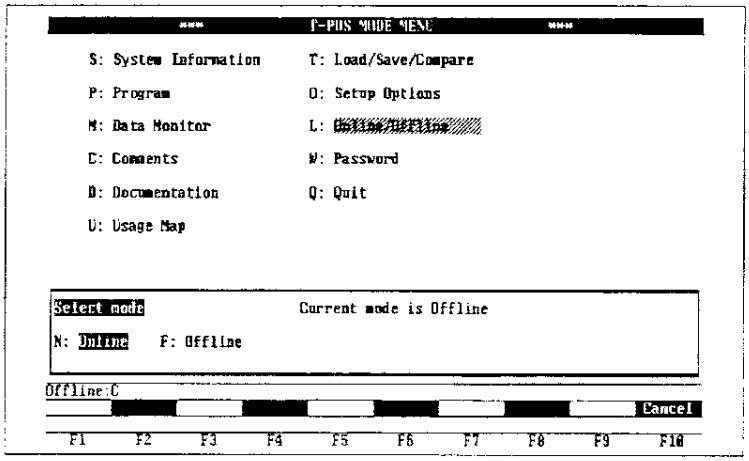
(5) When the whole program has been written in work file in the operation up to this point, load the program into the S2T.

First, connect the S2T and the T-PDS with the dedicated cable. (This assumes that the modules in Section 6.2 are mounted in the S2T)

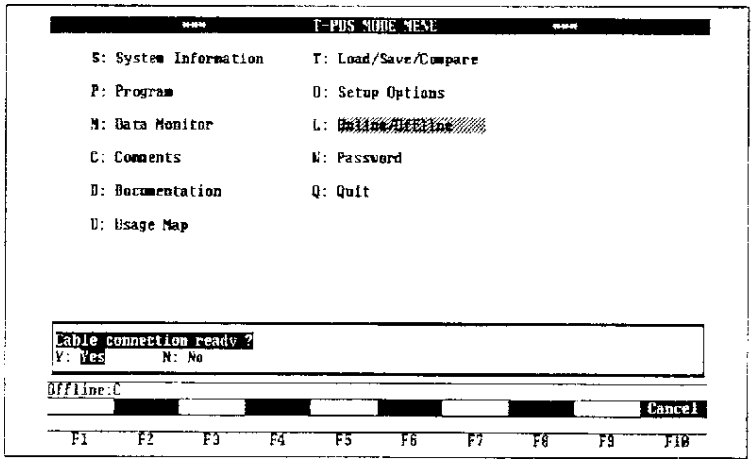
Next, put the RAM/ROM switch on the CPU to RAM, the operation mode switch to the RUN position, and turn on power to the S2T. (The S2T will start up in the HALT mode)

(6) Put the T-PDS into communication mode with the PLC (S2T).

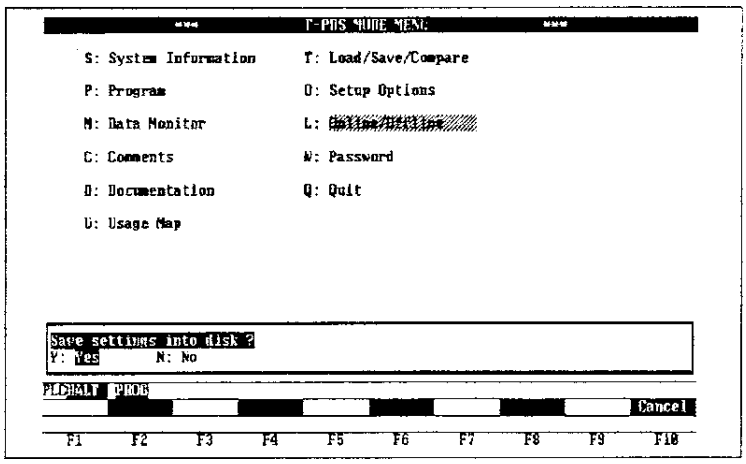
First, return the T-PDS display to the initial menu by pressing [Esc] [Enter], and then select “L: Online/Offline”.



Here, select “N: Online” to select online mode. Key-in N.



Confirm the connection state and key-in Y

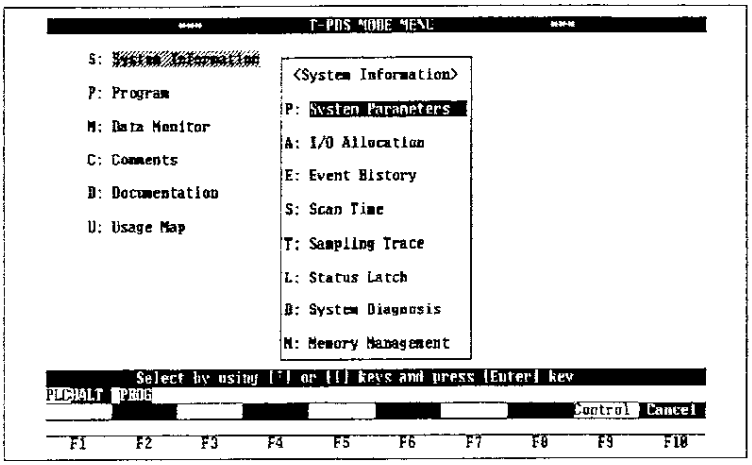


When the communication of the T-PDS with the S2T is correctly connected, “PLC HALT” message will be displayed at the bottom left of the screen.

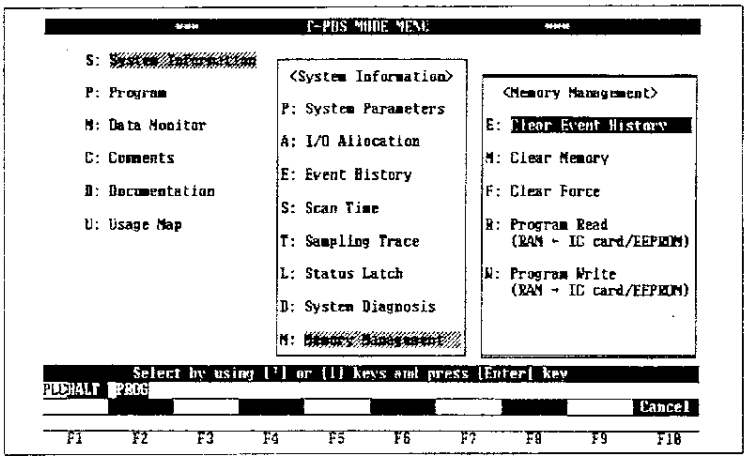
Although the record of settings is not always required, here, select “Y: Yes”.

Now the T-PDS has been changed to the online mode.

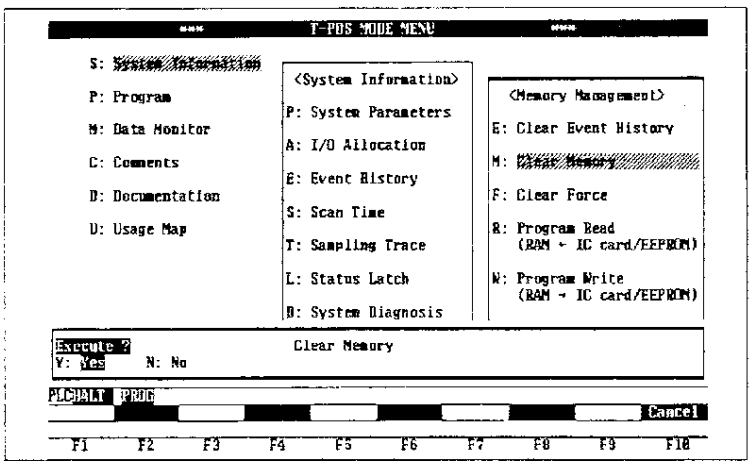
(7) Next, clear the memory of the S2T. Select “S: System Information”. Key-in S.



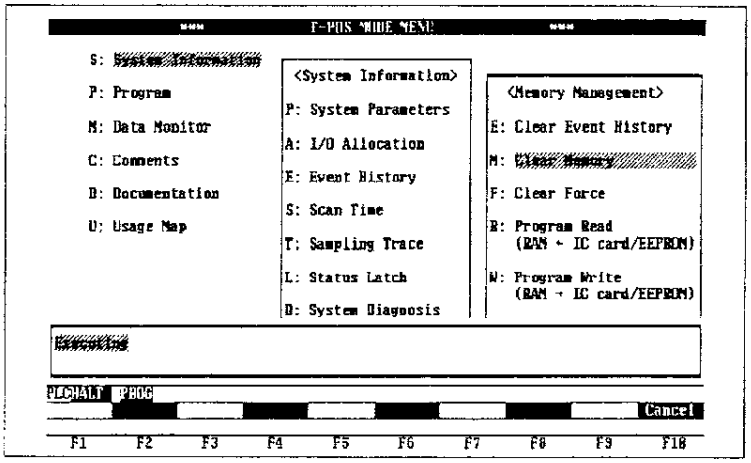
Here, select “M: Memory Management” from the <System Information> menu. Key-in M.



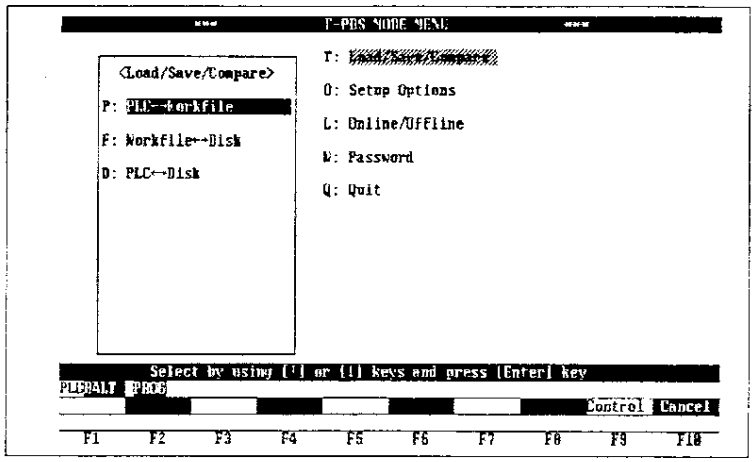
Next, select “M: Clear Memory” from the <Memory Management> menu. Key-in M.



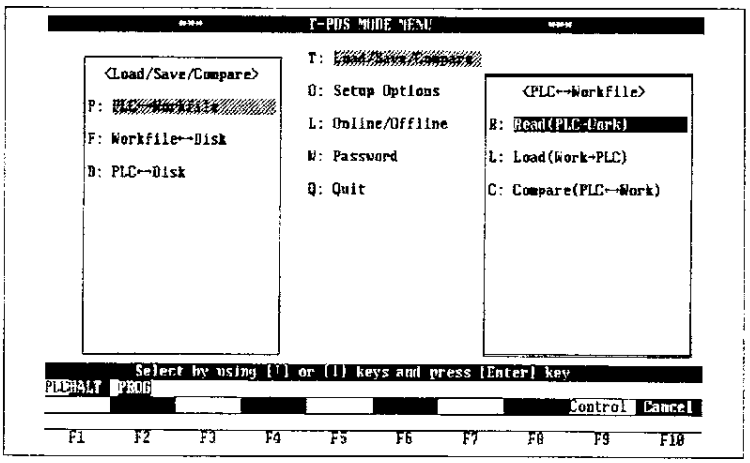
The programmer will await execution confirmation. Execute Clear by keying-in Y.



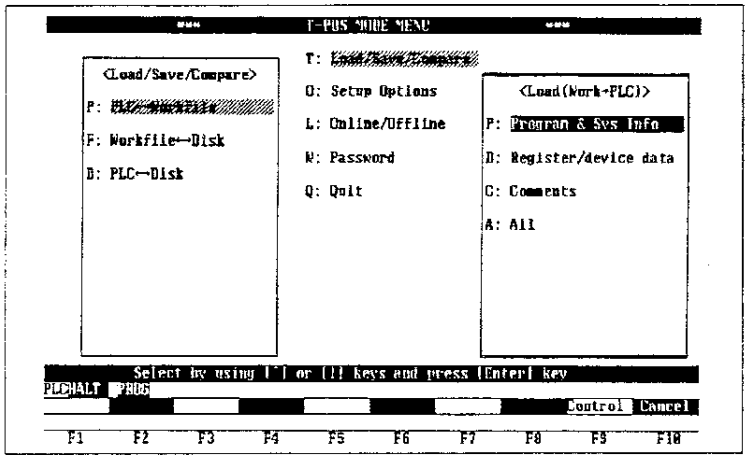
(8) Next, transfer (load) the program which has been written in the work file to the S2T. First, display the initial menu by pressing [Esc] [Enter], and then select “T: Load/Save/Compare”.



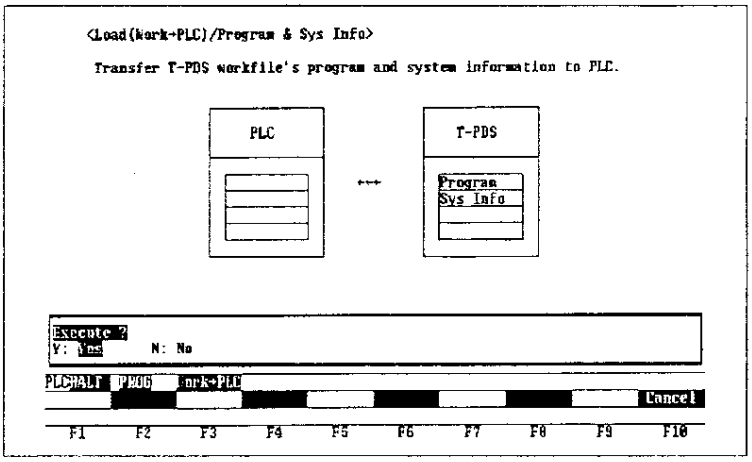
Here, select “P: PLC ↔ Work File” from the <Load/Save/Compare> menu.



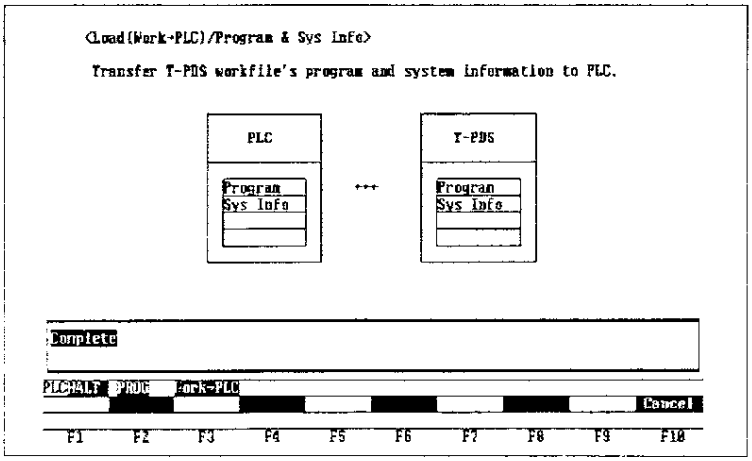
Then, select “L: Load (Work → PLC)” from the <PLC ↔ Work File> menu.



The selection menu for loading details is displayed. Since it is simply the program in this example, select “P: Program & Sys Info”.

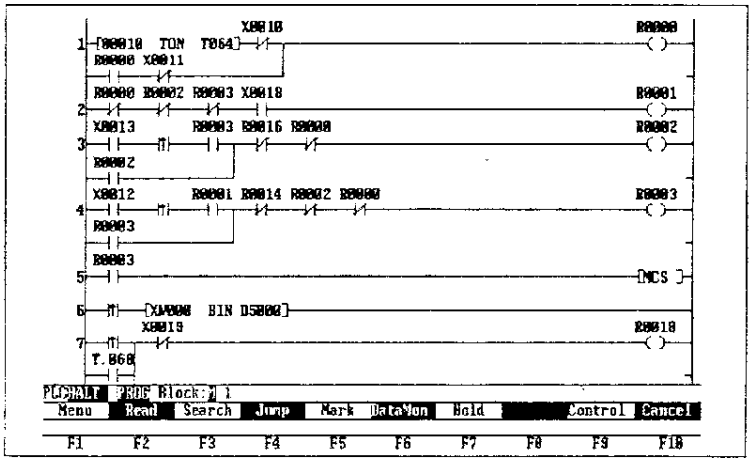


The programmer will await execution confirmation. Key-in Y.



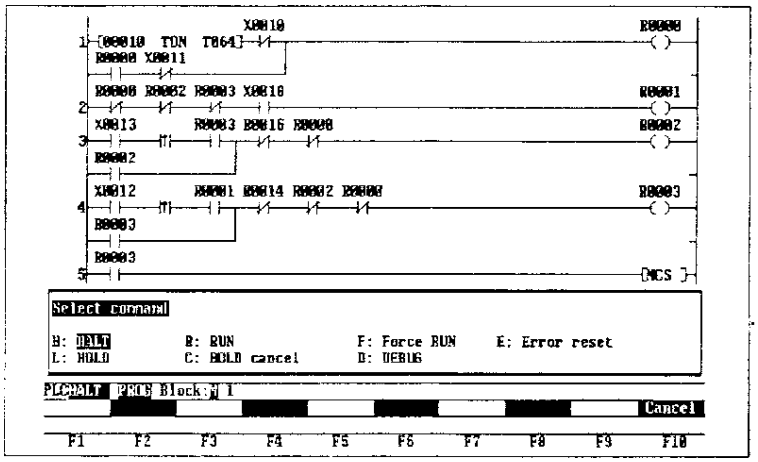
When correct loading has been carried out “Complete” will be displayed.

(9) When the loading of the program has been completed by the above operations, operate the S2T (RUN mode) and debug the program. Here, try to change the S2T mode by the Control command of the T-PDS. First display the initial menu by pressing [Esc] [Enter], and then select “P: Program”.



The T-PDS will enter the monitor mode for the program which has been loaded in the S2T.

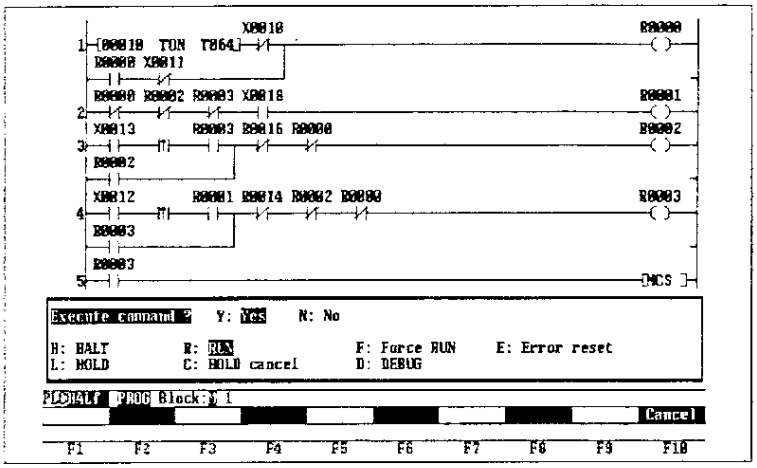
Here, select F9 (Control) from the command line.



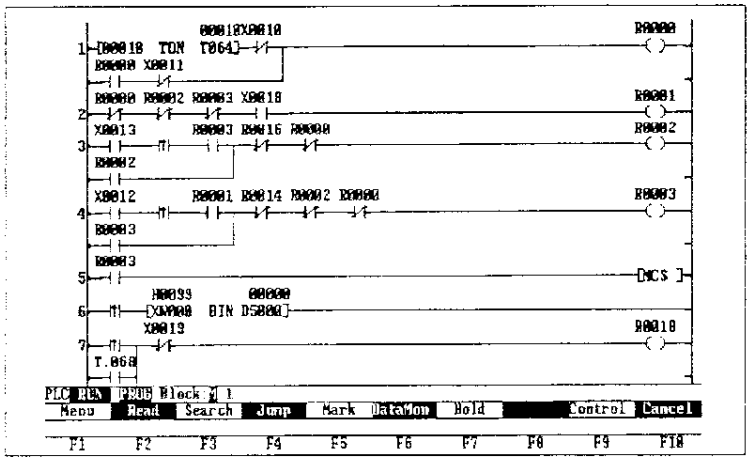
NOTE

When the S2T is put into the RUN mode with the aim of program debugging and test running, take thorough precautions for safety, such as switching OFF the motive power circuit.

Select “R: RUN” from the menu window.



The programmer will await execution confirmation, key-in Y after rechecking the safety of the surroundings.



“PLC: RUN” will be displayed on the screen. This is the monitor screen for the program execution state.

Perform confirmation of operation by using the external simulation switch and the T-PDS simulation input function (Force function). For operation, see separate T-PDS operation manual.

When carrying out program correction/modification, stop the S2T temporarily (put into the HALT mode), and correct/modify the program in the S2T.

When carrying out creation/modification of the program while still in the online mode, the operations are the same as in to offline mode.

(10) When program correction and operation check are completed, save the program in the disk and switch OFF the S2T power.

To finish with the T-PDS, press [Esc] [Enter] and select “Q: Quit” in the state with the initial menu displayed.

The above completes the programming procedure. If the S2T’s RAM/ROM switch is put to ROM and the Operation Mode switch is put to RUN, the S2T will operate automatically when power is next switched ON.

NOTE

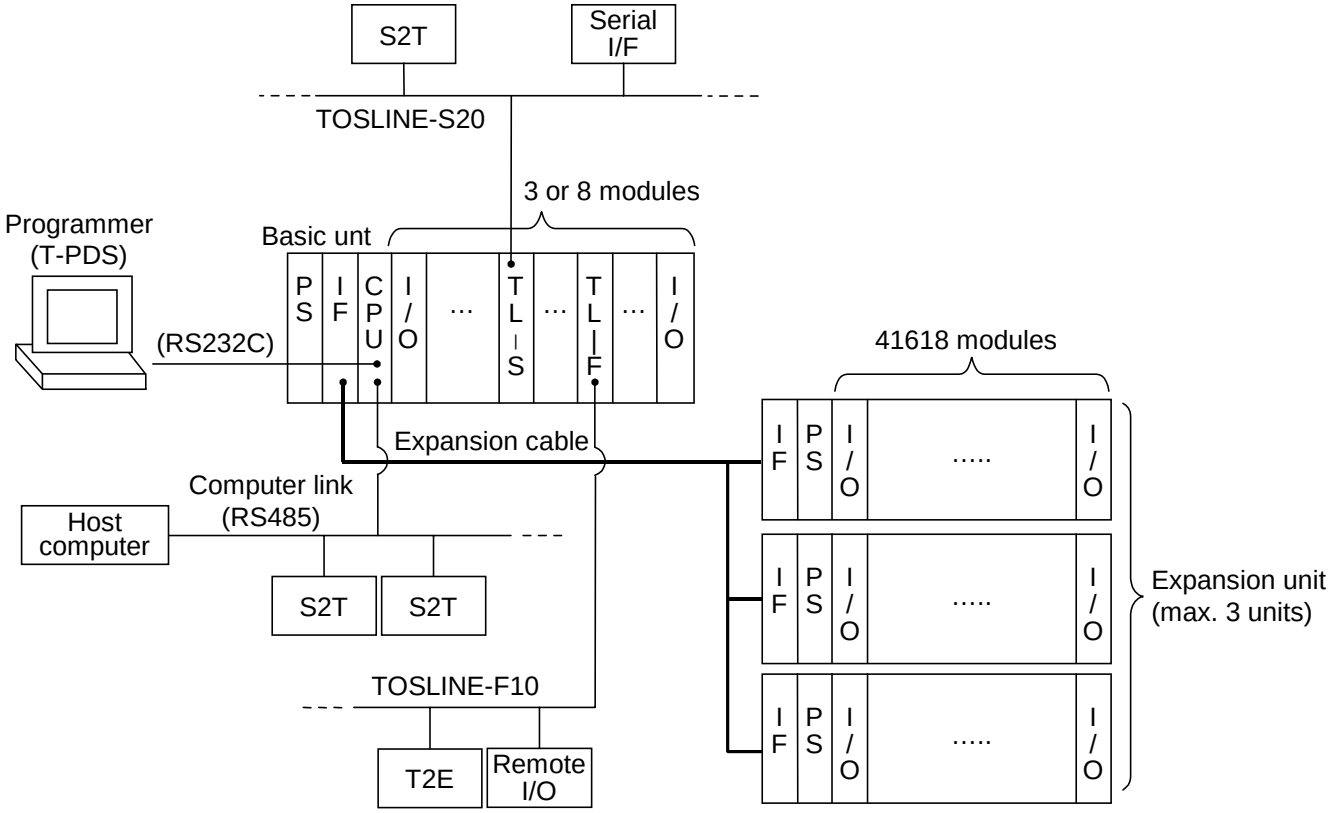
In the case of a CPU with a built-in flash memory, write the program into the flash memory before the above procedure (10).
The operation can be performed by selecting “W: Program Write” from the <Memory Management> menu. (See the screen on the procedure (7)).

PART 2

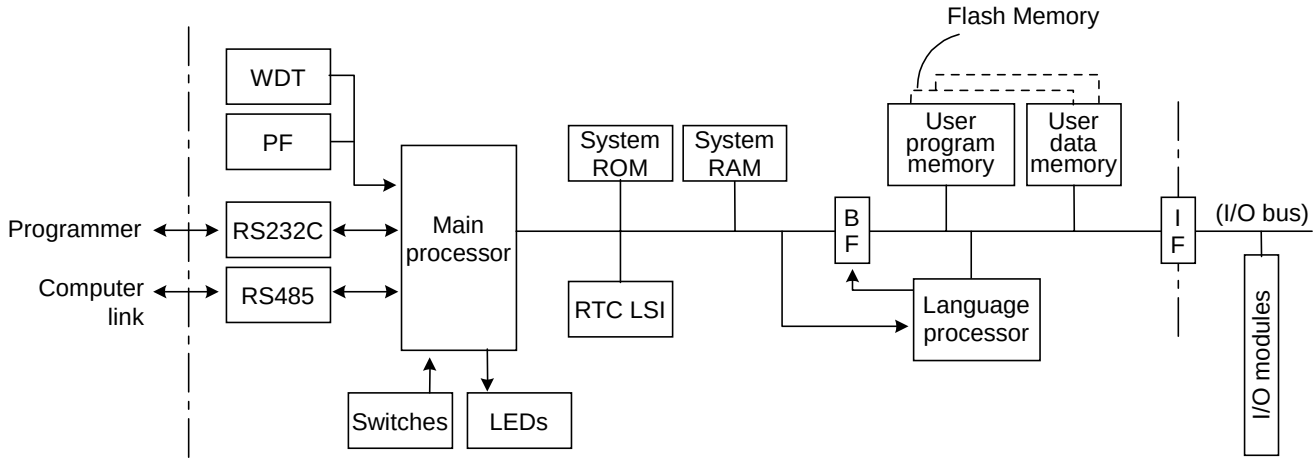
FUNCTIONS

1.1 S2T System configuration

The S2T system configuration is shown in the figure below. Part 2 explains the S2T system functions, concentrating on the S2T CPU functions.



The internal block diagram of the S2T CPU is shown below.



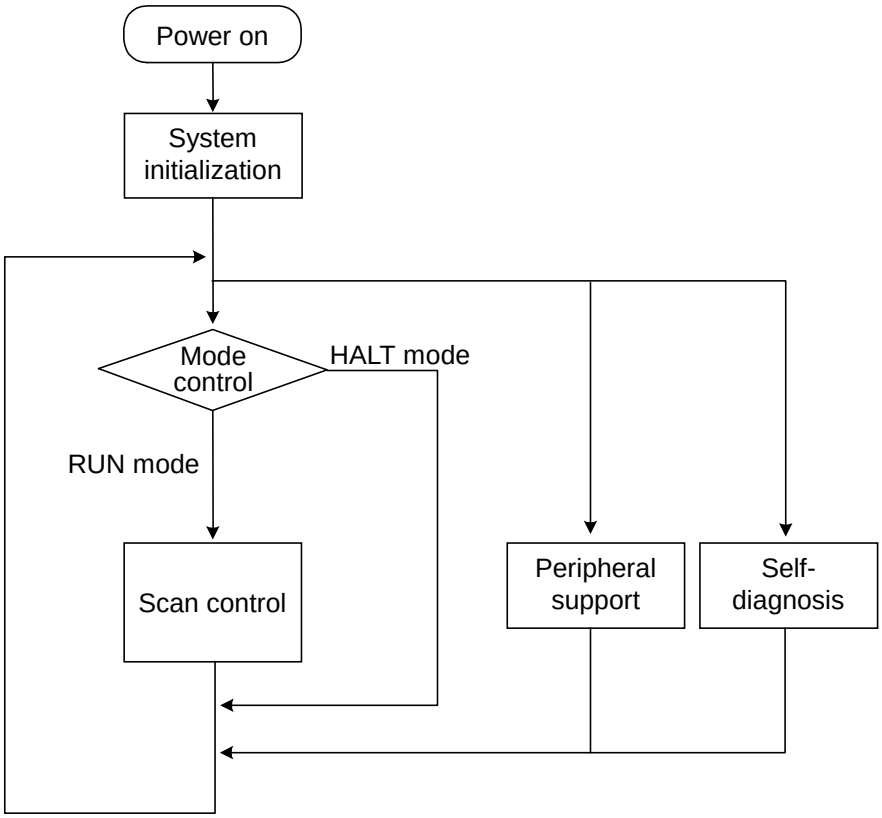
The Main processor controls overall execution tasks. The Language processor (LP) works as co-processor and executes the user program (bit operation and word operation). These two processors work in parallel during scan operation.

1.2 Functional specifications

Item		Specification
Control method		Stored program, cyclic scan system
I/O method		Batch I/O (refresh), Direct I/O, or combination
Number of I/O points		1024 points (when 32 pts I/Os are used) 2048 points (when 64 pts I/Os are used) Total space: 8192 points/512 words
User Program	Programming language	SFC (Sequential Function Chart) Ladder diagram (relay symbol+function block)
	Program capacity	32k steps (PU662T) 64k steps (PU672T) (incl. comment space) (1 step=24 bits)
	Memory	Main memory: SRAM (battery back up) Optional memory: Flash Memory
	Instructions	Basic ladder instructions: 24, function instructions: 206 * transfer (single length/double length/register table) * arithmetic calculation (single length/double length/binary/BCD) * logical operation (single length/double length/register table/bit file) * comparison (single length/double length, sign/unsign) * program control (jump/FOR-NEXT/subroutine and others) * function (limit/trigonometric integral/PID/function generator) * conversion (ASCII/BCD/7 segment other) * Floating point operations
	Execution speed	0.1 µs/contact, 0.2 µs/coil 0.54 µs/transfer, 0.9 µs/addition
Scanning system		Floating scan/constant scan (interval: 10-200 msec. 10 msec units)
Multitasking		1 main program, 4 sub-programs 1 timer interrupt (1-1000 msec, 1 msec units), 8 I/O interrupt
User data	I/O device/register	8192 points/512 words (X/Y, XW/YW, batch I/O) (I/O, IW/OW direct I/O)
	Auxiliary device/register	16000 points/1000 words (R/RW)
	Special device/register	4096 points/256 words (S/SW)
	Timer device/register	1000 points (T./T) (proportion of 0.1s and 0.01s timer is user definable)
	Counter device/register	512 points (C./C)
	Data register	8192 words (D)
	Link device/register	16000 points/2048 words (Z/W) (for TOSLINE-S20)
	Link relay/register	4096 points/256 words (L/LW) (for TOSLINE-F10)
	File register	8192 words (F)
	Index register	I, J, K (total 3 words)
	Retentive memory	User specified for RW, T, C and D
RAS	Diagnosis	Battery level, I/O bus check, I/O response, I/O registration, I/O parity, Watch dog timer, illegal instruction, LP check, others
	Monitoring	Event history record, scantime measurement, others
	Debugging	Online trace monitor, force, sampling trace, status latch, single step/N scan execution, break point, others

2.1 Basic internal operation flow

The S2T basic operation flow chart is shown below.



S2T performs system initialization following power on. If no abnormality is detected, S2T proceeds the mode control processing.

Here, if the RUN mode transitional condition is fulfilled, the scan control begins. The scan control is the basic function of the S2T for the user program execution operation. And if the RUN mode transitional condition is not fulfilled, S2T enters the HALT mode and does not execute the user program.

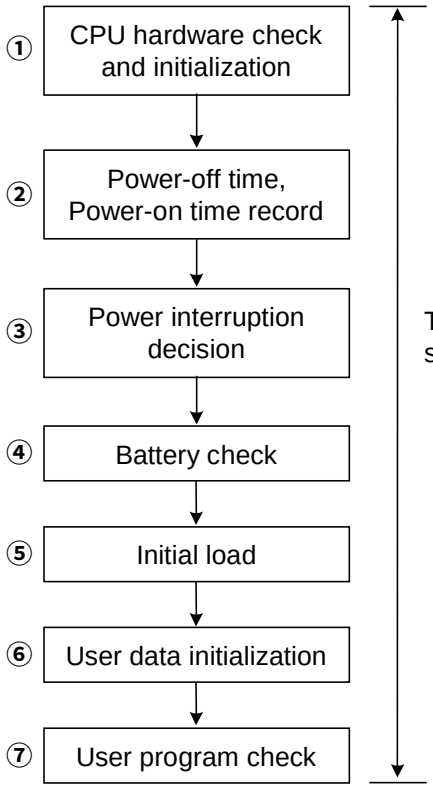
The peripheral support processing is executed as background for communicating with the programmer and the computer link.

Self-diagnosis is carried out in each processing. The above figure shows the self diagnosis executed as background.

The details of these processes are explained in this section. Self-diagnosis is explained in 5 RAS functions.

2.2 System initialization

The system initialization is performed after power is turned on.
The following flow chart shows the sequence of processes explained below.



① CPU hardware check and initialization
System ROM check, system RAM check and initial set up, peripheral LSI check and initial set up, RTC LSI check, and language processor (LP) check take place.

② Power-off time, Power-on time record
The last time the power was switched off is recorded in the event history table, and the present date and time read from the RTC LSI is recorded as power-on time. Also the present date and time are set into the special register (SW007-SW013).

③ Power interruption decision
In the hot restart mode (S0400 is ON), if power-off period is less than 2 seconds, it is decided as power interruption. In this case, initial load and user data initialization explained below will not be carried out. (only when the last power-off occurred in the RUN mode)

④ Battery check
The battery voltage is checked for the user program and the user data backup. If the battery voltage is lower than the specified value a message is recorded in the event history table 'batt voltage drop' together with the special relay battery alarm flag (S000F) setting.

⑤ Initial load

The initial load means the term for the transfer of the contents of the user program and the leading 4k words of the data register (D0000 to 04095), from the peripheral memory (Flash Memory) to the main memory (RAM), prior to running the user program.
The initial load is initiated when the power is turned on, the operation mode switch is in RUN and the RAM/ROM switch is turned to ROM.

* The initial load is not performed if the user program is written in the flash memory, but the contents are destroyed (BCC error detection).

⑥ User data initialization

The user data (registers and devices) is initialized according to the conditions in the following table:

Register/Device	Initialization
Input registers/devices(XW/X)	For forced input devices, the previous state is maintained, the others are 0-cleared.
Output registers/devices(YW/Y)	For coil forced output devices, the previous state is maintained, the others are 0-cleared.
Auxiliary registers/devices (RW/R)	For registers designated as retentive and coil forced devices, the previous state is maintained, the others are 0-cleared.
Special registers/devices (SW/S)	CPU setting part is initialized and the user setting part is maintained.
Timer registers/relays (T/T.)	For registers designated as retentive and the device corresponding to the previous state is maintained, the others are 0-cleared.
counter registers/relays (C/C.)	
Data registers (D)	For registers designated as retentive, the previous state is maintained, the others are 0-cleared.
Link registers/relays (W/Z)	For forced link devices the previous state is maintained, the others are 0-cleared.
Link relays (LW/L)	For forced link relays, the previous state is maintained, the others are 0-cleared.
File registers (F)	All maintained
Index registers (I, J K)	All 0-cleared

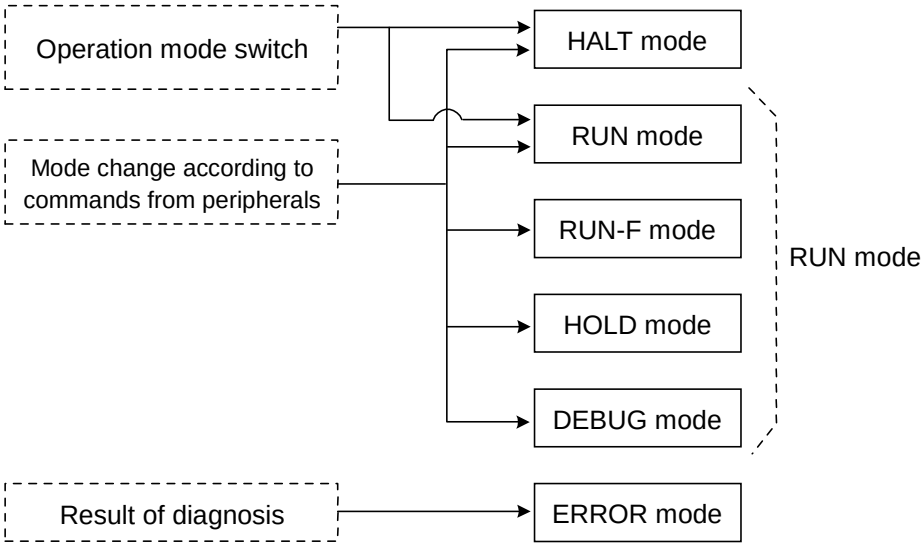
*1) For the force function, refer to 5.11 Debug Support Function.
*2) For the retentive memory area designation, refer to Part 3, Section 2.2.

⑦ User program check
The contents of the user program on the main memory (RAM) are checked by BCC.

2.3 Mode control

The S2T operation mode is selected according to the status of the operation mode switch on the CPU module and mode change requests from the peripherals (programmer, computer link, data transmission system).

The S2T operation mode is basically divided into three; RUN mode, HALT mode and ERROR mode. Also, within the RUN mode, other than the usual RUN mode, RUN-F, HOLD and DEBUG modes mainly for debugging are also available.



The following explains the operation of each mode, after which the conditions (mode transition conditions) are explained.

HALT: All external outputs are switched OFF, user program execution and I/O processing are halted. In the HALT mode the mode control is run periodically (every 50 ms), idle time is shared to peripheral support and diagnostic control. Externally this is the mode for creating/amending user programs.

RUN: After initial load (where necessary), user data initialization (where necessary), I/O module mounting check, user program check, and scan mode decisions, S2T goes into the RUN mode. Mode control, batch I/O processing timer update, and user program execution are run repeatedly in the RUN mode. This is called scan control. There are 2 scanning methods; the floating scan repeats program execution continuously and the constant scan repeats program execution in a fixed cycle. Selection is called scan mode selection. Scan control is explained in detail in 2.4.

RUN-F: This is the forced run mode. It differs from the above RUN mode in that scan control begins even if the allocated I/O modules are not actually mounted. (If other modules are mounted instead, the mode will not run.)
Otherwise action is the same as the above RUN mode.

HOLD: This is the scan temporary stop mode. Only the batch I/O processing is run, the timer update and the user program execution are halted. The scan mode continues from the status previously reached.
The I/O module test can be performed by the data monitor/set function.

DEBUG: This is the mode which may be used for program debugging functions (single step execution, single rung execution, N scan execution, breakpoint setting, etc.).
In this mode, there are three sub-modes; D-HALT, D-STOP and D-RUN.
For the DEBUG mode functions, see Section 5.11.3.

ERROR: When an error is detected in one of the diagnostic checks and operation cannot be resumed by the prescribed retry action, S2T will enter this mode. In the ERROR mode the output is completely OFF, only the error reset command is effective from the programmer (the error reset command takes S2T back to the HALT mode). Refer to 5 RAS Functions for detailed diagnosis.

The transition conditions for each mode are shown below.

- HALT mode transition conditions

Previous state			OP mode transition factor	OP mode after transition	Note
OP mode	RAM/ROM	Mode SW			
(Power off)	RAM	—	Power on	HALT	INZ
	ROM	HALT	Power on		IL, INZ
ERROR	—	—	Command Error Reset		
Other than above	—	RUN	Mode SW → HALT		
			Command HALT		

- RUN mode transition conditions

Previous state			OP mode transition factor	OP mode after transition	Note
OP mode	RAM/ROM	Mode SW			
(Power off)	ROM	RUN	Power on	RUN	IL, INZ
	—	RUN	Power on (HOT restart)		
HALT	RAM	HALT	Mode SW → RUN		INZ
		RUN	Command RUN		INZ
	ROM	HALT	Mode SW → RUN		IL, INZ
		RUN	Command RUN		IL, INZ
HOLD	—	RUN	Command HOLD Cancel	RUN or RUN-F	Return to mode before HOLD

- RUN-F mode transition conditions

Previous state			OP mode transition factor	OP mode after transition	Note
OP mode	RAM/ROM	Mode SW			
HALT	RAM	RUN	Command Force Run	RUN-F	INZ
	ROM	RUN	Command Force Run		IL, INZ
HOLD	—	RUN	Command HOLD Cancel	RUN or RUN-F	Return to mode before HOLD

- HOLD mode transition conditions

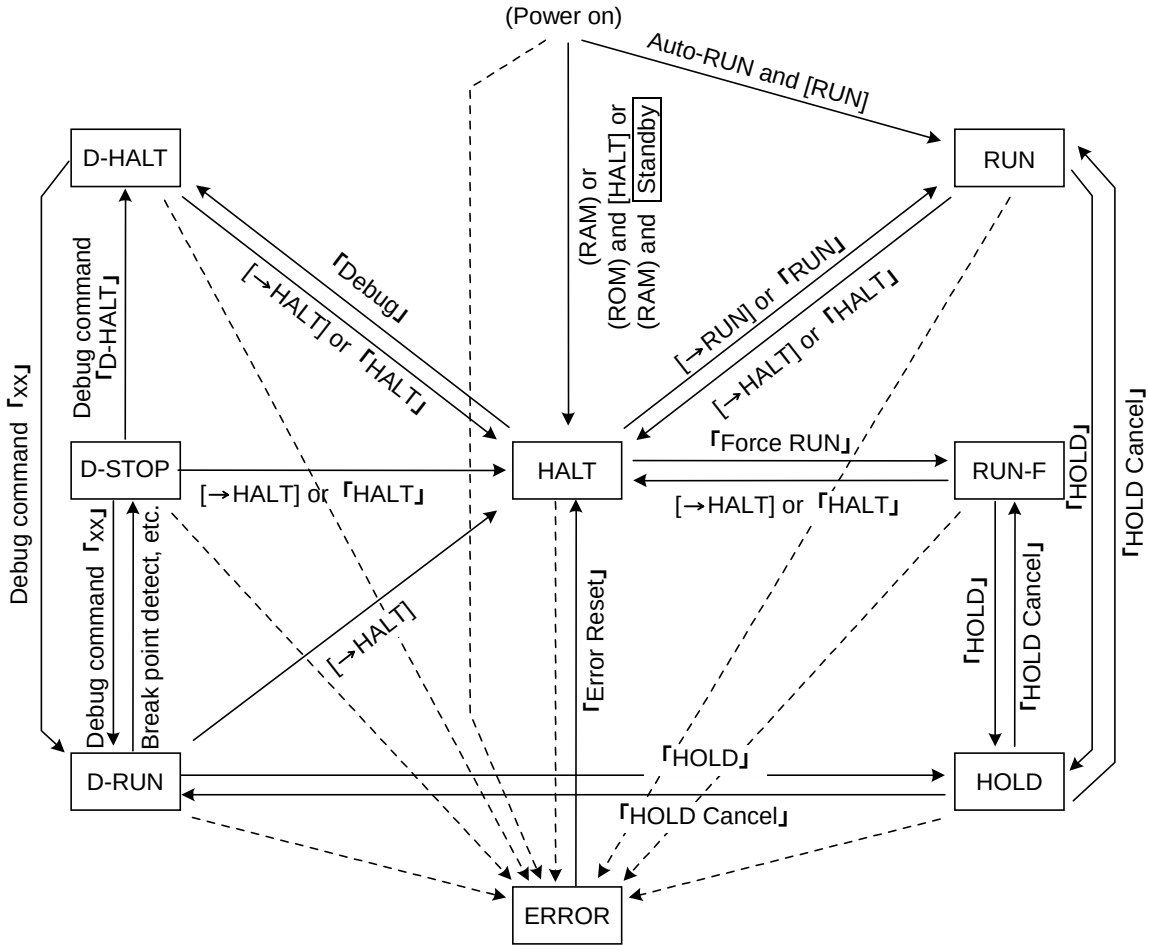
Previous state			OP mode transition factor	OP mode after transition	Note
OP mode	RAM/ROM	Mode SW			
RUN	—	RUN	Command HOLD	HOLD	
RUN-F	—	RUN	Command HOLD		
D-RUN	—	RUN	Command HOLD		

- DEBUG mode transition conditions

Previous state			OP mode transition factor	OP mode after transition	Note
OP mode	RAM/ROM	Mode SW			
HALT	—	RUN	Command Debug	D-HALT	
D-STOP	—	RUN	Command D-HALT		
D-HALT	—	RUN	Command Initial	D-RUN	INZ
			Command Continue		
			Command Step		
			Command Rung		
D-STOP	—	RUN	Command Initial		INZ
			Command Continue		
			Command Step		
			Command Rung		
HOLD	—	RUN	Command HOLD Cancel		
D-RUN	—	RUN	N scan complete	D-STOP	
			Break point detected		
			Stop condition fulfilled		
			Step execution completed		
			Rung execution completed		
			Command Stop		
D-HALT	—	RUN	Mode SW → HALT	HALT	
			Command → HALT		
D-STOP	—	RUN	Mode SW → HALT		
			Command → HALT		
D-RUN	—	RUN	Mode SW → HALT		

*1) In the table, OP mode, RAM/ROM and Mode SW mean Operation mode, RAM/ROM switch and Operation mode switch, respectively.
*2) — means the switch status is not related to.
*3) In the OP mode transition factor column, “Mode SW → XX” means switching the Operation mode switch to XX position. And “Command XX” means issue of the command XX from the programmer.
*4) Switching the Operation mode switch between RUN will not affect the operation mode. However, the protect state will be changed accordingly. (Refer to Section 5.4).
*5) In the Note column, IL means initial load execution, and INZ means the user data initialization.
*6) See Section 5.11.3 for the DEBUG mode functions.

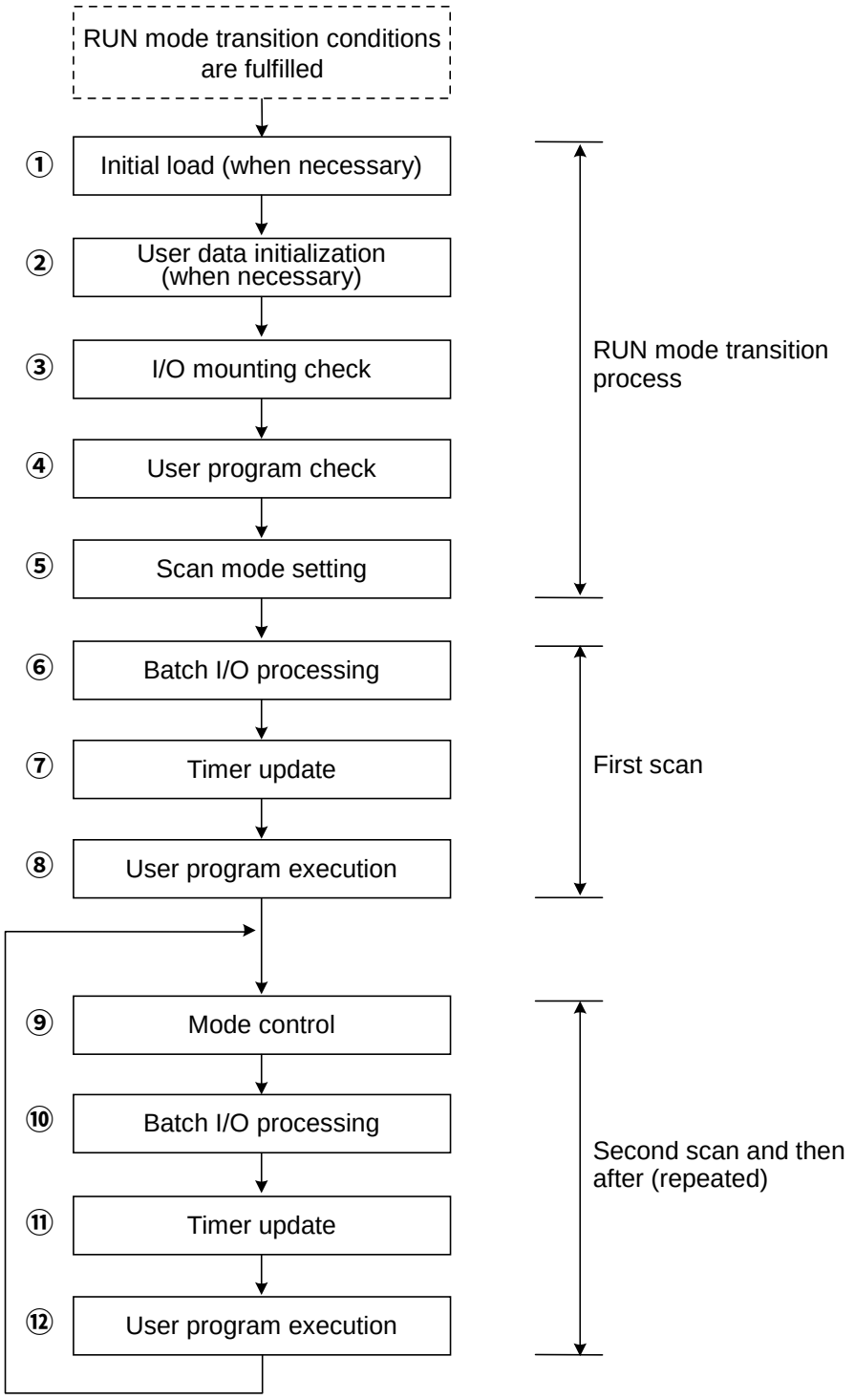
The following diagram illustrates the mode transition conditions.



*1) --- means the ERROR mode transition.
*2) [→XX] means switching the Operation mode switch to the XX position.
*3) 「 XX 」 means issuing of the command XX from the programmer.
*4) The setting status of the RAM/ROM switch and the Operation mode switch at power on are indicated by (XX) and [XX], respectively.

2.4 Scan control

As explained in 2.3, when the RUN mode transition conditions are fulfilled, initial load (when necessary), user data initialization (when necessary), I/O mounting check, program check and scan mode setting are performed, and scan control begins. In scan control, mode control, batch I/O processing, timer update and user program execution are repeated. The following diagram shows the scan control flow chart.



① Initial load
When the RAM/ROM switch is in the ROM side and the Operation mode switch is in the RUN position, the user program and the leading 4k words of the data register (D0000 to D4095) stored in the peripheral memory (flash memory) will be transferred to the main memory (RAM) in accordance with the following conditions.

- Initial load will not be performed if the user program is written in the flash memory but the contents are destroyed (BCC error detection). In this case, the S2T will enter the ERROR mode.

- Initial load will not be performed if the S2T is in the Hot restart mode from power interruption.

② User data initialization
User data initialization takes place. Refer to 2.2, System initialization, for detailed initialization. User data initialization will not be performed if the S2T is in the Hot restart mode from power interruption.

③ I/O mounting check
The I/O module mounting status is checked based on the I/O allocation information. (Refer to details in 5 RAS functions)

④ User program check
BCC check will be performed on the user program in the main memory (RAM). (Refer to 5 RAS functions for details)

⑤ Scan mode setting
Setting of the scan mode (floating scan or constant scan) will be performed. The scan mode is explained in 2.4.1.

⑥,⑩ Batch I/O processing
Data exchange between the I/O image table (I/O register/device) and the I/O module will be performed based on the I/O allocation information. Data exchange with the data transmission module (TOSLINE-S20, TOSLINE-F10) will be also performed. The first scan is input only.
Batch I/O processing is explained in 2.4.2.

⑦,⑪ Timer update
The activated timer registers and the timing relays (S0040-S0047) will be updated. Timer update is explained in 2.4.3.

⑧,⑫ User program execution
User program instructions will be executed in sequence from the beginning to the END instruction. The execution object is a main program and sub-programs.
In case of an interrupt program, when the interrupt is generated, the corresponding interrupt program is activated immediately.
The user program execution control is explained in detail in section 3.

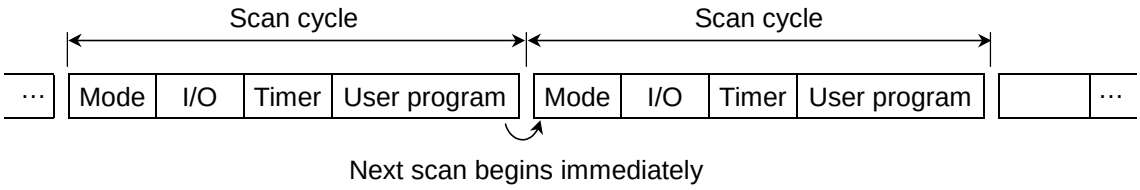
⑨ Mode control
Will check the Operation mode switch and for mode change commands from the programmer and change the operation mode. Also, scan timing control will be performed by measuring the scan cycle.

2.4.1 Scan mode

In the S2T, the scan mode enables select from floating scan and constant scan.

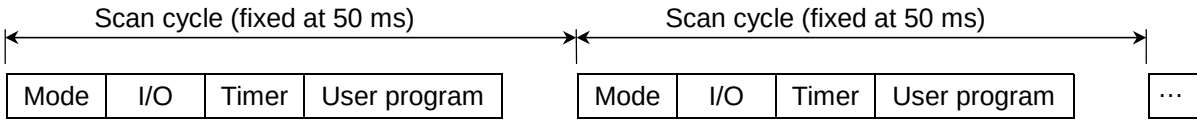
The floating scan mode is that, immediately after one scan is complete the next scan commences. It is the shortest scan cycle but the scan cycle varies according to the user program execution state.

The action of the floating scan is shown in the following diagram.



The constant scan mode has a specified time cycle for scanning. The setup range of the cycle is 10-200 ms (10 ms units). Use this scan cycle to avoid variation in scan intervals.

The action of the constant scan when the cycle is fixed at 50 ms is shown in the following diagram.



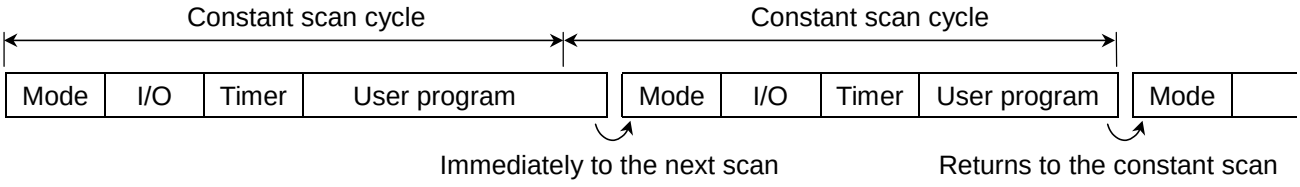
Scan mode selection will be performed by setting up the scan cycle in the system information menu of the programmer.

To select floating scan, do not set up a scan time (leave blank).

With the constant scan, scan time can be set up within the range 10-200 ms (10 ms units).

NOTE

In the constant scan, if the time for one scan exceeds a specified cycle, it will turn to floating scan, and the constant scan delay flag (special relay-S0008) comes ON. Also, when the scan time reverts to within the specified cycle, the scan cycle will return to the original constant scan.



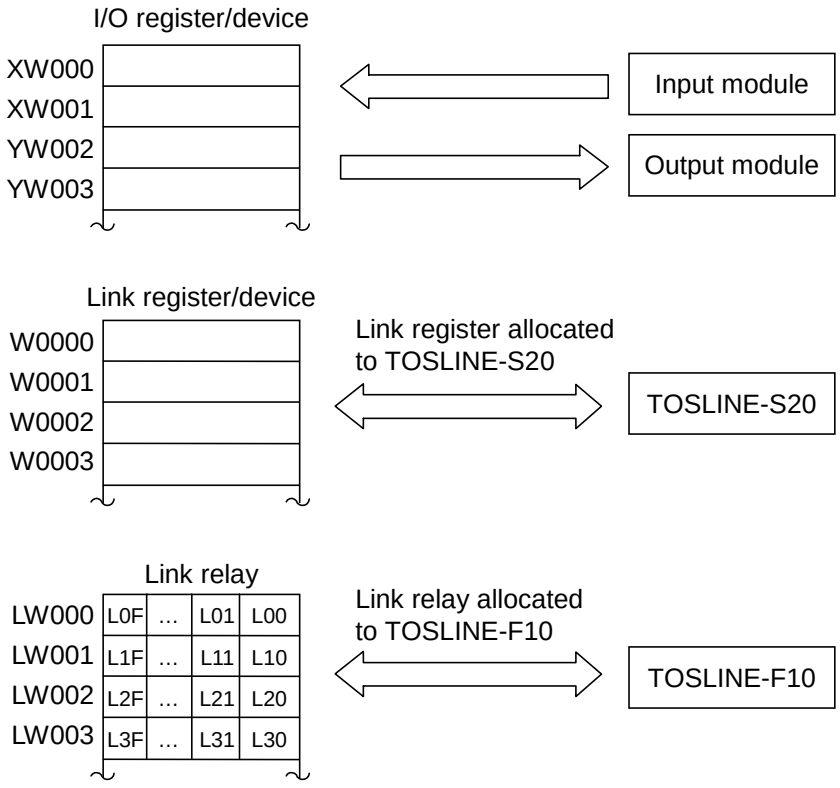
2.4.2 Batch I/O processing

The status of the external input signals will be read from input modules onto the I/O register/device (XW/X). Output register/device (YW/Y) status will be output to the output modules. This process takes place before user program execution and is done in batches, hence named batch I/O processing. The object of the batch I/O processing is as follows:

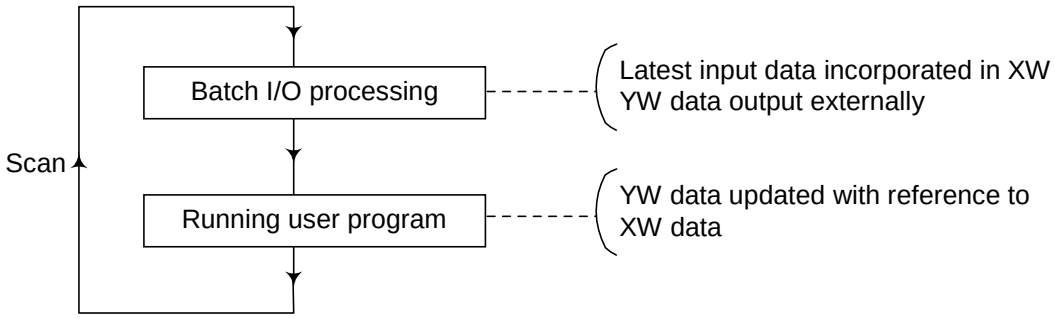
Batch input ... signals from input modules without i designation on I/O allocation and input registers/device (XW/X) which are not forced.

Batch output ... output registers/devices (YW/Y) corresponding to output modules without i designation on I/O allocation.

Also, data reading/writing between the data transmission module (TOSLINE-S20, TOSLINE-F10) and the link registers/relays (W/Z and LW/L) will be performed in this process.



If we consider S2T operation simply from the viewpoint of external signal exchanges, batch I/O processing and user program execution can be considered to be repeated continuously, as shown in the following diagram.



Basically, this has the advantage that high speed scanning is achieved because the S2T CPU does not access to the I/O modules during user program execution. Also it is easy to create program logic because the XW data are not changed during user program execution. This method is called the batch I/O processing method (refresh method).

There is also another method of S2T operation whereby I/O module data exchange takes place during user program execution, using IW/I instead of XW/X, and OW/O instead of YW/Y. This method is called the direct I/O processing method. It is recommended that the I/O modules used in direct I/O are inhibited from batch I/O (they have i specification on I/O allocation) to shorten the time for batch I/O processing.

NOTE

(1) Use the following criteria for batch I/O processing time.
Input (XW) ·· 22 μs/register
Output (YW) ·· 22 μs/register
Link (W/LW)) ·· 7 μs/register

(2) I/O modules with i designation on I/O allocation (iX, iY, iX+Y) are not part of batch I/O processing. Refer to Part 3 for I/O allocation.

(3) Forced input devices (X), link register devices (Z), and link relays (L) are not part of batch I/O processing. The force function is explained in section 5.11.1.

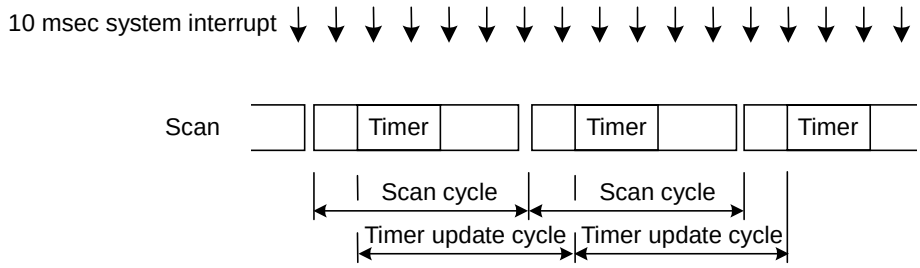
(4) Refer to the data transmission module manual for the allocation of the link register/relay (W/Z and L/LW) to the data transmission module.

(5) With direct I/O processing, output will be in register units even when the bit (O) is specified. Refer to Part 3 for direct I/O registers.

2.4.3 Timer update

The timer registers activated by timer instructions will be updated (increased), and the timing relays (S0040-S0047) will be updated.

- Updating timer registers



The number of system interrupts which occur during the timer update cycle (≈ scan cycle) will be counted, and the counts will be added up in the timer registers which are started up by the timer instructions (TON, TOF, SS, TRG).

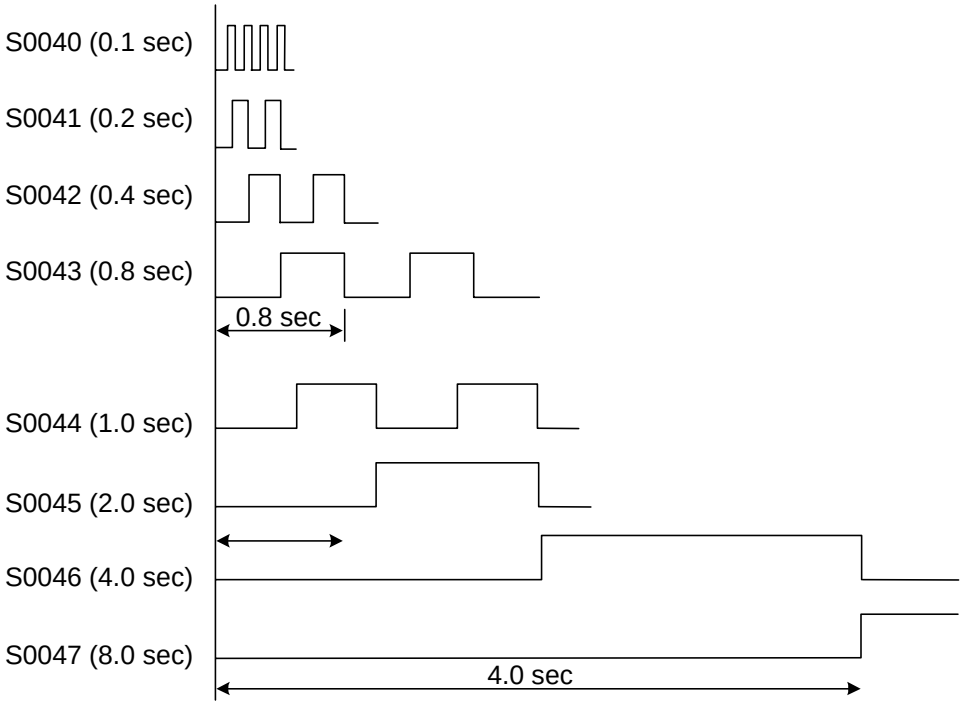
The 10 msec interrupt is used for the 0.01 second timer (T000-user), the 10 ms interrupts are accumulated and used for the 0.1 second timer (user-T999). The timer reset and the time-up processing will be performed in the execution of the timer instruction.

Timer classification	Timer register (Timer device)	Preset range	Notes
0.01 second timer	T000-T063 (T.000-user)	0-32767 (0 ~ 327.67 seconds)	On-delay timer (TON) Off-delay timer (TOF) Single shot timer (SS) Timer trigger (TRG)
0.1 second timer	T064-T999 (user-T.999)	0-32767 (0 ~ 3276.7 seconds)	

*) Take the criteria for the time for performing the timer register update as follows.

4 μs/timer register (update time)

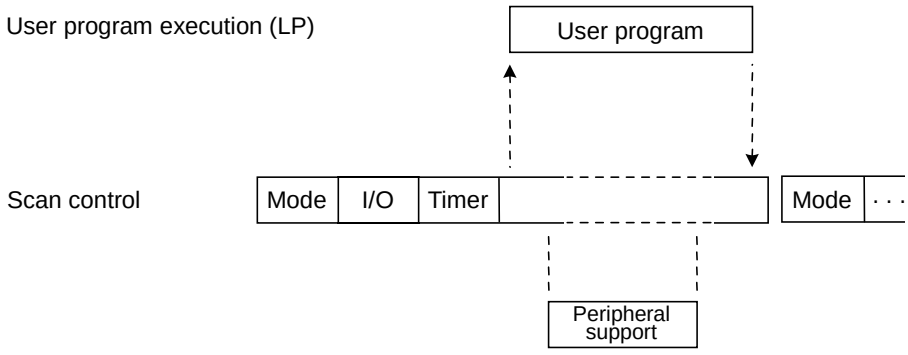
- Updating timing relays
  The timing relays (S0040-S0047) ON/OFF status is controlled by using the 10 msec system interrupt. The binary counter is configured as shown on the next page. (When RUN is started up they will be all OFF)



2.5 Peripheral support

Peripheral support processing will interpret request commands from the peripherals (programmer, computer link, data transmission module), process the requests and responds.

In the S2T, the Language processor (LP) takes charge of user program execution. The peripheral support processing will be performed by the main processor during user program execution in parallel.



*1) For commands which require accessing to user data, the command interpretation will be performed in parallel and the data accessing will be performed at the bottom of scan at batch for data synchronization.

*2) If two or more commands are received simultaneously from the request sources, the order of priority will be as follows:
Programmer > Computer link > TOSLINE-S20(CH1) > TOSLINE-S20(CH2)

2.6 Programming support functions

The programming support functions are part of the functions realized as a result of peripheral support processing. Detailed programming support functions are explained in separate manuals for the programmer. The explanation here relates to an overview of the functions and their relation to the S2T operation modes.

(1) Memory clear
When the memory clear command is received, the content of the user program memory (RAM) will be initialized and the content of the user data memory (RAM) will be cleared to 0.

(2) Automatic I/O allocation
When the automatic I/O allocation command is received, the types of I/O modules mounted will be read and the I/O allocation information will be stored on the system information. (System information is in the user program memory.)

(3) Reading the I/O allocation information
The I/O allocation information will be read from the system information, and sent to the peripherals.

(4) Writing I/O allocation information
I/O allocation information received from peripherals is stored on the system information.

(5) Reading the system information
The system information (program ID, retentive memory specification, number of steps used, scan mode specification, other) is read and sent to the peripherals.

(6) Writing system information
The system information (user setup items) received from the peripherals is stored in the system information.

(7) Reading the program
In response to a request from peripherals, a specified range of instructions will be read from the user program memory, and sent to the peripherals.

(8) Writing the program
A specified range of instructions is received from peripherals and written onto the user program memory. After writing, the BCC (check code) correction will be carried out immediately.

(9) On-line program change
Changing the content of the user program memory (adding/changing/inserting/deleting) and the BCC correction will be carried out in the RUN mode. This action is performed after completion of one scan, so the scan cycle is extended while this is being processed.

Changing the program on-line is subject to the following restrictions.

- You may not change the number or running order of instructions which are related to the program execution (see below).

  END, MCS, MCR, JOS, JCR, JUMP, LBL, FOR, NEXT, CALL, SUBR, RET, IRET

- You may not change the SFC structure in the SFC program, but you may change the action corresponding to a step and a transition condition. (Ladder diagram part).

(10) Batch reading of program
The content of the user program memory (including the system information) is read and sent to the peripherals.
It is used for the program uploading (S2T → Programmer → Disk).

(11) Batch writing the program
The user program (including the system information) is received from peripherals and will be stored in the user program memory.
It is used for program download (Disk → Programmer → S2T).

(12) Search
The instruction/operand specified by peripherals will be searched through the user program memory and their address will be sent to peripherals.

(13) Program check
When the program check command is received, the user program syntax will be checked. The result of this check will be sent to peripherals.

(14) Reading data
The specified data will be read from the user data memory in response to a request from the peripherals, and the data will be sent to the peripherals.

(15) Writing data
User data address and data content received from peripherals will be stored in the user data memory.

(16) Program reading from the EEPROM (flash memory).
The checked the flash memory content will be transferred to the user program memory and user data memory (RW, T, C, D) of the main memory (RAM).

(17) Program writing to EEPROM (flash memory).
The content of the user program memory and the user data memory (RW, T, C, D) will be transferred to the flash memory.

The execution conditions for these functions are shown in the following table.

Function	Execution conditions
Reading I/O allocation information	Always possible
Reading system information	
Reading the program	
Reading data	
Batch reading the program	Possible except in ERROR mode
Search	
Program check	Possible in HALT mode
Program writing to IC memory card/EEPROM	
Memory clear	Possible in the HALT mode
Automatic I/O allocation	
Writing I/O allocation information	
Writing the system information	
Writing the program	
Batch writing the program	
Program reading from flash memory	
On-line program change	Possible except in the ERROR mode
Writing data	Possible except in the ERROR mode

NOTE

If the password function is used, available functions are limited according to the protect level of the password. Refer to 5.13 for the password function.

3.1 Program types

The S2T can run several different program types in parallel (this function is called the multitask function). This function can be used to realize the optimal response time for each application.

The programs are classified into the 3 types below. There are a total of 14 programs.

- Main program (one)
  This program will be executed every scan and forms the main part of the scan.

- Sub-programs (4)
  This program can be activated by other programs. A total of 4 (#1-#4) are provided. (#1 is fixed function)
  In the floating scan, the sub-program will be executed after the main program execution with time limit (user setting). And in the constant scan, the sub-program will be executed in idle time from completion of the main program execution to the beginning of the next scan.

  By means of sub-programs, the main program can be used as fast scanning task, and the sub-programs as slow scanning (background) tasks.

- Interrupt programs (9)
  When the interrupt condition is fulfilled, the S2T will stop other operations and execute the corresponding interrupt program immediately. A total of 5 are provided: one program which starts up at specified intervals (Timer interrupt program), and 8 programs which start up according to interrupt signals from I/O modules with an interrupt function (I/O interrupt programs #1-#8).

  By means of timer interrupt, time critical control can be achieved, and by means of I/O interrupts, I/O responses can take place without affecting the scan cycle.

The sub-programs and the interrupt programs execution method and the execution conditions are explained in this section.

3.2 Main/sub programs execution control

Four sub-programs (Sub#1 to Sub#4) can be registered. They will be executed according to the conditions described in the table below. Sub#1 will be executed only once before the main program execution in the first scan. The function of Sub#2 can be selected from the normal mode or special mode. Sub#3 and Sub#4 are fixed in normal mode function.

In the normal mode, the execution mode can be selected from one time execution or cyclic execution.

No.	Normal/special	One time/cyclic	Operation
Sub#1	N/A	N/A	Executed only once before main program in the first scan. (after I/O processing)
Sub#2	Normal mode when S0403=0	One time mode when 30405=0	Executed when S0409=1. S0409 is reset automatically.
		Cyclic mode when S0405=1	Executed once every specified scans (SW042) during S0409=1.
	Special mode when S0403=1	N/A	Executed only once before main program in the first scan, instead of Sub#1, if S0400=1 and the last power off period is less than 2s.
Sub#3	Normal mode only	One time mode when S0406=0	Executed when S040A=1. S040A is reset automatically.
		Cyclic mode when S0406=1	Executed once every specified scans (SW043) during S040A=1.
Sub#4	Normal mode only	One time mode when S0407=0	Executed when S040B=1. S0408 is reset automatically.
		Cyclic mode when S0407=1	Executed once every specified scans (SW044) during S0408=1.

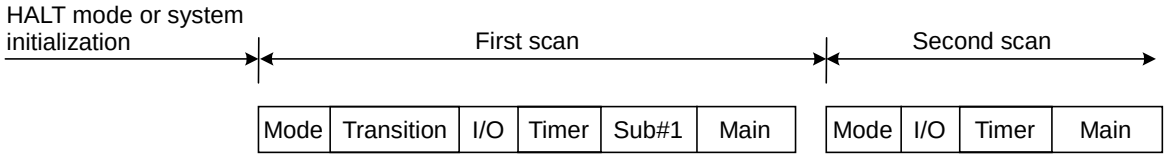
*) Hereafter, the main program, and sub-program #1 to sub-program #4 are referred as Main, Sub#1 to Sub#4, respectively.

The flags (special relays/registers) related to the sub-program operation are summarized in the table below.

Sub No.	Flag (Name)	Function	Note
Sub#1	S0410 (Sub#1 executing)	0: Not executing 1: Executing	Status
Sub#2	S0400 (Hot restart mode)	0: Normal 1: Hot restart	Setting
	S0403 (Special mode)	0: Normal 1: Special	Setting
	S0405 (Sub#2 mode)	0: One time 1: Cyclic	Setting
	S0409 (Sub#2 start)	0: No request 1: Start request	Command
	SW042 (Sub#2 interval)	Scan number setting for cyclic mode	Setting
	S0411 (Sub#2 executing)	0: Not executing 1: Executing	Status
	S0415 (Sub#2 delay)	0: Normal 1: Delay	Status
Sub#3	S0406 (Sub#3 mode)	0: One time 1: Cyclic	Setting
	S040A (Sub#3 start)	0: No request 1: Start request	Command
	SW043 (Sub#3 interval)	Scan number setting for cyclic mode	Setting
	S0412 (Sub#3 executing)	0: Not executing 1: Executing	Status
	S0416 (Sub#3 delay)	0: Normal 1: Delay	Status
Sub#4	S0407 (Sub#4 mode)	0: One time 1: Cyclic	Setting
	S040B (Sub#4 start)	0: No request 1: Start request	Command
	SW044 (Sub#4 interval)	Scan number setting for cyclic mode	Setting
	S0413 (Sub#4 executing)	0: Not executing 1: Executing	Status
	S0417 (Sub#4 delay)	0: Normal 1: Delay	Status

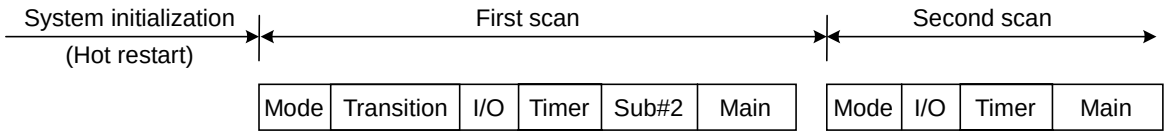
*) In the above table, “Setting” means the user preset flag for execution mode selection, “Command” means the user control flag for activating the sub-program, and “Status” means the execution status flag which can be monitored in the user program.

Sub#1 operation Sub#1 will be executed only once in the first scan before Main execution. Therefore, Sub#1 can be used as the initial setting program at the start of the operation.



Sub#2 special mode operation

If Sub#2 is set as the special mode (S0403=1) and the Hot restart condition is fulfilled (S0400=1 and recovery from power off less than 2 sec), Sub#2 will be executed once in the first scan before Main execution. In this case, Sub#1 is not executed. Also, when the Hot restart condition is fulfilled, the initial load and the user data initialization will not be performed.
Sub#2 special mode can be used as the initial setting program for the restart from power interruption.



Normal mode operation (Sub#2, Sub#3, Sub#4)

In the normal mode, the sub-programs will be executed after the main program execution with time limit. The time assigned for the sub-program execution is different between in the floating scan mode and in the constant scan mode.

In the floating scan mode:
The user sets the sub-program execution time in the system information. The setting range is 1 to 100 ms (1 ms units). The activated sub-program(s) will be executed within this time limit. If the execution cannot finish within this time limit, the execution will be interrupted and re-started in the next scan.

In the constant scan mode:
The activated sub-program(s) will be executed in idle time from completion of the main program execution to the beginning of the next scan. If the sub-program execution cannot finish within this time limit, the execution will be interrupted and re-started in the next scan.

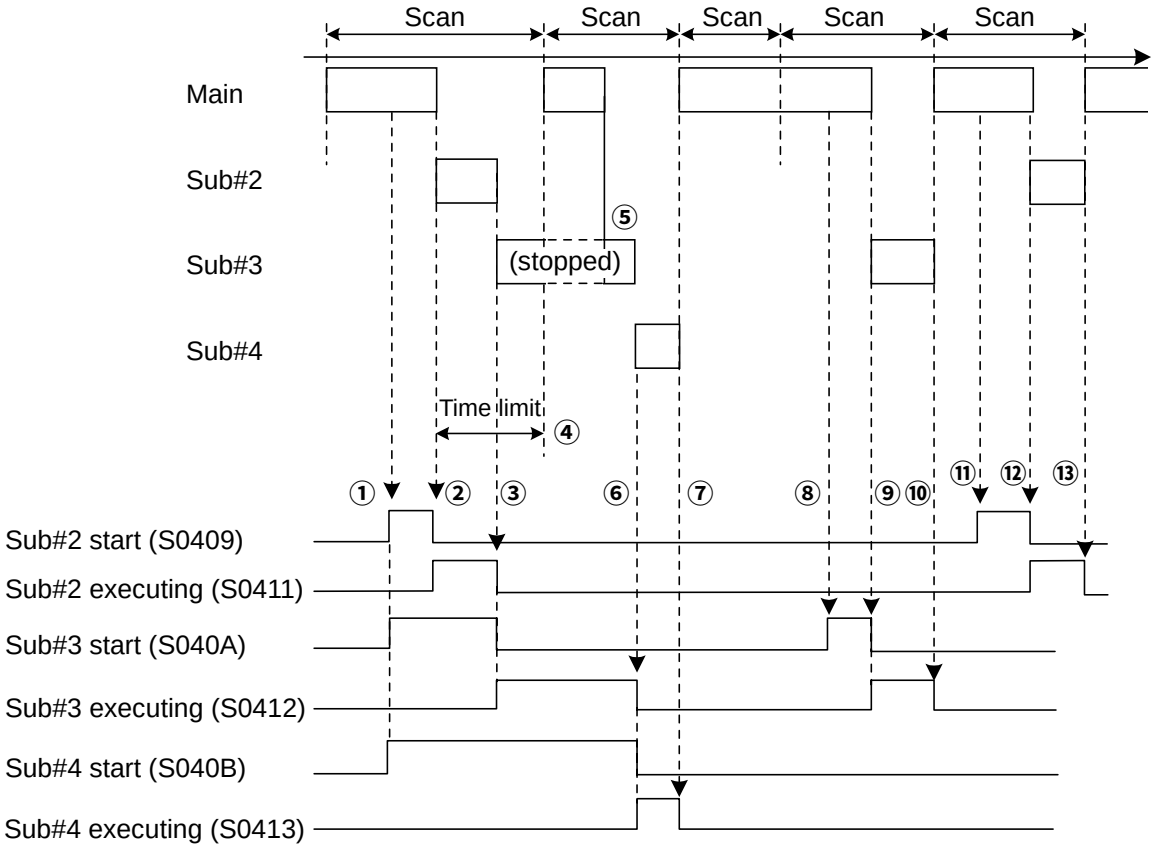
There are two execution modes in the normal mode operation; the one time execution and the cyclic execution.
In the one time mode, the sub-program will be activated when the Sub#n start flag changes from OFF to ON.
In the cyclic mode, the sub-program will be cyclically activated every designated number of scans during the Sub#n start flag is ON.

One time mode The sub-program start request is checked at each time of the main program and the sub-program execution completed. If two or more start requests occur at a time, the order of priority will be as follows.

Sub#2>Sub#3>Sub#4

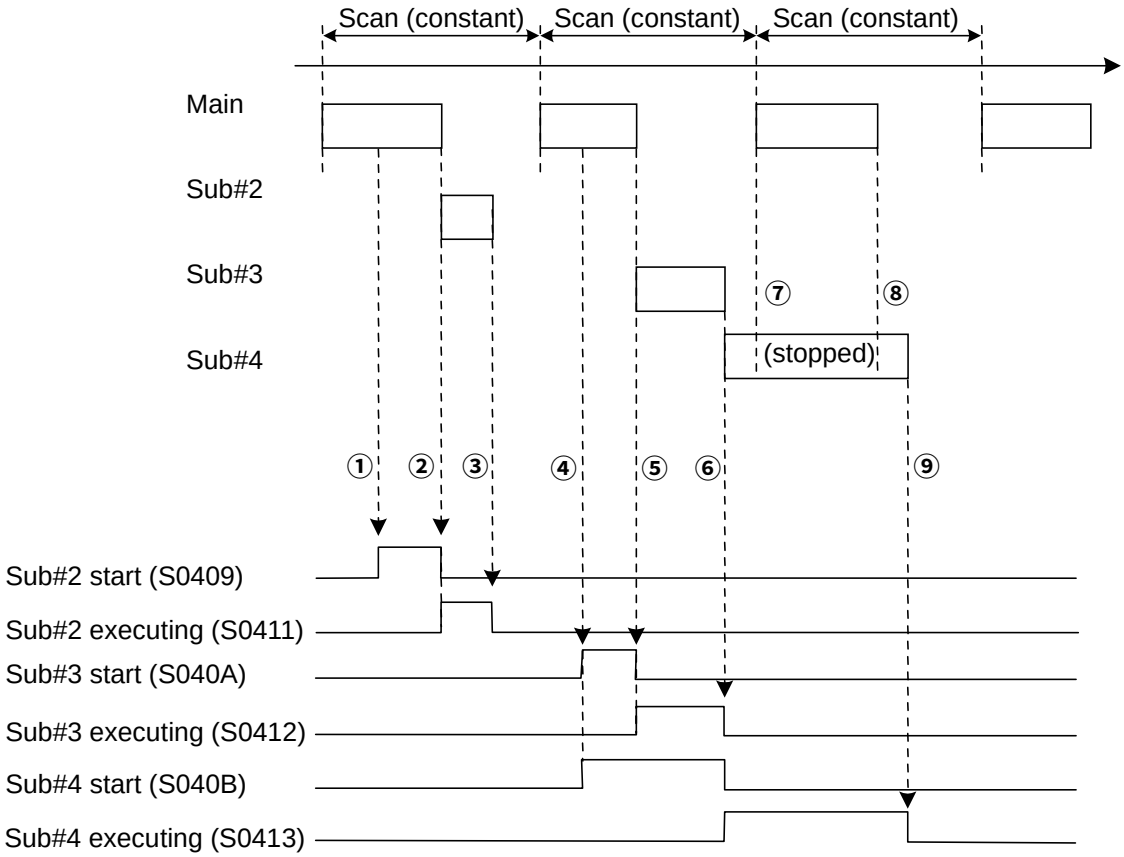
When the sub-program is activated, the start flag is reset automatically.

- Operation example in the floating scan



① Start requests to Sub#2, Sub#3 and Sub#4 from Main
② Sub#2 activated
③ Sub#2 completed and Sub#3 activated
④ Sub#3 interrupted and next scan started
⑤ Main completed and Sub#3 re-started
⑥ Sub#3 completed and Sub#4 activated
⑦ Sub#4 completed and next scan started
⑧ Start request to Sub#3 from Main
⑨ Sub#3 activated
⑩ Sub#3 completed and next scan started
⑪ Start request to Sub#2 from Main
⑫ Sub#2 activated
⑬ Sub#2 completed and next scan started

- Operation example in the constant scan



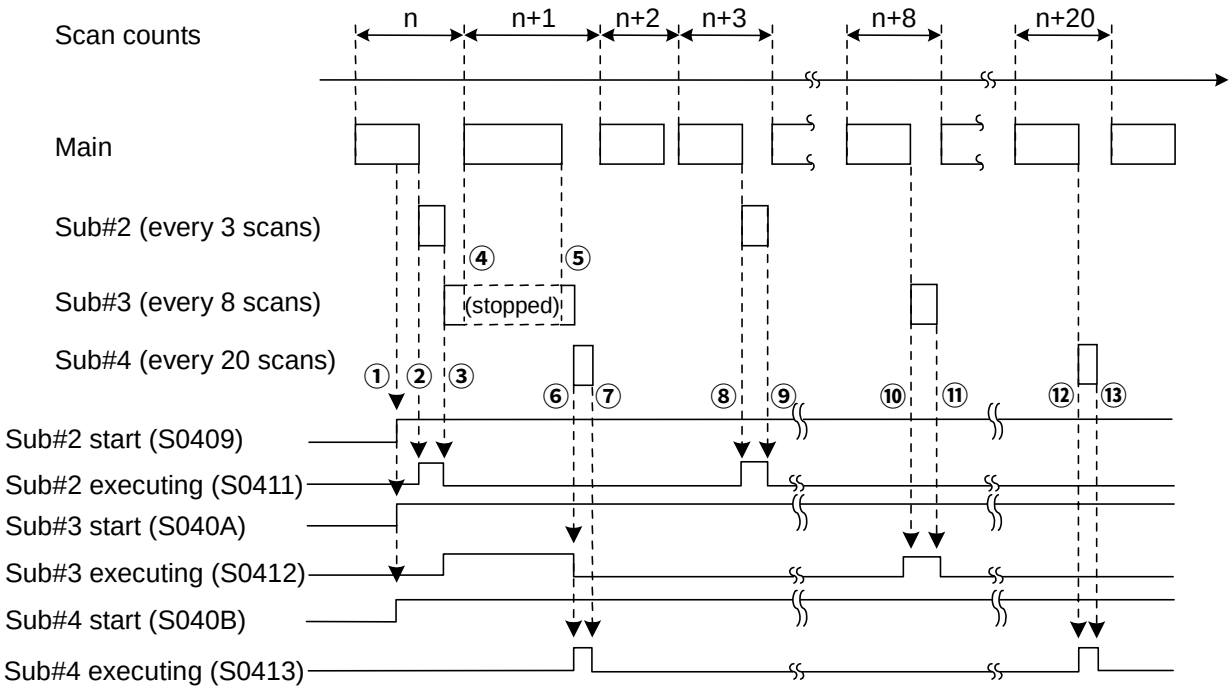
① Start request to Sub#2 from Main
② Sub#2 activated
③ Sub#2 completed
④ Start requests to Sub#3 and Sub#4 from Main
⑤ Sub#3 activated
⑥ Sub#3 completed and Sub#4 activated
⑦ Sub#4 interrupted and next scan started
⑧ Sub#4 re-started
⑨ Sub#4 completed

Cyclic mode While the start flag is ON, the sub-program will be executed once every designated number of scans. The order of execution priority is as follows:

Sub#2>Sub#3>Sub#4

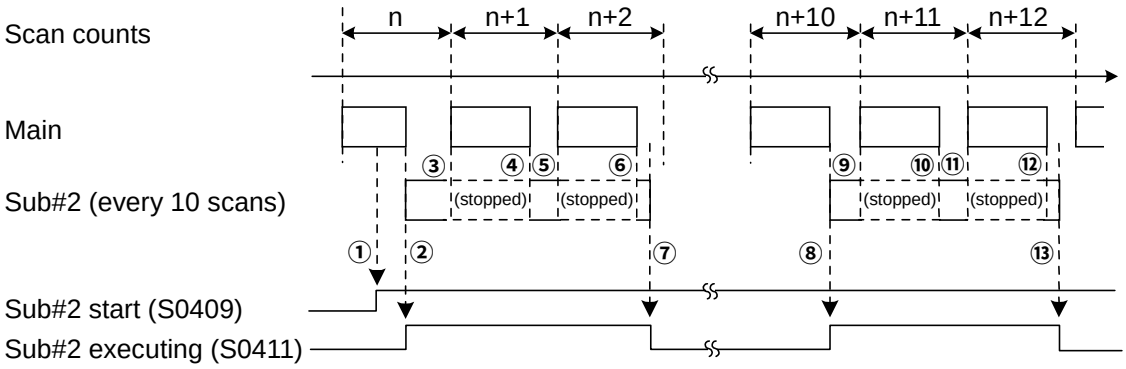
The start flag should be controlled (ON/OFF) by the user program. If the sub-program execution cannot be completed within the designated scans, the delay flag (S0415, S0416, S0417) is set to ON.

- Operation example in the floating scan



① Start requests to Sub#2, Sub#3 and Sub#4 from Main
② Sub#2 activated
③ Sub#2 completed and Sub#3 activated
④ Sub#3 interrupted and next scan started
⑤ Sub#3 re-started
⑥ Sub#3 completed and Sub#4 activated
⑦ Sub#4 completed
⑧ Sub#2 activated in the first scan of next 3 scans
⑨ Sub#2 completed
⑩ Sub#3 activated in the first scan of next 8 scans
⑪ Sub#3 completed
⑫ Sub#4 activated in the first scan of next 20 scans
⑬ Sub#4 completed

- Operation example in the constant scan (Sub#3 and Sub#4 are omitted)

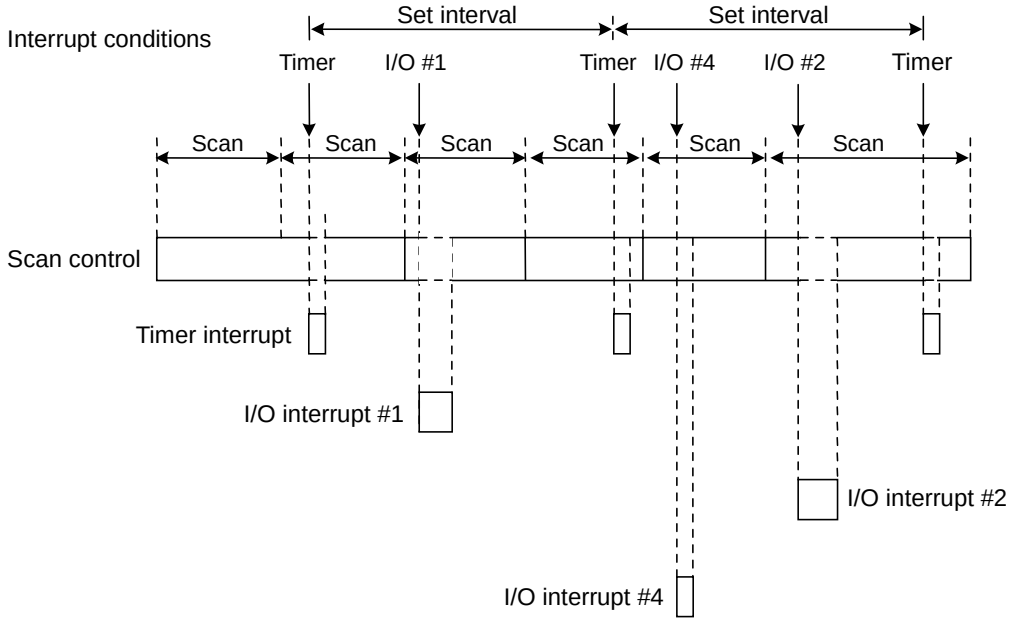


① Start request to Sub#2 from Main
② Sub#2 activated
③ Sub#2 interrupted
④ Sub#2 re-started
⑤ Sub#2 interrupted
⑥ Sub#2 re-started
⑦ Sub#2 completed
⑧ Sub#2 activated in the first scan of the next 10 scans
⑨ Sub#2 interrupted
⑩ Sub#2 re-started
⑪ Sub#2 interrupted
⑫ Sub#2 re-started
⑬ Sub#2 completed

3.3 Interrupt programs execution control

When the interrupt condition is fulfilled, the S2T will stop other operations and execute the corresponding interrupt program immediately. As shown below, you can register one timer interrupt program which starts up according to an interval setup in system information and 8 I/O interrupt programs which start up according to interrupt signals from I/O modules with an interrupt function.

Interrupt program	Operation
Timer interrupt	Activated according to the interrupt interval setup in system information. The interrupt interval is set at 2 to 1000 ms (1 ms units)
I/O interrupt #1 -I/O interrupt #8	I/O interrupt programs are activated by interrupt signals generated from I/O modules with interrupt function



(1) Interrupt priority

When several interrupt conditions occur simultaneously, the programs will be executed in the order of priority shown in the following table (the lower the numerical value the higher the level of priority). Also, if other interrupt conditions occur during an interrupt program execution the interrupt conditions will be put on hold, and after the interrupt program execution is completed, they will be executed in priority order.

Interrupt program	Priority level	Priority in class
Timer interrupt	0	—
I/O interrupt #1	1	0 (initial value)
I/O interrupt #2		1 (ditto)
I/O interrupt #3		2 (ditto)
I/O interrupt #4		3 (ditto)
I/O interrupt #5		4 (ditto)
I/O interrupt #6		5 (ditto)
I/O interrupt #7		6 (ditto)
I/O interrupt #8		7 (ditto)

The timer interrupt has the highest level of priority, followed by the I/O interrupt programs in order.
With respect to the level of priority for I/O interrupt, the I/O interrupt from the module nearest the CPU has the highest level of priority.
Refer to (3) below regarding the correspondence between interrupt programs and I/O modules.

(2) Interrupt enable/disable

You can switch between interrupt disable and enable by using the DI instruction (interrupt disable) and EI instruction (interrupt enable).
By executing the DI instruction, the interrupt conditions which occur during interrupt disable mode will be put on hold; these will be then executed instantly when the interrupt enable mode is entered by executing the EI instruction. (DI and EI should be used in a pair)
Also, in transition to RUN mode, the interrupt will be disabled in the first scan. It will be enabled automatically from the second scan.

(3) Allocation of I/O interrupt program

The I/O interrupt with the lowest number corresponds to the I/O module with interrupt function nearest the CPU, in the initial state.
This allocation can be changed. See Part 3 Section 2.3.3.
There are no restrictions on the mounting position of I/O modules with the interrupt function.

NOTE

The I/O interrupt response time (from the time interrupt conditions arise until interrupt program starts up), with normal interrupt enable and no other interrupt program started up, is an instruction execution time +500 μs in worst case.

4.1 Flash Memory (EEPROM) support

The contents of the user program and the register data can be stored in the flash memory. They can be read into the main memory (RAM) by the initial load function or programmer operation. Also, the data registers (D) stored in the flash memory can be accessed from the user program. Flash memory makes it possible to run without battery, and recovery is easy in the event of a program being destroyed.

The following functions are available with EEPROM.

Function	Details	Conditions
Program write into flash memory	Writes the contents of the user program (including the system information) and the data registers (D), the timer registers (T), the counter registers (C) and the auxiliary relay registers(RW) in the main memory (RAM) into the flash memory.	Performed by the 'Program write (RAM → IC card/ EEPROM)' command from the programmer in the following state. - HALT mode
Program read from flash memory	Transfers the contents of the flash memory to the user program memory, the data registers (D), the timer registers (T), the counter registers (C), and the auxiliary relay registers (RW) in the main memory (RAM).	Performed by the 'Program read (RAM ← IC card/ EEPROM)' command from the programmer in the following state. - HALT mode
Initial load	Transfers the contents of the flash memory to the user program memory and the leading 4 k words of the data registers (D0000 to D4095) in the main memory (RAM).	At system initialization: - RAM/ROM switch is in ROM
		At transition to RUN mode: - RAM/ROM switch is in ROM - Mode switch is in RUN
Read/write the data registers in flash memory	Reads the data of data registers in flash memory and stores in the main memory by user program. Writes the specified data of the main memory into the data registers in flash memory by user program.	Accessed by Expanded data transfer instruction (XFER)

NOTE

(1) Refer to 2.2, System Initialization and 2.4, Scan Control, with respect to the initial load function.
(2) The number of times the flash memory can be written will be limited by the hardware to 100,000 times. The S2T counts the number of times the flash memory write is performed. If the 100,000 times is exceeded, the flash memory alarm flag (S0007) will come ON. However, this checking is not effective for data writing by XFER instruction. It is recommended to check it by user program for the XFER instruction.

4.2 Expansion memory support

Expansion memory can be used as user data expansion area (expanded file register).

The following functions are available with the expansion memory card.

Use type	Function	Details	Conditions
Expansion memory	Sampling trace buffer	Stores trace data when the sampling trace is executed.	Used with the sampling trace function when the MMR allocation is set in the CPU slot.
	Expanded file register	Reads/writes the data in the expansion memory (512k words) as expanded file registers from the user program.	Accessed by the expanded data transfer instruction (XFER).

5.1 Overview

The meaning of RAS is Reliability, Availability and Serviceability. The RAS function is the general term used for the functions installed in the S2T which increase the reliability and serviceability of the applied systems and support the operation of the system.

This section explains the self-diagnostic functions, maintenance functions, the debugging functions installed in the S2T, and the system diagnostic function which can be used by the S2T user.

5.2 Self-diagnosis

The details of the self-diagnosis which are designed to prevent abnormal operation, the timing of the diagnosis and behavior when malfunctions are detected are shown below.

In building up a system, consider the system operation safety in case of the S2T shutdown (fail safe) and the system operation backup function.

In the following explanation, error registration means the storing of the details of the error and the time when it occurred on the event history table; error down means that all the outputs turn OFF and ERROR mode is entered; alarm means that the error is registered, the special relay is set, and running is continued.

(1) Diagnosis at system initialization (when power supply is turned on)

Items	Diagnostics details	Behavior when error detected
System ROM BCC check	The correctness of the system ROM is checked by BCC.	Error registration takes place, FAULT and I/O LED flash. (Programmer communication impossible)
System RAM check	The system RAM read/write is checked.	Error registration takes place, the FAULT LED flashes. (Programmer communication impossible)
Peripheral LSI check	Peripheral LSI is checked for normal initialization. (Read back check)	Error registration takes place,the FAULT LED flashes, the I/O LED lights up. (Programmer communication impossible)
LP check	LP (language processor) is checked for normal initialization.	Error registration takes place, ERROR mode is entered. (Error reset command invalid)
User program memory check	The correctness of the content of the user program memory is checked by BCC. (Checked after initial load when peripheral memory is present)	Error registration takes place, ERROR mode is entered.
User data memory check	The user data memory read/write is checked.	Error registration takes place, ERROR mode is entered. (Error reset command invalid)

Peripheral memory check	The correctness of the peripheral memory (flash memory) is checked by BCC.	Error registration takes place. ERROR mode is entered.
RTC LSI check	The validity of the data read from the RTC LSI (date and time) is checked. The data is set in the special register.	Alarm. Until reset, the date and time data (in the special register) are HFF.
Battery check	The voltage of the memory backup battery is checked	Alarm. If the user program memory BCC is normal, it will start up normally. (However, user data in the retentive memory specification is not guaranteed.)

(2) RUN start-up diagnosis

Items	Diagnostics details	Behavior when error detected
I/O verify check	The I/O allocation information and the I/O modules mounted are verified, to check that they agree.	Error registration, error down. However, when start-up is activated by a command from the programmer, a message will the displayed. It remains in HALT mode and no error registration will take place.
I/O bus check	Checks that I/O bus is normal.	Error registration, error down. However, when start-up is activated by a command from the programmer, a message will be displayed. It remain in HALT mode and no error registration will take place.
Expansion unit power check	Checks that power of expansion units is normal.	Error registration, error down. However, when start-up is activated by a command from the programmer, it will remain the in HALT mode and no error registration will take place.
I/O response check	Checks that response when I/O module is accessed is within specified response time limits.	Error registration, error down. However, when start-up is activated by a command from the programmer, a message will be displayed. It remain in HALT mode and no error registration will take place.
Program check	User program syntax is checked.	Error registration, error down. However, when start-up is activated by a command from the programmer a message will be displayed. It remain in HALT mode and no error registration will take place.

(3) Diagnosis during scan

Items	Diagnostics details	Behavior when error detected
I/O bus check	Checks that I/O bus is normal. (at batch I/O processing)	Error registration then error down. (However, if recovered by retries, only registration will take place; no error down.)
Expansion unit power check	Checks that power of expansion units is normal. (at batch I/O processing)	Error registration then error down. (However, if recovered by retries, only registration will take place; no error down.)
I/O response check	Checks that response when I/O module is accessed is within specified response time limits. (At batch I/O processing and at direct I/O instruction)	Error registration then error down. (However, if recovered by retries, only registration will take place; no error down.)
I/O bus parity check	Bus parity is checked when the I/O module is accessed. (At batch I/O processing and direct I/O instruction)	Error registration then error down. (However, if recovered by retries, only registration will take place; no error down.)
LP function check	Test program run in LP (language processor) and checked for correct results. (When running the user program)	Error registration then error down. (However, if recovered by retries, only registration will take place; no error down.)
LP illegal instruction detection check	Checks whether or not illegal instruction is detected in LP (language processor). (When running the user program)	Error registration and then error down.
Scan time over check	Checks that scan cycle does not exceed set value (200 ms). However, set value can be changed by user instruction (WDT). (When running the user program)	Error registration and then error down.

(4) Diagnosis in any mode (executed in background)

Items	Diagnostics details	Behavior when error detected
System ROM BCC check	The correctness of the system ROM is checked by BCC.	Error registration and then error down. (Error reset command invalid)
System RAM check	The system RAM read/write is checked.	Error registration and then error down. (Error reset command invalid)
Peripheral LSI check	Peripheral LSI setting status is checked.	Error registration and then error down. (Error reset command invalid)
Watchdog timer check	Watchdog timer system runaway check. (Set at 350 ms)	Error registration and transition to ERROR mode after system reset.
User memory check	User memory (RAM) read/write checked.	Error down after error registration (with retry).
LP check	LP (language processor) read/write is checked.	Error registration and then error down.
Battery check	Memory backup battery voltage checked.	Alarm
RTC LSI check	Date and time data read from RTC LSI every 300ms, validity checked, data set in special register.	Alarm. Until reset, date and time data are HFF.

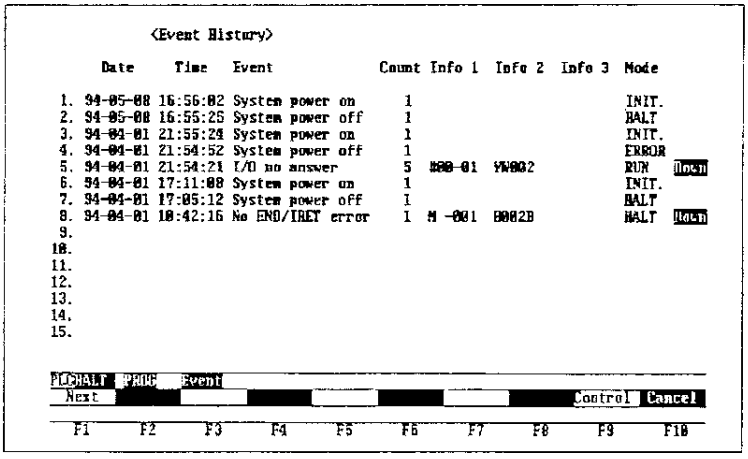
NOTE

Refer to the separate S2T User's Manual-Hardware, for details of troubleshooting.

5.3 Event history

When an error is detected by the S2T diagnosis, the details and time of occurrence will be registered in the event history table (besides errors, the times power ON/OFF are also registered). The 30 most recent occurrences of errors can be registered in the event history table. As new data is registered, the data registered previously will be shifted down in sequence, and the oldest data will be deleted.

Use the event history table for maintenance information. It can be displayed on the programmer as below. The contents of the event history table are remained until executing the event history clear command or the memory clear command from the programmer.



The meaning of each item on the screen above is as follows.

(1) Number (1-30)
Indicates the order of occurrence. Number one is the most recent.

(2) Date (year-month-day)
Indicates the date of occurrence. This is shown as “??-??-??” if the RTC LSI is abnormal.

(3) Time (hours: minutes: seconds)
Indicates the time of occurrence. This is shown as"??:??:??” if the RTC LSI is abnormal.

(4) Event
Indicates the sort of error detected. (System power on and system power off are also registered.)

(5) Count
Indicates the number of times the error was detected. For example, an error is detected during a process, the retry is repeated 4 times, the malfunction does not change and it goes to error down. This is indicated as count 5 and DOWN will be displayed under the Mode.

(6) Information 1, Information 2, Information 3
Indicates supplementary information regarding the error. For example, with an I/O error the I/O module position (unit No, slot No) where the error occurred and the read/write register address etc. will be indicated.

(7) Mode
Indicates the actual mode when the error was detected. Also displays DOWN when error down occurs. On the mode display, INIT indicates the system initialization after power is turned on.

*) Refer to the separate S2T User's Manual-Hardware for display details of detected errors and methods of proceeding.

5.4 Power interruption detection function

The S2T has one function that control the S2T's operation in the event of power interruption. That is the hot restart function which enables the restart from the power interruption without initialization.

5.4.1 Hot restart function

For the S2T, the user can decide the operation re-start condition at the recovery from the power interruption.

The hot restart function will be effective when the special relay S0400 is set to ON (S0400=1). In this case, if power is turned off in the RUN mode and recovered within 2 seconds, the S2T moves into RUN mode without the initial load and the user data initialization.

By using this function together with the special mode of the sub-program #2, the user can decide the operation re-start condition as follows:

Interruption time	Re-start condition	Method
Longer than 2 seconds	Re-start after the normal initialization	—
Within 2 seconds	Re-start after the normal initialization	Do not use the hot restart function (S0400=0)
	Re-start after setting the prespecified data into registers/devices	Use sub-program #2 as special mode to set prespecified data
	Re-start after setting the data according to input status	Use sub-program #2 as special mode to set data according to input status
	Re-start without any initialization (hot restart)	Do not use sub-program #2 special mode

NOTE

(1) When power interruption is longer than 2 seconds, normal initialization will be carried out even if S0400 is ON.

(2) The hot restart function is also available by using the programmer's System Diagnosis menu in addition to setting S0400 to ON.

5.5 Execution status monitoring

The following functions are served by the S2T for user to monitor the S2T execution status. (Refer to separate manuals for the programmer for operation of these.)

(1) Execution time measurement function
Measures the following execution times. This data can be monitored on the programmer.

- Scan cycle
  current value, maximum value, minimum value (1 ms units)
- Main program execution time
  current value, maximum value, minimum value (1 ms units)
- Sub-program execution time (Sub#1-#4)
  current value, maximum value, minimum value (1 ms units)
- Timer interrupt execution time
  latest value, maximum value, minimum value (0.1 ms units)
- I/O interrupt execution time (I/O #1-#8)
  latest value, maximum value, minimum value (0.1 ms units)

NOTE

(1) The scan cycle value includes the scan overhead and all interrupts occurring during the scan.

(2) With the main program and the sub-program execution times the interrupt time for any interrupts occurring are excluded.

(2) Online trace function
This function traces the status during program execution and displays on the programmer screen (power flow display, register value display). Since this displays data from the paint in time that the instruction is executed rather than at the end of a scan cycle, it is useful for program debugging.

5.6 Sampling trace function

The sampling trace function collects the status of specified registers/devices and stores it into the sampling buffer, according to the specified sampling condition. The collected data can be displayed on the programmer screen in the format of trend graph (for registers) or timing chart (for devices).
The sampling trace function is useful for program debugging and troubleshooting.

Sampling buffer

Expand memory of the S2T CPU module is used for the sampling buffer.
The sampling buffer size is 8k words (fixed).

Sampling target

The sampling targets (registers/devices) are selected from the following combinations.

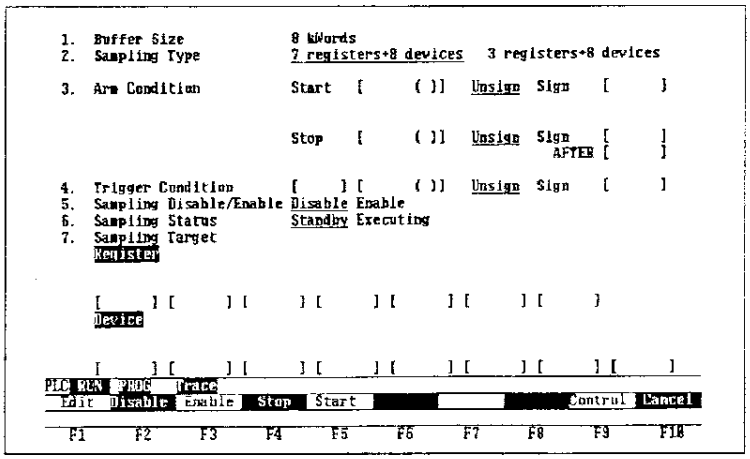
① 3 registers + 8 devices
② 7 registers + 8 devices

In case of ①, 256 times per 1 k words (max. 2048 times) of collection is available. In case of ②,128 times per 1 k words (max. 1024 times) of collection is available.

Sampling condition

There are the arm condition and the trigger condition for the sampling trace execution conditions.
The arm condition consists of the start condition and the stop condition. When the start condition is fulfilled, the data collection is started. And when the stop condition is fulfilled, the data collection is stopped. However, if the after counts is added to the stop condition, the arm condition is extended for specified counts of scans after the stop condition is fulfilled.
The trigger condition specifies the timing of the data collection. That is, the data collection is carried out at the moment of the trigger condition is fulfilled while the arm condition is fulfilled.

The sampling target and the condition are set on the programmer screen (below). Setting is available when the S2T is in HALT mode or the sampling trace is disabled by pressing F2 (Disable).



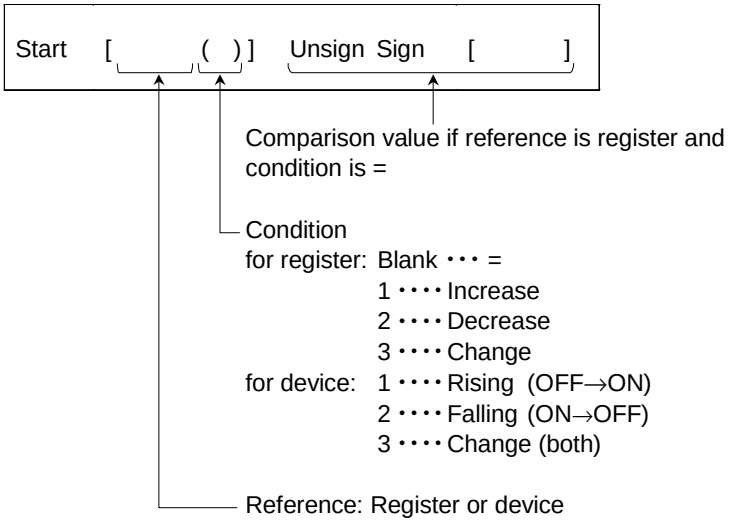
The sampling trace is executed when it is enabled by pressing F3 (Enable).

NOTE

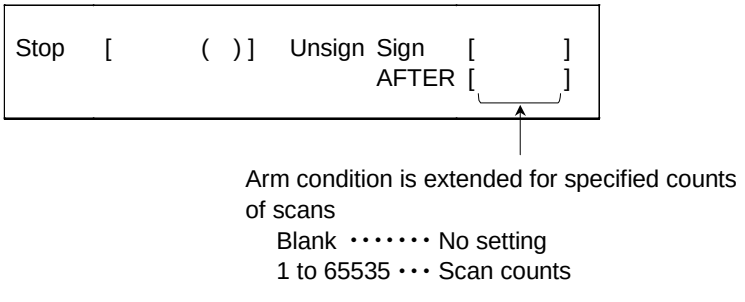
The sampling trace can also be started/stopped by manually without setting the arm condition. F5 (Start) and F4 (Stop) are used.

The setting method for each condition is as follows.

Arm start condition:

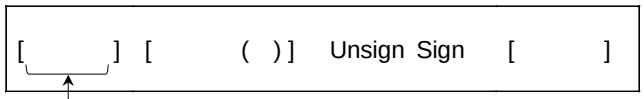


Arm stop condition:



*) Other setting items are the same as the arm start condition.

Trigger condition:



Counts of condition fulfilled:
Data collection is carried out once per counts times the following condition fulfilled

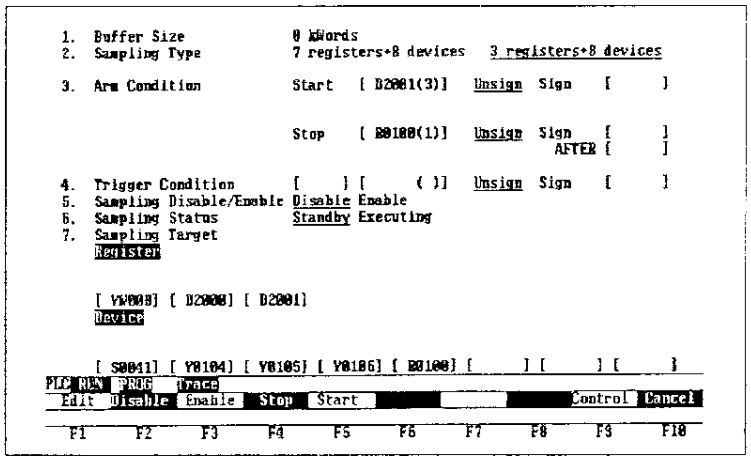
Blank ••••••• No setting (counts = 1)
1 to 65535 ••• Counts

*) Other setting items are the same as the arm start condition.

NOTE

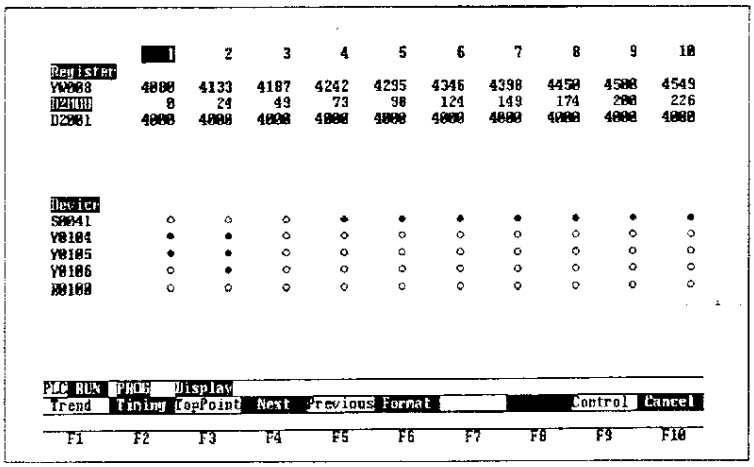
The evaluation of the conditions are performed at the end of every scan.

Execution example Sampling target and condition setting example:

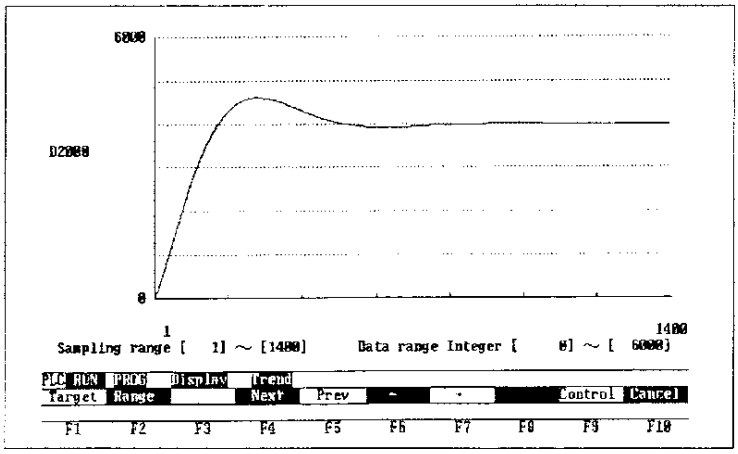


In the above example, the data of YW008, D1000, D2001, S0041, Y0104, Y0105, Y0106 and R0100 are collected every scan, for the duration of from D2001 changed to 10 scans after R0100 changed to ON.

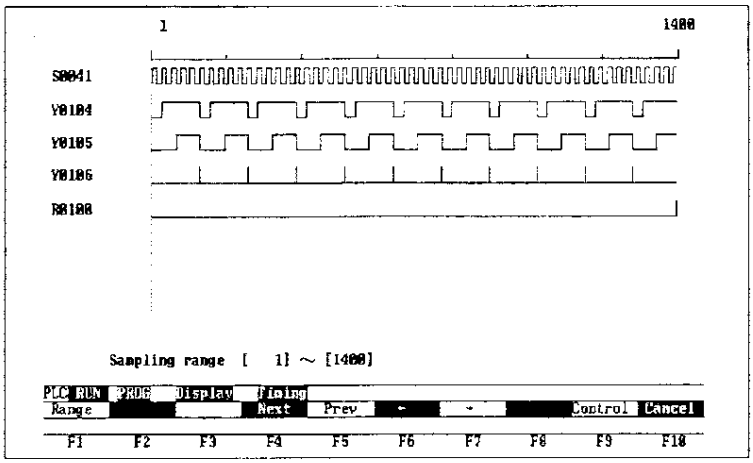
Data display example 1 (Data):



Data display example 2 (Trend graph):



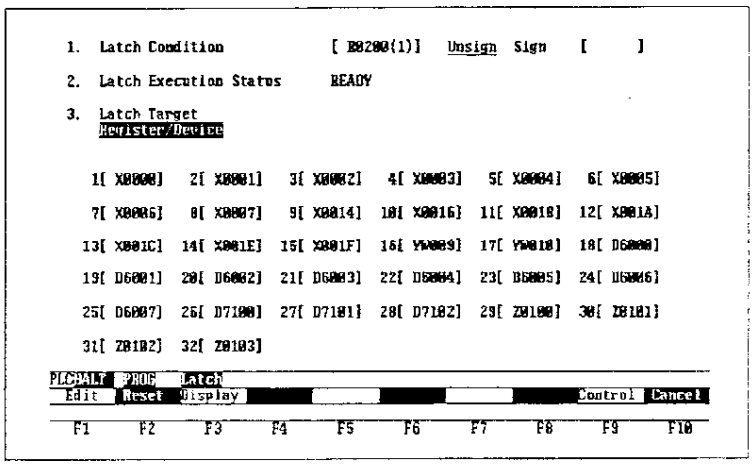
Data display example 3 (Timing chart):



5.7 Status latch function

The status latch function will transfer the specified devices/registers data in batches to the internal latch data storage area when the latch condition set by the programmer is fulfilled or when the Status latch instruction (STLS) is executed.
The latch condition is evaluated and data collected at the end of the scan. However, when the STLS instruction is executed, the data collection is carried out at the time of the instruction is executed.
Latched data can be displayed on the programmer.
The latched status can be reset by the latch reset command of the programmer or by executing the Status latch reset instruction (STLR).

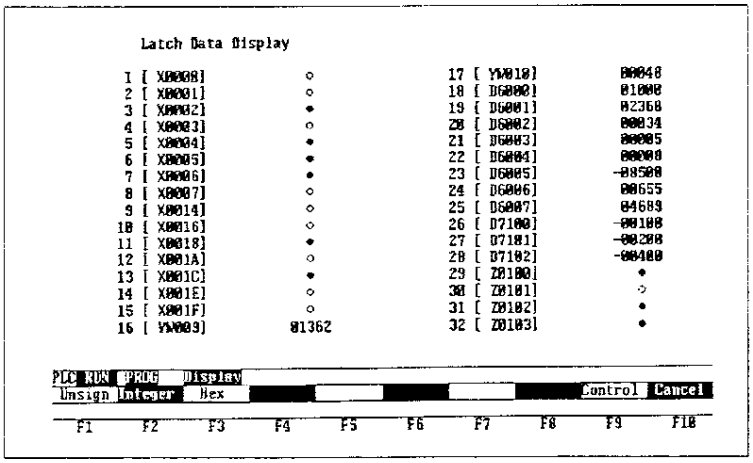
The latch target and condition setting screen is shown below.



The setting method for the latch condition is the same as the arm condition of the sampling trace function. (See Section 5.9)

In the example above, 32 devices/registers data will be transferred to the latch data storage area when R0100 is changed from OFF to ON.

The latched data display screen is shown below.



This function is useful for program debugging.

5.8 Debug support function

The following functions are supported by S2T for effective program debugging.
(Refer to separate manuals for programmers for operation of these.)

5.8.1 Force function

There are two functions in the force function, input force and coil force. Batch input data is not updated in the input force specified register/device. The registers/devices which can be specified for forced input are the input register/device (XW/X), link register/relay (W/Z) in the receiver area and link register/relay (LW/L) in the receiver area. On the other hand, coil force specified coil instruction can not be processed when the program is running, so despite the state of the program, the coil device maintains its previous state.
Simulated input and simulated output are made possible by the combined use of the force function and the data setting function.

5.8.2 Online program changing function

This function enables to change the user program online (during RUN). The changes are made after completion of one scan, so it extends the inter-scan cycle.
Online program change is subject to the following conditions.

- You cannot make changes to the number or order of execution control instructions (below).
  END, MCS, MCR, JOS, JCR, JUMP, LBL, FOR, NEXT, CALL, SUBR, RET, IRET
- You cannot change the SFC structure in the SFC program section, but you can change the detail parts (ladder diagram) which relate to steps and transitions.

Also, there is the constant operand changing function.
This function enables to change the constant operand, such as timer/counter preset value and constant data used in function instructions, online (during RUN). For the timer/counter presets, changing is possible even in the memory protect state (P-RUN).

NOTE

When using the online program changing function, pay attention for safety.
If changed rung contains a transition-sensing type instruction (below), the instruction will be executed at the online changing if the input condition is ON, because the input condition of last scan is initialized. Pay attention for this point.
—|↑|—, —|P|—, —(P)—|, Edged function instructions.

5.8.3 DEBUG mode functions

The S2T has a special mode for supporting the program debugging. It is the DEBUG mode. In the DEBUG mode, the following functions become available.

- Breakpoint setting function
  Starts and stops at the instruction which is set as the breakpoint.
- Single step execution function
  Starts and stops in unit of one instruction.
- Single rung execution function
  Starts and stops in units of one rung.
- N scans execution function
  Executes specified times of scans and stops.
- Stop condition setting function
  Executes until the specified stop condition is fulfilled.

DEBUG mode

The S2T can enter into the DEBUG mode only from the HALT mode. There are three sub-modes in the DEBUG mode, D-HALT, D-RUN and D-STOP.

D-HALT: When mode is changed from HALT to DEBUG, S2T enters this mode. The execution condition setting of the DEBUG mode function is possible in this mode. (All outputs OFF)

D-RUN: Program execution mode. When the stop condition is fulfilled in each DEBUG mode function, the mode moves into D-STOP.

D-STOP: Temporary stop mode. The mode transition factor of D-RUN to D-STOP can be displayed on the programmer. (Output state remains)

I/O disable

In the DEBUG mode, I/O module accessing can be disabled by the execution condition setting. When I/O disable is selected, external input status is not read into the input devices/registers (X/XW) and the status of the output devices/registers (Y/YW) is not sent the output modules.
In this case, operation modes displayed on the programmer are changed from D-HALT to S-HALT, D-RUN to S-RUN and D-STOP to S-STOP respectively.

Trace back function

In the program execution of the DEBUG mode functions, the online trace information of latest 10 scans is maintained. This information can be monitored after the execution is stopped (D-STOP mode).

*1) This function is not available for the single step execution and the single rung execution.
*2) This function is available only for the program range currently monitored.

Function details

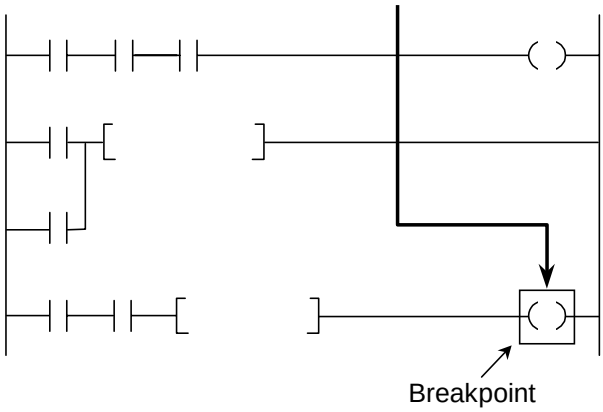
(1) Breakpoint setting function
Program execution is stopped when the instruction which is set as the breakpoint is fetched. The breakpoint can be set on one location only. This function becomes available when any number except 0 is set in the Breakpoint counts in the execution condition setting. When the breakpoint is fetched specified times, the program execution is stopped.

The start of execution can be selected from the initial start and the continue start.

- Initial start ····· User data initialization is performed then program execution is started from the top.
- Continue start ····· Program execution is started from the point where the execution was stopped last time.

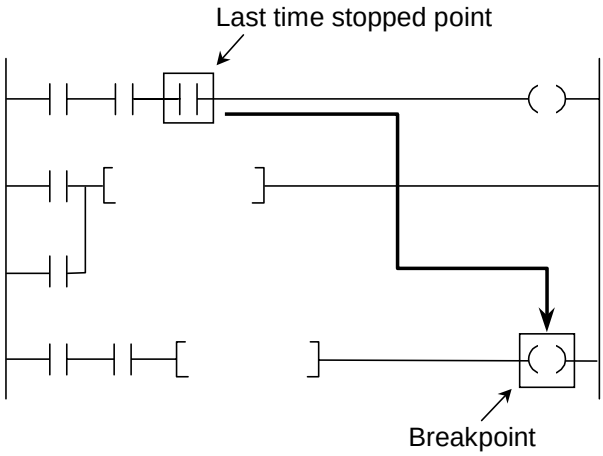
When execution is started from the D-HALT mode, the initial start is selected automatically.

Execution example 1 (Initial start)



User data initialization is performed. Then program execution is started from the top and stopped at the breakpoint.
(The breakpoint instruction is not executed)

Execution example 2 (Continue start)



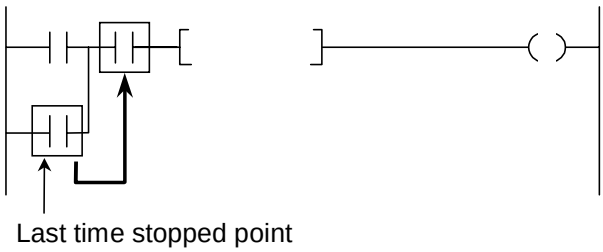
Execution is started from the point of last time stopped and stopped at the breakpoint.

(2) Single step execution function

The execution is started and stopped in units of one instruction. When this function is activated from the D-HALT mode, the user data initialization is performed and the program execution is stopped at the top instruction. (D-RUN → D-STOP)

When this function is activated from the D-STOP mode, S2T executes the last time stopped instruction and stops at the next instruction.

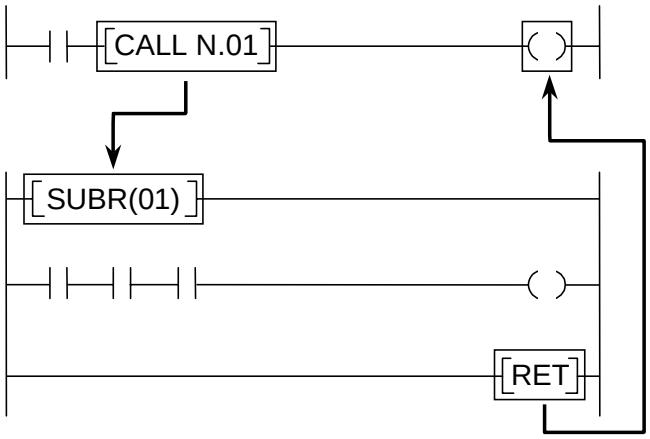
Execution example 1



Executes the last time stopped instruction and stops at the next instruction.

If execution is stopped at the sub-routine call instruction (CALL) and if the sub-routine call condition is satisfied, the next stop point is the corresponding sub-routine entry (SUBR).

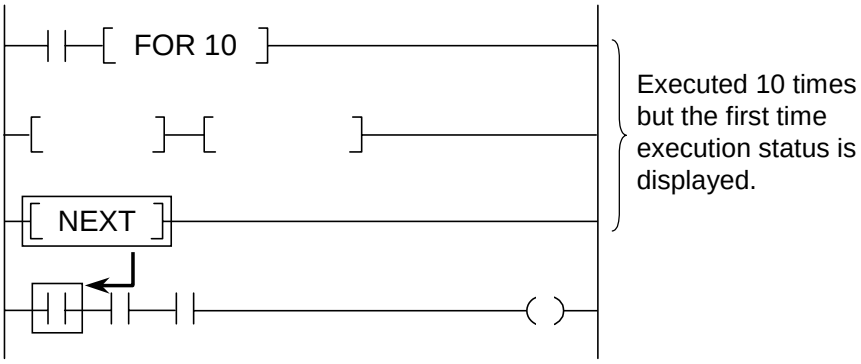
Execution example 2 (CALL/RET)



As same as above, if execution is stopped at the jump instruction (JUMP) and if the jump condition is satisfied, the next stop point is the corresponding label instruction (LBL).

In case of the FOR-NEXT loop, the instructions inside the loop are executed specified times, but the execution trace is not possible. The first time execution status is displayed and the execution is stopped at the next instruction to the loop.

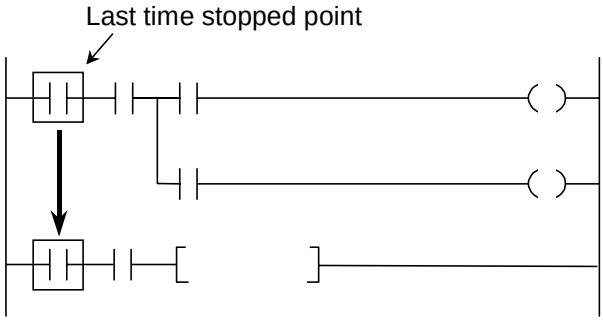
Execution example 3 (FOR-NEXT)



The interrupt program is executed during the single step execution, but it is not traced.

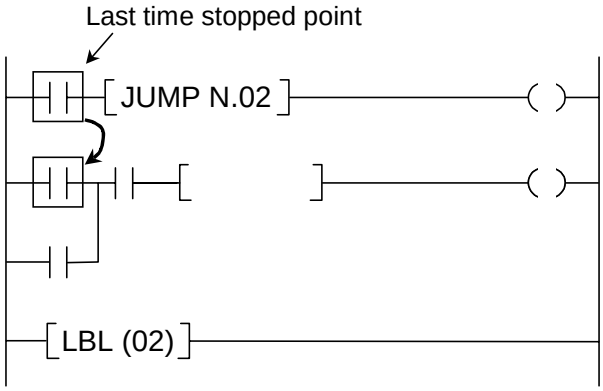
(3) Single rung execution function
The execution is started and stopped in units of one rung. When this function is activated from the D-HALT mode, the S2T performs the user data initialization and stops at the top instruction.
(D-RUN → D-STOP)
When this function is activated from the D-STOP mode, the S2T executes the last time stopped rung and stops at the first instruction of the next rung.

Execution example 1



Even if the rung contains the sub-routine call (CALL) or the jump (JUMP) instructions, the next stopping point is the next rung despite of calling or jumping.

Execution example 2 (JUMP)



If jump condition is not satisfied, the execution is stopped at the next rung.

If jump condition is satisfied, the execution is moved to the LBL instruction. (not stopped)

In case of the FOR-NEXT loop, the instructions inside the loop are executed specified times, but only the first time execution can be traced as same as the single step execution.

Also, the same precautions as the single step execution are applied to the interrupt program.

(4) N scans execution function
The S2T executes the specified times of scans and stops at the end of the scan.
The scan counts is set in the execution condition setting. The setting range is 0 to 65535. If 0 is set, this function is disabled.

The start of execution can be selected from the initial start and the continue start, as same as the breakpoint setting function.

(5) Stop condition setting function
The S2T executes the program until the stop condition is fulfilled.
The checkpoint of the condition can be selected either at the end of scan or at the breakpoint.

The stop condition can be set as either AND or OR conditions of up to four registers/devices data.

The start of execution can be selected from the initial start and the continue start, as same as the breakpoint setting function.

Notes (1) The DEBUG mode functions can also be used in combinations as follows.

Breakpoint setting or Single step execution or Single rung execution	and/or	N scans execution and/or Stop condition setting

(2) The initial load is not performed at the mode changing from D-HALT (S-HALT) to D-RUN (S-RUN).

(3) The timers used in the program are updated as normal in free scan, and updated as 100 ms/scan in the single step/rung execution.

(4) The sub-program execution is not interrupted in the single step/rung execution. In free scan, it is interrupted as normal.

(5) The actions of the interrupt program are as follows.

At D-HALT (S-HALT) ..... inhibited
At D-STOP (S-STOP)..... holded (executed when changed to enable)
At D-RUN (S-RUN)..... enabled

Restrictions (1) The DEBUG mode function is not available for the SFC program block.

(2) The DEBUG mode function is available only when the programmer is connected directly to the S2T's programmer port.

(3) Program modification should not be made in the DEBUG mode. Otherwise, the DEBUG mode functions may not work correctly.

NOTE

In the D-STOP and D-RUN modes, FAULT LED blinks. And in the S-STOP and S-RUN modes, FAULT and I/O LEDs blink. Both of above are not error.

5.9 System diagnostics

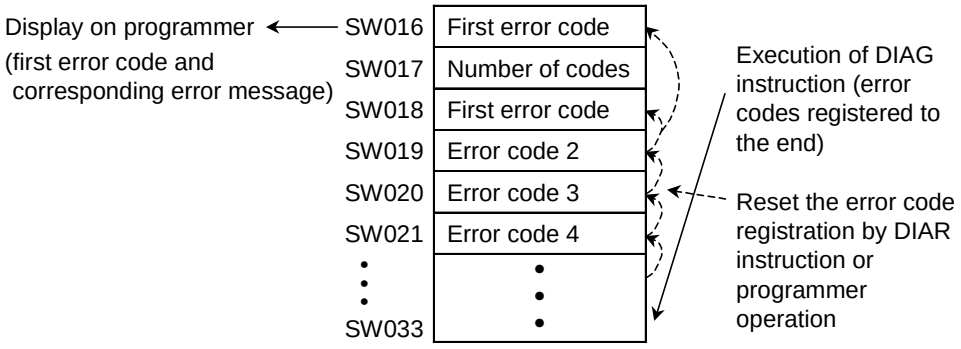
The following functions are provided for diagnosis of controlled system operation. The system can be monitored easily using of these functions.

(1) Diagnostics display function

By using the diagnostics display instruction (DIAG) in the user program, the relevant error code (1-64) and error message (maximum 12 characters per message) can be displayed on the programmer screen. Also, the error code generated is stored in the special registers (SW016-SW033) in order of generation up to a maximum of 16 codes and the annunciator relay (S0340-S037F) corresponding to the error code goes ON. It is possible to use the special register/relay to display the error code on an external display monitor.

The error codes registered can be reset one by one (shift up after erased) using the programmer or by the diagnostics display reset instruction (DIAR).

This function may also be used effectively in conjunction with the bit pattern check and the sequence time over detection mentioned below. (Refer to details of diagnosis display instructions in other manual for instruction set)



When error codes are registered, for example 3,10, 29, 58, each corresponding annunciator relay, S0342, S0349, S035C, S0379 comes ON.

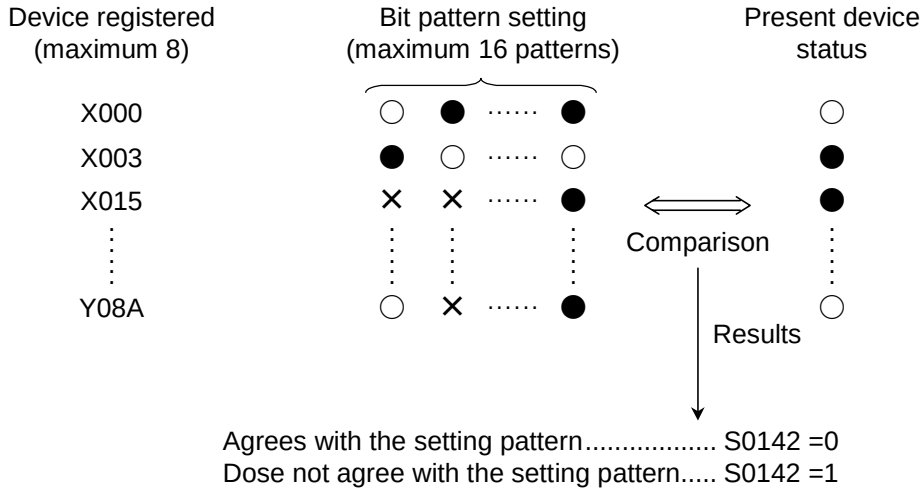
(Annunciator relay)

	F	E	D	C	B	A	9	8	7	6	5	4	3	2	1	0
SW034	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1
SW035	32	31	30	29	28	27	26	25	24	23	22	21	20	19	18	17
SW036	48	47	46	45	44	43	42	41	40	39	38	37	36	35	34	33
SW037	64	63	62	61	60	59	58	57	56	55	54	53	52	51	50	49

(2) Bit pattern check function

This function checks that the device ON/OFF status for a number of devices are in the normal combinations (pattern). For example, checks that not more than 2 from device 1, 2 and 3 are ON simultaneously. Up to 8 devices can be registered, and up to 16 patterns can be set. The checkpoint can be selected either before program execution or end of scan. The results are reflected in the special relay S0142.

This function is enabled when the special relay S0140 is set to ON.



In the pattern setting, OFF is shown as ○, ON is shown as ● and do not care is shown as ×.

The device and bit pattern registration takes place in programmer system diagnosis menu.

*) The checkpoint of this function can be selected by the special relay S015F as below.

S015F = OFF ..... Before user program execution (after I/O processing)

S015F = ON ..... After user program execution

(3) Register value validity check function

This function checks that the register value is within the specified numerical value range. Up to 4 registers can be registered with the maximum and the minimum data. Also, it is possible to select the register value to be taken as an integer (signed) or as a positive integer (unsigned).

The checkpoint can be selected either before program execution or end of scan. The results are stored in the special relay S0143-S0146 (within the range: 0, outside the range: 1).

This function is enabled when the special relay S0140 is set to ON.

Registered register (maximum 4)	Type	Minimum value	Maximum value		Present register value
XW034	Unsigned	0	400		200
XW035	Signed	-1500	1500	⟺	2000
D0011	Unsigned	H0200	H9000	Comparison	H1234
W0100	Signed	-300	600		-1000

Results

Register 1 (XW034)..... S0143 = 0
Register 2 (XW035)..... S0144 = 1
Register 3 (D0011) ..... S0145 = 0
Register 4 (W0100) ..... S0146 = 1

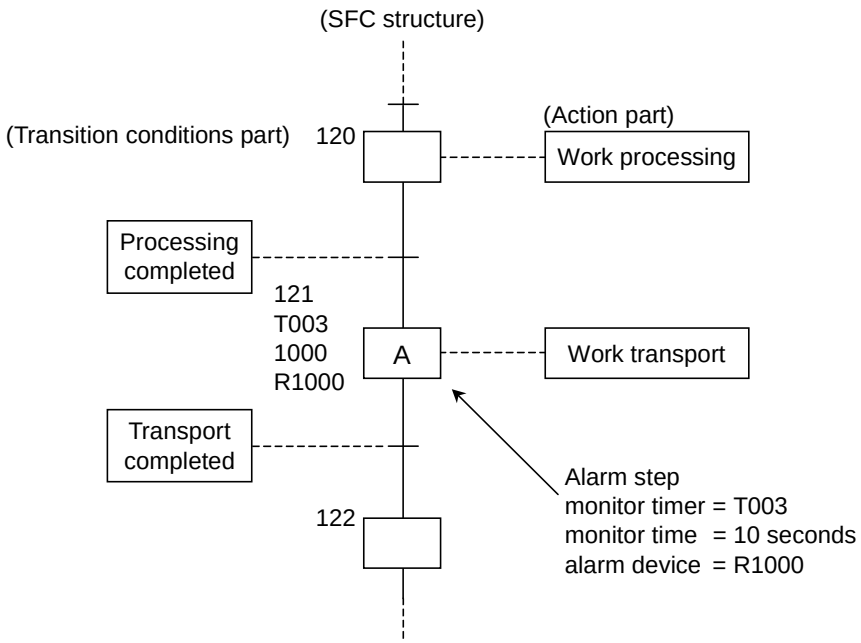
The register and the numerical value range are registered in programmer system diagnosis menu.

*) The checkpoint of this function can be selected by the special relay S015F as below.

S015F = OFF .....Before user program execution
(after I/O processing)

S015F = ON .....After user program execution

(4) Sequence time over detection function
The alarm step is provided for one of SFC (sequential function chart) instructions. This Alarm step turns ON the specified device when the following transition is not come true within the preset time. This function allows easy detection of operation hold ups in sequential control process.

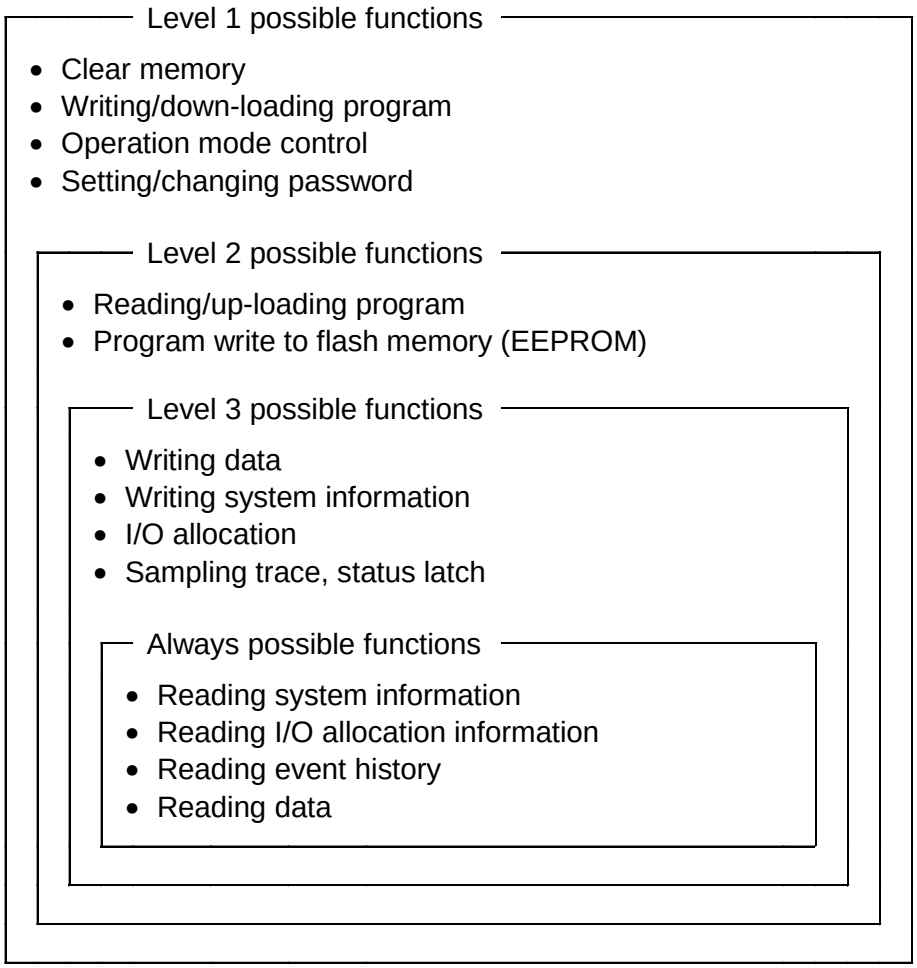


With the above example, if the transport has not been completed (work arrived signal ON etc) within 10 seconds from when the work transport started, the specified alarm device (R1000) comes ON. By this means a malfunction of the work drive or the sensor can be detected.

Refer to Part 3 of this manual and the other instruction set manual for explanation with respect to SFC.

5.10 Password function

For the system security, the password function is provided.
There are three levels of protection as shown below. Accordingly, three levels of passwords can be set.



For example, if level 1 and level 2 passwords have been set, only level 3 and always possible functions are enabled. In this state, if the level 2 password is entered, the level 2 possible functions are also enabled.

NOTE

(1) Do not forget your level 1 password. Otherwise, you cannot release the password protection.
(2) Protection level for each programmer command is explained in the programmer operation manual.

PART 3

PROGRAMMING INFORMATION

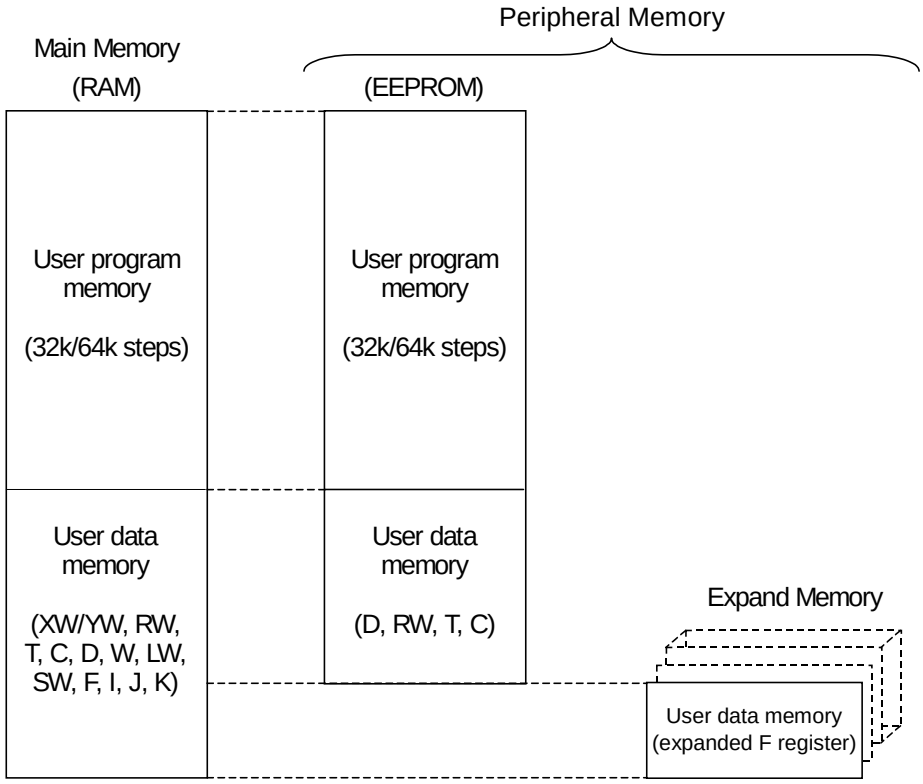
1.1 Aims of Part 3

The main functions of the S2T are to store the user program, to execute the stored user program and to control and monitor the operation/state of machines/processes which are the result of such execution.
The user program is a series of instructions for achieving the request control function, operation conditions, data processing and the interface with the operator. It is stored in the user program memory. The execution of the user program is the sequential performance of the processes of reading user data in which external input/output data and control parameters are stored, processing the respective instructions and storing the results of this in the user data memory.

Part 2 described the types of processing which are executed by the S2T internally, functions for executing the user program efficiently and the RAS functions. Part 3 describes the necessary information for creating user programs, that is to say detailed user data, detail of the input/output allocation and the programming languages. Also, the user program configuration is described to use the S2T's multi-tasking function.

1.2 User memory configuration

The following diagram shows the user memory configuration of the S2T.



The memory which can be used by user is called user memory. The user memory can be divided by configuration into main memory and peripheral memory. And the user memory can be divided by function into user program memory and user data memory.

The main memory is a built-in RAM memory with battery backed up. On the other hand, the peripheral memory is an optional memory configured by flash memory. The peripheral memory can be used as back up for main memory (user program and register data).

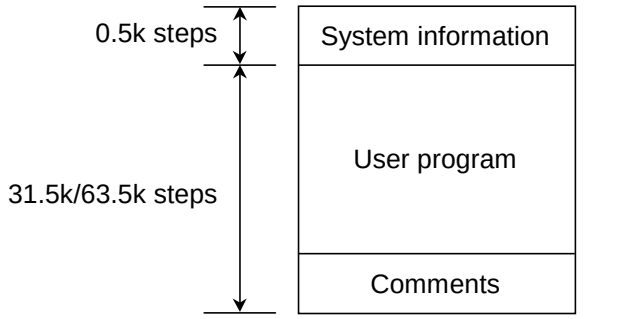
The user program memory has a capacity of 32k/64k steps (step is a unit for instruction storage), and stores a series of instructions created by ladder diagram or SFC.

The user data memory stores variable data for user program execution. It is separated by function into input/output registers, data registers, etc.

2.1 Overview

The user program memory can be divided into the system information storage area, the user program storage area and comments storage area as shown below.

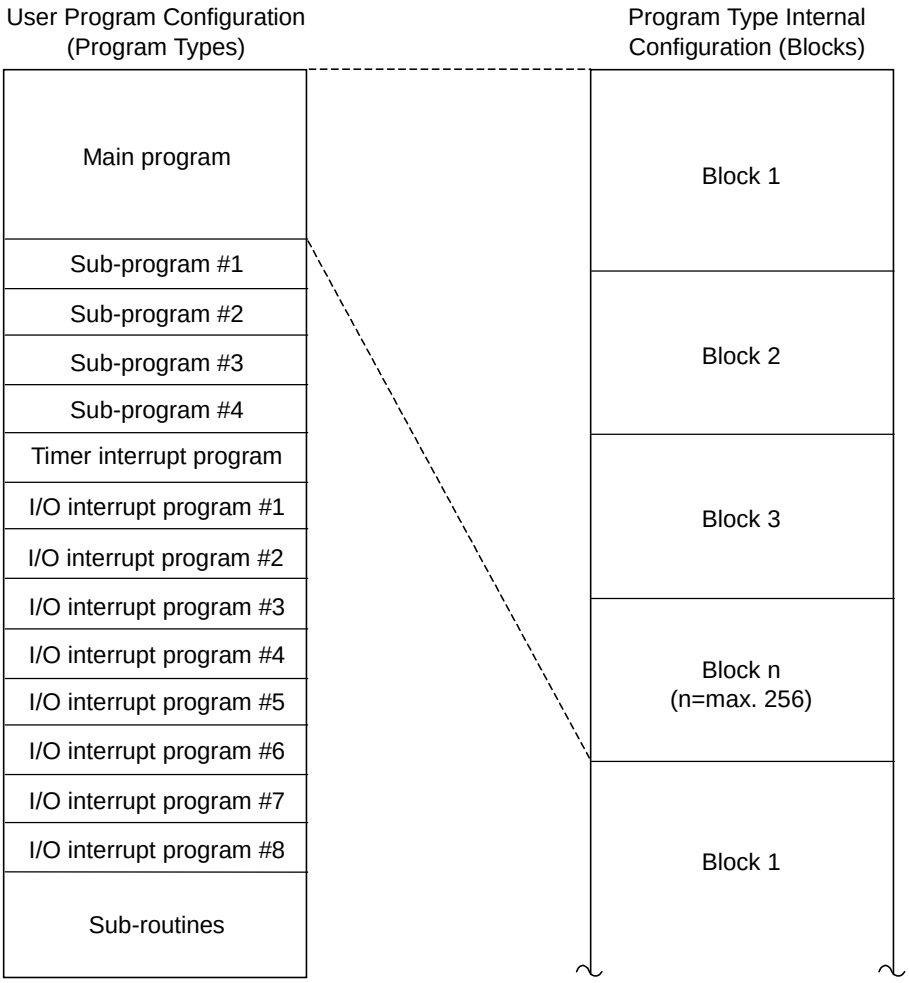
User Program Memory Configuration



System information is the area which stores execution control parameters for the user program and user program management information, and it always occupies 0.5k steps.

Comments are added and stored for easy maintenance of the user program. The comments storage area is not fixed. (user setting)

The user programs is divided into the program types of main program, sub-programs, interrupt programs and sub-routines, depending on the function.
Of these, the main program is the core of the user program.
On the other hand, when it is difficult to achieve the requested control functions by the main program alone, sub-programs and interrupt programs are used as required, but need not be provided.
Also, sub-routines are used when repetition of the same process in a program is required, or in order to see the program more easily by making one function into a block, but may not be provided if not required.



Also, in each program type, the user program is arranged by units called ‘blocks’.

Internally, a block definition label is present at the head of each block. The program type, block number and programming language information are in the block definition label (there is no need for the user to be concerned with the block definition label).

Although the 2 programming languages of ladder diagram and SFC can be used in combination in the S2T, only 1 language can be used in any 1 block.

NOTE

(1) In each program type and block, there is no limit to the program capacity (number of steps). The only limit is the total capacity (31.5k/63.5k steps).
(2) The block number need not be consecutive. In other words, there may be vacant blocks in the sequence.

2.2 System information

System information is the area which stores execution control parameters and user program management information when executing a user program, and occupies 0.5k steps of the user program memory. The following details are included in system information.

(1) Program ID
This is the user program identification. A setting of up to 10 alphanumeric characters can be set. The program ID can be registered/monitored on the system information screen of the programmer.

(2) System Comments
These are comments attached to the user program. A setting of up to 30 alphanumeric characters can be set. The system comments can be registered/monitored on the system information screen of the programmer.

(3) Memory Capacity
This stores the memory type (user program capacity/data register capacity). The memory capacity can be monitored on the system information screen of the programmer. (monitor only)

(4) Steps Used
This stores the number of steps used in the user program. The number of steps used can be monitored on the system information screen of the programmer. (monitor only)

(5) PLC Type
This stores the model type. The PLC type can be monitored on the system information screen of the programmer. (monitor only)

(6) Program Size Setting
This is the capacity assigned to the user program. The rest of this setting out of total 32k steps is assigned to the comments. The program size setting can be registered/monitored on the system information screen of the programmer.

(7) Sampling Buffer Setting
This performs the setting and registration of the storage capacity of the sampling buffer for the sampling trace function. The maximum setting is 8k words. The sampling buffer setting can be registered/monitored on the system information screen of the programmer.

(8) Retentive Memory Area Designation

This sets and registers the address ranges for the auxiliary register (RW), timer register (T), counter register (C) and data register (D) which retain pre-power cut data out of the user data. The ranges registered here are outside the subjects of the user data initialization process. For each of these registers, the ranges from the leading address (0) to the designated address are the retentive memory areas. The retentive memory area designations can be registered/monitored on the system information screen of the programmer.

(9) Scan Time Setting

This sets and registers the scan mode (floating/constant). When no scan time is registered (blank), the mode becomes the floating scan mode. When a numerical value is set for the scan time, the mode becomes a constant scan mode which takes that time as the scan cycle. The setting for the scan cycle is 10-200 ms (in 10 ms units).

The scan time setting can be registered/monitored on the system information screen of the programmer.

(10) Sub-Program Execution Time

Time limit factor assigned for sub-programs in the floating scan. The setting range is 1-100 ms (in 1 ms units). The sub-program execution time can be registered/monitored on the system information screen of the programmer.

(11) Timer Interrupt Interval

This sets and registers the interrupt cycle of the timer interrupt program. The setting range is 1-1000 ms (in 1 ms units). The timer interrupt interval can be registered/monitored on the system information screen of the programmer.

(12) Computer Link Parameters

This sets and registers the parameters for the computer link. The computer link parameters can be registered/monitored on the system information screen of the programmer.

The parameter items and their setting ranges are as follows:

* Station No. ····· 1-32 (initial value=1)
* Baud rate ····· 300, 600,1200, 2400, 4800, 9600, 19200(initial value 9600)
* Parity ····· None, odd, even (initial value=odd)
* Data length (bits) ···· 7, 8 (initial value=8)
* Stop bit ····· 1,2 (initial value=1)

(13) I/O Allocation Information
This stores I/O allocation information and unit base address designation information. This information is created either by executing the automatic I/O allocation command or by setting and registering an I/O module type for each slot (manual I/O allocation) on the I/O allocation information screen of the programmer.

(14) Interrupt Assignment Information
This stores the information of correspondence between the I/O interrupt program and I/O modules with interrupt functions. In the initial state (without setting this information), the lower number of I/O interrupt programs are assigned in sequence from the interrupt module closest to the CPU.
This information can be registered/monitored on the interrupt assignment screen of the programmer.

(15) Network Assignment Information
Information on the link register areas allocated to the data transmission modules (TOSLINE-S20, TOSLINE-F10) is stored here. This information can be registered/monitored on the network assignment information screen of the programmer.

2.3 User program

The user program is composed of each of the program types of main program, sub-programs (#1 - #4), interrupt programs (Timer, I/O#1 - I/O #8) and sub-routines. Of these program types, a main program must always be present. However, the other program types may not be present at all if they are not used. Therefore, needless to say, a user program can be configured with a main program only.

Also in the program types, the program can be divided into units called ‘blocks’ (block division is not necessary unless required). Block division is required in the following cases.

* When using languages other than ladder diagram (1 language/ block)
* When creating multiple SFC programs (1 SFC/block, see Section 5.3)
* When block division by control function units makes the program easier to see.

There are no restrictions on program capacities (number of steps) by program types and blocks. (Except in the case of SFC)

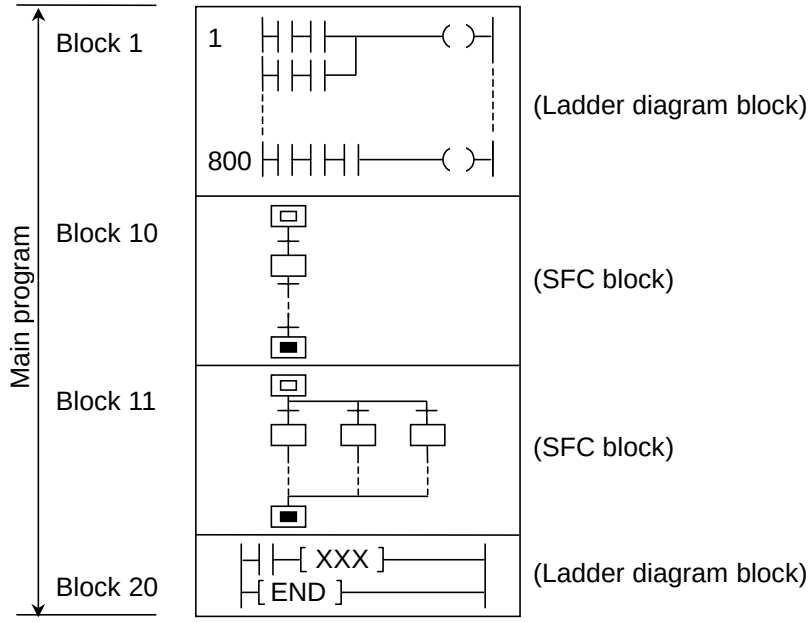
As block numbers, 1 to 256 are available. However, the block numbers need not be consecutive. When executing the program, the program is executed in sequence from the block with the lowest number.

2.3.1 Main program

The main program is the portion which is the core of the user program and is always executed every scan. The main program must be finished by the END instruction.

Although instructions may be present after the END instruction, these portions will not be executed. (However, they count in the number of steps used)

(Example of Main Program Configuration)



2.3.2 Sub-program

The sub-program is a program type to achieve the multi-tasking function. 4 sub-programs (Sub #1 - Sub #4) are provided.

Sub #1 is executed once in the first scan before the main program execution. Therefore, the Sub #1 can be used for the initial setting program.

Sub #2 can be selected from the two functions, the initial setting program in the case of power interruption and the normal sub-program function which can be controlled by other program types.

Sub #3 and Sub #4 are fixed as the normal sub-program function.

In the normal sub-program function of Sub #2, Sub #3 and Sub #4, the execution mode can be selected either the one time mode or the cyclic mode.

NOTE

For the details of the sub-program execution, see Part 2 Section 3.2. Also, for Sub #2, see Part 2 Section 5.5.2.

Each sub-program must be finished by the END instruction.
Although instructions may be present after the END instruction, these instructions will not be executed. (However, they count in the number of steps used)

Sub-programs execution conditions are summarized in the table below.

Sub No.	Execution condition
Sub #1	Executed once in the first scan before the main program execution, except when S2T is in the hot restart mode (S0400=1 and power recovery within 2s).
Sub #2	[Special mode] S0403=1 Executed once in the first scan before the main program execution when S2T is in the hot restart mode (S0400=1 and power recovery within 2s).
	[One time mode] S0403= 0 and S0405=0 Executed once when S0409 is changed from 0 to 1. (S0409 is reset to 0 automatically)
	[Cyclic mode] S0403=0 and S0405=1 Executed once per every specified number of scans which is specified by SW042, during S0409=1.
Sub #3	[One time mode] S0406=0 Executed once when S040A is changed from 0 to 1. (S040A is reset to 0 automatically)
	[Cyclic mode] S0406=1 Executed once per every specified number of scans which is specified by SW043, during S040A=1.
Sub #4	[One time mode] S0407=0 Executed once when S040B is changed from 0 to 1. (S040B is reset to 0 automatically)
	[Cyclic mode] S0407=1 Executed once per every specified number of scans which is specified by SW044, during S040B=1.

NOTE

The sub-program execution may be time-sliced by scan.
Therefore, to prevent the unexpected status changes of I/O registers (XW/YW) used in the sub-program, it is recommended to use the batch I/O inhibition (with i allocation) and the direct I/O instruction (I/O).

2.3.3 Interrupt program

There are a total of 9 types of interrupt program. These are 1 timer interrupt program which is executed cyclically with a cycle which is set in system information, and 8 I/O interrupt programs (#1 - #8) which are started by interrupt signals from I/O modules with interrupt function.

- Timer interrupt program
  This is executed cyclically with a cycle of 1-1000 ms which is registered in system information. When no cycle is registered (blank), it is not executed.
  Set the interval setting of the timer interrupt with 1 ms units in item 16 of the T-PDS system information screen.
  For details, see T-PDS operation manuals.

- I/O interrupt programs (#1 - #8)
  These are started by interrupt signals generated by I/O modules with the interrupt function. The coordination between the interrupt program numbers and the I/O modules with interrupt function can be changed by the interrupt assignment function.

Each interrupt program must be finished by the IRET instruction.

NOTE

(1) For details of interrupt program operation, see Part 2 Section 3.3.
(2) SFC cannot be used in the interrupt program.

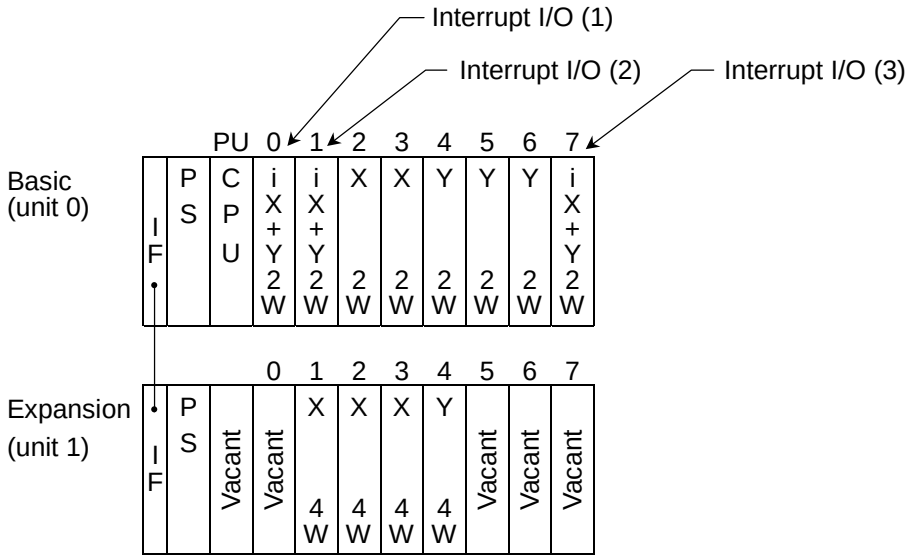
The following modules are available as the I/O module with the interrupt function (interrupt I/O).

- 2 channels pulse input
  (Part No.: PI632/672, allocation type: iX+Y2W)

When automatic I/O allocation is carried out in the state with interrupt I/O mounted, for coordination between the interrupt program number and the interrupt I/O, the lower number I/O interrupt programs are allocated in sequence from the interrupt I/O closest to the CPU. (See the example on the following page)

Example)

(1) Module mounting status



(2) Register allocation

Unit 0

Slot	Module type	Register
PU	—	—
0	iX+Y 2W	XW000, YW001
1	iX+Y 2W	XW002, YW003
2	X 2W	XW004, XW005
3	X 2W	XW006, XW007
4	Y 2W	XW008, YW009
5	Y 2W	XW010, YW011
6	Y 2W	XW012, YW013
7	iX+Y 2W	XW014, YW015

Unit 1

Slot	Module type	Register
0		
1	X 4W	XW016 ~ XW019
2	X 4W	XW020 ~ XW023
3	Y 4W	YW024 ~ YW027
4	Y 4W	YW028 ~ YW031
5	Vacant	—
6	Vacant	—
7	Vacant	—

(3) Interrupt program assignment

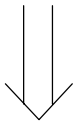
Program type	Corresponding input register	Corresponding interrupt I/O	Remarks
I/O interrupt program #1	XW000	Unit 0-Slot 0	Interrupt I/O (1)
I/O interrupt program #2	XW002	Unit 0-Slot 1	Interrupt I/O (2)
I/O interrupt program #3	XW014	Unit 0-Slot 7	Interrupt I/O (3)

The interrupt program assignment determined as the page before can be changed as follows.

Example)

Interrupt assignment information (before changing)

Interrupt level	Interrupt program No.	Input register No.
0	[1]	XW000
1	[2]	XW002
2	[3]	XW014



Change to

Interrupt assignment information (after changing)

Interrupt level	Interrupt program No.	Input register No.
0	[1]	XW000
1	[2]	XW002
2	[3]	XW014

In this example, interrupt programs for XW002 and XW004 are exchanged.

NOTE

By using the interrupt assignment function, the correspondence between the interrupt I/O and the interrupt program No. can be changed. However, the interrupt level (priority) is fixed as the hardware. The interrupt I/O mounted closer to the CPU has higher interrupt priority. The interrupt priority cannot be changed.

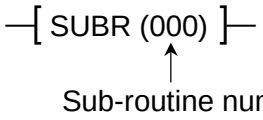
2.3.4 Sub-routines

When it is necessary to execute repetitions of the same process in a program, this process can be registered as a sub-routine. This sub-routine can be executed by calling it at the required location. By this means, the number of program steps can be reduced and, at the same time, the program becomes easier to see since the functions have been put in order.

Sub-routines can be called from other program types (main program, sub-programs, interrupt programs) and from other sub-routines (they can also be called from the action part of SFC).

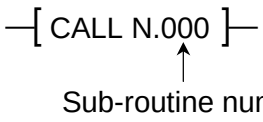
The sub-routine should be located in the program type “Sub-routine”, and started by SUBR instruction and finished by RET instruction. Up to 256 sub-routines can be programmed.

It is necessary to assign a sub-routine number to the SUBR instruction (sub-routine entry instruction). The effective numbers are from 0 to 255.

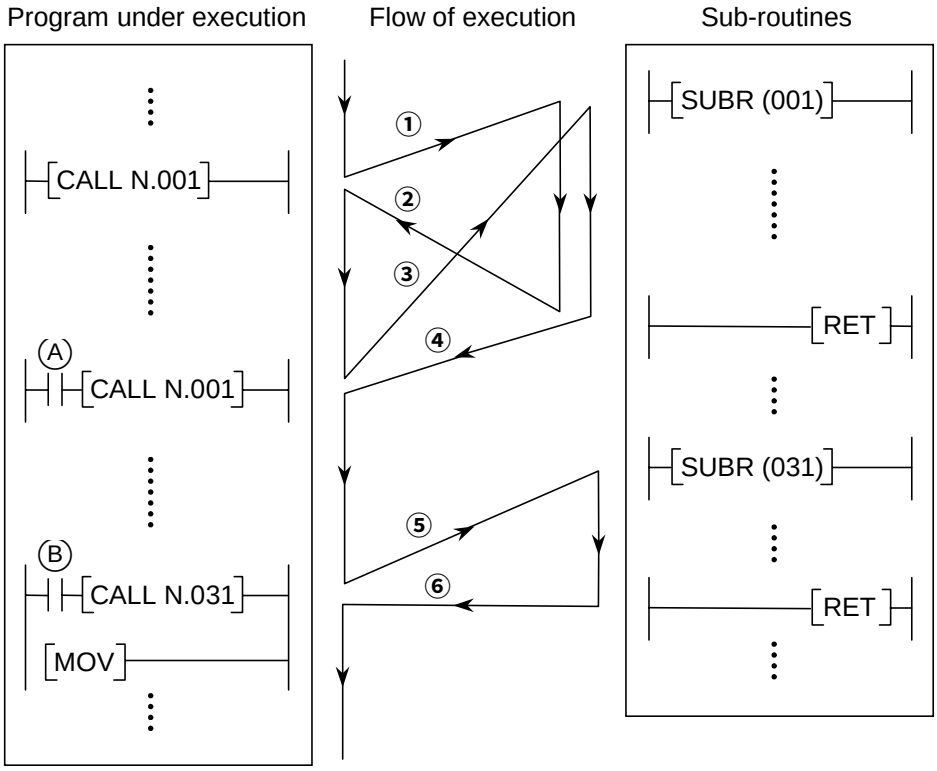


The RET instruction (sub-routine return instruction) has no sub-routine number.

The instruction which calls a registered sub-routine is the CALL instruction (sub-routine call instruction) of ladder diagram. The CALL instruction requires the number of the sub-routine it calls.



The following is an execution sequence when sub-routines are included.



① By the sub-routine 001 CALL instruction execution, the execution shifts to sub-routine 001
② When it has proceeded to the RET instruction, the execution returns to the instruction following the CALL instruction in ①
③ When device Ⓐ is ON, the CALL instruction is executed, and the execution shifts to sub-routine 001
④ When it has proceeded to the RET instruction, the execution returns to the instruction following the CALL instruction in ③
⑤ When device Ⓑ is ON, the CALL instruction is executed, and the execution shifts to sub-routine 031
⑥ When it has proceeded to the RET instruction, the execution returns to the instruction following the CALL instruction in ⑤ (the MOV instruction in this example)

NOTE

(1) Multiple sub-routines can be programmed in a block. However for execution monitor by programmer, 1 sub-routine on 1 block is recommended.
(2) SFC cannot be used in a sub-routine.
(3) Other sub-routines can be called from a sub-routine (nesting), up to 6 layers.
(4) Since the operation will become abnormal in cases such as calling the same sub-routine during the execution of a sub-routine, take care that the cases do not occur.

2.4 Comments

Comments can be added and stored in the S2T's user program memory. By this means, the user program becomes easier to understand.

The types of comments which can be stored in the S2T are tags/comments for registers, devices and SFC steps.

Tag ・・・・・・・・ up to 5 characters
Comment ・・・ up to 20 characters

The comments storage capacity is the rest of the program size setting out of total 32k/64k steps.
The maximum storage number of comments (tag and comment paired) is calculated as follows.

$(1024 \times (32 \text{ or } 64 - N) - 38) / 10$

N: Program size setting (assigned to the user program)

NOTE

Here, the comments which can be stored in the S2T are explained. Comments can also be saved in a disk file.
For the disk file usage, see separate manual for the programmer (T-PDS).

3.1 Overview

The area which stores the external input/output data, current values of timers and counters and the values of the variables for data processing is called the ‘user data’.

For user data, the storage location of the data is expressed by a combination of ‘function type’ and a sequence of numbers which starts from 0 (this is called the ‘address’)

Example) XW 005

- 005 → Address 005 (in this case it is the register address)
- XW → Function type XW=Input register

To say that the content of XW005 is 100 is to say that the numerical value 100 is stored in a location in the user data memory indicated by XW005.

Also, user data is divided into registers and devices according to the type of data to be stored. (Although the expression ‘relay’ is also used, a relay should be regarded as one type of device)

A ‘register’ is an area which stores 16 bits of data and it is expressed as a combination of a function type and a register address. (the register address is a decimal number)

Example) D 1024

- 1024 → Register address (decimal number)
- D → Function type D=Data register

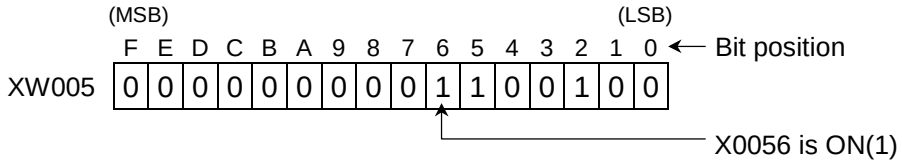
On the other hand a ‘device’ is an area which stores 1 bit of data (it expresses 1 or 0, in other words ON or OFF), and it is expressed as a combination of a function type and a device address. However, a device does not use an independent memory area. It is allocated as 1 bit in the 16 bits of the corresponding register. Therefore, the device address is expressed in the form of the corresponding register address+bit position.

Example) X 005 6

- 6 → Bit position (there are 16 positions 0-F)
- 005 → Register address (decimal number)
- X → Function type X=Input device (corresponds to input register XW)

The correspondence between register data and device data should be considered as follows.

Example) When it is said that the content of XW005 is 100, since the decimal number 100 is expressed as 1100100 in binary notation, this indicates that each of the bits of XW005 will be as follows.



At this time, the data of device X0056 corresponding to bit position “6” of XW005 is 1, that is to say X0056 is ON.

The correspondence of registers and devices is shown by function types.

- Input device (X)・・・・・・ corresponds to 1 bit of input register (XW)
- Output device (Y) ・・・・ corresponds to 1 bit of output register (YW)
- Auxiliary device (R)・・・ corresponds to 1 bit of auxiliary register (RW)
- Special device (S)・・・・ corresponds to 1 bit of special register (SW)
- Link device (Z)・・・・・・・ corresponds to 1 bit of link register (W)
- Link relay (L) ・・・・・・・・ corresponds to 1 bit of link register (LW)

The treatment of the other devices, I, O, T. and C., is slightly different. It is described in detail in Section 3.2.

The following Table shows the types of registers and devices and their address ranges. Their functions and methods of use are described in Section 3.2.

Function Type	Type Code	Address Range	Quantity	Expression Example
Input register	XW	000-511	Total 512 words	XW001
Output register	YW			YW034
Direct input register	IW			IW001
Direct output register	OW			OW034
Input device	X	0000-511F	Total 8192 points	X001 A
Output device	Y			Y0348
Direct input device	I			I0012
Direct output device	O			O0340
Auxiliary register	RW	000-999	1000 words	RW100
Auxiliary device	R	0000-999F	16000 points	R1001
Special register	SW	000-255	256 words	SW014
Special device	S	0000-255F	4096 points	S0140
Timer register	T	000-999	1000 words	T030
Timer device	T.	000-999	1000 points	T.030
Counter register	C	000-511	512 words	C199
Counter device	C.	000-511	512 points	C.199
Data register	D	0000-8191	8192 words	D4055
Link register	W	0000-2047	2048 words	W0200
Link device	Z	0000-999F	16000 points	Z2001
Link relay register	LW	0000-255	256 words	LW123
Link relay	L	0000-255F	4096 points	L123F
File register	F	0000-32767	32768 words	F0500
Index register	I	None	1 word	I
	J	None	1 word	J
	K	None	1 word	K

NOTE

In the S2T, 1 word is treated as equal to 16 bits, and the number of registers is counted in word units.

3.2 Registers and devices

The following Tables describe the functions and address ranges for each function type of registers and devices Input registers and Input devices.

Input registers and Input devices

Codes	Input registers ..... XW Input devices..... X
Addresses	Input registers ..... 000-511 (512 words) Input devices..... 0000-511F (8192 points) } Common use as output registers/output devices
Functions	These are allocated in the input module as register units (word units) by performing input/output allocation. The signal state inputted to the input module is stored in the corresponding input register by batch input/output timing (except for modules which have the designation attached when allocating). An input device expresses 1 bit of the corresponding input register. The data of input register/input devices basically do not change during 1 scan. However, when executing a direct I/O instruction (FLJN235), data is read from the corresponding input module when the instruction is executed and is stored in an input register/input device (XW/X). Thus, the data changes during the scan.

Output registers and Output devices

Codes	Output registers .... YW Output devices..... Y
Addresses	Output registers .... 000-511 (512 words) Output devices..... 0000-511F (8192 points) } Common use as input registers/input devices
Functions	These are allocated in the output module as register units (word units) by performing input/output allocation. The data stored in the output register is written to the corresponding output module by batch input/output timing, and the state of the output signal of the output module is determined (except for modules which have the designation attached when allocating). An output device expresses 1 bit of an output register.

Direct input registers and Direct input devices

Codes	Direct input registers ..... IW Direct input devices..... I
Addresses	Direct input registers ..... 000-511 (correspond to input registers (XW)) Direct input devices..... 0000-511F (correspond to input devices (X))
Functions	Direct input registers/direct input devices do not themselves indicate specific memories. When the instruction which uses these registers/devices is executed, they operate and read data directly from the input module corresponding to the address. These registers/devices are used when using the S2T as the direct input/output system (direct system) and not the batch input/output system (refresh system). Example) I0000 —┤├— NO contact instruction of I0000 When executing the instruction, the bit data corresponding to X0000 is read from the input module and the instruction is executed by this data. (The X0000 data is not affected) —[IW005 MOV RW 100]— Transfer instruction fromIW005 to RW100 When executing the instruction, the word data corresponding to XW005 is read from the input module and is transferred to RW100. (The XW005 data is not affected)

Direct output registers and Direct output devices

Codes	Direct output registers ... OW Direct output devices..... O
Addresses	Direct input registers ..... 000-511 (correspond to output registers (YW)) Direct input devices..... 0000-511F (correspond to output devices (Y))
Functions	When instructions are executed using direct output registers/direct output devices, data is stored in the corresponding output registers/output devices (YW/Y). Then, this output register (YW) data is written directly to the corresponding output module. These registers/devices are used when using the S2T as the direct input/output system (direct system) and not the batch input/output system (refresh system). Example) O0020 —( )—┤ Coil O0020 When the instruction is executed, the data (ON/OFF data) corresponding to the left link state is stored in Y0020. Then the 16-bit data of YW002 is written to the corresponding output module.

Auxiliary registers and Auxiliary devices

Codes	Auxiliary registers.....RW Auxiliary devices .....R
Addresses	Output registers.....000-999 (1000 words) Output devices .....0000-999F (corresponding to one bit in a register, 16000 points)
Functions	These are general purpose registers/devices which can be used for temporary storage of execution results in a program. An auxiliary register is used for storing 16-bit data. An auxiliary device indicates 1 bit in an auxiliary register. Auxiliary registers/devices can be designated as retentive memory areas.

Special registers and Special devices

Codes	Special registers ..... SW Special devices ..... S
Addresses	Special registers ..... 000-255 (256 words) Special devices ..... 0000-255F (corresponding to one bit in a register, 4096 points)
Functions	These are registers/devices which have special function such as fault flags (Error down/Warning) which are set when the CPU detects a malfunction; timing relays and clock calendar data (year, month, day, hour, minute, second, day of week) which are updated by the CPU; flags/data which the user sets for executing operational control of the sub-programs. For details, see the following table.

Timer registers and Timer devices

Codes	Timer registers ..... T Timer devices ..... T.
Addresses	Timer registers ..... 000-999 (1000 words) Timer devices ..... 000-999 (1000 points)
Functions	The timer registers are used together with timer instructions (TON, TOE, SS, TRG), and store elapsed time (increment system) when the timer is operating. Also, the timer devices are linked to the operation of the timer registers with the same address, and store the output results of timer instructions. The timer registers can be designated as retentive memory areas.

Counter registers and Counter devices

Codes	Counter registers ..... C Counter devices ..... C.
Addresses	Counter registers ..... 000-511 (512 words) Counter devices ..... 000-511 (512 points)
Functions	The counter registers are used together with counter instructions (CNT, U/D), and store the current count value when the counter is operating. Also, the counter devices are linked to the operation of the counter registers with the same address, and store the output results of counter instructions. The counter registers can be designated as retentive memory areas.

Data registers

Codes	D
Addresses	000-8191 (8192 words)
Functions	General-purpose registers which can be used for such purposes as a temporary memory for arithmetic results and the storage of control parameters. Apart from the fact that bit designation is not possible, they can be used in the same way as auxiliary registers. Data registers can be designated as retentive memory areas. Also, when a peripheral memory is used, D0000-D4095 become subjects for the initial load. In the 'memory protect' state (P-RUN), data writing to D0000-D4095 is prohibited.

Link registers and Link device (TOSLINE-S20)

Codes	Link registers.....W Link devices .....Z
Addresses	Link registers.....0000-2047 (2048 words) Link devices .....0000-999F (corresponding to the leading 1000 words of the register, 16000 points)
Functions	Used for a data link by the TOSLINE-S20. For the leading 1000 words (W0000-W0999) of he link registers, bit designation is possible as link devices (Z0000-Z999F). For areas not allocated to TOSLINE-S20, they can be used in the same way as auxiliary registers and data registers.

Link registers and Link relays (TOSLINE-F10)

Codes	Link registers.....LW Link relays.....L
Addresses	Link registers.....000-255 (256 words) Link relays.....000-255F (4096 points)
Functions	Used as registers/relays for remote I/O by the TOSLINE-F10. When TOSLINE-F10 is not used, they can be used in the same way as auxiliary relays.

File registers

Codes	F
Addresses	0000-32767 (32768 words)
Functions	Can be used in the same way as data registers for such as storing control parameters and storing field collection data. Bit designation is not possible. The whole file register area is retained for power off. The file registers can also be used for the sampling buffer.

Index registers

Codes	I, J, K (3 types, 3 words)
Addresses	None
Functions	When registers (apart from index registers) are used by instructions, apart from the normal address designation system (direct address designation, for instance D0100), indirect designation (indirect address designation, for instance D0100.I) is possible by using the index registers. (If, for instance the content of I is 5, D0100.I indicates 00105) For indirect address designation, see Section 3.4.

Tables of special register/special relays are shown below.

Overall map

Register	Content
SW000	Operation mode, error flags, warning flags
SW001	CPU error-related flags
SW002	I/O error-related flags
SW003	Program erro-related flags, IC memory card status
SW004	Timing relays
SW005	Carry flag, error flag
SW006	Flags related to error during program execution
SW007 ~ SW013	Clock-calendar data (Year, month, day, hour, minute, second, day of the week)
SW014	Flags related to bit pattern check/data validity check
SW015	Flags related to I/O error mapping, etc.
SW016 ~ SW033	Diagnosis display record (system diagnosis)
SW034 ~ SW037	Annunciator relay (system diagnosis)
SW038	Reserve (for future use)
SW039	Interrupt program execution status
SW040	Sub-program execution control
SW041	Sub-program execution status
SW042 ~ SW044	Sub-program execution intervals (for cyclic mode)
SW045	Power interruption continuous operation time
SW046 ~ SW049	I/O error map
SW050 ~ SW077	Reserve (for future use)

Overall map (continued)

Register	Content
SW078 ~ SW093	TOSLINE-F10 commands/status
SW094 ~ SW109	TOSLINE-F10 scan error map
SW110	TOSLINE-S20 CH1 station status
SW111	TOSLINE-S20 CH2 station status
SW112 ~ SW115	TOSLINE-S20 CH1 online map
SW116 ~ SW119	TOSLINE-S20 CH2 online map
SW120 ~ SW123	TOSLINE-S20 CH1 standby map
SW124 ~ SW127	TOSLINE-S20 CH2 standby map
SW128 ~ SW191	TOSLINE-S20 scan healthy map
SW192 ~ SW255	Reserve (for future use)

Special device	Name	Function
S0000	Operation mode	0 : Initializing 4 : HOLD mode B : D-STOP 1 : HALT mode 6 : ERROR mode D : S-HALT 2 : RUN mode 9 : D-HALT E : S-RUN 3 : Run-F mode A : D-RUN F : S-STOP
S0001		
S0002		
S0003		
S0004	CPU error (Down)	ON when error occurs (OR condition of related flag in SW001)
S0005	I/O error (Down)	ON when error occurs (OR condition of related flag in SW002)
S0006	Program error (Down)	ON when error occurs (OR condition of related flag in SW003)
S0007	EEPROM alarm (Warning)	ON when EEPROM number of writing times 100,000 exceeded (operation continues)
S0008	Constant scan delay (Warning)	ON when actual scan time exceeds the constant scan time setting
S0009	I/O alarm (Warning)	ON when I/O error detected by I/O error mapping
S000A	Calendar LSI error (Warning)	ON when clock-calendar data fault (operation continues)
S000B		Reserve (for future use)
S000C		
S000D	TOSLINE-F10 error (Warning)	ON when TOSLINE-F10 error (operation continues)
S000E	TOSLINE-S20 error (Warning)	ON when TOSLINE-S20 error (operation continues)
S000F	Battery volatge low (Warning)	ON when battery voltage low (operation continues)
S0010	System ROM error (Down)	ON when system ROM error
S0011	System RAM error (Down)	ON when system RAM error
S0012	Program memory error (Down)	ON when program memory (RAM) error
S0013	EEPROM error (Down)	ON when EEPROM error
S0014		Reserve (for future use)
S0015	LP error (Down)	ON when language processor (LP) error
S0016	Main CPU error (Down)	ON when main error (Down)
S0017		Reserve (for future use)
S0018		
S0019		
S001A		
S001B		
S001C		
S001D		
S001E		
S001F	Watch-dog timer error (Down)	ON when watch-dog timer error occurs

*1) This area is for reference only. (Do not write)
*2) The error flags are reset at the beginning of RUN mode.

Special device	Name	Function
S0020	I/O bus error (Down)	ON when I/O bus error occurs
S0021	I/O mismatch error (Down)	ON when I/O mismatch error occurs (allocation information and mounting state do not agree)
S0022	I/O response error (Down)	ON when no I/O response occurs
S0023	I/O parity error (Down)	ON when I/O data parity error occurs
S0024		Reserve (for future use)
S0025	I/O interrupt error (Warning)	ON when unused I/O interrupt occurs (operation continues)
S0026	Special module error (Warning)	ON when fault occurs in special module (operation continues)
S0027		Reserve (for future use)
S0028		
S0029		
S002A		
S002B		
S002C		
S002D		
S002E		
S002F		
S0030	Program error	ON when program error occurs (OR condition of SW006 flags)
S0031	Scan timer error (Down)	ON when scan cycle exceeds the limit value
S0032		Reserve (for future use)
S0033		
S0034		
S0035		
S0036		
S0037		
S0038		
S0039		
S003A		
S003B		
S003C		
S003D		
S003E		
S003F		

*1) This area is for reference only. (Do not write)
*2) The error flags are reset at the beginning of RUN mode.

Special device	Name	Function	
S0040	Timing relay 0.1 sec	0.05 sec OFF/0.05 sec ON (Cycle 0.1 sec)	All OFF when RUN starts up
S0041	Timing relay 0.2 sec	0.1 sec OFF/0.1 sec ON (Cycle 0.2 sec)	
S0042	Timing relay 0.4 sec	0.2 sec OFF/0.2 sec ON (Cycle 0.4 sec)	
S0043	Timing relay 0.8 sec	0.4 sec OFF/0.4 sec ON (Cycle 0.8 sec)	
S0044	Timing relay 1.0 sec	0.5 sec OFF/0.5 sec ON (Cycle 1.0 sec)	
S0045	Timing relay 2.0 sec	1.0 sec OFF/1.0 sec ON (Cycle 2.0 sec)	
S0046	Timing relay 4.0 sec	2.0 sec OFF/2.0 sec ON (Cycle 4.0 sec)	
S0047	Timing relay 8.0 sec	4.0 sec OFF/4.0 sec ON (Cycle 8.0 sec)	
S0048		Reserve (for future use)	
S0049			
S004A			
S004B			
S004C			
S004D			
S004E	Always OFF	Always OFF	
S004F	Always ON	Always ON	
S0050	CF (carry flag)	Used by instructions with carry	
S0051	ERF (Error flag)	ON through error occurrence when executing instructions (linked with each error flag of SW006)	
S0052		Reserve (for future use)	
S0053			
S0054			
S0055			
S0056			
S0057			
S0058			
S0059			
S005A			
S005B			
S005C			
S005D			
S005E			
S005F			

*) This area (except for S0050, S0051) is for reference only. (Writing is ineffective)

Special device	Name	Function
S0060	Illegal instruction detection (Down)	ON when illegal instruction detected
S0061		Reserve (for future use)
S0062		
S0063		
S0064	Boundary error (Warning)	ON when address range exceeded by indirect address designation (operation continues)
S0065	Address boundary error (Warning)	ON when destination (indirect) error by CALL instruction or JUMP instruction (operation continues)
S0066		Reserve (for future use)
S0067		
S0068	Division error (Warning)	ON when error occurs by division instruction (operation continues)
S0069	BOD data error (Warning)	ON when fault data detected by BCD instruction (operation continues)
S006A	Table operation error (Warning)	ON when table limits exceeded by table operation instruction (operation continues)
S006B	Encode error (Warning)	ON when error occurs by encode instruction (operation continues)
S006C	Address registration error (Warning)	ON when destination for CALL instruction or JUMP instruction unregistered (operation continues)
S006D	Nesting error (Warning)	ON when nesting exceeded by CALL instruction, FOR instruction or MCSn instruction (operation continues)
S006E		Reserve (for future use)
S006F		

*1) The error flags are reset at the beginning of RUN mode.
*2) For warning flags, resetting by user program is possible.

Special register	Name	Function	
SW007	Calendar data (Year)	Last 2 digits of the calendar year (91, 92, ...)	Stored in lower 8 bits by BCD code
SW008	Calendar data (Month)	Month (01-12)	
SW009	Calendar data (Day)	Day (01-31)	
SW010	Calendar data (Hour)	Hour (00-23)	
SW011	Calendar data (Minute)	Minute (00-59)	
SW012	Calendar data (Second)	Second (00-59)	
SW013	Calendar data (Day of the week)	Day of the week (Sunday=00, Monday= 01, ...Saturday=06)	

*1) The clock-calendar data setting is performed by calendar setting instruction (CLND) or by calendar setting operation by programmer. (It is ineffective to write data directly to the special registers)
*2) When the data cannot be read correctly due to the calendar LSI fault, these registers become H00FF.
*3) Calendar accuracy is ± 30 seconds/month.

Special device	Name	Function
S0140	Bit/register check	Bit pattern/register value check is ecuted by setting ON
S0141	Bit/register check result	ON when either S0142-S0146 is ON
S0142	Bit pattern check result	ON when bit pattern check error detected
S0143	Register value check result (1)	ON when register value check error detected for register 1
S0144	Register value check result (2)	ON when register value check error detected for register 2
S0145	Register value check result (3)	ON when register value check error detected for register 3
S0146	Register value check result (4)	ON when register value check error detected for register 4
S0147		Reserve (for future use)
S0148		
S0149		
S014A		
S014B		
S014C		
S014D		
S014E		
S014F		
S0150	I/O error mapping	I/O error mapping is executed by setting ON
S0151		Reserve (for future use)
S0152		
S0153		
S0154		
S0155		
S0156		
S0157		
S0158		
S0159		
S015A		
S015B		
S015C		
S015D		
S015E		
S015F	Checkpoint for bit/register check	OFF: before program execution ON: after program execution

Special register	Name	Function
SW016	First error code	• The designated error codes (1-64) are stored in order of execution in SW018-SW033 (the earlier the code, the lower the address), and the number of registration (SW017) is updated. • The earliest error code occurring (the content of SW018) is stored in the leading error code (SW016). • The registered error codes are cancelled one by one by the execution of the diagnostic display reset instruction or by a reset operation by the programmer. At this time, the number of registers is reduced by 1 and the storage positions of the error codes are shifted up.
SW017	Number of registration	
SW018	Error code (First)	
SW019	Error code (2)	
SW020	Error code (3)	
SW021	Error code (4)	
SW022	Error code (5)	
SW023	Error code (6)	
SW024	Error code (7)	
SW025	Error code (8)	
SW026	Error code (9)	
SW027	Error code (10)	
SW028	Error code (11)	
SW029	Error code (12)	
SW030	Error code (13)	
SW031	Error code (14)	
SW032	Error code (15)	
SW033	Error code (16)	

Special device	Name	Function
S0340	Annunciator relay 1	• The annunciator relays corresponding to the error codes registered in SW018-SW033 become ON
S0341	Annunciator relay 2	
S0342	Annunciator relay 3	
S0343	Annunciator relay 4	
S0344	Annunciator relay 5	
S0345	Annunciator relay 6	
S0346	Annunciator relay 7	
S0347	Annunciator relay 8	
S0348	Annunciator relay 9	
S0349	Annunciator relay 10	
S034A	Annunciator relay 11	
S0348	Annunciator relay 12	
S034C	Annunciator relay 13	
S034D	Annunciator relay 14	
S034E	Annunciator relay 15	
S034F	Annunciator relay 16	

Special device	Name	Function
S0350	Annunciator relay 17	• The annunciator relays corresponding to the error codes registered in SW018-SW033 become ON
S0351	Annunciator relay 18	
S0352	Annunciator relay 19	
S0353	Annunciator relay 20	
S0354	Annunciator relay 21	
S0355	Annunciator relay 22	
S0356	Annunciator relay 23	
S0357	Annunciator relay 24	
S0358	Annunciator relay 25	
S0359	Annunciator relay 26	
S035A	Annunciator relay 27	
S035B	Annunciator relay 28	
S035C	Annunciator relay 29	
S035D	Annunciator relay 30	
S035E	Annunciator relay 31	
S035F	Annunciator relay 32	
S0360	Annunciator relay 33	
S0361	Annunciator relay 34	
S0362	Annunciator relay 35	
S0363	Annunciator relay 36	
S0364	Annunciator relay 37	
S0365	Annunciator relay 38	
S0366	Annunciator relay 39	
S0367	Annunciator relay 40	
S0368	Annunciator relay 41	
S0369	Annunciator relay 42	
S036A	Annunciator relay 43	
S036B	Annunciator relay 44	
S036C	Annunciator relay 45	
S036D	Annunciator relay 56	
S036E	Annunciator relay 47	
S036F	Annunciator relay 48	

Special device	Name	Function
S0370	Annunciator relay 49	• The annunciator relays corresponding to the error codes registered in SW018-SW033 become ON
S0371	Annunciator relay 50	
S0372	Annunciator relay 51	
S0373	Annunciator relay 52	
S0374	Annunciator relay 53	
S0375	Annunciator relay 54	
S0376	Annunciator relay 55	
S0377	Annunciator relay 56	
S0378	Annunciator relay 57	
S0379	Annunciator relay 58	
S037A	Annunciator relay 59	
S037B	Annunciator relay 60	
S037C	Annunciator relay 61	
S037D	Annunciator relay 62	
S037E	Annunciator relay 63	
S037F	Annunciator relay 64	
SW38	Programmer port response delay	0 ~ 30 × 10 ms

Special device	Name	Function
S0390	Timer interrupt execution status	ON during execution
S0391	I/O interrupt #1 execution status	
S0392	I/O interrupt #2 execution status	
S0393	I/O interrupt #3 execution status	
S0394	I/O interrupt #4 execution status	
S0395	I/O interrupt #5 execution status	
S0396	I/O interrupt #6 execution status	
S0397	I/O interrupt #7 execution status	
S0398	I/O interrupt #8 execution status	
S0399		Reserve (for future use)
S039A		
S039B		
S039C		
S039D		
S039E		
S039F		

Special device	Name	Function
S0400	Hot restart mode	ON when hot restart mode (setting by program is available)
S0401	HOLD device	ON during HOLD mode (setting by program is available)
S0402		Reserve (for future use)
S0403	Sub-program #2 mode	Sub-program #2 mode setting (OFF: Normal ON: Special)
S0404		Reserve (for future use)
S0405	Sub-program #2 execution mode	Sub-program #2 execution mode setting (OFF: One time ON: Cyclic)
S0406	Sub-program #3 execution mode	Sub-program #3 execution mode setting (OFF: One time ON: Cyclic)
S0407	Sub-program #4 execution mode	Sub-program #4 execution mode setting (OFF: One time ON: Cyclic)
S0408		Reserve (for future use)
S0409	Sub-program #2 request	Sub-program #2 request command (Execution request by setting ON)
S040A	Sub-program #3 request	Sub-program #3 request command (Execution request by setting ON)
S040B	Sub-program #4 request	Sub-program #4 request command (Execution request by setting ON)
S040C		Reserve (for future use)
S040D		
S040E		
S040F		
S0410	Sub-program #1 execution status	ON during sub-program #1 execution
S0411	Sub-program #2 execution status	ON during sub-program #2 execution
S0412	Sub-program #3 execution status	ON during sub-program #3 execution
S0413	Sub-program #4 execution status	ON during sub-program #4 execution
S0414		Reserve (for future use)
S0415	Sub-program #2 delay (Warning)	ON when sub-program #2 execution delay (cyclic mode)
S0416	Sub-program #3 delay (Warning)	ON when sub-program #3 execution delay (cyclic mode)
S0417	Sub-program #4 delay (Warning)	ON when sub-program #4 execution delay (cyclic mode)
S0418		Reserve (for future use)
S0419		
S041A		
S041B		
S041C		
S041D		
S041E		
S041F		

Special register	Name	Function
SW042	Sub-program #2 interval	Number of scans for sub-program #2 cyclic mode
SW043	Sub-program #3 interval	Number of scans for sub-program #3 cyclic mode
SW044	Sub-program #4 interval	Number of scans for sub-program #4 cyclic mode
SW045		Reserve (for future use)

Special device	Name	Function
SW046 ~ SW052		Reserve (for future use)

Special register	Name	Function
SW067	Write protect for SEND/RECV	Used for setting write protect against SEND and RECV instructions

Special device	Name		Function
S0780	TOSLINE-F10 CH1 command	Transmission status	ON during transmission
S0781		Output inhibit status	ON when output inhibit mode
S0782		Re-configuration	ON during re-configuration
S0783			Reserve (for future use)
S0784		Scan transmission error	On when scan transmission error occurs
S0785			Reserve (for future use)
S0786			
S0787			
S0788		Transmission stop	Transmission stop by setting ON
S0789		Output inhibit	Output inhibit by setting ON
S078A			Reserve (for future use)
S078B			
S078C			
S078D			
S078E			
S078F			
S0790	TOSLINE-F10 CH1 status	Transmission status	ON during transmission
S0791		Scan transmission	ON during scan transmission
S0792			Reserve (for future use)
S0793			
S0794			
S0795		MS operation mode	OFF: Normal mode ON: Test mode
S0796			Reserve (for future use)
S0797			
S0798			
S0799			
S079A			
S079B			
S079C			
S079D			
S079E			
S079F			

*) Refer to the TOSLINE-F10 manual for details.

Special register	Name	Function
SW080	TOSLINE-F10 CH2 command	• Bit assignment in the register is the same as SW078 and SW079.
SW081	TOSLINE-F10 CH2 status	
SW082	TOSLINE-F10 CH3 command	
SW083	TOSLINE-F10 CH3 status	
SW084	TOSLINE-F10 CH4 command	
SW085	TOSLINE-F10 CH4 status	
SW086	TOSLINE-F10 CH5 command	
SW087	TOSLINE-F10 CH5 status	
SW088	TOSLINE-F10 CH6 command	
SW089	TOSLINE-F10 CH6 status	
SW090	TOSLINE-F10 CH7 command	
SW091	TOSLINE-F10 CH7 status	
SW092	TOSLINE-F10 CH8 command	
SW093	TOSLINE-F10 CH8 status	

Special register	Name		Function
SW094	TOSLINE-F10 scan error map	LW000 ~ LW015	• The corresponding bit comes ON when the LW register is not updated normally. • The lowest address of LW register corresponds to bit 0 in the SW register, and in the order.
SW095		LW016 ~ LW031	
SW096		LW032 ~ LW047	
SW097		LW048 ~ LW063	
SW098		LW064 ~ LW079	
SW099		LW080 ~ LW095	
SW100		LW096 ~ LW111	
SW101		LW112 ~ LW127	
SW102		LW128 ~ LW143	
SW103		LW144 ~ LW159	
SW104		LW160 ~ LW175	
SW105		LW176 ~ LW191	
SW106		LW192 ~ LW207	
SW107		LW208 ~ LW223	
SW108		LW224 ~ LW239	
SW109		LW240 ~ LW255	

Special device	Name		Function
S1100	TOSLINE-S20 CH1 station status	Test mode	ON when test mode
S1101			Reserve (for future use)
S1102			
S1103			
S1104		Master/slave	ON when master station
S1105		Scan inhibit	ON when scan transmission inhibited
S1106			Reserve (for future use)
S1107			
S1108			
S1109			
S110A			
S110B			
S110C		Online	ON when online mode
S110D		Standby	ON when standby mode
S110E		Offline	ON when offline mode
S110F		Down	ON when down mode
S1110	TOSLINE-S20 CH2 station status	Test mode	ON when test mode
S1111			Reserve (for future use)
S1112			
S1113			
S1114		Master/slave	ON when master station
S1115		Scan inhibit	ON when scan transmission inhibited
S1116			Reserve (for future use)
S1117			
S1118			
S1119			
S111A			
S111B			
S111C		Online	ON when online mode
S111D		Standby	ON when standby mode
S111E		Offline	ON when offline mode
S111F		Down	ON when down mode

*) Refer to the TOSLINE-S20 manual for details.

Special register	Name		Function
SW112	TOSLINE-S20 CH1 online map	station No. 1 ~ No. 16	• The corresponding bit is ON when the station is online. • The lowest station number corresponds to bit 0 in the SW register, and in the order.
SW113		station No. 17 ~ No. 32	
SW114		station No. 33 ~ No. 48	
SW115		station No. 49 ~ No. 64	
SW116	TOSLINE-S20 CH2 online map	station No. 1 ~ No. 16	
SW117		station No. 17 ~ No. 32	
SW118		station No. 33 ~ No. 48	
SW119		station No. 49 ~ No. 64	
SW120	TOSLINE-S20 CH1 standby map	station No. 1 ~ No. 16	• The corresponding bit is ON when the station is standby. • The lowest station number corresponds to bit 0 in the SW register, and in the order.
SW121		station No. 17 ~ No. 32	
SW122		station No. 33 ~ No. 48	
SW123		station No. 49 ~ No. 64	
SW124	TOSLINE-S20 CH2 standby map	station No. 1 ~ No. 16	
SW125		station No. 17 ~ No. 32	
SW126		station No. 33 ~ No. 48	
SW127		station No. 49 ~ No. 64	

Special register	Name		Function
SW128	TOSLINE-S20 scan healthy map	W0000 ~ W0015	• The corresponding bit is ON when the W register is updated normally. • The lowest address of W register corresponds to bit 0 in the SW register, and in the order.
SW129		W0016 ~ W0031	
SW130		W0032 ~ W0047	
SW131		W0048 ~ W0063	
SW132		W0064 ~ W0079	
SW133		W0080 ~ W0095	
SW134		W0096 ~ W0111	
SW135		W0112 ~ W0127	
SW136		W0128 ~ W0143	
SW137		W0144 ~ W0159	
SW138		W0160 ~ W0175	
SW139		W0176 ~ W0191	
SW140		W0192 ~ W0207	
SW141		W0208 ~ W0223	
SW142		W0224 ~ W0239	
SW143		W0240 ~ W0255	

Special register	Name		Function
SW144	TOSLINE-S20 scan healthy map	W0256 ~ W0271	• The corresponding bit is ON when the W register is updated normally. • The lowest address of W register corresponds to bit 0 in the SW register, and in the order.
SW145		W0272 ~ W0278	
SW146		W0288 ~ W0303	
SW147		W0304 ~ W0319	
SW148		W0320 ~ W0335	
SW149		W0336 ~ W0351	
SW150		W0352 ~ W0367	
SW151		W0368 ~ W0383	
SW152		W0384 ~ W0399	
SW153		W0400 ~ W0415	
SW154		W0416 ~ W0431	
SW155		W0432 ~ W0447	
SW156		W0448 ~ W0463	
SW157		W0464 ~ W0479	
SW158		W0480 ~ W0495	
SW159		W0496 ~ W0511	
SW160		W0512 ~ W0527	
SW161		W0528 ~ W0543	
SW162		W0544 ~ W0559	
SW163		W0560 ~ W0575	
SW164		W0576 ~ W0591	
SW165		W0592 ~ W0607	
SW166		W0608 ~ W0623	
SW167		W0624 ~ W0639	
SW168		W0640 ~ W0655	
SW169		W0656 ~ W0671	
SW170		W0672 ~ W0687	
SW171		W0688 ~ W0703	
SW172		W0704 ~ W0719	
SW173		W0720 ~ W0735	
SW174		W0736 ~ W0751	
SW175		W0752 ~ W0767	

Special register	Name		Function
SW176	TOSLINE-S20 scan healthy map	W0768 ~ W0783	• The corresponding bit is ON when the W register is updated normally. • The lowest address of W register corresponds to bit 0 in the SW register, and in the order.
SW177		W0784 ~ W0799	
SW178		W0800 ~ W0815	
SW179		W0816 ~ W0831	
SW180		W0832 ~ W0847	
SW181		W0848 ~ W0863	
SW182		W0864 ~ W0879	
SW183		W0880 ~ W0895	
SW184		W0896 ~ W0911	
SW185		W0912 ~ W0927	
SW186		W0928 ~ W0943	
SW187		W0944 ~ W0959	
SW188		W0960 ~ W0975	
SW189		W0976 ~ W0991	
SW190		W0992 ~ W1007	
SW191		W1008 ~ W1023	

Special register	Name		Function
SW192	TOSLINE-S20 scan healthy map	W1024 ~ W1039	• The corresponding bit is ON when the W register is updated normally. • The lowest address of W register corresponds to bit 0 in the SW register, and in the order.
SW193		W1040 ~ W1055	
SW194		W1056 ~ W1071	
SW195		W1072 ~ W1087	
SW196		W1088 ~ W1103	
SW197		W1104 ~ W1119	
SW198		W1120 ~ W1135	
SW199		W1136 ~ W1151	
SW200		W1152 ~ W1167	
SW201		W1168 ~ W1183	
SW202		W1184 ~ W1199	
SW203		W1200 ~ W1215	
SW204		W1216 ~ W1231	
SW205		W1232 ~ W1247	
SW206		W1248 ~ W1263	
SW207		W1264 ~ W1279	
SW208		W1280 ~ W1295	
SW209		W1296 ~ W1311	
SW210		W1312 ~ W1327	
SW211		W1328 ~ W1343	
SW212		W1344 ~ W1359	
SW213		W1360 ~ W1375	
SW214		W1376 ~ W1391	
SW215		W1392 ~ W1407	
SW216		W1408 ~ W1423	
SW217		W1424 ~ W1439	
SW218		W1440 ~ W1455	
SW219		W1456 ~ W1471	
SW220		W1472 ~ W1487	
SW221		W1488 ~ W1503	
SW222		W1504 ~ W1519	
SW223		W1520 ~ W1535	

NOTE

In case of TOSLINE-S20LP, it does not have the scan healthy map. Therefore these SW registers are not effective for the TOSLINE-S20LP.

Special register	Name		Function
SW224	TOSLINE-S20 scan healthy map	W1536 ~ W1551	• The corresponding bit is ON when the W register is updated normally. • The lowest address of W register corresponds to bit 0 in the SW register, and in the order.
SW225		W1552 ~ W1567	
SW226		W1568 ~ W1583	
SW227		W1584 ~ W1599	
SW228		W1600 ~ W1615	
SW229		W1616 ~ W1631	
SW230		W1632 ~ W1647	
SW231		W1648 ~ W1663	
SW232		W1664 ~ W1679	
SW233		W1680 ~ W1695	
SW234		W1696 ~ W1711	
SW235		W1712 ~ W1727	
SW236		W1728 ~ W1743	
SW237		W1744 ~ W1759	
SW238		W1760 ~ W1775	
SW239		W1776 ~ W1791	
SW240		W1792 ~ W1807	
SW241		W1808 ~ W1823	
SW242		W1824 ~ W1839	
SW243		W1840 ~ W1855	
SW244		W1856 ~ W1871	
SW245		W1872 ~ W1887	
SW246		W1888 ~ W1903	
SW247		W1904 ~ W1919	
SW248		W1920 ~ W1935	
SW249		W1936 ~ W1951	
SW250		W1952 ~ W1967	
SW251		W1968 ~ W1983	
SW252		W1984 ~ W1999	
SW253		W2000 ~ W2015	
SW254		W2016 ~ W2031	
SW255		W2032 ~ W2047	

NOTE

In case of TOSLINE-S20LP, it does not have the scan healthy map. Therefore these SW registers are not effective for the TOSLINE-S20LP.

3.3 Register data types

It has already been explained the register is “a location which stores 16 bits of data”. In the S2T instructions, the following types of data can be processed using single registers or multiple consecutive registers.

- Unsigned integers (integers in the range 0 to 65535)
- Integers (integers in the range -32768 to 32767)
- BCD (integers in the range 0 to 9999 expressed by BCD code)
- Unsigned double-length integers (integers in the range 0 to 4294967295)
- Double-length integers (integers in the range -2147483648 to 2147483647)
- Double-length BCD (integers in the range 0 to 99999999 expressed by BCD code)
- Floating point data (real number in the range -3.40282×10^{38} to 3.40282×10^{38})

However, there are no dedicated registers corresponding to the types for processing these types of data. The processing of the register data varies according to which instruction is used.

In other words, as shown in the following example, even when the same register is used, if the data type of the instruction differs, the processing of the register data will also differ.

Example)

When the value of D0005 is HFFFF (hexadecimal FFFF):

(1) In the unsigned comparison instruction (Greater than),

—[D0005 U > 100]— decision output (ON when true)

The value of D0005 is regarded as 65535 (unsigned integer), therefore it is judged to be greater than the compared value (100) and the output of the instruction becomes ON.

(2) In the (signed) comparison instruction (Greater than),

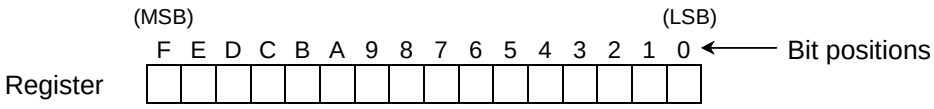
—[D0005 > 100]— decision output (ON when true)

The value of D0005 is regarded as -1 (integer), therefore it is judged not to be greater than the compared value (100) and the output of the instruction becomes OFF.

In this way, since there is no classification of registers by data type, it is possible to execute complex data operations provided their use is thoroughly understood. However, in order to make the program easier to see, it is recommended that registers be used by allocation by data types (1 register is processed by 1 data type) as far as possible.

(1) Unsigned Integer

This is a 16-bit unsigned integer expressed by 1 register. The bit configuration inside the register is as shown below.



Bit 0 is the least significant bit (LSB), and bit F is the most significant bit (MSB). The processable numerical value range is as shown in the following Table.

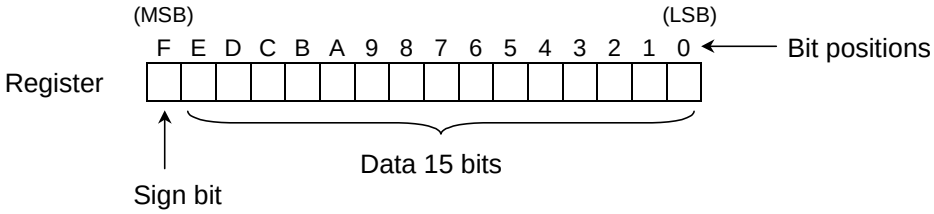
Numerical Value (Decimal)	Binary Expression	Hexadecimal Expression
65535	1111 1111 1111 1111	FFFF
65534	1111 1111 1111 1110	FFFE
∫	∫	∫
1	0000 0000 0000 0001	0001
0	0000 0000 0000 0000	0000

NOTE

When programming and when program monitoring, it is possible to change between decimal numbers and hexadecimal numbers for displaying/setting register data. When using a hexadecimal display, “H” is attached before the numerical value.
Example) H89AB (hexadecimal 89AB)

(2) Integer

This is a 16-bit integer expressed by 1 register. A negative number is expressed by 2’s complement.



The numerical value is expressed by the 15 bits from bit 0 to bit E. Bit F expresses the sign (0 when positive, 1 when negative)

Processable numerical range and expression format are shown in the following Table.

Numerical Value (Decimal)	Binary Expression	Hexadecimal Expression
32767	0111 1111 1111 1111	7FFF
32766	0111 1111 1111 1110	7FFE
∫	∫	∫
1	0000 0000 0000 0001	0001
0	0000 0000 0000 0000	0001
-1	1111 1111 1111 1111	FFFF
∫	∫	∫
-32767	1000 0000 0000 0001	8001
-32768	1000 0000 0000 0000	8000

The 2's complement is that the lower 16 bits become all 0 by adding the 2's complement data and the original data.

Example)

```
        0111 1111 1111 1111   (Binary)=32767
+       1000 0000 0000 0001   (Binary)=-32767
------------------------------
    1   0000 0000 0000 0000
```

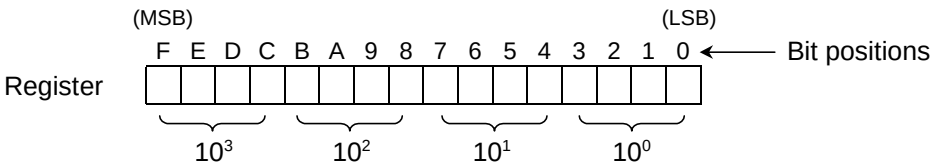
In calculation, the 2's complements of a numerical value can be found by the operation of inverting each bit of that numerical value and adding 1.

Example)

```
0111 1111 1111 1111        (Binary)=32767
   (bit inversion)
1000 0000 0000 0000        (Binary)=-32768
     (add 1)
1000 0000 0000 0001        (Binary)=-32767
```

(3) BCD

BCD is the abbreviation of Binary Coded Decimal. BCD expresses 1 digit (0-9) of a decimal number by 4 bits of a binary number. Therefore, 1 register can express the numerical value of a 4-digit decimal number.



Processable numerical range and expression format are shown in the following Table.

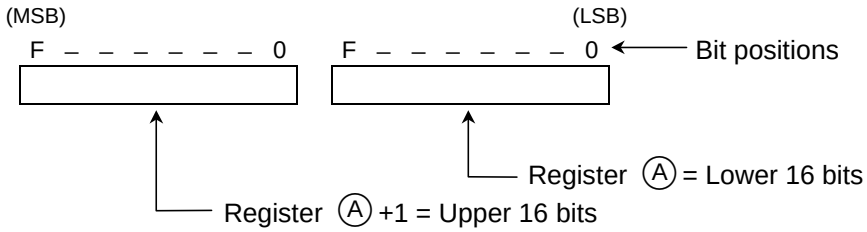
Numerical Value (Decimal)	Binary Expression	Hexadecimal Expression
9999	1001 1001 1001 1001	9999
9998	1001 1001 1001 1000	9998
∫	∫	∫
10	0000 0000 0001 0000	0010
9	0000 0000 0000 1001	0009
∫	∫	∫
1	0000 0000 0000 0001	0001
0	0000 0000 0000 0000	0000

NOTE

Basically, BCD is a data format used for data inputs from BCD-output type numerical setting devices and data outputs to BCD-input type numerical display devices. However, the S2T is provided with dedicated instructions which execute the calculations on BCD data as they stand.

(4) Unsigned Double-Length Integer

This is 32-bit unsigned integer which is expressed using 2 consecutive registers. In the case of double-length data, the registers are designated in the form Ⓐ+1 • Ⓐ. Ⓐ indicates the lower 16 bits and Ⓐ+1 shows the upper 16 bits. (Ⓐ+1 is the register following register Ⓐ)



Example) When processing an unsigned double-length integer in double length register D0201•D0200, D0200 becomes Ⓐ and D0201 becomes Ⓐ+1. D0200 becomes the lower side and D0201 becomes the upper side.
In programming, when D0200 is entered in the position which designates the double-length operand, D0201•D0200 is automatically displayed.

The numerical value range in which unsigned double-length integers can be processed is shown in the table on the following page.

Numerical Value	Hexadecimal Expression	
	Register Ⓐ+1	Register Ⓐ
4294967295	FFFF	FFFF
∫	∫	∫
65536	0001	0000
65535	0000	FFFF
∫	∫	∫
0	0000	0000

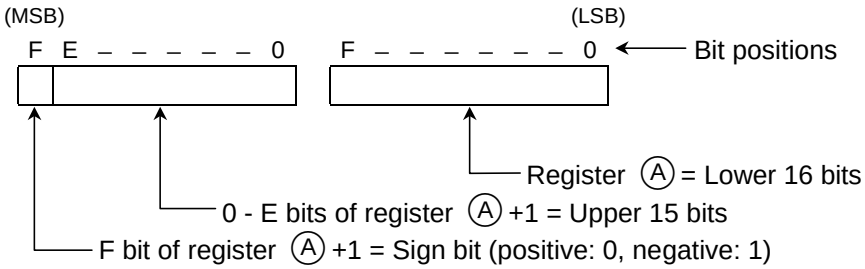
NOTE

Both odd-numbered addresses and even-numbered addresses may be used as register Ⓐ.

(5) Double-Length Integer

This is 32-bit integer which is expressed using 2 consecutive registers. Negative numbers are expressed by 2's complement. (See (2) 'Integers')

The registers are designated in the form Ⓐ+1 • Ⓐ. Ⓐ becomes the lower and Ⓐ+1 becomes the upper.



The numerical value is expressed by the 31 bits from bit 0 of register Ⓐ to bit E of register Ⓐ+1. The sign is expressed by bit F of register Ⓐ+1 (0 when positive, 1 when negative).

Example) When a double-length integer is processed by registers D1002•D1001, D1001 becomes Ⓐ and D1002 becomes Ⓐ+1, and D1001 is the lower and D1002 is the upper. Also, the sign is expressed by the bit F of D1002.

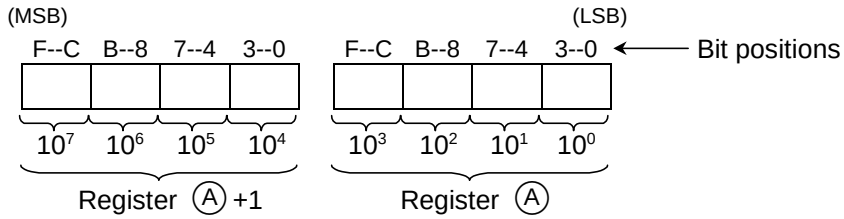
In programming, when D1001 is entered in the position which designates the double-length operand, D1002•D1001 is automatically displayed.

The numerical value range in which double-length integers can be processed is shown in the table on the following page.

Numerical Value	Hexadecimal Expression	
	Register Ⓐ+1	Register Ⓐ
2147483647	7FFF	FFFF
∫	∫	∫
65536	0001	0000
65535	0000	FFFF
∫	∫	∫
0	0000	0000
-1	FFFF	FFFF
∫	∫	∫
-65536	FFFF	0000
-65537	FFFE	FFFF
∫	∫	∫
-2147483648	8000	0000

(6) Double-Length BCD

This is 8-digit BCD data which is expressed by using 2 consecutive registers.



The registers are designated in the form Ⓐ+1• Ⓐ, and Ⓐ becomes the lower 4 digits while Ⓐ+1 becomes the upper 4 digits.

Example) When processing a double-length BCD by registers XW001•XW000, XW000 becomes Ⓐ while XW001 becomes Ⓐ +1 and XW000 becomes the lower 4 digits while XW001 becomes the upper 4 digits.

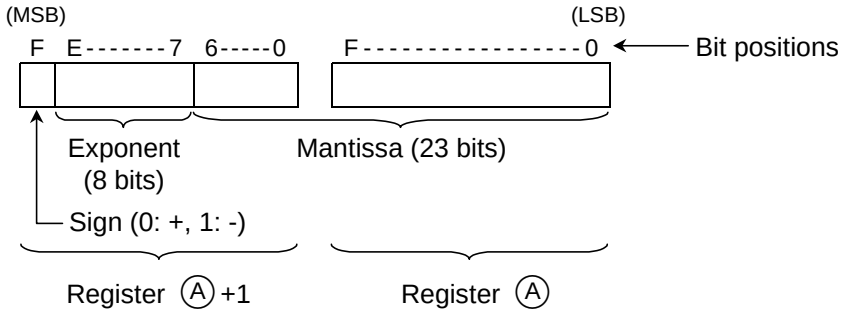
The following table shows the numerical range and the expression format in which double-length BCD data can be processed.

Numerical Value	Hexadecimal Expression	
	Register Ⓐ+1	Register Ⓐ
99999999	9999	9999
∫	∫	∫
1	0000	0001
0	0000	0000

(7) Floating Point Data

This is a real number which is expressed using 2 consecutive registers (32-bit).

The registers are designated in the form Ⓐ+1 • Ⓐ. Internally, the following format is used. (conforms to IEEE754)



Value = (Sign)1.(Mantissa) $\times 2^{(\text{Exponent-127})}$

The floating point data is used with the following floating point instructions. Therefore, there is no need for user to consider the format.

- Conversions (Floating point ↔ Double-length integer)
- Floating point arithmetics
- Floating point comparisons
- Floating point functions (Trigonometrics, square root, etc.)
- Floating point process operations (Integral, PID, etc.)

The following table shows the numerical range in which the floating point data can be processed.

Numerical value	Expression	Remarks
3.40282×10^{38}	3.40282E38	Maximum
∫	∫	
1.17549×10^{-38}	1.17549E-38	Nearest to 0
0	0	
-1.17549×10^{-38}	-1.17549E-38	Nearest to 0
∫	∫	
-3.40282×10^{38}	-3.40282E38	Minimum

3.4 Index modification

When registers are used by instructions, the method of directly designating the register address as shown in Example 1) below is called 'direct addressing'.

As opposed to this, the method of indirectly designating the register by combination with the contents of the index registers (I, J, K) as shown in Example 2) below is called the 'indirect addressing'. In particular, in this case, since the address is modified using an index register, this is called 'index modification'.

Example 1)

```
—[ RW100 MOV D3500 ]—
```

Data transfer instruction
Transfer content of RW100 to D3500

Example 2)

```
          I          J
—[ RW100 MOV D3500 ]—
```

Data transfer instruction (index modification attached)
Transfer content of RW(100+I) to D(3500+J)
(If I=3 and J=200, the content of RW103 is transferred to D3700)

There are 3 types of index register, I, J and K. Each type processes 16-bit integers (-32768 to 32767). There are no particular differences in function between these 3 types of index register.

There is no special instruction for substituting values in these index registers. There are designated as destination for normal instructions.

Example 1) Substituting a constant in an index register

```
—[ 64 MOV I ]—  (Substitute 64 in index register I)

—[ -2 MOV J ]—  (Substitute -2 in index register J)
```

Example 2) Substituting register data in an index register

```
—[ D0035 MOV K ]— (Substitute the value of D0035 in index
                   register K)

—[ RW078 MOV I ]— (Substitute the value of RW078 in index
                   register I)
```

Example 3) Substituting the result of an operation in an index register

—[RW200 - 30 → I]—

(Substitute the result of subtracting 30 from RW200 in I)

—[XW004 ENC (4) J]—

(Substitute the uppermost ON bit position of XW004 in J (encode))

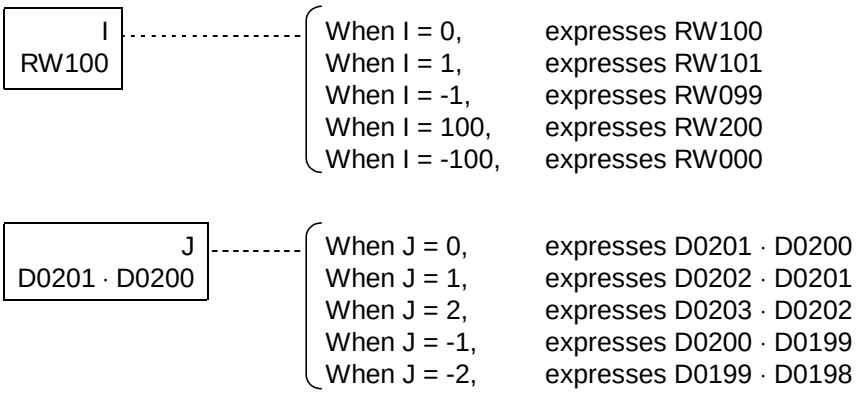
NOTE

Although, basically, index registers are processed as single-length (16 bits), when, for instance, using an index register as the storage destination for a instruction which becomes double-length as the result of a multiplication instruction or the like, only the combinations J • I or K • J are effective. In this case, it becomes J • I by designating I in the double-length operand position, and J becomes upper while I becomes lower. In the same, by designating J, it becomes K • J, and K becomes upper while J becomes lower.

Example)

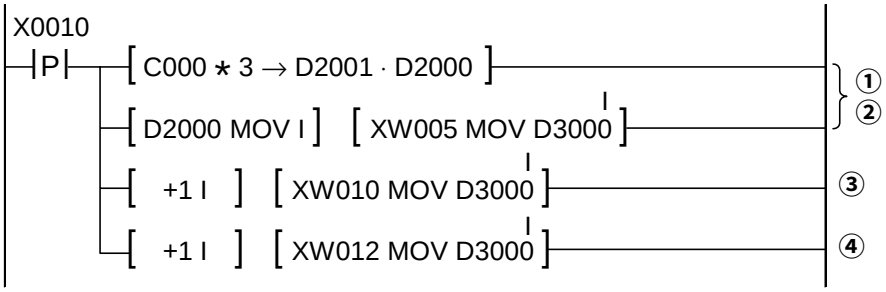
—[D1357 * 10 → J • I]—

The following are examples of registers in which index modification has been executed.



The following shows an example of the operation when index modification is applied to a program.

Example)



The following processing is carried out when X0010 changes from OFF to ON

① Substitute 3 times the value of the content of C000 in index register I
② Store content of XW005 in D(3000+1)
③ Add 1 to the content of I and store content of XW010 in D(3000+I)
④ Add a further 1 to the content of I and store content of XW012 in D(3000+I)

Incidentally,

Ⓐ
—| P |— is positive transition-sensing contact which becomes ON once only when device Ⓐ changes from OFF to ON (until the instruction is executed in the next scan)

—[Ⓐ * Ⓑ → Ⓒ +1 • Ⓒ]— is multiplication instruction which multiplies Ⓐ by Ⓑ and stores it in double-length register Ⓒ +1 • Ⓒ

—[+1 Ⓐ]— is increment instruction which adds 1 to the content of Ⓐ and stores it in Ⓐ

—[Ⓐ MOV Ⓑ]- is a data transfer instruction which substitutes the content of Ⓐ in Ⓑ

NOTE

(1) Substitutions of values to index registers and index modification may be carried out any number of times during a program. Therefore, normally, the program will be easier to see if a value substitution to an index register is executed immediately before index modification.
(2) Be careful that the registers do not exceed the address range through index modification. When the results of index modification exceed the address range, the instruction is not executed, and special devices (S0051 and S0064) which indicate 'boundary error' become ON.

As explained before, the main purpose of the index modification is indirect designation of register. However, as the special usage of the index modification, the followings are also possible.

- For CALL and JUMP instructions, indirect designation of the destination address is possible.

  I
  ─[JUMP N.000]─ (If I=5, jump to Label 5)

  If indexed destination is not registered, the special devices (S0051 and S006C) become ON. If indexed destination exceeds the range, the special devices (S0051 and S0065) become ON. And both cases, the instruction is not executed.

- For SET and RST instructions, indirect designation of device is possible.

  I
  ─[SET R0100]─ (If I=H005F, set R015F to ON)

- For constant operand, the constant value can be modified by the index register.

  I
  ─[500 MOV D5000]─ (If 1=10, 510 is stored in D5000)

NOTE

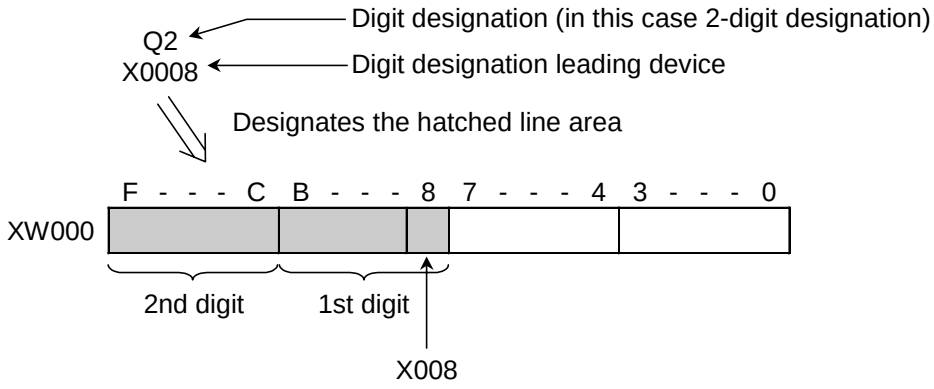
Refer to the Instruction Set manual for the operands to which the index modification is available in each instruction.

3.5 Digit designation

There is a method called ‘digit designation’ which is a special designation method for register data. ‘Digit designation’ treats 1 digit (4 bits) of a hexadecimal number as a data unit. It is a method of designation in which a number of digits from the designated devices (bit positions) are made the subject of data operation.

In practice, in the case of the following Example, 2 digits from X0008 (that is to say, the upper 8 bits of XW000) become the subject of data operation.

Example)

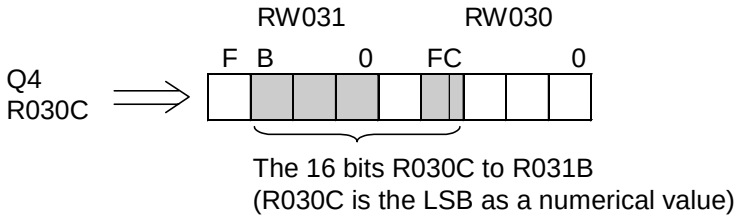


There are 9 types of digit designation – Q0, Q1, ..., Q8 which have the following significations

Q0.... makes the designated device 1 bit the subject of data operation
Q1.... makes 1 digit (4 bits) started with the designated device the subject of data operation
Q2.... makes 2 digits (8 bits) started with the designated device the subject of data operation
Q3.... makes 3 digits (12 bits) started with the designated device the subject of data operation
Q4.... makes 4 digits (16 bits) started with the designated device the subject of data operation
Q5.... makes 5 digits (20 bits) started with the designated device the subject of data operation
Q6.... makes 6 digits (24 bits) started with the designated device the subject of data operation
Q7.... makes 7 digits (28 bits) started with the designated device the subject of data operation
Q8.... makes 8 digits (32 bits) started with the designated device the subject of data operation

In digit designation, when the area designated covers multiple registers, as shown below, the area is designated from the smaller address to the greater address.

Example)



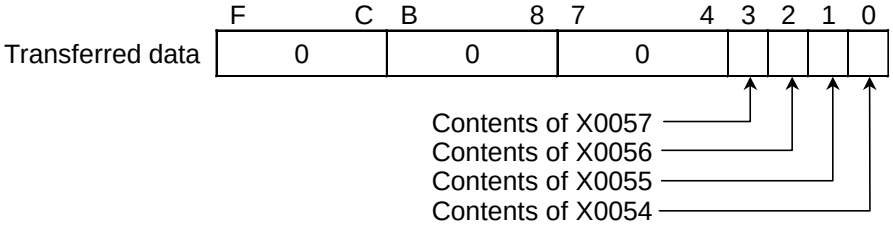
Below, the operation of digit designation is described for the case when digit designation is executed as a source operand (a register for executing an instruction using its data) and the case when digit designation is executed as a destination operand (a register which stores the result of instruction execution).

It is possible to carry out digit designation for both a source operand and a destination operand with 1 instruction.

(1) Digit designation for a source operand
For a single-length (16 bits) operand, Q0 to Q4 are available. The upper digits which are out of the designated digits are regarded as 0.

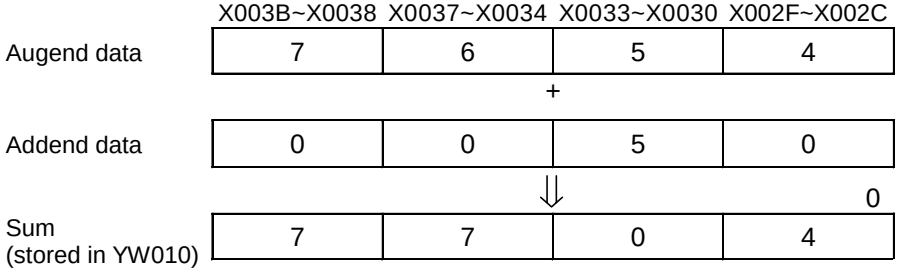
Example 1)

Q1
—[X0054 MOV D1000]— (Data transfer)



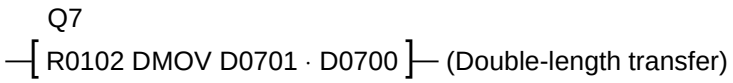
Example 2)

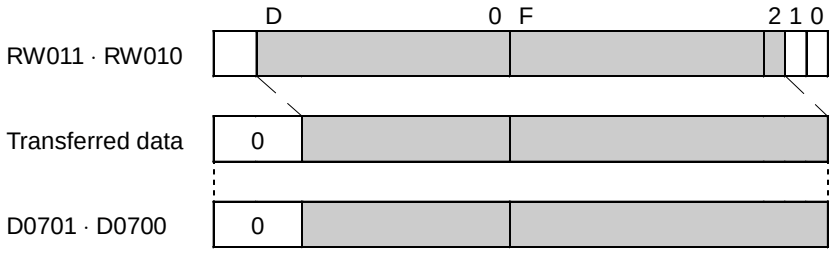
Q4
—[X002C B + H0050 → YW010]— (BCD addition)
(Example of XW003=H8765, XW002=H4321)



For a double-length (32 bits) operand, all Q0 to Q8 are available.

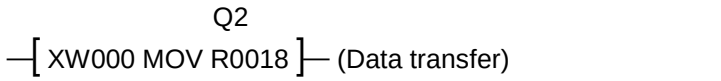
Example 3)

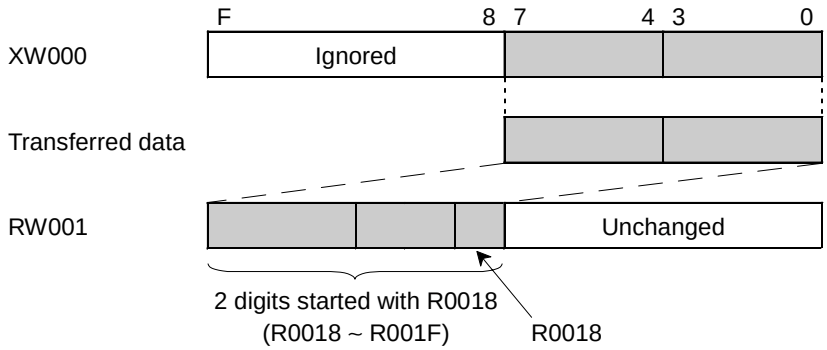




(2) Digit designation for a destination operand
For single-length (16 bits) operand, Q0 to Q4 are available. The result data of the operation is stored in the specified digits of the destination register. The digits which are out of the designated digits are unchanged.

Example 1)

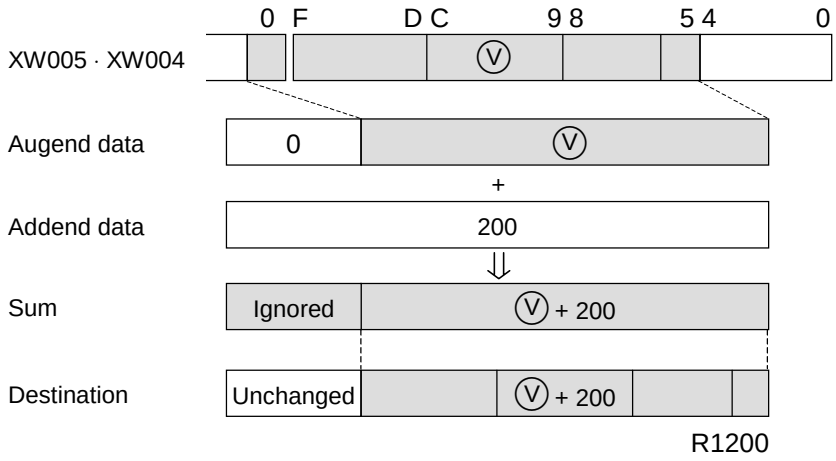




Example 2)

Q3 Q3

—[X0045 + 200 → R1200]— (Addition)



If, XW005=H0077=0000 0000 0111 0111 (binary)
XW004=H182A=0001 1000 0010 1010 (binary)

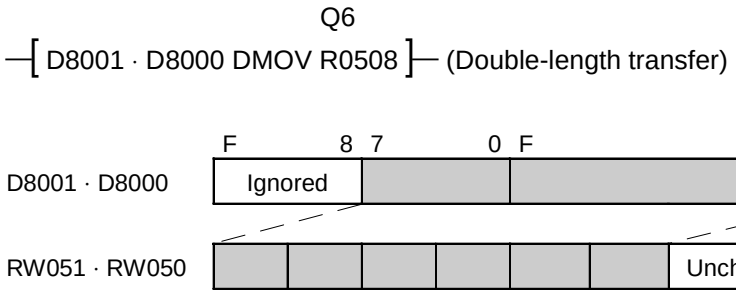
augend data is;
0000 1000 1100 0001 (binary)=H08C1=2241 (decimal)

sum by adding 200;
0000 1001 1000 1001 (binary)=H0989=2441 (decimal)

Therefore, the data below is stored in the 3 digits (12 bits) started with R1200.
1001 1000 1001 (binary)=H989=2441 (decimal)

For a double-length (32 bits) operand, all Q0 to Q8 are available.

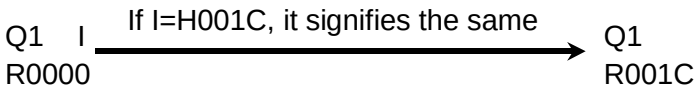
Example 3)



NOTE

(1) Be careful that the result of digit designation does not exceed the address range. When the result of digit designation exceeds the address range, the excess portion will be ignored.
(2) A combination of digit designation and index modification can also be used.

Example)



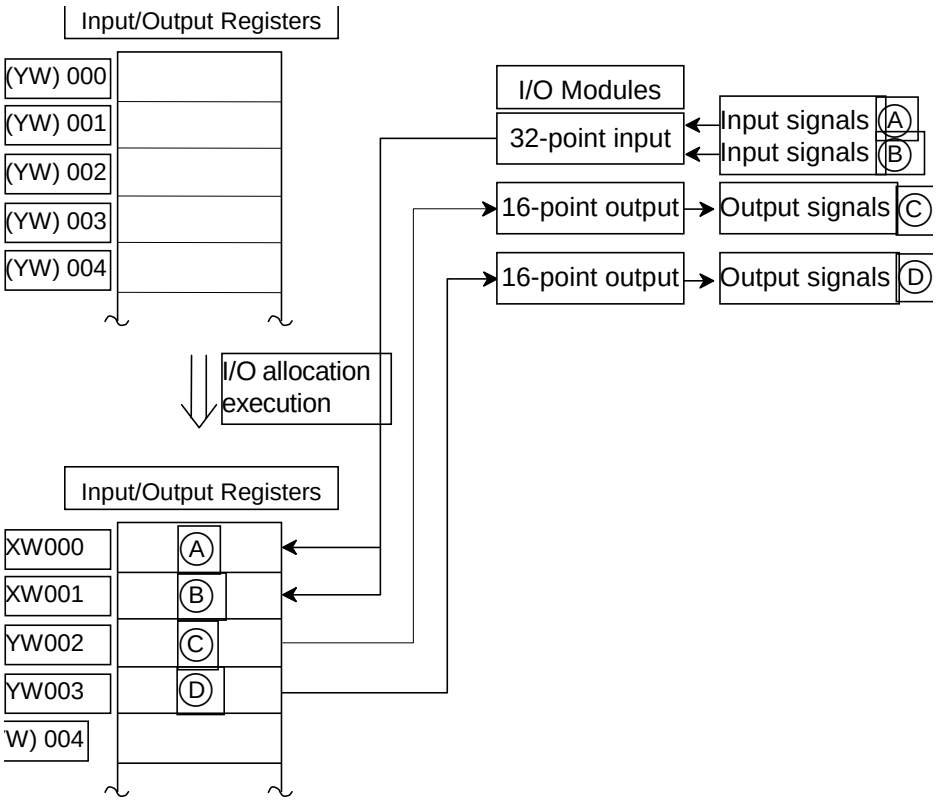
4.1 Overview

The state of external input signals inputted to input modules is read via the input registers/devices (XW/X or lW/I) when scan control is executed. On the other hand, the output data determined in user program execution are outputted to output modules via output registers/devices (YW/Y or OW/O) and outputs from the output modules to external loads are based on these data.

I/O allocation is the execution of mapping between input registers/devices and input modules and of mapping between output registers/devices and output modules. In other words, physical devices called I/O modules are allocated to logic devices called registers/devices.

Input registers/devices and output registers/devices do not use their own independent memory areas. They use a series of memory areas which can be said to be input/output registers/devices (a register address range of 256 words from 000 to 255).

By executing I/O allocation, function type determination is carried out by making addresses allocated to input modules input registers/devices and addresses allocated to output modules output registers/devices.



Note) Addresses not allocated to I/O modules are output (YW) internally.

4.2 Methods of VO allocation

The execution of I/O allocation can be said in other words to be the carrying out of the registration of I/O allocation information in system information. The S2T CPU checks whether the I/O modules are correctly mounted based on this I/O allocation information when RUN starts-up. Also, at the same time, the correspondence between the input/output registers (XW/YW) and the I/O modules is determined based on this I/O allocation information. On the other hand, the programmer reads this I/O allocation information when communicating with the S2T and recognizes the assignment whether input. (XW) or output (YW) for every input/output register address.

There are 2 methods for the registration of I/O allocation information in system information. These are automatic I/O allocation and manual I/O allocation.

The registration of I/O allocation information is only available when the S2T is in the HALT mode .

Automatic I/O allocation

This is a method of causing the S2T to execute the registration of I/O allocation information. It is carried out by selecting and executing the AutoSet command on the I/O allocation screen of the programmer (T-PDS).

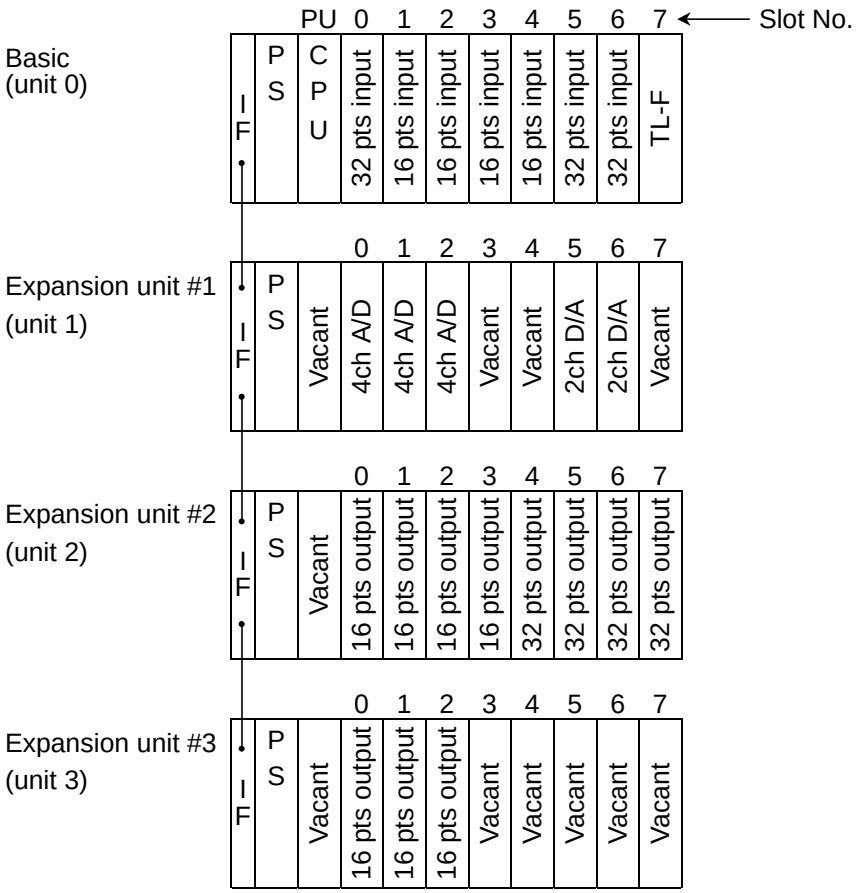
When the automatic I/O allocation is executed, the S2T CPU reads out state of the I/O modules which are mounted (what type of module is mounted in which position) and registers the I/O allocation information.

Each I/O module has one of the module types shown below.

Module	Description	Module Type
DI632D/652	8 points DC input	X 1W
DI633	16 points DC input	X 1W
DI634	32 points DC input	X 2W
DI635/635H	64 points DC input	X 4W
IN653/663	16 points AC input	X 1W
DO633/633P/653	16 points DC output	Y 1W
DO634	32 points DC output	Y 2W
DO635	64 points DC output	Y 4W
AC663	16 points AC output	Y 1W
RO663	16 points Relay output	Y 2W
RO662S	8 points Relay output (isolated)	Y 1W
AD624L/634L AD624/634 RT614	4 channels analog input	X 4W
AD668/TC618	8 channels analog input	X 8W
DA632L DA662/672	4 channels analog output	Y 4W
DA664	4 channels analog output	Y 4W
PI632	2 channels pulse input	iX+Y 2W
CF611	ASCII module	iX+Y 4W
SN621/622/625/626/627	TOSLINE-S20 data transmission	TL-S
UM611/612	TOSLINE-F10 data transmission	TL-F

For instance, when automatic I/O allocation is executed with the I/O module mounting state shown below, the CPU reads the I/O module types which are mounted and creates I/O allocation information and it registers it in system information.

- Module mounting state



- I/O allocation information

Unit 0		Unit 1		Unit 2		Unit 3	
Slot	Module type	Slot	Module type	Slot	Module type	Slot	Module type
PU		0	X 4W	0	Y 1W	0	Y 1W
0	X 2W	1	X 4W	1	Y 1W	1	Y 1W
1	X 1W	2	X 4W	2	Y 1W	2	Y 1W
2	X 1W	3		3	Y 1W	3	
3	X 1W	4		4	Y 2W	4	
4	X 1W	5	Y 2W	5	Y 2W	5	
5	X 2W	6	Y 2W	6	Y 2W	6	
6	X 2W	7		7	Y 2W	7	
7	TL-F						

Manual I/O allocation

This is the method by which the user edits the I/O allocation information on the I/O allocation information screen of the programmer (T-PDS) and writes it to the S2T. The manual I/O allocation is used in the following cases.

- When carrying out programming in a state in which the I/O modules are not fully mounted
- When it is desired to remove some modules from the subjects of batch input/output processing
- When using the unit base address setting function
- When allocating a specified number of registers to slot left vacant for future addition
- When carrying out offline programming

For manual I/O allocation, module types are set for each slot. The module types which can be set at this time are as shown below. Module types are expressed by combinations of function classifications and numbers of registers occupied. (except for TL-S and TL-F)

Function classification	Number of registers occupied	Remarks
X	01, 02, 04, 08	Input (batch input/output)
Y	01, 02, 04, 08	Output (batch input/output)
X+Y	02, 04, O8	lnput+output (batch input/output)
iX	01, 02, 04, 08	Input (out of batch input/output)
iY	01, 02, 04, 08	Output (out of batch input/output)
iX+Y	02, 04, 08	Input+output (out of batch input/output)
Z	08, 16, 32	
SP	01, 02, 04, 08	Space
TL-S	—	For TOSLINE-S20
TL-F	—	For TOSLINE-F10

(1) Allocations to input/output modules are: -X and iX to input modules, Y and iY to output modules and X+Y and iX+Y to input/output mixed modules. The input/output registers which correspond to modules with the designation i attached are not included in batch input/output subjects.
(2) SP is used when allocating an arbitrary number of registers to a vacant slot.
(3) TL-S is allocated to data transmission module TOSLINE-S20.
(4) TL-F is allocated to data transmission module TOSLINE-F10.
(5) Z is not used in the S2T.

NOTE

The I/O allocation information can be freely edited and registered by carrying out manual I/O allocation. However, it is necessary that the registered input/output allocation information and the I/O module mounting state should agree for starting-up RUN.
When executing the 'forced RUN' command, operation (RUN-F mode) is possible even if the modules registered in the allocation information are not mounted. However, in this case also, operation cannot be executed when a module of a different type to the registered module is mounted (I/O mismatch).

Unit base address setting function

In manual I/O allocation, the starting register address (input/output registers) of each unit can be set.

The register addresses can be arranged for each unit by using this function. Also, when an I/O module is added in a vacant slot in the future, it is possible to avoid affecting the register addresses of other units.

(Unit base address setting screen on T-PDS)

Unit #0	Unit #1	Unit #2	Unit #3
Top Register No.	Top Register No.	Top Register No.	Top Register No.
[0]	[15]	[35]	[50]

In the case of this screen example, address allocations can be carried out

from XW/YW000 for the basic unit
from XW/YW015 for expansion unit #1
from XW/YW035 for expansion unit #2
from XW/YW050 for expansion unit #3

NOTE

Settings by which latter stage units become lower register addresses cannot be made.

4.3 Register and module correspondence

When I/O allocation information is registered by carrying out automatic I/O allocation or manual I/O allocation, correspondence between registers and modules is automatically determined by the following rules.

(1) In any unit, allocation is the lower address registers are allocated in sequence from the module at the left end.

(2) In a case when the unit base addr.ess is not set.(it is not set by automatic I/O allocation), the registers are allocated in continuation from the previous stage unit.

(3) A slot for which a module type is not set (any vacant slot in automatic I/O allocation is the same) does not occupy any registers.

(4) The cases of the half size racks also are handled in the same way as standard size rack for I/O allocation, and they are regarded as having slots without settings in the latter portions of the unit. Therefore these portions do not occupy registers.

(5) Slots for which SP (space) is set, output registers are allocated internally by a number of set words.

(6) Modules for which Z, TL-S and TL-F are set do not occupy input/output registers (XW/YW).

(7) Input/output registers which are not allocated to I/O modules become output registers (YW) in the programming. Thus, they can be used in the same way as auxiliary registers/relays (RW/R).

The following examples show the register allocation when the I/O allocation information is registered.

Example 1)

- I/O allocation information

Unit 0		Unit 1		Unit 2		Unit 3	
Base address [ ]		Base address [ ]		Base address [ ]		Base address [ ]	
Slot	Module type	Slot	Module type	Slot	Module type	Slot	Module type
PU		0	X 4W	0	Y 1W	0	Y 1W
0	X 2W	1	X 4W	1	Y 1W	1	Y 1W
1	X 1W	2	X 4W	2	Y 1W	2	Y 1W
2	X 1W	3		3	Y 1W	3	
3	X 1W	4		4	Y 2W	4	
4	X 1W	5	Y 2W	5	Y 2W	5	
5	X 2W	6	Y 2W	6	Y 2W	6	
6	X 2W	7		7	Y 2W	7	
7	TL-F						

- Register allocation

Unit 0		Unit 1		Unit 2		Unit 3	
Slot	Register	Slot	Register	Slot	Register	Slot	Register
PU		0	XW010 ~ XW013	0	YW026	0	YW038
0	XW000, XW001	1	XW014 ~ XW017	1	YW027	1	YW039
1	XW002	2	XW018 ~ XW021	2	YW028	2	YW040
2	XW003	3		3	YW029	3	
3	XW004	4		4	YW030, YW031	4	
4	XW005	5	YW022, YW023	5	YW032, YW033	5	
5	XW006, XW007	6	YW024, YW025	6	YW034, YW035	6	
6	XW008, XW009	7		7	YW036, YW037	7	
7							

4.4 Network assignment

For the data transmission module (TOSLINE-S20, TOSLINE-F10), the network assignment is necessary in addition to the I/O allocation mentioned before.
The network assignment is the declaration of assignment between the link registers and the scan data memory in the data transmission module.

TOSLINE-S20

The TOSLINE-S20 has 1024 words of scan data memory in the module. By using the network assignment, S2T's link registers (W) are assigned to the scan data memory in units of blocks.
(64 words/block)

Here, the block is not related to the data send block in the TOSLINE-S20. The data transfer direction between the link registers and the scan data memory is determined by S2T CPU for each address, according to the data send block setting in the TOSLINE-S20.

The following 3 types of assignment setting are available.

Setting	Function
Blank	The block of link registers (W) are not assigned to TOSLINE-S20.
LINK	The block of link registers (W) are assigned to TOSLINE-S20. (S2T accesses TOSLINE-S20 for the block)
GLOBAL	Used when 2 TOSLINE-S20s are mounted on the S2T, and when the S2T functions as bridge station for the 2 TOSLINE-S20 networks.

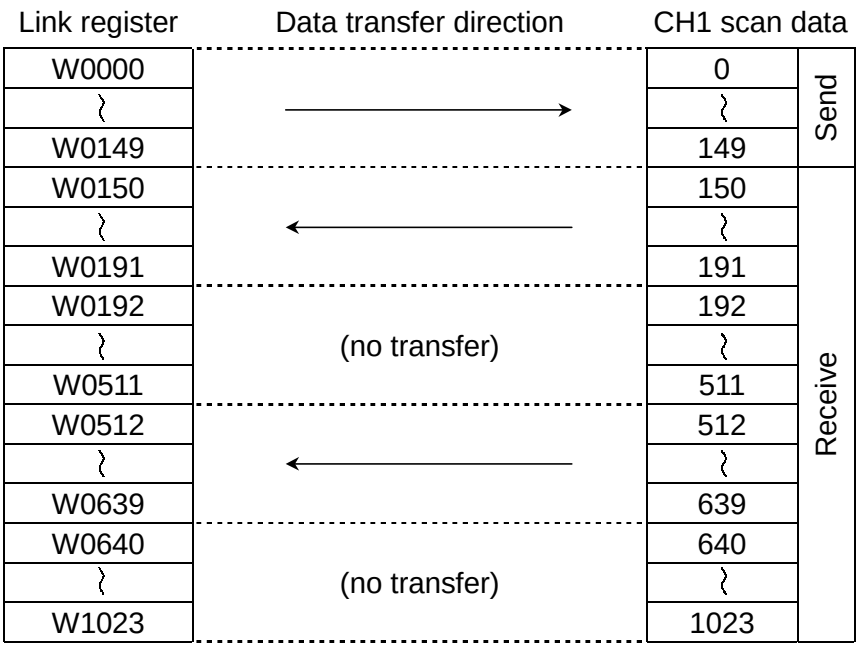
Note) Up to 2 TOSLINE-S2Os can be mounted on a S2T.
In this case, the TOSLINE-S20 nearer to the S2T CPU is regarded as CH1, and the other is CH2.

(1) Example when 1 TOSLINE-30 is mounted (CH1 only)

- Network assignment example

Block	Corresponding link registers	CH1	CH2
1	W0000 ~ W0063	LINK	
2	W0064 ~ W0127	LINK	
S	W0128 ~ W0191	LINK	
4	W0192 ~ W0255		
5	W0256~-W0319		
6	W0320 ~ W0383		
7	W0384 ~ W0447		
8	W0448 ~ W0511		
9	W0512 ~ W0575	LINK	
10	W0576 ~ W0639	LINK	
11	W0640 ~ W0703		
12	W0704 ~ W0767		
13	W0768 ~ W0831		
14	W0832 ~ W0895		
15	W0896 ~ W0959		
16	W0960 ~ W1023		

- Data transfer direction



(2) Example when 2 TOSLINE-S20 are mounted (CH1, CH2)
Regarding the network assignment, the W register is divided into 32 blocks. (64 words per one block)

The S20 has 1024 words of scan memory. In case of the S2T, even if two 320's are used, the scan memory of each S20 can be fully mapped to the W register. Channel 1 320 is allocated to the blocks 1 to 16, and channel 2 S20 is allocated to the blocks 17 to 32. The allocation example below shows the case of all the blocks are set as "LINK".

S2T's link register W	Block	Setting		CH1 S20 scan memory	CH2 S20 scan memory
		CH1	CH2		
W0000 - W0063	1	LINK		0000 - 0063	
W0064 - W0127	2	LINK		0064 - 0127	
W0128 - W0191	3	LINK		0128 - 0191	
W0192 - W0255	4	LINK		0192 - 0255	
W0256 - W0319	S	LINK		0256 - 0319	
W0320 - W0383	6	LINK		0320 - 0383	
W0384 - W0447	7	LINK		0384 - 0447	
W0448 - W0511	8	LINK		0448 - 0511	
W0512 - W0575	9	LINK		0512 - 0575	
W0576 - W0639	10	LINK		0576 - 0639	
W0640 - W0703	11	LINK		0640 - 0703	
W0704 - W0767	12	LINK		0704 - 0767	
W0768 - W0831	13	LINK		0768 - 0831	
W0832 - W0895	14	LINK		0832 - 0895	
W0896 - W0959	15	LINK		0896 - 0959	
W0960 - W1023	16	LINK		0960 - 1023	
W1024 - W1087	17		LINK		0000 - 0063
W1088 - W1151	18		LINK		0064 - 0127
W1152 - W1215	19		LINK		0128 - 0191
W1216 - W1279	20		LINK		0192 - 0255
W1280 - W1343	21		LINK		0256 - 0319
W1344 - W1407	22		LINK		0320 - 0383
W1408 - W1471	23		LINK		0384 - 0447
W1472 - W1535	24		LINK		0448 - 0511
W1536 - W1599	25		LINK		0512 - 0575
W1600 - W1663	26		LINK		0576 - 0639
W1664 - W1727	27		LINK		0640 - 0703
W1728 - W1791	28		LINK		0704 - 0767
W1792 - W1855	29		LINK		0768 - 0831
W1856 - W1919	30		LINK		0832 - 0895
W1920 - W1983	31		LINK		0896 - 0959
W1984 - W2047	32		LINK		0960 - 1023

When “GLOBAL” setting is used, the link registers of “GLOBAL” setting block are assigned to both CH1 and CH2 S20’s.

S2T's link register W	Block	Setting		CH1 S20 scan memory	CH2 S20 scan memory
		CH1	CH2		
⋮	⋮	⋮	⋮	⋮	⋮
W0192 - W0255	4	LINK		0192 - 0255	—
W0256 - W0319	5	GLOBAL		0256 - 0319	0256 - 0319
W0320 - W0383	6	GLOBAL		0320 - 0383	0320 - 0383
W0384 - W0447	7	GLOBAL		0384 - 0447	0384 - 0447
W0448 - W0511	8	GLOBAL		0448 - 0511	0448 - 0511
W0512 - W0575	9	LINK		0512 - 0575	—
⋮	⋮	⋮	⋮	⋮	⋮
W1216 - W1279	20		LINK		0192 - 0255
W1280 - W1343	21				
W1344 - W1407	22			—	—
W1408 - W1471	23				
W1472 - W1535	24				
W1536 - W1599	25		LINK		0512 - 0575
⋮	⋮	⋮	⋮	⋮	⋮

- The blocks 1 - 16 are dedicated to the CHI S20, and the blocks 17 - 32 are dedicated to the CH2 S20. It is not allowed to assign the blocks 1 - 16 to CH2, and blocks 17 - 32 to CH1.
- For the blocks set as “LINK” or “GLOBAL”, the S2T performs data read from S20 (for data receive area) and data write to S20 (for data send area). The data transfer direction (read or write) is automatically decided by the S2T according to the S20’s receive/send setting.
- For the blocks set as “GLOBAL”, the data transfer is as follows.
  1) If CH1 is receive and CH2 is send CH1 receive data is read and written into both W register and CH2.
  2) If CHI is send and CH2 is receive CH2 receive data is read and written into both W register and CH1.
  3) If both CH1 and CH2 are send; W register data is written into both CH1 and CH2.
  4) If both CH1 and CH2 are receive; The receive data of “GLOBAL” setting channel is read and stored in W register.

NOTE

In case of TOSLINE-S20LP, it has 4096 words of scan memory. The leading 2048 words can be assigned straight to W register. The following 2048 words can be accessed by using XFER instruction.

TOSLINE-F10

The TOSLINE-F10 has 32 words of scan data memory in the module. Up to 8 TOSLINE-F10 can be mounted on a S2T. In this case, the TOSLINE-F10 nearer to the S2T CPU is assigned in sequence from CH1 to CH8.

For theTOSLINE-F10, set LINK for all existing CHs by the network assignment. By this setting, the link registers (LW) are assigned to the TOSLINE-F10 in units of 32 words from the lowest address.

- Network assignment when 4 TOSLINE-F10s.are mounted

CH	Setting	Assigned link register (LW)
1	LINK	LW000 ~ LW031
2	LINK	LW032 ~ LW063
S	LINK	LW064 ~ LW095
4	LINK	LW096 ~ LW127
5		—
6		
7		
8		

The data transfer direction between the link registers (LW) and the scan data in the TOSLINE-F10 is determined by S2T CPU, according the TOSLINE-F10 network configuration.

NOTE

For details of the data transmission modules (TOSLINE-S20, TOSLINE-F10), see separate manuals for them.

5.1 Overview

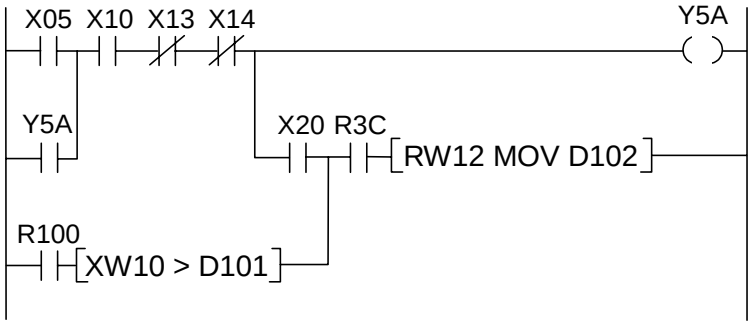
The S2T supports 2 types of programming language for the user programs-ladder diagram and SFC. Multiple programming languages can be used in mixed by a single user program by separating blocks of the program. Thus, the optimum program configuration for the control functions can be achieved.

(1) Ladder Diagram
This is the language which is core programming language for the S2T. The program is configured by a combination of relay symbols and function blocks. This language is suitable for logic control.

Relay Symbols ..... These are NO contact, NC contact, coil, etc.

Function Blocks ..... These are box type instructions which express single functions. They can be freely positioned in a ladder diagram network by treating them in a similar way to relay contacts. The output of one function block can be connected to the input of another function block.

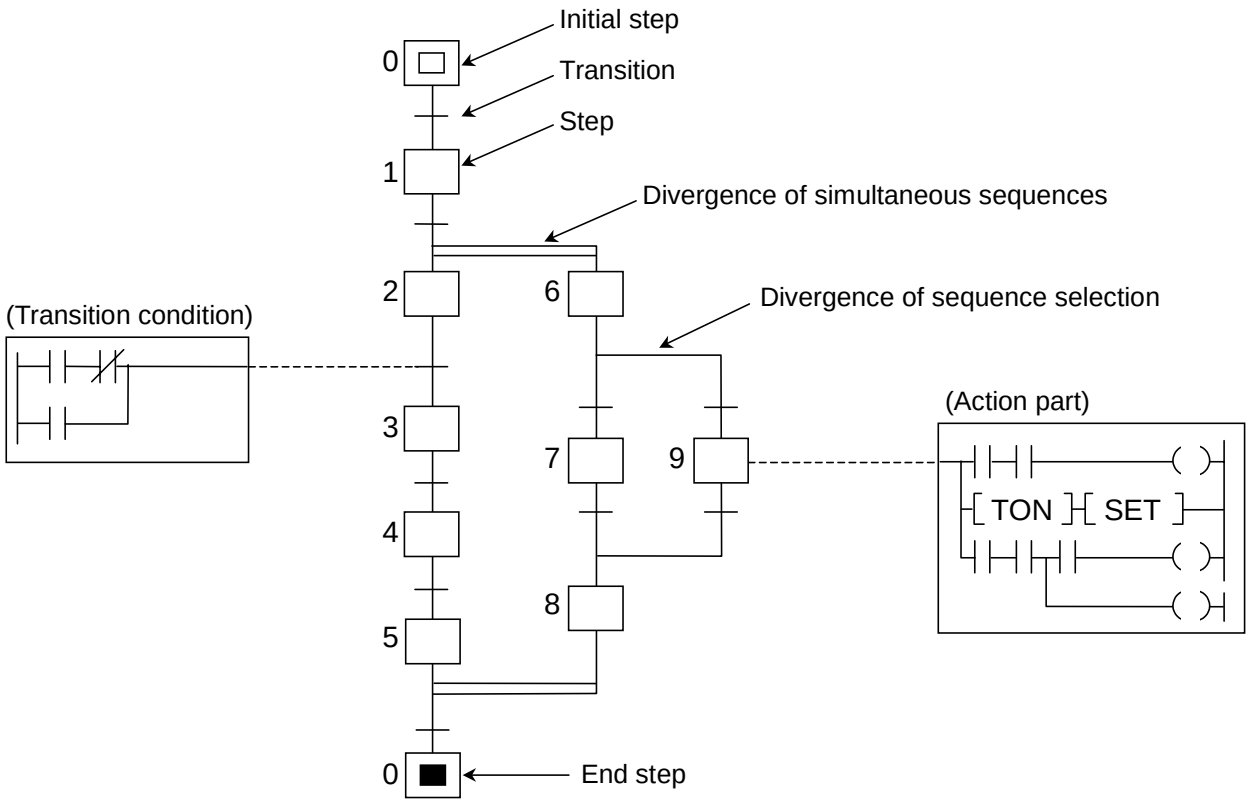
Example)



(2) SFC (Sequential Function Chart)

This is a programming language suitable for process stepping control (sequential control). Also, it is a language which makes the flow of control easy to see. Therefore, it is effective for program maintenance and standardization. SFC program is composed of structure part which shows the flow of control, action parts which show the operation of each step and transition condition parts which enable the process to advance. Action parts and transition condition parts are produced by ladder diagram. SFC can be considered as an execution control element for making a program easier to see by arranging the control processes and conditions rather than a single programming language.

(SFC Structure)



The flow of control advances downward from the initial step and, when it reaches the end step, it returns to the initial step. A step corresponds to an operational process, and there is an action part corresponding to each step. The condition of shifting from one step to the next is called ‘transition’, and there is a transition condition corresponding to each transition. When the immediately preceding step of a transition is in the active state and the transition condition is ON, the state of the immediately preceding step is changed to inactive and the next step becomes active.

The following Table shows the programming languages which are usable for each program type/part.

Program type/part	Ladder diagram	SFC
Main program	○	○
Sub-program	○	○
Interupt program	○	×
Sub-routine	○	×*
SFC action program part	○	×*
SFC transition condition part	○	×

○: Usable
×: Not usable

*) SFC can be made an hierarchical structure (other SFC can be made to correspond to 1 step of SFC). In this case a macro-step (equivalent to an SFC sub-routine) is used.

5.2 Ladder diagram

Mixed use can be made of the two types of programming language, ladder diagram and SFC in the S2T. However, of these, ladder diagram is the basic language which must be present in the user program.

Here, the structure, execution sequence and general items of ladder diagram instructions are explained for ladder diagram programs.

As explained before, a user program is registered by every functional type which is called a program type. Furthermore, in each program type the user program is registered by one or a multiple of units called 'blocks'.

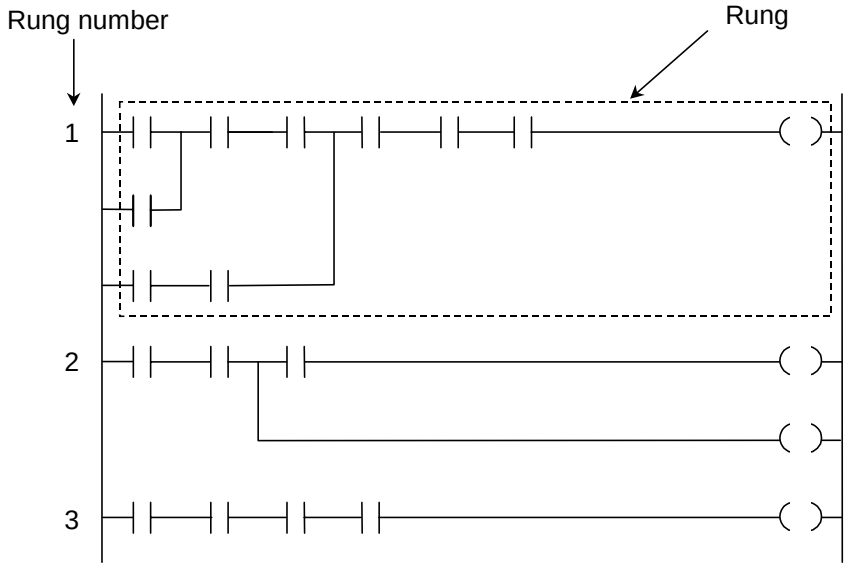
Program Types..... Main program, sub-program #1 - #4, timer interrupt program, I/O interrupt programs #1 - #8, sub-routine

Blocks ..... Blocks 1-256 (1 language/1 block).

When commencing programming in a block to be newly registered, that program is designated by the language which is used (this is called 'language designation').

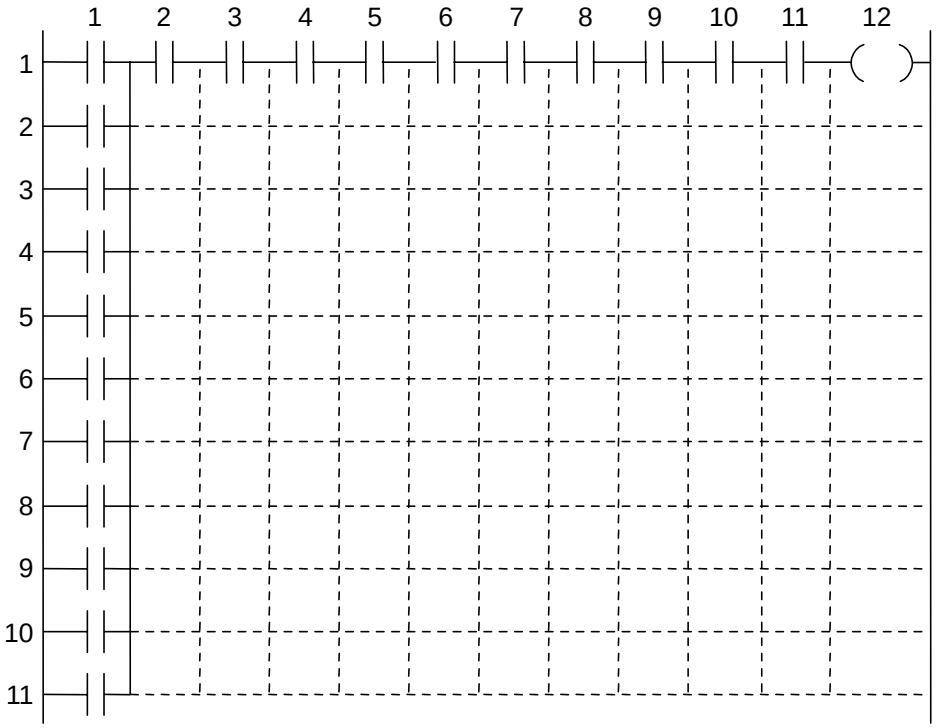
However, in the case of ladder diagram, the operation of language designation is not required (the default is ladder diagram).

The ladder diagram program in any one block is registered/arranged by units called 'rung'. A rung is defined as 1 network which is connected to each other, as shown below.



The rung numbers are a series of numbers (decimal numbers) starting from 1, and rung numbers cannot be skipped. There is no limit to the number of rungs.

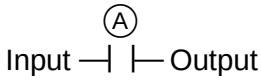
The size of any one rung is limited to 11 lines × 12 columns, as shown below.



Ladder diagram is a language which composes programs using relay symbols as a base in an image similar to a hard-wired relay sequence. In the S2T, in order to achieve an efficient data-processing program, ladder diagram which are combinations of relay symbols and function blocks are used.

Relay Symbols ..... These are NO contact, NC contact, coil and contacts and coils to which special functions are given. Each of these is called an 'instruction'. (Basic ladder instructions)

Example) NO contact



When device Ⓐ is ON, the input side and the output side become conductive.

Viewed from the aspect of program execution, the operation is such that when the input is ON and the content of device Ⓐ is also ON, the output will become ON.

Function Blocks.....These are expressed as boxes which each show 1 function. As types of function, there are data transfers, the four arithmetic operations, logic operations, comparisons, and various mathematical functions. Each of these is called an 'instruction'. (Function instructions)

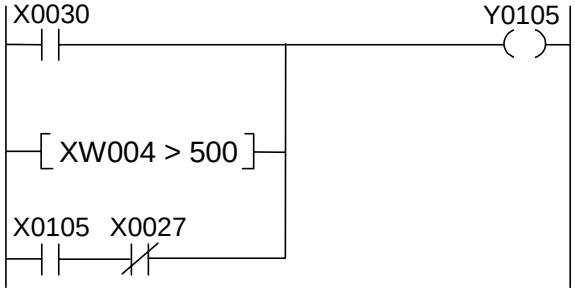
In a function block there are 1 or more inputs and 1 output. When a certain condition is satisfied by the input state, a specified function is executed and the ON/OFF of the output is determined by the result of execution.

Example 1) Addition

Input —| Ⓐ + Ⓑ → Ⓒ |— Output

When the input is ON the content of register Ⓐ and the content of register Ⓑ are added and the result is stored in register Ⓒ. The output becomes ON if an overflow or an underflow is generated as the result of the addition.

Example 2) Combination of Relay Symbols and Function Blocks



When X0030 is ON or the content of XW004 exceeds 500, Y0105 becomes ON. Y0105 stays on even if X0030 is OFF and the content of XW004 is 500 or less, then Y0105 will become OFF when X0027 becomes ON.

NOTE

(1) A function block can be regarded as a contact which has a special function. By carefully arranging the function blocks in the order of execution of instructions, complex control functions can be achieved by an easily understandable program.
(2) A list of ladder diagram instructions is shown in Section 5.5. For the detailed specifications of each instruction, see the separate volume, 'Instruction set Manual'.

Instruction execution sequence

The instructions execution sequence in a block composed by ladder diagram are shown below.

(1) They are executed in the sequence rung1, rung2, rung3... through to the final rung in the block (in the case of a block with an END instruction, through to the rung with the END instruction).

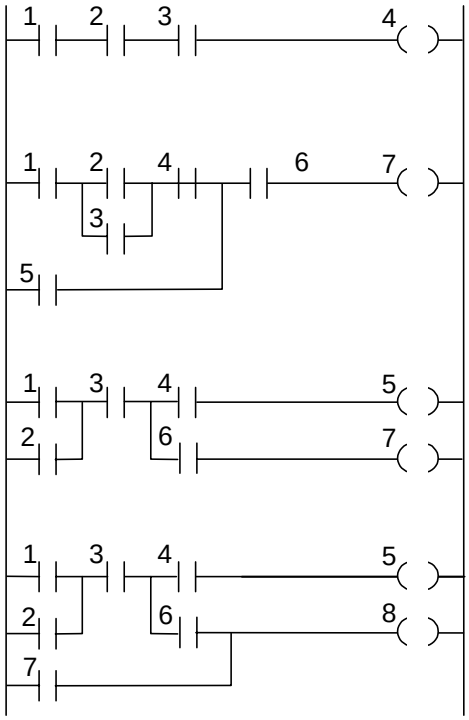
(2) They are executed according to the following rules in any one rung.

① When there is no vertical connection, they are executed from left to right.

② When there is an OR connection, the OR logic portion is executed first.

③ When there is a branch, they are executed in the order from the upper line to the lower line.

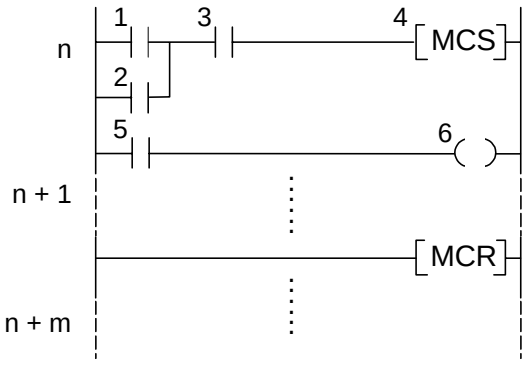
④ A combination of ② and ③ above



The instructions execution sequence in which function instructions are included also follows the above rules. However, for program execution control instructions, this will depend on the specification of each instruction.

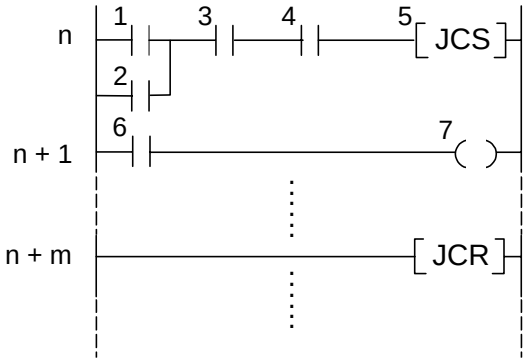
The following show the execution sequences in cases in which program execution control instructions are used.

- Master Control (MCS/MCR, MCSn/MCRn)



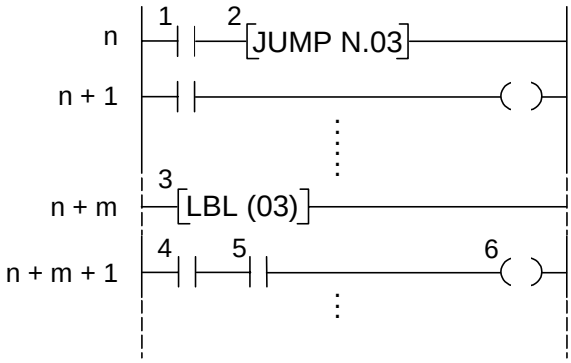
When the MCS input is ON, execution is normal.
When the MCS input is OFF, execution is by making the power rail from the rung following MCS to the rung of MCR OFF (the execution sequence is the same).

- Jump Control (JCS/JCR)



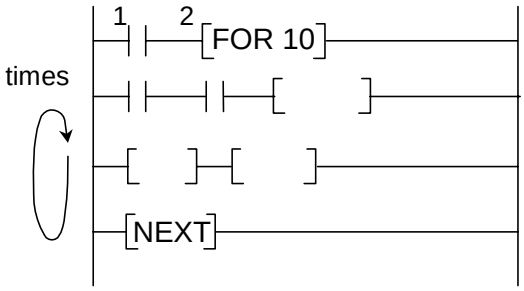
When the JCS input is ON, the instructions from the rung following JCS to the rung of JCR are read and skipped at high speed (instructions are only read and not executed). When the JCS input is OFF, execution is normal.

- Conditional Jump (JUMP/LBL)



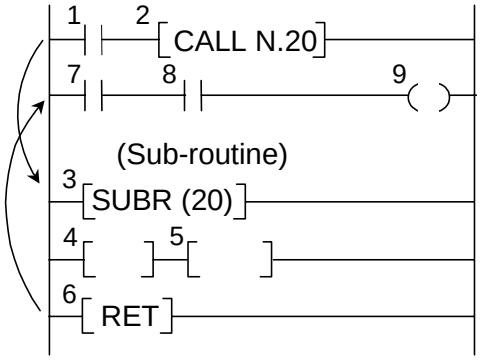
When the JUMP instruction input is ON, execution shifts to the rung following the LBL instruction with the corresponding label number (03 in the example on the left) (the numbers in the diagram on the left are the execution sequence at this time). When the JUMP instruction input is OFF, execution is normal.

- Repeat (FOR/NEXT)



When the FOR instruction input is ON, the instructions between FOR and NEXT are repeatedly executed the designated number of times (10 times in the example on the left), and when the designated number of times is reached, execution is shifted to the rung following the NEXT instruction. When the FOR instruction input is OFF, execution is normal.

- Sub-Routine (CALL/SUBR/RET)



When the CALL instruction input is ON, execution is shifted to the rung following the SUBR instruction with the corresponding sub-routine number (20 in the example in the left). When the RET instruction is reached, execution is returned to the instruction following the CALL instruction (the numbers in the diagram on the left are the execution sequence at this time). When the CALL instruction input is OFF, execution is normal.

General information on ladder diagram instructions

The general information required for designing programs with ladder diagram are listed below.

(1) In all program types, it is necessary to create at least one block by ladder diagram. In other words, the ends of the main program and each sub-program are judged by ladder diagram END instruction. Also, the end of each interrupt program is judged by a ladder diagram IRET instruction. Furthermore, it is necessary to compose the entry to and exit from a sub-routine by the ladder diagram SUBR instruction and RET instruction.

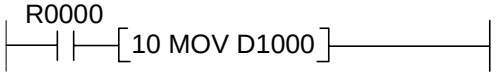
(2) The group of instructions which includes the timer instructions (4 types), counter instruction, jump control instruction, master control instruction and END instruction in the relay symbol type instructions is called the 'basic ladder instructions'.

(3) Instructions other than the basic ladder instructions are called 'function instructions'. The function instructions have respective individual function numbers (FUN No.). Also, even if instructions have the same function number, selection of the execution conditions is possible as shown below. (There are some instructions which cannot be selected)

Normal .... Executed every scan while the instruction input is ON.
Edged..... Executed only in the scan in which the instruction input changes from OFF to ON.

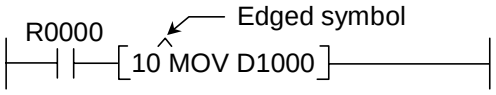
Example) Data Transfer Instruction

Nomal



The MOV instruction (substitute 10 in D1000) is executed every scan while R0000 is ON.

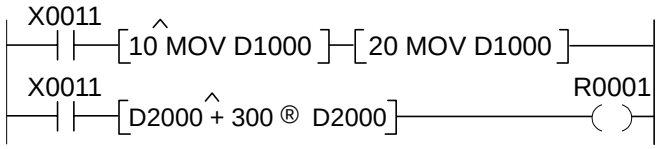
Edged



The MOV instruction (substitute 10 in D1000) is executed only in the scan in which R0000 changes from OFF to ON.

Any instructions cannot be positioned after (to the right of) a edged function instruction.

Example)

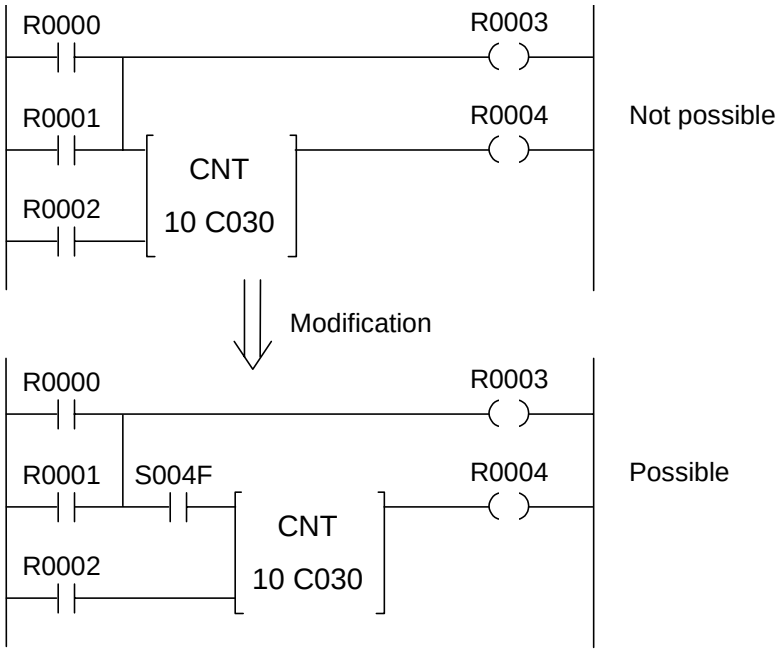


Neither of these two rungs can be created.

(4) The number of steps required for one instruction differs depending on the type of instruction. Also, even with the same instruction, the number of steps occupied varies depending on whether digit designation is used in the operand, a constant or a register is used in a double-length operand, etc. (1-10 steps/1 instruction).
Also, basically step numbers are not required for vertical connection lines and horizontal connection lines.

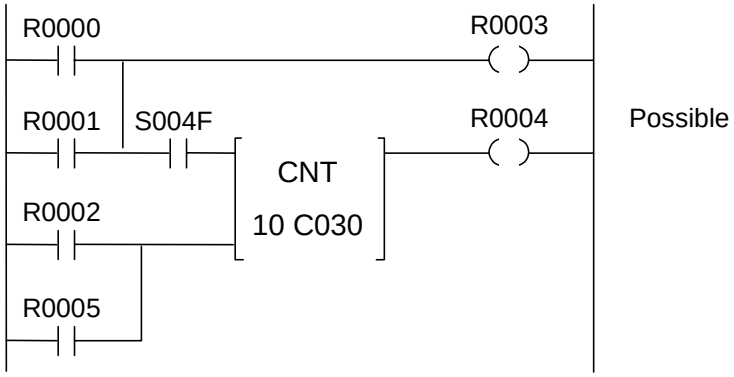
(5) In an instruction which has multiple inputs, a vertical connection line cannot be placed immediately before an input. In this case, insert a dummy contact (such as the NO contact of special relay S004F which is always ON) immediately before the input.

Example)



The above arrangement is not required for the lowest input of multiple inputs.

Example)



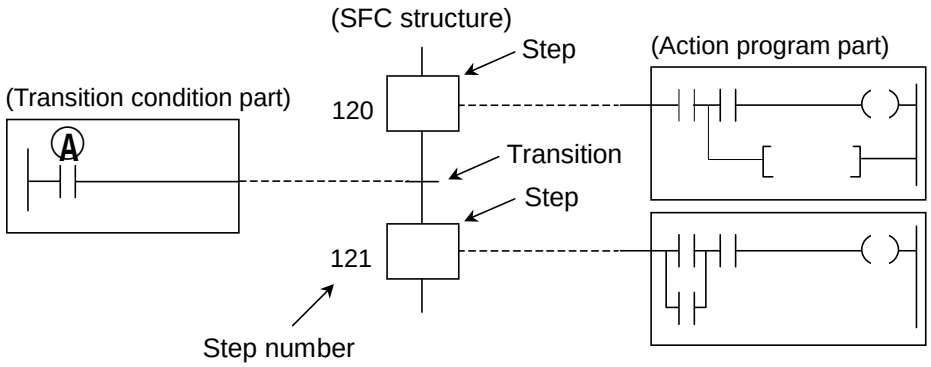
5.3 SFC

SFC is the abbreviation of Sequential Function Chart. This is a programming language suitable for process stepping control (sequential control). In the S2T, the following function can be used in the SFC.

- Jump ..... Moves the active state to an arbitrary step when a jump condition is satisfied.
- Step with waiting time..... Even if the transition condition is satisfied, step transition is not carried out until a set time has elapsed. (Wait step)
- Step with alarm ..... When transition to the following step is not carried out even if the set time has elapsed, the designated alarm device becomes ON. (Alarm step)

SFC can be used in the main program and in the sub-programs. Here the overall composition of SFC, the elements of SFC and notes on program creation are described.

An SFC program is composed of SFC structure,action program parts and transition condition parts.



An SFC structure regulates the flow of the control operation and has steps and transitions as its basic elements. A step is expressed by one box, as shown above. Each step has its own step number. Also, corresponding action program parts are annexed 1 to 1 to steps.

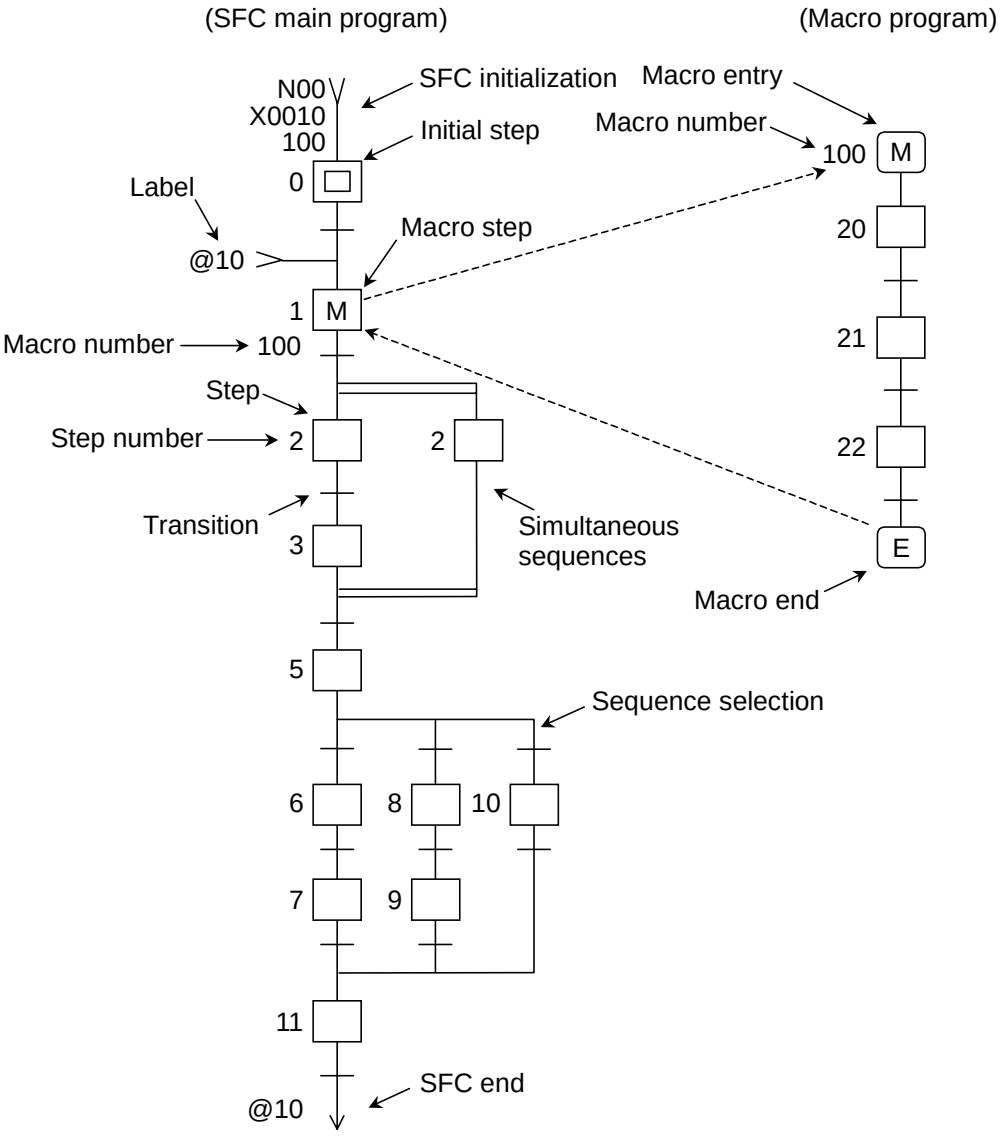
Steps have the two states of active and inactive. When a step is active, the power rail of the corresponding action program will be ON. When a step is inactive, the power rail of the corresponding action program will be OFF.

On the other hand, a transition is located between step and step, and expresses the conditions for transition of the active state from the step immediately before (upper step) to the following step (lower step). Corresponding transition conditions are annexed 1 to 1 to transitions.

For instance, in the diagram above, when step 120 is active, the action program power rail corresponding to step 120 becomes ON. In this state, when device Ⓐ becomes ON, the transition conditions are satisfied, and step 120 becomes inactive and step 121 becomes active. In accompaniment to this, the action program power rail corresponding to step 120 becomes OFF (executed as power rail OFF), and the action program power rail corresponding to step 121 becomes ON.

Overall configuration

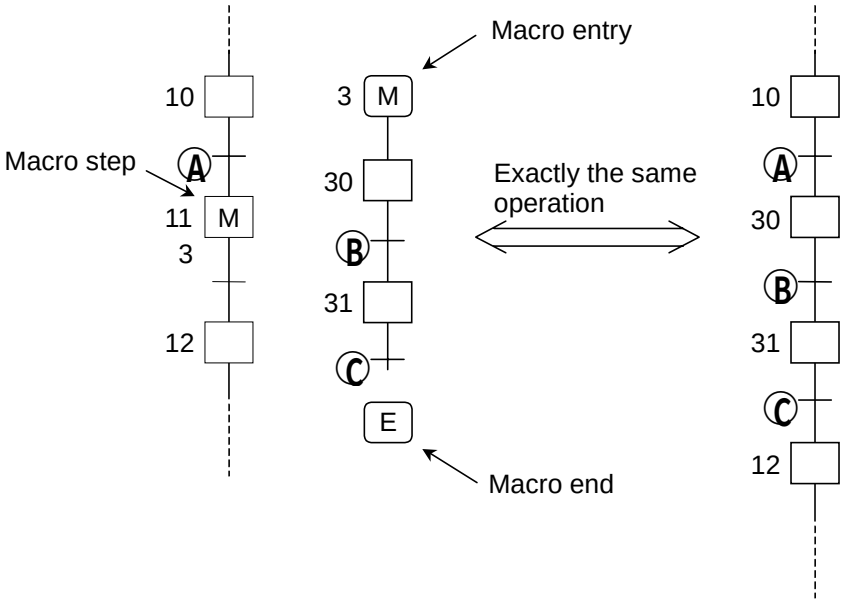
The following illustrates the overall configuration of an SFC Program.



The overall SFC program can be considered as divided into an SFC main program and a macro program.

The SFC main program has an initial step in its structure, and has an SFC end or an End step in its bottom. In the S2T, a maximum of 64 SFC main programs can be created.

On the other hand a macro program is a sub-sequence which starts from 'macro entry' and finishes at 'macro end'. Each macro program has its own macro number, and corresponds 1 to 1 to macro steps which are present in the SFC main program or other macro programs. Macro programs are used for rendering the program easy to see by making the SFC program an hierarchical structure. In all, 128 macro programs can be created.



NOTE

(1) Macro steps can be used in macro programs (SFC multi-level hierarchy). There is no limit to the number of levels.
(2) Macro programs and macro steps must correspond 1 to 1 .That is to say, macro steps designated with the same macro number cannot be used in multiple locations.
(3) Macro program should be programmed in the following location than the SFC main program/macro program which has the corresponding macro step. (in upper numbered block)

SFC programming becomes possible by designating blocks and then selecting SFC by language designation.

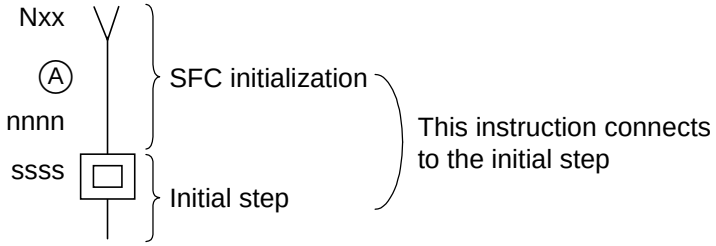
Only one SFC main program or one macro program can be created in 1 block. (1 SFC/block)

Also, the maximum number of SFC steps per block is 128.

SFC elements The following is a description of the elements which compose an SFC program.

(1) SFC Initialization
This is the function which starts-up (makes active) the designated initial step by making the steps in a designated area inactive. Either of the two methods of an SFC instruction or a ladder diagram instruction is used. One SFC initialization is required for 1 SFC main program.

① SFC Instruction



Operands: xx = Program number (0-63)
Ⓐ=Start-up device (except T.and C.)
nnnn = Number of initialized steps (1-4096)

Function: When the device (with the exception of a timer device or a counter device) designated by Ⓐ changes from OFF to ON, the number of steps following the initial step (ssss) which are designated by nnnn (from step number ssss to ssss + nnnn -1), are made inactive, and the initial step (ssss) is made active.

② Ladder Diagram Instruction (FUN 241)

Input —[SFIZ (nnnn) ssss]— Output

Operands: nnnn=N umber of initialized steps (1-4096)
ssss = Step number of initial step (0-4095)

Function: When the input changes from OFF to ON, the number of steps designated by nnnn from the step number designated by ssss (from step number ssss to ssss + nnnn -1) are made inactive, and the initial step designated by ssss is made active.

(2) Initial Step

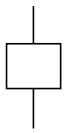
This is the step which indicates the start of an SFC main program. It has its own step number and can have an action program part which corresponds 1 to 1.

Only 1 initial step can be programmed in 1 block.

ssss  ssss = Step number (0-4095)

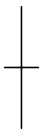
(3) Step

This expresses one unit of contral steps. The step has its own step numbers and has an action program part which corresponds 1 to 1.

ssss  ssss = Step number (0-4095)

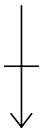
(4) Transition

This expresses the conditions for shifting the active state from a step to the following step. Transition has a transition condition part which corresponds 1 to 1.



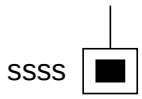
(5) SFC End

This expresses the end of an SFC main program. An SFC main program requires either this 'SFC end' or the 'end step' of (6). The 'SFC end' has a transition condition which corresponds 1 to 1 and a return destination label number. When transition condition is satisfied with the step immediately before being in the active state, the step following the designation label is made active with making the step immediately before inactive. (This is the same operation as that described in 'SFC jump' below).

@IIII  IIII = Label number (0-1023)

(6) End Step

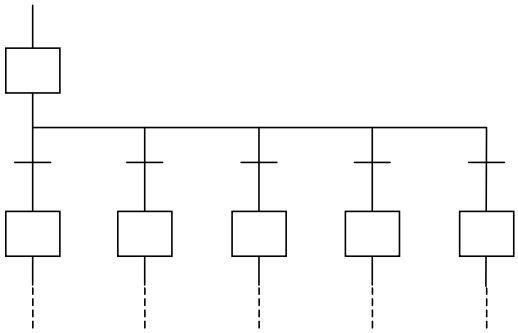
This expresses the end of an SFC main program. An SFC main program requires either this 'end step' or the 'SFC end' of (5). The end step has the same step number as the initial step. When the immediately preceding transition condition is satisfied, the initial step returns to the active state.



ssss = Initial step number (0-4095)

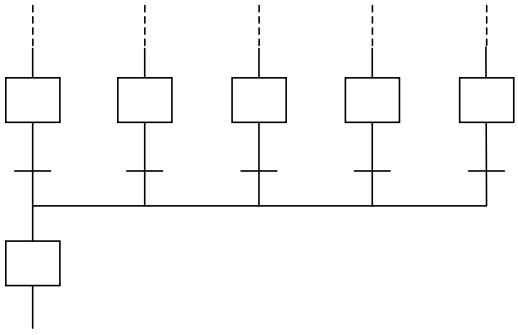
(7) Sequence Selection (divergence)

This transfers the active state to 1 step in which the transition condition is satisfied out of multiple connected steps. When the transition conditions are satisfied simultaneously, the step on the left has priority. (The number of branches is a maximum of 5 columns).

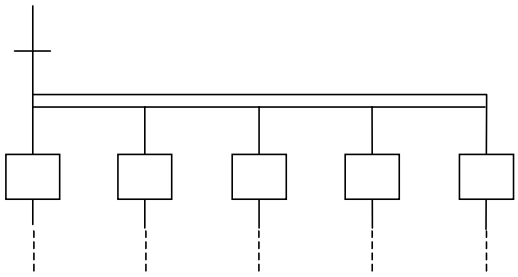


(8) Sequence Selection (convergence)

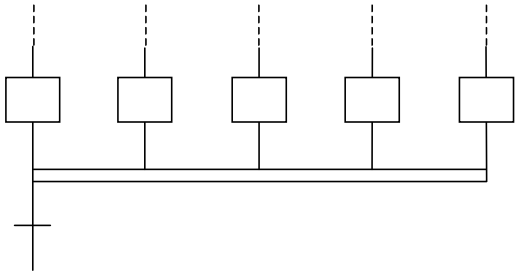
This collects into 1 step the paths diverged by above (7).



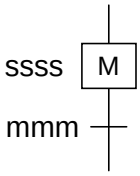
(9) Simultaneous Sequences (divergence)
After the immediately preceding transition condition is satisfied, this makes all the connected steps active. (The number of branches is a maximum of 5 columns).



(10) Simultaneous Sequences (convergence)
When all the immediately preceding steps are active and the transition condition is satisfied, this shifts the active state to the next step.



(11) Macro Step
A macro step corresponds to one macro program. When the immediately preceding transition condition is satisfied, this shifts the active state to macro program with the designated macro number. When the transition advances through the macro program and reaches the macro end, the active state is shifted to the step following the macro step. A macro step is accompanied by a dummy transition which has no transition condition (always true).

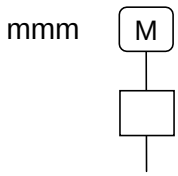


ssss = Step number (0-4095)

mmmm = Macro number (0-127)

(12) Macro Entry

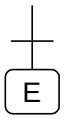
This expresses the start of a macro program. The macro entry has no action program. Steps are connected below the macro entry. Only 1 macro entry can be programmed in 1 block.



mmm = Macro number (0-127)

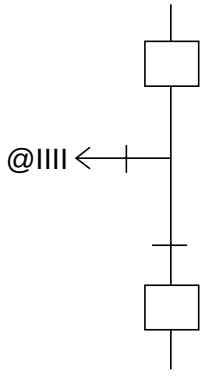
(13) Macro End

This expresses the end of a macro program. Macro end has a transition condition which corresponds 1 to 1, and returns to the corresponding macro step when this transition condition is satisfied.



(14) SFC Jump

This expresses a jump to any arbitrary step. Jump has a jump condition which corresponds 1 to 1, and jump destination label numbers. When the transition condition is satisfied, the active state jumps to the step following the designated label. When the jump transition condition and the transition condition for the following step are simultaneously satisfied, jump has priority.

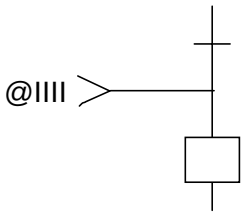


IIII = Label number (0-1023)

'SFC Jump' is located immediately after a step. SFC Jumps with the same label number may be present in multiple locations.

(15) SFC Label

This expresses the return destination from an 'SFC end' and the jump destination from a 'SFC jump'. Label is located immediately after transitions.



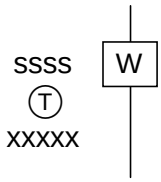
IIII = Label number (0-1023)

NOTE

Note that, when SFC label corresponding to SFC end or SFC jump is not present, or when SFC labels with the same label number are present in multiple locations, an error will occur when RUN starts-up.

(16) Wait Step

This is a step which measures the time after becoming active, and does no execute transition even if the following transition condition is satisfied, until a set time has elapsed. It has an action program corresponding 1 to 1.

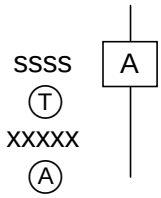


ssss = Step number (0-4095)
T = Timer register (T000-T999)
xxxxx = Set time (0-65535)

(Note) T000-user are 0.01 second timers
user-T999 are 0.1 second timers

(17) Alarm Step

This is a step which measures the time after becoming active, and when the transition condition is not satisfied within a set time, switches ON a designated alarm device. It has an action program corresponding 1 to 1. When the transition condition is satisfied and the alarm step becomes inactive, the alarm device also becomes OFF.



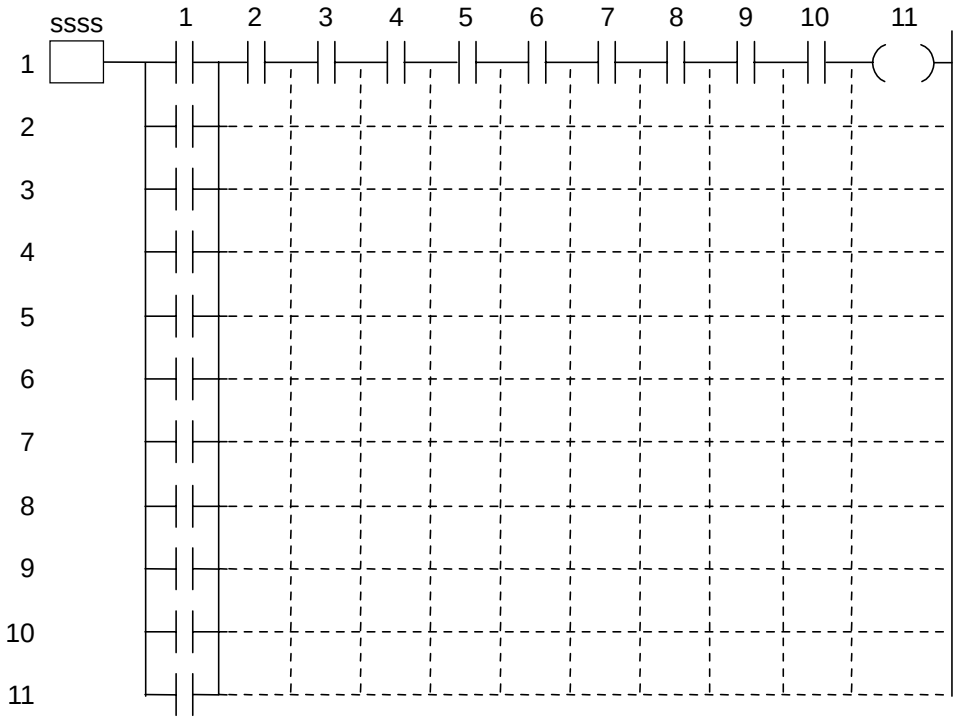
ssss = Step number (0-4095)
T = Timer register (T000-T999)
xxxxx = Set time (0-65535)
A = Alarm device (other than X, T., C.)

(Note) T000-user are 0.01 second timers
user-T999 are 0.1 second timers

Action program and transition condition

The action program corresponds to 1 step, and the transition condition corresponds to 1 transition.
These are programmed by ladder diagram.

(1) Action Program
The size of 1 action program is 11 lines × 11 columns as shown below, and the number of instruction steps is a maximum of 121 steps.



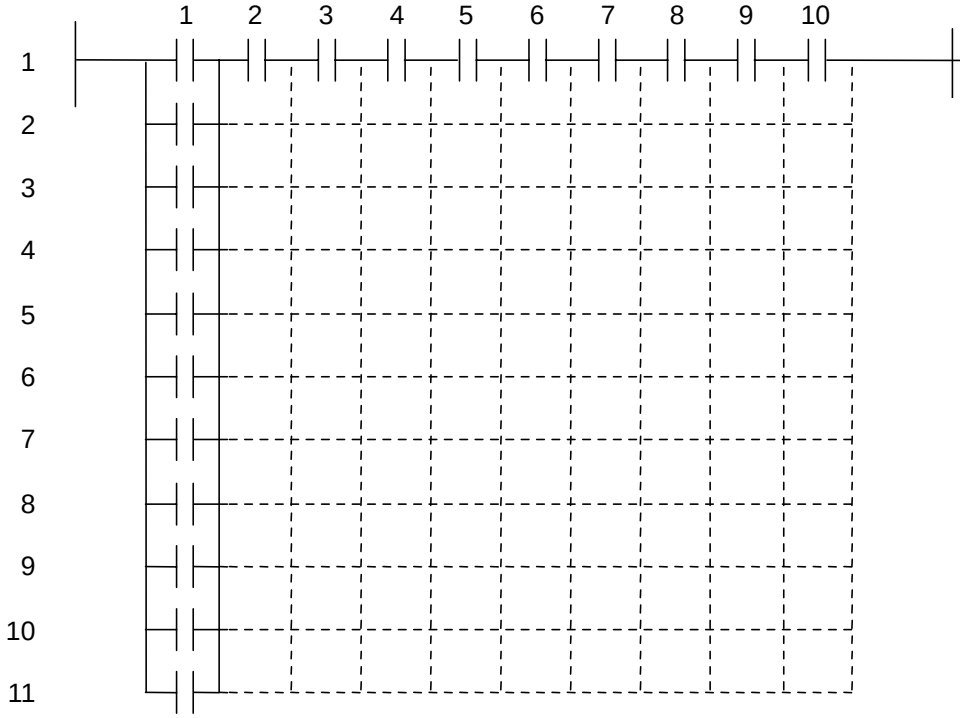
In a case when a larger size than the above is required as an action program, a sub-routine is used. (CALL instruction)

Even if there is no action corresponding to a step, this does not affect SFC operation. In this case, the step becomes a dummy step (a step which waits only the next transition condition will be satisfied).

In programming, by designating the step on the SFC screen and selecting the detail display mode, the monitor/edit screen for the action program corresponding to that step will appear.
In the case when the content of the action program is only 1 instruction out of SET, RST, coil, invert coil, positive pulse coil and negative transition-sensing coil, direct editing can be carried out without puffing up the detail display screen. See the programmer (T-PDS) operation manual in a separate volume for this operation.

(2) Transition Condition

The size of 1 transition condition is 11 lines × 10 columns, and the number of instruction steps is a maximum of 110 steps.



When there is no transition condition corresponding to a certain transition, that transition condition is always regarded as true. (Dummy transition)

In programming, by designating the transition on the SFC screen and selecting the detail display mode, the monitor/edit screen for the transition condition corresponding to that transition will appear. In the case when the content of the transition condition is only 1 instruction of NO contact or NC contact, direct editing can be carried out without putting up the detail display screen. See the programmer (T-PDS) operation manual in a separate volume for this operation.

NOTE

The following execution control instructions cannot be used in action programs and transition conditions.

- Jump (JSC/JCR, JUMP/LBL)
- Master control (MCS/MCR, MCSn/MCRn)
- End (END)
- FOR-NEXT (FOR/NEXT)

Also, the invert contact and various coil instructions cannot be used in transition conditions.

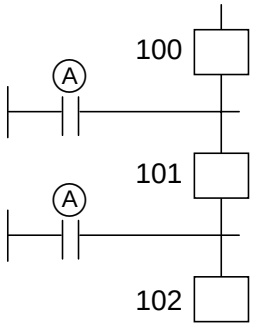
Execution system

The following shows the concept of the execution system in one SFC program.

(1) In one scan, evaluation of the transition condition, the step transition processing and the execution of the action program are sequentially operated.

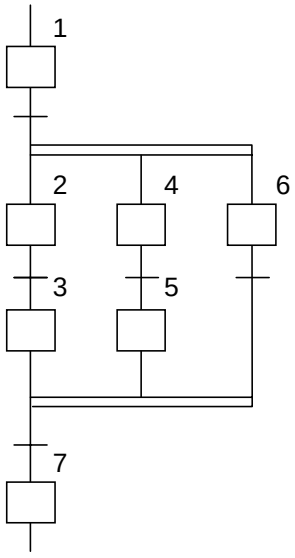
(2) Evaluation of the transition condition means the execution of the transition condition connected to an active step and carrying out a check for transition condition establishment. At this time, since evaluation is made only for active step, there are no multiple step transitions by 1 scan in consecutively connected steps.

For instance, as shown in the diagram on the right, in a program in which the transition condition from step 100 to 101 and the transition condition from step 101 to 102 are the same, step 100 becomes active in the previous scan, and when device Ⓐ has been switched ON in the present scan, there is transition to step 101 in the present scan. (Transition to step 102 will be from the next scan onward)



(3) Step transition processing means making the previous step inactive and the following step active if the transition condition is satisfied, based on the result of evaluation of the transition condition.

(4) Execution of the action program corresponding to the active step is carried out by switching the power rail ON, and executing the action program corresponding to the inactive step by switching the power rail OFF. At this time, as shown in the following diagram, the execution sequence is from top to bottom, and from left to right in branches.



The numerals in the diagram show the execution sequence of the action programs.

Points to note The following is a list of points to note when creating SFC programs.

(1) The capacity limits of SFC programs are set out in the following Tables. Be careful not to exceed these capacities.

- Overall Capacities (Maximum numbers which can be programmed in the S2T)

Number of SFC main programs	64 (063)
Number of macro programs	128 (0127)
Number of SFC steps	4096 (04095)
Number of SFC labels	1024 (01023)

- Capacities per SFC Main Program/Macro Program

Number of SFC steps	128
Number of instruction steps (SFC, actions and transition conditions total)	1024 steps*
Number of simultaneous branches	5
SFC edit screen capacity	128 lines by 5 columns

- Capacities per Action/Transition condition

Action program capacity	121 steps*
Transition condition capacity	110 steps*

*) See 5.5 ‘List of instructions’ for the required numbers of steps for SFC instructions and ladder diagram instructions.

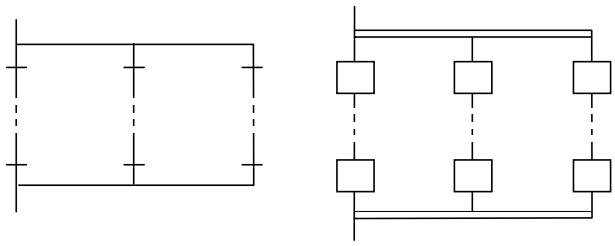
(2) The starting and re-setting of an SFC program is carried out by the SFC initialization instruction (SFC instruction/ladder diagram instruction). SFC initialization makes the steps in a designated area inactive and makes the initial step active. Therefore, the area of the steps designated by SFC initialization (the number of initialized steps) includes all the step numbers which are used in that SFC program (including macro programs as well). Take care that step numbers used in other SFC programs are not involved.

For instance, if the SFC initialization designation is 50 steps from step number 0 and step 50 is used in that SFC program, when SFC initialization is executed with step 50 in the active state, step 50 will remain active.

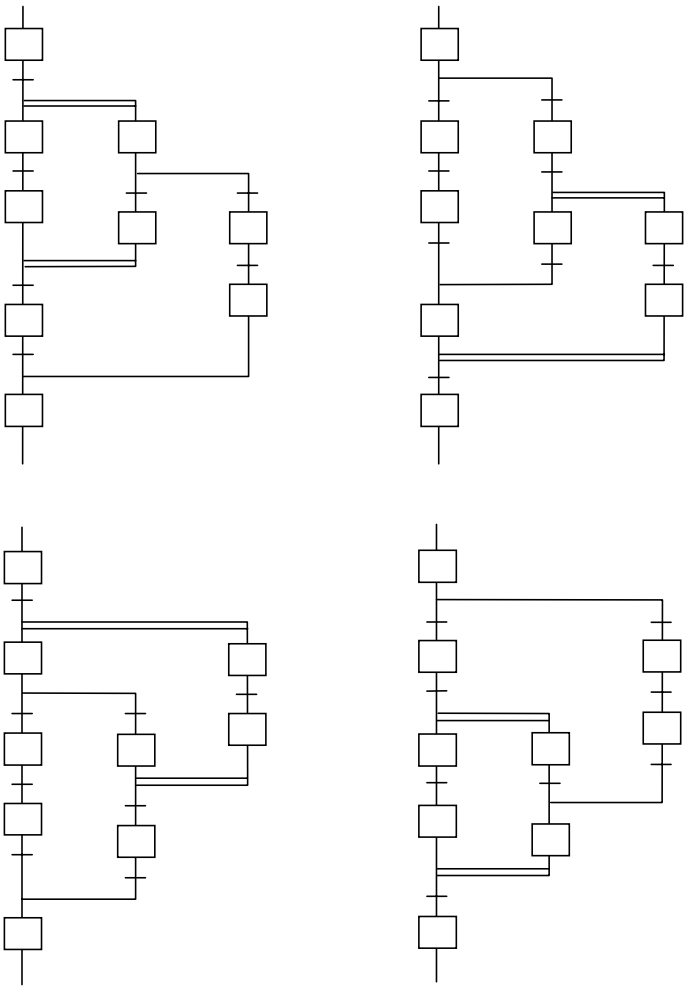
On the other hand, if the SFC initialization designation is 201 steps from step number 100 and step 300 is used in another SFC program, when SFC initialization is executed with step 300 in the active state, step 300 will become inactive without any condition.

(3) There is no limit to the step number sequence used in 1 SFC program (including macro programs). However, the initial step must be made the lowest step number in that sequence. (See (2) above)

(4) A sequence selection diverges above transitions, and converges below transitions. Also, a simultaneous sequence diverges above a steps and converges below a steps.



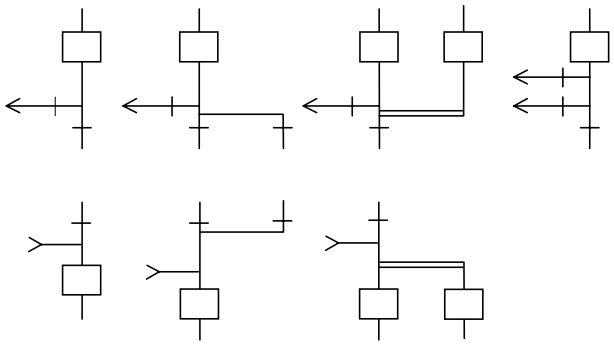
However, the divergence must end in a corresponding convergence. Therefore, programs such as the following are not allowed.



(5) The jump destination of a SFC jump may be either in the upward direction or in the downward direction, or it may be in another SFC program. Also, it is possible to jump to the outside from inside a branch.

Since a SFC jump can be very freely used in this way, take thorough precautions so that the SFC logic will not become abnormal (so that multiple unrelated steps in a series of SFC will not become active) through jumping.

A SFC jump is always positioned immediately after a step, Also, although basically a SFC label is positioned immediately after a transition, it is positioned between the convergence line and the step in the case of a sequence selection (convergence).



(6) The states (active/inactive) of SFC steps are not retained for power off. When starting-up, all become inactive.

(7) The output of an SFC step can be controlled by sandwiching the SFC program block by ladder diagram master control (MCS/MSR). When the input of MCS is OFF, the power rail of the action program corresponding to the active step also becomes OFF. However, in the state, step transition is carried out.

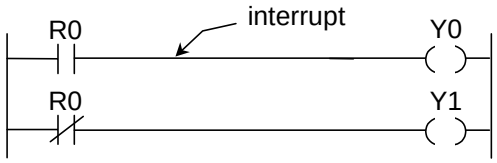
5.4 Programming precautions

The S2T supports multi-task function. When using this function, there is the possibility of the sub-program being interrupted by the main program or the interrupt program, and the main program being interrupted by the interrupt program. Precautionary notes arising from this are given below, and should be taken into account when creating programs.

(1) Avoid using the same sub-routine in the main program, the sub-programs and the interrupt programs. When the main program execution is interrupted during a sub-routine is being executed and the same sub-routine is executed in that state, the results after re-starting are sometimes not as expected.

(2) There is no classification of user data (register/device) by program type. Therefore, take thorough precautions that there is no erroneous mixed use between program types.

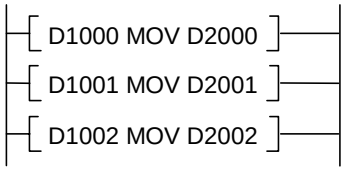
Example)



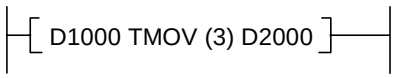
Interrupt occurs through the timing in the above diagram. And when the content of R0 is modified in the interrupt, the simultaneous ON (or the simultaneous OFF) of Y0 and Y1, which normally could not occur, happens.

(3) Try to execute the exchange of data between different program types by 1 instruction or by using the interrupt disable (DI) and the interrupt enable (EI) instructions. Otherwise, the same thing as in (2) above may happen.

Example) Composition of the main program when transferring the three data, D1000, D1001 and D1002, from the interrupt program to the main program.



In the above program, when an interrupt occurs between instructions, synchronization between D2000, D2001 and D2002 cannot be guaranteed. In this case, make 1 instruction by using the table transfer instruction, as follows.

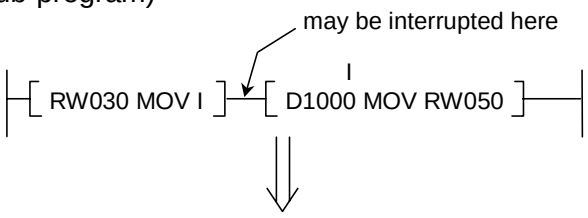


Or sandwich these instructions by DI and EI instructions.

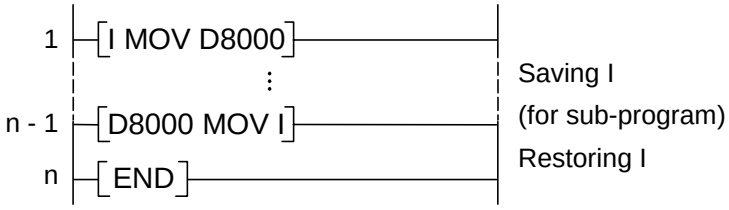
(4) If the same index register is used in different program types, the data of the index register should be saved and restored as follows.

Example)

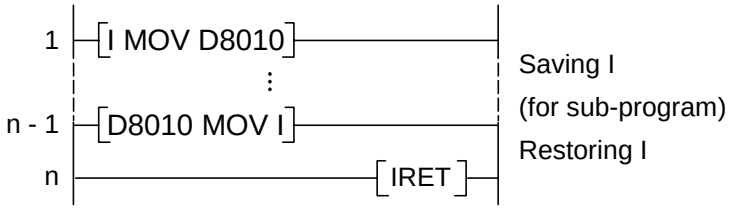
(Sub-program)



(Main-program)



(Interrupt program)



With respect to the main program, the data of index registers are saved when interrupt occurs and restored when operation returns to main program automatically. However, because of this, even if an index register is used only in an interrupt program, the data continuity of the index register between interrupt intervals is not kept. In such case, use another register to store index value substitute the value into an index register in the interrupt program.

5.5 Network support function

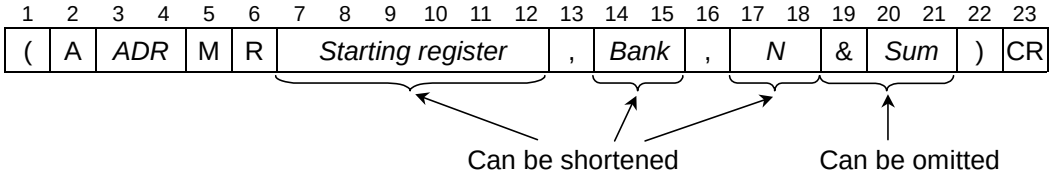
5.5.1 Expand memory card data access through computer link

The expanded file register data stored in the backuped memory can be read/written through RS-485 computer link.

There are two types of data storage format for the expand memory. They are 8 k words per bank and 64 k words per bank. (Refer to XFER instruction)
Note that the computer link command for these formats are slightly different.

Expanded file register data read [MR]

Request message format (Host → S2T):



ADR: Station address ... 01 to 32

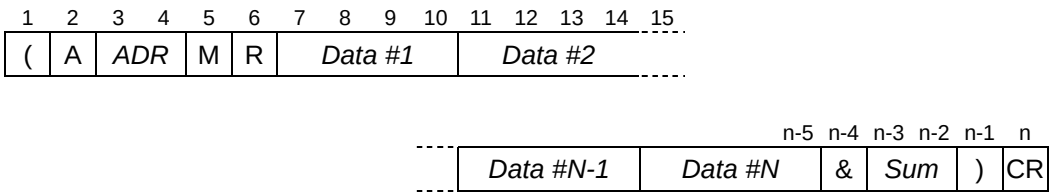
Starting register:
For 8 k words per bank..... F0000 to F8191 ← Upper case F
For 64 k words per bank ..... f0000 to f65535 (bank 1) ← Lower case f
f0000 to f57343 (bank 2)

Bank: For 8k words per bank ..... 1 to 15
For 64k words per bank ..... 1 to 7

N: Number of registers to be read ... 1 to 61 (61 words max.)

Sum: Check sum

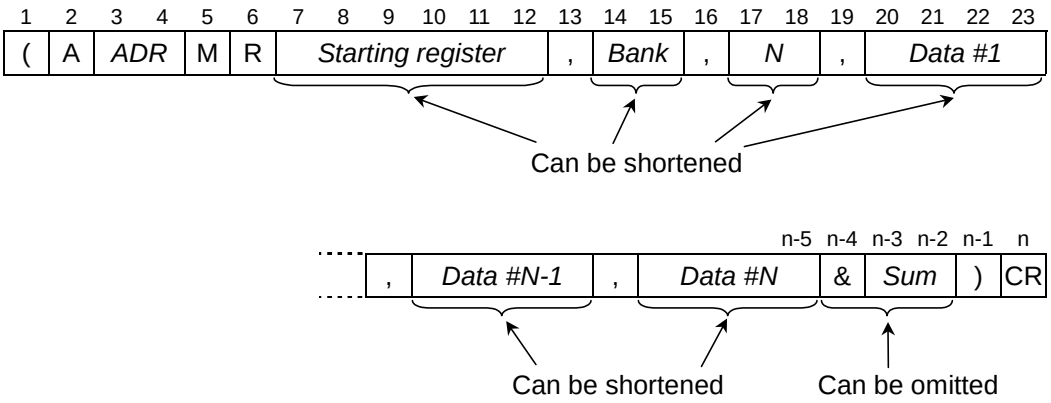
Response message format (S2T → Host):



Data: Data in hexadecimal

Expanded file register data read [MW]

Request message format (Host → S2T):



ADR: Station address ... 01 to 32

Starting register:
For 8 k words per bank ..... F0000 to F8191 ← Upper case F
For 64 k words per bank ..... f0000 to f65535 (bank 1) ← Lower case f
f0000 to f57343 (bank 2)

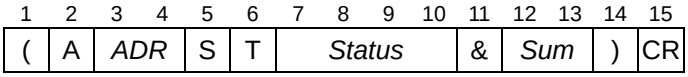
Bank: For 8k words per bank ..... 1 to 15
For 64k words per bank ..... 1 to 7

Data: Data in hexadecimal

N: Number of registers to be read ... 1 to 61 (61 words max.)

Sum: Check sum

Response message format (S2T → Host):



Status: S2T operation status

NOTE

(1) The maximum message text length is limited to 255 bytes.
(2) Shortening expression for starting register, bank, number and data (MW only) are available. E.g. F9 for F00009.
When shortening expression is used, the maximum number of MW command can be increased more than 46 words. In this case, it is limited by the maximum message text length (255 bytes).
(3) When an error has occurred, error response CE or EE is returned.
- If designated register or bank is out of the effective range, EE115 (register no./size error) is returned.

(4) For general information of computer link function, refer to T-series Computer Link Operation Manual.

5.5.2 TOSLINE-S20LP (loop) support

In addition to th standard bus connection type TOSLINE-S20 (here called S20), the optical loop connection type TOSLINE-S20LP (here called S20LP) can be used with the S2T. (SN627: S2T station module of S20LP)
By using the S20LP, high speed control-data linkage is available as same as the S20. Furthermore, peer-to-peer communication between S2T's becomes available via S20LP.

- Up to two S20LP can be installed on a S2T. (S20LP and S20 total)
- The S20LP has 4 k words of scan transmission capacity. The leading 2 k words of the scan memory can be assigned to S2T's link register (W). And the following 2 k words can be read/written by using XFER instruction.
- The S20LP does not have the scan healthy map. Therefore, SW128 to SW255 are not used for the S20LP.
- The S20LP has the loop map which indicates loop connection status of each station. This loop map can be read by using READ instruction.
- By using SEND and RECV instructions, any register data of a S2T can be sent to other S2T, and any register data of other S2T can be read into a S2T, via S20LP. (peer-to-peer communication)

NOTE

(1) The S20LP is under development.
(2) For details of the S20LP, refer to the separate manual for S20LP.

5.5.3 Ethernet support

The Ethernet module (EN611/EN631) is available for the S2T. By using the EN611/EN631, the S2T can be connected to Ethernet network.
Using the Ethernet module, the S2T supports the following communication functions.

- Computer link function:
  Host computer on the Ethernet can perform data read/write, S2T status read, program up-load/down-load, etc. for the S2T, by using the T-series computer link command.

- Peer-to-peer communication:
  By using SEND and RECV instructions, any register data of a S2T can be sent to other S2T, and any register data of other S2T can be read into a S2T, via Ethernet.

- Socket service:
  Communication between a computer and a S2T user program is available by using SEND and RECV instructions. Maximum 8 ports of socket are available. The protocol can be selected either TCP/IP or UDP/IP for each port.

Up to four EN611/EN631's can be installed on a S2T.
To activate the EN611/EN631, SEND instruction is required to set parameters (IP address, UDP port number) and to send commands (communication start, etc.)

NOTE
▽▲▽

(1) For details of the EN611/EN631, refer to the separate manual for EN611/EN631.

5.6 Instructions

This section explains the specifications of the following instructions.

Double-word multiplication and division (FUN042 D*/)

Combination instruction of multiplication and division for double-word data.
This instruction is not available on the S2T.

Essential PID (FUN156 PID3)

PID (Proportional, Integral, Derivative) control instruction which has the following features.
· Incomplete derivative action expanding stable application range
· Essential digital algorithm succeeding to benefits of analog PID
This instruction is not available on the S2T.

Floating point essential PID (FUN232 FPID3)

Essential RID instruction for floating point data.
This instruction is not available on the S2T.

Expanded data transfer (FUN236 XFER)

Data transfer instruction between special objects, i.e. expanded file register, data in flash memory, TOSLINE-S20 scan memory, etc.
Some functions are added to this instruction for the S2T.

Network data send (FUN239 SEND)

Used to peer-to-peer communication via TOSLINE-S20LP or Ethernet. This instruction is also used for Ethernet module (EN611/EN631) control.
This instruction is not available on the S2T.

Network data receive (FUN240 RECV)

Used to peer-to-peer communication via TOSLINE-S20LP or Ethernet. This instruction is also used for Ethernet module (EN611/EN631) control.
This instruction is not available on the S2T.

5.6.1 Double-word multiplication and division (D∗/)

FUN 042	D∗/	Double-word multiplication and division

Expression

Input —[*A+1·A* D∗/ *B+1·B* → *C+1·C*]— Output

Function

When the input is ON, the data of *A+1·A* is multiplied by the data of *B*+1·*B*, and the product is divided by *B+3·B+2*, then the quotient is stored in *C+1·C* and the remainder in *C+3·C+2*.
The data range is -2147483648 to 2147483647. If the result (quotient) is out of the data range, the following limit value is stored.

Positive overflow: quotient = 2147483647, remainder = 0
Negative overflow: quotient = -2147483647, remainder = 0

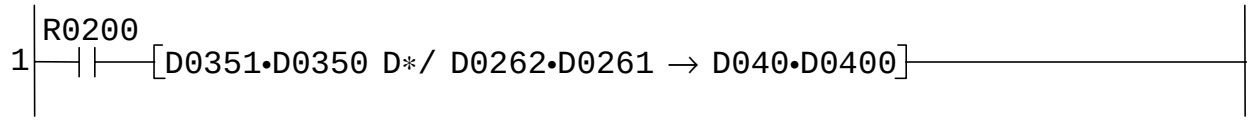
Execution condition

Input	Operation		Output	ERF
OFF	No execution		OFF	—
ON	*B+3·B+2* ≠ 0, no overflow	Normal execution	ON	—
	B+3·B+2 ≠ 0, overflow	Limit	ON	ON
	B+3·B+2 = 0	No execution	OFF	ON

Operand

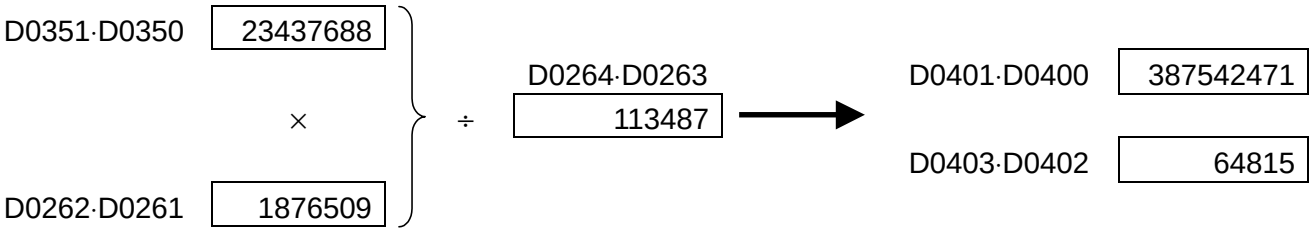
	Name	Device										Register															Con-stant	Index
		X	Y	S	L	R	Z	T.	C.	I	O	XW	YW	SW	LW	RW	W	T	C	D	F	IW	OW	I	J	K		
A	Operation data											√	√	√	√	√	√	√	√	√	√						√	√
B	Multiplier, divisor											√	√	√	√	√	√	√	√	√	√							√
C	Result												√	√	√	√	√	√	√	√	√							√

Example



When R0200 is ON, the double-word data of D0351·D0350 is multiplied by the data of D0262·D0261, and the product is divided by the data of D0264·D0263, then the quotient is stored in D0401·D0400 and the remainder in D0403·D0402.

If the data of D0351·D0350 is 23437688, D0262·D0261 is 1876509, and D0264·D0263 is 113487, the quotient (387542471) is stored in D0401·D0400 and the remainder (64815) is stored in D0403·D0402.



NOTE

Edge execution modifier is also available for this instruction.

5.6.2 Essential PID (PID3)

FUN 156	PID3	Essential PID

Expression

Input —[*A* PID3 *B* → *C*]— Output

Function

Performs PID (Proportional, Integral, Derivative) control which is a fundamental method of feed-back control. (Pre-derivative real PID algorithm)
This PID3 instruction has the following features.

- For derivative action, incomplete derivative is used to suppress interference of high-frequency noise and to expand the stable application range,
- Controllability and stability are enhanced in case of limit operation for MV, by using digital PID algorithm succeeding to benefits of analog PID.
- Auto, cascade and manual modes are supported in this instruction.
- Digital filter is available for PV.
- Direct / reverse operation is selectable.

Execution condition

Input	Operation	Output
OFF	Initialization	OFF
ON	Execute PID every setting interval	ON when execution

Operand

	Name	Device										Register															Con-stant	Index
		X	Y	S	L	R	Z	T.	C.	I	O	XW	YW	SW	LW	RW	W	T	C	D	F	IW	OW	I	J	K		
A	Top of input data											√	√	√	√	√	√	√	√	√	√							√
B	Top of parameter											√	√	√	√	√	√	√	√	√	√							√
C	Top of output data												√	√	√	√	√	√	√	√	√							√

Input data

A	Process input value	**VC**
A+1	A-mode set value	**ASV**
A+2	C-mode set value	**CSV**
A+3	M-mode MV input	**MMV**
A+4	MV tracking input	**TMV**
A+5	Mode setting	**MODE**

A-mode: Auto mode
C-mode: Cascade mode
M-mode: Manual mode

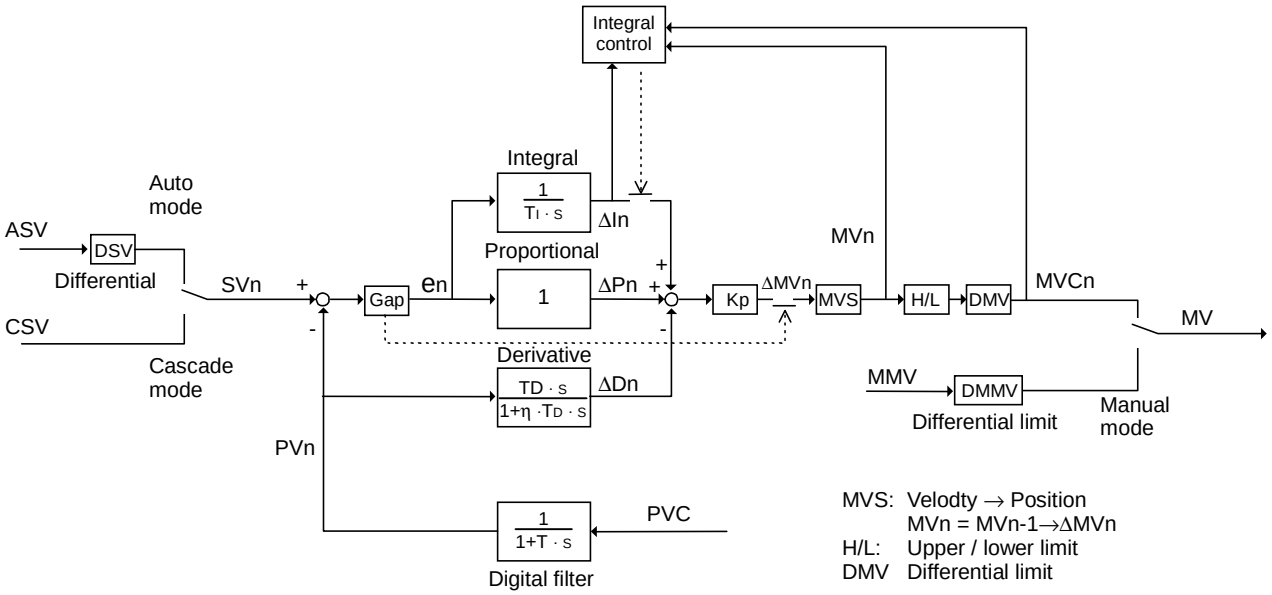
Control parameter

B	Proportional gain	**K_P**
B+1	Integral time	**T_I**
B+2	Derivative time	**T_D**
B+3	Dead-band	**GP**
B+4	A-mode initial SV	**ISV**
B+5	Input filter constant	**FT**
B+6	ASV differential limit	**DSV**
B+7	MMV differential limit	**DMMV**
B+8	Initial status	**STS**
B+9	MV upper limit	**MH**
B+10	MV lower limit	**ML**
B+11	MV differential limit	**DMV**
B+12	Control interval setting	**n**

Output data

C	Manipulation value	**MV**
C+1	Last error	**e_{n-1}**
C+2	Last derivative value	**D_{n-1}**
C+3	Last PV	**PV_{n-1}**
C+4	Last SV	**SV_{n-1}**
C+5	Integral remainder	**Ir**
C+6	Derivative remainder	**Dr**
C+7	Internal MV	**MV_n**
C+8	Internal counter	**C**
C+9	Control interval	**Δt**

Control block diagram



Integral action control:

When MV is limited (H/L, DMV) and the integral value has same sign as limit over, integral action is stopped.

Velocity → Position conversion:

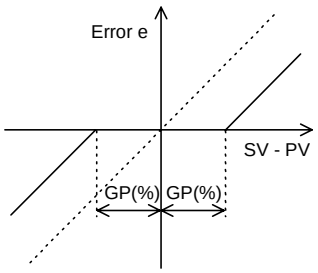
In Direct mode, MV increases when PV is increased.

→ $MV_n = MV_{n-1} - \Delta MV_n$

In Reverse mode, MV decreases when PV is increased.

→ $MV_n = MV_{n-1} + \Delta MV_n$

Gap (dead-band) operation:



Algorithm Digital filter:

$PV_n = (1 - FT) \cdot PVC + FT \cdot PV_{n-1}$

Here,

$0.000 \leq FT \leq 0.999$

PID algorithm:

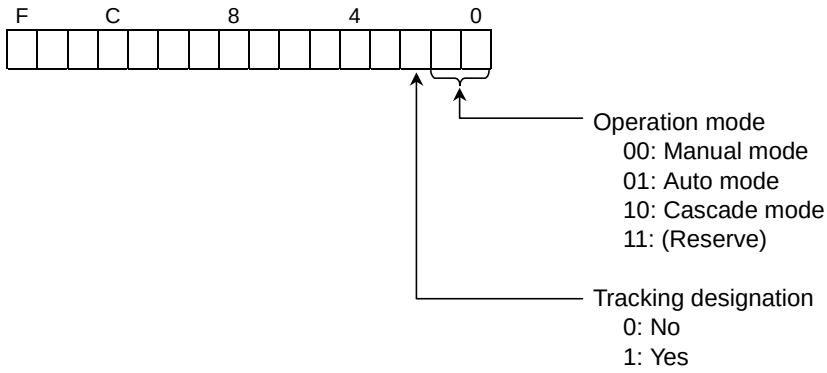
$$\Delta MV_n = K_P \cdot (\Delta P_n + \Delta I_n + \Delta D_n)$$
$$MV_n = MV_{n-1} \pm \Delta MV_n$$

Here,

$$\Delta P_n = e_n - e_{n-1}$$
$$e_n = SV_n - PV_n \text{ (If GP } \quad 0\text{, Gap is applied)}$$
$$\Delta I_n = \frac{e_n \cdot \Delta t + Ir}{T_I} \quad (\text{If } T_I = 0,\ \Delta I_n = 0)$$
$$\Delta D_n = \frac{T_D \cdot (PV_{n-1} - PV_n) - \Delta t \cdot D_{n-1} + Dr}{\Delta t + \eta \cdot TD}$$
$$D_n = D_{n-1} + \Delta D_n$$
$$\eta = 0.1 \text{ (Fixed)}$$

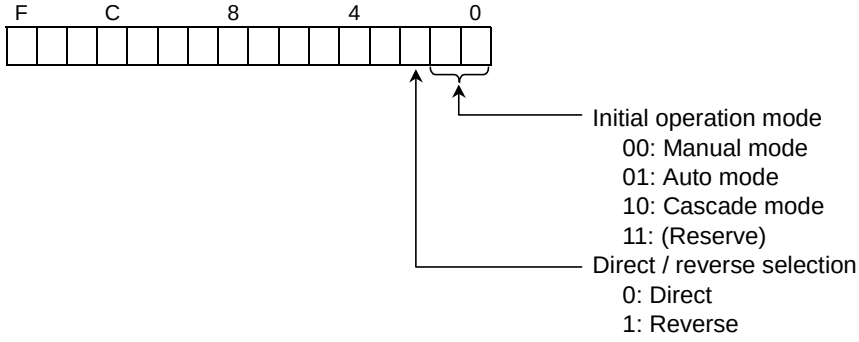
Parameter details

A	Process input value PVC (0.00 to 100.00 %)	Data range: 0 to 10000
A+1	Auto mode set value ASV (0.00 to 100.00 %)	Data range: 0 to 10000
A+2	Cascade mode set value CSV (0.00 to 100.00 %)	Data range: 0 to 10000
A+3	Manual mode MV MMV (-25.00 to 125.00 %)	Data range:
A+4	MV tracking input TMV (-25.00 to 125.00 %)	Data range: -2500 to 12500
A+5	Mode setting MODE	Data range: -2500 to 12500



B	Proportional gain K_P (0.00 to 327.67)	Data range: 0 to 32767
B+1	Integral time T_I (0.000 to 32.767 min., stop if $T_I = 0$)	Data range: 0 to 32767
B+2	Derivative time T_D (0.000 to 32.767 min.)	Data range: 0 to 32767
B+3	Gap (dead-band) GP (0.00 to 10.00 %)	Data range: 0 to 1000
B+4	Auto mode initial set value ISV (0.00 to 100.00 %)	Data range: 0 to 10000
B+5	Input filter constant FT (0.000 to 0.999)	Data range: 0 to 999
B+6	ASV differential limit DSV (0.00 to 100.00 %/Δt)	Data range: 0.to 10000
B+7	MMV differential limit DMMV (0.00 to 100.00 %/Δt)	Data range: 0.to 10000

B+8 Initial status STS



B+9	MV upper limit MH (-25.00 to 125.00 %)	Data range: -2500 to 12500
B+10	MV lower limit ML (-25.00 to 125.00 %)	Data range: -2500 to 12500
B+11	MV differential limit DMV (0.00 to 100.00 %/Δt)	Data range: 0 to 10000
B+12	Control interval setting n (1 to 32767 times)	Data range: 1 to 32767

Executes PID every n scan. Therefore, control interval Δt = n × constant scan interval (It is treated as n = 1 when n ≤ 0)

C	Manipulation value MV (-25.00 to 125.00 %)	Data range: -2500 to 12500
C+1 to *C+9*	Internal work area	

Operation

1. When the instruction input is OFF:
   Initializes the PID3 instruction.
   Operation mode is set as specified by *B+8*
   A+5 bit 0, 1 ← *B+8* bit 0, 1
   Auto mode SV is set as specified by *B+4*.
   ASV ← ISV
   Manual mode MV is set as current MV.
   MMV ← MV
   Internal calculation data is initialized.
   MV remains unchanged.

2. When the instruction input is ON:
   Executes PID calculation every n scan which is specified by *B+12*.
   The following operation modes are available according to the setting of *A+5*.

   - Auto mode
     This is a normal PID control mode with ASV as set value.
     Set value differential limit DSV, manipulation value upper/lower limit MHIML and differential limit DMV are effective.
     Bump-less changing from auto mode to manual mode is available. (Manual mode manipulation value MMV is over-written by current MV automatically. MMV ←MV)

- Manual mode
  In this mode, the manipulation value MV can be directly controlled by the input value of MMV.
  MV differential limit for manual mode DMMV is effective. MH/ML and DMV are not effective.
  When mode is changed from manual to auto or cascade, the operation is started from the current MV.

- Cascade mode
  This is a mode for PID cascade connection. PID is executed with CSV as set value.
  Different from the auto mode, set value differential limit is not effective. Manipulation value upper/lower limit MH/ML and differential limit DMV are effective.
  Bump-less changing from cascade mode to manual mode is available. (Manual mode manipulation value MMV is over-written by current MV automatically. MMV ← MV)
  And, bump-less changing from cascade mode to auto mode is available. (Auto mode set value ASV is over-written by current CSV automatically. ASV ← CSV)

- MV tracking
  This function is available in auto and cascade modes. When the tracking designation (A+5 bit 2) is ON, tracking input TMV is directly output as MV.
  Manipulation value upper/lower limit MH/ML is effective, but differential limit DMV is not effective.
  When the tracking designation is changed to OFF, the operation is started from the current MV.

NOTE

- PID3 instruction is only usable on the main-program.
- PID3 instruction must be used under the constant scan mode. The constant scan interval can be selected in the range of 10 to 200 ms, 10 ms increments.
- The data handled by the PID3 instruction are % units. Therefore, process input value PVC, manipulation value MV, etc., should be converted to % units (scaling), before and/or after the PID3 instruction. For this purpose, the function generator instruction (FUN165 FG) is convenient.

5.6.3 Floating point essential PID (FPID3)

FUN 232	FPID3	Floating point essential PID

Expression

Input —[*A+1·A* FPID3 *B+1·B* → *C+1·C*]— Output

Function

Performs PID (Proportional, Integral, Derivative) control which is a fundamental method of feed-back control. (Pre-derivative real PID algorithm)
The operation of this FPID3 instruction is the same as the PID3 (FUN 156) instruction except for dealing data as floating point data.

Execution condition

Input	Operation	Output
OFF	Initialization	OFF
ON	Execute PID every setting interval	ON when execution

Operand

	Name	Device										Register															Con-stant	Index
		X	Y	S	L	R	Z	T.	C.	I	O	X W	Y W	S W	L W	R W	W	T	C	D	F	I W	O W	I	J	K		
A	Top of input data											√	√	√	√	√	√	√	√	√	√							√
B	Top of parameter											√	√	√	√	√	√	√	√	√	√							√
C	Top of output data												√	√	√	√	√	√	√	√	√							√

Input data

A+1·A		
	Process input value	**VC**
	A-mode set value	**ASV**
	C-mode set value	**CSV**
	M-mode MV input	**MMV**
	MV tracking input	**TMV**
	Mode setting	**MODE**

A-mode: Auto mode
C-mode: Cascade mode
M-mode: Manual mode

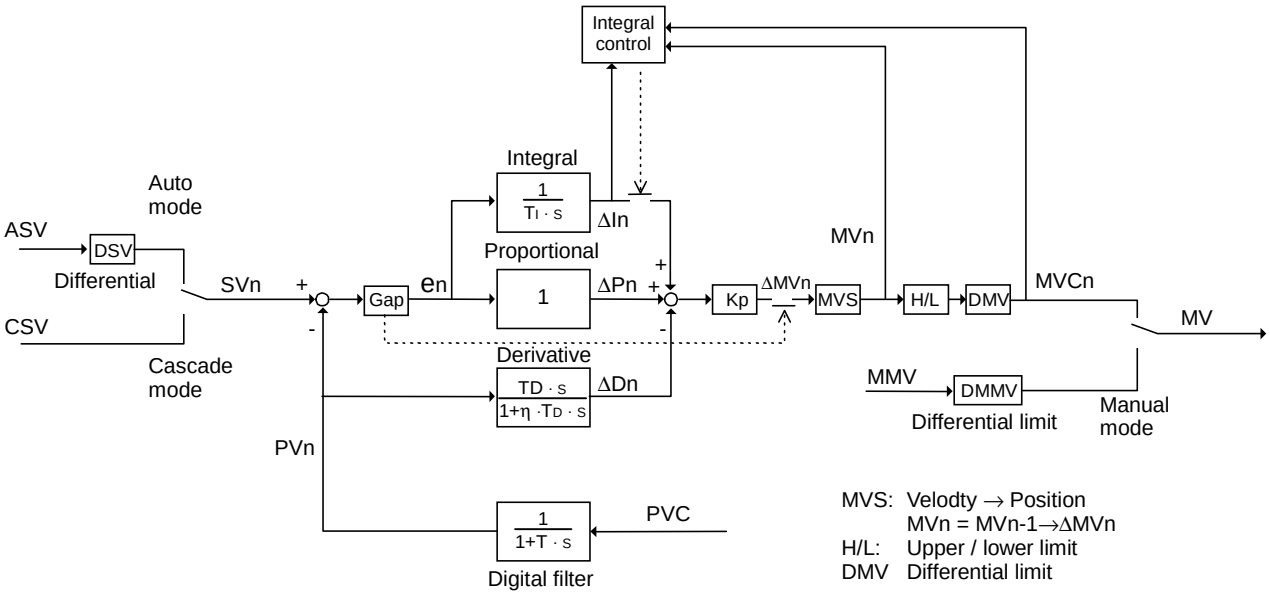
Control parameter

B+1·B		
	Proportional gain	**K_P**
	Integral time	**T_I**
	Derivative time	**T_D**
	Dead-band	**GP**
	A-mode initial SV	**ISV**
	Input filter constant	**FT**
	ASV differential limit	**DSV**
	MMV differential limit	**DMMV**
	Initial status	**STS**
	MV upper limit	**MH**
	MV lower limit	**ML**
	MV differential limit	**DMV**
	Control interval setting	**n**

Output data

C+1·C		
	Manipulation value	**MV**
	Last error	**e_{n-1}**
	Last derivative value	**D_{n-1}**
	Last PV	**PV_{n-1}**
	Last SV	**SV_{n-1}**
	Integral remainder	**Ir**
	Derivative remainder	**Dr**
	Internal MV	**MV_n**
	Internal counter	**C**
	Control interval	**Δt**

Control block diagram



Integral action control:

When MV is limited (H/L, DMV) and the integral value has same sign as limit over, integral action is stopped.

Velocity → Position conversion:

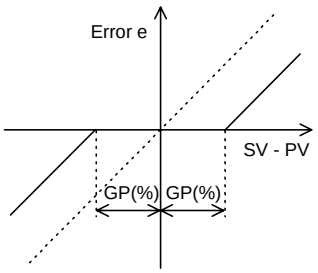
In Direct mode, MV increases when PV is increased.

→ $MV_n = MV_{n-1} - \Delta MV_n$

In Reverse mode, MV decreases when PV is increased.

→ $MV_n = MV_{n-1} + \Delta MV_n$

Gap (dead-band) operation:



Algorithm

Digital filter:

$PV_n = (1 - FT) \cdot PVC + FT \cdot PV_{n-1}$

Here,

$0 \leq FT \leq 1$

PID algorithm:

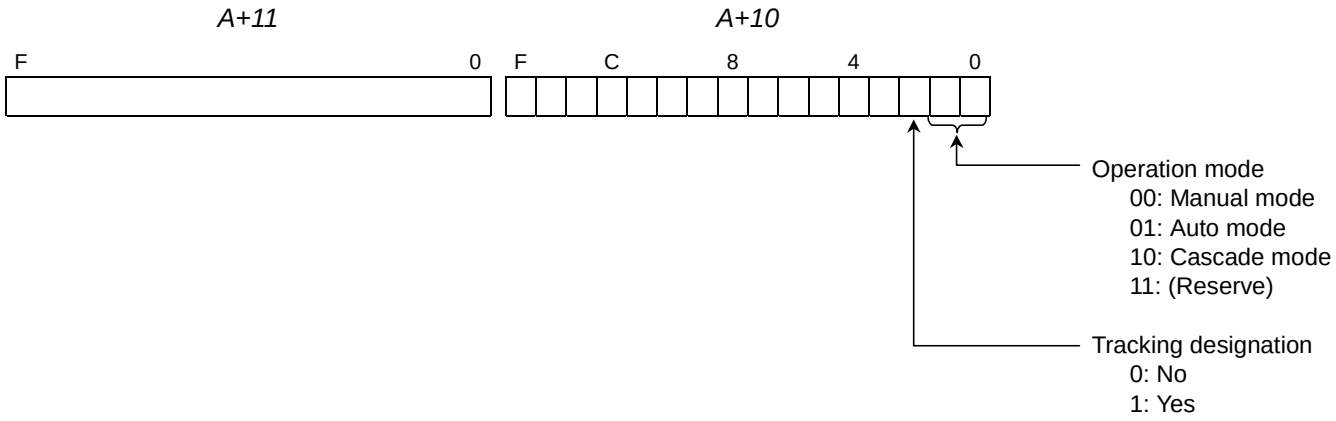
$$\Delta MV_n = K_P \cdot (\Delta P_n + \Delta I_n + \Delta D_n)$$
$$MV_n = MV_{n-1} \pm \Delta MV_n$$

Here,

$$\Delta P_n = e_n - e_{n-1}$$
$$e_n = SV_n - PV_n \text{ (If GP } \neq 0\text{, Gap is applied)}$$
$$\Delta I_n = \frac{e_n \cdot \Delta t + Ir}{T_I} \quad (\text{If } T_I = 0,\ \Delta I_n = 0)$$
$$\Delta D_n = \frac{T_D \cdot (PV_{n-1} - PV_n) - \Delta t \cdot D_{n-1} + Dr}{\Delta t + \eta \cdot TD}$$
$$D_n = D_{n-1} + \Delta D_n$$
$$\eta = 0.1 \text{ (Fixed)}$$

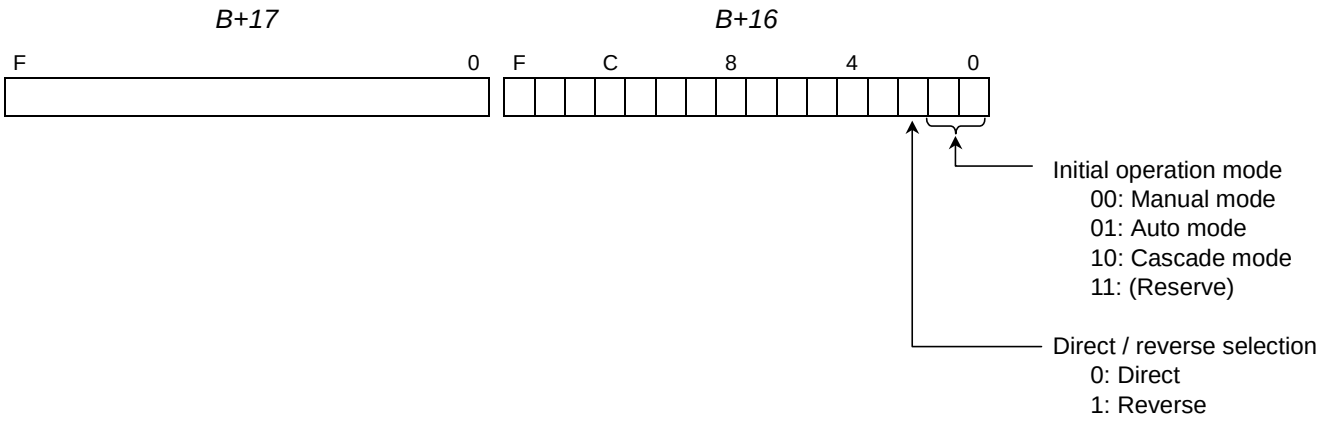
Parameter details

A+1·A	Process input value PVC (0 to 100 %)	Data range: 0.0 to 100.0
A+3·A+2	Auto mode set value ASV (0 to 100 %)	Data range: 0.0 to 100.0
A+5·A+4	Cascade mode set value CSV (0 to 100 %)	Data range: 0.0 to 100.0
A+7·A+6	Manual mode MV MMV (-25 to 125 %)	Data range: -25.0 to 125.0
A+9·A +8	MV tracking input TMV (-25 to 125 %)	Data range: -25.0 to 125.0
A+11·A+10	Mode setting MODE	



B+1·B	Proportional gain K_P (0 to 327.67)	Data range: 0.0 to 327.67
B+3·B+2	Integral time T_I (0 to 32.767 min., stop if $T_I = 0$)	Data range: 0.0 to 32.767
B+5·B+4	Derivative time T_D (0 to 32.767 min.)	Data range: 0.0 to 32.767
B+7·B+6	Gap (dead-band) GP (0 to 10 %)	Data range: 0.0 to 10.0
B+9·B+8	Auto mode initial set value ISV (0 to 100 %)	Data range: 0.0 to 100.0
B+11·B+10	Input filter constant FT (0 to less than 1)	Data range: 0.0 to less than 1.0
B+13·B+12	ASV differential limit DSV (0 to 100 %/Δt)	Data range: 0.0 to 100.0
B+15·B+14	MMV differential limit DMMV (0 to 100 %/Δt)	Data range: 0.0 to 100.0

B+17·B+16 Initial status STS



B+19·B+18	MV upper limit MH (-25 to 125 %)	Data range: -25.0 to 125.0
B+21·B+20	MV lower limit ML (-25 to 125 %)	Data range: -25.0 to 125.0
B+23·B+22	MV differential limit DMV (0 to 100 %/Δt)	Data range: 0.0 to 100.0
B+25·B+24	Control interval setting n (1 to 32767 times) Executes PID every n scan. Therefore, control interval Δt = n × constant scan interval (It is treated as n = 1 when n ≤ 0)	Data range: 1.0 to 32767.0

C+1·C	Manipulation value MV (-25 to 125 %)	Data range: -25.0 to 125.0
C+3·C+2 to *C+15·C+14*	Internal work area	

Operation

1. When the instruction input is OFF:
   Initializes the FPID3 instruction.
   Operation mode is set as specified by B+17 · B+16.
   A+10 bit 0,1 ← *B+16* bit 0, 1
   Auto mode SV is set as specified by B+9 · B+8.
   ASV ← ISV
   Manual mode MV is set as current MV.
   MMV ← MV
   Internal calculation data is initialized.
   MV remains unchanged.

2. When the instruction input is ON:
   Executes PID calculation every n scan which is specified by *B+25·B+24*. The following operation modes are available according to the setting of *A+11·A+10*.

   - Auto mode
     This is a normal PID control mode with ASV as set value. Set value differential limit DSV, manipulation value upper/lower limit MH/ML and differential limit DMV are effective.
     Bump-less changing from auto mode to manual mode is available. (Manual mode manipulation value MMV is over-written by current MV automatically. MMV ← MV)

- Manual mode
  In this mode, the manipulation value MV can be directly controlled by the input value of MMV.
  MV differential limit for manual mode DMMV is effective. MH/ML and DMV are not effective.
  When mode is changed from manual to auto or cascade, the operation is started from the current MV.

- Cascade mode
  This is a mode for PID cascade connection. PID is executed with CSV as set value.
  Different from the auto mode, set value differential limit is not effective. Manipulation value upper/lower limit MH/ML and differential limit DMV are effective.
  Bump-less changing from cascade mode to manual mode is available. (Manual mode manipulation value MMV is over-written by current MV automatically. MMV ← MV)
  And, bump-less changing from cascade mode to auto mode is available. (Auto mode set value ASV is over-written by current CSV automatically. ASV ← CSV)

- MV tracking
  This function is available in auto and cascade modes. When the tracking designation (A+5 bit 2) is ON, tracking input TMV is directly output as MV.
  Manipulation value upper/lower limit MH/ML is effective, but differential limit DMV is not effective.
  When the tracking designation is changed to OFF, the operation is started from the current MV.

NOTE

- PID3 instruction is only usable on the main-program.
- PID3 instruction must be used under the constant scan mode. The constant scan interval can be selected in the range of 10 to 200 ms, 10 ms increments.
- The data handled by the PID3 instruction are % units. Therefore, process input value PVC, manipulation value MV, etc., should be converted to % units (scaling), before and/or after the PID3 instruction.

5.6.4 Expanded data transfer (XFER)

FUN 236	XFER	Expanded data transfer

Expression

Input —[*A* XFER *B* → *C*]— Output

Function

When the input is ON, data block transfer is performed between the source which is indirectly designated by *A* and *A+1* and the destination which is indirectly designated by *C* and *C+1*. The transfer size (number of words) is designated by *B*.
The transfer size is 1 to 256 words. (except for writing into flash memory)
Data transfer between the following objects are available.

- CPU register ↔ CPU register
- CPU register ↔ Expanded F register
- CPU register ↔ TOSLINE-S20 or TOSLINE-S20LP (here called S20 or S20LP)
- CPU register ↔ Flash memory (D register)

Execution condition

Input	Operation	Output	ERF
OFF	No execution	OFF	—
ON	Normal execution	ON	—
	When error is occurred (see Note)	ON	Set

Operand

	Name	Device										Register															Con-stant	Index
		X	Y	S	L	R	Z	T.	C.	I	O	X W	Y W	S W	L W	R W	W	T	C	D	F	I W	O W	I	J	K		
A	Source parameter											√	√	√	√	√	√	√	√	√	√							√
B	Transfer size											√	√	√	√	√	√	√	√	√	√							√
C	Destination parameter												√	√	√	√	√	√	√	√	√							√

Source parameter

A	Bank / CH	Type
A+1	Leading address	

Transfer size and status

B	Transfer size
B+1	Status flag (Scan healthy map)
B+16	Max. 16 words

Destination parameter

C	Bank / CH	Type
C+1	Leading address	

- Refer to the following table for contents of each designation.
- The status flag is created only when the transfer from S20 to Register.

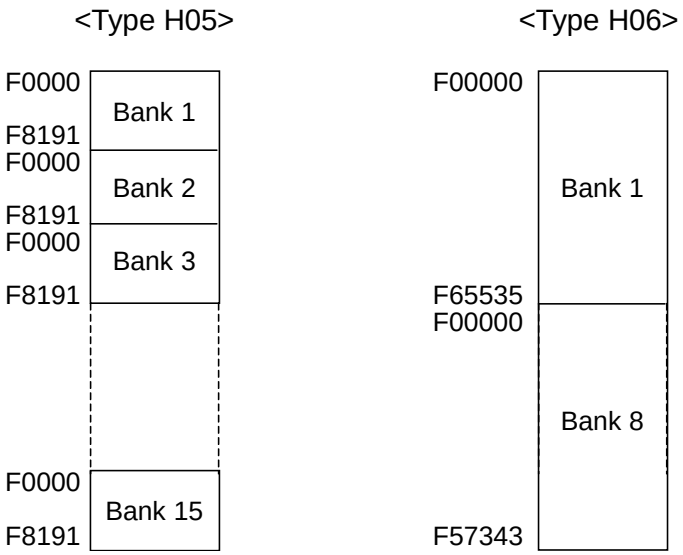
Transfer parameter table

Transfer object		Bank / CH	TYPE	Leading address	Transfer size	Status flag
CPU register	XW/YW register	0	H00	0 to 511	1 to 256	None
	W register	0	H01	0 to 2047	1 to 256	None
	LW register	0	H02	0 to 255	1 to 256	None
	RW register	0	H03	0 to 999	1 to 256	None
	D register	0	H04	0 to 8191	1 to 256	None
	F register	0	H05	0 to 32767	1 to 256	None
Expanded F register*1		1 to 15	H05	0 to 8191	1 to 256	None
		1 or 2	H06	0 to 65535 (bank 1~7) 0 to 57343 (bank 8)	1 to 256	None
S20 scan memory		1 or 2*2	H10	0 to 1023	1 to 256	Yes*2
S20LP scan memory		1 or 2	H10	0 to 4095	1 to 256	None
EEPROM (D register)		0	H20	0 to 8191	Source (read) 1 to 256	None
					Destination (write) 1 to 128	

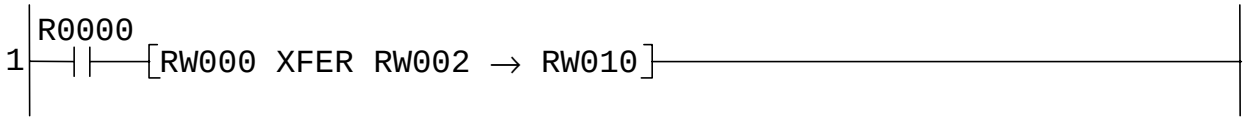
*1) Two format types of the expand memory is available. They are 8 k words/bank (type: H05) and 64 k words/bank (type: H06). Type H06 is available only in the S2T.
*2) The status flag is created only when S20 is designated as transfer source.

CPU register ↔ Expanded F register

Expanded F register configuration:



Example



Source designation

RW000	H00	H04
RW001	00000	

D0000 (CPU register)

Transfer size

RW002	00045

45 words transfer

Destination designation

RW010	H01	H05
RW011	00000	

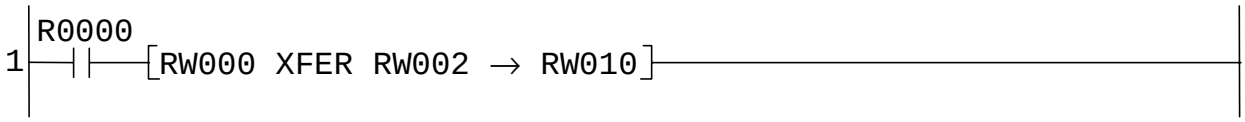
Bank 1 F0000 (Expanded F register)

When R0000 is ON, 45 words data starting with D0000 is transferred to Bank 1 F0000 and after in the expand memory.

Remark: When type H06 is used in the S2T, the expanded F register can be accessed as F00000 to F65535 (bank 1 ~ 7) and F00000 to F57343 (bank 8).

CPU register ↔ S20/S20LP scan memory

Example

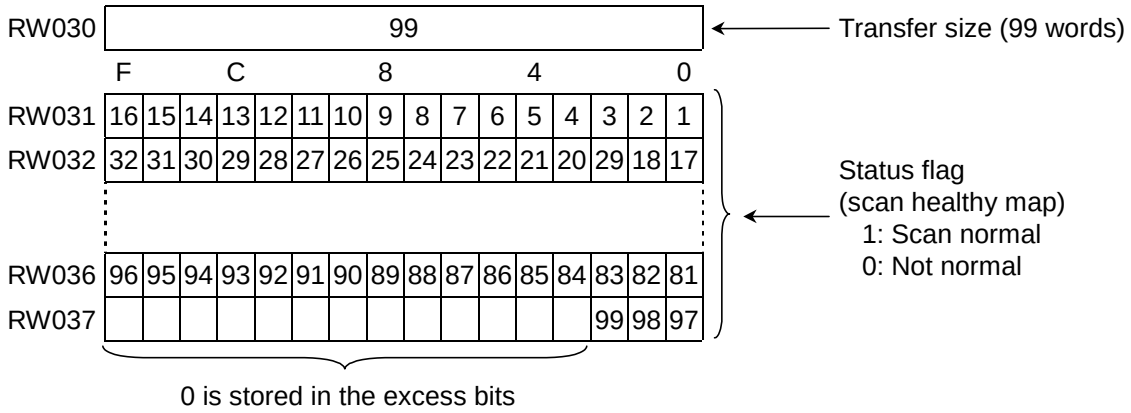


Source designation			Transfer size		Destination designation		
RW000	H00	H01	RW002	00010	RW010	H01	H10
RW001	00000				RW011	00000	
W0000 (CPU register)			10 words transfer		Channel 1 S20/S20LP scan memory address 00000		

When R0000 is ON, 10 words data starting with W0000 is transferred to scan memory address 00000 and after of channel 1 S20/S20LP.

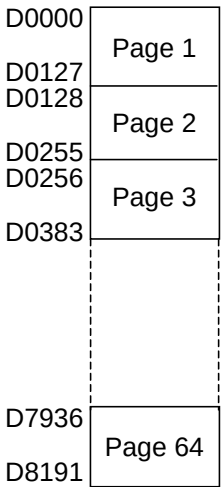
Remarks:

- When writing data into S20/S20LP scan memory, confirm that the address range is S20/S20LP's data send block.
- If S20/S20LP scan memory is accessed only by this XFER instruction, the network assignment, i.e. "LINK" or "GLOBAL" setting, is not necessary.
- When S20 is designated as source, the status flag (scan healthy map) for the read-out data is stored in operand B+1 and after. (Status flag is not created for S20LP)
  For example, when 99 words data is read from S20 with using RW030 as transfer size designation, RW031 to RW037 (7 words) are used to store the scan healthy map.

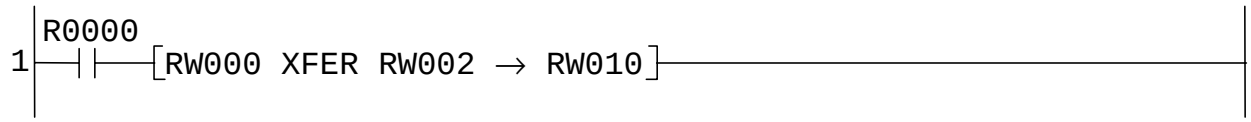


CPU register ↔ Flash Memory (D register)

Flash Memory D register configuration:



Example



Source designation		
RW000	H00	H04
RW001	00100	

D0100 (CPU register)

Transfer size	
RW002	00032

32 words transfer

Destination designation		
RW010	H00	H20
RW011	00064	

D0064 (flash memory)

When R0000 is ON, 32 words data starting with D0100 is transferred to D0064 and after in the flash memory. (Data write into flash memory)

Remark:

- Flash memory is internally divided by page.
- Writing data into the flash memory is available within one page at a time.
- For data reading from the flash memory, there is no need to consider the pages.
- The flash memory has a life limit for data writing into an address. It is 100,000 times. Pay attention not to exceed the limit. (flash memory alarm flag = S0007 is not updated by executing this instruction)
- Once data writing into the flash memory is executed, flash memory access (read/write) is prohibited for the duration of 10 ms. Therefore, minimum 10 ms interval is necessary for data writing.

NOTE

- Edge execution modifier is also available for this instruction.
- The XFER instruction is not executed as error in the following cases. (ERF = S0051 is set to ON)

Transfer	Error cause
Between CPU registers	1) When the transfer size is 0 or more than 256. 2) When the source/destination table of transfer is out of the valid ranqe.
CPU register to expanded F register	1) When the transfer size is 0 or more than 256. 2) When the source/destination table of transfer is out of the valid range. 3) When the PU662T module.
CPU register to S20/S20LP	1) When the transfer size is 0 or more than 256. 2) When the source/destination table of transfer is out of the valid range. 3) When channel designation is other than 1 or 2. (other than 1 for T2) 4) When S20/S20LP is not installed or not allocated. 5) When status flag area is not sufficient. 6) When an odd address is designated as the leading address in the case of S20/S20LP is set as double-word access. 7) When the transfer size is odd address in the case of S20/S20LP is set as double-word access. 8) When the S20/S20LP module is not normal.
CPU register to EEPROM	1) When the transfer size is 0 or more than 256. 2) When the source/destination table of transfer is out of the valid range. 3) When the data writing address range exceeds page boundary. 4) When this instruction is executed during flash memory access inhibited (10 ms). 5) When the CPU does not have flash memory.
Others	1) When source/destination designation is invalid. 2) When an invalid transfer combination is designated. 3) When the index modification is used for an operand and register boundary error is occurred as the result of the index modification. (in this case, the instruction output comes OFF)

5.6.5 Network data send (SEND)

FUN 239	SEND	Network data send

Expression

Input —[*A* SEND *B*]— Output

Function

This instruction sends the designated range of register data to another S2T through the network. (Network: TOSLINE-S20LP or Ethernet)
The transfer source register (self-station) is designated by *A+3* and *A+4*.
The transfer destination register (target-station) is designated by *A+5* and *A+6*.
The transfer size (number of words) is designated by *A+2*. The maximum transfer size is 128 words (S20LP), or 485 words (Ethernet).
The designation method of the target-station is different between S20LP and Ethernet.

Execution condition

Input	Operation	Output	ERF
OFF	No execution	OFF	—
ON	During execution	OFF	—
	Normal complete	ON	—
	When error is occurred (see Note)	ON	Set

Operand

	Name	Device										Register															Con-stant	Index
		X	Y	S	L	R	Z	T.	C.	I	O	XW	YW	SW	LW	RW	W	T	C	D	F	IW	OW	I	J	K		
A	Transfer parameter											√	√	√	√	√	√	√	√	√	√							√
B	Status												√	√	√	√	√	√	√	√	√							√

<In case of S20LP>

	F C B 8 7 0		
A	MID	CH	Target station No.
A+1	0 (fixed)		
A+2	Transfer size		
A+3	Register type (self-station)		
A+4	Leading address (self-station)		
A+5	Register type (target-station)		
A+6	Leading address (target-station)		
A+7	Response time limit		

<In case of Ethernet>

	F C B 8 7 0		
A	MID	CH	0 (fixed)
A+1	Request command		
A+2	Transfer size		
A+3	Register type (self-station)		
A+4	Leading address (self-station)		
A+5	Register type (target-station)		
A+6	Leading address (target-station)		
A+7	Response time limit		
A+8	Target-station IP address		
A+9			
A+10	Target-station UDP port No.		

NOTE

Parameters for the Ethernet varies depending on the request command. Above figure shows the parameters for the register read/write command (H0021).

	F	E	D	C	B	8	7	0
B	Abn	Busy	Status		0		TermSTS	
B+1	Transmission error information (if TermSTS is H0B)							

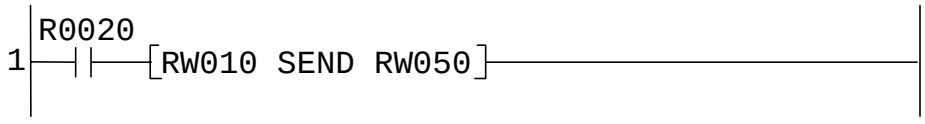
Inside the parameter:

Transfer parameter	S20LP	Ethernet
MID (network type)	2	3
CH (channel of self-station)	1 or 2 (max. two S20LP's on S2T)	1 to 4 (max. four EN611/EN631's on S2T)
Target station No.	1 to 64	0 (fixed)
Request command	0 (fixed)	H0021: Register read/write
Transfer size (number of words)	1 to 128 (max. 84 words for T or C register) (designation across T511 and T512 is not allowed)	1 to 485 (max. 323 words for T or C register) (designation across T511 and T512 is not allowed)
Register type	H0000: XW/YW register H0001: W register H0002: LW register H0003: RW register H0004: D register H0005: F register (CPU) H∗∗05: Expanded F register (expand memory, 8k words/bank, ∗∗ is bank No. 01 - 0F) H∗∗06: Expanded F register (expand memory, 64 words/bank, ∗∗ is bank No. 01 - 08) H0007: T register H0008: C register H0009: SW register	
Leading address	Designates the leading register address to be transferred	
Response time limit	Specifies the time limit of the response from target-station. (0.1 s units) When the bit F is set to ON, the following default value is used. S20LP ..... 4.1 s Ethernet ..... 30 s	
Target-station IP address	N/A	Designates the IP address of the target-station
Target-station UDP port No.	N/A	Designates the UDP port No. of the target-station

Inside the parameter (cont'd):

Status	S20LP	Ethernet
Abn	0: Normal complete 1: Error complete	
Busy	0: Initial state 1: Transmission port busy	
Status	0: Initial state 1: While send requesting 2: While waiting response 3: Complete	
TermSTS	H00: Normal complete H01: Register designation error H02: Response time-out H03: Parameter error H04: Register write protect H05: (Reserve) H06: Module error (send time-out) H07: No send channel H08: Invalid station No. H09: Transfer size error H0A: Boundary error H0B: Transmission error H0C: I/O no answer error H0D: expand memory designation error H0E: (Reserve) H0F: (Reserve)	Bit 7 indicates the error is occurred whether self-station or target-station. 0: Self-station 1: Target-station
Transmission error information	When TermSTS is H0B, the error information is stored. (0 for other cases) For detailed information, refer to the S20LP or EN311 manual.	

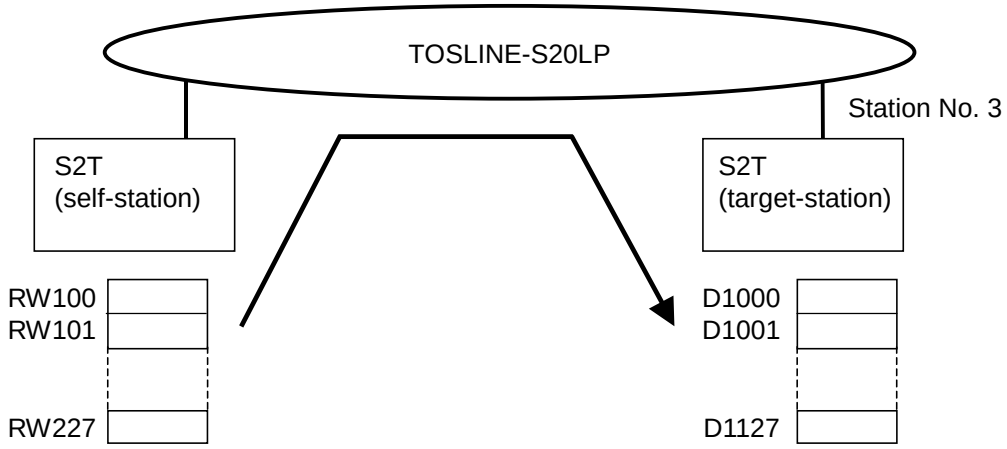
Example



RW010	2	1	3	S20LP, channel 1, target station No. is 3
RW011	0			
RW012	128			Transfer size: 128 words
RW013	3			Self-station RW register
RW014	100			Leading address: RW100
RW015	4			Target-station D register
RW016	1000			Leading address: D1000
RW017	10			Response time limit: 1 second

Send requesting

RW050	0	0	1	0	0
RW051	0				

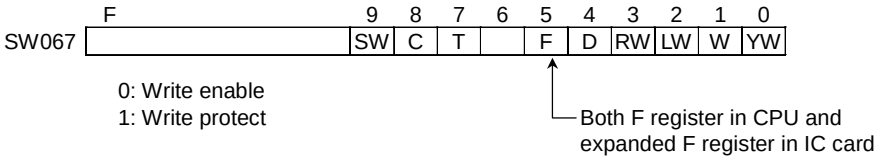


When R0020 is ON, 128 words data starting with RW100 is transferred to D1000 and after of the S2T on which station No. 3 S20LP is installed. When the operation is completed, the status is set in RW050 and instruction output comes ON.

NOTE

- Keep the input ON until the output comes ON.
- This instruction becomes error complete in the following cases. (ERF = S0051 is set to ON)
  (1) Target station No. is invalid. (for S20LP)
  (2) Invalid register designation. (In case of T and C registers, T → T and C → C is only possible)
  (3) Source/destination register address range is out of valid range.
  (4) Destination register is write-protected.
  (5) Response time-out is occurred.

- By using SW067, register write-protect is available against SEND instruction of other S2T.



- Resetting the status register (operand *B*) is necessary at the first scan.

- When using the TOSLINE-S20LP or Ethernet module (EN611/EN631), read the manual for these network modules.

5.6.6 Network data receive (RECV)

FUN 240	RECV	Network data receive

Expression

Input —[*A* RECV *B*]— Output

Function

This instruction reads the designated range of register data from another S2T through the network.
(Network: TOSLINE-S20LP or Ethernet)
The transfer source register (target-station) is designated by *A+5* and *A+6*.
The transfer destination register (self-station) is designated by *A+3* and *A+4*.
The transfer size (number of words) is designated by *A+2*. The maximum transfer size is 128 words (S20LP), or 485 words (Ethernet).
The designation method of the target-station is different between S20LP and Ethernet.

Execution condition

Input	Operation	Output	ERF
OFF	No execution	OFF	—
ON	During execution	OFF	—
	Normal complete	ON	—
	When error is occurred (see Note)	ON	Set

Operand

	Name	Device										Register														Con-stant	Index
		X	Y	S	L	R	Z	T.	C.	I	O	X W	Y W	S W	L W	R W	W	T	C	D	F	I W	O W	I	J	K		
A	Transfer parameter											√	√	√	√	√	√	√	√	√	√							√
B	Status												√	√	√	√	√	√	√	√	√							√

<In case of S20LP>

	F C B 8 7 0		
A	MID	CH	Target station No.
A+1	0 (fixed)		
A+2	Transfer size		
A+3	Register type (self-station)		
A+4	Leading address (self-station)		
A+5	Register type (target-station)		
A+6	Leading address (target-station)		
A+7	Response time limit		

<In case of Ethernet>

	F C B 8 7 0		
A	MID	CH	0 (fixed)
A+1	Request command		
A+2	Transfer size		
A+3	Register type (self-station)		
A+4	Leading address (self-station)		
A+5	Register type (target-station)		
A+6	Leading address (target-station)		
A+7	Response time limit		
A+8	Target-station IP address		
A+9			
A+10	Target-station UDP port No.		

NOTE

Parameters for the Ethernet varies depending on the request command. Above figure shows the parameters for the register read/write command (H0021).

	F	E	D	C	B	8	7	0
B	Abn	Busy	Status		0		TermSTS	
B+1	Transmission error information (if TermSTS is H0B)							

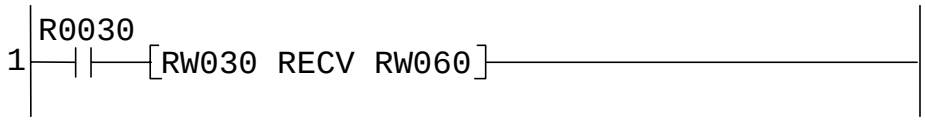
Inside the parameter:

Transfer parameter	S20LP	Ethernet
MID (network type)	2	3
CH (channel of self-station)	1 or 2 (max. two S20LP's on S2T)	1 to 4 (max. four EN611/EN631's on S2T)
Target station No.	1 to 64	0 (fixed)
Request command	0 (fixed)	H0021: Register read/write
Transfer size (number of words)	1 to 128 (max. 84 words for T or C register) (designation across T511 and T512 is not allowed)	1 to 485 (max. 323 words for T or C register) (designation across T511 and T512 is not allowed)
Register type	H0000: XW/YW register H0001: W register H0002: LW register H0003: RW register H0004: D register H0005: F register (CPU) H∗∗05: Expanded F register (expand memory, 8k words/bank, ∗∗ is bank No. 01 - 0F) H∗∗06: Expanded F register (expand memory, 64 words/bank, ∗∗ is bank No. 01 - 02) H0007: T register H0008: C register H0009: SW register	
Leading address	Designates the leading register address to be transferred	
Response time limit	Specifies the time limit of the response from target-station. (0.1 s units) When the bit F is set to ON, the following default value is used. S20LP ..... 4.1 s Ethernet ..... 30 s	
Target-station IP address	N/A	Designates the IP address of the target-station
Target-station UDP port No.	N/A	Designates the UDP port No. of the target-station

Inside the parameter (cont'd):

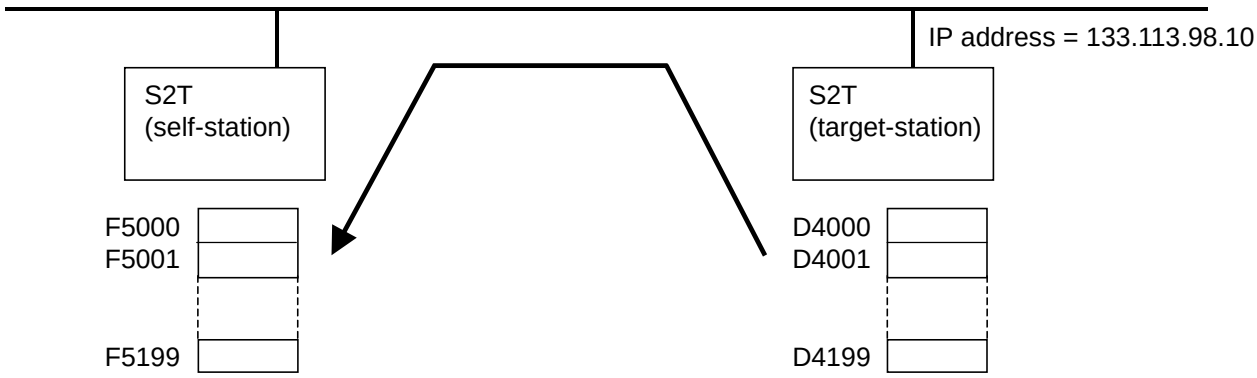
Status	S20LP	Ethernet
Abn	0: Normal complete 1: Error complete	
Busy	0: Initial state 1: Transmission port busy	
Status	0: Initial state 1: While send requesting 2: While waiting response 3: Complete	
TermSTS	H00: Normal complete H01: Register designation error H02: Response time-out H03: Parameter error H04: Register write protect H05: (Reserve) H06: Module error (send time-out) H07: No send channel H08: Invalid station No. H09: Transfer size error H0A: Boundary error H0B: Transmission error H0C: I/O no answer error H0D: expand memory designation error H0E: (Reserve) H0F: (Reserve)	Bit 7 indicates the error is occurred whether self-station or target-station. 0: Self-station 1: Target-station
Transmission error information	When TermSTS is H0B, the error information is stored. (0 for other cases) For detailed information, refer to the S20LP or EN311 manual.	

Example



RW030	3	1	0	Ethernet, channel 1
RW031	33 (H21)			Request command H21: Register read/write
RW032	200			Transfer size: 200 words
RW033	5			Self-station F register
RW034	5000			Leading address: F5000
RW035	4			Target-station D register
RW036	4000			Leading address: D4000
RW037	50			Response time limit: 5 second
RW038	H62		H0A	Target-station IP address:
RW039	H85		H71	133.113.98.10 = H85.H71.H62.H0A
RW040	1024			Target-station UDP port No.: 1024

RW060	0	0	1	0	0	Send requesting
RW061	0					

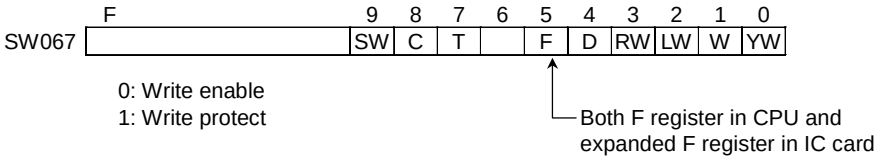


When R0030 is ON, 200 words data starting with D4000 of the S2T on which EN611/EN631 (IP address = 133.113.98.10) is installed, is read and stored in F5000 and after.
When the operation is completed, the status is set in RW060 and instruction output comes ON.

NOTE

- Keep the input ON until the output comes ON.
- This instruction becomes error complete in the following cases. (ERF = S0051 is set to ON)
  (1) Target station No. is invalid. (for S20LP)
  (2) Invalid register designation. (In case of T and C registers, T → T and C → C is only possible)
  (3) Source/destination register address range is out of valid range.
  (4) Destination register is write-protected.
  (5) Response time-out is occurred.

- By using SW067, self-station's register write-protect is available.



- Resetting the status register (operand *B*) is necessary at the first scan.

- When using the TOSLINE-S20LP or Ethernet module (EN611/EN631), read the manual for these network modules.

5.7 List of instructions

An instruction list is given in the sequence of ladder diagram instructions and SFC instructions on the next page and thereafter.

The groups in the list correspond to the group classifications of function instructions used in the programmer (T-PDS). (Except for SFC).

The required numbers of steps signify the size of memory required for storing these instructions. The showing of the required number of steps by a range such as 4-7, is because the number of steps changes due to the following conditions, even for the same instruction.

- When using digit designation, there is an increase of 1 step per 1 operand.
- When a constant is used in a double-length operand, there is an increase of 1 step.
- When executing index modification in a constant, there is an increase of 1 step.

The minimum execution time figure shows normal case value, i.e. when no index modification, no digit designation and normal registers are used for each operand.

The maximum execution time figure shows worst case value, i.e. when direct input/output registers (IW/OW) are used for each operand, etc.

NOTE

Here, an overview of each instruction is given. See the instruction set manual in a separate volume for details.

Ladder Diagram Instructions (Sequence Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Sequence instructions		NO contact	(A) ⊣ ⊢	NO contact of device (A) (contact normally open)	1	0.09
		NC contact	(A) ⊣/⊢	NC contact of device (A) (contact normally closed)	1	0.09
		Transitional contact (rising)	⊣↑⊢	Switches output ON only when input in the previous scan is OFF and the input in this scan is ON.	1	0.36
		Transitional contact (falling)	⊣↓⊢	Switches output ON only when input in the previous scan is ON and input in this scan is OFF.	1	0.36
		Coil	(A) ⊣( )⊢	Switches device (A) ON when input is ON.	1	0.18
		Forced coil	(A) ⊣*( )⊢	Retains state of device (A) regardless of whether input is ON or OFF.	1	0.09
		Inverter	(A) ⊣I⊢	Inverts the input state	1	0.09
		Invert coil	(A) ⊣(I)⊢	Inverts the input state and stores in device (A).	1	0.18
		Positive Transition-sensing contact	(A) ⊣P⊢	Turns output ON for 1 scan when input is ON and device (A) is changed from OFF to ON.	1	0.36
		Negative Transition-sensing contact	(A) ⊣N⊢	Turns output ON for 1 scan when input is ON and device (A) is changed from ON to OFF.	1	0.36
		Positive Transition-sensing coil	(A) ⊣(P)⊢	Turns device (A) ON for 1 scan when input is changed from OFF to ON.	1	0.36
		Negative Transition-sensing coil	(A) ⊣(N)⊢	Turns device (A) ON for 1 scan when input is changed from ON to OFF.	1	0.36
		Jump control set	⊣[JCS]⊢	Carries out high-speed skipping on instructions between JCS and JCR when input is ON.	1	0.09
		Jump control reset	⊢[JCR]⊢		1	0.09
		End	⊢[END]⊢	Indicates end of main program and sub-program.	1	—

Ladder Diagram Instructions (Sequence Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Sequence instructions		ON delay timer	—[(A) TON (B)]—	Turns output ON when set period specified by (A) has elapsed since input came ON. (B) is timer register.	2	0.18
		OFF delay timer	—[(A) TOF (B)]—	Turns output OFF when set period specified by (A) has elapsed since input went OFF. (B) is timer register.	2	0.18
		Single shot timer	—[(A) SS (B)]—	Turns output ON only for the set period, specified by (A), starting when input comes ON. (B) is timer register.	2	0.18
		Counter	—[C CNT Q —[E (A) (B)]—	When enable input (E) is ON, counts the number of times the count input (C) has come ON. When count value becomes equal to set value specified by (A), turns output (Q), ON. (B) is counter register.	2	0.18
		Master control set	—[MCS]—	Turns ON power rail between MCS and MCR when MCS input is ON.	1	0.09
		Master control reset	—[MCR]—		1	0.09
	134	Master control set (with nesting number)	—[MCSn]—	Turns ON power rail to corresponding MCR when MCS input is ON. n is a nesting number. (1 - 7).	2	4.9
	135	Master control reset (with nesting number)	—[MCRn]—		2	4.9
	148	Timer trigger	—[TRG (A)]—	When input is changed from OFF to ON, clears timer register specified by (A) and activates timer.	2	2.89

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Transfer instructions	18	Data transfer	—[(A) MOV (B)]—	Transfers contents of (A) to (B).	3~5	0.54
	19	Double-length data transfer	—[(A)+1·(A) DMOV (B)+1·(B)]—	Transfers contents of (A)+1 and (A) to (B)+1 and (B).	3~6	4.14
	20	Invert and transfer	—[(A) NOT (B)]—	Transfers the bit-reversed data comprising the contents of (A) to (B).	3~5	3.6
	21	Double-length invert and transfer	—[(A)+1·(A) DNOT (B)+1·(B)]—	Transfers the bit-reversed data comprising the contents of (A)+1 and (A) to (B) +1 and (B).	3~6	4.32
	22	Data exchange	—[(A) XCHG (B)]—	Exchanges the contents of (A) with the contents of (B).	3~5	6.12
	23	Double-length data exchange	—[(A)+1·(A) DXCH (B)+1·(B)]—	Exchanges the contents of (A)+1·(A) with the contents of (B)+1·(B).	3~5	7.56
	24	Table initialization	—[(A) TINZ (n) (B)]—	Initializes the contents of the table of size n, headed by (B), by the contents of (A).	4~6	15.5+0.37n
	25	Table transfer	—[(A) TMOV (n) (B)]—	Transfers the contents of the table of size n, headed by (A), to the table headed by (B).	4~6	24.32+0.49n
	26	Table invert and transfer	—[(A) TNOT (n) (B)]—	Transfers the bit-reversed data comprising the contents of the table of size n headed by (A) to the table headed by (B).	4~6	24.44+0.58n
Arithmetic operations	27	Addition	—[(A) + (B) → (C)]—	Adds the contents of (B) to the contents of (A), and stores the result in (C).	4~7	0.9
	28	Subtraction	—[(A) - (B) → (C)]—	Subtracts the contents of (B) from the contents of (A), and stores the result in (C).	4~7	0.9
	29	Multiplication	—[(A) * (B) → (C)+1·(C)]—	Multiplies the contents of (A) by the contents of (B) and stores the result in (C) + 1·(C).	4~7	1.08
	30	Division	—[(A) / (B) → (C)]—	Divides the contents of (A) by the contents of (B), stores the quotient in (C), and the remainder in (C)+1.	4~7	4.59
	31	Double-length addition	—[(A)+1·(A) D+ (B)+1 ·(B) → (C)+1·(C)]—	Adds the contents of (B)+1·(B) to the contents of (A)+1·(A), and stores the result in (C)+1·(C).	4~9	6.1
	32	Double-length subtraction	—[(A)+1·(A) D- (B)+1·(B) → (C)+1·(C)]—	Subtracts the contents of (B)+1·(B) from the contents of (A)+1·(A), and stores the result in (C)+1·(C).	4~9	6.1

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Arithmetic operations	33	Double-length multiplication	—[(A)+1·(A) D * (B)+1·(B) → (C)+1·(C)]—	Multiplies the contents of (A)+1·(A) by the contents of (B)+1·(B), and stores the result in (C)+3·(C)+2·(C)+1·(C).	4~9	6.22
	34	Double-length division	—[(A)+1·(A) D/ (B)+1·(B) → (C)+1·(C)]—	Divides the contents of (A)+1·(A) by the contents of (B)+1·(B), and stores the quotient in (C)+1·(C) and the remainder in (C)+3·(C)+2.	4~9	9.85
	35	Addition with carry	—[(A) +C (B) → (C)]—	Adds the contents of the carry flag and the contents of (B) to the contents of (A), and stores the result in (C). The carry flag changes according to the operation result.	4~7	6.29
	36	Subtraction with carry	—[(A) -C (B) → (C)]—	Subtracts the contents of (B) and the contents of the carry flag from the contents of (A), and stores the result in (C). The carry flag changes according to the operation result.	4~7	6.29
	37	Double-length addition with carry	—[(A)+1·(A) D+C (B)+1·(B) → (C)+1·(C)]—	Adds the contents of the carry flag to the contents of (A)+1·(A) and the contents of (B)+1·(B), and stores the result in (C)+1·(C). The carry flag chances according to the operation result.	4~9	7.21
	38	Double-length subtraction with carry	—[(A)+1·(A) D-C (B)+1·(B) → (C)+1·(C)]—	Subtracts the contents of (B)+1·(B) plus the contents of the carry flag from the contents of (A)+1·(A), and stores the result in (C)+1·(C). The carry flag changes according to the operation result.	4~9	7.21
	39	Unsigned multiplication	—[(A) U * (B) → (C)+1·(C)]—	Multiplies the contents of (A) by the contents of (B), and stores the result in (C)+1·(C) (unsigned integer calculation).	4~7	7.37
	40	Unsigned division	—[(A) U/ (B) → (C)]—	Divides the contents of (A) by the contents of (B), and stores the quotient in (C), and the remainder in (C)+1 (unsigned integer operation).	4~7	7.77
	41	Unsigned double/single division	—[(A)+1·(A) DIV (B) → (C)]—	Divides the contents of (A)+1·(A) by the contents of (B), stores the quotient in (C), and the remainder in (C)+1 (unsigned integer operation).	4~8	8.67
	43	Increment	—[+1 (A)]—	Increments the contents of (A) by 1.	2~3	3.23
	44	Double-length increment	—[D+1 (A)+1·(A)]—	Increments the contents of (A)+1·(A) by 1.	2~3	4.11
	45	Decrement	—[-1 (A)]—	Decrements the contents of (A) by 1.	2~3	3.23
	46	Double-length decrement	—[D-1 (A)+1·(A)]—	Decrements the contents of (A)+1·(A) by 1.	2~3	4.11

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Arithmetic operations	208	Floating point addition	—[(A)+1·(A) F+ (B)+1·(B) → (C)+1·(C)]—	Adds the floating point data of (A)+1·(A) and (B)+1·(B), and stores the result in (C)+1·(C).	4	14.4
	209	Floating point subtraction	—[(A)+1·(A) F- (B)+1·(B) → (C)+1·(C)]—	Subtracts the floating point data of (B)+1·(B) from (A)+1·(A), and stores the result in (C)+1·(C).	4	14.82
	210	Floating point multiplication	—[(A)+1·(A) F* (B)+1·(B) → (C)+1·(C)]—	Multiplies the floating point data of (A)+1·(A) by (B)+1·(B), and stores the result in (C)+1·(C).	4	12.08
	211	Floating point division	—[(A)+1·(A) F/ (B)+1·(B) → (C)+1·(C)]—	Divides the floating point data of (A)+1·(A) by (B)+1·(B), and stores the result in (C)+1·(C).	4	12.06
Logical operations	48	AND	—[(A) AND (B) → (C)]—	Finds the logical AND of (A) and (B) and stores it in (C).	4~7	4.84
	49	Double-length AND	—[(A)+1·(A) DAND (B)+1·(B)→(C)+1·(C)]—	Finds the logical AND of (A)+1·(A) and (B)+1·(B) and stores it in (C)+1·(C).	4~9	5.92
	50	OR	—[(A) OR (B) → (C)]—	Finds the logical OR of (A) and (B) and stores in (C).	4~7	4.84
	51	Double-length OR	—[(A)+1·(A) DOR (B)+1·(B) → (C)+1·(C)]—	Finds the logical OR of (A)+1·(A) and (B)+1·(B) and stores it in (C)+1·(C).	4~9	5.92
	52	Exclusive OR	—[(A) EOR (B) → (C)]—	Finds the exclusive logical OR of (A) and (B) and stores it in (C).	4~7	4.84
	53	Double-length exclusive OR	—[(A)+1·(A) DEOR (B)+1·(B)→(C)+1·(C)]—	Finds the exclusive logical OR of (A)+1·(A) and (B)+1·(B) and stores it in (C)+1·(C).	4~9	5.92
	54	Not exclusive OR	—[(A) ENR (B) → (C)]—	Finds the negative exclusive OR of (A) and (B) and stores it in (C).	4~7	4.84
	55	Double-length Not exclusive OR	—[(A)+1·(A) DENR (B)+1·(B)→(C)+1·(C)]—	Finds the negative exclusive OR of (A)+1·(A) and (B)+1·(B) and stores it in (C)+1·(C).	4~9	5.92

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Logical operations	57	Table AND	—[(A) TAND (n) (B) → (C)]—	Finds the logical AND of the table of size n headed by (A) and the table of size n headed by (B), and stores it in the location headed by (C).	5	23.31+0.72n
	58	Table OR	—[(A) TOR (n) (B) → (C)]—	Finds the logical OR of the table of size n headed by (A) and the table of size n headed by (B), and stores it in the location headed by (C).	5	23.31+0.72n
	59	Table exclusive OR	—[(A) TEOR (n) (B) → (C)]—	Finds the exclusive OR of the table of size n headed by (A) and the table of size n headed by B), and stores it in the location headed by (C).	5	23.31+0.72n
	60	Table Not exclusive OR	—[(A) TENR (n) (B) → (C)]—	Finds the NOT exclusive OR of the table of size n headed by (A) and the table of size n headed by (B) and stores it in the location headed by (C).	5	23.31+0.72n
	64	Test	—[(A) TEST (B)]—	Turns the output ON if the logical AND of (A) and (B) is other than 0.	3~5	3.76
	65	Double-length test	—[(A)+1·(A) DTST (B)+1·(B)]—	Turns the output ON if the logical AND of (A)+1·(A) and (B)+1·(B) is other than 0.	3~7	4.68
	66	Bit file bit test	—[(A) TTST (n) (B)]—	Decides the ON/OFF state of the (A)th bit of the bit table size n headed by (B).	4~5	8.98
Shifts	68	1 bit shift right	—[SHR 1 (A)]—	Shifts the data in (A) 1 bit to the right (LSB direction) and stores the result in (A). The carry flag changes according to the result.	2~3	4.12
	69	1 bit shift left	—[SHL 1 (A)]—	Shifts the data in (A) 1 bit to the left (MSB direction) and stores the result in (A). The carry flag changes according to the result.	2~3	4.68
	70	n bit shift right	—[(A) SHR n → (B)]—	Shifts the data in (A) n bits to the right (LSB direction) and stores the result in (B). The carry flag changes according to the result.	4~6	4.77+0.27n
	71	n bit shift left	—[(A) SHL n → (B)]—	Shifts the data in (A) n bits to the left (MSB direction) and stores the result in (B). The carry flag changes according to the result.	4~6	5.33+0.27n

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Shift	72	m bit file n bits shift right	(A) TSHR (m) → (B)	When (B) is a register: Takes the m-word table headed by (B), and shifts it to the right (low address direction) by the number of words indicated by (A). When (B) is a device: Takes the m-bit file headed by (B), and shifts it to the right (LSB direction) by the number of bits indicated by (A). The carry flag changes according to the result.	4~5	26.8+0.23n
	73	m bit file n bits shift left	(A) TSHL (rn) → (B)	When (B) is a register: Takes the m-word table headed by (B), and shifts it to the left (high address direction) by the number of words indicated by (A). When (B) is a device: Takes the m-bit file headed by (B), and shifts it to the left (MSB direction) by the number of bits indicated by (A). The carry flag changes according to the result.	4~5	27.7+0.23n
	74	Shift register	D SR Q S (n) E (A)	If the enable input (E) is ON, then when the shift input (S) comes ON, the instruction takes the contents of the n devices headed by the device (A) and shifts them 1 bit to the left. The carry flag changes according to the result.	3	35.8+5.18n
	75	Bidirectional shift register	D DSR Q S (n) E L (A)	If the enable input (E) is ON, then when the shift input (S) comes ON, the instruction takes the contents of the n devices headed by the device (A) and shifts them 1 bit to the left or to the right (the shift direction depends on the state of the direction input (L)). The carry flag changes according to the result.	3	35.8+6.75n
	76	Device shift	SFT (A)	Takes the contents of the device ((A)-1) which immediately precedes the device (A), stores it in (A), and sets (A)-1 to 0.	2	30.2

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Rotate	78	1 bit rotate right	—[RTR 1 (A)]—	Rotates the data in (A) 1 bit to the right (LSB direction). The carry flag changes according to the result.	2~3	9.23
	79	1 bit rotate left	—[RTL 1 (A)]—	Rotates the data in (A) 1 bit to the left (MSB direction). The carry flag changes according to the result.	2~3	8.78
	80	n bits rotate right	—[(A) RTR n → (B)]—	Rotates the data in (A) n bits to the right (LSB direction). The carry flag changes according to the result.	4~6	11.5+0.23n
	81	n bits rotate left	—[(A) RTL n → (B)]—	Rotates the data in (A) n bits to the left (MSB direction). The carry flag changes according to the result.	4~6	10.8+0.23n
	82	m bit file n bits rotate right	—[(A) TRTR (m) (B)]—	When (B) is a register: Takes the table of m words, headed by (B), and rotates it to the right (low address direction) by the number of words specified by (A). --- When (B) is a device: Takes the bit file of m bits, headed by (B), and rotates it to the right (LSB direction) by the number of bits specified by (A). The carry flag changes according to the result.	4~5	30.6+2.25m
	83	m bit file n bits rotate left	—[(A) TRTL (m) (B)]—	When (B) is a register: Takes the table of m words, headed by (B), and rotates it to the left (high address direction) by the number of words specified by (A). --- When (B) is a device: Takes the bit file of m bits, headed by (B), and rotates it to the left (MSB direction) by the number of bits specified by (A). The carry flag changes according to the result.	4~5	30.6+2.25m
	84	1 bit rotate right with carry	—[RRC 1 (A)]—	Rotates the data in (A) 1 bit to the right (LSB direction) including the carry flag. The carry flag changes according to the result.	2~3	9.9

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Rotate	85	1 bit rotate left with carry	—[RLC1 (A)]—	Rotates the data in (A) 1 bit to the left (MSB direction) including the carry flag. The carry flag changes according to the result.	2~3	9.45
	86	n bits rotate right with carry	—[(A) RRC n → (B)]—	Rotates the data in (A) n bit to the left (LSB direction) including the carry flag, and stores the result in (B). The carry flag changes according to the result.	4~6	9.9+2.03n
	87	n bits rotate left with carry	—[(A) RLC n → (B)]—	Rotates the data in (A) n bit to the left (MSB direction) including the carry flag, and stores the result in (B). The carry flag changes according to the result.	4~6	11.3+1.8n

	88	m bit file n bits rotate right with carry	—[(A) TRRC (m) (B)]—	If (B) is a register:
				Takes the table of m words headed by (B) and rotates it to the right (low address direction) by the number of words indicated by (A). (Same as register specification in FUN82.)
				--- 	
				If (B) is a device:
				Takes the bit file of m bits headed by (B), including the carry flag, and rotates it to the right (LSB direction) by the number of bits indicated by (A). The carry flag changes according to the result.
					4~5	30.6+2.25m

	89	m bit file n bits rotate left with carry	—[(A) TRLC (m) (B)]—	If (B) is a register:
				Takes the table of m words headed by (B) and rotates it to the right (high address direction) by the number of words indicated by (A). (Same as register specification in FUN83.)
				--- 	
				If (B) is a device:
				Takes the bit file of m bits headed by (B), including the carry flag, and rotates it to the right (MSB direction) by the number of bits indicated by (A). The carry flag changes according to the result.
					4~5	30.6+2.25m

	90	Multiplexer	—[(A) MPX (n) (B) → (C)]—	Takes the contents of the (B)th register in the table of size n headed by the register (A), and stores them in the register (C).	5~6	29.3

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (µs)
Rotate	91	Demultiplexer	(A) DPX (n) (B) → (C)	Stores the contents of the register (A) in the (B)th register of the table of size n headed by the register (C).	5–6	25.9
	92	Table→bit transfer	(A) TBM (n) (B) → (C)	Takes the (B)th bit from the head of the table of size n words headed by the register (A) and stores it in the device (C).	5–6	36.1
	93	Bit→table transfer	(A) BTM (n) (B) → (C)	Takes the contents of the device (A) and stores them in the (B)th bit of the table of size n headed by the register (C).	5–6	32.7

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Compare	95	Bit file comparison	—[(A) TCMP (n) (B) → (C)]—	Compares the register tables starting from (A) and (B), and stores the non-matching bits in (C).	5	67.6+2.48n
	96	Greater than	—[(A) > (B)]—	Turns output ON if (A)>(B) (merger comparison).	3~5	6.75
	97	Greater than or equal	—[(A) >= (B)]—	Turns output ON if (A)≥(B) (merger comparison).	3~5	6.98
	98	Equal	—[(A) = (B)]—	Turns output ON if (A)=(B) (merger comparison).	3~5	6.98
	99	Not equal	—[(A) <> (B)]—	Turns output ON if (A)≠(B) (merger comparison).	3~5	6.98
	100	Less than	—[(A)< (B)]—	Turns output ON if (A)<(B) (merger comparison).	3~5	6.98
	101	Less than or equal	—[(A) <= (B)]—	Turns output ON if (A)≤(B) (merger comparison).	3~5	6.98
	102	Double-length greater than	—[(A)+1·(A) D> (B)+1·(B)]—	Turns output ON if (A)+1·(A)>(B)+1·(B) (double-length integer comparison).	3~7	8.33
	103	Double-length greater than or equal	—[(A)+1·(A) D>= (B)+1·(B)]—	Turns output ON if (A)+1·(A)≥(B)+1·(B) (double-length integer comparison).	3~7	8.1
	104	Double-length equal	—[(A)+1·(A) D= (B)+1·(B)]—	Turns output ON if (A)+1·(A)=(B)+1·(B) (double-length integer comparison).	3~7	8.33
	105	Double-length not equal	—[(A)+1·(A) D<> (B)+1·(B)]—	Turns output ON if (A)+1·(A)≠(B)+1·(B) (double-length integer comparison).	3~7	8.33
	106	Double-length less than	—[(A)+1·(A) D< (B)+1·(B)]—	Turns output ON if (A)+1·(A)<(B)+1·(B) (double-length integer comparison).	3~7	8.33
	107	Double-length less than or equal	—[(A)+1·(A) D<= (B)+1·(B)]—	Turns output ON if (A)+1·(A)≤(B)+1·(B) (double-length integer comparison).	3~7	8.1

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Compare	108	Unsigned greater than	—[(A) U> (B)]—	Turns output ON if (A)>(B) (unsigned integer comparison).	3~5	6.98
	109	Unsigned greater than or equal	—[(A) U>= (B)]—	Turns output ON if (A)≥B) (unsigned integer comparison).	3~5	6.98
	110	Unsigned equal	—[(A) U= (B)]—	Turns output ON if (A)=(B) (unsigned integer comparison).	3~5	6.98
	111	Unsigned not equal	—[(A) U<> (B)]—	Turns output ON if (A)≠B) (unsigned integer comparison).	3~5	6.98
	112	Unsigned less than	—[(A) U< (B)]—	Turns output ON if (A)<(B) (unsigned integer comparison).	3~5	6.98
	113	Unsigned less than or equal	—[(A) U<= (B)]—	Turns output ON if (A)≤B) (unsigned integer comparison).	3~5	6.98
	212	Floating point greater than	—[(A)+1·(A) F> (B)+1·(B)]—	Turns output ON if (A)+1·(A)>(B)+1·(B) (floating point data comparison).	3	20.5
	213	Floating point greater than or equal	—[(A)+1·(A) F>= (B)+1·(B)]—	Turns output ON if (A)+1·(A)≥(B)+1·(B) (floating point data comparison).	3	20.5
	214	Floating point equal	—[(A)+1·(A) F= (B)+1·(B)]—	Turns output ON if (A)+1·(A)=(B)+1·(B) (floating point data comparison).	3	16.7
	215	Floating point not equal	—[(A)+1·(A) F<> (B)+1·(B)]—	Turns output ON if (A)+1·(A)≠(B)+1·(B) (floating point data comparison).	3	16.7
	216	Floating point less than	—[(A)+1·(A) F< (B)+1·(B)]—	Turns output ON if (A)+1·(A)<(B)+1·(B) (floating point data comparison).	3	20.5
	217	Floating point less than or equal	—[(A)+1·(A) F<= (B)+1·(B)]—	Turns output ON if (A)+1·(A)≤(B)+1·(B) (floating point data comparison).	3	20.5

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Special data processing	114	Set device/register	—[SET (A)]—	If (A) is a device: Sets device (A) to ON.	2~3	6.53
				If (A) is a register: Stores HFFFF in register (A).		4.28
	115	Reset device/register	—[RST (A)]—	If (A) is a device: Sets device (A) to OFF.	2~3	6.53
				If (A) is a register: Stores 0 in register (A).		4.28
	116	Table bit set	—[(A) TSET (n) (B)]—	From the bit file of n words, headed by the register (B), the instruction takes the bit in the location indicated by (A) and sets it to ON.	4~5	31.7
	117	Table it reset	—[(A) TRST (n) (B)]—	From the bit file of n words, headed by the register (B), the instruction takes the bit in the position indicated by (A) and resets it to OFF.	4~5	31.1
	118	Set carry	—[SETC]—	Sets the carry flag.	1	2.48
	119	Reset catty	—[RSTC]—	Resets the carry flag.	1	2.48
	120	Encode	—[(A) ENC (n) (B)]—	In the bit file of size 2^n bits headed by (A), the instruction stores the uppermost ON bit position in register (B).	3~4	29.0
	121	Decode	—[(A) DEC (n) (B)]—	Takes the bit file of size 2^n bits headed by (B), sets the bit position indicated by the lower n bits of register (A) to ON, and sets all the rest to OFF.	3~4	30.4
	122	Bit count	—[(A) BC (B)]—	Counts the number of ON bits in the data in (A) and stores the result in (B).	3~5	25.2
	123	Double-length bit count	—[(A) DBC (B)]—	Counts the number of ON bits in the double-length data in (A)+1·(A) and stores the result in (B)+1·(B).	3-~6	43.9

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Special data processing	124	Data search	(A) SCH (n) (B) → (C)	Searches through data table of n words headed by (B) for data matching the contents of (A). Stores the number of matches in (C), and stores the lowest register address of the matching registers in (C)+1.	5~6	23.6+2.7n
	125	Push	(A) PUSH (n) (B) → (C)	Pushes the data in (A) into the table of n words headed by (C), and increments the value of (B) by 1.	5~6	15.8
	126	Pop last	(A) POPL (n) (B) → (C)	Takes out the data pushed in last to the table of n words headed by (A) and stores it in (C). Also decrements the value of (B) by 1.	5~6	16.4
	127	Pop first	(A) POPF (n) (B) → (C)	Takes out from the table of n words headed by (A) the data which was pushed in first, and stores it in (C). Also decrements the value of (B) by 1.	5~6	16.8
	147	Flip-flop	S F/F Q R (A)	When the set input (S) is ON, the instruction sets the device (A) to ON; when the reset input (R) is ON, it resets the device (A) to OFF. (Reset takes priority)	2	8.1
	149	Up-down counter	U U/D Q C E (A)	If the enable input (E) is ON, the instruction counts the number of times the count input (C) has come ON and stores it in the counter register (A). The selection of the count direction (increment/decrement) is made according to the state of the up/down selection input (U) (see below). ON : UP count (increment) OFF : DOWN count (decrement)	2	4.28

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Program control	128	Subroutine call	├[CALL N. nn]┤	If the input is ON, the instruction calls the subroutine for the subroutine number nn.	2~3	0.45
	129	Subroutine return	├[RET]┤	Indicates the end of the subroutine.	1	6.98
	130	Conditional jump	—[JUMP N. nn]—	If the input is ON, jumps directly to the label for the label number nn.	2~3	0.45
	136	Jump label	├[LBL (nn)]┤	Indicates the jump destination for the conditional jump.	2	1.35
	132	FOR-NEXT loop (FOR)	—[FOR n]┤	Executes the section from FOR to NEXT repeatedly the number of times specified by n.	2	6.98
	133	FOR-NEXT loop (NEXT)	—[NEXT]┤		1	4.95
	137	Subroutine entry	├[SUBR (nn)]┤	Indicates the entrance to the subroutine (number nn).	2	1.35
	138	Stop	—[STOP]—	Stops the program execution (to HALT).	1	—
	140	Enable interrupt	—[EI]—	Enables execution of the interrupt program.	1	51.0
	141	Disable interrupt	—[DI]—	Disables execution of the interrupt program.	1	53.0
	142	Interrupt program end	├[IRET]┤	Indicates the end of the interrupt program.	1	—
	143	Watchdog timer reset	—[WDT n]—	Extends the scan time over detection time.	2	32.0
	144	Step sequence initialize	—[STIZ (n) (A)]—	Turns OFF the n devices headed by device (A), and turns (A) ON (activation of step sequence). These comprise one step sequence.	3	20.7
	145	Step sequence input	—[(A)]—	Tums output ON when input is ON and device (A) is ON.	2	9.0
	146	Step sequence output	—[(A)]┤	When input is ON, the instruction turns OFF the devices with step sequence input instructions on the same rung, and turns device (A) ON.	2	8.1
	241	SFC initialize	—[SFIZ (n) (A)]—	When input is changed from OFF to ON, the instruction resets the n steps from the SFC step (A), and activates step (A) (activation of SFC).	3	9.23+0.9× INT (n/16-1)

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
RAS	150	Diagnostic display	—[DIAG (A) (B)]—	When input has changed from OFF to ON, the instruction records the error code indicated by (A) in the special register, and turns ON the corresponding annunciator relay. The error messages (max 12 characters) recorded in the register tables headed by (B) can be monitored on the peripheral devices.	3~4	24.3
	151	Diagnostic display reset	—[DIAR (A)]—	Erases the error code (A) from the error code list recorded by the diagnostic display instruction (FUN150) and from the annunciator relay.	2~3	16.0+3.83n
	152	Status latch set	—[STLS]—	Takes the devices/registers (max 32) set by the programmer and stores them in the latch area.	1	944
	153	Status latch reset	—[STLR]—	Cancels the state of the status latch.	1	126
	154	Set calendar	—[(A) CLND]—	Takes the 6 words of data headed by the register (A) and sets them in the calendar LSI (date and time setting).	2	856.0
	155	Calendar operation	—[(A) CLDS (B)]—	Subtracts the 6 words of date and time data headed by (A), from the current date and time, and stores the result in the 6 words starting with (B).	3	1502.0
	158	Drum sequencer	—[(A) DRUM (n) (B) → C) (m)]—	Compares the count value (B) with the count value setting table ((A)+2n onwards), then decides the step number and stores it in (B)+1. Using the data output pattern table (A), the instruction looks up the output pattern corresponding to this step number and outputs it to the bit table (C).	6	At initialize: 54.1 Executing: 60.1
	159	Cam sequencer	—[(A) CAM (n) (B) → (C)]—	Compares the register (B) with the activation and deactivation setting value for table (A), and carries out ON/OFF control on the corresponding devices.	5	20.9+11.3n
Function	160	Upper limit	—[(A) UL (B) → (C)]—	Applies an upper limit to the contents of (A) using the value of (B), and stores the results in (C).	4~7	10.58

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Function	161	Lower limit	—[(A) LL (B) → (C)]—	Applies a lower limit to the contents of (A), using the value of (B), and stores the results in (C).	4~7	10.58
	162	Maximum value	—[(A) MAX (n) (B)]—	Searches the n-word data table headed by (A) for the maximum value, stores the maximum value in (B), and stores the pointer with the maximum value in (B)+1.	4	20.3
	163	Minimum value	—[(A) MIN (n) (B)]—	Searches the n-word data table headed by (A) for the minimum value, stores the minimum value in (A), and stores the pointer with the minimum value in (B)+1.	4	20.3
	164	Average value	—[(A) AVE (n) (B)]—	Calculates the average value for the n-word data table headed by (A), and stores it in (B).	4	28.6
	165	Function generator	—[(A) FG (n) (B) → (C)]—	Using the function defined by the 2x n parameters headed by (B), finds the function value which takes the contents of (A) as its argument, and stores it in (C).	5~7	38.7+2.03n
	166	Dead band	—[(A) DB (B) → (C)]—	Finds the value which gives the dead band indicated by (B) for the contents of (A), and stores it in (C).	4~7	11.7
	167	Square root	—[(A)+1·(A) RT → (B)]—	Finds the square root of the double-length data (A)+1·(A), and stores it in (B).	3~6	88.2
	168	Integral	—[(A) INTG (B) → (C)]—	Calculates the integral for the value of (A) from the integral constant for (B)+1·(B), and stores the result in (C)+1·(C).	4~7	33.5
	169	Ramp function	—[(A) RAMP (B) → (C)]—	Generates the ramp function for the value of (A) by the parameters starting with (B), and stores it in (C).	4~7	43.0
	170	PID	—[(A) PID (B) → (C)]—	Carries out the PID calculation for the value of (A) by the parameters starting with (B), and stores it in (C).	4	890.6
	171	Deviation square PID	—[(A) PID2 (B) → (C)]—	Carries out the deviation square PID calculation for the value of (A) using the parameters starting with (B), and stores it in (C).	4	760.7
	172	Sine function (SIN)	—[(A) SIN (B)]—	Stores in (B) the value obtained by taking the angle (degree) obtained by dividing the value of (A) by 100 and multiplying its sine value by 10000.	3~5	31.3
	173	Cosine function (COS)	—[(A) COS (B)]—	Stores in (B) the value obtained by taking the angle (degree) obtained by dividing the value of (A) by 100 and multiplying its cosine value by 10000.	3~5	32.6

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Function	174	Tangent function (TAN)	—[(A) TAN (B)]—	Stores in (B) the value obtained by taking the angle (degree) obtained by dividing the value of (A) by 100 and multiplying its tangent value by 10000.	3~5	60.5
	175	Arc sine function (SIN^{-1})	—[(A) ASIN (B)]—	Divides the value of (A) by 10000, multiplies the arc sine value by 100, then stores it in (B).	3~5	34.9
	176	Arc cosine function (COS^{-1})	—[(A) ACOS (B)]—	Divides the value of (A) by 10000, multiplies the arc cosine value by 100, then stores it in (B).	3~5	35.6
	177	Arc tangent function (TAN^{-1})	—[(A) ATAN (B)]—	Divides the value of (A) by 10000, multiplies the arc tangent value by 100, then stores it in (B).	3~5	903.4
	178	Exponential function	—[(A) EXP (B)+1·(B)]—	Finds the exponential of 1/1000 of the absolute value of (A) and stores it in (B)+1·(B).	3~5	784.4
	179	Logarithm	—[(A) LOG (B)]—	Calculates the common logarithm of the absolute value of (A), multiplies it by 1000 and stores the result in (B).	3~5	1082.3

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Conversion	180	Absolute value	(A) ABS (B)	Stores the absolute value of (A) in (B).	3~5	8.55
	181	Double-length absolute value	(A)+1·(A) DABS (B)+1·(B)	Stores the absolute value of (A)+1·(A) in (B)+1·(B).	3~6	10.4
	182	2's complement	(A) NEG (B)	Stores the 2's complement of (A) in (B).	3~5	7.43
	183	Double-length 2's complement	(A)+1·(A) DNEG (B)+1·(B)	Stores the 2's complement of (A)+1·(A) in (B)+1·(B).	3~6	10.1
	184	Double-length conversion	(A) DW (B)+1·(B)	Converts the signed data in (A) into double-length data, and stores in (B)+1·(B).	3~5	8.55
	185	7-segment decode	(A) 7 SEG (B)	Converts the 4 bits of (A) into 7-segment code, and stores in (B).	3~5	7.43
	186	ASCII conversion	(A) ASC (B)	Takes the alphanumerics (maximum 16 characters) indicated by (A) and converse them into ASCII code. Stores the result in the location headed by (B).	3~10	19.8+1.35n
	188	Binary conversion	(A) BIN (B)	Converts the BCD data in (A) into binary data and stores it in (B).	3~5	35.6
	189	Double-length binary conversion	(A)+1·(A) DBIN (B)+1·(B)	Converts the double-length BCD data in (A)+1·(A) into binary data and stores it in (B)+1·(B).	3~6	75.2
	190	BCD conversion	(A) BCD (B)	Converts the binary data in (A) into BCD data and stores it in (B).	3~5	11.9
	191	Double-length BCD conversion	(A)+1·(A) DBCD (B)+1·(B)	Converts the binary data in (A)+1·(A) into BCD data and stores it in (B)+1·(B).	3~6	42.3
	204	Floating point conversion	(A)+1·(A) FLT (B)+1·(B)	Converts the double-length integer of (A)+1·(A) into floating point data and stores it in (B)+1·(B).	3~5	25.9
	205	Fixed point conversion	(A)+1·(A) FIX (B)+1·(B)	Converts the floating point data of (A)+1·(A) intod ouble-length integer data and stores it in (B)+1·(B).	3	80.6
	206	Floating point absolute value	(A)+1·(A) FABS (B)+1·(B)	Stores the absolute value of floating point data of (A)+1·(A) in (B)+1·(B).	3	11.3
	207	Floating point sign inversion	(A)+1·(A) FNEG (B)+1·(B)	Stores the sign inversion data of floating point data of (A)+1·(A) in (B)+1·(B).	3	17.6

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
BCD operation	192	BCD addition	—[(A) B+ (B) → (C)]—	Carries out BCD addition of the contents of (A) and (B), and stores the result in (C).	4~7	59.2
	193	BCD subtraction	—[(A) B- (B) → (C)]—	Subtracts the contents of (B) from the contents of (A) in BCD, and stores the result in (C).	4~7	59.2
	194	BCD multiplication	—[(A) B* (B) → (C)+1·(C)]—	Multiplies the contents (A) and (B) together in BCD, and stores the result in (C)+1·(C).	4~7	102.6
	195	BCD division	—[(A) B/ (B) → (C)]—	Divides the contents of (A) by the contents of (B) in BCD, and stores the quotient in (C) and the remainder in (C)+1.	4~7	82.4
	196	Double-length BCD addition	—[(A)+1·(A) DB+ (B)+1·(B) → (C)+1·(C)]—	Adds the contents of (B)+1·(B) to the contents of (A)+1·(A) in BCD, and stores the result in (C)+1·(C).	4~9	112.1
	197	Double-length BCD subtraction	—[(A)+1·(A) DB- (B)+1·(B) → (C)+1·(C)]—	Subtracts the contents of (B)+1·(B) from the contents of (A)+1·(A) in BCD, and stores the result in (C)+1·(C).	4~9	111.6
	198	Double-length BCD multiplication	—[(A)+1·(A) DB* (B)+1·(B) → (C)+1·(C)]—	Multiplies the contents of (A)+1·(A) by the contents of (B)+1·(B) in BCD, and stores the result in (C)+3·(C)+2·(C)+1·(C).	4~9	278.3
	199	Double-length BCD division	—[(A)+1·(A) DB/ (B)+1·(B) → (C)+1·(C)]—	Divides the contents of (A)+1·(A) by the contents of (B)+1·(B) in BCD, and stores the quotient in (C)+1·(C) and the remainder in (C)+3·(C)+2.	4~9	228.2
	200	BCD addition with carry	—[(A) B+C (B) → (C)]—	Adds (B) plus the contents of the carry flag to (A) in BCD, and stores the result in (C). The carry flag changes according to the operation result.	4~7	60.5
	201	BCD subtraction with carry	—[(A) B-C (B) → (C)]—	Subtracts (B) plus the contents of the carry flag from (A) in BCD, and stores the result in (C). The carry flag changes according to the operation result.	4~7	60.5
	202	Double-length BCD addition with carry	—[(A)+1·(A) DB+C (B)+1·(B) → (C)+1·(C)]—	Adds the contents of (B)+1·(B), plus the contents of the carry flag, to (A)+1·(A) in BCD, and stores the result in (C)+1·(C). The carry flag changes according to the operation result.	4~9	112.7
	203	Double-length BCD subtraction with carry	—[(A)+1·(A) DB-C (B)+1·(B) → (C)+1·(C)]—	Subtracts (B)+1·(B) plus the contents of the carry flag from (A)+1·(A) in BCD, and stores the result in (C)+1·(C). The carry flag changes according to the operation result.	4~9	115.2

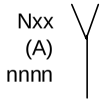
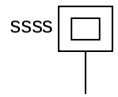
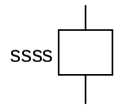
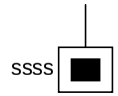
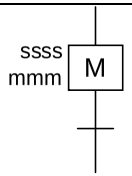
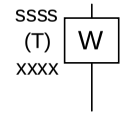
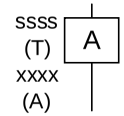
Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Real functions	218	Floating point upper limit	—[(A)+1·(A) FUL (B)+1·(B) → (C)+1·(C)]—	Applies the upper limit to the floating point data (A)+1·(A) using (B)+1·(B), and stores the result in (C)+1·(C).	4	23.6
	219	Floating point lower limit	—[(A)+1·(A) FLL (B)+1·(B) → (C)+1·(C)]—	Applies the lower limit to the floating point data (A)+1·(A) using (B)+1·(B), and stores the result in (C)+1·(C).	4	23.9
	220	Floating point dead band	—[(A)+1·(A) FDB (B)+1·(B) → (C)+1·(C)]—	Finds the floating point data which gives the dead band by (B)+1·(B) for (A)+1·(A), and stores it in (C)+1·(C).	4	40.5
	221	Floating point square root	—[(A)+1·(A) FRT (B)+1·(B)]—	Finds the square root of the floating point data (A)+1·(A), and stores it in (B)+1·(B).	3	288.9
	222	Floating point PID	—[(A)+1·(A) FPID (B)+1·(B) → (C)+1·(C)]—	Carries out the PID calculation for the floating point data (A)+1·(A) using parameters starting with (B)+1·(B), and stores it in (C)+1·(C).	4	430.0
	223	Floating point deviation square PID	—[(A)+1·(A) FPID2 (B)+1·(B)→(C)+1·(C)]—	Carries out the deviation square PID calculation for the floating point data (A)+1·(A) using parameters starting with (B)+1·(B), and stores it in (C)+1·(C).	4	478.6
	224	Floating point sine (SIN)	—[(A)+1·(A) FSIN (B)+1·(B)]—	Finds the sine for the floating point data of (A)+1·(A), and stores it in (B)+1·(B).	3	333.9
	225	Floating point cosine (COS)	—[(A)+1·(A) FCOS (B)+1·(B)]—	Finds the cosine for the floating point data of (A)+1·(A), and stores it in (B)+1·(B).	3	613.6
	226	Floating point tangent (TAN)	—[(A)+1·(A) FTAN (B)+1·(B)]—	Finds the tangent for the floating point data of (A)+1·(A), and stores it in (B)+1·(B).	3	755.6
	227	Floating point arc sine (SIN^{-1})	—[(A)+1·(A) FASIN (B)+1·(B)]—	Finds the arc sine for the floating point data of (A)+1·(A), and stores it in (B)+1·(B).	3	35.1
	228	Floating point arc cosine (COS^{-1})	—[(A)+1·(A) FACOS (B)+1·(B)]—	Finds the arc cosine for the floating point data of (A)+1·(A), and stores it in (B)+1·(B).	3	35.1
	229	Floating point arc tangent (TAN^{-1})	—[(A)+1·(A) FATAN (B)+1·(B)]—	Finds the arc tangent for the floating point data of (A)+1·(A), and stores it in (B)+1·(B).	3	430.0

Ladder Diagram Instructions (Function Instructions)

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Real functions	230	Floating point exponential	—[(A)+1·(A) FEXP (B)+1·(B)]—	Finds the exponential of the floating point data of (A)+1·(A), and stores it in (B)+1·(B).	3	678.8
	231	Floating point logarithm	—[(A)+1·(A) FLOG (B)+1·(B)]—	Calculates the common logarithm of the floating point data of (A)+1·(A), and stores it in (B)+1·(B).	3	80.6
Input/output	235	Direct I/O	—[I/O (n) (A)]—	For the n words registers headed by the input/output register (A), the instruction carries out input/output of data from/to the corresponding I/O module.	3	20.7+9.7n
	236	Expanded data transfer	—[(A) XFER (B) → (C)]—	Transfers the word block of size (B) from the transfer source indirectly specified by the register (A) to the transfer destination indirectly specified by the register (C).	4	Dependent on the target
	237	Special module data read	—[(A) READ (B) → (C)]—	Carries out data transfer from the memory in the special module to the user area.	4~5	712+13.5n
	238	Special module data write	—[(A) WRITE (B) → (C)]—	Transfers the contents of the user register area to the memory in the special module.	4~5	712+13.5n

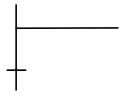
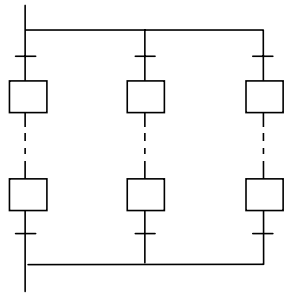
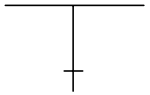
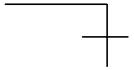
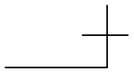
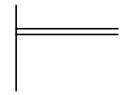
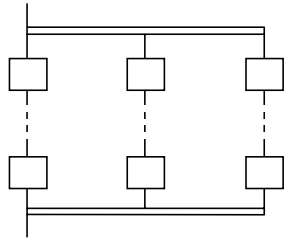
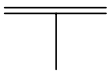
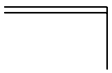
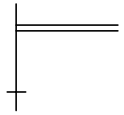
SFC Instructions

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
SFC initialize		SFC initialize		When the device (A) has changed from OFF to ON, the instruction in activates the nnnn steps of the succeeding SFC program, and activates the initial step (SFC activation).	4	197.48
SFC step		Initial step		Indicates the start of the SFC program and contains action program which correspond on a one-to-one basis. ssss is the step number.	2 (excluding action)	7.88
		Step		This is the single unit of control. It contains action program which correspond on a one-to-one basis. ssss is the step number.	1 (excluding action)	3.00
		End step		Indicates the end of the SFC program. Returns processing to the corresponding initial step when the immediately preceding transition condition comes true. ssss is the initial step number.	2	3.15
		Macro step		Corresponds on a one-to-one basis to the macro program indicated by mmm. ssss is the step number, and mmm is the macro number.	3	9.90
		Wait step		Even if the immediately preceding transition condition comes true, this instruction does not carry out the transition until the set period has elapsed. It has action program which correspond on a one-to-one basis. ssss is the step number, (T) is the timer register, and xxxx is the set period.	4 (excluding action)	9.53
		Alarm step		Monitors the active period, and if the transition has not been made within the set period, sets the alarm device (A) to ON. Contains action program which correspond on a one-to-one basis. ssss is the step number, (T) is the timer register, and xxxx is the set period.	5 (excluding action)	10.88

SFC Instructions

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (µs)
Transition		Transition		Indicates the condition for transition between steps. Contains transition condition which correspond on a one-to-one basis.	1 (excluding condition)	5.62
		SFC End	@IIII	Indicates the end of SFC program. Jumps to the label indicated by 1111 when the transition condition comes true. Contains transition condition which correspond on a one-to-one basis.	2 (excluding condition)	6.53
		SFC Jump	@IIII	Indicates jump to desired step. Jumps to the label indicated by till when the condition comes true. Contains jump condition which correspond on a one-to-one basis.	5 (excluding condition)	8.03
		Macro end	E	Indicates the end of the macro program. Contains transition condition which correspond on a one-to-one basis.	2 (excluding condition)	6.53
Label		SFC label	@IIII	Indicates the return destination from the SFC end, or the jump destination from the SFC jump.	2	11.03
		Macro entry	mmm M	Indicates start of macro program.	1	0.30

SFC Instructions

Group	FUN No.	Name	Representation	Summary	Number of steps required	Execution time required (μs)
Sequence selection		Sequence selection Divergence (I)		From among several connected steps, activates the step for which the transition condition comes true (left priority). 	2xn-1 n is the branch count (Excluding transitions, steps, and individual details within the branch)	6.45
		Sequence selection Divergence (II)				6.45
		Sequence selection Divergence (III)				5.77
		Sequence selection Convergence				0.15
Simultaneous sequences		Simultaneous sequences Divergence (I)		Activates all the connected steps. 	n+3 n is the branch count (Excluding transitions, steps, and individual details within the branch)	0.15
		Simultaneous sequences Divergence (II)				0.15
		Simultaneous sequences Divergence (III)				0.15
		Simultaneous sequences Convergence (I)				4.28+0.45n
		Simultaneous sequences Convergence (II)				2.93+2.93n

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Integrated Controller V series