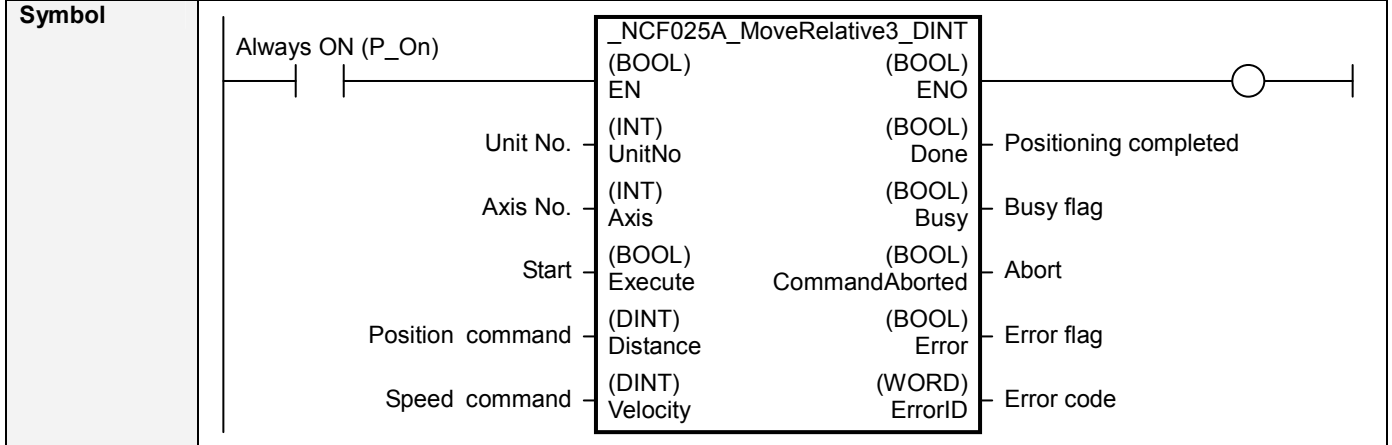| NCF 025A	Move Relative with Interrupt Feeding (DINT) _NCF025A_MoveRelative3_DINT

Basic function	Executes Interrupt Feeding with Move Relative command. (Busy attachment)
Symbol	

```
Always ON (P_On)        _NCF025A_MoveRelative3_DINT
   ─┤├─                (BOOL)                (BOOL)                              ─( )─
                        EN                    ENO

                        (INT)                 (BOOL)
            Unit No. ─  UnitNo                 Done  ─ Positioning completed

                        (INT)                 (BOOL)
            Axis No. ─  Axis                   Busy  ─ Busy flag

                        (BOOL)                (BOOL)
              Start  ─  Execute        CommandAborted ─ Abort

                        (DINT)                (BOOL)
   Position  command ─  Distance              Error  ─ Error flag

                        (DINT)                (WORD)
      Speed  command ─  Velocity             ErrorID ─ Error code
```
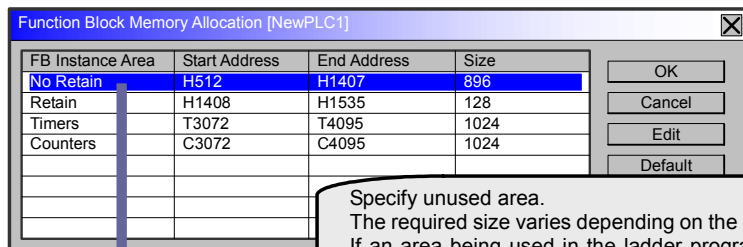
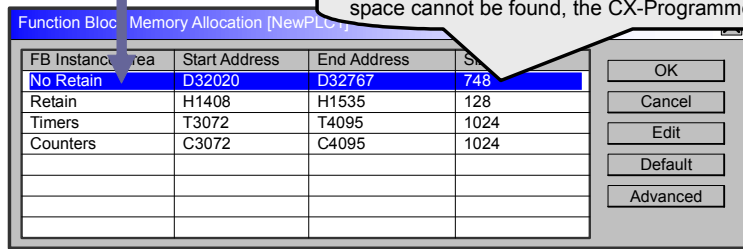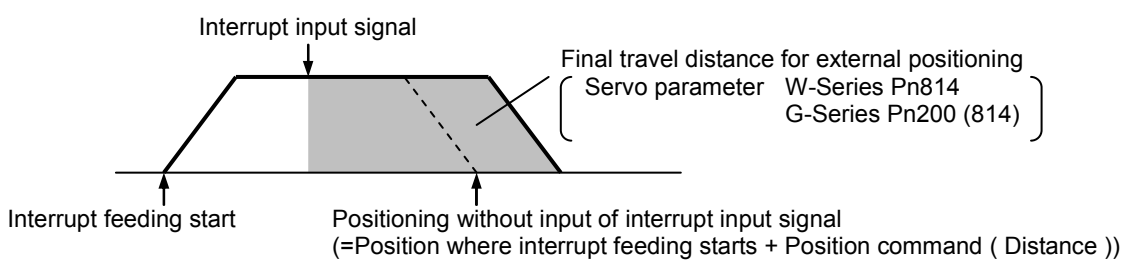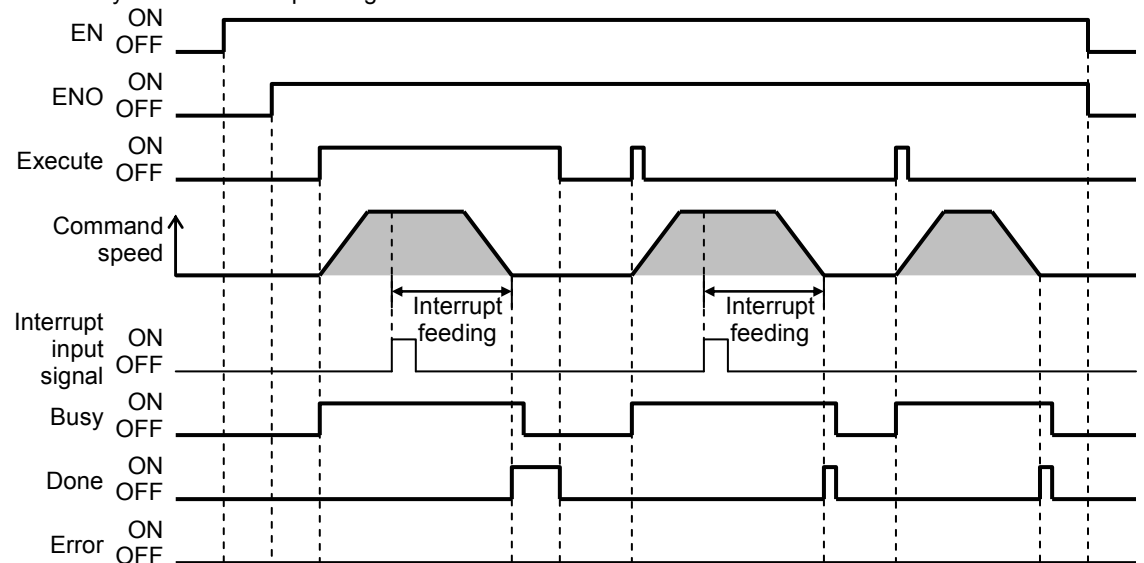| File name	Lib\FBL\omronlib\PositionController\NCF_NCF025A_MoveRelative3_DINT10.cxf
Applicable models	Position Control Unit	CJ1W-NCF71, CS1W-NCF71
	CPU Unit	CS1*-CPU**H Unit Version 3.0 or later CJ1*-CPU**H Unit Version 3.0 or later CJ1M-CPU** Unit Version 3.0 or later CP1H
	CX-Programmer	Version 5.0 or later
Languages in function block definitions	Ladder programming
Conditions for usage	The following conditions for usage should be the Position Control Unit version 1.2 or earlier. (It will not be required in the Position Control Unit version 1.3 or later) ■CX-Programmer Setting The function blocks related to the Position Control Units will not operate if the area H512 or higher (default setting) is specified as the Non Retain Area through the Function block memory allocation. Make sure to change the memory area to unused area (DM or EM, for example) from the CX-Programmer. To change this value, click **PLC/Function Block Memory/Function Block Memory Allocation** from the Menu Bar.

Function Block Memory Allocation [NewPLC1]

FB Instance Area	Start Address	End Address	Size	
No Retain	H512	H1407	896	OK
Retain	H1408	H1535	128	Cancel
Timers	T3072	T4095	1024	Edit
Counters	C3072	C4095	1024	Default

Specify unused area.
The required size varies depending on the used FB and the number of FBs.
If an area being used in the ladder program is specified or sufficient free space cannot be found, the CX-Programmer will display a compile error.

Function Block Memory Allocation [NewPLC1]

FB Instance Area	Start Address	End Address	Size	
No Retain	D32020	D32767	748	OK
Retain	H1408	H1535	128	Cancel
Timers	T3072	T4095	1024	Edit
Counters	C3072	C4095	1024	Default
				Advanced

For example, to use the memory area from D32020 to D32767 (748 words), specify the addresses as shown in the left.

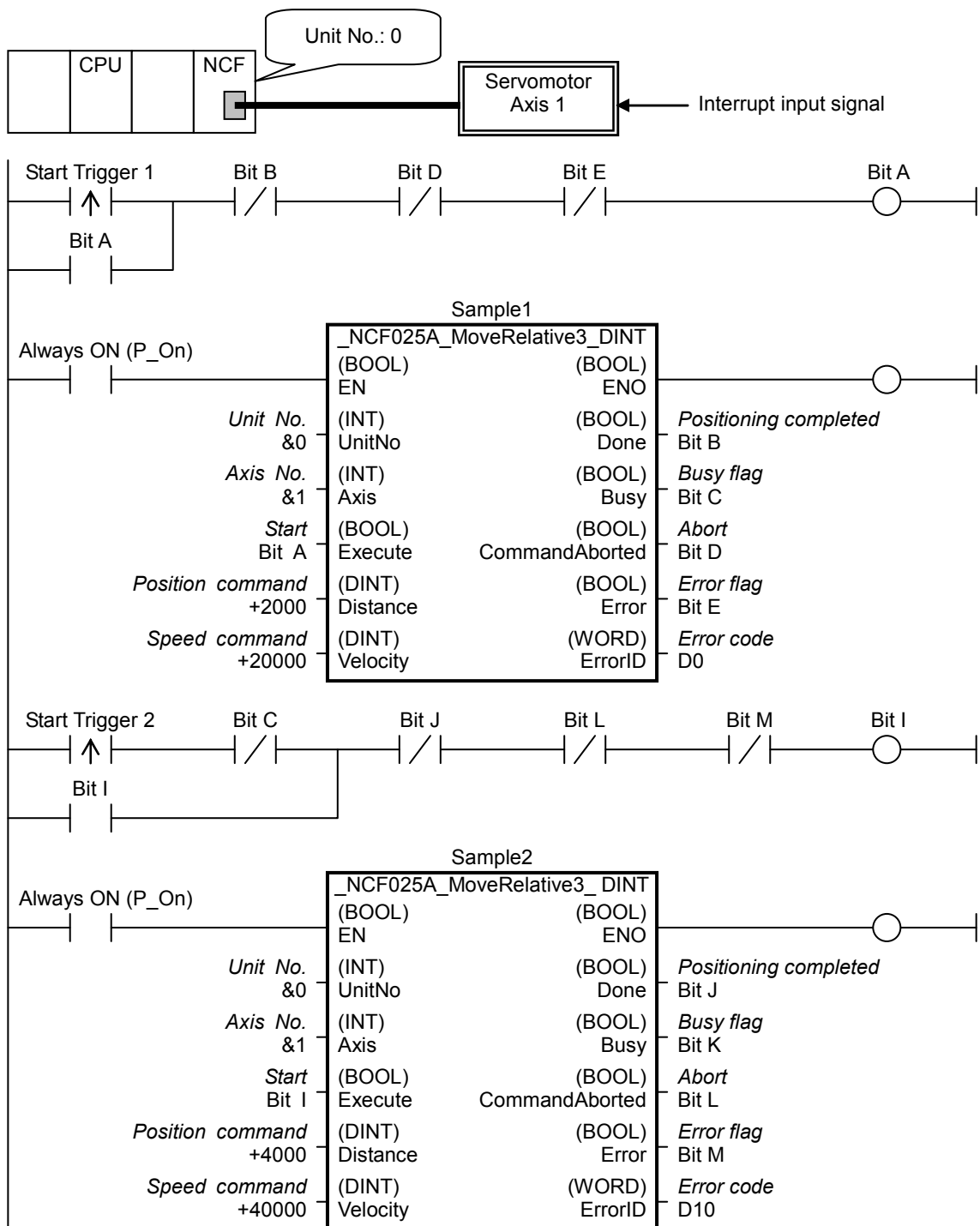|	
Function description	The Busy Output is added to the _NCF025_MoveRelative3_DINT in this FB. When the Start (Execute) turns ON, the Interrupt Feeding (Move Relative) for the axis of the specified Unit No. (UnitNo) and Axis No. (Axis) is started using the specified Position command (Distance) and Speed command (Velocity). (An Interrupt Feeding Designation Bit of the Axis Operating Output Memory Area is turned ON in the FB, so it does not need to be turned ON at the external ladder program.) Changing the Speed command (Velocity) during positioning by this FB will change the actual operation speed. Positioning is executed on the axis being positioned for an amount specified in the Servo Parameter, "Final travel distance for external positioning", when the external interrupt input signal is input. When an interrupt input signal is not input, an axis is moved to the position specified in "Position command (Distance)". The Positioning completed (Done) is turned ON when the positioning operation for the FB has been completed. This Flag is also turned ON when the positioning operation is completed without the interrupt feeding signal input. This flag will not be turned ON if the positioning operation is canceled because another operation has been started from a different instance, for a deceleration stop, or because an error has occurred. The Busy flag (Busy) will be set when the Start (Execute) is turned ON. The Busy flag (Busy) will be reset when any of the Positioning completed (Done), Abort (CommandAborted), or Error flag (Error) is turned ON. Even if an error occurs when the input variable is out of the range, etc., the Busy flag (Busy) will be set for at least one cycle. The Error flag (Error) will be turned ON and the Error code (ErrorID) will be output if an error occurs for the FB. This will not occur for error in other FBs or other instances of the FB. These statuses (Done/CommandAborted/Error/ErrorID) will be reset when the Start (Execute) turns OFF. If the Start (Execute) turns OFF before the positioning operation has been completed, the status will be set for at least one cycle when corresponding conditions have occurred.

Kind of FB definition	Always execution type.
	  Connect the EN input to the Always ON Flag (P_On).
	  The same instance cannot be used in two or more places.

FB precautions	·Executing this FB during the positioning operation will cause a multistart error. ·Positioning operation will be performed to the relative position specified in Position command (Distance) from the point at which the last execution was started when executing this FB during the Speed Control or Torque Control. Refer to the *Related Manuals* for details. ·The setting of Axis Parameters and Servo Parameters is required for executing the Interrupt Feeding operation. Refer to 9-5 Interrupt Feeding of the Operation Manual, W426-E1, in the Related Manuals for details.
EN input condition	·Connect the EN input to the Always ON Flag (P_On). If another bit is connected to EN, the FB outputs will be held when the connected bit turns OFF.

Restrictions Other	・The following cannot be specified for this FB: "Acceleration/deceleration curve designation", "Forward rotation current limit designation" and "Reverse rotation current limit designation". If any of these functions is required, specify them in advance outside the FB. ・This FB uses Unit Error Reset, Write Data, Read Data and Save Data Bits of the Position Control Unit (see Note). Therefore, do not turn these bits ON or OFF between the period from the rising edge of EN to the rising edge of ENO. For the same reason, do not use these bits for coil outputs (OUT commands). ・The output variable of FB may not change even if EN is turned ON. In that case, check if any of Unit Error Reset, Write Data, Read Data and Save Data Bit is left ON. ・This FB uses the Relative Movement/ Interrupt Feeding Bit in the Axis Operating Output Memory Areas. Therefore, do not turn these bits ON or OFF until the operation is completed. For the same reason, do not use these bits for coil outputs (OUT commands). Note: For calculation of bit addresses, these bits are referenced in this FB in the first execution of each instance, and when changing "Unit No. (UnitNo)", "Axis No. (Axis)" of the input variable and set "Start (Execute) ".
Application example	Turning the Start Trigger 1 ON from OFF will operate the Servomotor (axis1) connected to the Position Control Unit with a unit number 0 using the Move Relative command with the Interrupt Feeding enabled. The Busy flag(Busy) can be used for not to operate the FB of the "Sample2" during the FB operation of the "Sample1".

Related manuals	Position Control Units OPERATION MANUAL (W426-E1) SECTION 9 Positioning 9-5 Interrupt Feeding 12-4 Error Codes

■**Variable Tables**
Input Variables

Name	Variable name	Data type	Default	Range	Description
EN	EN	BOOL			1 (ON): FB started 0 (OFF): FB not started
Unit No.	UnitNo	INT	&0	&0 to &15	Specify the unit number.
Axis No.	Axis	INT	&1	&1 to &16	Specify the axis number.
Start	Execute	BOOL	0(OFF)		⬆: Starts the relative move.
Position command	Distance	DINT	+0	-2,147,483,648 to +2,147,483,647	Specify the target position. Unit: Command units
Speed command	Velocity	DINT	+0	+0 to +2,147,483,647	Specify the target speed. Unit: Command units/s Changing the value while this FB is in operation will change the actual operating speed.

Output Variables

Name	Variable name	Data type	Range	Description
ENO	ENO	BOOL		1 (ON): FB operating normally 0 (OFF): FB not operating normally ・FB not started ・Input variable out of the range ・FB ended with error ・Common Parameters could not be read
Positioning completed	Done	BOOL		Turns ON when the positioning operation has been completed.
Busy flag	Busy	BOOL		1 (ON) indicates that the FB is in progress.
Abort	CommandAborted	BOOL		1 (ON): Aborted It will be aborted when any of the following conditions is met during operation ・Turns ON when the other Move command done (Duplicate Move). ・Stopped with Decleration Stop or Emergency Stop. ・Executed Servo Unlock, Deviation Counter Reset on an operating axis. ・Attempted to execute FB while Servo Unlock, Deceleration Stop, Emergency Stop or Deviation Counter Reset Bit is ON. ・Detected the Stop Execution Flag is ON. ・The Relative Movement Bit is changed by the other FB during Relative Movement in operation.
Error flag	Error	BOOL		Turns ON when an error has occurred in the FB.
Error code	ErrorID	WORD		Returns the error code when an error has occurred in the FB. Refer to the *Related Manuals* for details on errors. A code of #0000 will be returned if any of the following conditions is satisfied. ・Input variable is out of range. ・The common parameters of the Position Control Units are out of range. ・Not established communications with a specified axis.

■**Version History**

Version	Date	Contents
1.01	2006.01.	Original production

■**Note**
This document explains the function of the function block.
It does not provide information of restrictions on the use of Units and Components or combination of them. For actual applications, make sure to read the operation manuals of the applicable products.