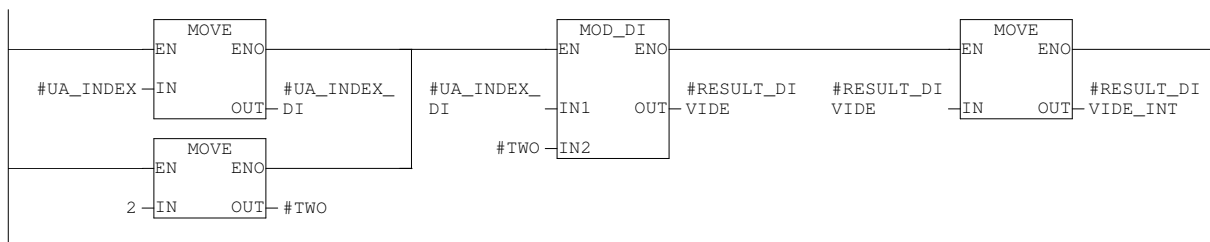
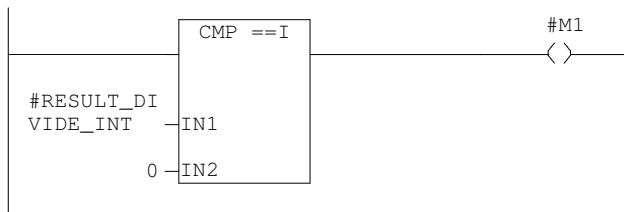


FC6 - <offline>

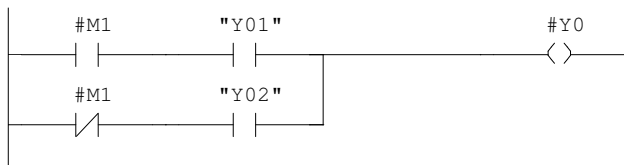
"FC_GO_HOME" Funcao que cordena o movimento do robo para a posicao HOME

Name: **Family:****Author:** **Version:** 0.1**Block version:** 2**Time stamp Code:** 08-09-2011 15:56:49**Interface:** 06-09-2011 16:27:06**Lengths (block/logic/data):** 00402 00266 00018

Address	Declaration	Name	Type	Initial value	Comment
0.0	in	GOHOME	BOOL		Inicia o processo de ida até a posicao d e repouso do robo
0.1	in	GORECEPTION	BOOL		Coloca o robo em posicao de pesagem da U A
2.0	in	UA_INDEX	INT		Index da UA
	out				
	in_out				
0.0	temp	M1	BOOL		Memoria Temporaria
0.1	temp	Y0	BOOL		Posicao do home
2.0	temp	UA_INDEX_DI	DINT		memoria temporaria
6.0	temp	TWO	DINT		Memoria temporaria
10.0	temp	RESULT_DIVIDE	DINT		Memoria tmeoporaria
14.0	temp	RESULT_DIVIDE_INT	INT		

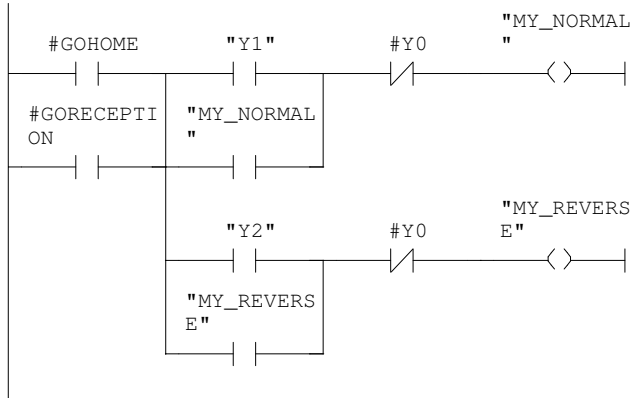
Block: FC6 Funcao que cordena os movimentos do robo ate a posicao HOME**Network: 1** Verifica se o indice da posicao e par ou impar**Network: 2** Compara o resto da divisao para ver se e zero**Network: 3**

Se o indice da UA for par a posicao da transporte e y02, se for impar e y01

**Symbol information**

I126.2	Y01	Posicao de transporte 1
I126.3	Y02	Posicao de transporte 2

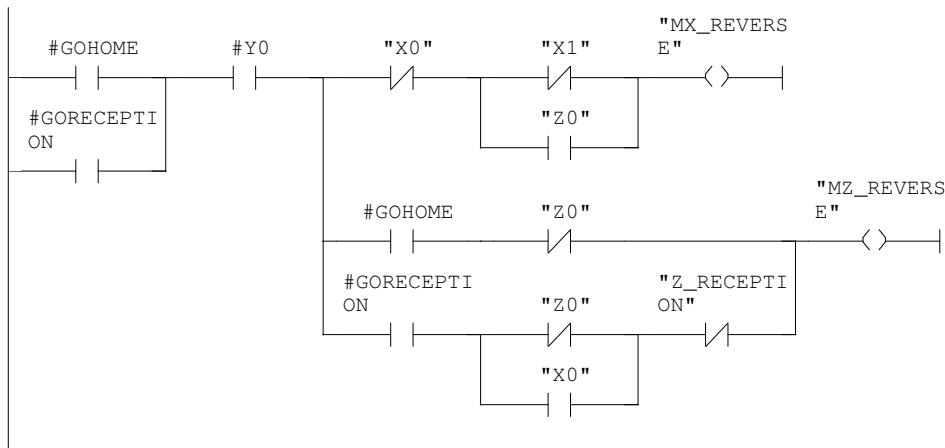
Network: 4 controla o motor y



Symbol information

I125.6	Y1	
Q125.2	MY_NORMAL	Motor Y - Sentido Normal
I125.7	Y2	
Q125.3	MY_REVERSE	Motor Y - Sentido Reverso

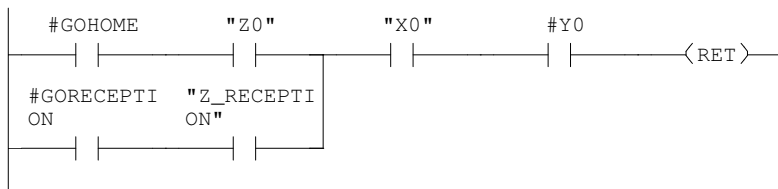
Network: 5 Controla o motor x e z quando é atingido y0



Symbol information

I124.6	X0	
I124.0	X1	
I125.3	Z0	
Q125.1	MX_REVERSE	Motor X - Sentido Reverso
I125.5	Z_RECEPTION	Z na zona de recepção e na zona de pesagem
Q125.5	MZ_REVERSE	Motor Z - Sentido Reverso

Network: 6 Termina a funcao



Symbol information

I125.3	Z0	
I125.5	Z_RECEPTION	Z na zona de recepção e na zona de pesagem

I124.6 X0