Sommario

DA11Ramp

D = *Device(anpos-camming-camming2)*

A = *Action functions*

The purpose of the DA11Ramp function is to build a ramp with an input set-point and acceleration and deceleration parameters.
This function can be used in the setting of speed without using a device.

IMPLEMENTATION

DA11Ramp (Setpoint, Acceleration, Deceleration, Start, Output, State)

Parameters:

IN/OUT	VARIABLE TYPE	EXAMPLE NAME	DIM	
IN	GLOBAL	Setpoint	L	Set-point (Um/s)
IN	GLOBAL	Acceleration	L	Acceleration value (Um/s²) If 0, in acceleration ramp, the adjusting output does not change.
IN	GLOBAL	Deceleration	L	Deceleration value (Um/s²) If 0, in deceleration ramp, the adjusting output does not change.
IN	GLOBAL	Start	F	Run adjustment flag. If 0 the setting is disabled and the Setpoint value is copied to the Output value.
OUT	GLOBAL	Output	L	Output value of the adjustment (Um/s)
OUT	GLOBAL	State	B	Adjustment mode 0 = disabled / set-point is reached 1 = active adjustment in acceleration ramp -1= active adjustment in deceleration ramp

Example

Adjustin output bringing the value of 1000, starting from 0, with ramp of 10 seconds.

```
IF Start
  Setvel = 1000
  Acc = 100
  Dec = 100
  Run = 1
ENDIF
DA11Ramp (Setvel, Acc, Dec, Run, Outvel, State)
```

Operation notes

- The function manages the setpoint changes and the acceleration and deceleration time changes “on the fly”.
- If the value of acceleration or deceleration is/or becomes 0 (ZERO), the value of the control output remains unchanged. For example, is used to stop a ramp to take it up.
- Upgrading of the adjustment output occurs at each call of the function, so the higher the time between two calls (cycle task) and the higher the relative vector.