Sommario

DT11BreakEnc

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

T = *Control functions*

The DT11BreakEnc functions executes a check to see any problems on the movement of analog axes. The function puts the device in emergency state (or report the emergency via a flag), when in 1/10 of a second (fixed time) with the analog output higher than the value contained in the *MinVout* parameter, the axis does not cover at least the space set to the *MinSpost* parameter.

IMPLEMENTATION

DT11BreakEnc(Asse, MinVout, MinSpost, EmrgOn, AlmEnc)

Parameters:

IN/OUT	VARIABLE TYPE	EXAMPLE NAME	DIM	
IN	ANPOS EANPOS CAMMING	Axis (INTDEVICE)	-	Device type to which you can apply the function
IN	SYSTEM	MinVout	L	Vout minimum value after which you enable the control (1/10 V)
IN	SYSTEM	MinSpost	L	Displacement value min to do in 1/10 of sec
IN	SYSTEM	EmrgOn	F	If the Flag is set to 1, in the event of an alarm, the function by an emergency command to device; if set to 0 the function simply set the alarm flag
OUT	SYSTEM/ GLOBAL	AlmEnc	F	Alarm flag. If setting to 1 when the function detect the alarm, (regardless of the value of the *EmrgOn* parameter).

Example

```
MinVout = 3           ;(0.3 Volt minimum voltage that enable the control)
MinSpost = 10           ;(10 units of minimum displacement measurement to be performed in 1/10 of sec)
EmrgOn = 0            ;(Enables only the flag and not the emergency command directly to the device)
DT11BreakEnc(Axis, MinVout, MinSpost, EmrgOn, AlmEnc)
IF AlmEnc
     IF NOT Axis:st_emrg
          EMRG Axis
     ENDIF
ENDIF
```

Note

- This function should be placed at a point of the application that runs on every round makes sense so that control is constant.
- The AlmEnc flag is reset automatically when the emergency situation becomes invalid (voltage for the device that falls below the set value in the (*MinVout*) parameter.