M 100

	M		M100 M200 M300 M500 M500S		
					-
	-				2025-08-4

M Sysctrl Studio 2.4

M100 M200 M300 M500 M500S

HCMXB-CAN-BD HCMXB-RTC-BD HCMXB-2RS232-BD HCMXB-2RS485-BD

M

2025-8-4	V1.0		

.....1

1. 100 1

2. RS485 ?.....1

3. ASCII RTU 1

4. E610 CAN 603F 2

5. RS485 2

6. 2

7. TCP 502 5020 3

8. Modbus TCP 3

9. Socket 4

10. 485 5

11. E600 485 6

12. 6

13. ModbusTCP M 6

14. 6

.....7

1. 7

2. 7

3. 7

4. 8

5. Q 8

6. M511S M511 2104 8
7. IP 8
8. 9
9. Time to DINT 9
10. 16#2103 9
11. 9
12. M514 10
13. 4-20ma 200 200 10
14. INT 10
15. TIME 11
16. 11
17. ID 12
18. M RTC 12
19. RTC 16690 12
20. 12
21. 13
22. 13
23. 13
24. IF 14
25. IF THEN END_IF 14
..... 16
1. MC_Setposition 16

2. 6064 PLC 16

3. M511S M511 16

4. 17

5. 200 50-80 17

6. MC_HomeByPLCIO 17

7. 17

8. 17

9. MC Stop MC_MoveContinuousVelocity 5377 18

10. MC_HomeByPLCIO 20 4105 18

11. 4612 18

12. XY 20 4618 18

13. MC_HomeByPLCIO homing 19

14. 19

15. M512 op 19

16. DI 19

17. 20

18. 4123 096 20

19. MC_GearIn InGear Eexcute ... 20

20. 16#2151 20

21. 20

22. 20

23. M511S M511 4116 20

.....26

1. ——RUN 26

2. —— 26

3. —— 26

4. —— 26

5. M : 26

6. M512 26

7. “ ” 26

8. 26

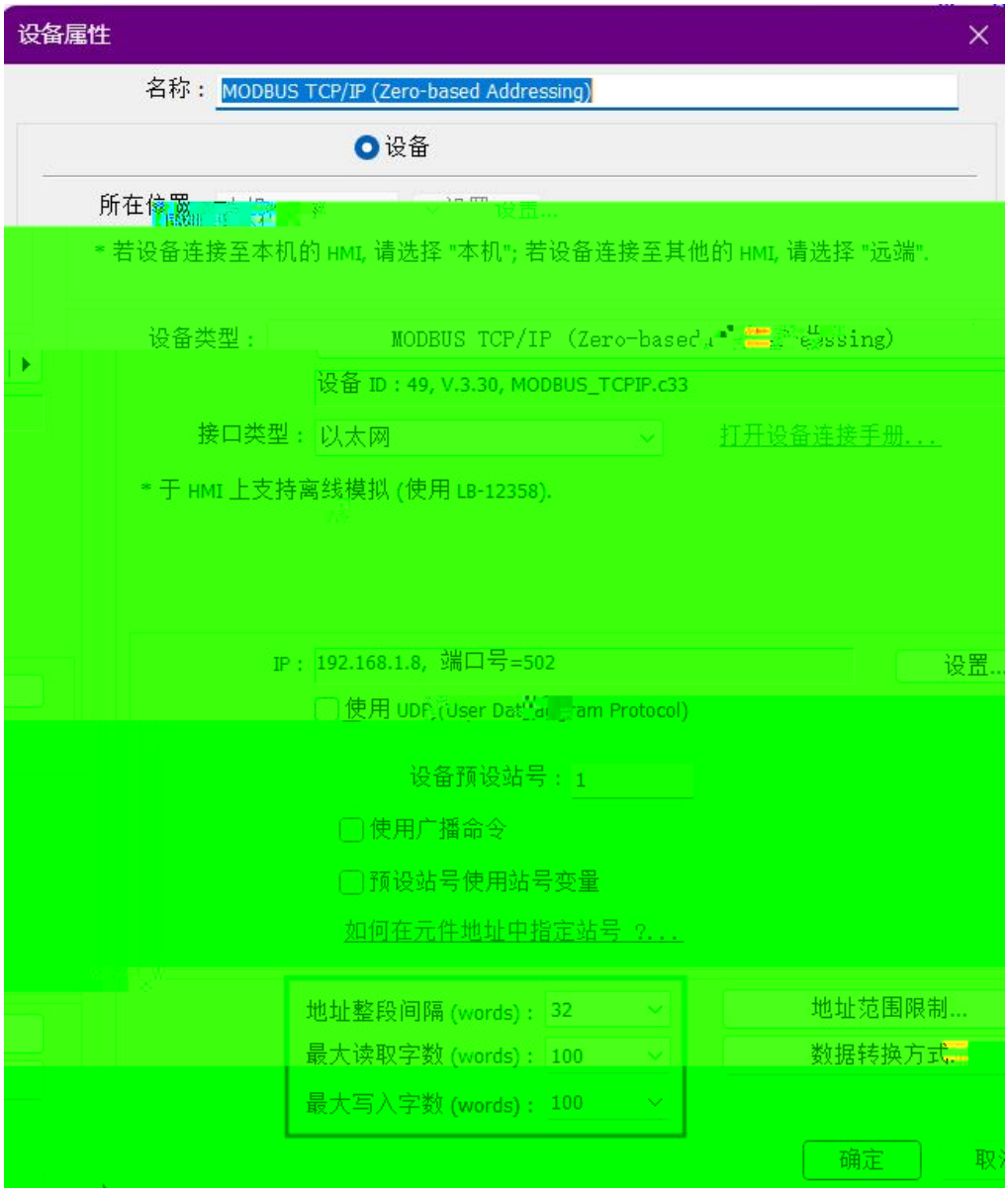
9. 16#2111 26

10. RUN PLC STOP 26

1. 100

104 WORD PLC 100WORD /

100word



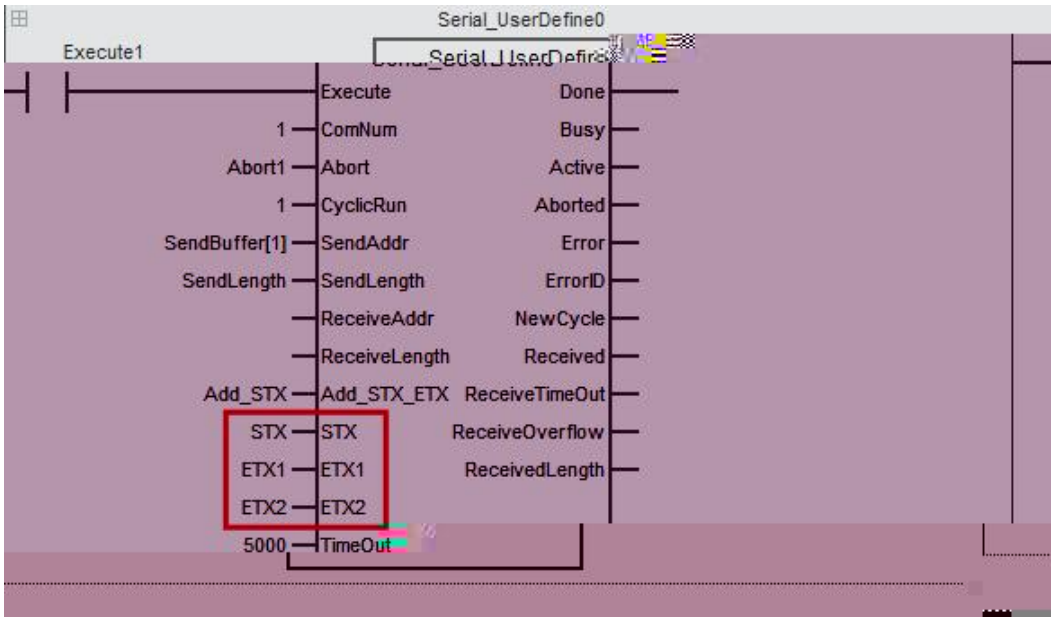
2. RS485 ?

ModbusRTU

06 10 10

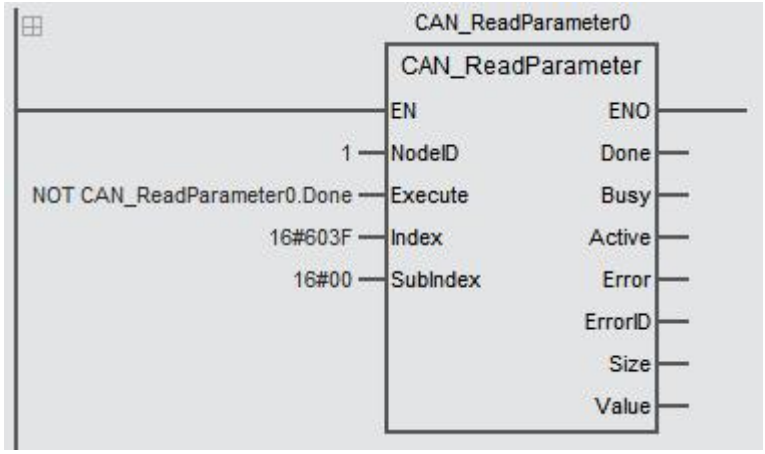
3. ASCII RTU

RTU ASCII M _



4. E610 CAN 603F

603F 00

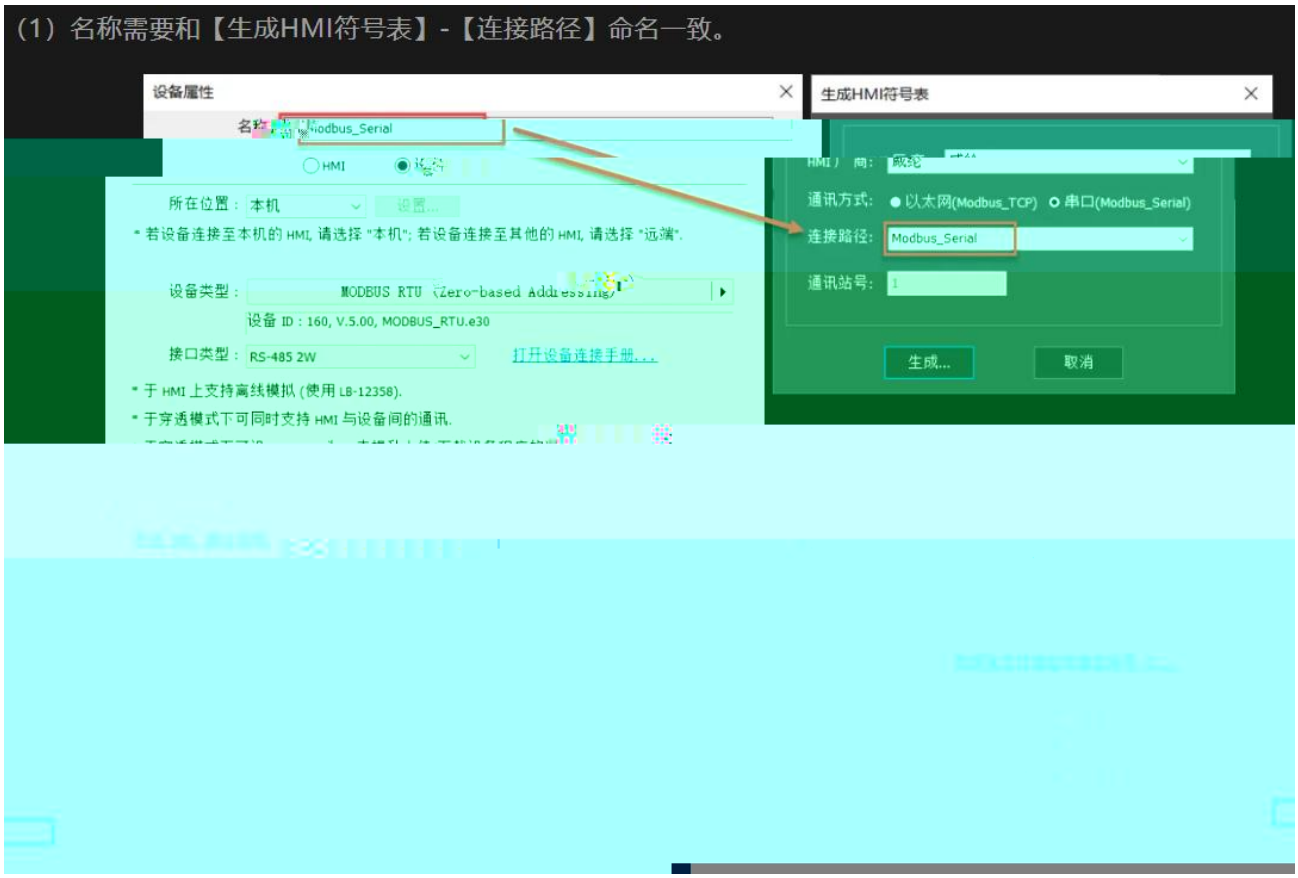


5. RS485

通道	启用	超时时间(ms)	触发方式	执行方式	读写类型	功能码	主站地址	..	从站地址	数量
1	☑	1000	默认触发	循环	读寄存器	默认	%MW1000	⇦	16#0001	1
2	☑	1000	默认触发	循环	写寄存器	默认	%MW1000	⇨	16#0002	1

6.

M HMI



7. TCP 502 5020

socket 5020 TCP

8. Modbus TCP

TCP 6 ASCII ACK 0 ASCII

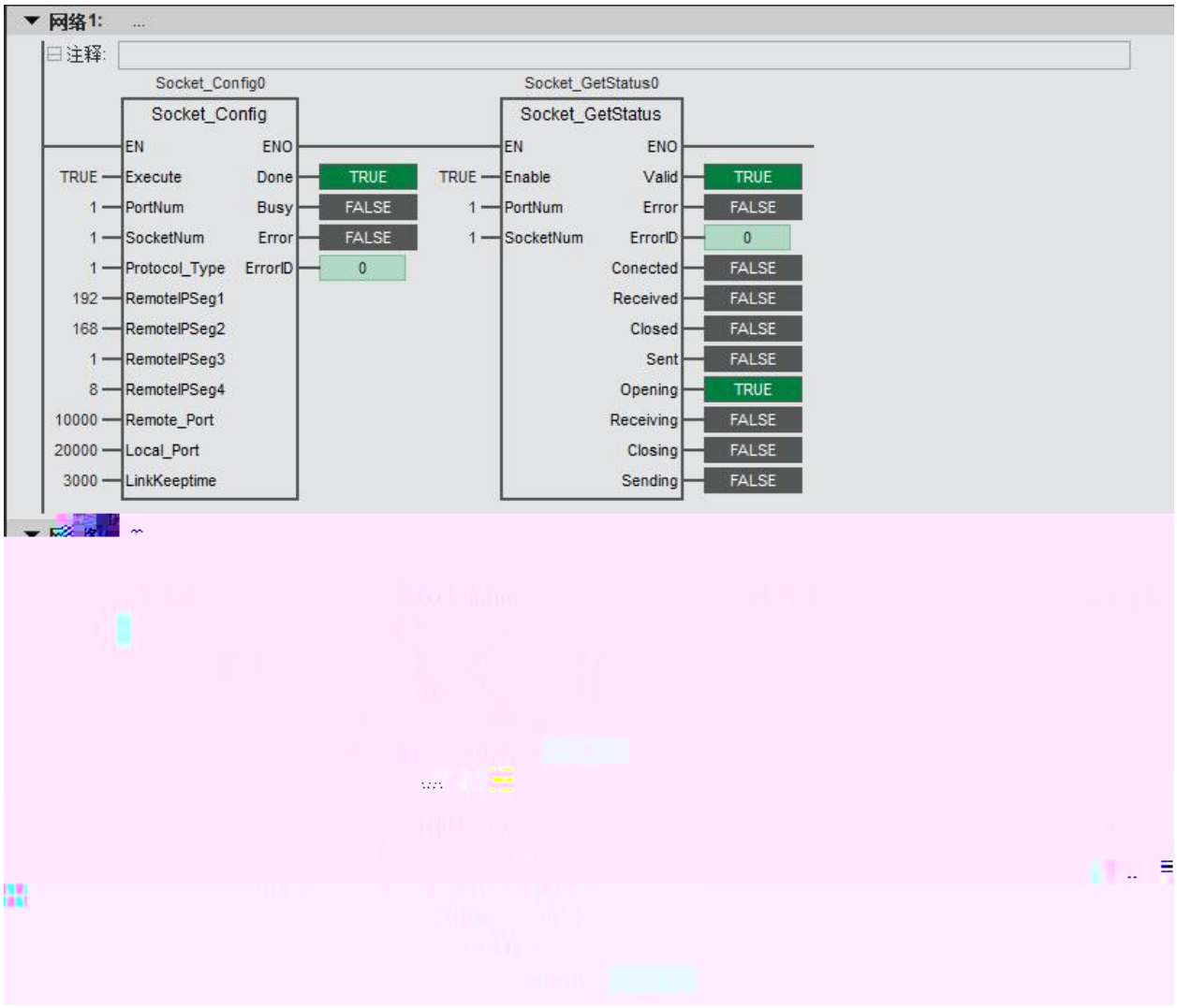
0 ASCII 0

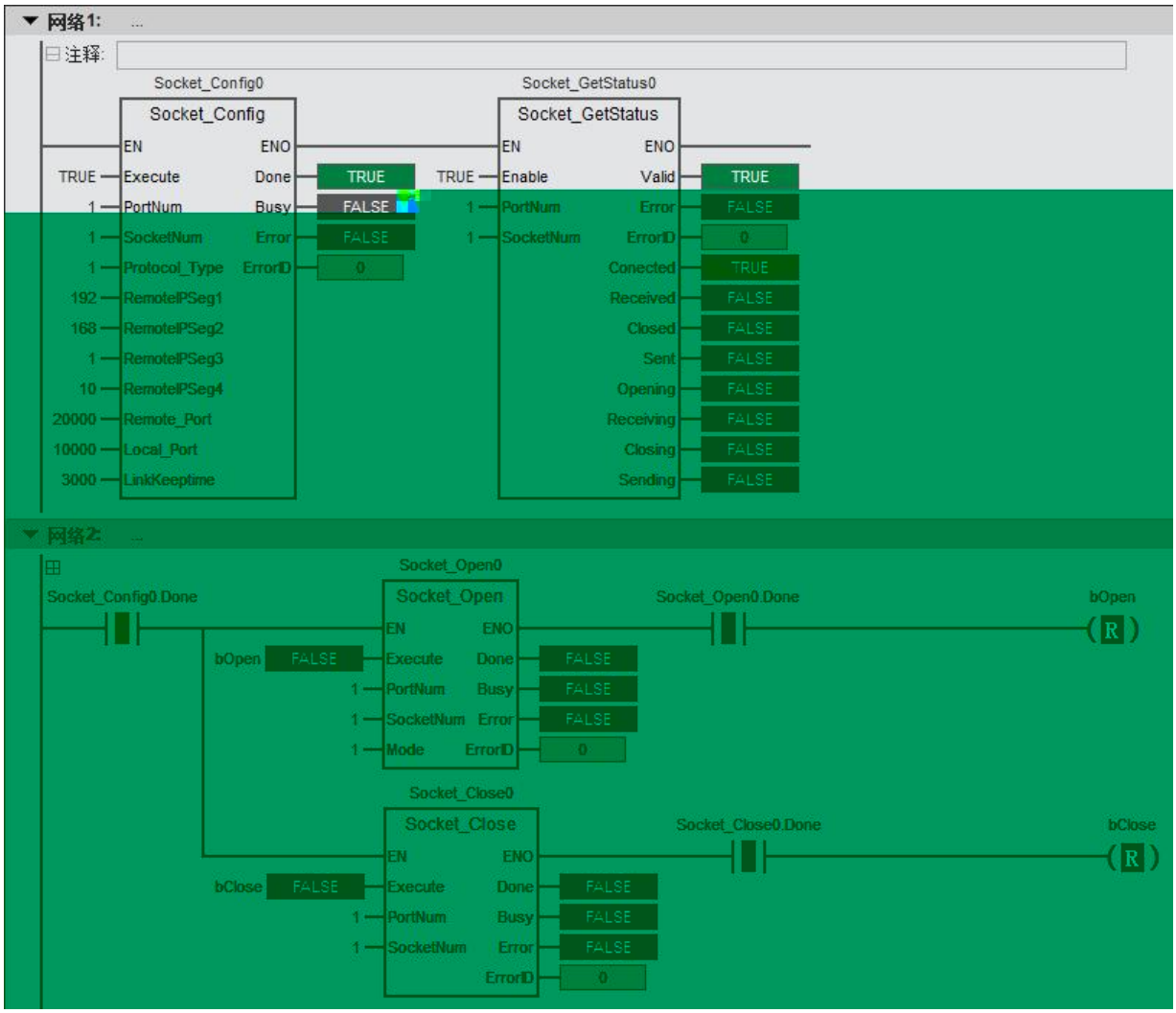
9. Socket

Socket_GetStatus Opening

Opening Socket_Open Socket Opening

Socket_Open Socket_Close Socket_Open Opening

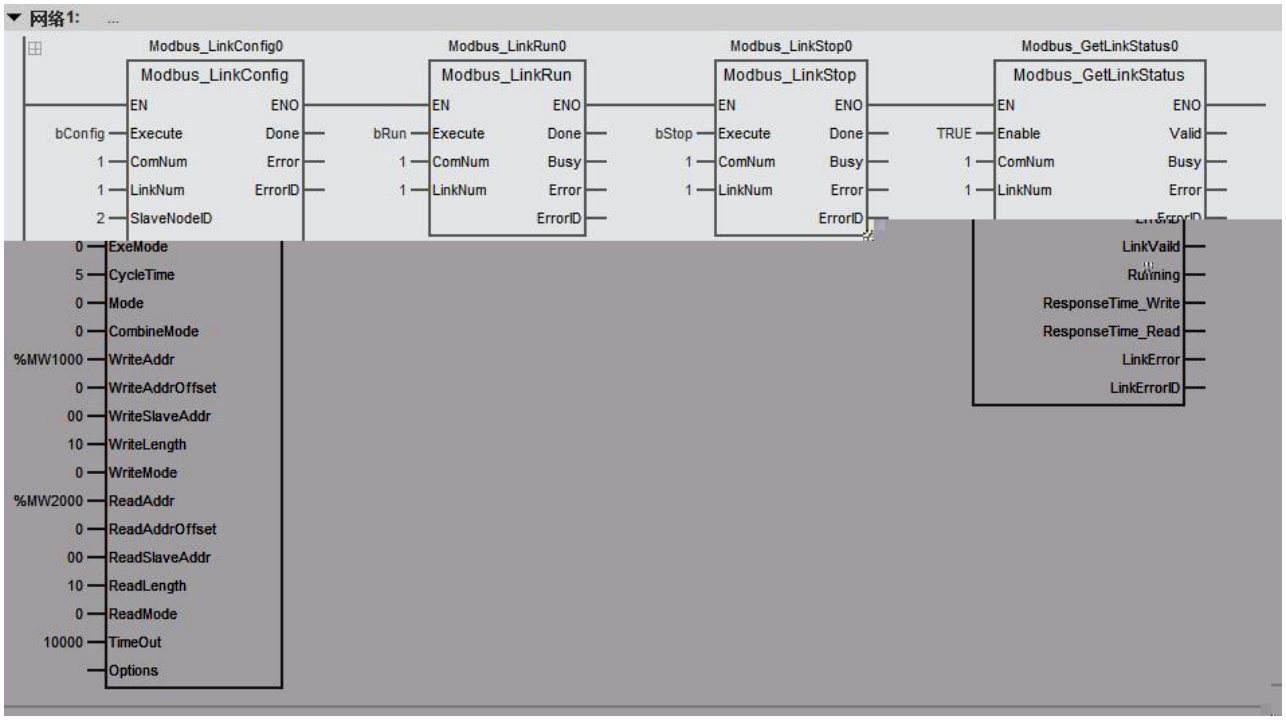




10. 485

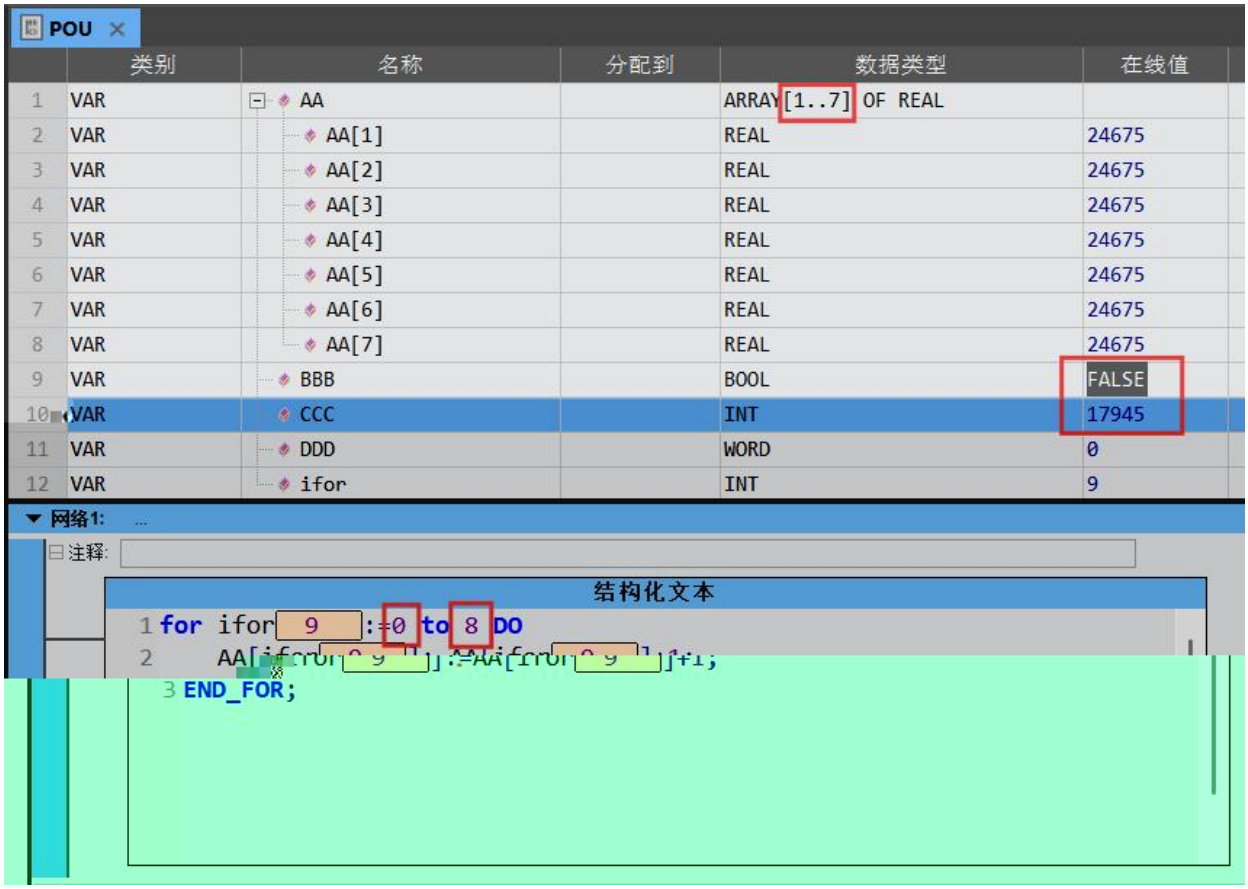
LINKCONFIG

1-Modbus_LinkConfig 2-Modbus_LinkRun 3-Modbus_GetLinkStatus 4- 5-Modbus_LinkStop


网络1:
Modbus_LinkConfig0
Modbus_LinkConfig
EN
ENO
bConfig
Execute
Done
1
ComNum
Error
1
LinkNum
ErrorID
2
SlaveNodeID
0
ExeMode
5
CycleTime
0
Mode
0
CombineMode
%MW1000
WriteAddr
0
WriteAddrOffset
00
WriteSlaveAddr
10
WriteLength
0
WriteMode
%MW2000
ReadAddr
0
ReadAddrOffset
00
ReadSlaveAddr
10
ReadLength
0
ReadMode
10000
TimeOut
Options
Modbus_LinkRun0
Modbus_LinkRun
EN
ENO
bRun
Execute
Done
1
ComNum
Busy
1
LinkNum
Error
ErrorID
Modbus_LinkStop0
Modbus_LinkStop
EN
ENO
bStop
Execute
Done
1
ComNum
Busy
1
LinkNum
Error
ErrorID
Modbus_GetLinkStatus0
Modbus_GetLinkStatus
EN
ENO
TRUE
Enable
Valid
1
ComNum
Busy
1
LinkNum
Error
LinkVaild
Running
ResponseTime_Write
ResponseTime_Read
LinkError
LinkErrorID

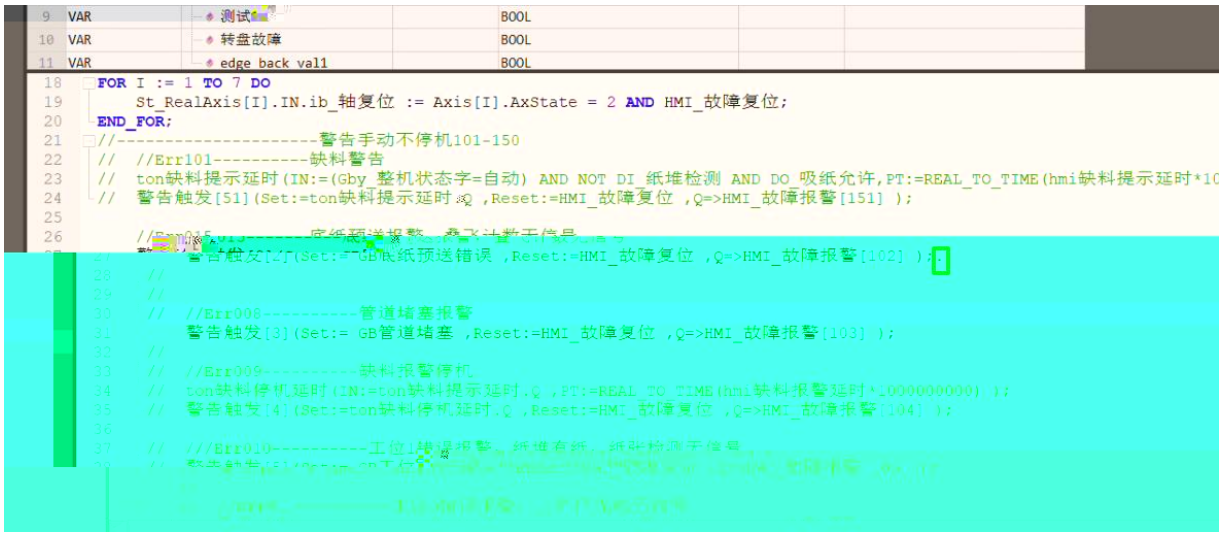
11. E600

1.



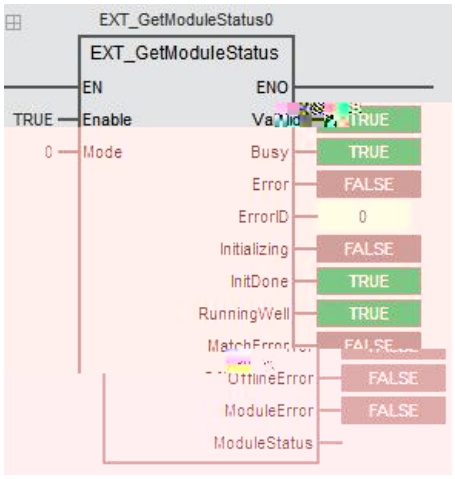
2.

“;” “.”



3.

EXT_GetModuleStatus



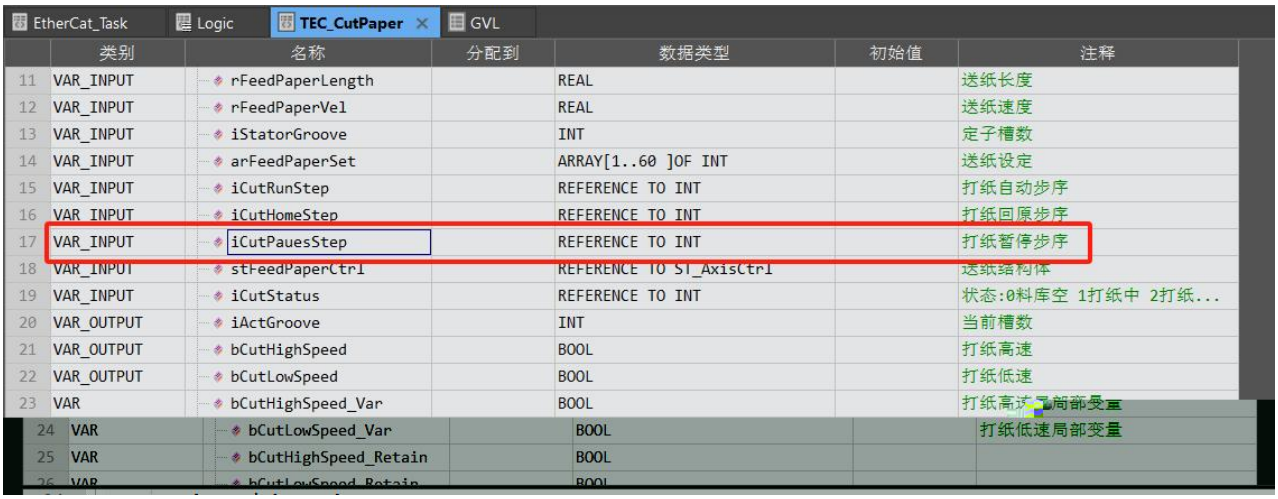
4.

PG .

5. Q

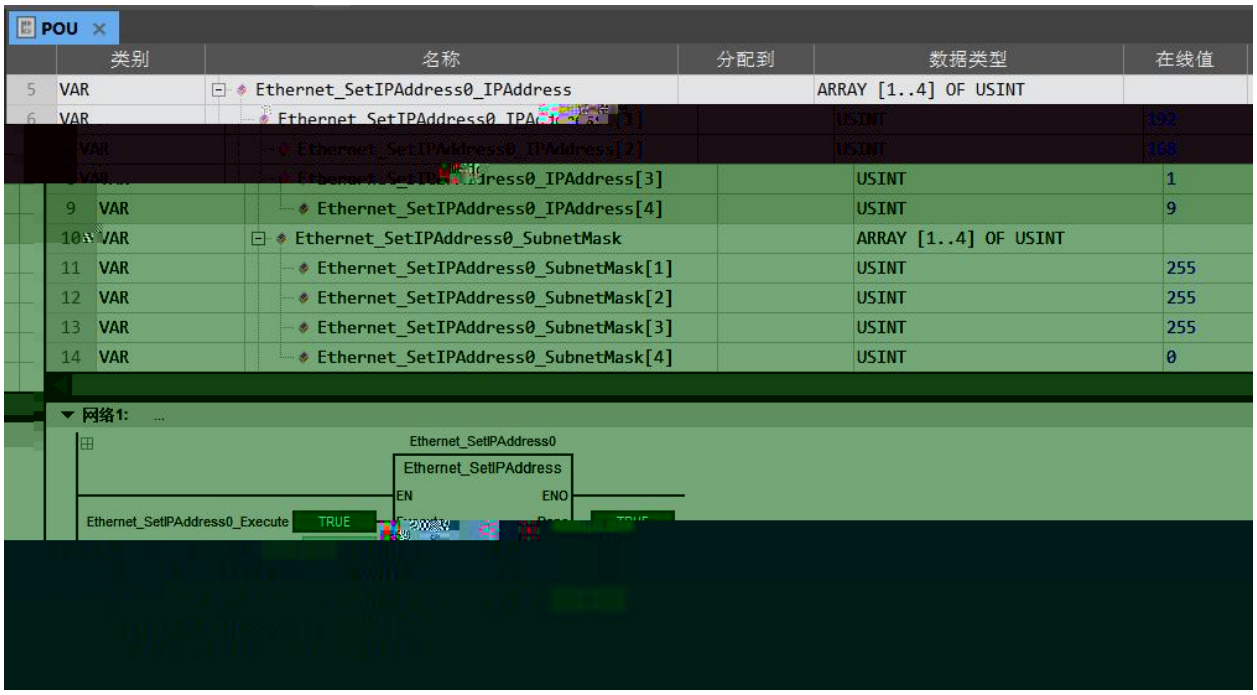
6. M511S M511 2104

CPU

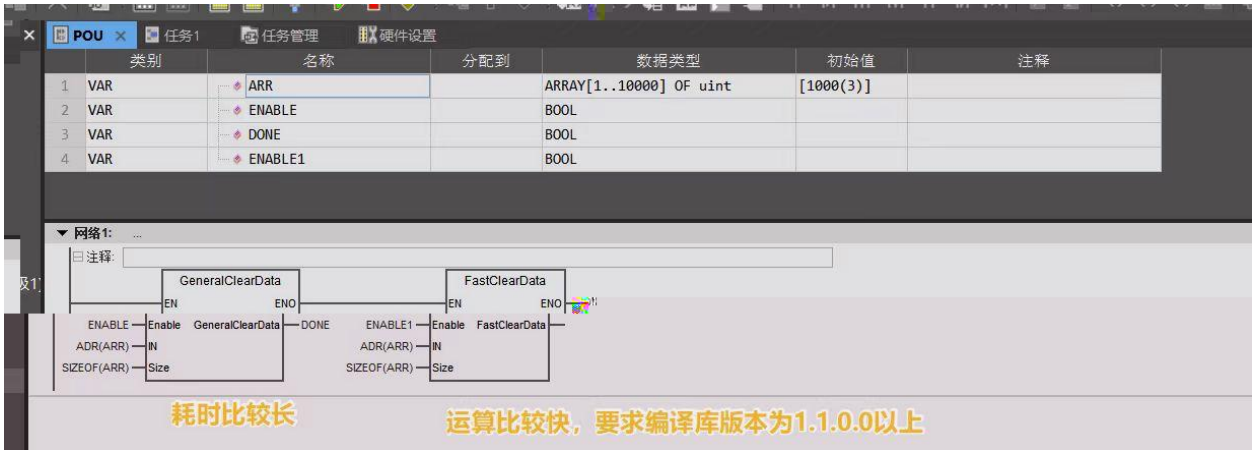


7. IP

Ethernet_SetIPAddress IP



8.



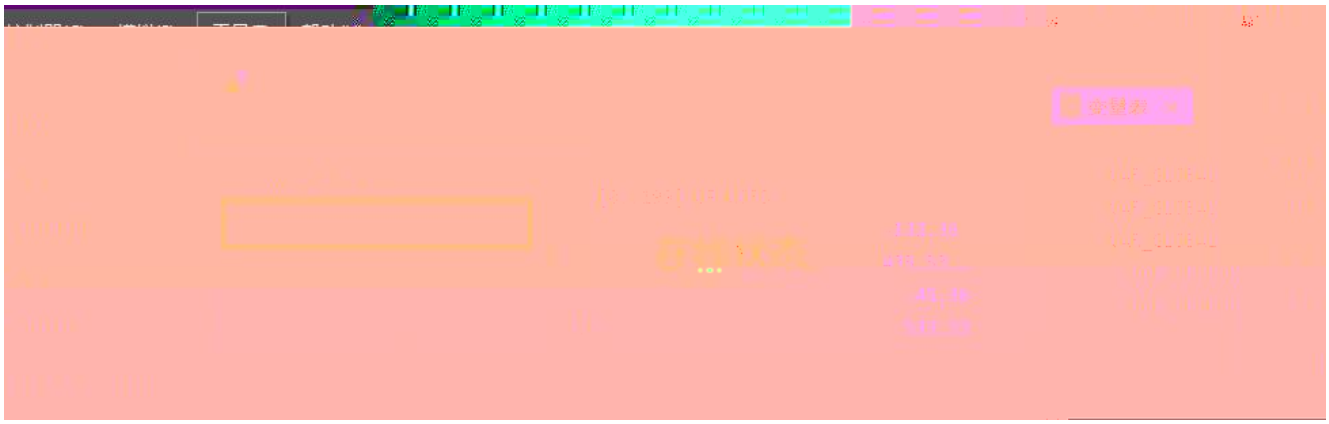
9. Time to DINT

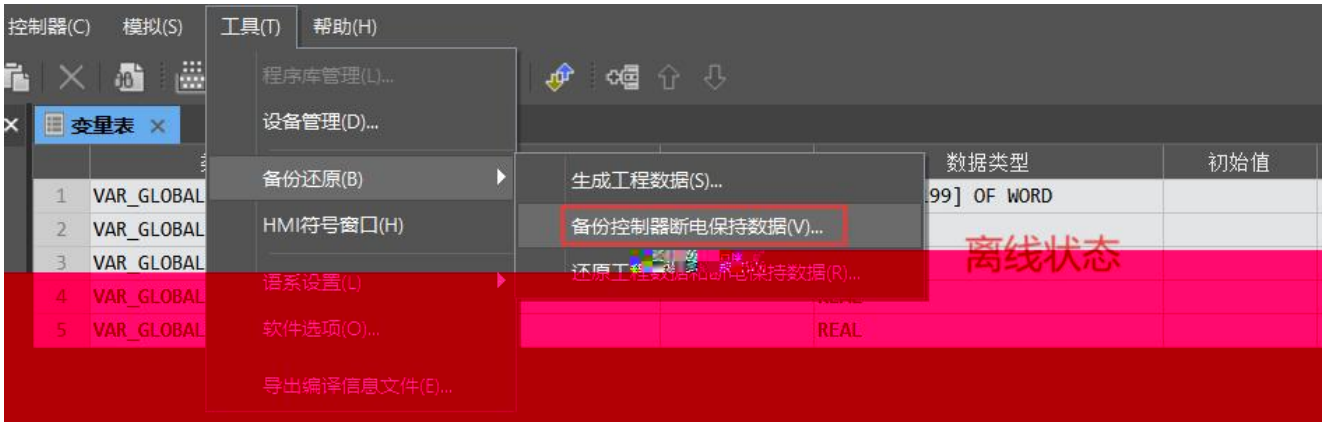
DINT 65536 ns ULINT

10. 16#2103

2ms 3ms 4ms

11.



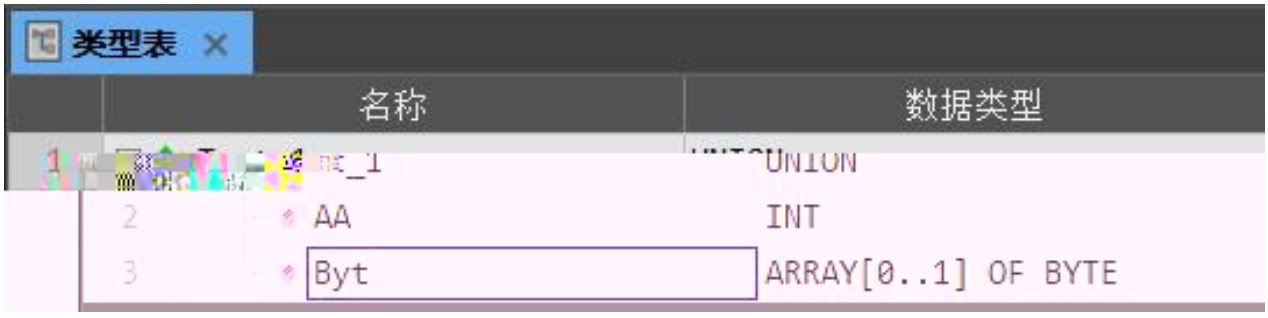


12. M514

13. 4-20ma 200 200

200 200 4-20ma 0ma

14. INT



15. TIME

TIME modbus

16.

80+1 1 modbus

17. ID

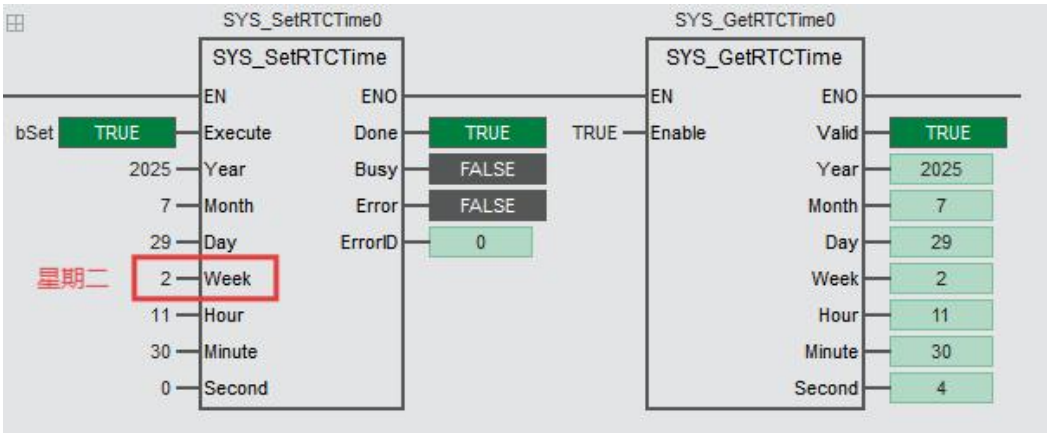
ID PLC

18. M RTC

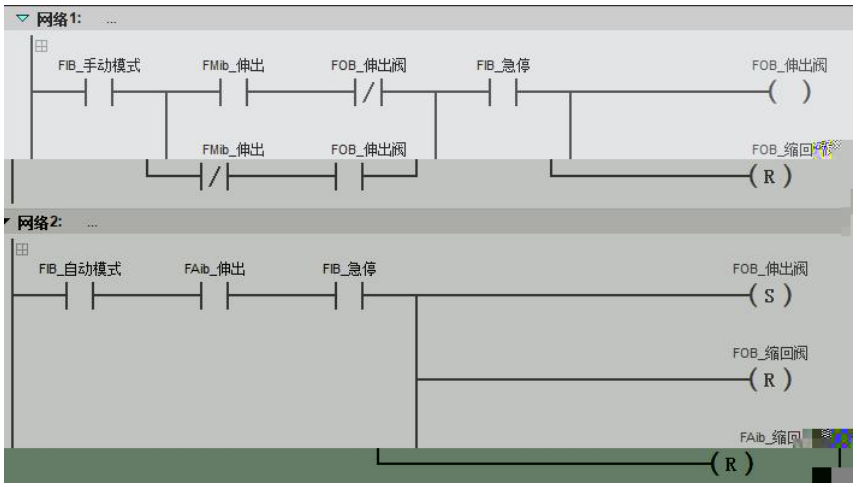
Sysctrl Studio 2.4.0.1705 SYS_SetRTCTime M100 M200 M300 M500 M500S

19. RTC 16690

week 1-7



20.

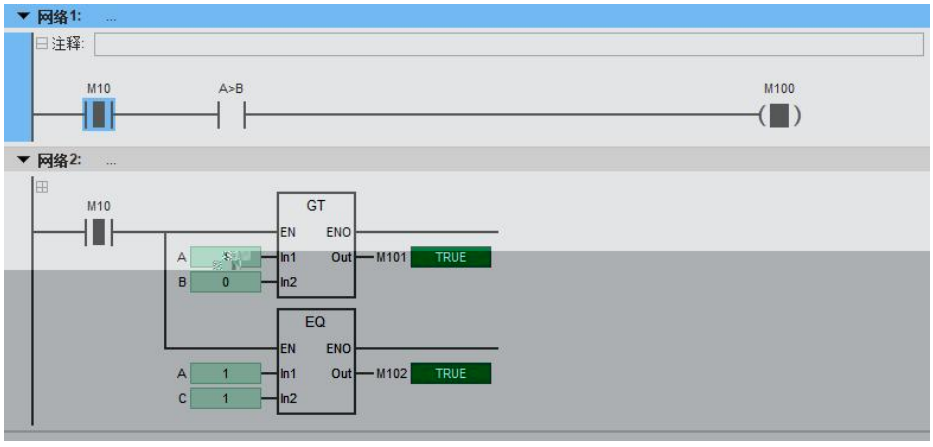

网络1:
FIB_手动模式
FMib_伸出
FOB_伸出阀
FIB_急停
FOB_伸出阀
FMib_伸出
FOB_伸出阀
FOB_缩回阀
R
网络2:
FIB_自动模式
FAib_伸出
FIB_急停
FOB_伸出阀
S
FOB_缩回阀
R
FAib_缩回
R

21.

- - - “

器(C)
模拟(S)
工具(T)
帮助(H)
程序库管理(L)...
备份还原(B)
HMI符号窗口(H)
语系设置(L)
软件选项(O)...
软件选项
基础设置
自动保存
间隔时间(分钟)
3
编译后询问是否要修正所有的 "边沿检测操作必须传入两个参数" 编译错误
确定
取消
应用

22.

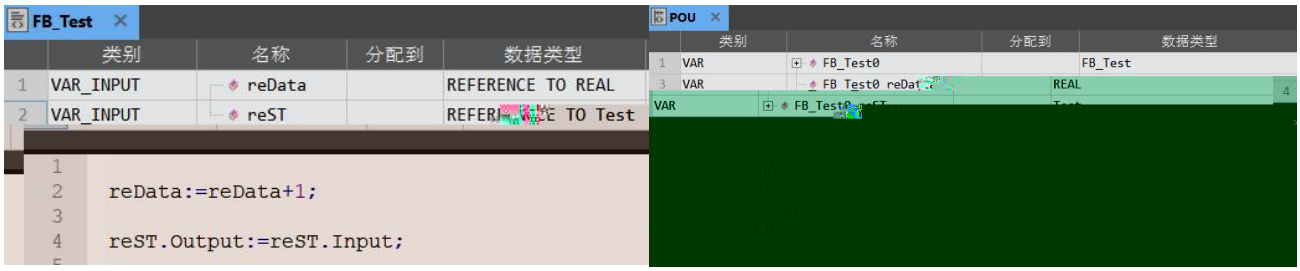

网络1:
注释:
M10
A>B
M100
网络2:
M10
GT
EN
ENO
A
In1
Out
M101
TRUE
B
0
In2
EQ
EN
ENO
A
1
In1
Out
M102
TRUE
C
1
In2

23.

V+ I+

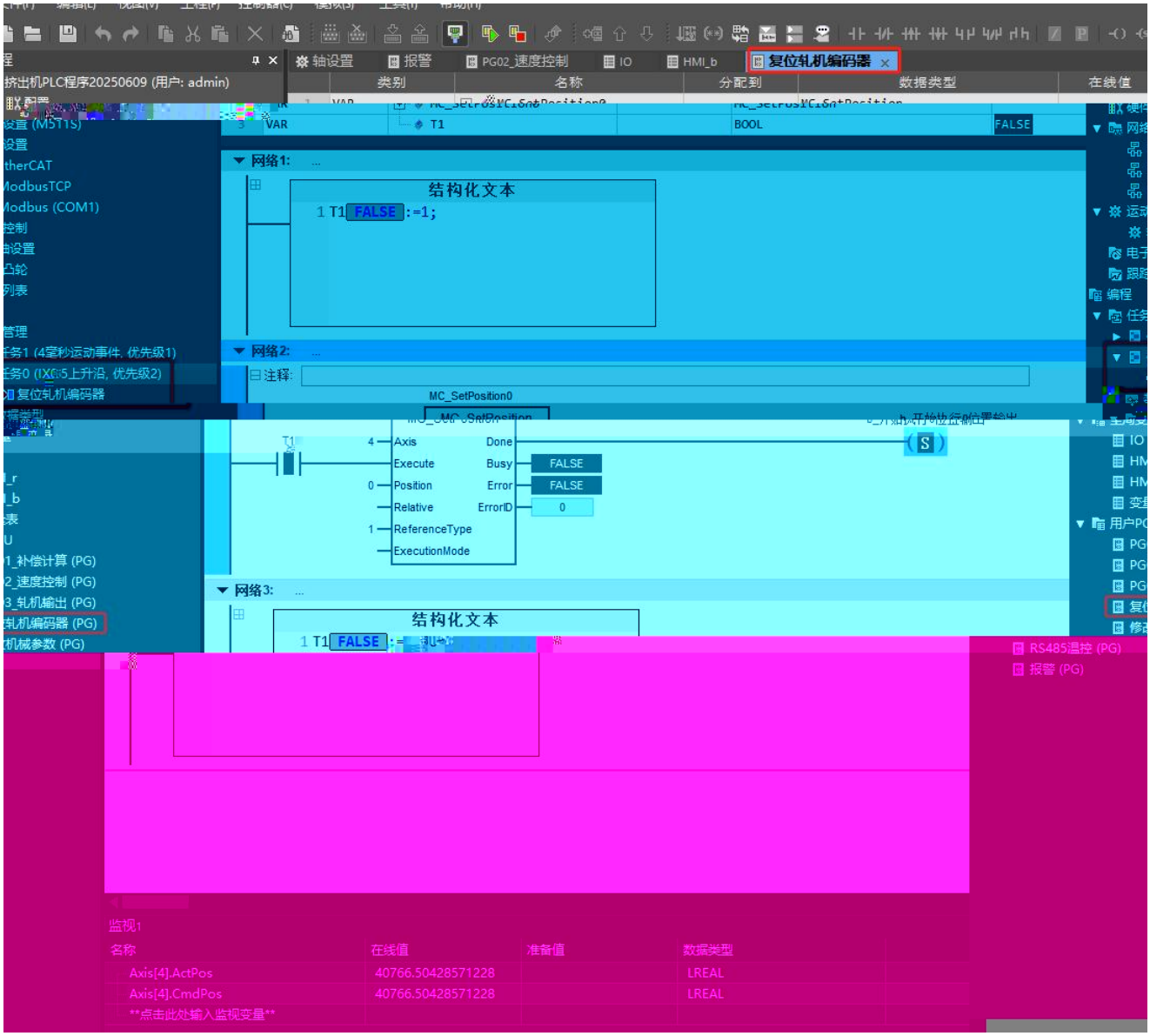
24. F I

Sysctrl Studio 2.4.1705 صھ ھغ ؤ ـئھ g̃ t


FB_Test
类别
名称
分配到
数据类型
1 VAR_INPUT reData REFERENCE TO REAL
2 VAR_INPUT reST REFERENCE TO Test
1
2 reData:=reData+1;
3
4 reST.Output:=reST.Input;
POU
类别
名称
分配到
数据类型
1 VAR FB_Test0 FB_Test
3 VAR REAL
4
VAR

1. MC_Setposition

MC_Setposition



2. 6064 PLC

6064

1:400 23 1 8388608 230.4mm 6064

PLC 6064

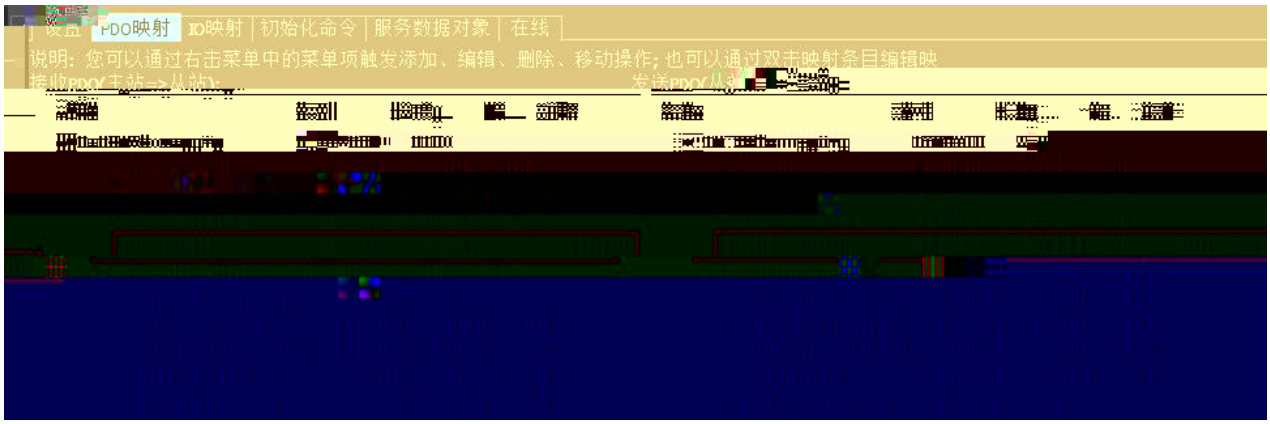
23 +Y7S

M 100000 Y7S Pn78C 8388608 Pn78E 100000

3. M511S M511

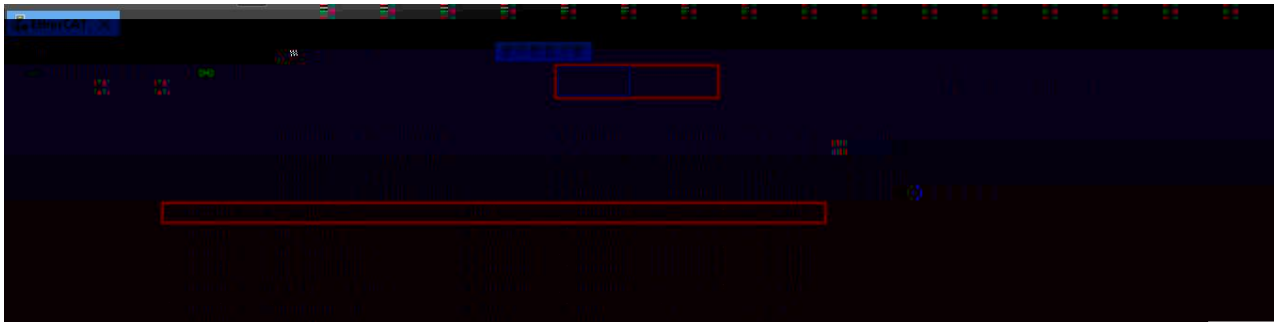
M500 PLC PDO XML

PDO 6077 6071



MC_TorqueControlWithVelocity 6080

6080 6080 6080 0 0 10000



4.

M -

5. 200 50-80

MC_TorqueControl InTorque Axis[].ActTrq

6. MC_HomeByPLCIO

On

7.

Jerk Jerk

8.

MC_StopAtPhase

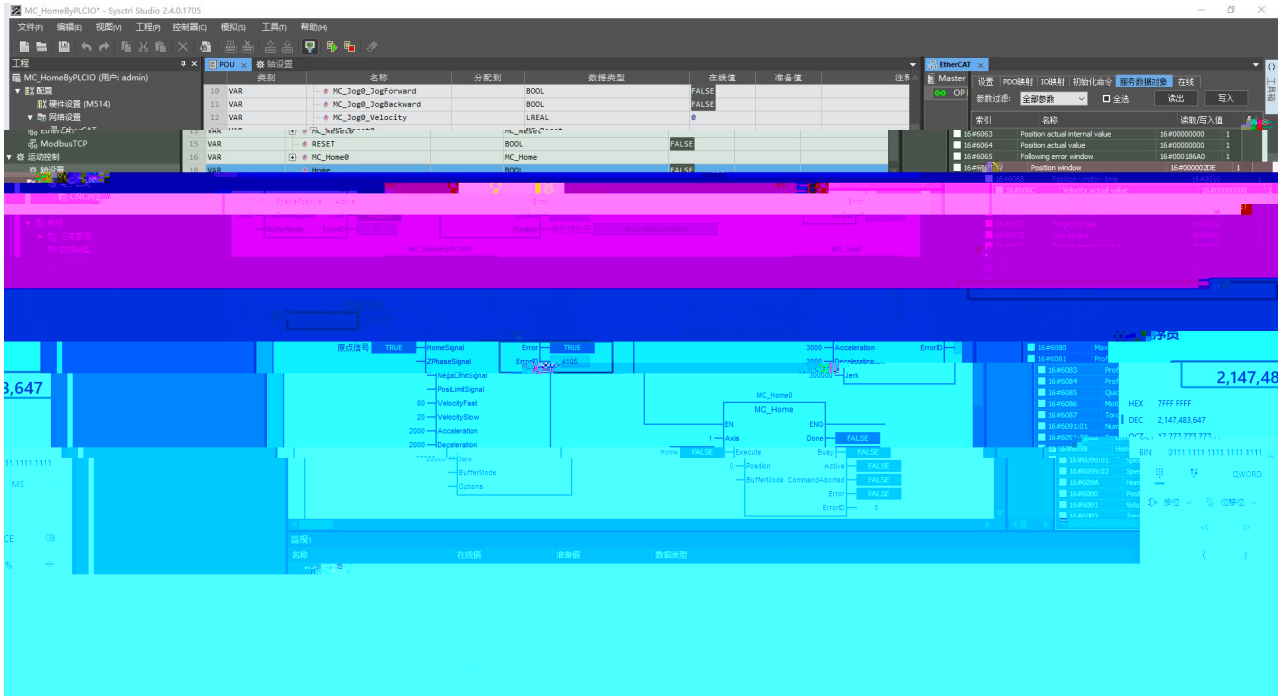
9. MC Stop MC_MoveContinuousVelocity 5377

MC_MoveContinuousVelocity stopping

10. MC_HomeByPLCIO 20 4105

8388608 1:10 150 3839

3839/150*10*8388608=2146924407 607C 2,147,487,744

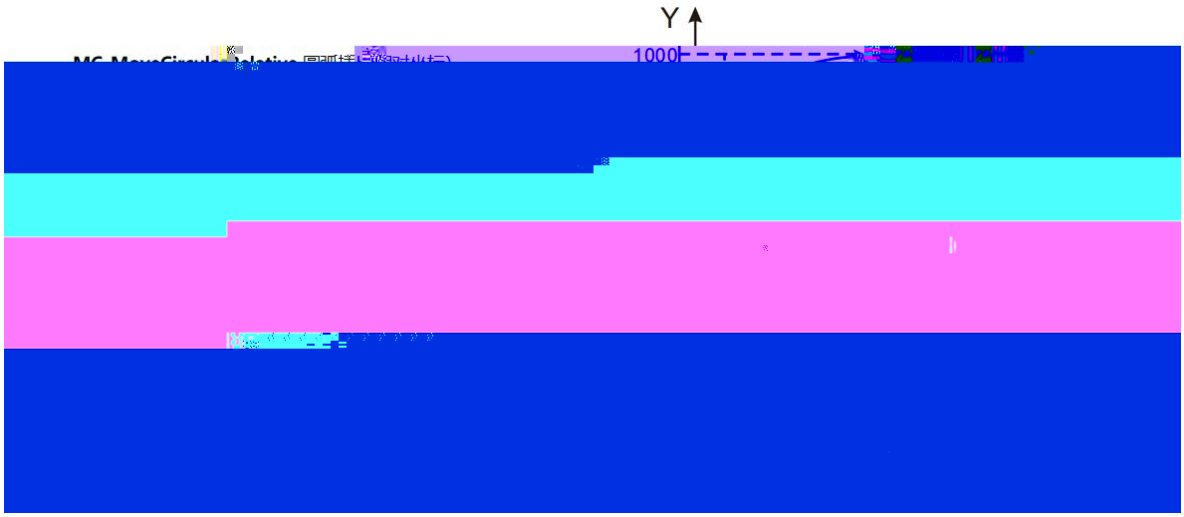


11. 4612

50 0 50 0 0

0 MC_Setposition 0

12. XY 20 4618



13. MC_HomeByPLCIO homing

PDO 6060

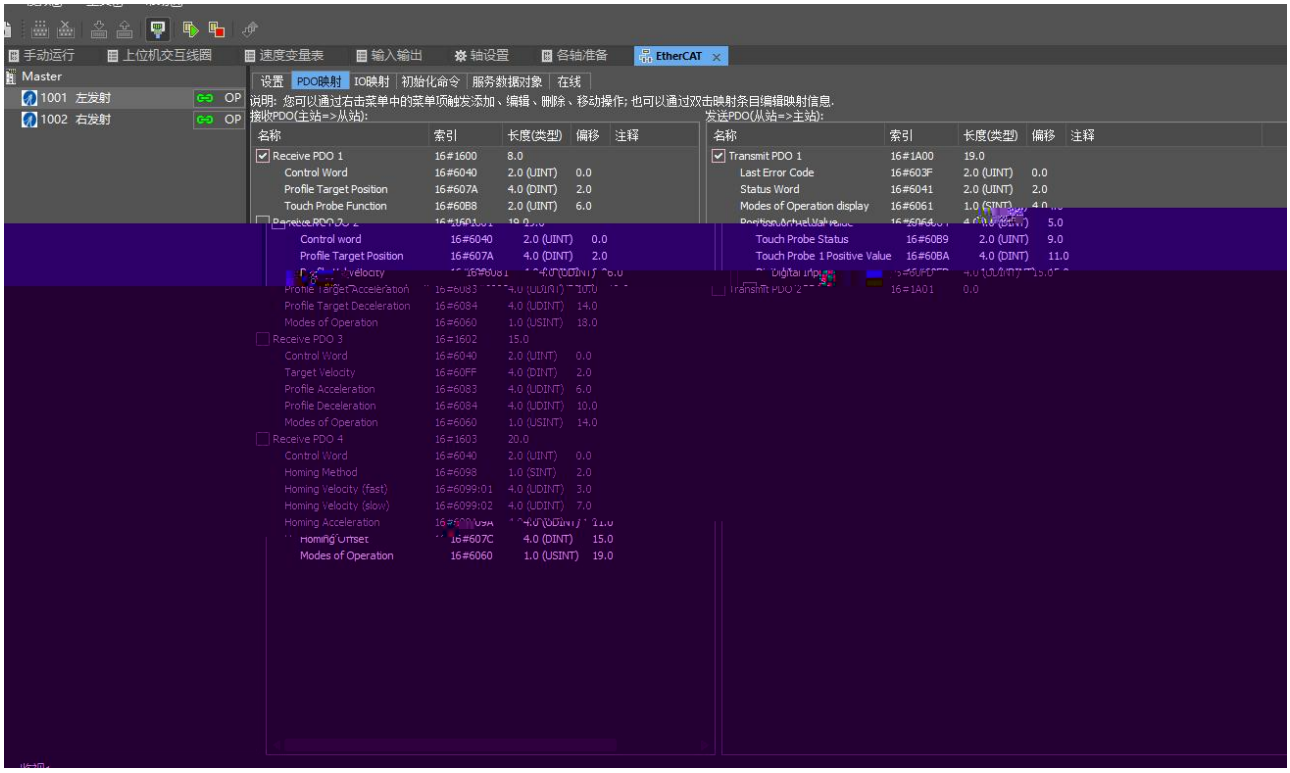
PDO 6060 6061 6040 6041 607A 6064

14.

Jerk JerkLimit 1E30

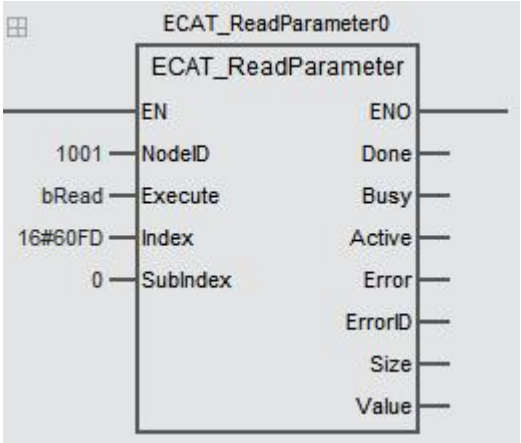
15. M512 op

pdo pdo



16. DI

ECAT_ReadParameter DI SDO



17.

ECAT_ReadParameter,ECAT_WriteParameter ECAT

PDO 1

18. 4123 096

19. MC_GearIn InGear Eexcute

MC_GearIn MC_GearIn

Eexcute InGear

20. 16#2151

16#2151

21.

360 3600

22.

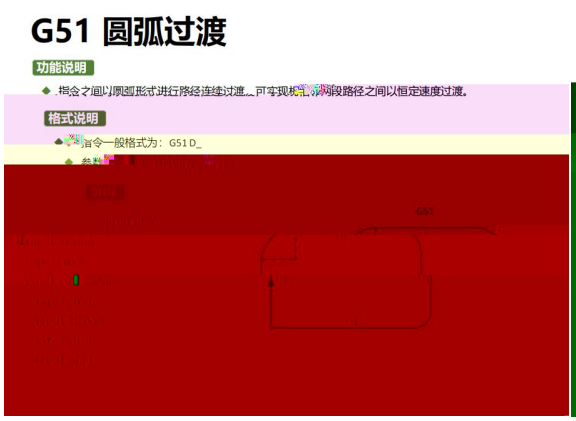
ECAT_WriteParameter SDO 16#60E0 16#60E1

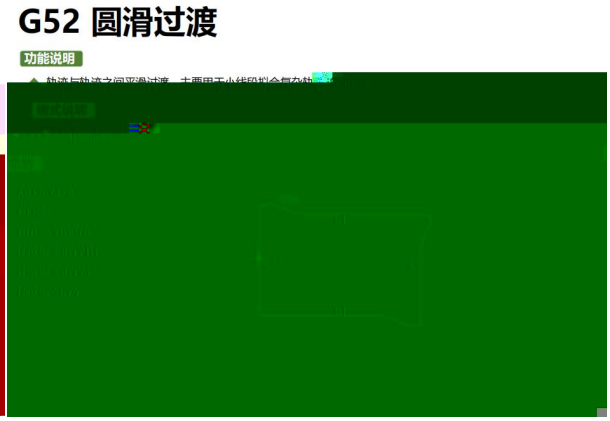
23. M511S M511 4116

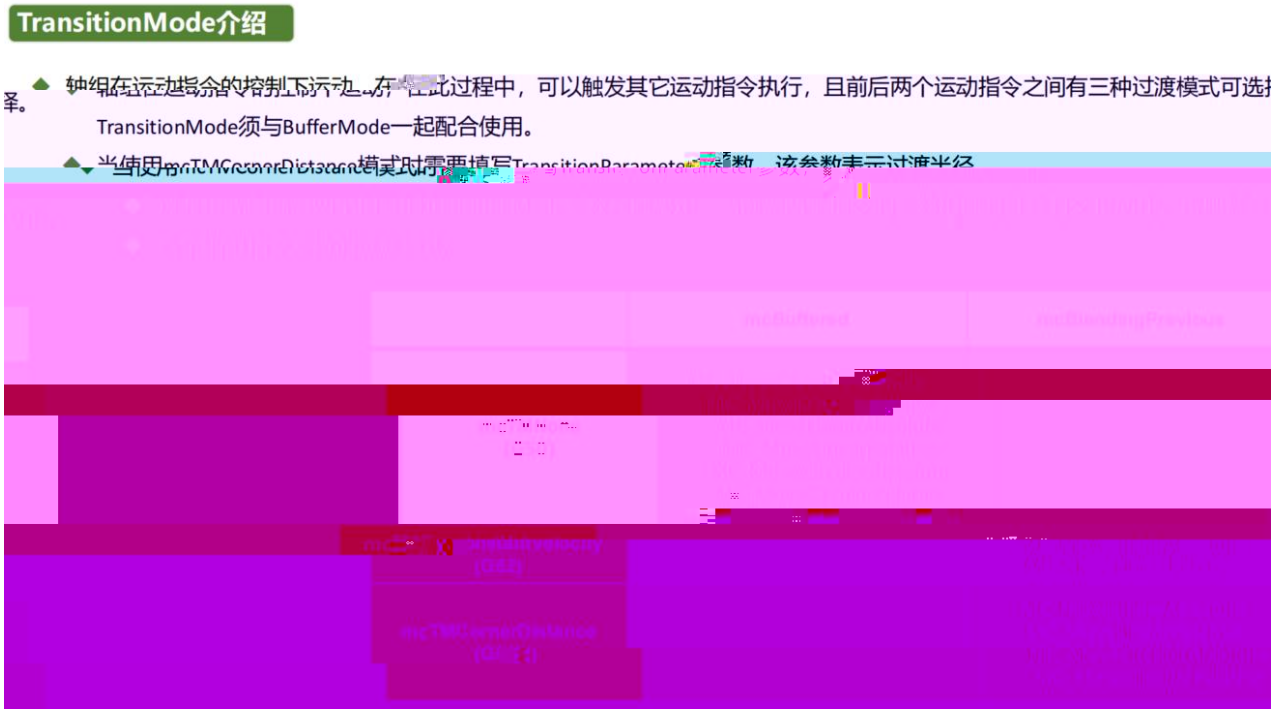
M500 1.0-1.7 TriggerInput 8-15

24. 3,2

CNC G52







25.

6080

26.

JERK 1000

27. MC_SetPosition

IF

```
IF bSetCon THEN
    MC_SetPosition1(
        Axis:=1 ,
        Execute:=bSetPosition ,
        Position:= ,
        Relative:= ,
        ReferenceType:= ,
        ExecutionMode:= ,
        Done=> ,
        Busy=> ,
        Error=> ,
        ErrorID=>
        );
END_IF;
IF MC_SetPosition1.Done THEN
    bSetCon:=FALSE;
END_IF;
```

```
MC_SetPosition1(
    Axis:=1 ,
    Execute:=bSetPosition AND bSetCon ,
    Position:= ,
    Relative:= ,
    ReferenceType:= ,
    ExecutionMode:= ,
    Done=> ,
    Busy=> ,
    Error=> ,
    ErrorID=>
    );
IF MC_SetPosition1.Done THEN
    bSetCon:=FALSE;
END_IF;
```

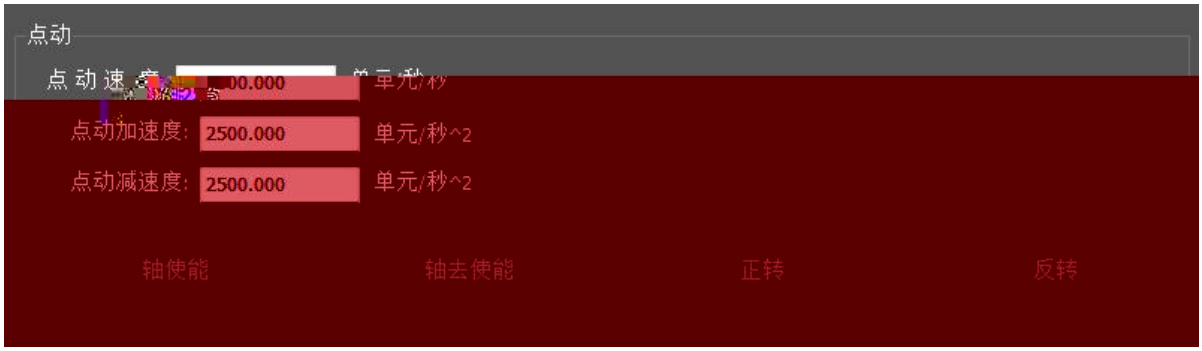
28. MC_SetPosition 0 Axis[].cmdPos 0

MC_SetPosition MC_ReadActualPosition

29. AXIS[1].CMDPOS

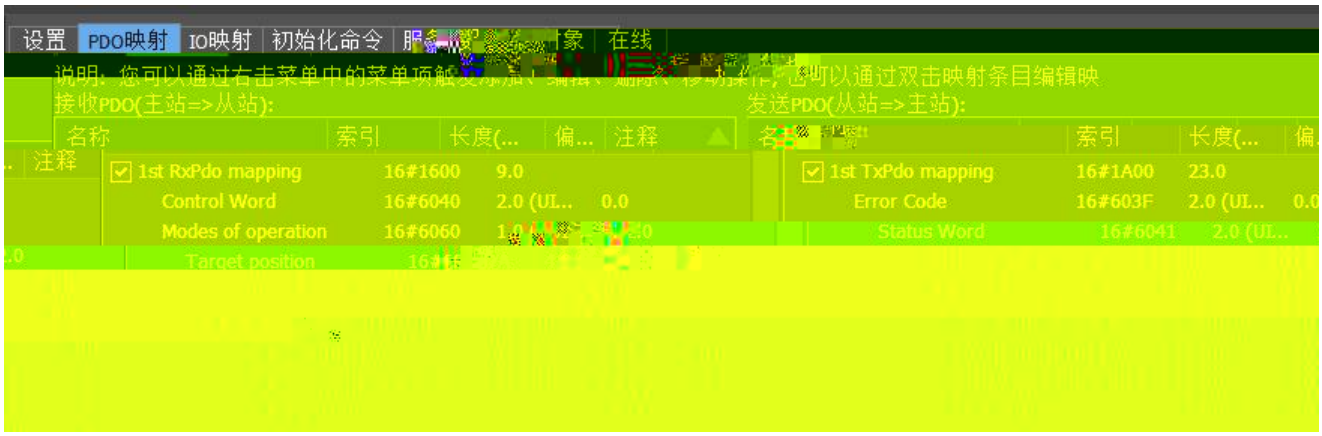
31. M511 Y7S

10000 / plc 10000 / plc



32. M512

M500 PDO PDO 16#606C M



33. Z

Z Axis[1].CmdPos

34.

1,000x1 ÷ 69x131,072=1,899,594.2028985 200Khz

1000

35.

+SetPosition MC_SetOverride 0

36. 4107

buffermode 1 3 0

37.

MC_EncoderCompare M100 M200 M300 M500S

38. MC_home 30 4105

30*10*8388608=2,516,582,400 607C

39. SV730W 4866

730W XML 6080 16#607F

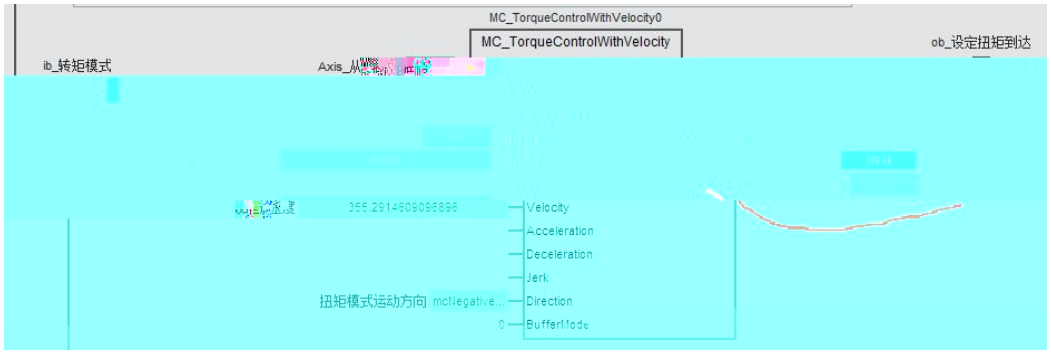
40. MC_TorqueControlwithVelocity 4865

SDO PDO

1) 1ms SDO

2) SDO SDO

SDO SDO



41.

MC_SetCamPoint

MC_GetCamPoint

42. 0

MC_CAMIN MasterValueSource

1 1

43.

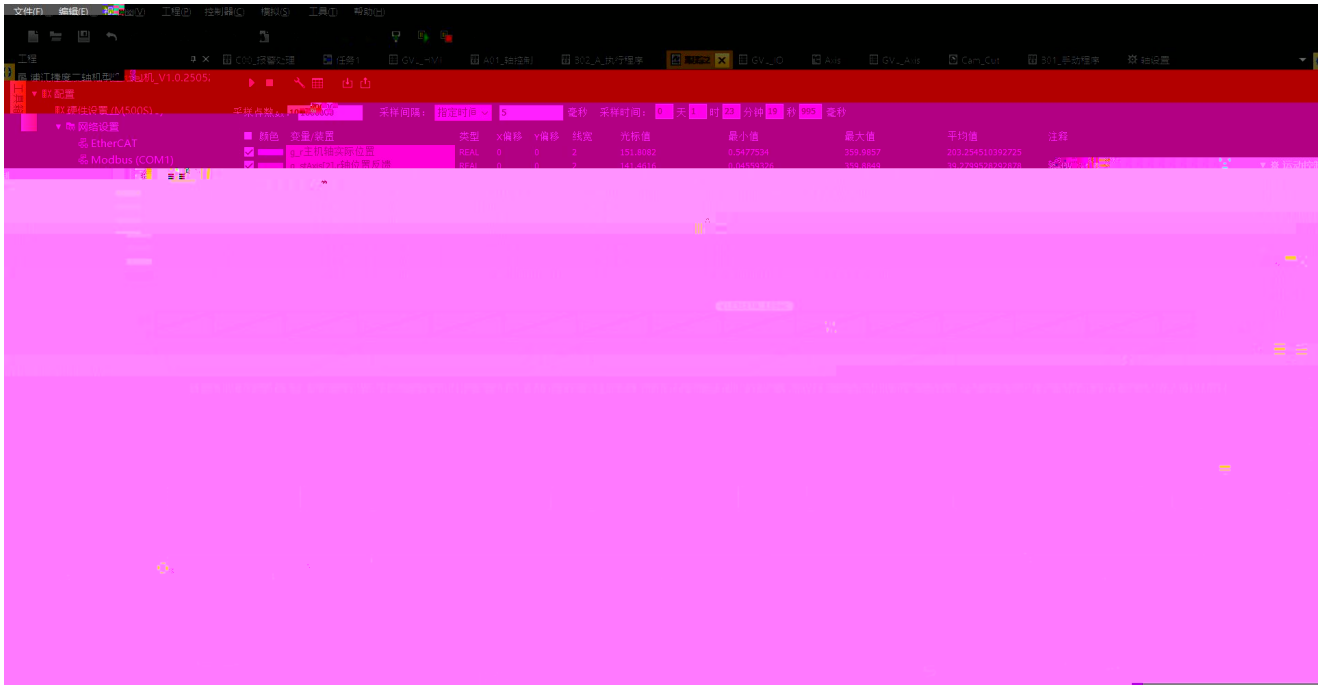
CAM

44. 1:1

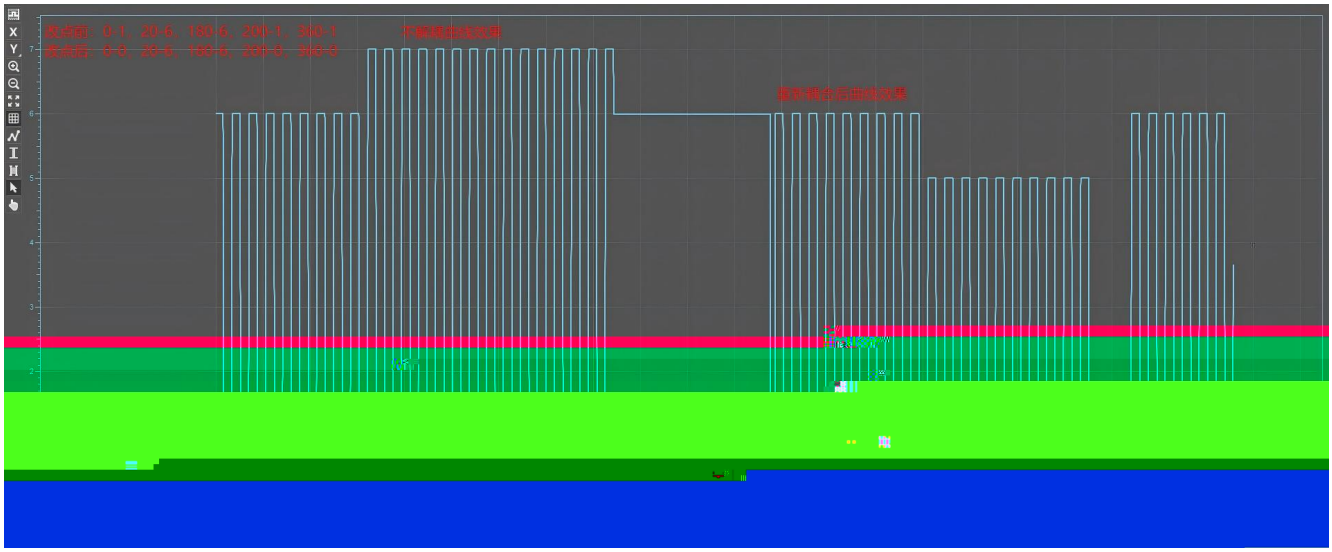
1 camin

AB

2 0 0



45.



1. ——RUN

ERR

2. ——

IP

STOP

3. ——

Sysctrl Studio

4. ——

PLC 0.0

5. M :

Sysctrl Studio

6. M512

500 500

7. “ ”

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https://blog.csdn.net/qq_33188565/article/details/112859534

8.

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9. 16#2111

10. RUN PLC STOP