System Manual
sysWORXX CTR-700

User Manual

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1 Introduction

Thank you that you have decided for the SYS TEC sysWORXX CTR-700. This product provides to you an innovative, Linux-based and high-capacity compact controller to process standard industrial signals. Due to its numerous in- and outputs and communication interfaces it is well-suitable as central control in distributed automation appliances.

Please take some time to read through this manual carefully. It contains important information about the commissioning, configuration and programming of sysWORXX CTR-700. It will assist you in getting familiar with the functional range and usage of the sysWORXX CTR-700. This document is complemented by other manuals, e.g. for the *OpenPCS* IEC 61131 programming system. Table 1 in section 2 lists relevant manuals for sysWORXX CTR-700. This table also references documentation to other software components and programming languages which are supported by the sysWORXX CTR-700 such as Node-RED, C# or Java. Please also refer to those complementary documents.

For more information, optional products, updates et cetera, we recommend you to visit our website: https://www.systec-electronic.com/. The content of this website is updated periodically and provides to you downloads of latest software releases and manual versions.

2 Overview / Where to find what?

Table 1 lists all manuals relevant for CTR-700. To program the CTR-700 as PLC according to IEC 61131-3, the programming environment *OpenPCS* is used. There are also some manuals for *OpenPCS* that describe the usage and SYS TEC-specific extensions. Those are part of the software package *"OpenPCS"*.

Table 1: Overview of relevant manuals for the CTR-700

Information about…	**In which manual?**
Basic information about the CTR-700 (connections, configuration, administration, process image)	In this manual
Basics about the *OpenPCS* IEC 61131 programming system	Brief instructions for the programming system (Entry "*OpenPCS Dokumentation*" in the *OpenPCS* program group of the start menu) (Manual no.: L-1005)
Complete description about the *OpenPCS* IEC 61131 programming system, basics of PLC programming according to IEC 61131-3	Online help about the *OpenPCS* programming system
Command overview and description of standard function blocks according to IEC 61131-3	Online help about the *OpenPCS* programming system
SYS TEC extension for IEC 61131-3: - String functions - UDP function blocks - SIO function blocks - FB for RTC, Counter, EEPROM, PWM/PTO	User Manual *"SYS TEC-specific extensions for OpenPCS / IEC 61131-3"* (Manual no.: L-1054)
CANopen extension for IEC 61131-3 (network variables, *CANopen* function blocks)	User Manual *"CANopen extension for IEC 61131-3"* (Manual no.: L-1008)
Textbook about PLC programming according to IEC 61131-3	IEC 61131-3: Programming Industrial Automation Systems John/Tiegelkamp Springer-Verlag ISBN: 3-540-67752-6 (a short version is available as PDF on the *OpenPCS* installation CD)

One can also use Node-RED, Java or C# to program the CTR-700. The following table provides links to the websites of those projects. On these sites you will also find guides and references on how to use these programming environments for developing applications. Getting started with these environments on the sysWORXX CTR-700 is described in this document.

Project	Website
Node-RED	https://nodered.org/
Mono / C#	http://www.mono-project.com/
OpenJDK / Java	http://openjdk.java.net/

Section 0 this manual describes **electric connections** of CTR-700 and their application; moreover, it documents their **internal structure**.

Section 5 makes available **details about the configuration of CTR-700**, e.g. the configuration of Ethernet and CAN interfaces, the configuration of Linux services and the selection of the firmware version. In addition, the **administration of CTR-700** is explained, e.g. the login to the system, the user administration and the execution of software updates.

Section 6 provides basic information on how to enable Node-RED on the CTR-700 and how to use the custom nodes to access digital inputs and outputs, or to access OpenPCS variables.

Section 7 provides information on how to develop and debug Mono/C# applications in form of a step-by-step guide of a sample project, which uses the I/O driver for the sysWORXX CTR-700.

Section 8 provides information on how to develop and debug Java applications in form of a step-by-step guide of a sample project, which uses the I/O driver for the sysWORXX CTR-700.

Section 9 includes details about the **usage of CTR-700**, e.g. the **setup of the process image**, the **meaning of control elements** and this section provides basic information about programming the module. Furthermore, it gives information about the usage of CAN interfaces in combination with **CANopen**.

Section 10 covers information about data exchange between a PLC program and a user-specific C/C++ application via **shared process image**.

3 Product Description

The sysWORXX CTR-700 extends the SYS TEC electronic GmbH product range within the field of IoT and control applications. It is an innovative, Linux-based compact controller for universal processing purposes of standard industrial signals. The controller module provides to the user numerous local in- and outputs as well as versatile communication interfaces. Due to CAN and Ethernet interfaces, the CTR-700 is suited for realizing decentral control tasks in distributed fieldbus systems of automation technology.

Figure 1: Top view of CTR-700

These are some significant features of CTR-700:

- Linux-based compact PLC for industrial controls
- High-capacity CPU kernel (Freescale i.MX7 series Dual ARM Cortex-A7 Core 1GHz, Real-time Core Cortex-M4 200MHz)
- Up to 1024 MiB RAM, 8GiB eMMC FLASH Memory
- 1x USB 2.0 Host interface
- 2x 10/100 Mbps Ethernet LAN interface
- 2x CAN 2.0B interface, usable as CANopen Manager (CiA 302-conform)
- 3x asynchronous serial ports (UART), usable as RS-232 or RS-485
- 16 digital inputs 24VDC, galvanic isolated
    - Alternate function: 1 high-speed counter inputs 24VDC(50kHz), galvanic isolated[1]
    - Alternate function: 1 A/B-Encoder[2]
- 16 digital outputs 24VDC/500mA, galvanic isolated, short-circuit-proof
    - Alternate function: 2 PWM/PTO[3] outputs 24VDC/500mA 1KHz
- 2 Relay outputs 250VAC/3A (2x two-way contact)
- 4 analog inputs 0-10VDC or 0-20mA with 12-Bit resolution
- RTC (with buffer capacitor)
- 2 temperature sensors, CPU and System temperature

[1] Counter functionality is not implemented yet. It will be available in a future release.
[2] A/B Encoder functionality is not implemented yet. It will be available in a future release.
[3] PTO functionality is not implemented yet. It will be available in a future release. The PWM functionality is already available.

- On-board software: Linux, PLC firmware with CANopen Master, Node-RED, HTTP and SFTP server
- Programmable according to IEC 61131-3, C/C++, C#, Java and Python
- Function block libraries for communication (CANopen, Ethernet and UART)
- Function block libraries for hardware components (RTC, Counter, PWM/PTO)
- Linux-based (other user programs are executable in parallel)
- Easy, HTML-based OpenPCS configuration via web browser
- Remote login via SSH
- Dimensions: 162 x 91 x 60mm
- Temperature 0° … 55°C
- Suitable for DIN top hat rail mounting

The default CTR-700 comes with a Linux operating system. This base system can be used to program in different programming languages and also provides the Node-RED programming environment. Some additional hardware and software components are also available:

Order no.: 16061000:	sysWORXX CTR-700 with basic Debian/GNU Linux installation, including microUSB cable for serial terminal via SERVICE plug
Order no.: 16062000:	Meshnet Extension sysWORXX RFG-2.4
Order no.: 240011:	Runtime license OpenPCS RT sysWORXX CTR-700
Order no.: 240012:	Runtime license OPC-UA basis server sysWORXX CTR-700

One can also buy the sysWORXX CTR-700 BSP KIT which includes all products for an easy entry point to developers.

Order no.: KIT-177: sysWORXX CTR-700 BSP KIT IoT, which includes:

- 16061000: sysWORXX CTR-700
- 192016: USB-Stick with virtual machine incl. Compiler / Demos
- 193006: sysWORXX phase tester
- L-2199: Download Instructions
- L-1190: ESD Handling Instructions

The CTR-700 is an all-round PLC for complex industrial control tasks. As Linux-based compact controller, the module is programmable in C/C++, C#, Java and Python and in IEC 61131-3. Also, the Node-RED node editor is available. All of these options allow highly efficient software development for this module. The on-board firmware of CTR-700 contains the entire PLC runtime environment including CANopen connection with CANopen Master Functionality. Thus, the module is able to operate control tasks such as linking in- and outputs or converting rule algorithms. Data and occurrences can be exchanged with other nodes (e.g. superior main controller, I/O slaves and so forth) via CANopen network, Ethernet (UDP protocol) and serial interfaces (UART). The numerous in- and outputs that the module provides can be decentrally extended by CANopen devices. CANopen IO modules of *sysWORXX Automation Series* are well-suited for this. Those modules are also designed for processing industrial standard signals (24VDC, 0-10VDC, 0-20mA etc.).

Programming the CTR-700 takes place according to IEC 61131-3 using the programming system *OpenPCS* of the company infoteam Software GmbH (http://www.infoteam.de). This programming system has been extended and adjusted for the CTR-700 by the company SYS TEC electronic GmbH. Hence, it is possible to program the CTR-700 graphically in KOP/FUB, AS and CFC as well as textually in AWL or ST. Downloading the PLC program onto the module takes place via Ethernet or

CANopen – depending on the firmware configuration. Addressing in- and outputs and creating a process image follows the SYS TEC scheme for compact control units. Hence, PLC programs developed by the user can be operated on different SYS TEC control modules without adjustments. Like all other SYS TEC controls, the CTR-700 supports backward documentation of the PLC program as well as the debug functionality including watching and setting variables, single cycles, breakpoints and single steps.

The CTR-700 uses Debian GNU/Linux as operating system. This allows for an execution of other user-specific programs while PLC firmware is running. If necessary, those other user-specific programs may interchange data with the PLC program via the process image or the Node-RED nodes for reading and writing of variable values. More information about this is provided in section 6 and 10.

The Linux applied to CTR-700 is licensed under GNU General Public License, version 2. Appendix C contains the license text. All sources of Linux BSP are included in the software package 3912005 ("Oracle VM VirtualBox-Image of the Linux development system"). If you require the Linux BSP sources independently from the Oracle VirtualBox-Image of the Linux development system, please contact our support:

support@systec-electronic.com

The PLC system and the PLC-, C# and C/C++ programs developed by the user are **not** subject to GNU General Public License!

3.1 Standards und approvals

CE-approval:

The CTR-700 fulfills the requirements and safety regulations of the following EC directives and complies with the harmonized European standards (EN) for programmable logic controllers in the journals of the European Community:

- 2014/30/EG “electromagnetic compatibility” (EMC directive):
  The CTR700 fulfills the EMC requirements of the harmonized European standard EN 61131-2:2007 (chapter 8, zone B).

  See declaration of conformity in Appendix D

- 2011/65/EG “restriction of hazardous substances” (RoHs directive)

  See declaration of conformity in Appendix E

The EC declarations of conformity will be available to the competent authorities held at:

SYS TEC electronic GmbH
Am Windrad 2
D-08468 Heinsdorfergrund

Use in the industrial sector

The CTR-700 is designed for use in the industrial sector (EN 61000-6-2:2005 & EN 61000-6-4:2007 + A1:2011).

4 Pinout of the CTR-700

4.1 Pin assignment

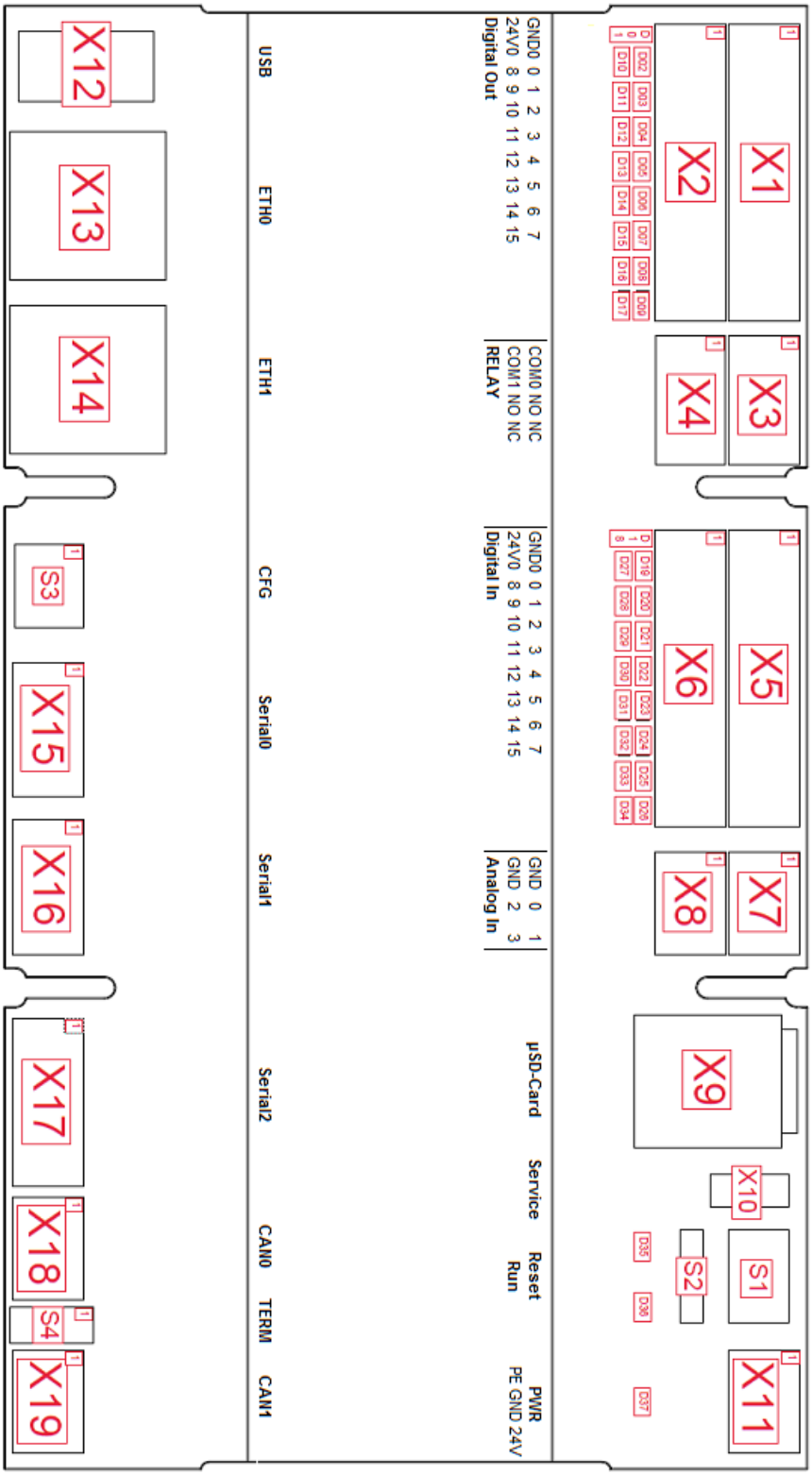


Figure 2: Pinout of CTR-700

Figure 2 shows the positioning of connectors on CTR-700 as an overview. Table 2 lists all connectors in detail.

Table 2: Pin assignment of CTR-700

Terminal	Port	Signal name	Remark
Digital Outputs X1	1	GND	24V
	2 … 9	DO0 … DO7	
Digital Outputs X2	1	+24VDC	
	2 … 9	DO8 … DO15*	
Relay 0 X3	1	COM	230V
	2	NO	
	3	NC	
Relay 1 X4	1	COM	230V
	2	NO	
	3	NC	
Digital Inputs X5	1	GND	24V
	2 … 9	DI0 … DI7	
Digital Inputs X6	1	+24VDC	
	2 … 9	DI8 … DI15	
Analog Inputs X7	1, 2	AIN 0, AIN 1	0 … 10V/0 … 20mA
	3	AGND	
Analog Inputs X8	1, 2	AIN 2, AIN 3	
	3	AGND	
µSD-Card-Holder X9	-	-	-
µUSB (console) X10	-	-	-
Power X11	1	PE	24V
	2	GND	
	3	+24VDC	
USB-Host X12	-	-	-
Ethernet 0 X13	-	-	-
Ethernet 1 X14	-	-	-
Serial Interface 0 X15	1	RX, D0	RS232/RS485-MOD-BUS
	2	D1	
	3	TX	
	4	GND	
Serial Interface 1	1	RX, D0	RS232/RS485-MOD-BUS
	2	D1	

X16	3	TX	
	4	GND	
Serial Interface 2 X17	1	RX, D0	RS232/RS485-MOD-BUS
	2	CTS, D1	
	3	TX	
	4	RTS	
	5	GND	
CAN 0 X18	1	HIGH	-
	2	LOW	
	3	GND	
CAN 1 X19	1	HIGH	-
	2	LOW	
	3	GND	

Table 3: Description Switches

Switch	Port	Feature	0	1
S1	-	RESET	-	-
S2	-	RUN	OFF	ON
S3	1	termination serial interface 2 (RS485-MOD-BUS)	OFF	ON
	2	termination serial interface 1 (RS485-MOD-BUS)	OFF	ON
	3	termination serial interface 0 (RS485-MOD-BUS)	OFF	ON
	4	configuration	OFF	ON
	5	boot	-	-
	6	boot mode (SD-Karte/EMMC)	SD	EMMC
S4	1	termination CAN 0	OFF	ON
	2	termination CAN 1	OFF	ON

Table 4: Description LEDs

LED	Color	Feature
D01	green	status of power supply digital outputs
D02 … D17	yellow	status of digital outputs
D18	green	status power supply digital inputs
D19 … D34	yellow	status digital inputs
D35	green	status of the system (RUN)
D36	red	status of the system (ERROR)
D37	green	power supply device

4.2 Power supply (24VDC)

The CTR-700 features three power supply inputs (24VDC ±20%) for CPU unit and two peripheries. The connector supplies the CPU unit, the digital in- and outputs. This input has reverse polarity protection.

4.3 In- and outputs for industrial standard signals

4.3.1 Digital inputs DI0 ... DI15 (24VDC)

The CTR-700 features 16 digital inputs (DI0 ... DI15). The inputs are galvanically isolated in groups of eight inputs. Each eight inputs have the same supply potential (DI0 ... 7, DI8 ... DI15). The inputs are highly active with the following selector shaft:

- Input voltage > 15 VDC: is shown as ‘1’ in the process image
- Input voltage < 5 VDC: is shown as ‘0’ in the process image

Digital inputs DI0 ... DI15 have the internal structure as shown in Figure 3.

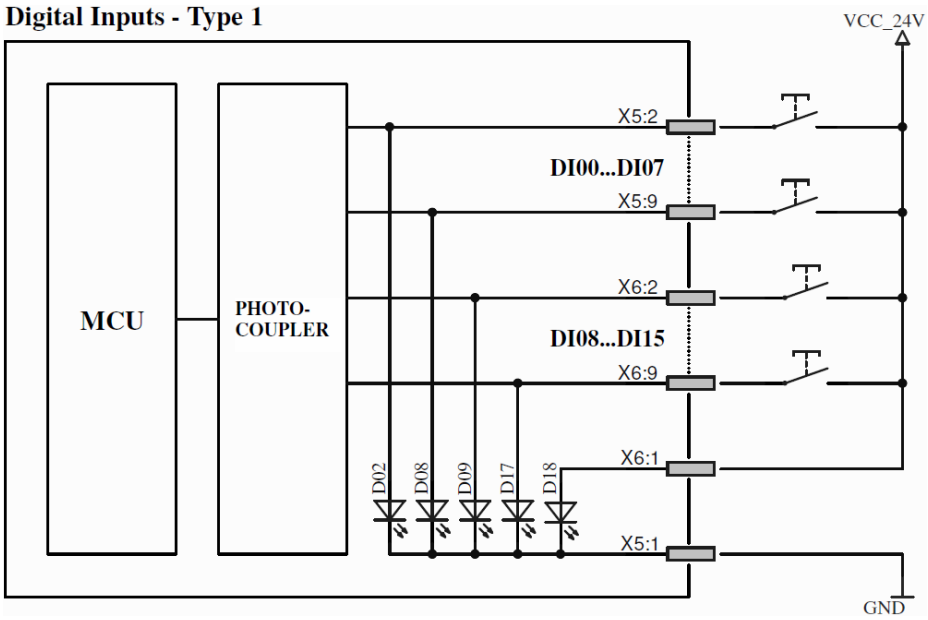


Figure 3: Setup of digital inputs DI0 ... DI15

The digital inputs in a PLC program are accessible via the process image (see Table 11 in section 9.3.1).

The maximum cable length for digital inputs is 30m.

4.3.1.1 Alternate function DI14: Counter input C0 (24VDC)[4]

The CTR-700 features a high-speed counter input (C0) which is galvanically isolated from one another and from the CPU kernel. The inputs are highly active with the following selector shafts:

- Input voltage > 15 VDC: is shown as ‘1’ in the process image
- Input voltage < 5 VDC: is shown as ‘0’ in the process image

The counter input C0 has the same internal structure as the digital inputs DI0 ... DI15 shown in Figure 3.

[4] Counter functionality is not implemented yet. It will be available in a future release.

The counter inputs in a PLC program are accessible via process image (see Table 11 in section 9.3.1) as well as via function block *"CNT_FUD"* (see manual *"SYS TEC-specific extensions for OpenPCS / IEC 61131-3"*, manual no.: L-1054).

4.3.1.2 Alternate function: DI14+DI15: A/B Encoder C0 (24VDC)[5]

The CTR-700 features a high-speed A/B-Encoder input which is galvanically isolated from one another and from the CPU kernel. The inputs are highly active with the following selector shafts:

- Input voltage > 15 VDC: is shown as ‘1’ in the process image
- Input voltage < 5 VDC: is shown as ‘0’ in the process image

Counter inputs C0 and C1 have the same internal structure as the digital inputs DI0 ... DI15 shown in Figure 3.

The encoder value in a PLC program are accessible via process image (see Table 11 in section 9.3.1) as well as via function block *"CNT_FUD"* (see and manual *"SYS TEC-specific extensions for OpenPCS / IEC 61131-3"*, manual no.: L-1054).

4.3.2 Digital outputs DO0 ... DO15 (24VDC / 0.5A, short-circuit-proof)

The CTR-700 features 16 digital transistor outputs (DO0 ... DO15). The outputs each connect the supply voltage Vcc of the appliance (switching positively). The maximum load current for each 24V output is 0.5A for ohmic, inductive or capacitive load. The outputs are short-circuit-proof and galvanically isolated from the CPU unit. The performance drivers used are protected against excess voltage, reverse polarity and excess temperature. The transistor outputs are accessed high-actively:

- ‘1’ in process image: output transistor active, appliance connected with Vcc
- ‘0’ in process image: output transistor inactive, appliance disconnected from Vcc

The digital transistor outputs DO0 ... DO15 have the internal structure as shown in Figure 4.

4.3.2.1 Alternate function: DO14, DO15: Pulse outputs P0 and P1 (24VDC / 0.5A, short-circuit-proof)

The CTR-700 features two Pulse outputs (P0 and P1) to output PWM and PTO signal sequences. The outputs each activate the ground signal (GND) of the connected appliance (switching negatively). The maximum load current for each 24V output is 0.5 A for ohmic, inductive or capacitive load. The outputs are short-circuit-proof and galvanically isolated from the CPU unit. The performance drivers used are protected against reverse polarity. The transistor outputs are activated low-actively:

- ‘1’ in process image: output transistor active, appliance connected with GND
- ‘0’ in process image: output transistor inactive, appliance disconnected from GND

Pulse outputs P0 and P1 have the same internal structure as the digital inputs DI0 ... DI15 shown in Figure 3.

In a PLC program, the PWM/PTO functionality of Pulse outputs is accessible via function block *"PTO_PWM"* (see manual *"SYS TEC-specific extensions for OpenPCS / IEC 61131-3"*, manual no.: L-1054).

[5] A/B Encoder functionality is not implemented yet. It will be available in a future release.

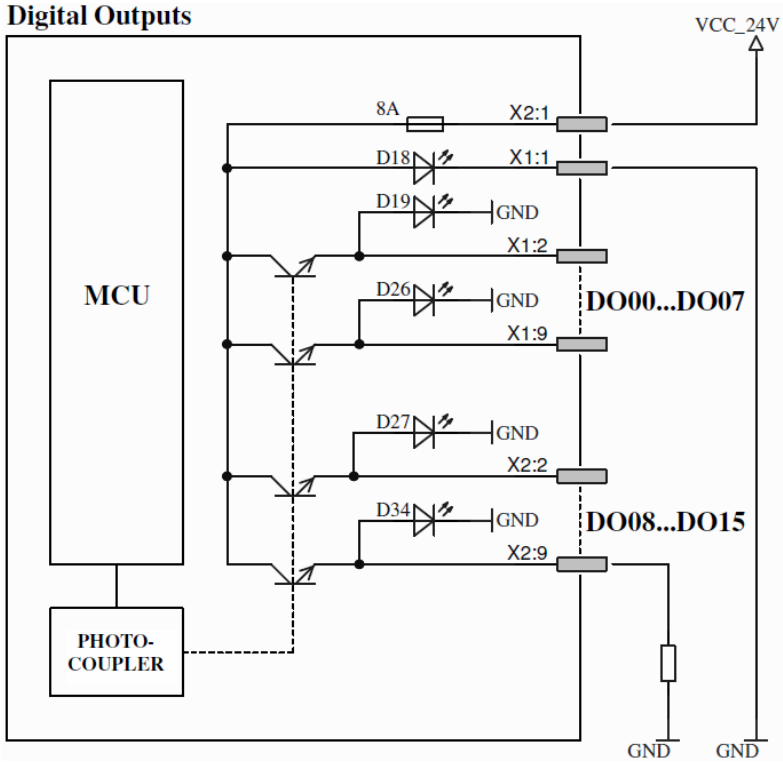


Figure 4: Setup of digital outputs DO0 ... DO15

The digital outputs in a PLC program are accessible via the process image (see Table 11 in section 9.3.1).

4.3.3 Relay outputs REL0 and REL1 (250VAC / 3A)

The CTR-700 features two Relay outputs. Outputs REL0 and REL1 are two-way contacts. The Relays are activated high-actively:

- ‘1’ in process image: contact is closed
- ‘0’ in process image: contact is open / two-way contact is close

Relay outputs REL0 and REL1 have the internal structure as shown in Figure 5.

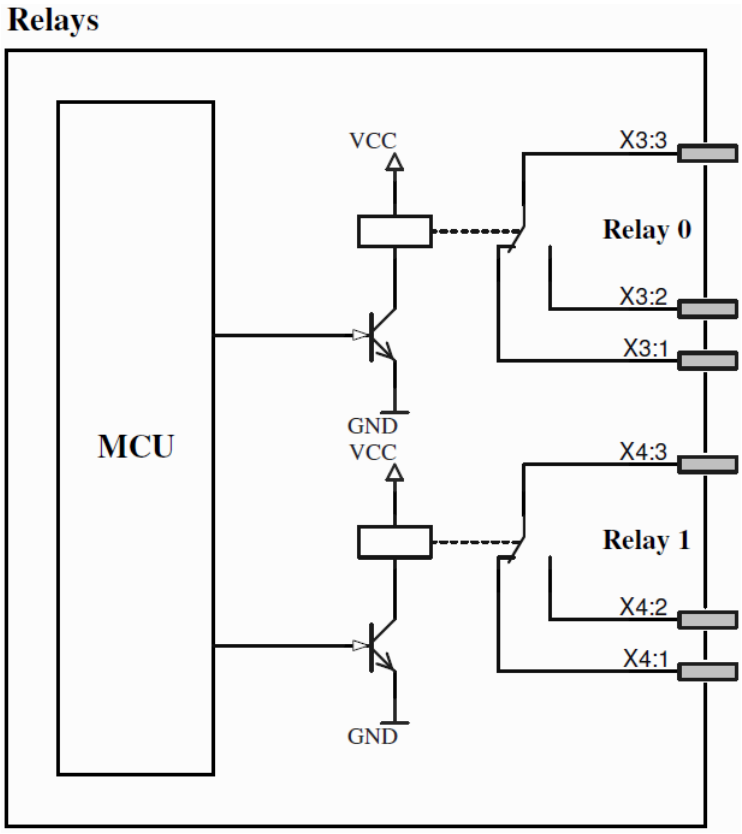


Figure 5: Setup of Relay outputs REL0 and REL1

Attention!	Country-typical technical standards for the usage of power supply voltage must be taken into consideration.

The Relay outputs are in a PLC program are accessible via the process image (see Table 11 in section 9.3.1).

4.3.4 Analog inputs AI0 … AI3 (0 … +10V / 0 … 20mA)

In its standard configuration, the CTR-700 features 4 analog inputs for a voltage range of 0 … +10 V and a resolution of 12-bit. Alternatively, these inputs can be configured to current inputs of 0 ... 20 mA.

The configuration of the ADC mode after bootup is described in section 5.5.

Analog inputs AI0 … AI3 have the same internal structure as shown in Figure 6.

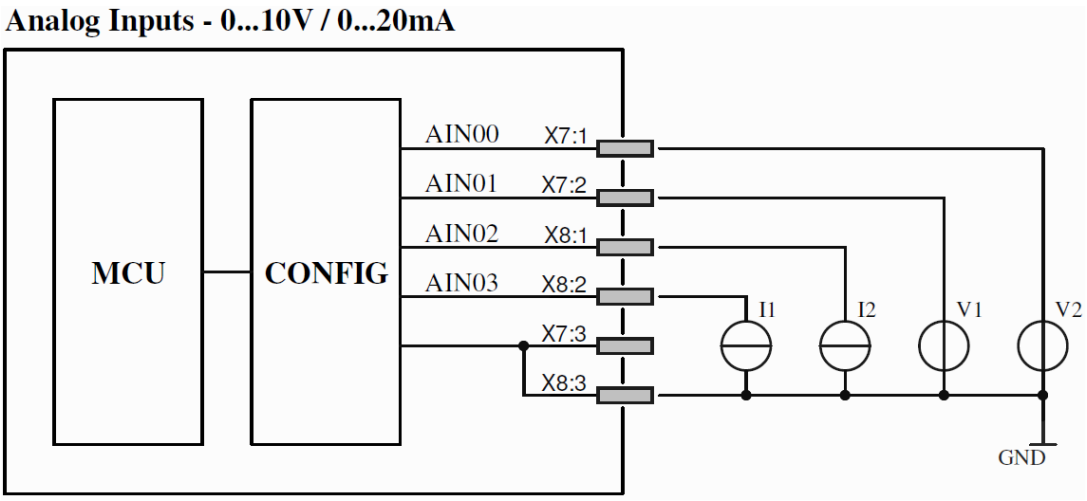


Figure 6: Setup of analog inputs AI0 ... AI3

The analog inputs in a PLC program are accessible via the process image (see Table 11 in section 9.3.1).

Process image and I/O user space driver give a 16-bit signed value for the ADC. In case of CTR-700 only positive values will be returned. Thus only 15-bit with a theoretical range of 0 to 32765 are used. The actual value ranges are shown in Table 5.

Table 5: ADC measurement range

		Voltage measurement	Current measurement
Raw value per digit		355,23 µV	819,87 nA
Maximum value	**in digits**	28151	24394
	in unit	10 V	20 mA

4.4 Communication interfaces

4.4.1 Serial interfaces

The CTR-700 features one service and three serial interfaces (X10, X15 … X17).

SERVICE (X10)
Interface Service serves as service interface to administer the CTR-700. The connection to a computer is established via Micro-USB.

The maximum cable length for the SERVICE interface is 3m.

SERIAL0 and SERIAL1 (X15 and X16)
Interface Serial 0 is disposable and usually used for data exchange between the CTR-700 and other field devices under control of the PLC program. RS-232 signals Rx, Tx and GND or RS-485 signals D0, D1 and COM are available at a X15, X16 connector. Additionally, the configuration for the RS-485 has to be added to the source code of an application. When used as RS-485, termination resistors can be activated vie the DIP-Switch (see Table 3: Description Switches).

The maximum cable length for the serial interfaces SERIAL0 and SERIAL1 is 30m.

SERIAL2 (X17)

Interface Serial 2 is disposable and **modem-compliant**. It is normally used for data exchange between the CTR-700 and other field devices under control of the PLC program. R-232 signals Rx, Tx, RTS, CTS and GND or R-485 signals D0, D1 and COM are available at a X17 connector. Additionally, the configuration for the RS-485 has to be added to the source code of an application. When used as RS-485, termination resistors can be activated vie the DIP-Switch (see Table 3: Description Switches).

The maximum cable length for the serial interfaces SERIAL2 is 30m.

To use the RS-485 interface, the following configuration has to be added. Substitute **INTERFACE** with the targeted interface (see Table 6):

```
iInterface = open("INTERFACE", O_RDWR | O_SYNC);

ioctl(iInterface, TIOCGRS485, &RS485);
RS485.flags |= SER_RS485_ENABLED;
RS485.flags &= ~SER_RS485_RX_DURING_TX;
ioctl(iInterface, TIOCSRS485, &RS485);

// Configure baud rate
tcgetattr(iInterface, &Termios);
memset(&Termios, 0, sizeof(struct termios));
Termios.c_lflag &= ~(ICANON | ECHO | ISIG);
Termios.c_oflag  = 0;
Termios.c_cflag  = (CLOCAL|CREAD);
Termios.c_iflag  = 0;

Termios.c_cflag |= CS8;
Termios.c_cflag &= ~CSTOPB;
Termios.c_cflag &= ~PARENB;
Termios.c_cc[VMIN] = 0;
Termios.c_cc[VTIME] = 0;

cfsetispeed(&Termios, B115200);
cfsetospeed(&Termios, B115200);
tcsetattr(iInterface, TCSANOW, &Termios);

close(iInterface);
iInterface = open("INTERFACE", O_RDWR | O_SYNC);
```

Table 6: Serial interface to Linux device node path

Interface	Linux-Device (*INTERFACE*)
SERIAL0	/dev/ttymxc6
SERIAL1	/dev/ttymxc5
SERIAL2	/dev/ttymxc1
SERVICE [6]	/dev/ttymxc0

[6] The **SERVICE** interface is used as the default Linux console for serial access to the device. Do not use this for custom applications unless you really know how to handle this without any conflicts.

4.4.2 CAN interfaces CAN0 … CAN1

The CTR-700 features 2 CAN interfaces (CAN0 and CAN1). Those two CAN-Bus-Transceivers are galvanically isolated to one another and to the CPU. The transceivers are supplied via two on-board DC/DC converter. CAN-Bus signals CAN0 HIGH, CAN0 LOW, CAN1 HIGH, CAN1 LOW and CAN0 GND/CAN1 GND are available from withdrawable terminal-block connectors.

Section 9.8 provides detailed information about the usage of both CAN interfaces in connection with CANopen.

CAN cable: The CAN-Bus usually is a twisted pair line. At both ends of the cable, a termination resistor of **120 Ohm termination** is necessary **between CAN_H and CAN_L**. CiA (CAN in Automation) suggests using CAN-GND in CiA DRP 303-1. For more information please refer to the appropriate CiA standards.

Both CAN interfaces also support the use of an internal termination resistor for one end of the CAN bus. The DIP-switch to make use of these resistors is described in Table 3.

4.4.3 Ethernet interface ETH0 and ETH1

The CTR-700 features two Ethernet interfaces (ETH0 and ETH1) which are designed as 10Base-T/100Base-TX.

The Ethernet interface serves as service interface to administer the CTR-700 and it can be used for data exchange with any other devices.

4.4.4 USB-Host

The CTR-700 features a USB 2.0 host interface (X12).

The maximum cable length for the USB-host interface interface is 3m.

5 Configuration and Administration

5.1 System requirements and necessary software tools

The administration of the CTR-700 requires any Windows or Linux computer that has available an Ethernet or USB interface. These allow a connection to administer the CTR-700 via a Linux command line-interface.

All examples referred to in this manual are based on an administration of the CTR-700 using a Windows computer. Procedures using a Linux computer would be analogous.

To administrate the CTR-700 the following software tools are necessary:

Terminal program

A Terminal program allows the communication with the **command shell** of the CTR-700 via **the integrated USB-to-UART bridge (USB service console) of the** CTR-700. This is required for the Ethernet configuration of the CTR-700 as described in section 5.4. After completing the Ethernet configuration, all further commands can either be entered in the Terminal program or alternatively in an SSH client (see below).

A suitable Terminal program would be *"TeraTerm",* which is available as Open Source Software (*BSD* License). The project page is located at: http://ttssh2.osdn.jp/.

Secure Shell (SSH)

SSH allows the encrypted communication with **command shell** of the CTR-700 via **Ethernet**. Using SSH requires a completed Ethernet configuration of the CTR-700 according to section 5.4. As alternative solution to SSH, all commands can be used via a Terminal program.

Suitable as SSH client would be *"PuTTY"* or *"TeraTerm",* which can also be used as Terminal program (see above). "*PuTTY*" is licensed under *MIT*-License and can be downloaded at: https://www.chiark.greenend.org.uk/~sgtatham/putty/.

SFTP client

An SFTP client allows file transfer between the CTR-700 and the computer. This allows for example **editing configuration files** by transferring those from the CTR-700 onto the computer where they can be edited and get transferred back to the CTR-700. Downloading files onto the CTR-700 is also necessary to **update the PLC firmware**. (Advice: The update of *PLC firmware* is not identical with the update of the *PLC user program*. The PLC program is directly transferred to the module from the *OpenPCS* programming environment. No additional software is needed for that.)

Suitable as SFTP client would be *"WinSCP"* which is available as Open Source Software (GNU GPL).

For programs that communicate via Ethernet interface, such as SFTP client or TFTP server, it must be paid attention to that rights in the Windows-Firewall are released. Usually Firewalls signal when a program seeks access to the network and asks if this access should be permitted or denied. In this case access is to be permitted.

5.2 Connection over the serial interface

Setting up a connection to the CTR-700 over the serial interface needs a Terminal Program like *"TeraTerm"* (see 5.1) and the *"Silicon Labs USB to UART Bridge"* driver installed on the computer. The driver can be found here: https://www.silabs.com/products/development-tools/software/usb-to-uart-bridge-vcp-drivers

Additionally, the USB host interface (SERVICE, see section 4) of the CTR-700 has to be connected to the computer with a µUSB cable.

If both are installed and the CTR-700 is connected to the computer, *"TeraTerm"* must be started and configured as follows (see Figure 7):

- 115200 Baud
- 8 Data bit
- 1 Stop bit
- no parity
- no flow control

Note: The Port has to be the COM-interface installed with the Silicon Labs driver. This is depending on the computer on which it was installed. COM3 as shown in Figure 7 is only an example, the real number of the COM interface can vary on other computers.

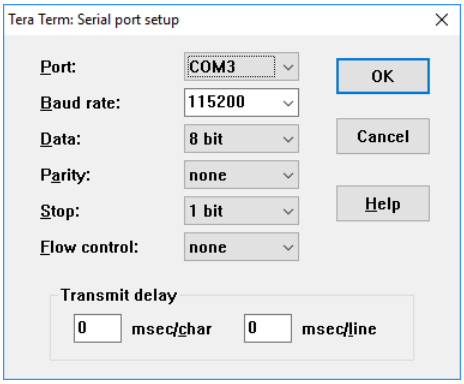


Figure 7: Terminal configuration using the example of "TeraTerm"

Clicking on OK will start the command shell. After pressing any key, the login screen should be visible and the user is able to interact with the CTR-700 (see Figure 8).

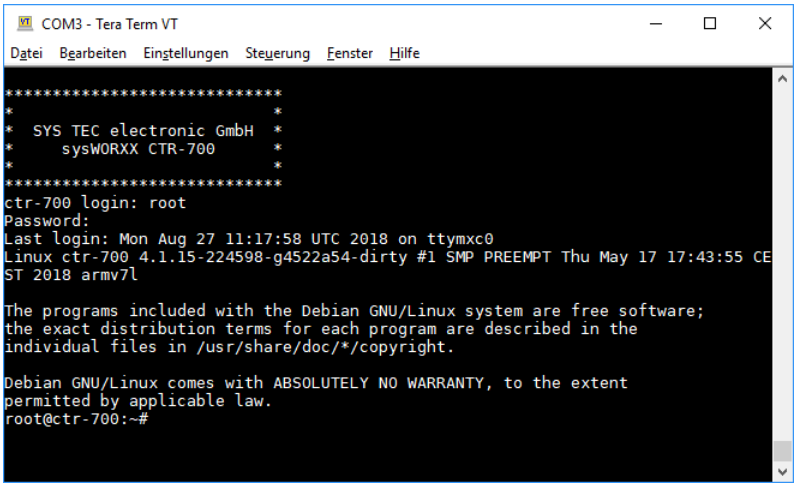


Figure 8: Login screen TeraTerm

To log into the CTR-700 you need a valid user account. There are predefined and ready to use accounts already available (see section 5.8). In this example, the user *"root"* was used.

5.3 Activation/Deactivation of Linux auto-boot

During standard operation mode, the bootloader "U-Boot" automatically starts the Linux operating system of the module after a reset (or power-on reset). Afterwards, the operating system loads all enabled services such as OpenPCS runtime or Node-RED (see section 5.7.3 on how to enable system services). For certain service tasks it may be required to access the "U-Boot" command prompt instead. Communicating with the bootloader "U-Boot" only takes place via the serial interface "Service" of the CTR-700. To disable the auto-boot, the corresponding DIP-Switch has to be set (see Table 3). After the switch is set and the system is rebooted, the "U-Boot" command prompt is activated.

5.4 Ethernet configuration

The CTR-700 has two ethernet interfaces ETH0 and ETH1.The main ethernet configurations are saved in the configuration file in */etc/network/interfaces.* By default, only ETH0 is used and configured to use DHCP and the interface ETH1 has no configuration. The following configuration examples below use "ethX" as placeholder. Substitute "ethX" with the targeted network interface *eth0* or *eth1*. Modifications are adopted upon the next reboot of the CTR-700.

Advice: After the configuration is finished, the serial connection between PC and CTR-700 is no longer necessary.

5.4.1 Get the current IP address

To get the current IP addresses of the CTR-700, one has to set up a connection with a Terminal program (see 5.1). After login one can use the following command, to get a list of IP addresses:

```
ifconfig eth0
```

The parameter *eth0* is optional. If not given, *ifconfig* will print the IP addresses of all interfaces.

The following example shows the IP address *192.168.10.134* for the network interface *eth0*:

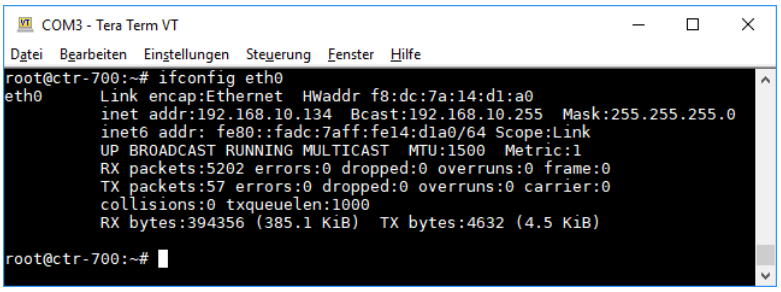


Figure 9: Example – get the IP address for eth0

5.4.2 DHCP configuration

Add the configuration options listed below to the configuration file, to change the network interface to DHCP.

```
allow-hotplug ethX
iface ethX inet dhcp
```

5.4.3 Static IP address configuration

Add the configuration options listed below to the configuration file, to change the network interface to static. Use the proper configuration for your network infrastructure.

```
allow-hotplug ethX
iface ethX inet static
      address 192.168.0.100
      netmask 255.255.255.0
      network 192.168.0.0
      broadcast 192.168.0.255
      gateway 192.168.0.1
```

5.5 Configuration of ADC inputs for voltage / current measurements

ADC inputs (“ANALOG IN”) of the sysWORXX CTR-700 can be configured for voltage measurements (default) as well as for current measurements. The configuration will be loaded at startup of the Linux system as a system service. This service is enabled by default. The configuration can be changed by using a text editor when some sort of terminal command line is connected or up-/download of the configuration file via SFTP.

The path of the configuration file: */etc/systec/adc_modes*

By default, all channels are configured for voltage measurements. The following example shows how to configure ADC input 2 (AI2) for current measurements and all other channels are configured for voltage measurements:

```
# Possible values for ADC modes are "voltage" or "current"
AI0_MODE="voltage"
AI1_MODE="voltage"
AI2_MODE="current"
AI3_MODE="voltage"
```

The configuration can also be changed by the I/O driver “libctr700drv” too. This driver is installed as a Debian package on the CTR-700.

5.6 PLC configuration

5.6.1 PLC configuration via WEB-Frontend

After finishing the Ethernet configuration (see section 5.4), all further adjustments can take place via the integrated WEB-Frontend of the CTR-700. The frontend service is disabled by default. To enable it, run the following command as described in section 5.7.3:

```
systemctl enable openpcs-lighttpd
```

To configure the CTR-700 via WEB-Frontend it needs a WEB-Browser on the PC (e.g. Microsoft Internet Explorer, Mozilla Firefox, etc.). To call the configuration page, prefix *"http:///"* must be entered into the address bar of the WEB-Browser prior to entering the IP address of the CTR-700 as set in section 5.1, e.g. *"http://192.168.10.193"*. Figure 10 exemplifies calling the CTR-700 configuration page in the WEB-Browser.

The standard setting (factory setting) requires a user login to configure the CTR-700 via WEB-Frontend. This is to prevent unauthorized access. Therefore, user name and password must be entered (see Figure 10). On delivery of the module, the following user account is preconfigured (see section 5.8):

User: PlcAdmin
Password: Plc123

Figure 10: User login dialog of the WEB-Frontend

All configuration adjustments for the CTR-700 are based on dialogs. They are adopted into the file ***"/home/plc/bin/ctr-700.cfg"*** of the CTR-700 by activating the pushbutton "Save Configuration" (also compare section 5.6.2). After activating Reset the CTR-700 starts automatically using the active configuration. Figure 11 shows the configuration of the CTR-700 via WEB-Frontend.

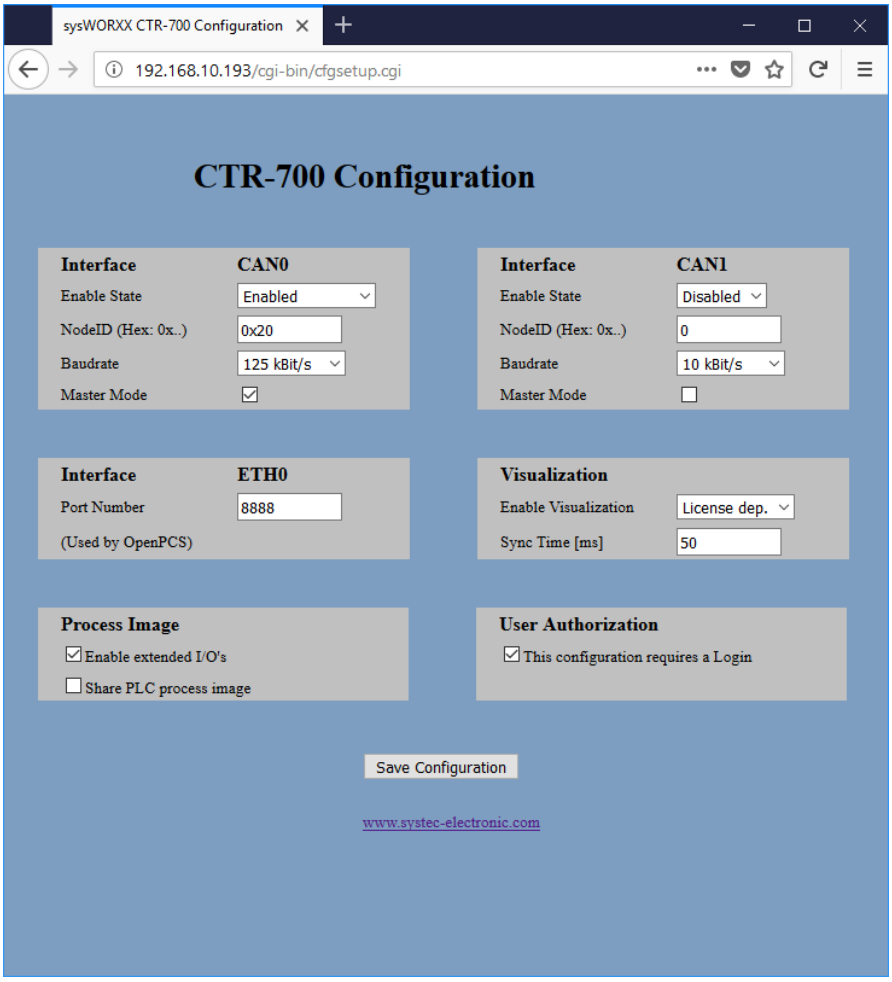


Figure 11: PLC configuration via WEB-Frontend

The standard setting (factory setting) of the CTR-700 requires a user login to access the WEB-Frontend. Therefore, only the user name indicated in configuration file ***"/home/plc/bin/ctr-700.cfg"*** is valid (entry *"User="* in section *"[Login]"*, see section 5.6.2). Procedures to modify the user login password are described in section 5.11. To allow module configuration to another user, an appropriate user account is to be opened as described in section 5.10. Afterwards, the new user name must be entered into the configuration file ***"/home/plc/bin/ctr-700.cfg"***. Limiting the user login to one user account is cancelled by deleting the entry *"User="* in section *"[Login]"* (see 5.6.2). Thus, any user account may be used to configure the module. By deactivating control box *"This configuration requires a Login"* in the field *"User Authorization"* of the configuration page (see Figure 11) free access to the module configuration is made available without previous user login.

5.6.2 Setup of the configuration file "ctr-700.cfg"

The configuration file ***"/home/plc/bin/ctr-700.cfg"*** allows for comprehensive configuration of the CTR-700. Although, working in it manually does not always make sense, because most of the adjustments may easily be edited via WEB-Frontend (compare section 5.6.1). The setup of the configuration file is similar to the file format "Windows INI-File". It is divided into "*[Sections]*" which include different entries "*Entry=*". Table 7 lists all configuration entries.

Table 7: Configuration entries of the CFG file

Section	Entry	Value	Meaning
[CAN0]	Enabled	0, 1	0: Interface CAN0 is deactivated 1: Interface CAN0 is activated, configuration takes place via entries of the configuration file below
	NodeID	1 … 127 or 0x01 … 0x7F	Node number for interface CAN0 (decimal or hexadecimal with prefix "0x")
	Baudrate	10, 20, 50, 125, 250, 500, 800, 1000	Bitrate for interface CAN0
	MasterMode	0, 1	1: Master mode is activated 0: Master mode is deactivated
[CAN1]	Enabled	0, 1	0: Interface CAN1 is deactivated 1: Interface CAN1 is activated, configuration takes place via entries of the configuration file below
	NodeID	1 … 127 or 0x01 … 0x7F	Node number for interface CAN1 (decimal or hexadecimal with prefix "0x")
	Baudrate	10, 20, 50, 125, 250, 500, 800, 1000	Bitrate for interface CAN1
	MasterMode	0, 1	1: Master mode is activated 0: Master mode is deactivated
[ETH0]	PortNum	Default Port no: 8888	Port number for the communication with the Programming-PC and for program download (only for CTR-700/Z5, order number 3090002)
[ProcImg]	EnableSharing	0, 1	0: No sharing of process image 1: Sharing of process image is enabled (see section 6)

[Login]	Authorization	0, 1	0: Configuration via WEB-Frontend is possible without user login 1: Configuration via WEB-Frontend requires user login
	User	Default Name: PlcAdmin	If entry *"User="* is available, only the user name defined is accepted for the login to configure via WEB-Frontend. If the entry is not available, any user registered on the CTR-700 (see section 5.10) may login via WEB-Frontend.

The configuration file ***"/home/plc/bin/ctr-700.cfg"*** includes the following factory settings:

```
[Login]
Authorization=1
User=PlcAdmin

[CAN0]
Enabled=1
NodeID=0x20
Baudrate=125
MasterMode=1

[CAN1]
Enabled=0
NodeID=0x30
Baudrate=125
MasterMode=0

[ETH0]
PortNum=8888

[ProcImg]
EnableExtIo=1
EnableSharing=0
```

5.7 Service configuration and boot scripts

The Debian GNU/Linux installed on the CTR-700 uses “systemd” for managing services. Besides the default services of the operating system, there are some additional services for the CTR-700 available. For executing simple commands on bootup of the system, one can also extend the old-fashioned *rc.local* start script.

5.7.1 Extend shell script in /etc/rc.local

The start script */etc/rc.local* will be executed automatically at startup of the system. This file can be altered by the user to execute additional shell commands. One has to keep in mind to not block the execution of the script for a long time or start long running commands in background.

5.7.2 Add custom systemd services

A much more flexible way to execute applications on boot-up or running Linux daemons, is to use "systemd" services. Users can add custom services on their own. System service files have to be added in */etc/systemd/system/<YOUR_ SERVICE>.service*. The service-file has to contain at least the following options:

```
[Unit]
Description=<YOUR_SERVICE_DESCRIPTION>
[Service]
ExecStart=/usr/bin/YOUR_SERVICE_EXECUTABLE
[Install]
WantedBy=multi-user.target
```

Description is the name for the service and *ExecStart* is the path to the executable file or script.
The service can be started automatically at boot-up with the following command:

```
systemctl enable YOUR_SERVICE
```

One can also disable it with the following command:

```
systemctl disable YOUR_SERVICE
```

As more in-depth examples, one could look up the service files of *OpenPCS* or *Node-RED*. The official documentation can be found in the provided man-pages or on the project site of *systemd*.
Important man-pages regarding system services:

```
man systemd
man systemd.unit
man systemd.service
```

Additional information can be found on the project homepage:
https://www.freedesktop.org/wiki/Software/systemd/

5.7.3 Configure Services

The CTR-700 comes with a few "systemd" services such as *OpenPCS, OPC UA Basis Server* or *Node-RED*. There are two ways to run these services:

1. The following commands are used to manually start or stop *OpenPCS* services on the CTR-700:
   ```
   systemctl start openpcs-z5
   systemctl stop openpcs-z5
   ```

2. There is also the possibility to start the *OpenPCS* services automatically on power-on reset or reboot. These are the same commands as mentioned in Section 5.7.2:
   `systemctl enable openpcs-z5`
   To disable the automatic start, the following command is used:
   `systemctl disable openpcs-z5`

Table 8 shows a list of services, which can be configured by the user. Use the commands as above to run each of the services by substituting the name of the service.

Table 8: systemd services for the CTR-700

Service file / name	Enabled by default	Description
adc-modes.service	Yes	Oneshot service, which sets up the ADC configuration from */etc/systec/adc_modes*
node-red.service	No	Enables the Node-RED programming tool, listens by default on port 1880
openpcs-lighttpd.service	No	Web configuration frontend for OpenPCS
openpcs-z4.service	No	OpenPCS RT, uses the CANopen (CAN0) for communication to OpenPCS on the PC **Hint:** This service can only be started if “openpcs-z5.service” is not running.
openpcs-z5.service	No	OpenPCS RT, uses ethernet (UDP) for communication to OpenPCS on the PC **Hint:** This service can only be started if “openpcs-z4.service” is not running.
docker.service	No	Docker container engine

5.8 Predefined user accounts

All user accounts listed in Table 9 are predefined upon delivery of the CTR-700. Those allow for a login to the command shell and at the SFTP server of the CTR-700.

Table 9: Predefined user accounts of the CTR-700

User name	Password	Remark
root	root	Predefined root user for the administration of the CTR-700 (system configuration, user administration, software updates etc.)
user	user	Main user account of the CTR-700
PlcAdmin	Plc123	Administration user for OpenPCS (root user alias; provided for compatibility reasons to older products)

Hint: To secure the device, users have to change all predefined passwords (see 5.11). If users are not needed they can be disabled or removed except the “root” user. Additionally, SSH can be configured for public key authentication for even better security.

5.9 Remote access

5.9.1 Remote login to the command shell

In some cases, the administration of the CTR-700 requires the ability to typing shell commands manually. Therefore, the user must be directly logged in at the module. There are two different possibilities:

- Logging in is possible with the help of a **Terminal program** (e.g. TeraTerm, see section 5.1) via the serial interface **SERVICE** of the CTR-700.
- Alternatively, the login is possible using an **SSH client** (e.g. PuTTY or also TeraTerm) via the Ethernet interface **ETH0** of the CTR-700.

For logging in to the CTR-700 with SSH via PuTTY or TeraTerm, the IP address provided in section 5.1 must be used.

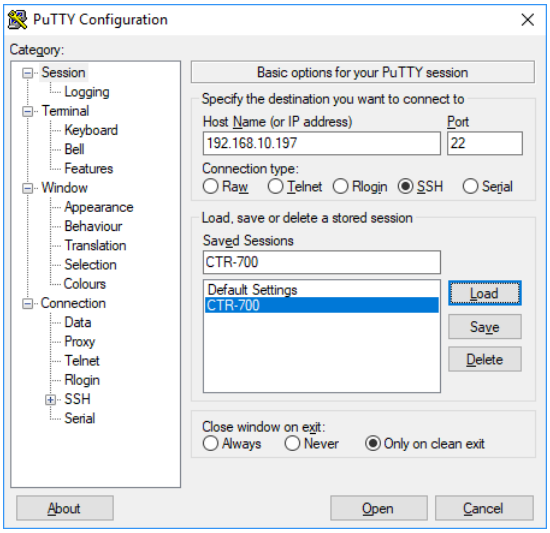


Figure 12: SSH login PuTTY

Logging in to the CTR-700 is possible in the Terminal window (if connected via Service) or in the SSH window (if connected via ETH0). The following user account is preconfigured for the administration of the module upon delivery of the CTR-700 (also compare section 5.8):

User: *root*
Password: *root*

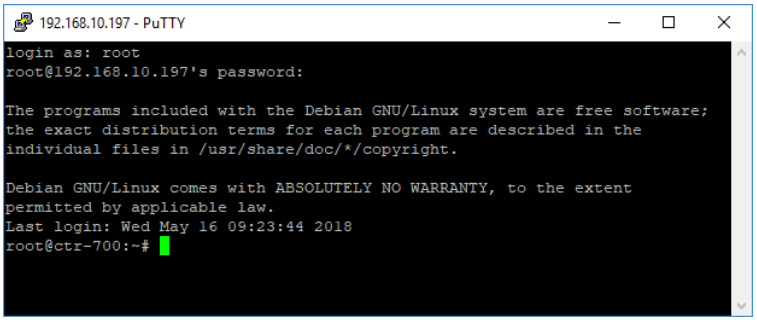


Figure 13: Login to the *CTR-700*

Figure *13* shows the login to the CTR-700 using PuTTY.

5.9.2 Login to the SFTP server

The CTR-700 has available a SFTP server that allows file exchange with any computer (up- and download of files). *"WinSCP"* - which is available as open source - is suitable as SFTP client for the computer (see section 5.1). It consists of only one EXE file, needs no installation and may be started immediately. After program start, dialog *"WinSCP Login"* appears (see Figure 15) and must be adjusted according to the following configurations:

File protocol:	SFTP
Host name:	IP address for the CTR-700 as set in section 5.4
User name:	*root* (for predefined user account, see section 5.8)
Password:	*root* (for predefined user account, see section 5.8)

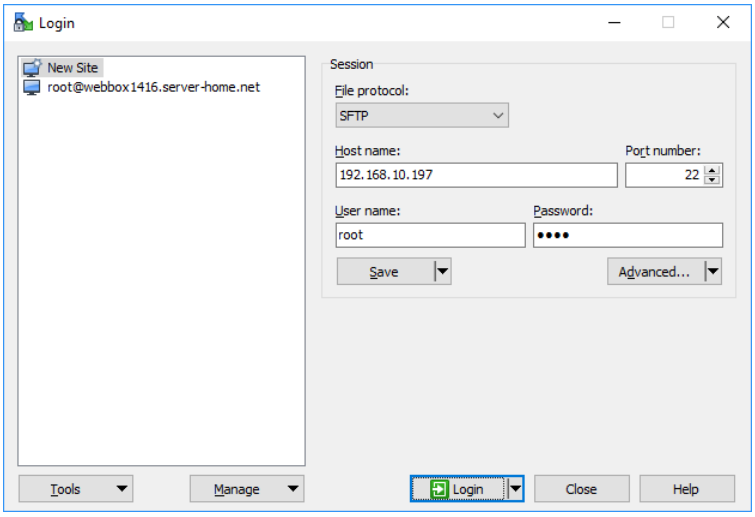


Figure 14: Login settings for „WinSCP“

After using pushbutton *"Login"*, the SFTP client logs in to the CTR-700 and lists up the active content of directory *"/root"* in the right window. Figure 15 shows SFTP client *"WinSCP"* after successful login to the CTR-700.

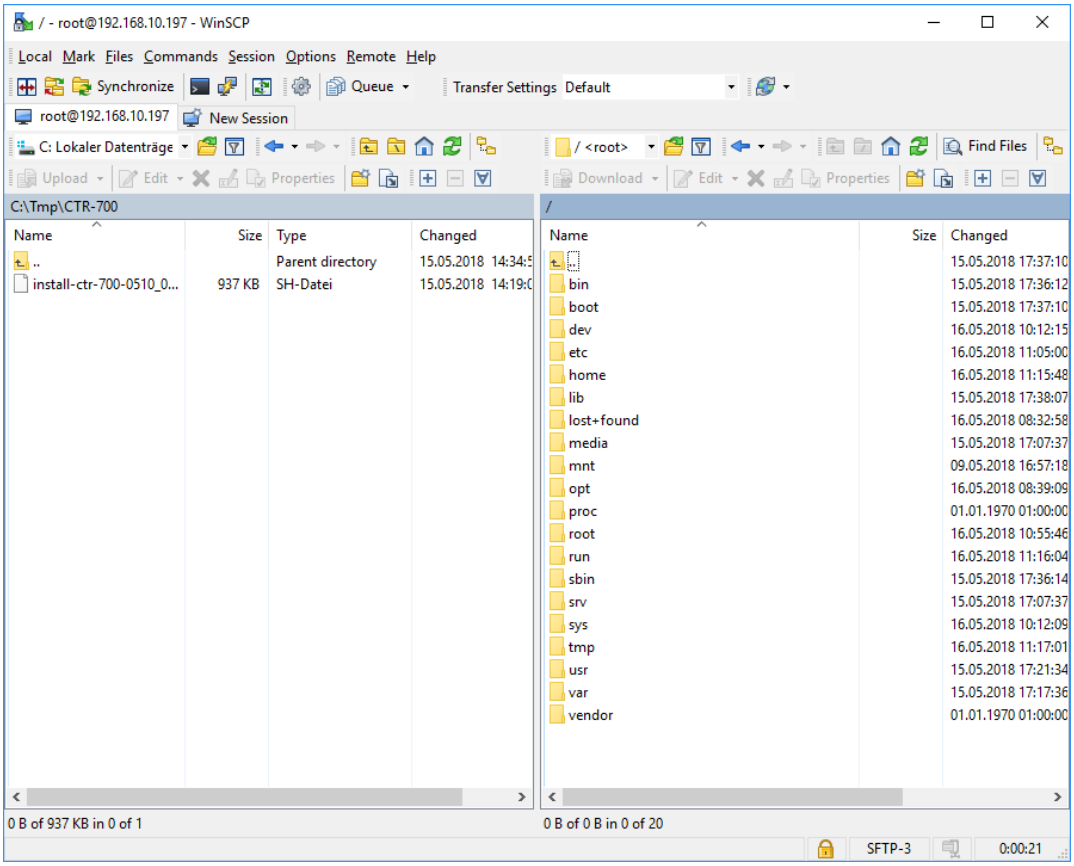


Figure 15: FTP client for Windows "WinSCP"

After successful login, configuration files on the CTR-700 may be edited by using pushbuttons *"F4"* or *"F4 Edit"* within the SFTP client *"WinSCP"* (select transfer mode *"Text"*). With the help of pushbutton *"F5"* or *"F5 Copy"*, files may be transferred between the computer and the CTR-700, e.g. for data backups of the CTR-700 or to transfer installation files for firmware updates (select transfer mode *"Binary"*).

5.10 Adding and deleting user accounts

Adding and deleting user accounts requires the login to the CTR-700 as described in section 5.9.1.

Adding a new user account takes place via Linux command *"useradd"*. To create a new user on the CTR-700, one can use the command *"useradd"* as follows:

```
useradd [options] [username]
```

Advice:	**If the new user account shall be used to access web frontend, the user name must be entered into the configuration file *"ctr-700.cfg"* (for details about logging in to WEB-Frontend please compare section 5.6.1 and 5.6.2).**

To **delete** an existing user account from the CTR-700, Linux command *"userdel"* plus the respective user name must be used:

```
userdel [options] [username]
```

To get a full list of options for one of the commands, run it with the "*--help*" argument.

5.11 How to change the password for user accounts

Changing the password for user accounts requires login to the CTR-700 as described in section 5.9.1.

To change the password for an existing user account on the CTR-700, Linux command *"passwd"* plus the respective user name must be entered:

```
passwd <username>
```

Figure 16
exemplifies the password change for a user named *"testuser"*.

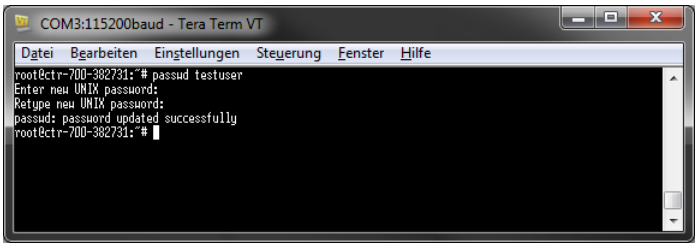


Figure 16: Changing the password for a user account

5.12 Setting the system time and time zone

Setting the system time requires login to the CTR-700 as described in section 5.9.1.

The current date and time must be set using the Linux command "timedatectl set-time". Linux command *"timedatectl set-time"* is structured as follows:

```
timedatectl [options] set-time "YYYY-MM-DD hh:mm:ss"
```

Example:

```
timedatectl set-time "2017-12-01 10:20:55"
```

The current system time is displayed by entering Linux command *"timedatectl"* (without parameter). Figure 17 exemplifies setting and displaying the system time.

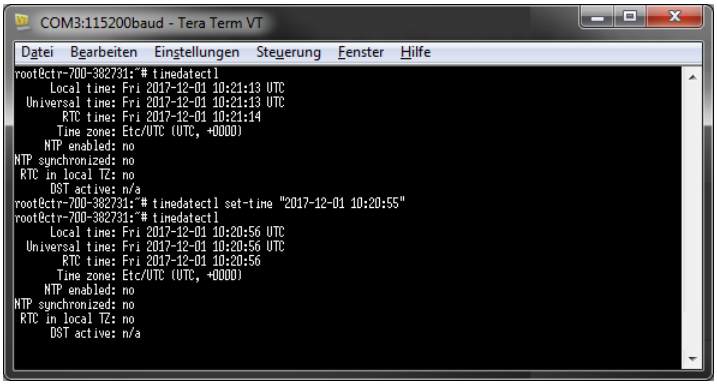


Figure 17: Setting and displaying the system time

Upon start of the CTR-700, date and time are taken over from the RTC and set as current system time of the module.

The current time zone must be set using the Linux command “timedatectl set-timezone”. Linux command ″ timedatectl set-timezone″ is structured as follows:

```
timedatectl [options] set-timezone [TIMEZONE]
```

Example:

```
timedatectl set-timezone Europe/Berlin
```

Figure 18 exemplifies setting and displaying the time zone setting.

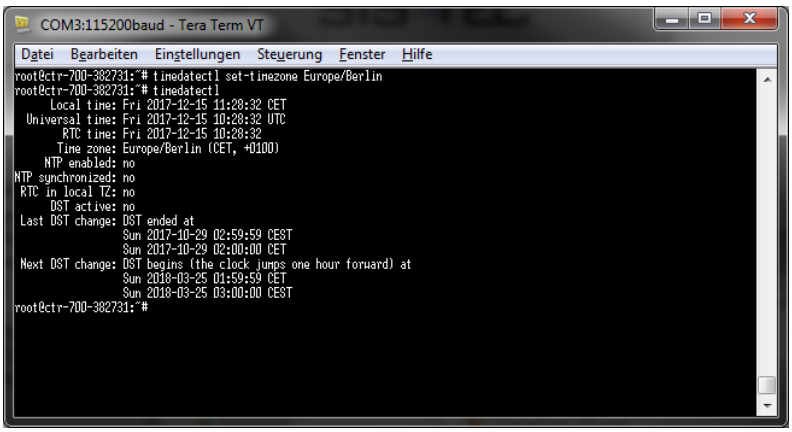


Figure 18: Setting and displaying the system time

With the following command, all available time zones can be looked up:

```
timedatectl list-timezones
```

5.13 File systems

Table 10 lists the default filesystems and mountpoints of the CTR-700.

Table 10: File system configuration of the CTR-700

Path	Size	Description
/	8 GiB / size of SD Card	Root filesystem where the Linux is installed to. The content of this partition is stored on the EMMC or SD Card depending on the current Boot-Mode (see Table 3)
/mnt	-	Target for mounting remote directories
/vendor	4 MiB	Read only configuration data of the CTR-700. These data should not be altered by the user. The content is stored on one of the general-purpose partitions (aka. “boot0”) to keep its contents event after a firmware update.

Size, usage and path of file systems which are mounted can be identified by using Linux command "df" ("disk free").

Advice: The general purpose EMMC partitions *“/dev/mmcblk2boot0”* and *“/dev/mmcblk2boot1”* contain vendor specific data. These partitions should **not** be used or altered by customers. Otherwise the device will not work as expected!

Particular information about the system login and handling the Linux command shell of the CTR-700 is given attention in section 5.9.

5.14 Software installation and update

All necessary firmware components to run the CTR-700 are already installed on the module upon delivery. Hence, firmware updates should only be required in exceptional cases, e.g. to input new software that includes new functionality.

5.14.1 Updating the PLC firmware

PLC firmware represents the run time environment of the PLC. The ***PLC firmware*** can only be generated and modified by the producer; **it is not identical with the PLC user program** which is created by the PLC user. The PLC user program is directly transferred from the *OpenPCS* programming environment onto the module. No additional software is needed.

Updating the PLC firmware requires login to the command shell of the CTR-700 as described in section 5.9.1 and login to the SFTP server as described in section 5.9.2.

Updating the PLC firmware takes place via a self-extracting firmware archive that is transferred onto the CTR-700 via SFTP. The respective firmware archive can be transferred into directory *"/tmp"* of the CTR-700 (see Figure 19).

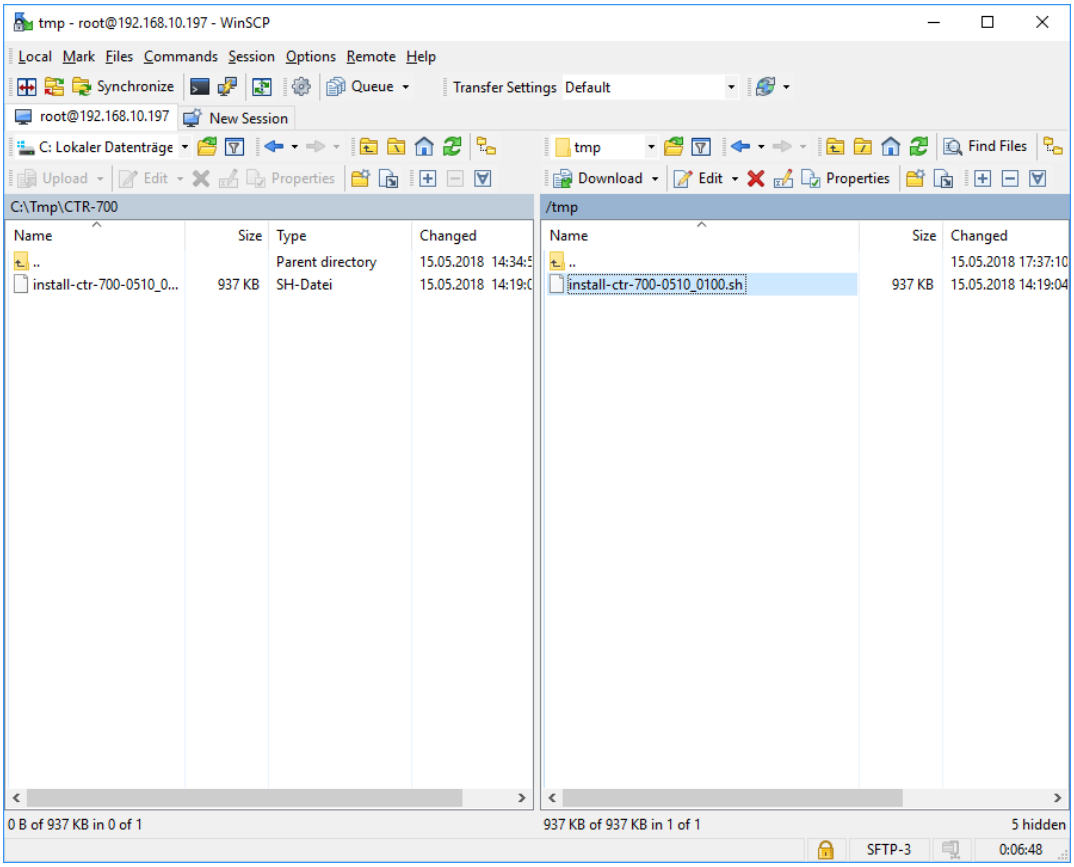


Figure 19: File transfer in SFTP client "WinSCP"

Important: To transfer the firmware archive via SFTP, transfer type “Default” or *"Binary"* must be chosen. If SFTP client *"WinSCP"* is used, the appropriate transfer mode is to be chosen from the menu bar. After downloading the firmware archive, it must be checked if the file transferred to the CTR-700 has the exact same size as the original file on the computer (compare Figure 19). Any differences in that would indicate a mistaken transfer mode (e.g. *"Text"*). In that case the transfer must be repeated using transfer type *"Binary"*.

After downloading the self-extracting archive, the PLC firmware must be installed on the CTR-700. Therefore, the following commands are to be entered in the SSH window. It must be considered that the file name for the firmware archive is labeled with a version identifier (e.g. *“*install-ctr-700-0510_0100.sh*"* for version 5.10.01.00). This number must be adjusted when commands are entered:

```
cd /tmp
chmod +x install-ctr-700-0510_0100.sh
./install-ctr-700-0510_0100.sh
```

Advice: The command shell of the CTR-700 is able to automatically complete names if the Tab key is used ("tab completion"). Hence, it should be sufficient to enter the first letters of each file name and the system will complement it automatically. For example, *"./ins"* is completed to *"./install-ctr-700-0510_0100.sh"* if the Tab key is used.

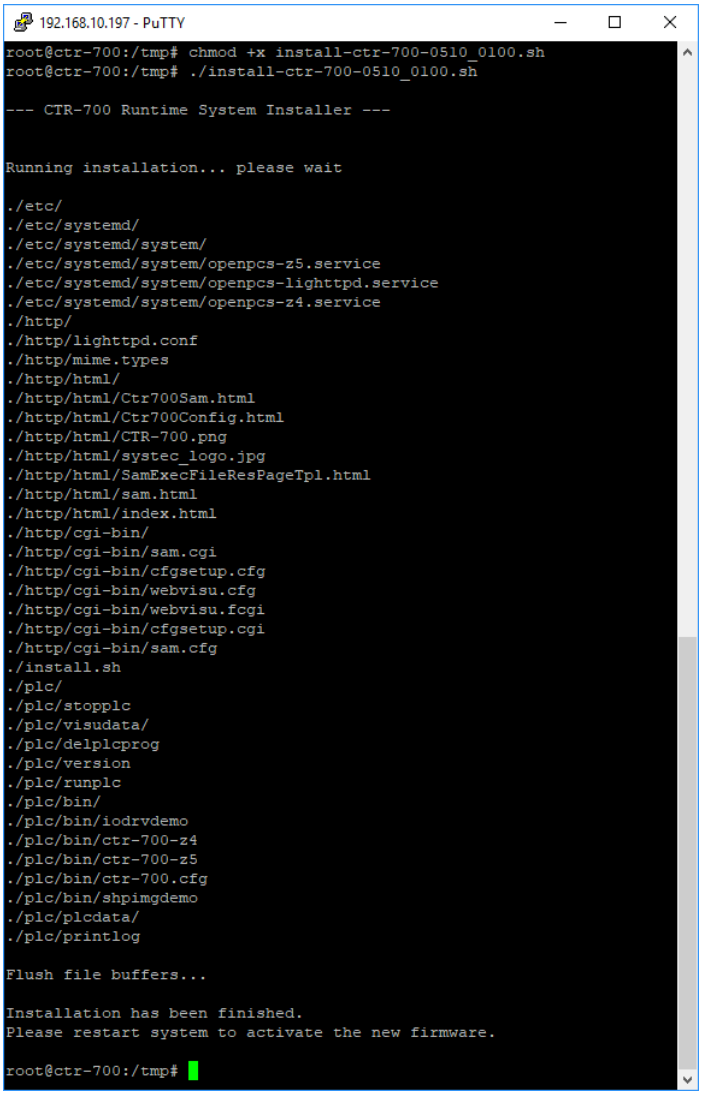


Figure 20: Installing PLC firmware on the CTR-700

Figure 20 shows the installation of PLC firmware on the CTR-700. After reboot the module is started using the updated firmware.

Advice:	**If the PLC firmware is updated, the configuration file *"/home/plc/bin/ctr-700.cfg"* is overwritten. This results in a reset of the PLC configuration to default settings. Consequently, after an update, the configuration described in section 5.6 should be checked and if necessary it should be reset.**

5.14.2 Install Debian GNU/Linux to a SD Card for update/recovery

Advice:	**Installing Debian GNU/Linux to the SD Card will format all partitions of the SD Card. This means all data on the device will be overwritten.**

The CTR-700 supports to boot from SD Card as well as from EMMC. The following steps describe how to install a new firmware version to an SD Card and boot from it. This card can then be used to install Debian GNU/Linux to the internal EMMC of the CTR-700. The SD Card has to have a size of at least 4 GiB. The SD Card software is provided as a compressed image, which contains the whole file system of the operating system.

The SD Card Image is provided by SYS TEC. The following steps assume the file *"ctr-700-sdcard-v0100.img.zip"* is used. Newer versions will have a slightly different file name. Follow the steps to install this file to an SD Card.

1. Unzip the file
2. Download the tool *"Win32 Disk Imager"*: https://sourceforge.net/projects/win32diskimager/
   This tool will be used to copy the image file to the SD Card image.
3. Insert your SD Card
4. Run *"Win32 Disk Imager"*
   a. Choose the uncompressed SD Card image
   b. Choose the drive letter of your SD Card
   c. Click on the "Write" button to write the image to your SD Card

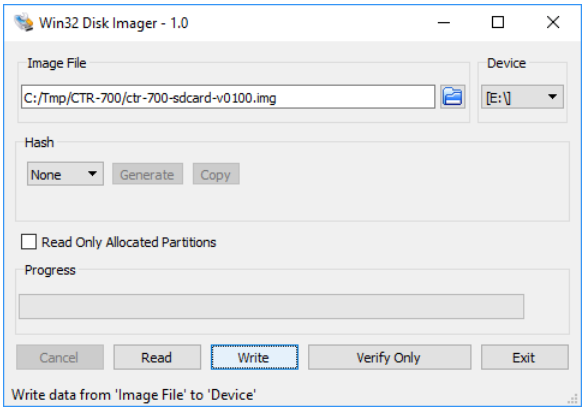


Figure 21: Write SD Card Image using Win32 Disk Imager

5. Insert the SD Card and switch the boot mode to SD Card (turn DIP-Switch 6 off, see Table 3)
6. Power-on the device

The device will now boot from the SD Card. Use a command shell as described in section 5.9.1 to work with the new firmware.

5.14.3 Install / Update Debian GNU/Linux to EMMC

Advice:	**Installing Debian GNU/Linux to the EMMC will format all partitions of the EMMC. This means all data on the device will be overwritten except vendor data partitions, which contain ADC calibration data or information of purchased licenses.**

To be able to install Debian GNU/Linux to the internal EMMC of the CTR-700, one has to create an SD Card as described in section 5.14.2.

After a SD Card is available, follow the steps to install the Linux Image from SD Card to the EMMC and boot it afterwards:

1. Insert the SD Card and switch the boot mode to SD Card (turn DIP-Switch 6 off, see Table 3)
2. Start / boot the device
3. Login to a command line shell as described in section 5.9.1
   User: root
   Password: root

4. Execute the following command to install the Linux to the EMMC. This will take a few minutes to execute.

```
debian-emmc.sh
================================
 SYS TEC sysWORXX CTR-700

 Installing Debian to eMMC
================================

...
...
...

Debian Flashed. Press any key to continue...
```

5. Switch the boot mode to EMMC (turn DIP-Switch 6 on, see Table 3)
6. Reboot or shutdown the system. The CTR-700 will now boot from EMMC.

```
reboot
```

Now the Debian GNU/Linux is installed to the EMMC memory and it can be booted. Using the EMMC has several benefits. The storage is most of the time faster than using an SD Card and it is more reliable in terms of durability.

6 Node-RED programming environment

The Node-RED programming environment allows a simple flow-driven approach to program *Internet of Things* applications in a web browser. This is based on a node editor, which provides nodes for:

- Inputs: These nodes have a single output and trigger a flow by sending a *msg* object. A trigger for an input node can be receiving a timer, a network packet, change of a digital input of the CTR-700 and much more.
- Outputs: These nodes finish the flow execution and provide some reaction to the outside world. Possible reactions can be sending a network packet or tweet, setting a digital output of the CTR-700 and much more.
- Functions: These nodes will operate on an input *msg* and provide some outputs. These are used to map data value, convert data or multiplex data. There are a lot of predefined nodes for common cases. For more advanced functionality they can also be programmed in *JavaScript*.

All nodes have zero or one Input and zero to n Outputs. SYS TEC provides Node-RED preinstalled on the CTR-700 together with some custom Nodes. These nodes can be used to access inputs and outputs of the CTR-700. Additionally, nodes to access OpenPCS variables are provided.

The following section will provide information on the creation of a simple demo program, using the Node-RED programming environment and the CTR-700 nodes for the I/O Driver.

6.1 Running Node-RED

As described in section 5.7.3, Node-RED has to be started by issuing the following command in a command line shell:

```
systemctl enable node-red
systemctl start node-red
```

This will enable it permanently after boot-up and start the environment without the need for a reboot. Starting Node-RED may take a few seconds. After this, one is able to open the Node-RED editor in a web browser. To access the editor, one can use the hostname or the IP address of the CTR-700. In case the device is configured for DHCP, one can find the IP address by issuing the following command.

```
ifconfig
```

To get the hostname of the device use the following command:

```
hostname
```

Now use one of the following links to get access to the Node-RED editor.

http://192.168.10.100:1880/ (replace with your IP address)
or
http://ctr-700-000000:1880/

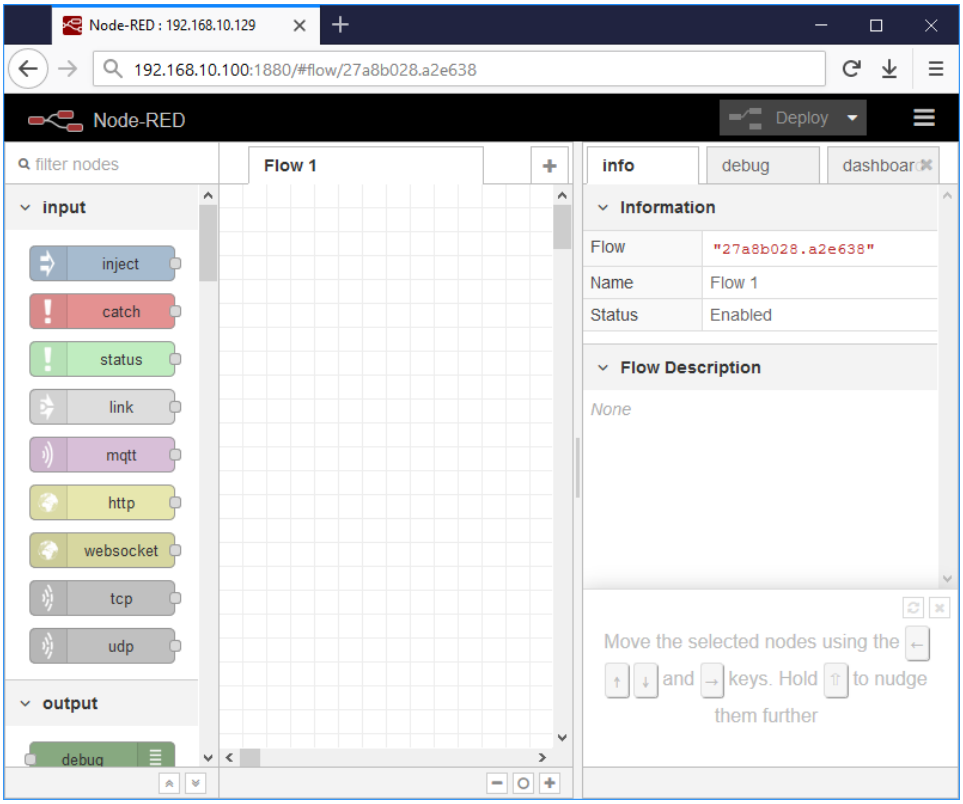


Figure 22: Node-RED editor in the web browser

Node-RED is configured for listening on port 1880 by default. This and the Node-RED configuration can be changed in the file */root/.node-red/settings.js.* The file contains a lot of comments describing the different options. For more documentation lookup the project site of Node-RED:

https://nodered.org/

6.2 Creating a demo application

This section describes the steps to create a simple run light application by using some of the default Node-RED nodes and the CTR-700 nodes from SYS TEC. Node-RED has to be running as described in the previous section.

The following figure shows the final application with all nodes. After a brief explanation of the setup the different settings of each node is explained in detail.

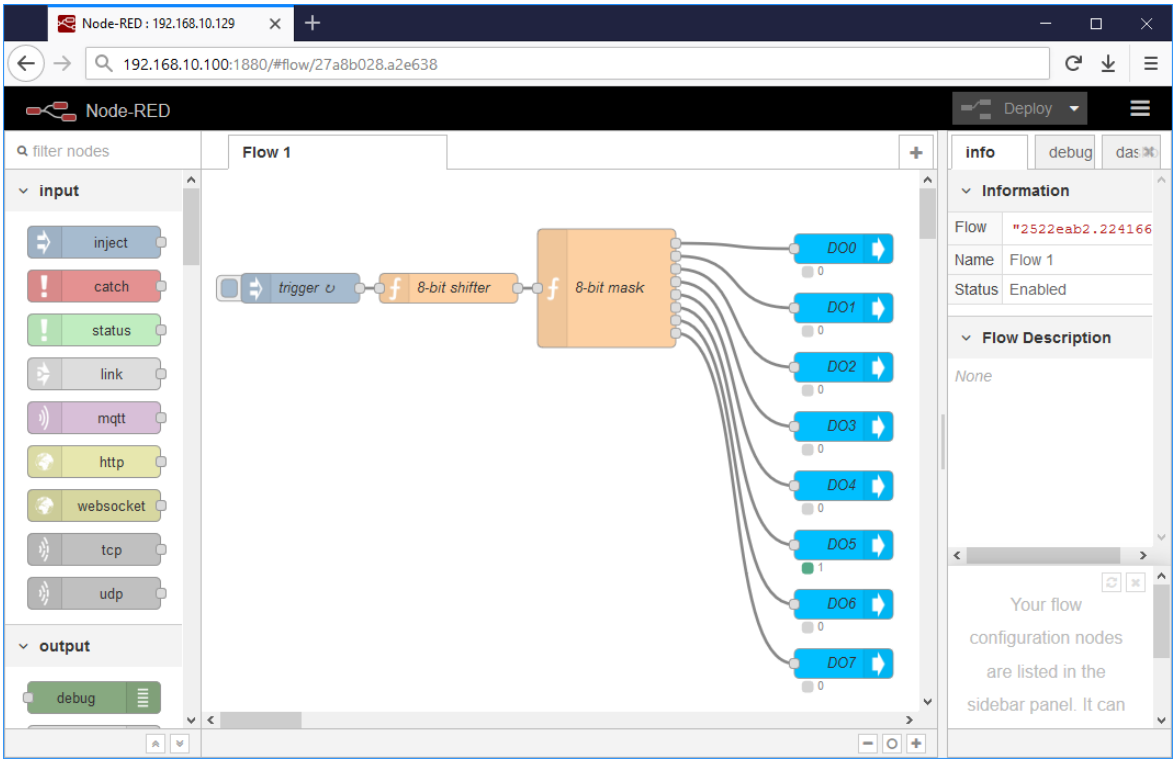


Figure 23: Node-RED demo application

The application contains 3 kinds of nodes starting from the left. The first node called “trigger” gives a repeating input signal, which triggers the execution of the flow. The second node “*8-bit shifter*” will shift a numeric value to the left at each incoming message and outputs the current value. The third node “*8-bit mask”* converts a numeric value (0-255) and provides an output for each value. The nodes “DO0” to “DO7” take the value 0 or 1 and set a digital output accordingly.

Setup the “*trigger*” node:

- Add a node of kind “*inject*” by dragging it to the editor pane and double click on it
- Set “Repeat” to interval, with a value of 0.1 seconds

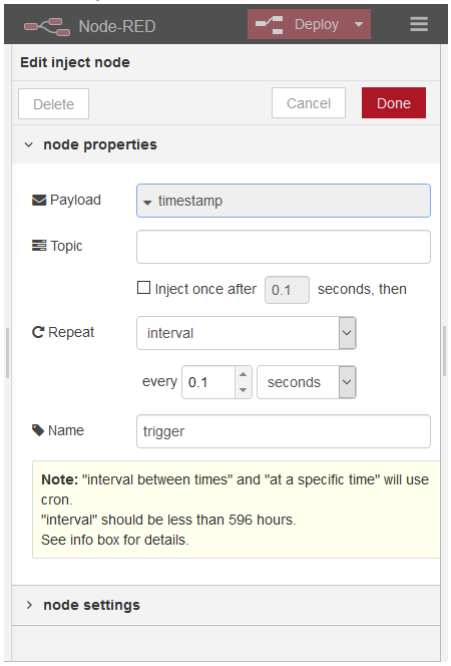


Figure 24: Node: “trigger”

- Click on “*Done*” to confirm the changes

Setup the “*8-bit shifter*” node:

- Add a node of kind “*function*” by dragging it to the editor panel and double click on it
- Copy the following code to the “*Function*” text area and adjust the settings as shown in the screenshot.

```
// ------------------------------------------------------------------
const START = 1;
let shifter = context.get('shifter') || START;

shifter = shifter << 1;
if (shifter > 256) {
    shifter = START;
}

context.set('shifter', shifter);
msg.payload = shifter;
return msg;
// ------------------------------------------------------------------
```

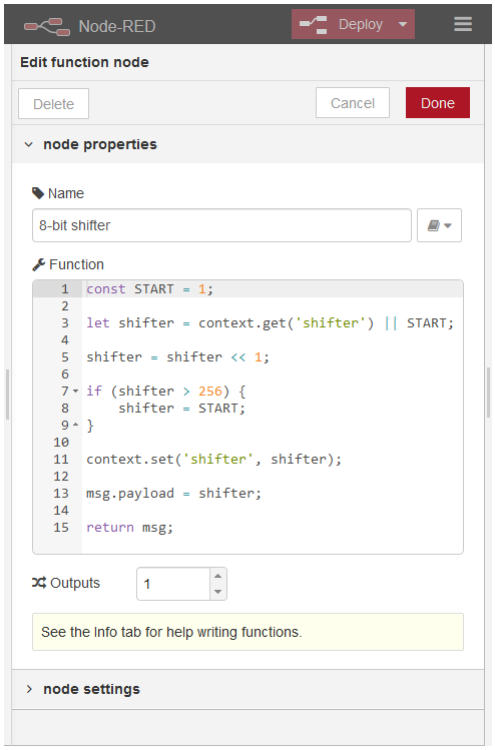


Figure 25: Node: “8-bit shifter”

- Click on “*Done*” to confirm the changes

Setup the “*8-bit mask*” node:

- Add a node of kind “*function*” by dragging it to the editor pane and double click on it
- Copy the following code to the “*Function*” text area, set *Outputs* to 8 and adjust the settings as shown in the screenshot.

```
// ----------------------------------------------------------------
let input = msg.payload;
let outputs = [];

for (let i = 0; i < 8; i++) {
    let channel = {};
    channel.topic = "";

    if (input & (1 << i)) {
        channel.payload = 1;
    } else {
        channel.payload = 0;
    }

    outputs.push(channel);
}

return outputs;
// ----------------------------------------------------------------
```

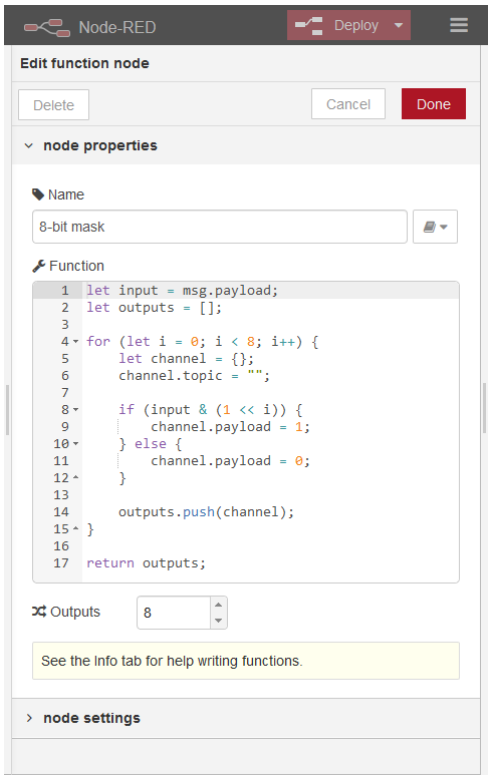


Figure 26: Node: "8-bit mask"

- Click on "*Done*" to confirm the changes

Setup the "*DO0*" node:

- Add a node of kind "*ctr700_out*" by dragging it to the editor pane and double click on it
- Set the *Channel* to DO0, the *Init state* to 0, select *Use alternative topic* and set it to "#" like shown in the screenshot below:

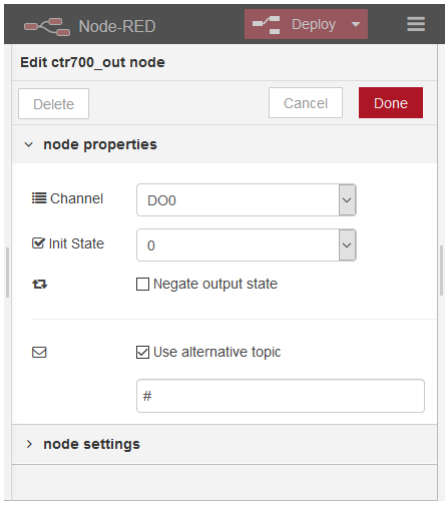


Figure 27: Node: "DO0"

- Click on "*Done*" to confirm the changes

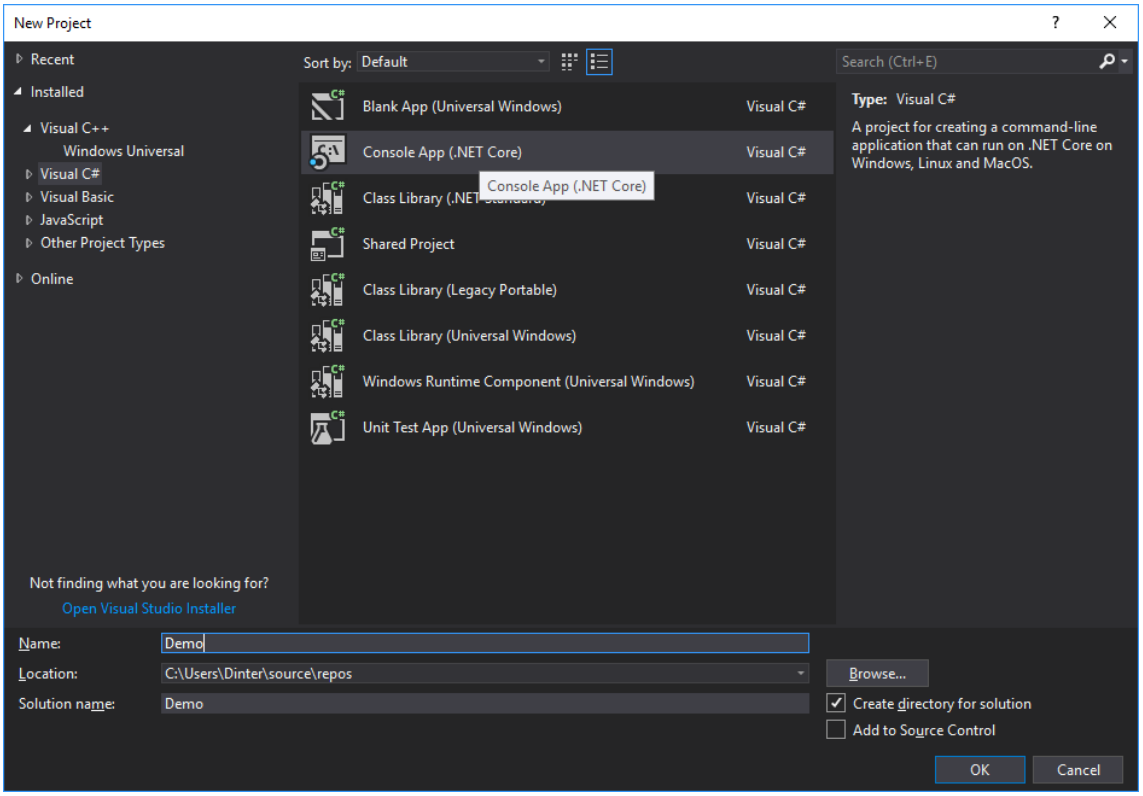
Copy the output node for *DO0* multiple times for each output until *DO7* and adjust the settings for each digital output. Connect all nodes as shown in Figure 23. Now the application is complete. To start it, click on the *Deploy* button in the top right corner of the editor interface. The output LED should now show a run light on *DO0* to *DO7*.

7 Mono/C#

The CTR-700 comes with the preinstalled mono package together with C# bindings for the I/O driver. This allows to write C# applications for the CTR-700 in Microsoft Visual Studio 2017. The application will implement a simple run light for digital outputs 0 to 7.

7.1 Create a C# application

Create a console application as shown in the screenshot below:



The bindings to the CTR-700 I/O Driver are located in the *Oracle VM VirtualBox* provided for the CTR-700. (3912005 "Oracle VM VirtualBox-Image of the Linux development system") The source code of the bindings need to be copied to the project. The path to the bindings in the *Oracle VM VirtualBox* is:

/projects/CTR-700/driver/ctr700drv/Bindings/CSharp/ Ctr700Drv.cs

The content of the file Program.cs needs to be replaced with the following source code:

```
using System;
using Ctr700;

namespace Demo
{
    class Program
    {
        static void Main(string[] args)
        {
            const byte START = 1;
            const byte DELAY_MS = 100;
            byte bMask = START;

            Ctr700Drv.Initialize();

            // Main loop
            try
            {
                while (true)
                {
                    bMask <<= 1;
                    if (bMask == 0)
                    {
                        bMask = START;
                    }

                    for (byte bChannel = 0; bChannel < 8; bChannel++)
                    {
                        bool fValue = (bMask & (1 << bChannel)) != 0;
                        Ctr700Drv.SetDigiOut(bChannel, fValue);
                    }

                    System.Threading.Thread.Sleep(DELAY_MS);
                }
            }
            finally
            {
                for (byte bChannel = 0; bChannel < 8; bChannel++)
                {
                    Ctr700Drv.SetDigiOut(bChannel, false);
                }
                Ctr700Drv.ShutDown();
            }
        }
    }
}
```

The application uses the class Ctr700Drv, which contains static methods to access the driver. This will be used to set the digital outputs of the CTR-700. Before using it, one needs to call the *Initialize()*-Method. On exit of the application the *ShutDown*()-Method should be called. Inside the main loop a mask will be shifted and reset, if the value is zero. The value of the mask will be signaled by bitwise activating the digital outputs represented by the mask. Each loop cycle is finished by sleeping for 100 milliseconds.

Now the project can be built by clicking on *Build / Build Demo.*

7.2 Run the application

To run the application on the target, copy the build Demo.dll in the projects output directory to the CTR-700. This can be done by using SFTP (see section 5.9.2). Login the CTR-700 with a command shell via SSH or a Terminal program. Run the application by running the following commands.

```
cd <DIRECTORY_CONTAINING_THE_DLL>
mono Demo.dll
```

The application can be stopped by pressing CTRL-C. One can also directly execute applications without using mono explicitly if the binary is marked as executable file. The following commands show how to achieve this:

```
chmod +x Demo.dll
./Demo.dll
```

8 Java

The CTR-700 comes with the preinstalled OpenJDK package and also with Java bindings for the I/O driver. The following section will describe how to setup a Java application in the Oracle VM VirtualBox provided for the CTR-700. (3912005 "Oracle VM VirtualBox-Image of the Linux development system") The application will implement a simple run light for digital outputs 0 to 7.

8.1 Create a Java Project

The following steps describe the steps necessary to create the demo application. Start Eclipse, choose a workspace and create a new *Java Project*.

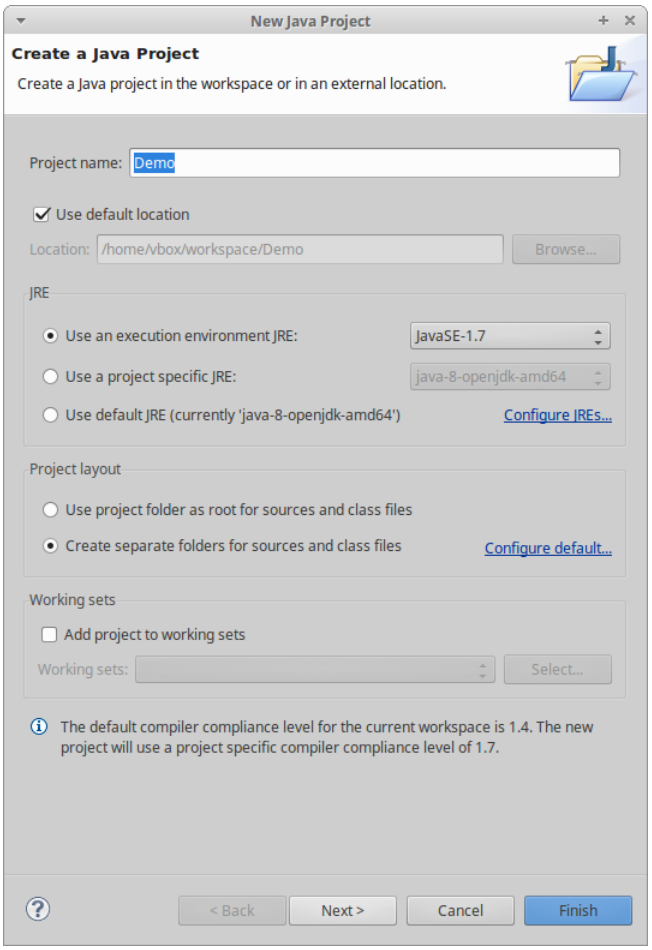


Figure 28: Java Demo: Project setup

Create the Project structure:
Open */projects/CTR-700/driver/ctr700drv/Bindings/Java/* in the file manager and copy the *lib* directory and the file *src/com/systec/Ctr700Drv.java* to the project. The file manager is not needed anymore and can be closed.
After this, one can use the auto-fix feature of *Eclipse* to move *Ctr700Drv.java* to the correct subdirectory of the project. By right clicking on *lib/jna.jar* in the *Package Explorer* and clicking on *Build Path / Add to Build Path* the JNA library can be used by the demo application.

Create a new class Main in the package demo by right clicking on *src* and then click *New / Class* and adjust setting as shown below:

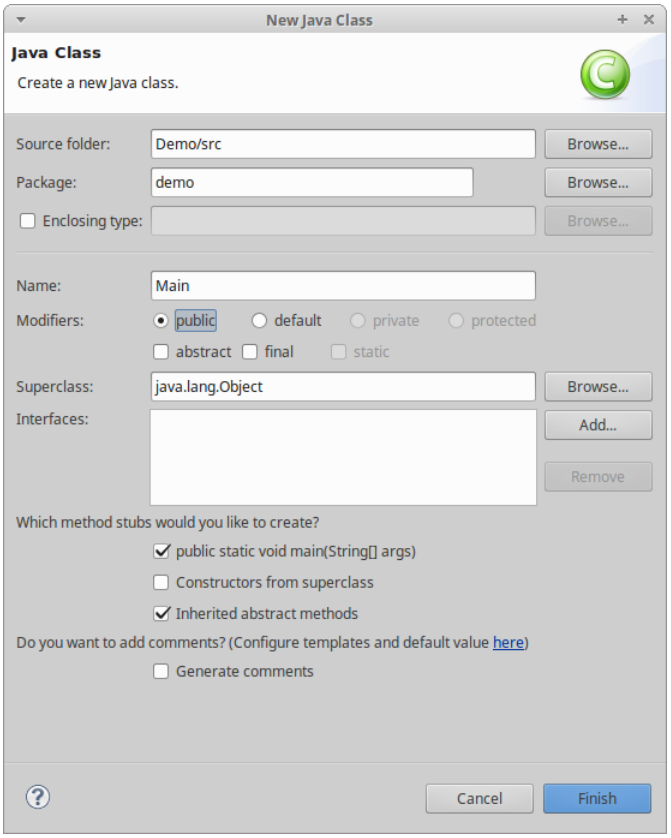


Figure 29: Java Demo: Main class

The structure in *Project Explorer* should now look like in the screenshot below. Both *Java* files have to exist under the *src* directory and the file *jna.jar* has to be a member of *Referenced Libraries.*

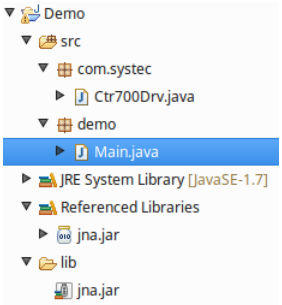


Figure 30: Java Demo: Project structure

Copy the following Java demo source code to Main.java:

```
package demo;
import com.systec.Ctr700Drv;
import com.systec.Ctr700Drv.Ctr700Exception;

public class Main {
      final static int START = 1;
      final static int DELAY_MS = 100;
      static Ctr700Drv ctr700;

      public static void main(String[] args) throws
                                InterruptedException {

            int iMask = START;

            try {
                  ctr700 = new Ctr700Drv();
                  ctr700.init();

                  Runtime.getRuntime().addShutdownHook(new Thread() {
                        @Override
                        public void run() {
                              for (int i = 0; i < 8; i++) {
                                    ctr700.setDigiOut(i, false);
                              }
                              ctr700.shutDown();
                        }
                  });

                  // Main loop
                  while (true) {
                        // Output LSB of the mask
                        for (int i = 0; i < 8; i++) {
                              boolean fValue =
                                    (iMask & (1 << i)) != 0;
                              ctr700.setDigiOut(i, fValue);
                        }

                        iMask <<= 1;
                        if (iMask > 256) {
                              iMask = START;
                        }

                        Thread.sleep(DELAY_MS);
                  }
            } catch (Ctr700Exception e) {
                  System.err.println(e.getMessage());
            }
      }
}
```

The application creates an object of Ctr700Drv. This will be used to set the digital outputs of the CTR-700. Before using it one needs to call the *init()*-Method. On exit of the application the *shutdown*()-Method should be called. Inside the main loop a mask will be shifted and reset, if the value is to large to show the enabled output(s). The value of the mask will be signaled by bitwise activating the digital outputs represented by the mask. Each loop cycle is finished by sleeping for 100 milliseconds.

The demo application is now complete and can be run or debugged.

8.2 Run the Java application

Create a new *Run Configuration* of kind "*Java Application*" and change the settings as shown in the screenshot below. *Apply* and *Close*.

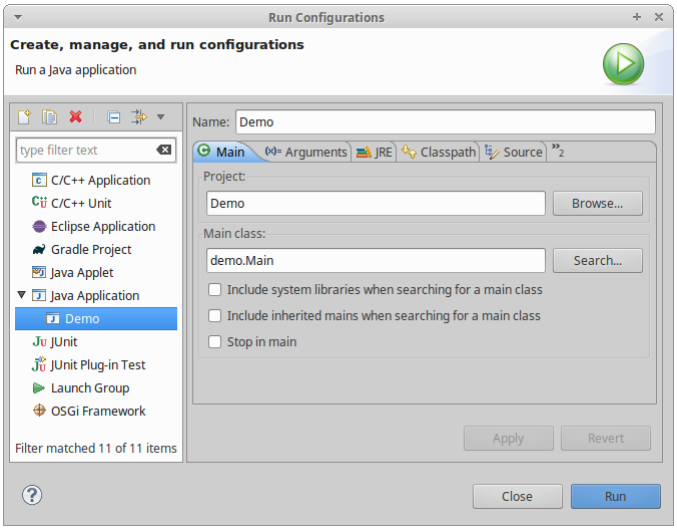


Figure 31: Java Demo: Run configuration

Export a runnable JAR file by *File / Export… / Runnable JAR file.* Click on *Next*, choose the created run configuration and choose a destination path to export the JAR file to. This JAR file will then contain the demo source with all dependencies packaged as a single file.

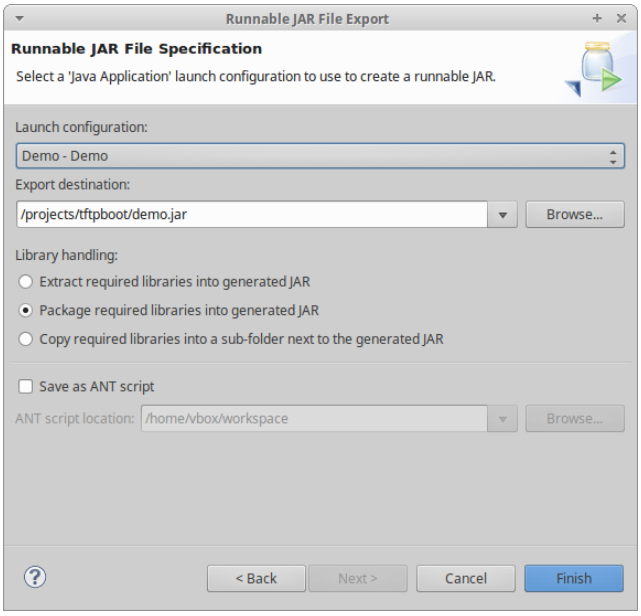


Figure 32: Java Demo: Export Java JAR archive

Copy the created JAR file to the CTR-700 by using SFTP for example. This is described in section 5.9.2. Login the CTR-700 with a command shell via SSH or a Terminal program. Run the application by running the JVM with the JAR file as argument.

```
cd <DIRECTORY_CONTAINING_THE_JAR>
java -jar demo.jar
```

The application can be stopped by pressing CTRL-C.

8.3 Debug the Java application

Start the application on the target with some additional arguments to the JVM. This will start JVM in a debug mode, waiting for a remote to connect.

```
java  -Xdebug \
      -Xrunjdwp:transport=dt_socket,server=y,suspend=y,address=8000 \
      -jar demo.jar
```

In *Eclipse* create another *Run Configuration* for debugging a *Remote Java Application* as shown below but substitute the *Host* IP address with the one of your CTR-700. After this click on *Debug* to start the debugging session.

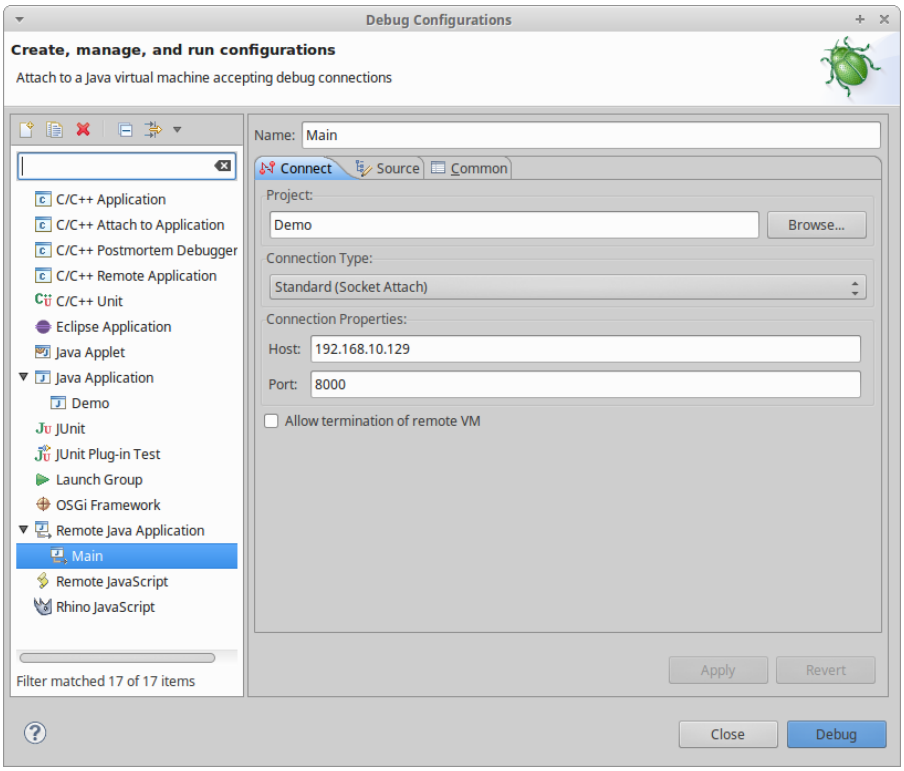


Figure 33: Java Demo: Debug configuration

Now all common debugging features can be used to debug the application. This includes features such as pause execution, stepping through your code, setting breakpoints, watching variable values and much more.

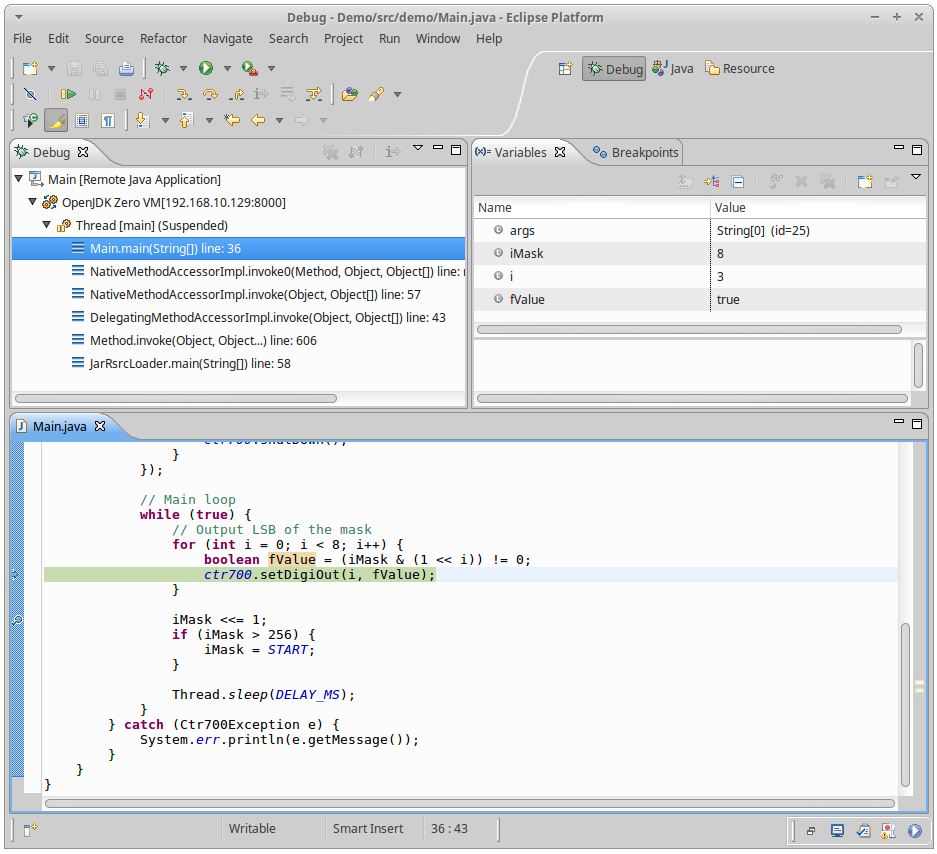


Figure 34: Java Demo: Debug example

9 PLC functionality of the CTR-700

9.1 System start of the CTR-700

The PLC runtime is not enabled by default. To activate the automatic start, one has to enable the services *“openpcs-z4”* or *“openpcs-z5”* as described in section 5.7.3.

If enabled, the CTR-700 loads all necessary firmware components upon power-on or reset and starts running the PLC program afterwards (if enabled). Hence, the CTR-700 is suitable for the usage in independent control systems. In case of power breakdown, such systems resume the execution of the PLC program independently and without user intervention.

9.2 Programming the CTR-700

The CTR-700 is programmed with IEC 61131-3-conform *OpenPCS* programming environment. There exist additional manuals about *OpenPCS* that describe the handling of this programming tool. Those are part of the software package *"OpenPCS"*. All manuals relevant for the CTR-700 are listed in Table 1.

CTR-700 firmware is based on standard firmware for SYS TEC's compact control units. Consequently, it shows identical properties like other SYS TEC control systems. This affects especially the process image setup (see section 9.3) as well as the functionality of control elements (DIP-Switch, Run/Stop switch, Run-LED, Error-LED).

Depending on the firmware version used, CTR-700 firmware provides numerous function blocks to the user to access communication interfaces. Section 5.7.3 describes the selection of the appropriate firmware version.

Table 19 in Appendix A contains a complete listing of firmware functions and function blocks that are supported by the CTR-700. Detailed information about using the CAN interfaces in connection with CANopen is provided in section 9.8.

9.3 Process image of the CTR-700

9.3.1 Local In- and Outputs

Compared to other SYS TEC compact control systems, the CTR-700 obtains a process image with identical addresses. All in- and outputs listed in Table 11 are supported by the CTR-700.

Table 11: Assignment of in- and outputs to the process image of the CTR-700

I/O of the CTR-700	Address and Data type in the Process Image	
DI0 ... DI7	**%IB0.0** %IX0.0 … %IX0.7	as Byte with DI0 … DI7 as single Bit for each input
DI8 ... DI15	**%IB1.0** %IX1.0 … %IX1.7	as Byte with DI8 … DI15 as single Bit for each input
AI0	**%IW8.0**	15Bit + sign (0 … +32767)
AI1	**%IW10.0**	15Bit + sign (0 … +32767)
AI2	**%IW12.0**	15Bit + sign (0 … +32767)
AI3	**%IW14.0**	15Bit + sign (0 … +32767)
C0[(1)]	**%ID40.0** counter input: DI24 (%IX3.0), direction: DI21 (%IX2.5)	31Bit + sign (-2^{31} - 2^{31} -1)
CPU Temperature Sensor	**%ID72.0**	31Bit + sign as 1/10000 °C
System Temperature Sensor	**%ID76.0**	31Bit + sign as 1/10000 °C
DO0 ... DO7	**%QB0.0** %QX0.0 … %QX0.7	as Byte with DO0 … DO7 as single Bit for each output
DO8 … DO15	**%QB1.0** %QX1.0 … %QX1.7	as Byte with DO8 … DO15 as single Bit for each output
REL0 and REL1 (corresponds to DO16 … DO17)	**%QB2.0** %QX2.0 … %QX2.1	as Byte with REL0 and REL1 as single Bit for each Relay

(1) Counters have not yet been implemented. Full function will be added in a future update.

Advice: The CTR-700 works with Little-Endian format (“Intel-Notation). Consequently, and on the contrary to controls using Big-Endian (“Motorola-Notation), it is **possible** to sum up several BYTE variables of the process image to one WORD or DWORD and to access Bits above Bit7. The following example shows issue described:

```
bInByte0  AT %IB0.0 : BYTE;
bInByte1  AT %IB1.0 : BYTE;
wInWord0  AT %IW0.0 : WORD;

wInWord0.0 == bInByte0.0  due to Little-Endian: wInWord0.0 <> bInByte1.0
wInWord0.8 == bInByte1.0  due to Little-Endian: wInWord0.8 <> bInByte0.0
```

In- and outputs of the CTR-700 are not negated in the process image. Hence, the H-level at one input leads to value "1" at the corresponding address in the process image. Contrariwise, value "1" in the process image leads to an H-level at the appropriate output.

9.3.2 Network variables for CAN1

Contrary to interface CAN0, interface CAN1 of the CTR-700 is designed as static object dictionary. Thus, at interface CAN1 the CTR-700 acts as a CANopen I/O device. All static network variables for CAN1 are accessible via the marker section of the process image.

Section 9.3.2 includes more detailed information about CAN interface CAN1 and the network variables that are provided by it in the marker section.

9.4 Communication interfaces

9.4.1 Serial interfaces

The CTR-700 features one service and three serial interfaces (X10, X15 … X17). Details about hardware activation are included in section 4.4.1.

SERVICE (X10)
Interface Service serves only as service interface to administer the CTR-700. The connection to a computer is established via Micro-USB.

SERIAL0 and SERIAL1 (X15 and X16)
Interface Serial 0 and 1 are disposable and support data exchange between the CTR-700 and other field devices kept under control of the PLC program.

The interfaces may be used from a PLC program via function blocks of type *"SIO_Xxx"* (see manual *"SYS TEC-specific Extensions for OpenPCS / IEC 61131-3"*, Manual no.: L-1054).

SERIAL2 (X17)
Interface Serial 2 is disposable and **modem-compatible**. It supports data exchange between the CTR-700 and other field devices kept under control of the PLC program.

The interface may be used from a PLC program via function blocks of type *"SIO_Xxx"* (see manual *"SYS TEC-specific Extensions for OpenPCS / IEC 61131-3"*, Manual no.: L-1054).

9.4.2 CAN interfaces

The CTR-700 features two CAN interfaces (CAN0 and CAN1). Details about the hardware activation are included in section 4.4.2.

Both CAN interfaces allow for data exchange with other devices via network variables and they are accessible from a PLC program via function blocks of type *"CAN_Xxx"* (see *"User Manual CANopen Extension for IEC 61131-3"*, Manual no.: L-1008).

Section 9.3.2 provides detailed information about the usage of the CAN interfaces in connection with CANopen.

9.4.3 Ethernet interface

The CTR-700 features 2 Ethernet interface (ETH0 and ETH1, also termed as ETHERNET). Details about the hardware activation are included in section 4.4.3

The Ethernet interface serves as service interface to administer the CTR-700 and it enables data exchange with other devices. The interface is accessible from a PLC program via function blocks of type *"LAN_Xxx"* (see manual *"SYS TEC-specific Extensions for OpenPCS / IEC 61131-3"*, Manual no.: L-1054).

The exemplary PLC program *"UdpRemoteCtrl"* illustrates the usage of function blocks of type *"LAN_Xxx"* within a PLC program.

9.5 Specific peripheral interfaces

9.5.1 Counter inputs[7]

The CTR-700 features a fast counter input (C0). Prior to its usage, all counter inputs must be parameterized via function block *"CNT_FUD"* (see manual *"SYS TEC-specific Extensions for OpenPCS / IEC 61131-3"*, Manual no.: L 1054). Afterwards, in a PLC program the current counter value is accessible via the process image (see Table 11 in section 9.3.1) or via function block *"CNT_FUD"*. Table 12 lists the allocation between counter channels and inputs.

Table 12: Allocation between counter channels and inputs

Counter channel	Counter input	Optional direction input	Counter value in process image
C0	C0 (DI24) %IX3.0	DI21 %IX2.5	%ID40.0

9.5.2 Pulse outputs

To release PWM and PTO signal sequences, the CTR-700 features 2 pulse outputs (P0 and P1). Prior to its usage, all pulse outputs must be parameterized using function block *"PTO_PWM"* (see manual *"SYS TEC-specific Extensions for OpenPCS / IEC 61131 3"*, Manual no.: L 1054). After the impulse generator is started, it takes over the control of respective outputs. After the impulse generator is deactivated, the respective output adopts the corresponding value that is filled in the process image for this output (see Table 11 in section 9.3.1). Table 13 lists the allocations between impulse channels and outputs.

Table 13: Allocation between impulse channels and outputs

Impulse channel	Impulse output
P0	P0 (DO20) %QX2.4
P1	P1 (DO21) %QX2.5

[7] Counter functionality is not implemented yet. It will be available in a future release.

9.6 Control and display elements

9.6.1 Run/Stop switch

The Run/Stop switch makes it possible to start and interrupt the execution of the PLC program. Together with start and stop pushbuttons of the *OpenPCS* programming environment, the Run/Stop switch represents a "logical" AND-relation. This means that the PLC program will not start the execution until the local Run/Stop switch is positioned to *"Run"* **AND** additionally the start command (cold, warm or hot start) is given by the *OpenPCS* user interface. The order hereby is not relevant. A run command given by *OpenPCS* while at the same time the Run/Stop switch is positioned to *"Stop"* is visible through quick flashing of the Run- and Error-LED.

9.6.2 Run-LED (green, D035)

The Run-LED provides information about the activity state of the control system. The activity state is shown through different modes:

Table 14: Display status of the Run-LED

LED Mode	PLC Activity State
Off	The PLC is in state *"Stop"*: • the PLC does not have a valid program, • the PLC has received a stop command from the *OpenPCS* programming environment or • the execution of the program has been canceled due to an internal error
Quick flashing in relation 1:8 to pulse	The PLC is on standby but is not yet executing: • The PLC has received a start command from the *OpenPCS* programming environment but the local Run/Stop switch is still positioned to *"Stop"*
Slow flashing in relation 1:1 to pulse	The PLC is in state *"Run"* and executes the PLC program.
Quick flashing in relation 1:1 to pulse	The PLC is in mode *"Reset"*

9.6.3 Error-LED (red, D036)

The Error-LED provides information about the error state of the control system. The error state is represented through different modes:

Table 15: Display status of the Error-LED

LED Mode	PLC Error State
Off	No error has occurred; the PLC is in normal state.
Permanent light	A severe error has occurred: • The PLC was started using an invalid configuration (e.g. CAN node address 0x00) and had to be stopped or • A severe error occurred during the execution of the program and caused the PLC to independently stop its state *"Run"* (division by zero, invalid Array access, ...), see below
Slow flashing in relation 1:1 to pulse	A network error occurred during communication to the programming system; the execution of a running program is continued. This error state will be reset independently by the PLC as soon as further communication to the programming system is successful.
Quick flashing in relation 1:1 to pulse	The PLC is in mode *"Reset"*
Quick flashing in relation 1:8 to pulse	The PLC is on standby, but is not yet running: • The PLC has received a start command from the *OpenPCS* programming environment but the local Run/Stop switch is positioned to *"Stop"*

In case of severe system errors such as division by zero of invalid Array access, the control system passes itself from state *"Run"* into state *"Stop"*. This is recognizable by the permanent light of the Error-LED (red). In this case, the error cause is saved by the PLC and is transferred to the computer and shown upon next power-on.

9.7 Local deletion of a PLC program

PLC programs can only be deleted with an established connection via a terminal program, SSH or SFTP (see section 7.1). First, the CTR-700 has to be stopped (S2 switched to left), then the file *PlcArchv.bin* found in ***"/home/plc/plcdata/"*** can be deleted. Only the file has to be deleted not the directory!

9.8 Using CANopen for CAN interfaces

The CTR-700 features 2 CAN interfaces (CAN0 … CAN1), both are usable as CANopen Manager (conform to CiA Draft Standard 302). The configuration of both interfaces (active/inactive, node number, Bitrate, Master on/off) is described in section 5.6.

Both CAN interfaces allow for data exchange with other devices via network variables and they are usable from a PLC program via function blocks of type *"CAN_Xxx"*. More details are included in *"User Manual CANopen Extension for IEC 61131-3"*, Manual no.: L-1008.

The CANopen services **PDO** (***P***rocess ***D***ata ***O***bjects) and **SDO** (***S***ervice ***D***ata ***O***bjects) are two separate mechanisms for data exchange between single field bus devices. Process data sent from a node (**PDO**) are available as broadcast to interested receivers. PDOs are limited to 1 CAN telegram and therewith to 8 Byte user data maximum because PDOs are executed as non-receipt broadcast messages. On the contrary, **SDO** transfers are based on logical point-to-point connections ("Peer to Peer") between two nodes and allow the receipted exchange of data packages that may be larger than 8 Bytes. Those data packages are transferred internally via an appropriate amount of CAN telegrams. Both services are applicable for interface CAN0 as well as for CAN1 of the CTR-700.

SDO communication basically takes place via function blocks of type *"CAN_SDO_Xxx"* (see *"User Manual CANopen Extension for IEC 61131-3"*, Manual no.: L-1008). Function blocks are also available for PDOs (*"CAN_PDO_Xxx"*). Those should only be used for particular cases in order to also activate non-CANopen-conform devices. For the application of PDO function blocks, the CANopen configuration must be known in detail. The reason for this is that the PDO function blocks only use 8 Bytes as input/output parameter, but the assignment of those Bytes to process data is subject to the user.

Instead of PDO function blocks, network variables should mainly be used for PDO-based data exchange. Network variables represent the easiest way of data exchange with other CANopen nodes. Accessing network variables within a PLC program takes place in the same way as accessing internal, local variables of the PLC. Hence, for PLC programmers it is not of importance if e.g. an input variable is allocated to a local input of the control or if it represents the input of a decentralized extension module. The application of network variables is based on the integration of DCF files that are generated by an appropriate CANopen configurator. On the one hand, DCF files describe communication parameters of any device (CAN Identifier, etc.) and on the other hand, they allocate network variables to the Bytes of a CAN telegram (mapping). The application of network variables only requires basic knowledge about CANopen.

For the CTR-700, the usage of PDO-based network variables is different for each CAN interface CAN0 and CAN1. Sections 9.8.1 and 9.8.2 provide more detail on this.

In a CANopen network, exchanging PDOs only takes place in status *"OPERATIONAL"*. If the CTR-700 is not in this status, it does not process PDOs (neither for send-site nor for receive-site) and consequently, it does not update the content of network variables. The CANopen Manager is in charge of setting the operational status *"OPERATIONAL"*, *"PRE-OPERATIONAL"* etc. (mostly also called "CANopen Master"). In typical CANopen networks, a programmable node in the form of a PLC is used as CANopen-Manager. The CTR-700 is able to take over tasks of the CANopen Manager at both CAN interfaces CAN0 and CAN1. How the Manager is activated is described in section 5.6.

As CANopen Manager, the CTR-700 is able to parameterize the CANopen I/O devices ("CANopen-Slaves") that are connected to the CAN bus. Therefore, upon system start via SDO it transfers DCF files generated by the CANopen configurator to the respective nodes.

9.8.1 CAN interface CAN0

Interface CAN0 features a dynamic object dictionary. This implicates that after activating the PLC, the interface does not provide communication objects for data exchange with other devices. After downloading a PLC program (or its reload from the non-volatile storage after power-on), the required communication objects are dynamically generated according to the DCF file which is integrated in the PLC project. Thus, CAN interface CAN0 is extremely flexible and also applicable for larger amount of data.

For the PLC program, all network variables are declared as *"VAR_EXTERNAL"* according to IEC61131-3. Hence, they are marked as „outside of the control“, e.g.:

```
VAR_EXTERNAL
    NetVar1 : BYTE ;
    NetVar2 : UINT ;
END_VAR
```

A detailed procedure about the integration of DCF files into the PLC project and about the declaration of network variables is provided in manual *"User Manual CANopen Extension for IEC 61131-3"* (Manual no.: L-1008).

When using CAN interface CAN0 it must be paid attention that the generation of required objects takes place upon each system start. This is due to the dynamic object directory. "Design instructions" are included in the DCF file that is integrated in the PLC project. **Hence, changes to the configuration can only be made by modifying the DCF file.** This implies that after the network configuration is changed (modification of DCF file), the PLC project must again be translated and loaded onto the CTR-700.

9.8.2 CAN interface CAN1

On the contrary to interface CAN0, interface CAN1 is provided as static object dictionary. This means that the amount of network variables (communication objects) and the amount of PDOs available are both strongly specified. During runtime, the configuration of PDOs is modifiable. This implies that communication parameters used (CAN Identifier, etc.) and the allocation of network variables to each Byte of a CAN telegram (mapping), can be set and modified by the user. Thus, only the number of objects (amount of network variables and PDOs) is strongly specified in the static object dictionary. Consequently, application and characteristics of objects can be modified during runtime. For this reason, at interface CAN1 the CTR-700 acts as a CANopen I/O device.

All network variables of the PLC program are available through the marker section of the process image. Therefore, 252 Bytes are usable as input variables and also 252 Bytes as output variables. To enable any data exchange with other CANopen I/O devices, the section of static network variables is mapped to different data types in the object dictionary (BYTE, SINT, WORD, INT, DWORD, DINT). Variables of the different data types are located within the same memory area which means that all variables represent the same physical storage location. Hence, a WORD variable interferes with 2 BYTE variables, a DWORD variable with 2 WORD or 4 BYTE variables. Figure 35 shows the positioning of network variables for CAN1 within the marker section.

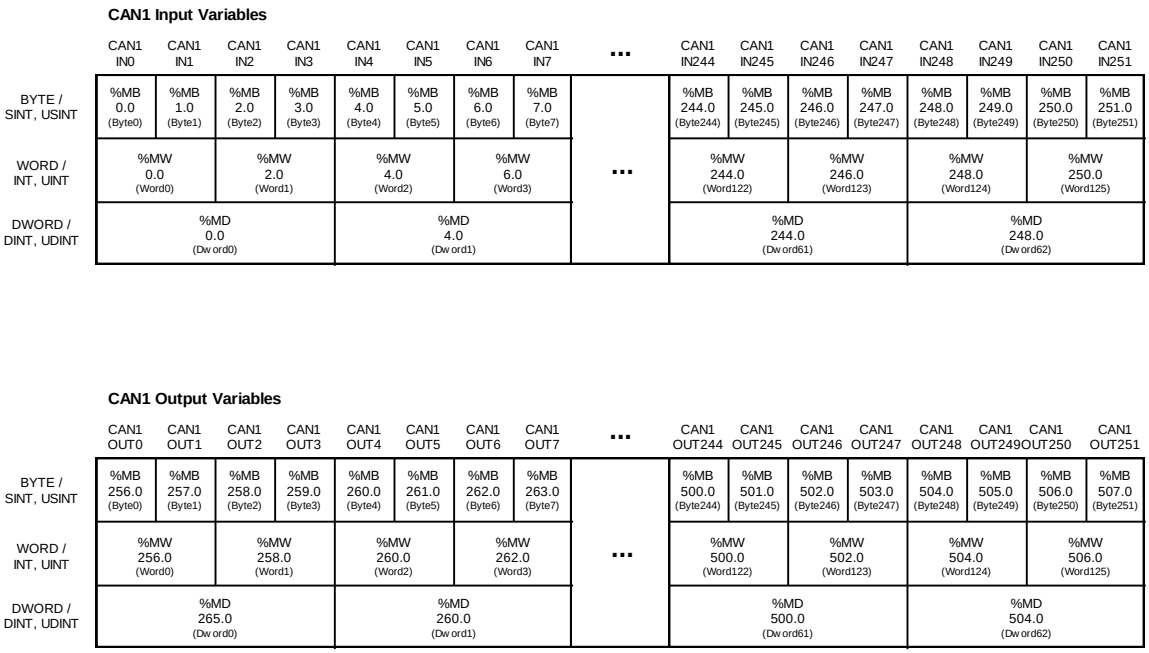


Figure 35: Positioning of network variables for CAN1 within the marker section

Table 16 shows the representation of network variables through appropriate inputs in the object dictionary of interface CAN1.

Table 16: Representation of network variables for CAN1 by entries in the object dictionary

OD section	OD variable / EDS input	Data type CANopen	Data type IEC 61131-3
Inputs (inputs for the CTR-700)			
Index 2000H Sub 1 … 252	CAN1InByte0 … CAN1InByte251	Unsigned8	BYTE, USINT
Index 2001H Sub 1 … 252	CAN1InSInt0 … CAN1InSInt251	Integer8	SINT
Index 2010H Sub 1 … 126	CAN1InWord0 … CAN1InWord125	Unsigned16	WORD, UINT
Index 2011H Sub 1 … 126	CAN1InInt0 … CAN1InInt125	Integer16	INT
Index 2020H Sub 1 … 63	CAN1InDword0 … CAN1InDword62	Unsigned32	DWORD, UDINT
Index 2021H Sub 1 … 63	CAN1InDInt0 … CAN1InDInt62	Integer32	DINT

Outputs (outputs for the CTR-700)			
Index 2030H Sub 1 … 252	CAN1OutByte0 … CAN1OutByte251	Unsigned8	BYTE, USINT
Index 2031H Sub 1 … 252	CAN1OutSInt0 … CAN1OutSInt251	Integer8	SINT
Index 2040H Sub 1 … 126	CAN1OutWord0 … CAN1OutWord125	Unsigned16	WORD, UINT
Index 2041H Sub 1 … 126	CAN1OutInt0 … CAN1OutInt125	Integer16	INT
Index 2050H Sub 1 … 63	CAN1OutDword0 … CAN1OutDword62	Unsigned32	DWORD, UDINT
Index 2051H Sub 1 … 63	CAN1OutDInt0 … CAN1OutDInt62	Integer32	DINT

The object dictionary of interface CAN1 in total has available 16 TPDO and 16 RPDO. The first 4 TPDO and RPDO are preconfigured and activated according to the Predefined Connection Set. The first 32 Byte of input and output variables are mapped to those PDOs. Table 17 lists all preconfigured PDOs for interface CAN1.

Table 17: Preconfigured PDOs for interface CAN1

PDO	**CAN-ID**	**Data**
1. RPDO	0x200 + NodeID	%MB0.0 … %MB7.0
2. RPDO	0x300 + NodeID	%MB8.0 … %MB15.0
3. RPDO	0x400 + NodeID	%MB16.0 … %MB23.0
4. RPDO	0x500 + NodeID	%MB24.0 … %MB31.0
1. TPDO	0x180 + NodeID	%MB256.0 … %MB263.0
2. TPDO	0x280 + NodeID	%MB264.0 … %MB271.0
3. TPDO	0x380 + NodeID	%MB272.0 … %MB279.0
4. TPDO	0x480 + NodeID	%MB280.0 … %MB287.0

Due to limitation to 16 TPDO and 16 RPDO, only 256 Bytes (2 * 16PDO * 8Byte/PDO) of total 504 Bytes for network variables in the marker section (2 252Bytes) can be transferred via PDO. Irrespective of that it is possible to access all variables via SDO.

The configuration (mapping, CAN Identifier etc.) of interface CAN1 typically takes place via an external Configuration Manager that parameterizes the object dictionary on the basis of a DCF file created by the CANopen configurator. By using default object inputs 1010H und 1011H, the CTR-700 supports the persistent storage and reload of a backed configuration.

Alternatively, the configuration (mapping, CAN Identifier etc.) of the static object dictionary for interface CAN1 can take place from the PLC program by using SDO function blocks. Therefore, inputs *NETNUMBER* and *DEVICE* must be used as follows:

```
NETNUMBER  := 1;           (* Interface CAN1 *)
DEVICE     := 0;           (* local Node     *)
```

The PLC program example *"ConfigCAN1"* exemplifies the configuration of interface CAN0 through a PLC program by using function blocks of type *"CAN_SDO_Xxx"*.

10 Data exchange via shared process image

10.1 Overview of the shared process image

The CTR-700 is based on the operating system Linux. Thus, it is possible to execute other user-specific programs simultaneously to running the PLC firmware. The PLC program and a user-specific C/C++ application can exchange data by using the same process image (shared process image). Implementing user-specific applications **is based on the Software package** 3912005 ("Oracle VM VirtualBox-Image of the Linux development system").

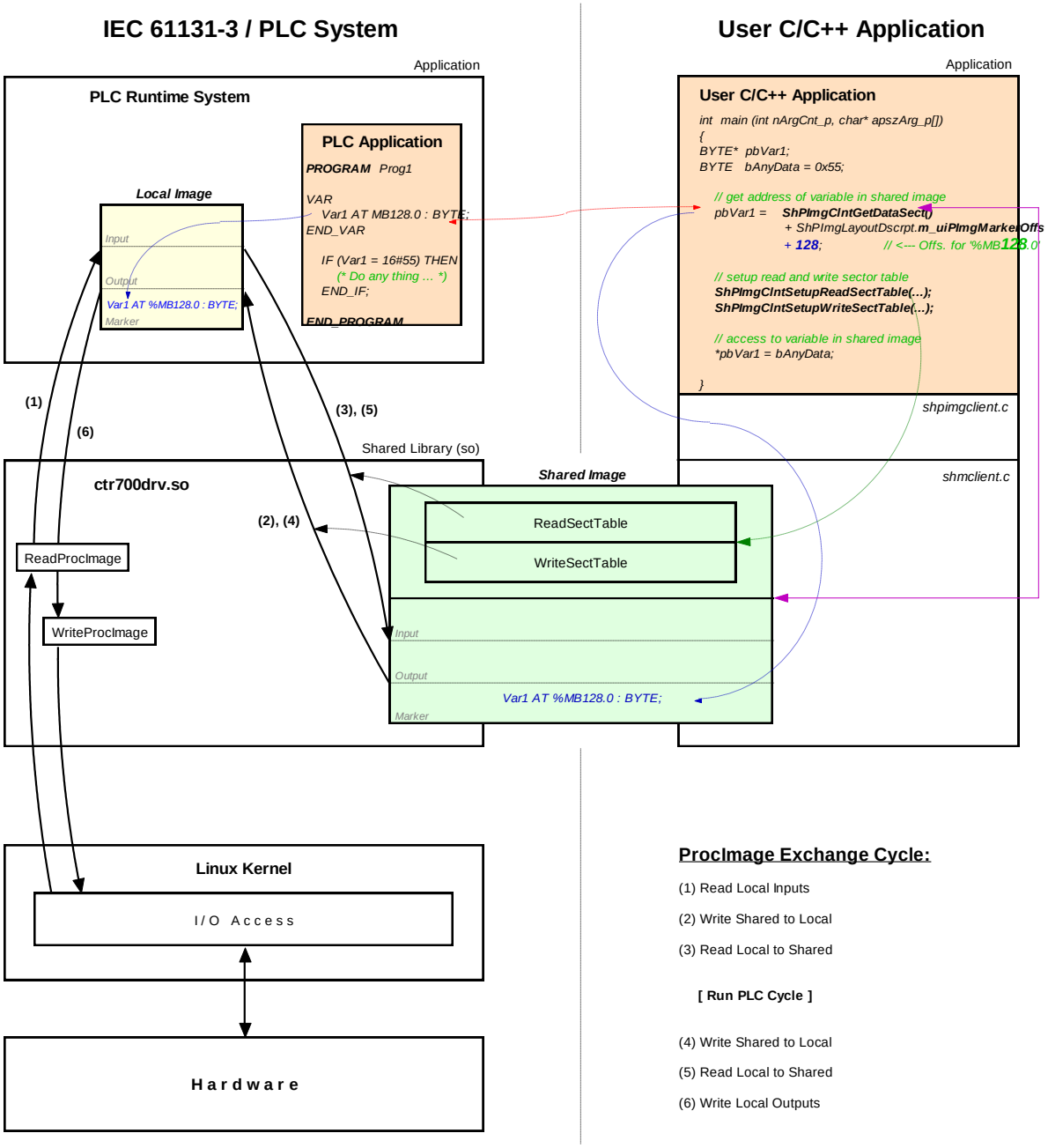


Figure 36: Overview of the shared process image

Not all variables are utilizable via the shared process image within a C/C++ application. Only those directly addressed variables that the PLC program generates within the process image. As shown in Figure 36, two separate process images are used for the data exchange with an external application inside of the PLC runtime system. This is necessary to meet the IEC 61131-3 requirement that the initial PLC process image may not be modified during the entire execution of one PLC program cycle. Thereby, the PLC program always operates with the internal process image that is locally generated within the PLC runtime system ("Local Image" in Figure 36). This is integrated within the PLC runtime system and is protected against direct accesses from the outside. On the contrary, the user-specific, external C/C++ application always uses the shared process image ("Shared Image" in Figure 36). This separation of two process images enables isolation between accesses to the PLC program and the external application. Those two in parallel and independently running processes now must only be synchronized for a short period of time to copy the process data.

An activation of **option *"Share PLC process image"*** within the PLC configuration enables data exchange with external applications (see section 5.6.1). Alternatively, entry *" EnableSharing="* can directly be set within section *"[ProcImg]"* of the configuration file ***"/home/plc/bin/ctr-700.cfg"*** (see section 5.6.2). The appropriate configuration setting is evaluated upon start of the PLC firmware. By activating option *"Share PLC process image"*, the PLC firmware creates a second process image as Shared Memory ("Shared Image" in Figure 36). Its task is to exchange data with external applications. Hereby, the PLC firmware functions as Server and the external, user-specific C/C++ application functions as Client.

ReadSectorTable and ***WriteSectorTable*** both control the copying of data between the two process images. Both tables are filled by the Client (external, user-specific C/C++ application) and are executed by Server (PLC runtime system). The Client defines ranges of the PLC process image from which it will read data (*ReadSectorTable*) or in which it will write data (*WriteSectorTable*). Hence, the terms *"Read"* and *"Write"* refer to data transfer directions from the viewpoint of the Client.

Sections to read and write may comprise all sections of the entire process image – input, output as well as marker sections. This allows for example that a Client application writes data into the input section of the PLC process image and reads data from the output section. Figure 36 shows the sequence of single read and write operations. Prior to the execution of a PLC program cycle, the physical inputs are imported into the local process image of the PLC (1). Afterwards, all sections defined in *WriteSectorTable* are taken over from the shared process image into the local process image (2). By following this sequence, a Client application for example is able to overwrite the value of a physical input. This may be used for simulation purposes as well as for setting input data to constant values (*"Forcen"*). Similarly, prior to writing the process image onto the physical outputs (6), sections defined in *WriteSectorTable* are taken over from the shared process image into the local process image. (4). Thus, a Client application is able to overwrite output information generated by the PLC program.

The PLC firmware provides the **setup of the process image**. The Client application receives information about the setup of the process image via function ***ShPImgClntSetup()***. This function enters start offsets and values of the input, output and marker sections into the structure of type *tShPImgLayoutDscrpt*. Function ***ShPImgClntGetDataSect()*** provides the start address of the shared process image. Upon defining a variable within the PLC program, its absolute position within the process image is determined through sections (%I = Input, %Q = Output, %M = Marker) and offset (e.g. %MB**128**.0). In each section the offset starts at zero, so that for example creating a new variable in the marker section would be independent of values in the input and output section. Creating a corresponding **pair of variables** in the PLC program as well as in the C/C++ application allows for data exchange between the PLC program and the external application. Therefore, both sides must refer to the same address. Structure *tShPImgLayoutDscrpt* reflects the physical setup of the process image in the PLC firmware including input, output and marker sections. This is to use an addressing

procedure for defining appropriate variables in the C/C++ application that is comparable to the PLC program. Hence, also in the C/C++ program a variable is defined in the shared process image by indicating the respective section and its offset. The following example illustrates the creation of a corresponding variable pair in the PLC program and C/C++ application:

PLC Program

```
VAR
    Var1 AT MB128.0 : BYTE;
END_VAR
```

C/C++ Application

```
BYTE*  pbVar1;

pbVar1 =   ShPImgClntGetDataSect()
         + ShPImgLayoutDscrpt.m_uiPImgMarkerOffs
         + 128;     // <--- Offset for '%MB128.0'
```

As described above, ***ReadSectorTable*** and ***WriteSectorTable*** manage the copy process to exchange variable contents between the PLC and the C/C++ program. Following the example illustrated, the Client (C/C++ application) must enter an appropriate value into the *WriteSectorTable* to transfer the value of a variable from the C/C++ application to the PLC program (*WriteSectorTable*, because the Client “writes” the variable to the Server):

```
// specify offset and size of 'Var1' and define sync type (always or on demand?)
WriteSectTab[0].m_uiPImgDataSectOffs = ShPImgLayoutDscrpt.m_uiPImgMarkerOffs + 128;
WriteSectTab[0].m_uiPImgDataSectSize = sizeof(BYTE);
WriteSectTab[0].m_SyncType           = kShPImgSyncOnDemand;

// define the WriteSectorTable with the size of 1 entry
ShPImgClntSetupWriteSectTable (WriteSectTab, 1);
```

If several variable pairs are generated within the same transfer direction for the data exchange between the PLC program and the C/C++ application, they should possibly all be defined in one coherent address range. Thus, it is possible to list them as one entry in the appropriate SectorTable. The address of the first variable must be set as the *SectorOffset* and the sum of the variable sizes as *SectorSize*. Combining the variables improves the efficiency and the performance of the copy processes.

For each entry of the *WriteSectorTable* an appropriate *SyncType* must be defined. It determines whether the section is generally taken over from the shared process image into the local image whenever there are two successive PLC cycles (***kShPImgSyncAlways***) or whether it is taken over on demand (***kShPImgSyncOnDemand***). If classified as *SyncOnDemand*, the data only is copied if the respective section before was explicitly marked as updated. This takes places by calling function ***ShPImgClntWriteSectMarkNewData()*** and entering the corresponding *WriteSectorTable*-Index (e.g. 0 for *WriteSectTab[0]* etc.).

kShPImgSyncAlways is provided as *SyncType* for the *ReadSectorTable* (the value of the member element *m_SyncType* is ignored). The PLC firmware is not able to identify which variables were changed by the PLC program of the cycle before. Hence, all sections defined in *ReadSectorTable* are always taken over from the local image into the shared process image. Thus, the respective variables in the shared process image always hold the actual values.

The PLC firmware and the C/C++ application both use the shared process image. To prevent conflicts due to accesses from both of those in parallel running processes at the same time, the shared process

image is internally protected by a semaphore. If one process requires access to the shared process image, this process enters a critical section by setting the semaphore first and receiving exclusive access to the shared process image second. If the other process requires access to the shared process image at the same time, it also must enter a critical section by trying to set the semaphore. In this case, the operating system identifies that the shared process image is already being used. It blocks the second process until the first process leaves the critical section and releases the semaphore. Thereby, the operating system assures that only one of the two in parallel running processes (PLC runtime system and C/C++ application) may enter the critical section and receives access to the shared process image. To ensure that both processes do not interfere with each other too much, they should enter the critical section as less as possible and only as long as necessary. Otherwise, the PLC cycle time may be extended and runtime variations (Jitter) may occur.

The client application has available two functions to set the semaphore and to block exclusive access to the shared process image. Function ***ShPImgClntLockSegment()*** is necessary to enter the critical section and function ***ShPImgClntUnlockSegment()*** to leave it. The segment between both functions is called protected section, because in this segment the client application holds access to the shared process image without competition. The consistency of read or written data is only guaranteed within such a protected section. Outside the protected section, the shared process image may anytime be manipulated by the PLC runtime system. The following example shows the exclusive access to the shared process image in the C/C++ application:

```
ShPImgClntLockSegment();
{
    // write new data value into Var1
    *pbVar1 = bAnyData;

    // mark new data for WriteSectorTable entry number 0
    ShPImgClntWriteSectMarkNewData (0);
}
ShPImgClntUnlockSegment();
```

For the example above, *kShPImgSyncOnDemand* was defined as *SyncType* upon generating entry *WriteSectorTable*. Hence, taking over variable *Var1* from the shared process image into the local image can only take place if the respective section was beforehand explicitly marked as updated. Therefore, it is necessary to call function ***ShPImgClntWriteSectMarkNewData()***. Since function *ShPImgClntWriteSectMarkNewData()* does not modify the semaphore, it may only be used within a protected section (see example) – such as the code section between *ShPImgClntLockSegment()* and *ShPImgClntUnlockSegment()*.

The synchronization between local image and shared process image by the PLC runtime system only takes place in-between two successive PLC cycles. A client application (user-specific C/C++ program) is not directly informed about this point of time, but it can get information about the update of the shared process image from the PLC runtime system. Therefore, the client application must define a callback handler of the type *tShPImgAppNewDataSigHandler*, e.g.:

```
static  void  AppSigHandlerNewData (void)
{
    fNewDataSignaled_l = TRUE;
}
```

This callback handler must be registered with the help of function ***ShPImgClntSetNewDataSigHandler()***. The handler is selected subsequent to a synchronization of the two images.

The **callback handler of the client application is called within the context of a Linux signal handler** (the PLC runtime system informs the client using Linux function *kill()*). Accordingly, all common **restrictions** for the Linux signal handler also apply to the callback handler of the client application. In particular, it is only allowed to call a few operating system functions that are explicitly marked as reentrant-proof. Please pay attention to not make reentrant calls of local functions within the client application. As shown in the example, only a global flag should be set for the signaling within the callback handler. This flag will later on be evaluated and processed in the main loop of the client application.

10.2 API of the shared process image client

As illustrated in Figure 36, the user-specific C/C++ application exclusively uses the API (Application Programming Interface) provided by the s*hared process image client*. This API is declared in the header file *shpimgclient.h* and implemented in the source file *shpimgclient.c*. It contains the following types (partly defined in *shpimg.h*) and functions:

Structure *tShPImgLayoutDscrpt*

```
typedef struct
{
    // definition of process image sections
    unsigned int        m_uiPImgInputOffs;      // start offset of input section
    unsigned int        m_uiPImgInputSize;      // size of input section
    unsigned int        m_uiPImgOutputOffs;     // start offset of output section
    unsigned int        m_uiPImgOutputSize;     // size of output section
    unsigned int        m_uiPImgMarkerOffs;     // start offset of marker section
    unsigned int        m_uiPImgMarkerSize;     // size of marker section

} tShPImgLayoutDscrpt;
```

Structure ***tShPImgLayoutDscrpt*** describes the setup of the process image given by the PLC firmware. The client application receives the information about the setup of the process image via function *ShPImgClntSetup()*. This function enters start offsets and values of input, output and marker sections into the structure provided upon function calling.

Structure *tShPImgSectDscrpt*

```
typedef struct
{
    // definition of data exchange section
    unsigned int        m_uiPImgDataSectOffs;
    unsigned int        m_uiPImgDataSectSize;
    tShPImgSyncType     m_SyncType;               // only used for WriteSectTab
    BOOL                m_fNewData;

} tShPImgSectDscrpt;
```

Structure ***tShPImgSectDscrpt*** describes the setup of a *ReadSectorTable* or *WriteSectorTable* entry that must be defined by the client. Both tables support the synchronization between the local image of the PLC runtime system and the shared process image (see section 10.1). Member element *m_uiPImgDataSectOffs* defines the absolute start offset of the section within the shared process images. The respective start offsets of the input, output and marker sections can be determined

through structure *tShPImgLayoutDscrpt*. Member element *m_uiPImgDataSectSize* determines the size of the section which may include one or more variables. Member element *m_SyncType* only applies to entries of the WriteSectorTable. It determines whether the section is generally taken over from the shared process image into the local image whenever there are two successive PLC cycles (***kShPImgSyncAlways***) or whether it is taken over on demand (***kShPImgSyncOnDemand***). If classified as *SyncOnDemand*, the data must be marked as modified by calling function *ShPImgClntWriteSectMarkNewData()*. It sets the member element *m_fNewData* to TRUE. The client application should never directly modify this member element.

Function *ShPImgClntSetup*

```
BOOL  ShPImgClntSetup  (tShPImgLayoutDscrpt* pShPImgLayoutDscrpt_p);
```

Function ***ShPImgClntSetup()*** initializes the *shared process image client* and connects itself with the storage segment for the shared process image which is generated by the PLC runtime system. Afterwards, it enters the start offsets and values of the input, output and marker sections into the structure of type *tShPImgLayoutDscrpt* provided upon function call. Hence, the client application receives notice about the process image setup managed by the PLC firmware.

If the PLC runtime system is not active when the function is called or if it has not generated a shared process image (option *"Share PLC process image"* in the PLC configuration deactivated, see section 10.1), the function will return with the return value FALSE. If the initialization was successful, the return value will be TRUE.

Function *ShPImgClntRelease*

```
BOOL  ShPImgClntRelease  (void);
```

Function ***ShPImgClntRelease()*** shuts down the s*hared process image client* and disconnects the connection to the storage segment generated for the shared process image by the PLC runtime system.

If executed successfully, the function delivers return value TRUE. If an error occurs, it will deliver return value FALSE.

Function *ShPImgClntSetNewDataSigHandler*

```
BOOL  ShPImgClntSetNewDataSigHandler  (
         tShPImgAppNewDataSigHandler pfnShPImgAppNewDataSigHandler_p);
```

Function ***ShPImgClntSetNewDataSigHandler()*** registers a user-specific callback handler. This callback handler is called after a synchronization of both images. Registered callback handlers are cleared by the parameter NULL.

The **callback handler is called within the context of a Linux signal handler**. Accordingly, all common **restrictions** for the Linux signal handler also apply to the callback handler (see section 10.1).

If executed successfully, the function delivers return value TRUE. If an error occurs, it will deliver return value FALSE.

Function *ShPImgClntGetHeader*

```
tShPImgHeader*  ShPImgClntGetHeader  (void);
```

Function ***ShPImgClntGetHeader()*** provides a pointer to the internally used structure type *tShPImgHeader* to manage the shared process image. The client application does usually not need this structure, because all data that it includes can be read and written through functions of the API provided by the *shared process image client*.

Function *ShPImgClntGetDataSect*

```
BYTE*  ShPImgClntGetDataSect  (void);
```

Function ***ShPImgClntGetDataSect()*** provides a pointer to the beginning of the shared process image. This pointer represents the basic address for all accesses to the shared process image; including the definition of sections *ReadSectorTable* and *WriteSectorTable* (see section 10.1).

Funktionen Functions *ShPImgClntLockSegment* and *ShPImgClntUnlockSegment*

```
BOOL  ShPImgClntLockSegment  (void);
BOOL  ShPImgClntUnlockSegment  (void);
```

To exclusively access the shared process image, the client application has available two functions - function ***ShPImgClntLockSegment()*** to enter the critical section and function ***ShPImgClntUnlockSegment()*** to leave it. The segment between both functions is called protected section, because in this segment the client application holds unrivaled access to the shared process image (see section 10.1). The consistency of read or written data is only guaranteed within such a protected section. Outside the protected section, the shared process image may anytime be manipulated by the PLC runtime system. To ensure that the client application does not interfere with the PLC runtime system too much, the critical sections should be set as less as possible and only as long as necessary. Otherwise, the PLC cycle time may be extended and runtime variations (Jitter) may occur.

If executed successfully, the function delivers return value TRUE. If an error occurs, it will deliver return value FALSE.

Function *ShPImgClntSetupReadSectTable*

```
BOOL  ShPImgClntSetupReadSectTable  (
         tShPImgSectDscrpt* paShPImgReadSectTab_p,
         unsigned int uiNumOfReadDscrptUsed_p);
```

Function ***ShPImgClntSetupReadSectTable()*** initializes the *ReadSectorTable* with the values defined by the client. The client hereby determines those sections of the PLC process image from which it wants to read data (see section 10.1). Parameter *paShPImgReadSectTab_p* holds elements of the structure *tShPImgSectDscrpt* and must be transferred as start address of a section. Parameter *uiNumOfReadDscrptUsed_p* indicates how many elements the section has.

kShPImgSyncAlways is provided as *SyncType* for the *ReadSectorTable*.

If executed successfully, the function delivers return value TRUE. If an error occurs, it will deliver return value FALSE.

Function *ShPImgClntSetupWriteSectTable*

```
BOOL  ShPImgClntSetupWriteSectTable  (
         tShPImgSectDscrpt* paShPImgWriteSectTab_p,
         unsigned int uiNumOfWriteDscrptUsed_p);
```

Function ***ShPImgClntSetupWriteSectTable***() initializes the *WriteSectorTable* with the values defined by the client. The client hereby determines those sections of the PLC process image from which it wants to write data (see section 10.1). Parameter *paShPImgWriteSectTab_p* holds elements of structure *tShPImgSectDscrpt* and must be transferred as start address of a section. Parameter *uiNumOfWriteDscrptUsed_p* indicates how many elements the section has.

For each entry in the *WriteSectorTable* the *SyncType* must be defined. This *SyncType* defines whether the section is always taken over into the local image between two PLC cycles (***kShPImgSyncAlways***) or only on demand (***kShPImgSyncOnDemand***). If taken over on demand, the respective section is explicitly marked as updated by calling *ShPImgClntWriteSectMarkNewData()*.

If executed successfully, the function delivers return value TRUE. If an error occurs, it will deliver return value FALSE.

Function *ShPImgClntWriteSectMarkNewData*

```
BOOL  ShPImgClntWriteSectMarkNewData  (unsigned int uiWriteDscrptIdx_p);
```

For the content of a section that is held by the *WriteSectorTable*, function ***ShPImgClntWriteSectMarkNewData()*** marks this content as modified. This function is used (for sections with *SyncType* ***kShPImgSyncOnDemand***) to initiate the copy process of data from the shared process image into the local image of the PLC.

Function *ShPImgClntWriteSectMarkNewData()* directly accesses the header of the shared process image without setting a semaphore before. Hence, it may only be used within the protected section – in the code section between *ShPImgClntLockSegment()* and *ShPImgClntUnlockSegment()*.

If executed successfully, the function delivers return value TRUE. If an error occurs, it will deliver return value FALSE.

10.3 Creating a user-specific client application

Software package 3912005 ("Oracle VM VirtualBox-Image of the Linux development system") is the precondition for the implementation of user-specific C/C++ applications. It contains a complete Linux development system in the form of a VirtualBox image. Hence, it allows for an easy introduction into the C/C++ software development for the CTR-700. Thus, the VirtualBox image is the ideal basis to develop Linux-based user programs on the same host PC that already has the *OpenPCS* IEC 61131 programming system installed on it. The VirtualBox image of the Linux development system includes

the GNU-Crosscompiler Toolchain for ARM processors. Additionally, it includes essential server services that are preconfigured and usable for effective software development.

As illustrated in Figure 36, the user-specific C/C++ application uses the API (files *shpimgclient.c* and *shpimgclient.h*) which is provided by the *shared process image client*. The *shared process image client* is based on services provided by the *shared memory client* (files *shmclient.c* and *shmclient.c*). Both client implementations are necessary to generate a user-specific C/C++ application. The directory of the s*hared process image demo* (*/projects/CTR-700/user/shpimgdemo*) contains the respective files. To create own user-specific client applications, it is recommended to use this demo project as the basis for own adaptations and extensions. Moreover, this demo project contains a Makefile with all relevant configuration adjustments that are necessary to create a Linux application for the CTR-700. Table 18 lists all files of the directory *shpimgdemo* and classifies those as general part of the C/C++ application or as specific component for the demo project *"shpimgdemo"*.

Table 18: Content of the archive files "shpimgdemo.tar.gz"

File	**Necessary for all C/C++ applications**	**In particular for demo *"shpimgdemo"***
shpimgclient.c	x	
shpimgclient.h	x	
shmclient.c	x	
shmclient.h	x	
shpimg.h	x	
global.h	x	
Makefile	draft, to be adjusted	
shpimgdemo.c		x
trmio.c		x
trmio.h		x
trace.c		x

The demo project can be built by calling command *"make"*:

```
cd  /projects/CTR-700/user/shpimgdemo
make
```

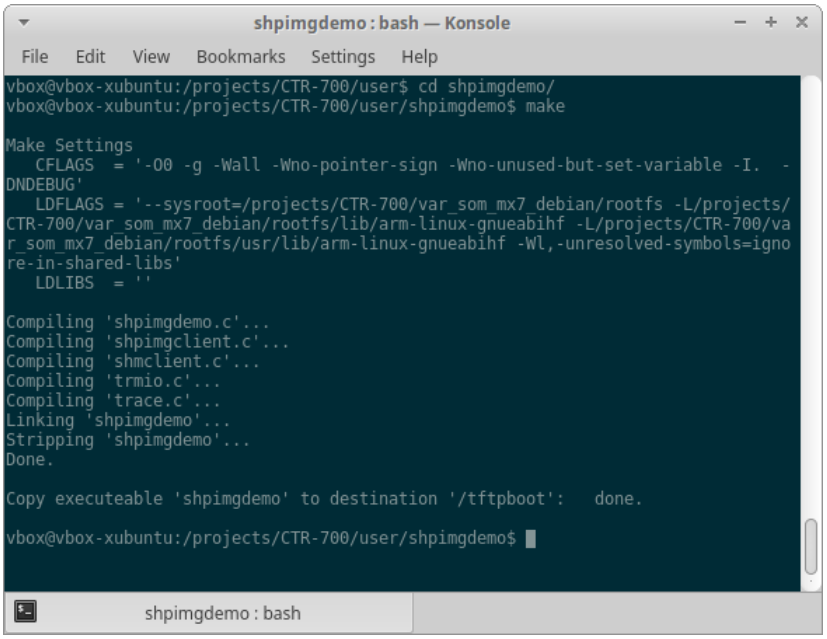


Figure 37: Generating the demo project "shpimgdemo" in the Linux development system

Section 10.4 describes the usage and handling of the demo project *"shpimgdemo"* on the CTR-700.

10.4 Example for using the shared process image

The demo project *"shpimgdemo"* (described in section 10.3) in connection with the PLC program example *"RunLight"* both exemplify the data exchange between a PLC program and a user-specific C/C++ application.

Technical background

The PLC program generates some variables in the process image as directly addressable variables. In a C/C++ application, all those variables are usable via the shared process image. For the PLC program example *"RunLight"* those are the following variables:

```
 (* variables for local control via on-board I/O's *)
bButtonGroup        AT %IB0.0   : BYTE;
iAnalogValue        AT %IW8.0   : INT;
bLEDGroup0          AT %QB0.0   : BYTE;
bLEDGroup1          AT %QB1.0   : BYTE;

(* variables for remote control via shared process image  *)
uiRemoteSlidbarLen  AT %MW512.0 : UINT;     (* out: length of slidebar         *)
bRemoteStatus       AT %MB514.0 : BYTE;     (* out: Bit0: RemoteControl=on/off *)
bRemoteDirCtrl      AT %MB515.0 : BYTE;     (* in:  direction left/right       *)
iRemoteSpeedCtrl    AT %MW516.0 : INT;      (* in:  speed                      *)
```

Variables of the PLC program are accessible from a C/C++ application via the shared process image. Therefore, sections must be generated for the *ReadSectorTable* and *WriteSectorTable* on the one hand and on the other hand, pointers must be defined for accessing the variables. The following program extract shows this using the example *"shpimgdemo.c"*. Function *ShPImgClntSetup()* inserts the start offsets of input, output and marker sections into the structure *ShPImgLayoutDscrpt*. Hence, on the basis of the initial address provided by *ShPImgClntGetDataSect()*, the absolute initial addresses of each section in the shared process image can be determined. To identify the address of a variable, the variable's offset within the particular section must be added. For example, the absolute address to access the variable *"bRemoteDirCtrl AT %MB515.0 : BYTE;"* results from the sum of the initial address of the shared process image (pabShPImgDataSect), the start offset of the marker section (*ShPImgLayoutDscrpt.m_uiPImgMarkerOffs für "%M…"*) as well as the direct address within the marker section which was defined in the PLC program (515 for "%MB515.0"):

```
    pbPImgVar_61131_bDirCtrl = (BYTE*) (pabShPImgDataSect
                + ShPImgLayoutDscrpt.m_uiPImgMarkerOffs + 515);
```

The following code extract shows the complete definition of all variables in the demo project used for exchanging data with the PLC program:

```
// ---- Setup shared process image client ----
fRes = ShPImgClntSetup (&ShPImgLayoutDscrpt);
if ( !fRes )
{
    printf ("\n*** ERROR *** Init of shared process image client failed");
}

pabShPImgDataSect = ShPImgClntGetDataSect();


// ---- Read Sector Table ----
// Input Section:       bButtonGroup AT %IB0.0
{
    ShPImgReadSectTab[0].m_uiPImgDataSectOffs =
                ShPImgLayoutDscrpt.m_uiPImgInputOffs + 0;
    ShPImgReadSectTab[0].m_uiPImgDataSectSize = sizeof(BYTE);
    ShPImgReadSectTab[0].m_SyncType           = kShPImgSyncAlways;

    pbPImgVar_61131_bButtonGroup = (BYTE*) (pabShPImgDataSect
                + ShPImgLayoutDscrpt.m_uiPImgInputOffs + 0);
}
```

```
// Output Section:      bLEDGroup0 AT %QB0.0
//                      bLEDGroup1 AT %QB1.0
{
    ShPImgReadSectTab[1].m_uiPImgDataSectOffs =
                ShPImgLayoutDscrpt.m_uiPImgOutputOffs + 0;
    ShPImgReadSectTab[1].m_uiPImgDataSectSize = sizeof(BYTE) + sizeof(BYTE);
    ShPImgReadSectTab[1].m_SyncType           = kShPImgSyncAlways;

    pbPImgVar_61131_bLEDGroup0 = (BYTE*) (pabShPImgDataSect
               + ShPImgLayoutDscrpt.m_uiPImgOutputOffs + 0);
    pbPImgVar_61131_bLEDGroup1 = (BYTE*) (pabShPImgDataSect
               + ShPImgLayoutDscrpt.m_uiPImgOutputOffs + 1);
}

// Marker Section:      uiSlidbarLen AT %MW512.0
//                      bStatus      AT %MB514.0
{
    ShPImgReadSectTab[2].m_uiPImgDataSectOffs =
                ShPImgLayoutDscrpt.m_uiPImgMarkerOffs + 512;
    ShPImgReadSectTab[2].m_uiPImgDataSectSize =   sizeof(unsigned short int)
                                                + sizeof(BYTE);
    ShPImgReadSectTab[2].m_SyncType           = kShPImgSyncAlways;

    pbPImgVar_61131_usiSlidbarLen = (unsigned short int*) (pabShPImgDataSect
               + ShPImgLayoutDscrpt.m_uiPImgMarkerOffs + 512);
    pbPImgVar_61131_bStatus = (BYTE*) (pabShPImgDataSect
               + ShPImgLayoutDscrpt.m_uiPImgMarkerOffs + 514);
}

fRes = ShPImgClntSetupReadSectTable (ShPImgReadSectTab, 3);
if ( !fRes )
{
    printf ("\n*** ERROR *** Initialization of read sector table failed");
}

// ---- Write Sector Table ----
// Marker Section:      bDirCtrl   AT %MB515.0
//                      iSpeedCtrl AT %MB516.0
{
    ShPImgWriteSectTab[0].m_uiPImgDataSectOffs =
                ShPImgLayoutDscrpt.m_uiPImgMarkerOffs + 515;
    ShPImgWriteSectTab[0].m_uiPImgDataSectSize = sizeof(BYTE) + sizeof(WORD);
    ShPImgWriteSectTab[0].m_SyncType           = kShPImgSyncOnDemand;

    pbPImgVar_61131_bDirCtrl = (BYTE*) (pabShPImgDataSect
               + ShPImgLayoutDscrpt.m_uiPImgMarkerOffs + 515);
    psiPImgVar_61131_iSpeedCtrl = (short int*) (pabShPImgDataSect
                + ShPImgLayoutDscrpt.m_uiPImgMarkerOffs + 516);
}

fRes = ShPImgClntSetupWriteSectTable (ShPImgWriteSectTab, 1);
if ( !fRes )
{
    printf ("\n*** ERROR *** Initialization of write sector table failed");
}
```

Realization on the CTR-700

To enable the execution of the *shared process image demo* without previous introduction into the Linux-based C/C++ programming for the CTR-700, the module comes with a preinstalled, translated and ready-to-run program version and PLC firmware (*"/home/plc/bin/shpimgdemo"*). The following description refers to this program version. Alternatively, the demo project can be newly-generated from the corresponding source files (see section 10.3) and can be started afterwards. As I/O-Simulator for practical controlling of the demo-program an I/O-Box is available from SYS TEC.

The following steps are necessary to run the *shared process image demo* on the CTR-700:

1. **Activate option *"Shared PLC process image"*** in the PLC configuration (see sections 10.1, 5.6.1 and 5.6.2).

2. Open the PLC program example *"RunLight"* in the *OpenPCS* IEC 61131 programming system und build the project for a target hardware of the type *"SYSTEC – CTR-700"*

3. Select the network connection to the CTR-700 und download the program.

4. Start the PLC program on the CTR-700

5. Login to the command shell of the CTR-700 as described in section 5.9.1.

6. Switch to the directory *"/home/plc/bin"* and call the demo program *"shpimgdemo"*:

```
cd /home/plc/bin
./shpimgdemo
```

   The digital outputs of the CTR-700 are selected as runlight. The speed is modifiable via the analog input AI0. With the help of digital inputs DI0 and DI1, the running direction can be changed. After starting the demo program *"shpimgdemo"* on the CTR-700, actual status information about the runlight is indicated cyclically in the terminal (see Figure 38).

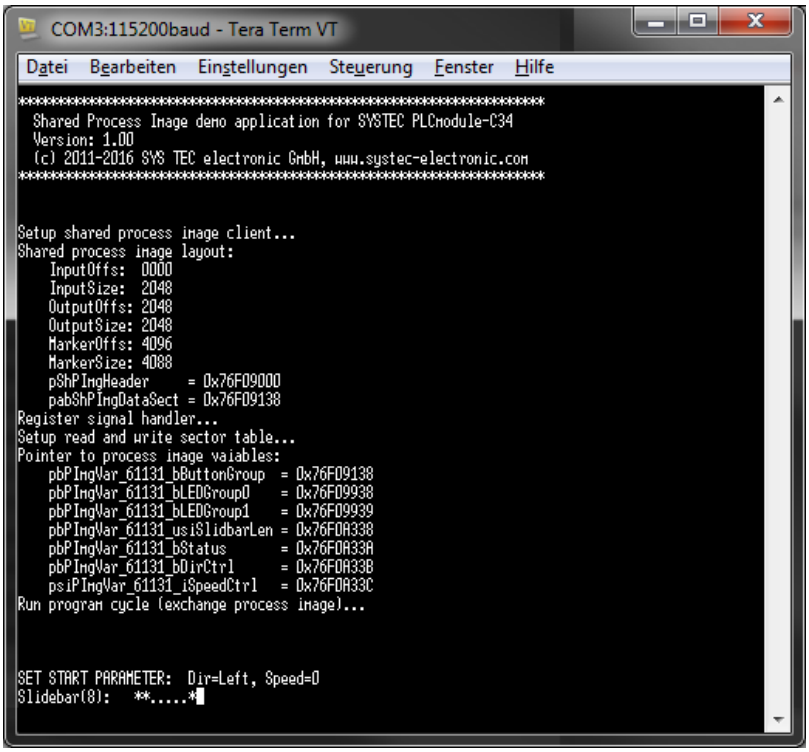


Figure 38: Terminal outputs of the demo program "shpimgdemo" after start

7. By activating of digital input DI3, the control of the runlight direction and speed is handed over to the demo program *"shpimgdemo"*. Afterwards, the running direction may be set by the C application by using the cursor pushbuttons left and right (← and →) in the terminal window and the speed may be changed by using cursor pushbuttons up and down (↑ and ↓).

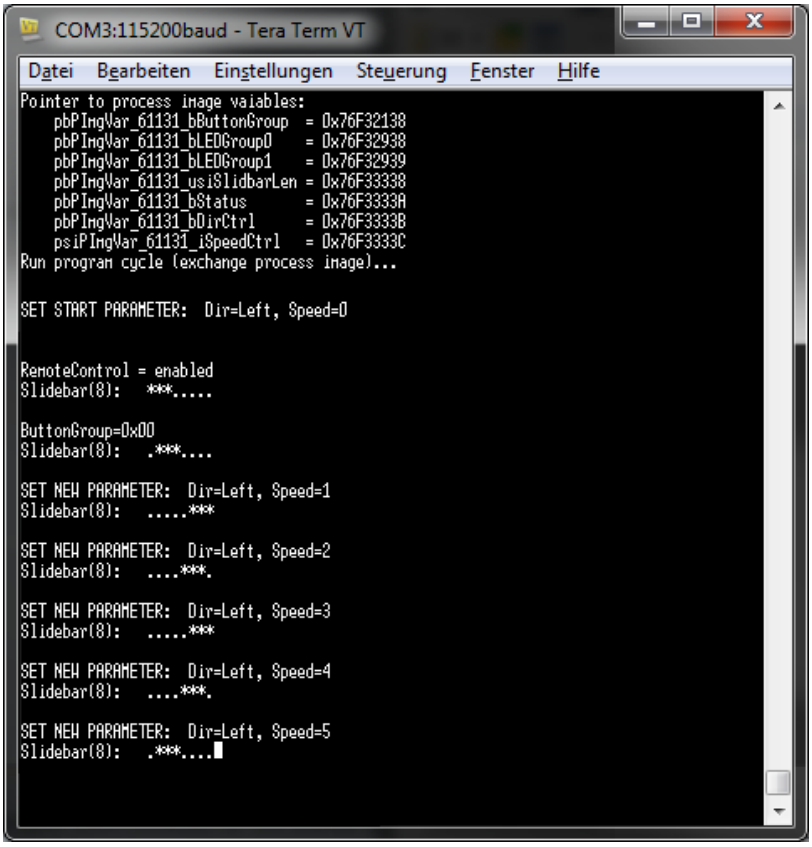


Figure 39: Terminal outputs of the demo program "shpimgdemo" after user inputs

Figure 39 shows the terminal outputs of the demo program *"shpimgdemo"* in answer to activating the cursor pushbuttons.

The demo program *"shpimgdemo"* may be terminated by pressing "Ctrl+C" in the terminal window.

Appendix A: Firmware function scope of CTR-700

Table 19 lists all firmware functions and function blocks available on the CTR-700.

Sign explanation:

FB	Function block
FUN	Function
Online Help	*OpenPCS* online help
L-1054	Manual *"SYS TEC-specific extensions for OpenPCS / IEC 61131-3"*, Manual no.: L-1054)
PARAM:={0,1,2}	values 0, 1 and 2 are valid for the given parameter

Table 19: Firmware functions and function blocks of CTR-700

Name	Type	Reference	Remark
PLC standard Functions and Function Blocks			
SR	FB	Online Help	
RS	FB	Online Help	
R_TRIG	FB	Online Help	
F_TRIG	FB	Online Help	
CTU	FB	Online Help	
CTD	FB	Online Help	
CTUD	FB	Online Help	
TP	FB	Online Help	
TON	FB	Online Help	
TOF	FB	Online Help	

Functions and Function Blocks for string manipulation			
ETRC	FB	L-1054	
PTRC	FB	L-1054	
GETVARPOINTER	FB	L-1054	
BIN_TO_STR	FUN	L-1054	
STR_TO_BIN	FUN	L-1054	
OBJ_TO_STR	FB	L-1054	
GETSTRINFO	FB	L-1054	
CHR	FUN	L-1054	
ASC	FUN	L-1054	
STR	FUN	L-1054	
VAL	FUN	L-1054	
LEN	FUN	L-1054	
LEFT	FUN	L-1054	
RIGHT	FUN	L-1054	
MID	FUN	L-1054	
CONCAT	FUN	L-1054	
INSERT	FUN	L-1054	
DELETE	FUN	L-1054	
REPLACE	FUN	L-1054	
FIND	FUN	L-1054	
STR_UPPER	FUN		
STR_LOWER	FUN		
STR_TRIM	FUN		
Functions and Function Blocks for OpenPCS specific task controlling			
GETVARDATA	FB	Online Help	
GETVARFLATADDRESS	FB	Online Help	
GETTASKINFO	FB	Online Help	
Functions and Function Blocks for handling of non-volatile data			
NVDATA_BIT	FB	L-1054	DEVICE:={0} see (1)
NVDATA_INT	FB	L-1054	DEVICE:={0} see (1)
NVDATA_STR	FB	L-1054	DEVICE:={0} see (1)
NVDATA_BIN	FB	L-1054	DEVICE:={0} see (1)
Functions and Function Blocks for handling of time			
GETTIME	FUN	Online Help	
GETTIMECS	FUN	Online Help	
TIME_TO_DINT	FUN		
DINT_TO_TIME	FUN		
DT_CLOCK	FB	L-1054	
DT_ABS_TO_REL	FB	L-1054	
DT_REL_TO_ABS	FB	L-1054	
DT_REL_TO_DT			

Functions and Function Blocks for counter inputs and pulse outputs			
CNT_FUD	FB	L-1054	CHANNEL:={0,1,2}
PTO_PWM	FB	L-1054	CHANNEL:={0,1}
PTO_TAB	FB	L-1054	CHANNEL:={0,1}
Function Block for PID regulator			
PID1	FB	L-1054	
Functions and Function Blocks for Serial interfaces			
SIO_INIT	FB	L-1054	PORT:={0,1,2,3} see (2)
SIO_STATE	FB	L-1054	PORT:={0,1,2,3} see (2)
SIO_READ_CHR	FB	L-1054	PORT:={0,1,2,3} see (2)
SIO_WRITE_CHR	FB	L-1054	PORT:={0,1,2,3} see (2)
SIO_READ_STR	FB	L-1054	PORT:={0,1,2,3} see (2)
SIO_WRITE_STR	FB	L-1054	PORT:={0,1,2,3} see (2)
SIO_READ_BIN	FB	L-1054	PORT:={0,1,2,3} see (2)
SIO_WRITE_BIN	FB	L-1054	PORT:={0,1,2,3} see (2)
Functions and Function Blocks for CAN interfaces / CANopen			
CAN_GET_LOCALNODE_ID	FB	L-1008	NETNUMBER:={0,1}
CAN_CANOPEN_KERNEL_STATE	FB	L-1008	NETNUMBER:={0,1}
CAN_REGISTER_COBID	FB	L-1008	NETNUMBER:={0,1}
CAN_PDO_READ8	FB	L-1008	NETNUMBER:={0,1}
CAN_PDO_WRITE8	FB	L-1008	NETNUMBER:={0,1}
CAN_SDO_READ8	FB	L-1008	NETNUMBER:={0,1}
CAN_SDO_WRITE8	FB	L-1008	NETNUMBER:={0,1}
CAN_SDO_READ_STR	FB	L-1008	NETNUMBER:={0,1}
CAN_SDO_WRITE_STR	FB	L-1008	NETNUMBER:={0,1}
CAN_SDO_READ_BIN	FB	L-1008	NETNUMBER:={0,1}
CAN_SDO_WRITE_BIN	FB	L-1008	NETNUMBER:={0,1}
CAN_GET_STATE	FB	L-1008	NETNUMBER:={0,1}
CAN_NMT	FB	L-1008	NETNUMBER:={0,1}
CAN_RECV_EMCY_DEV	FB	L-1008	NETNUMBER:={0,1}
CAN_RECV_EMCY	FB	L-1008	NETNUMBER:={0,1}
CAN_WRITE_EMCY	FB	L-1008	NETNUMBER:={0,1}
CAN_RECV_BOOTUP_DEV	FB	L-1008	NETNUMBER:={0,1}
CAN_RECV_BOOTUP	FB	L-1008	NETNUMBER:={0,1}
CAN_ENABLE_CYCLIC_SYNC	FB	L-1008	NETNUMBER:={0,1}
CAN_SEND_SYNC	FB	L-1008	NETNUMBER:={0,1}

CANL2_INIT	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_SHUTDOWN	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_RESET	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_GET_STATUS	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_DEFINE_CANID	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_DEFINE_CANID_RANGE	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_UNDEFINE_CANID	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_UNDEFINE_CANID_RANGE	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_MESSAGE_READ8	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_MESSAGE_READ_BIN	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_MESSAGE_WRITE8	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_MESSAGE_WRITE_BIN	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_MESSAGE_UPDATE8	FB	L-1008	NETNUMBER:={0,1} see (3)
CANL2_MESSAGE_UPDATE_BIN	FB	L-1008	NETNUMBER:={0,1} see (3)
Functions and Function Blocks for Ethernet interfaces / UDP			
LAN_GET_HOST_CONFIG	FB	L-1054	NETNUMBER:={0}
LAN_ASCII_TO_INET	FB	L-1054	NETNUMBER:={0}
LAN_INET_TO_ASCII	FB	L-1054	NETNUMBER:={0}
LAN_GET_HOST_BY_NAME	FB	L-1054	NETNUMBER:={0}
LAN_GET_HOST_BY_ADDR	FB	L-1054	NETNUMBER:={0}
LAN_UDP_CREATE_SOCKET	FB	L-1054	NETNUMBER:={0}
LAN_UDP_CLOSE_SOCKET	FB	L-1054	NETNUMBER:={0}
LAN_UDP_RECVFROM_STR	FB	L-1054	NETNUMBER:={0}
LAN_UDP_SENDTO_STR	FB	L-1054	NETNUMBER:={0}
LAN_UDP_RECVFROM_BIN	FB	L-1054	NETNUMBER:={0}
LAN_UDP_SENDTO_BIN	FB	L-1054	NETNUMBER:={0}

Functions and Function Blocks for file access			
FILE_OPEN	FB	L-1828	
FILE_CLOSE	FB	L-1828	
FILE_READ	FB	L-1828	
FILE_READ_LINE	FB	L-1828	
FILE_WRITE	FB	L-1828	
FILE_SEEK	FB	L-1828	
FILE_SYNC	FB	L-1828	
FILE_STAT	FB	L-1828	
FILE_CHMOD	FB	L-1828	
FILE_TOUCH	FB	L-1828	
FILE_DELETE	FB	L-1828	
FILE_RENAME	FB	L-1828	
FILE_COPY	FB	L-1828	
FILE_SPLIT_PATH	FB	L-1828	
FILE_DIR_OPEN	FB	L-1828	
FILE_DIR_CLOSE	FB	L-1828	
FILE_DIR_READ	FB	L-1828	
FILE_GET_DIR	FB	L-1828	
FILE_SET_DIR	FB	L-1828	
FILE_MKDIR	FB	L-1828	
FILE_RMDIR	FB	L-1828	
FILE_MKFIFO	FB	L-1828	
FILE_EXEC_SYS_CMD	FB	L-1828	
FTYPE_TO_UINT	FUN	L-1828	
FSEEK_TO_UINT	FUN	L-1828	
FPERM_TO_STRING	FUN	L-1828	
SYSERR_TO_STRING	FUN	L-1828	
Functions and Function Blocks for Modbus communication			
MODBUS_OPEN_INSTANCE	FB	L-1829	
MODBUS_CLOSE_INSTANCE	FB	L-1829	
MODBUS_REGISTER_VAR_LIST	FB	L-1829	
MODBUS_READ_REGS	FB	L-1829	
MODBUS_WRITE_SINGLE_REG	FB	L-1829	
MODBUS_WRITE_MULTI_REGS	FB	L-1829	
MODBUS_READ_WRITE_REGS	FB	L-1829	
MODBUS_READ_INPUT_REGS	FB	L-1829	
MODBUS_READ_DISCR_INPUTS	FB	L-1829	
MODBUS_READ_COILS	FB	L-1829	
MODBUS_WRITE_SINGLE_COIL	FB	L-1829	
MODBUS_WRITE_MULTI_COILS	FB	L-1829	
MODBUS_RAW_PDU_REQUEST	FB	L-1829	

Functions and Function Blocks for Modbus communication			
MQTT_GET_CAPABILITIES	FB	Demo	
MQTT_CONNECT	FB	Demo	
MQTT_DISCONNECT	FB	Demo	
MQTT_GET_CONNECT_STATE	FUN	Demo	
MQTT_SUBSCRIBE	FB	Demo	
MQTT_UNSUBSCRIBE	FB	Demo	
MQTT_GET_ARRIVED_MESSAGE	FB	Demo	
MQTT_PUBLISH	FB	Demo	
Functions and Function Blocks for Modbus communication			
WPC_CONNECT	FB		
WPC_DISCONNECT	FB		
WPC_READ_FRAME	FB		
WPC_GET_STATE	FB		

(1) All nonvolatile data is filed into directory *"/home/plc/plcdata/PlcPData.bin"* on the CTR-700. This file has a fix size of 32 KiB. By calling function blocks of type *NVDATA_Xxx* in a writing mode, the modified data is directly stored into file *"/home/plc/plcdata/PlcPData.bin"* ("*flush*"). Thus, unsecured data is not getting lost in case of power interruption.

(2) Interface SERVICE (PORT:=3) primarily serves as service interface to administer the CTR-700. Hence, this interface should only be used for sign output. The module always tries to interpret and execute sign inputs as Linux commands (see section 5.9.1).

(3) The usage of Function Blocks from type CANL2_Xxx is only possible, if the according CAN interface is not used already by CANopen. Due to its necessary to disable the according CAN interface in the PLC configuration (see section 5.6.1), otherwise the Function Blocks from type CANL2_Xxx can't be used. Alternatively, entry *"Enable="* can directly be set to 0 within section *"[CANx]"* of the configuration file *"/home/plc/bin/ctr-700.cfg***"** (see section 5.6.2).

Appendix B: Technical Specification

Environmental Parameters		Typical	Minimum Maximum
Power Supply	V_{CPU}	24VDC	- 19,2…30VDC
	V_{IO}	24VDC	19,2…30VDC
	power fail level	18,2V	
	power fail delay time	10ms	
Current Consumption (inactive IOs)	I_{CPU}	100mA	
	I_{IO}	30mA	
Temperature Range	Storage temperature		-20..+70°C
	Operating temperature		0…55°C
Protection class	Housing	IP20	
Weight	without any cable and packing	295g	
Dimensions	Width Height Depth		162mm 61mm 91mm
Connector type	Spring type connector		

I/O-configuration (digital)		Typical	Maximum
Digital Outputs DO0 ... 15			
24VDC-Output (High Side Switch)	U_{OH} at I_{OH} = 500 mA	V_{IO}-0,12V < U_{OH} <V_{IO}	
	U_{OL} at I_{OL} = 0 mA		0.5V
	Current limitation I_{OH_max}		700mA
	Max. current		16x0,5A
	$I_{OL(off)}$		10µA
	t_{off} at I_{OH} = 500 mA	22µs	27µs
	t_{on} at I_{OH} = 500 mA	27µs	45µs
Digital Outputs RLY0/RLY1			
Relay output (N.O.)	Switching Voltage		220VDC 250VA
	Switching Current		2A
	Contact rating		60VA
	Durability (mechanical.)	$100x10^6$	
	Durability (electrical.) @12V/10mA @60V/500mA @30V/1000mA @30V/2000mA	 $5x10^7$ $5x10^5$ $1x10^6$ $2x10^5$	
	t_{on}	4ms	

	t_{off}	4ms	
	Isolation	1000Vrms	
Digital Inputs DI0 … 23			
24VDC- Inputs, plus switching	U_{IH}	15V	30V
	U_{IL}	-3V	5V
	I_{IH}	3,5mA	6mA
Counter Input C0			
24VDC- Inputs, plus switching	U_{IH}	15V	30V
	U_{IL}	-3V	5V
	I_{IH}	3,4mA	6mA
	Frequency		70kHz?????

I/O-configuration (analog)		Typical	Maximum
Analog Inputs AI0 ... 3			
0 ... +10V	Measurement range U_I	0…10V	
	Destructive voltage U_{I_max}		>30V
	Input resistance R_I	97kΩ ±0.1%	
	Physical Resolution		12Bit
0 ... +20mA	Measurement range U_I	0…20mA	
	Input resistance R_I	67Ω ±0.1%	
	Physical Resolution		12Bit

Communication Interfaces		Minimum	Maximum
CAN-Bus			
CAN1, CAN2	Baudrate	5kBaud	1Mbaud
	Max. number of nodes		64
	Transceiver	TJF1051T	
	CAN-H, CAN-L short-circuit-proof towards 24V		
RS-232/RS-485			
SERIAL0	Baudrate	1200Baud	115200Baud
SERIAL1	Baudrate	1200Baud	115200Baud
SERIAL2	Baudrate	1200Baud	115200Baud
SERVICE	Baudrate	1200Baud	115200Baud
Ethernet			
ETH0	Bandwith	10Mbit/s	100Mbit/s
ETH1	Bandwith	10Mbit/s	100Mbit/s

Appendix C: Third Party Software Components

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===============

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* gettext

  m4 source files used to probe features at build time: GPL

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* mcs/class/I18N/mklist.sh, tools/cvt.sh: GNU GPLv2

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============

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* mono/utils/freebsd-dwarf.h, freebsd-elf_common.h, freebsd-elf64.h
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* mono/metadata/w32file-unix-glob.c, w32file-unix-glob.h: BSD license

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```

==========

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From: james.newtonking@gmail.com [mailto:james.newtonking@gmail.com] On
Behalf Of James Newton-King
Sent: Tuesday, June 05, 2007 6:36 AM
To: Konstantin Triger
Subject: Re: Support request by Konstantin Triger for Json.NET

Hey Kosta

I think it would be awesome to use Json.NET in Mono for
System.Web.Extensions.

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waived if you get permission from the copyright holder.

I can waive that statement for you and Mono. Would that be acceptable?


Regards,
James

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Node-RED

A visual tool for wiring the Internet of Things.

Project URL: https://github.com/node-red/node-red

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Docker CE (Community Edition)

The Docker CE package is an open source operating-system-level virtualization (containerization) application, which provides resource isolation of “containers” by using various features of the Linux kernel instead of running actual virtual machines (VMs).

Project URL: https://github.com/docker/docker-ce/

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EMV-KONFORMITÄTSERKLÄRUNG
DECLARATION OF EMC-CONFORMITY

Wir (Name des Herstellers)
We (name of the producer)

SYS TEC electronic GmbH

Adresse
address

Am Windrad 2
D-08468 Heinsdorfergrund

Erklären in alleiniger Verantwortung, dass das Produkt:
declare under sole responsibility, that the product:

sysWORXX CTR-700

Typ, Artikel-Nr.
type, article no.

16061001, Rev.1

die Anforderungen der folgenden harmonisierten Normen erfüllt /
fulfils the following harmonized standards

EN 61131-2:2007 **Chapter 8, zone B**	Speicherprogrammierbare Steuerungen – Teil 2: Betriebsmittelanforderungen und Prüfungen (IEC 61131-2:2007); Deutsche Fassung EN 61131-2:2007 *Programmable controllers – Part 2: Equipment requirements and tests (IEC 61131-2:2007); German version EN 61131-2:2007*

und damit folgender EU-Richtlinie entspricht:
and therefore, corresponds to the EU-directive:

EMV-Richtlinie 2014/30/EG
EMC-Directive 2014/30/EG

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Name / *name*	Siegmar Schmidt
Funktion / *title*	Chief Executive Officer
Datum / *date*	23.05.2018
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SYS TEC
ELECTRONIC GmbH
Am Windrad 2
D-08468 Heinsdorfergrund
Tel.: 03765 38600-0 / Fax: 38600-4100
info@systec-electronic.com
www.systec-electronic.com

Appendix E: Declaration of RoHS-Conformity

RoHS-KONFORMITÄTSERKLÄRUNG
DECLARATION OF RoHS-CONFORMITY

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We (name of the producer)

SYS TEC electronic GmbH

Adresse
address

Am Windrad 2
D-08468 Heinsdorfergrund

Erklären in alleiniger Verantwortung, dass das Produkt:
declare under sole responsibility, that the product:

sysWORXX CTR-700

Typ, Artikel-Nr.
type, article no.

16061001, Rev.1

die Anforderungen der EU-Richtlinie 2011/65/EU entsprechend erfüllt. Dieses Produkt erfüllt die derzeitigen Anforderungen der RoHS Direktive für alle 7 benannten Materialien (max. 0,1% des Gewichtes in homogenem Material für Blei, Quecksilber, sechswertiges
Chrom, polybromiertes Biphenyl (PBB), polybromierten Diphenylether (PBDE), Deca-BDE und max. 0,01% des Gewichtes für Cadmium).

complies with the requirements of the fulfils the EG directive 2011/65/EU This product is compatible with the current RoHS requirements for the 7 substances (max 0.1% by weight in homogeneous materials for lead, mercury, hexavalent chromium, polybrominated biphenyls (PBB), polybrominated diphenyl ethers (PBDE), Deca-BDE and max 0.01% for cadmium).

und damit folgender EU-Richtlinie entspricht:
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