

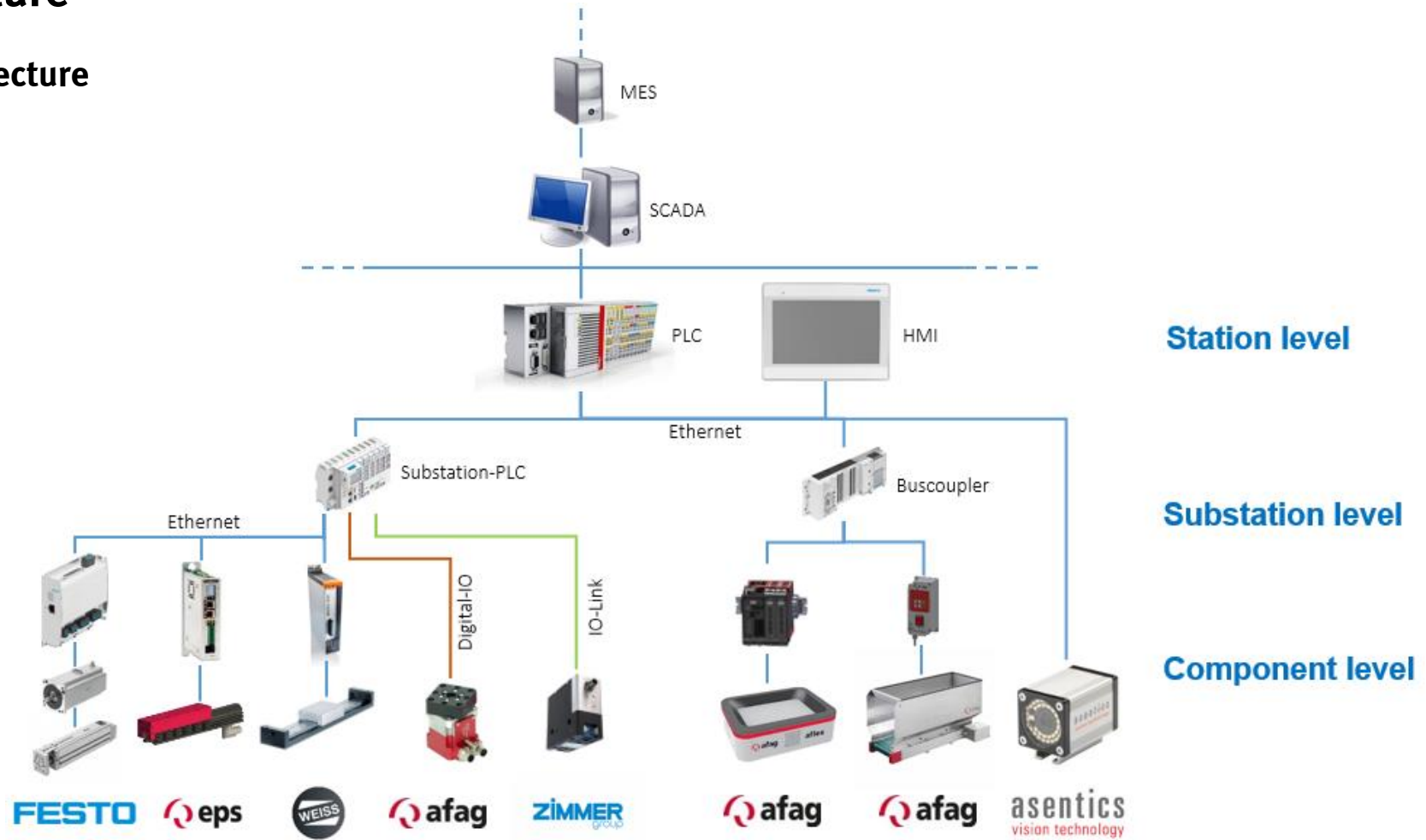
# AutomationML for automation components

**Mathias Wiegand**  
**Festo AG & Co. KG, Esslingen am Neckar**  
**Advanced Development Automation Engineering**

**Johannes Hoos**  
**Festo AG & Co. KG, Esslingen am Neckar**  
**Specialist System Architecture**

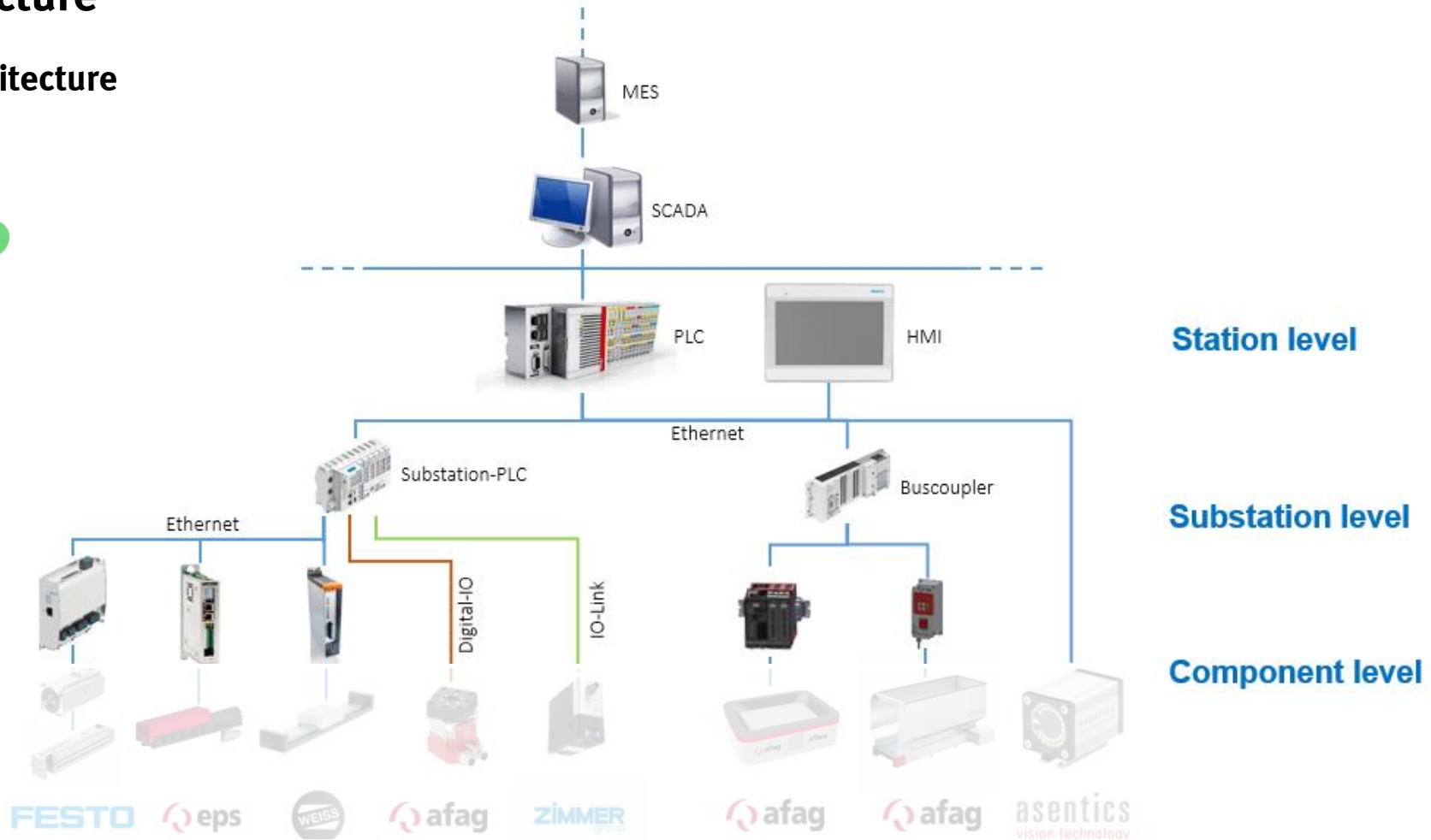
# Machine architecture

## Classical control architecture



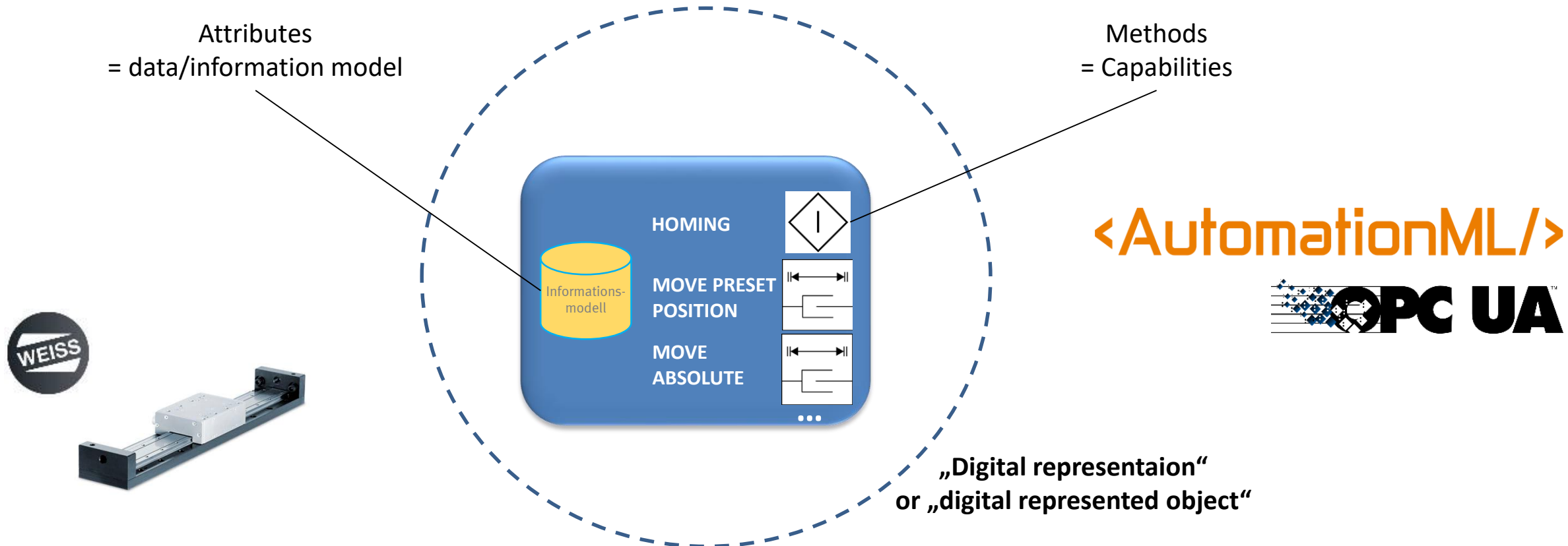
# Machine architecture

## Classical control architecture



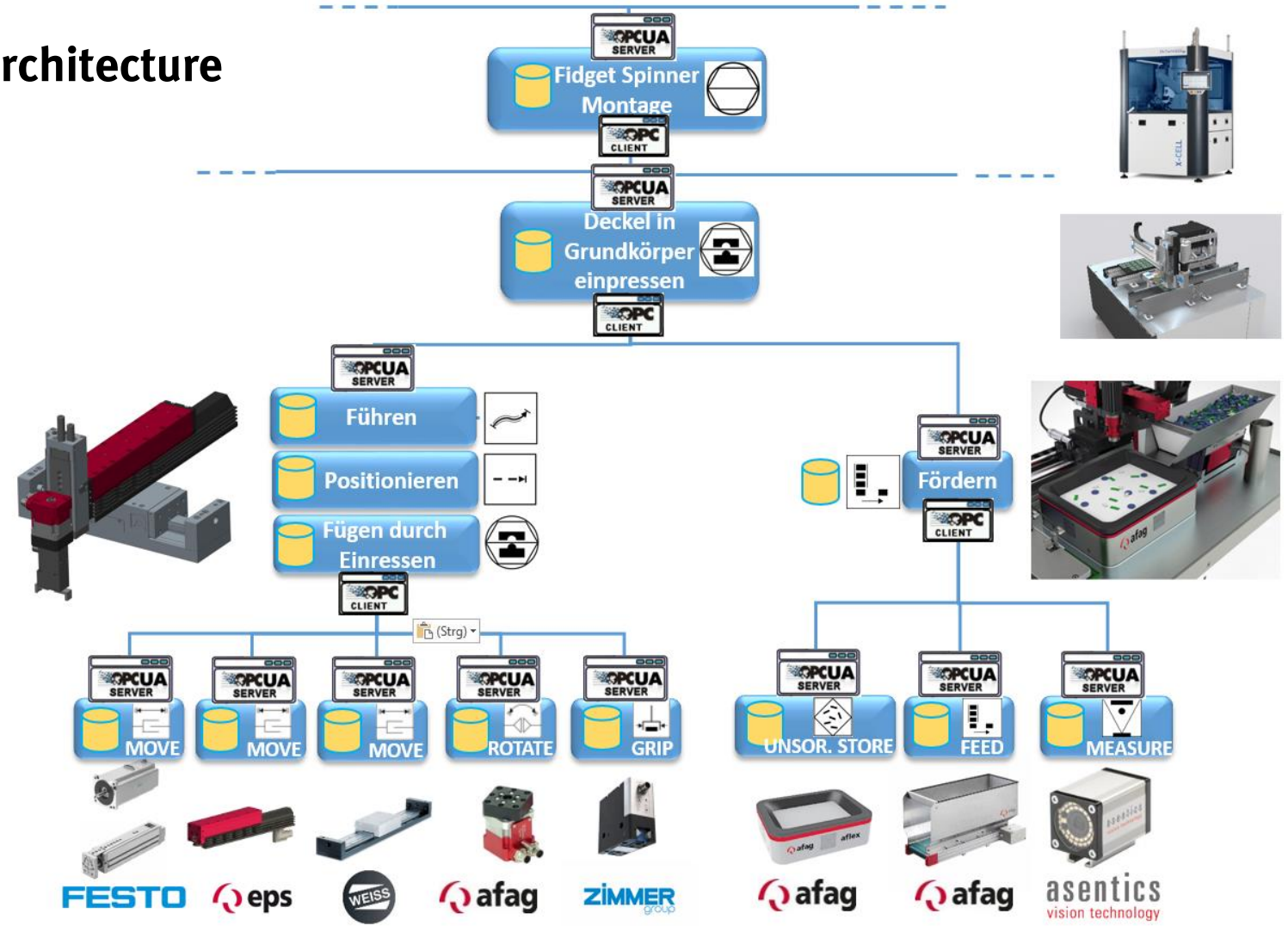
# Object and capability based machine architecture

## Digital representation



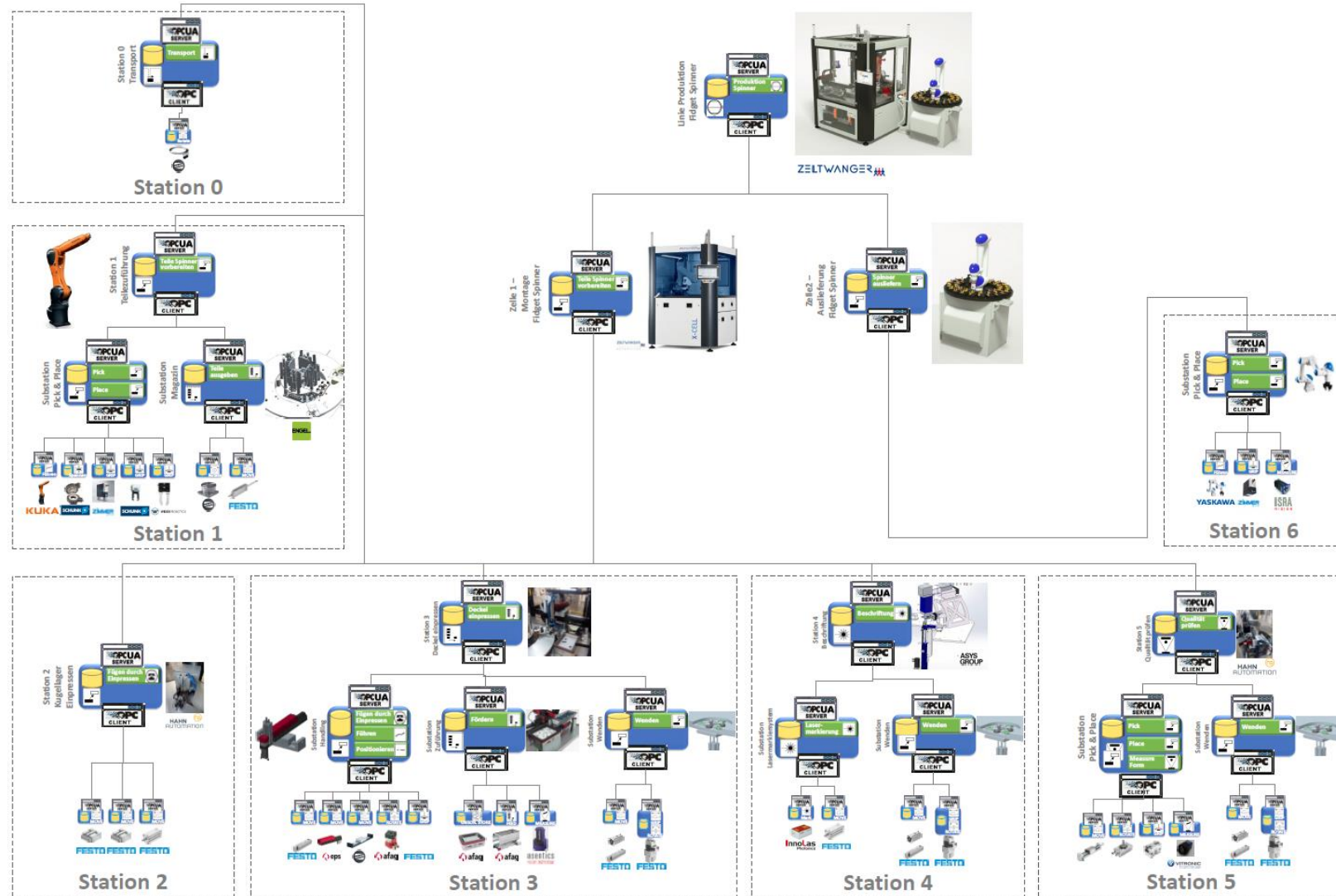
# Object and capability based machine architecture

Digital representation as architectural element



Realised with OPC UA





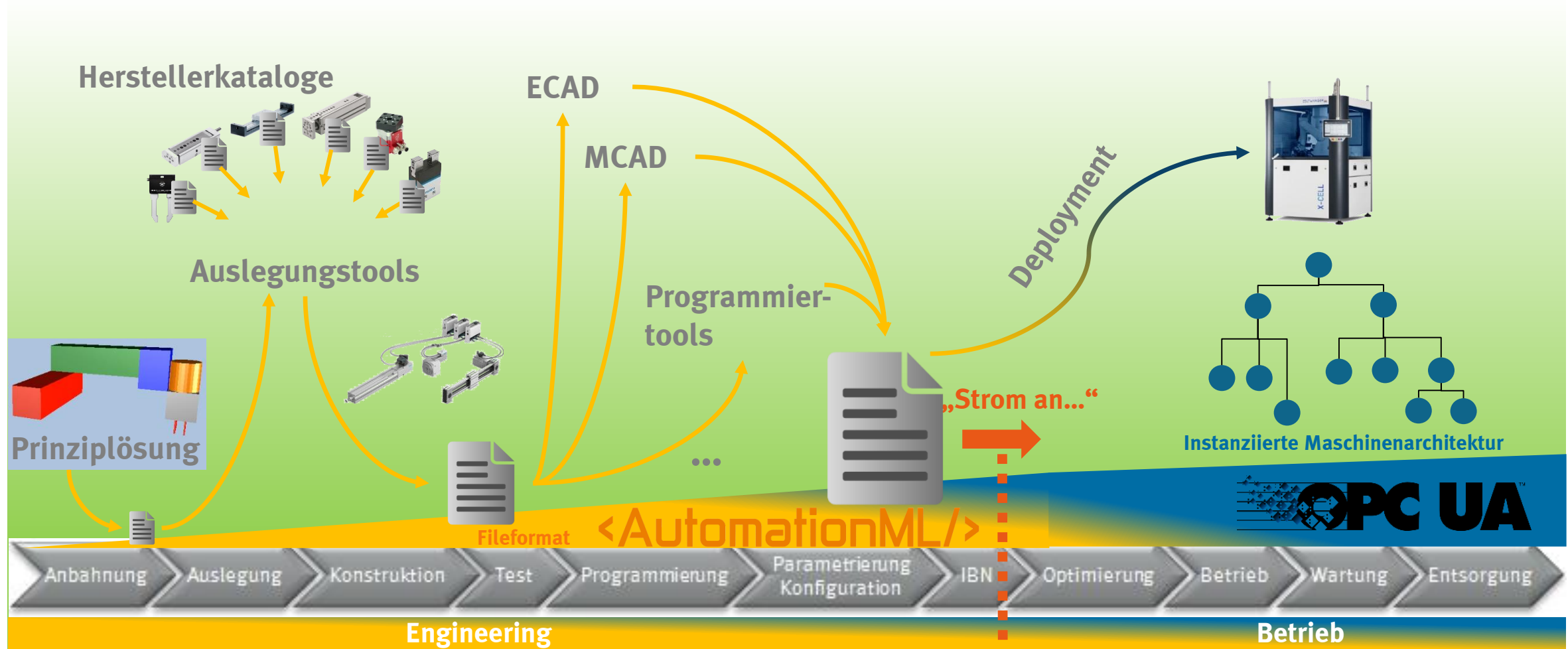
**New machine architectures on the basis of digital  
representations  
→ for engineering and operation**



**<AutomationML/>**



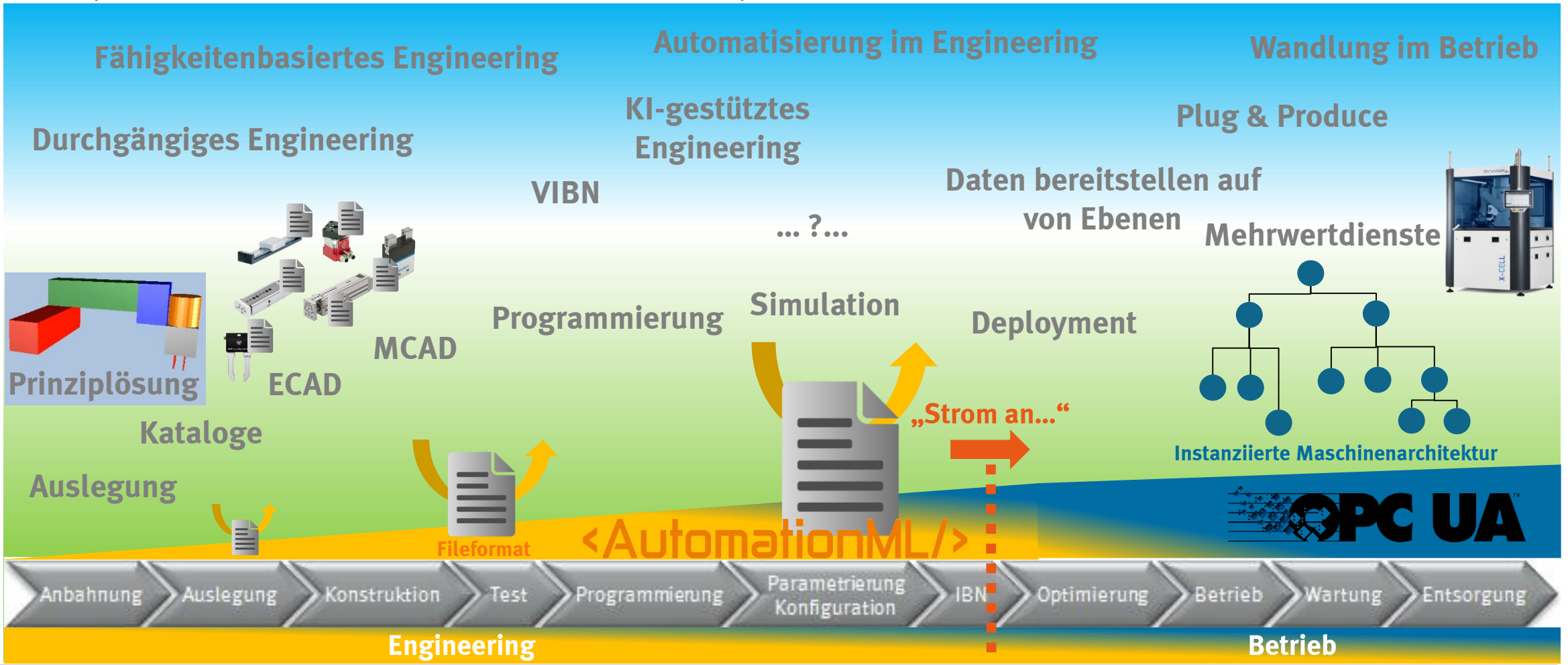
# Digital representation – during Engineering and operation



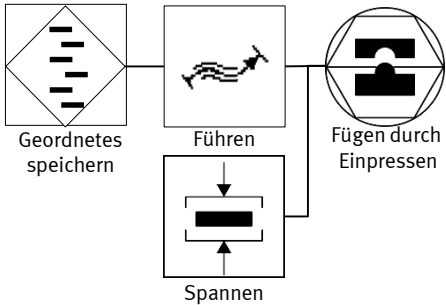


# Digital representation – during Engineering and operation

HEUTE  
ZUKUNFT

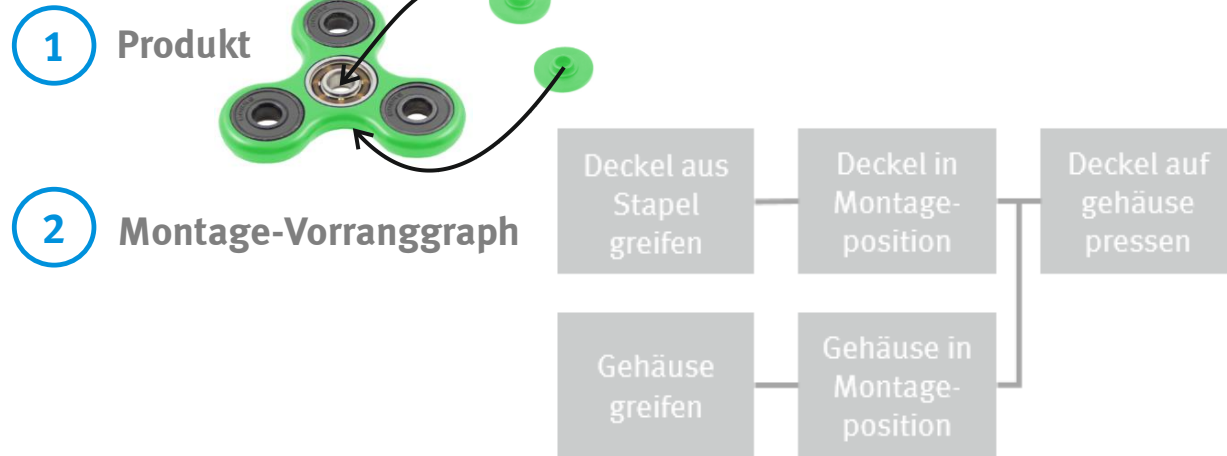


# Capability based engineering

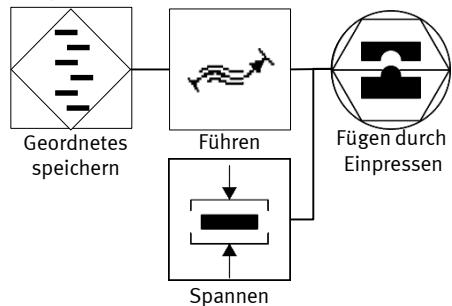


# Capability based engineering

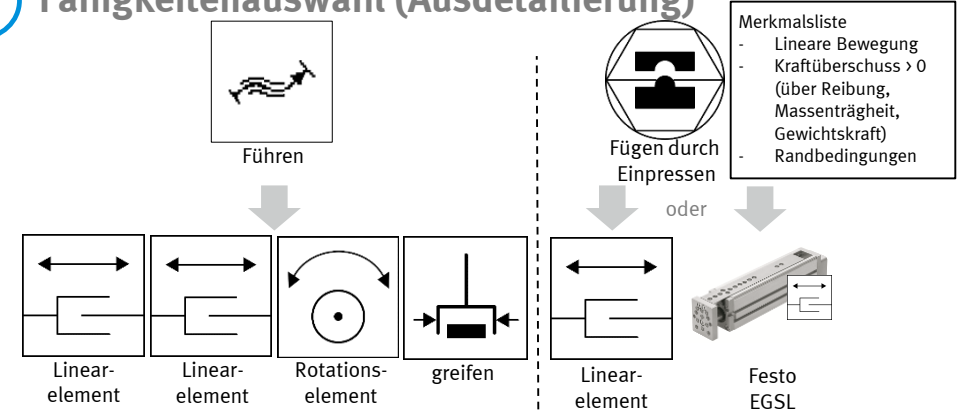
## Capability based engineering



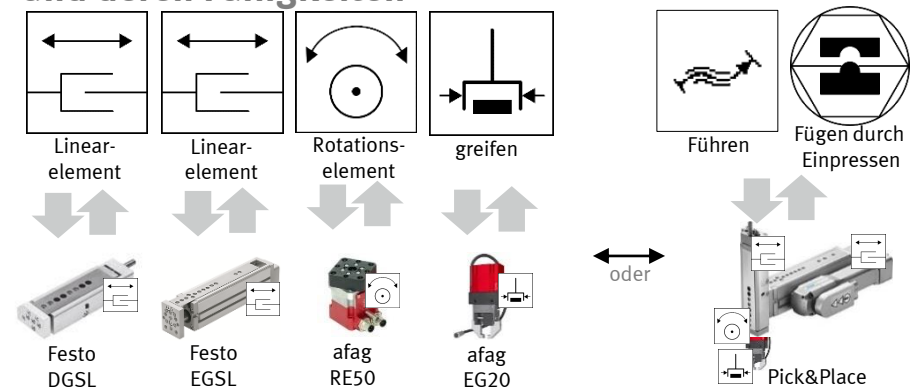
**3 Fähigkeitsauswahl (1. Näherung)**



**4 Fähigkeitsauswahl (Ausdetailierung)**



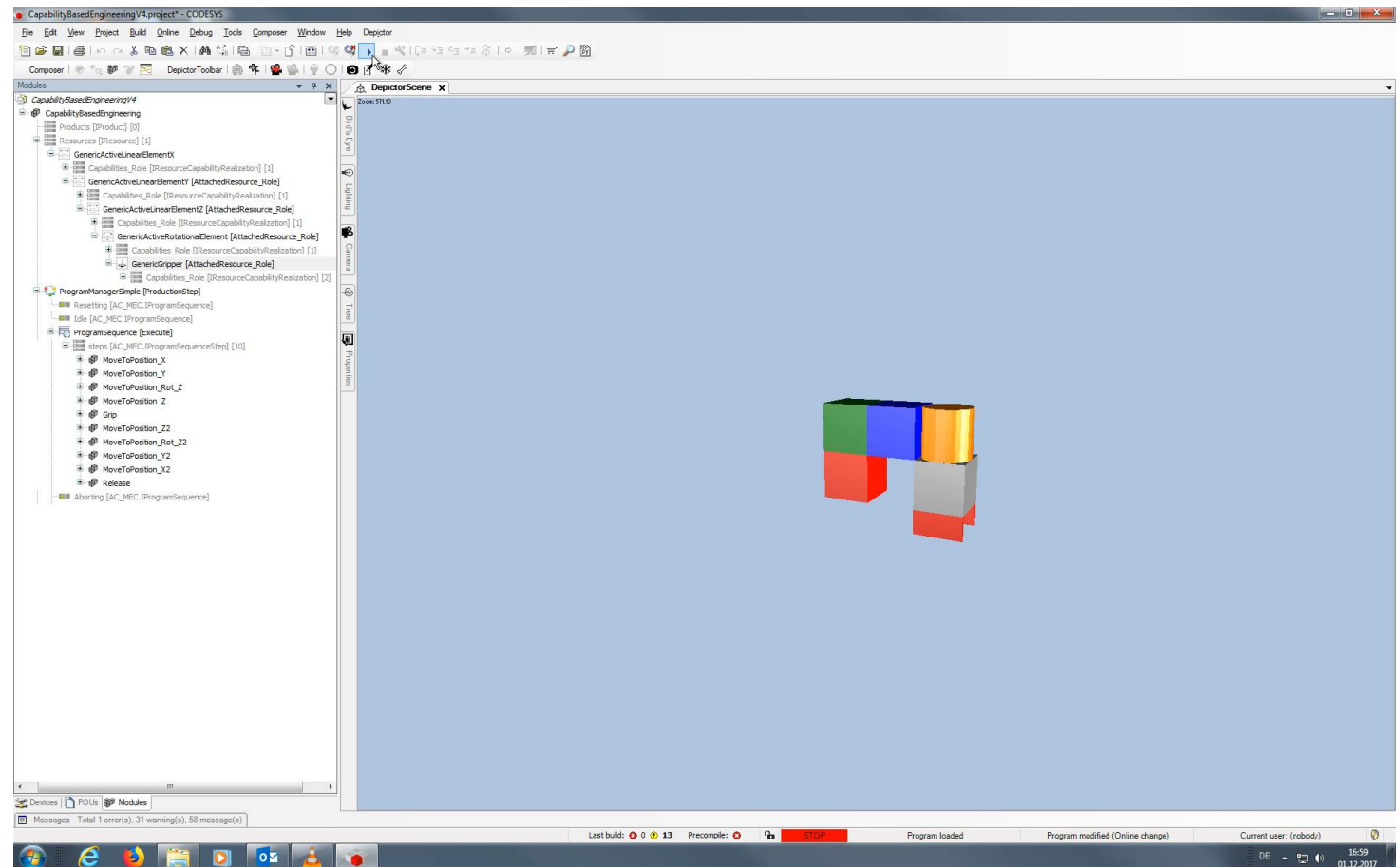
**5 Matching mit konkreten Komponenten und deren Fähigkeiten**



# Capability based engineering

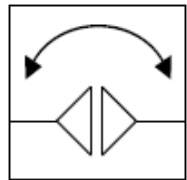
Realised with CODESYS

1. Generic solution
2. Virtual commissioning of generic solution
3. Exchange with real products
4. Virtual commissioning of real commissioning

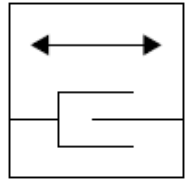


# Capability based engineering

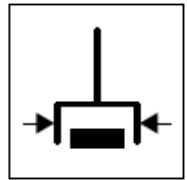
## Manufacturer independent categorisation of mechatronic capabilities



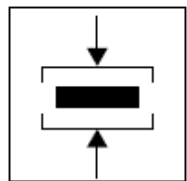
Rotative  
Movement



Linear  
Movement



Gripping



Clamping

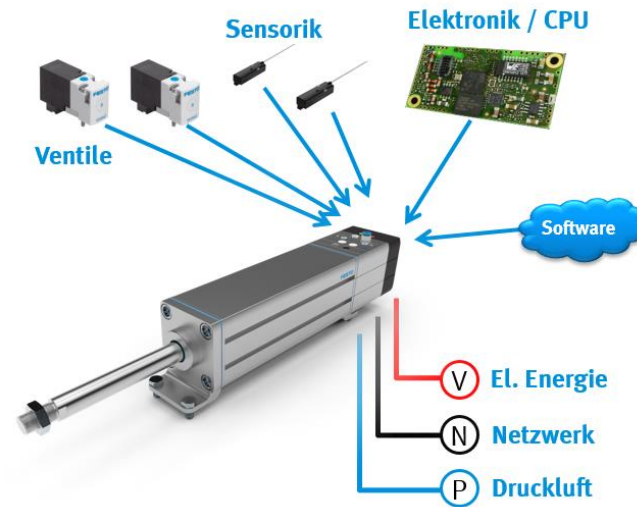
Standardisation

VDI 2860  
Montage und Handhabung

DIN 8580  
Fertigungsverfahren



# Physical digital representation of automation components



# Physical digital representation

## Mechatronic object oriented systems

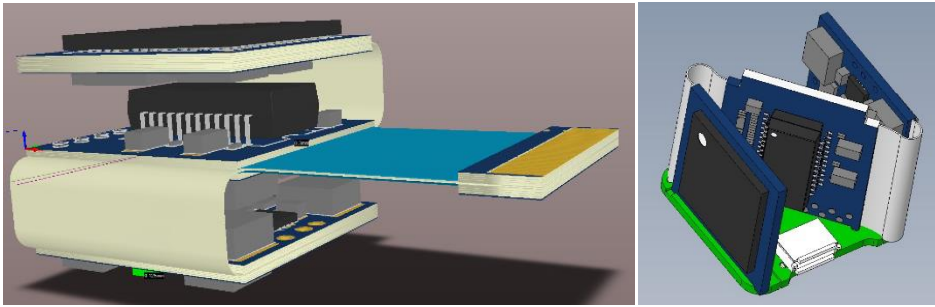


Abb.: EMC2xx gefaltet



U-Form

Stapel

Z-Form

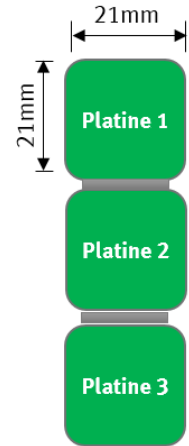
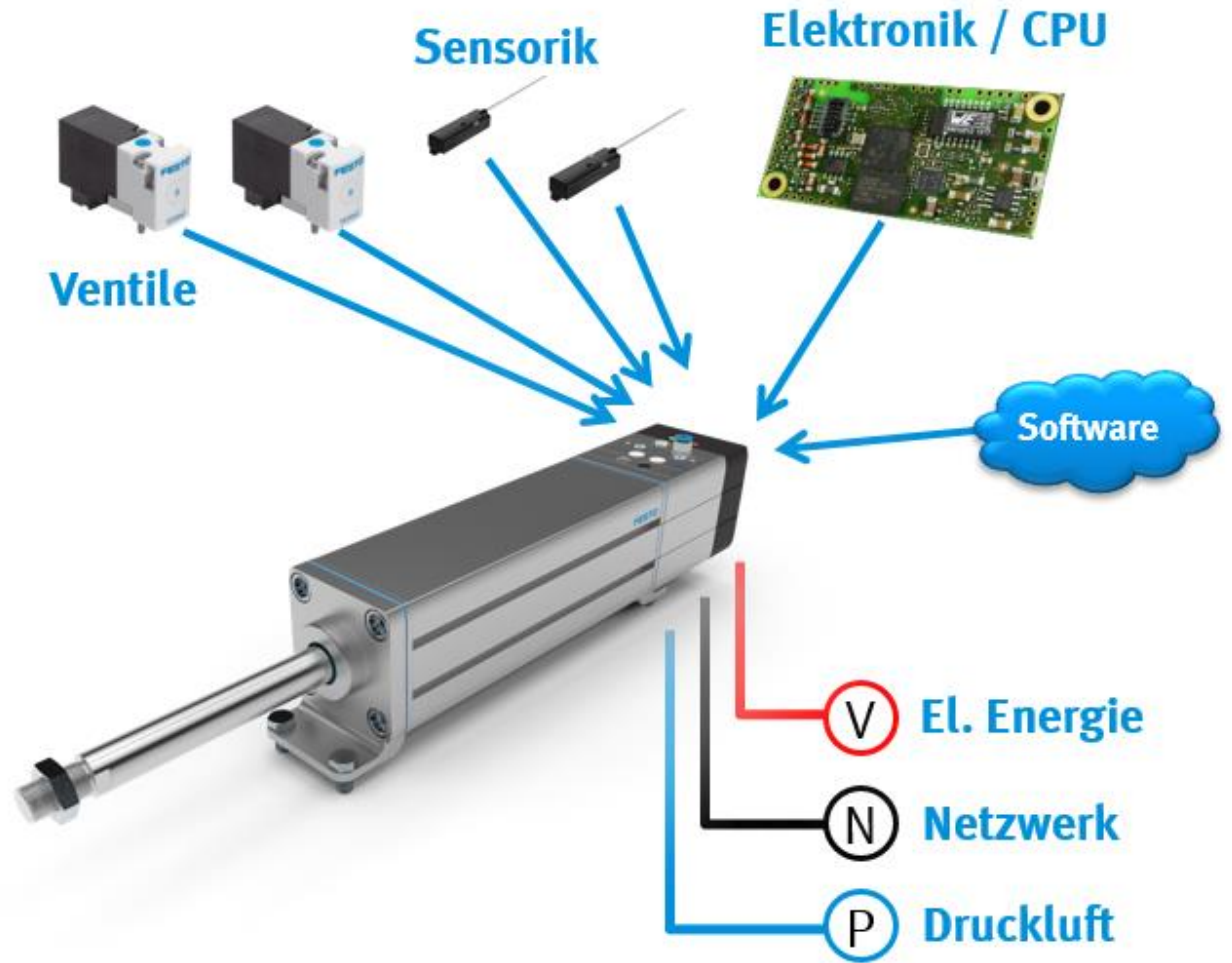


Abb.: Abmessungen

Flach

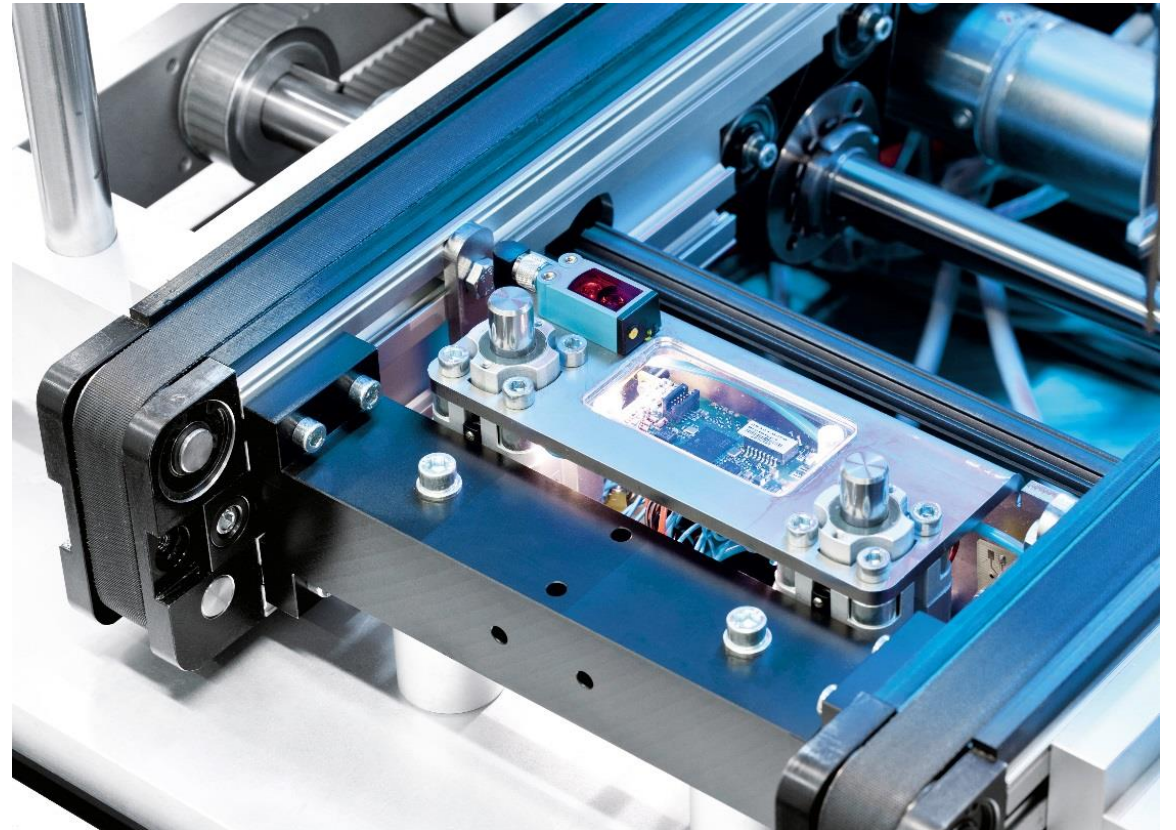
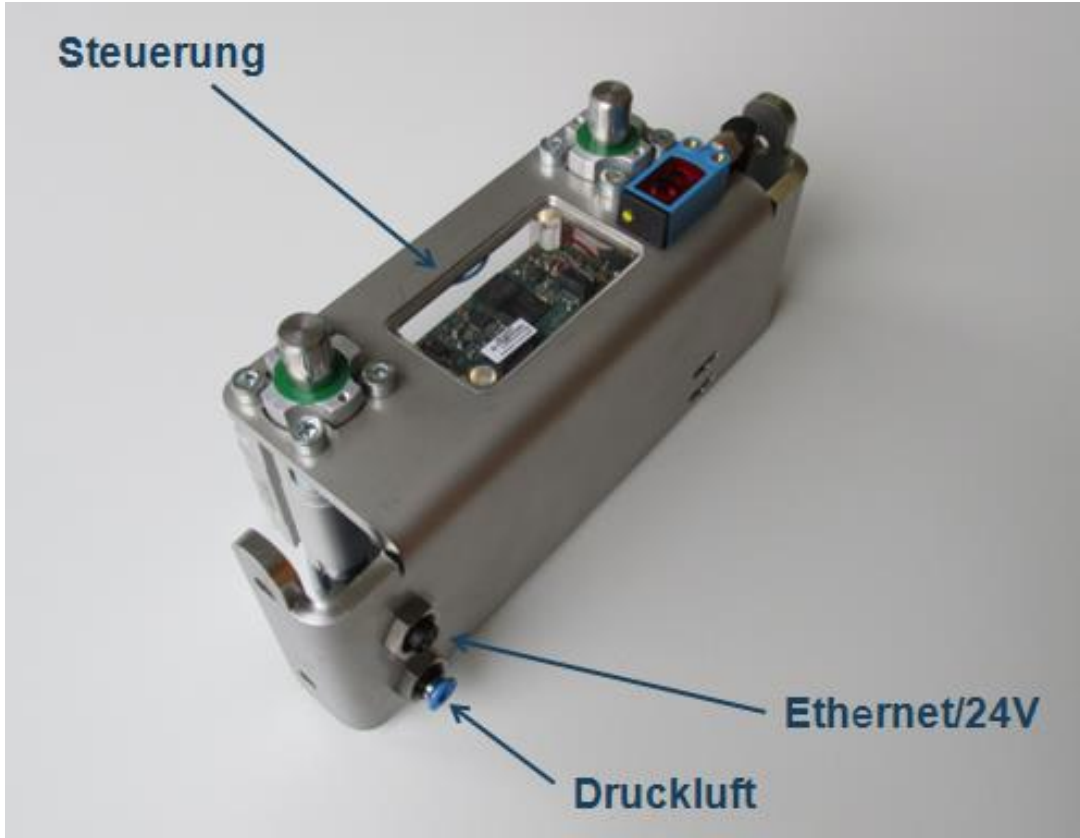
Abb.: Flexibler Einbau durch Faltung



# Physical digital representation

Example logistic module (stopper) machine builder ASYS

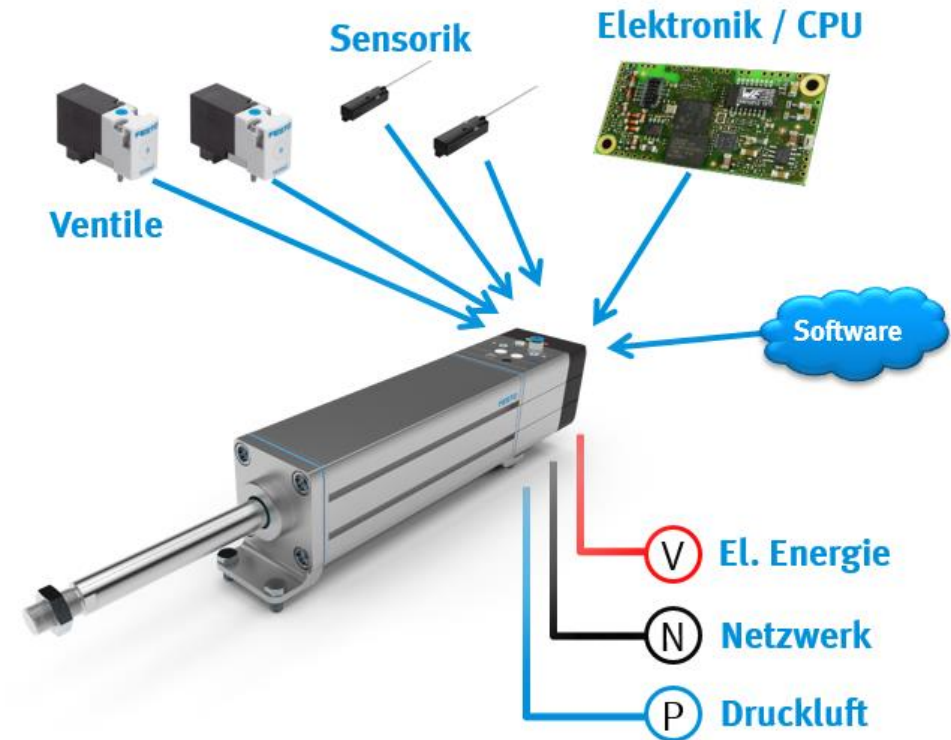
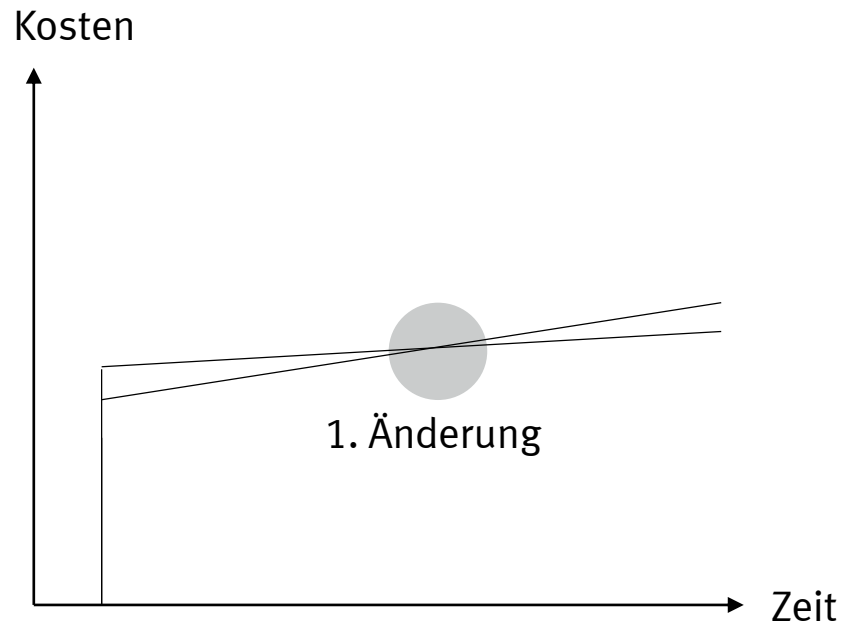
ASYS  
GROUP





# Physical digital representation

## Economical analysis



# VDMA OPC UA Demonstrator



# VDMA OPC UA Demonstrator

Montage Fidget-Spinner



- All devices of all manufacturers described in **AutomationML**
- All devices offer **standardised capabilities**
- **Capability based control software:**
- All **devices present with OPC UA** in the system (data & control)



# VDMA OPC UA Demonstrator

Hersteller

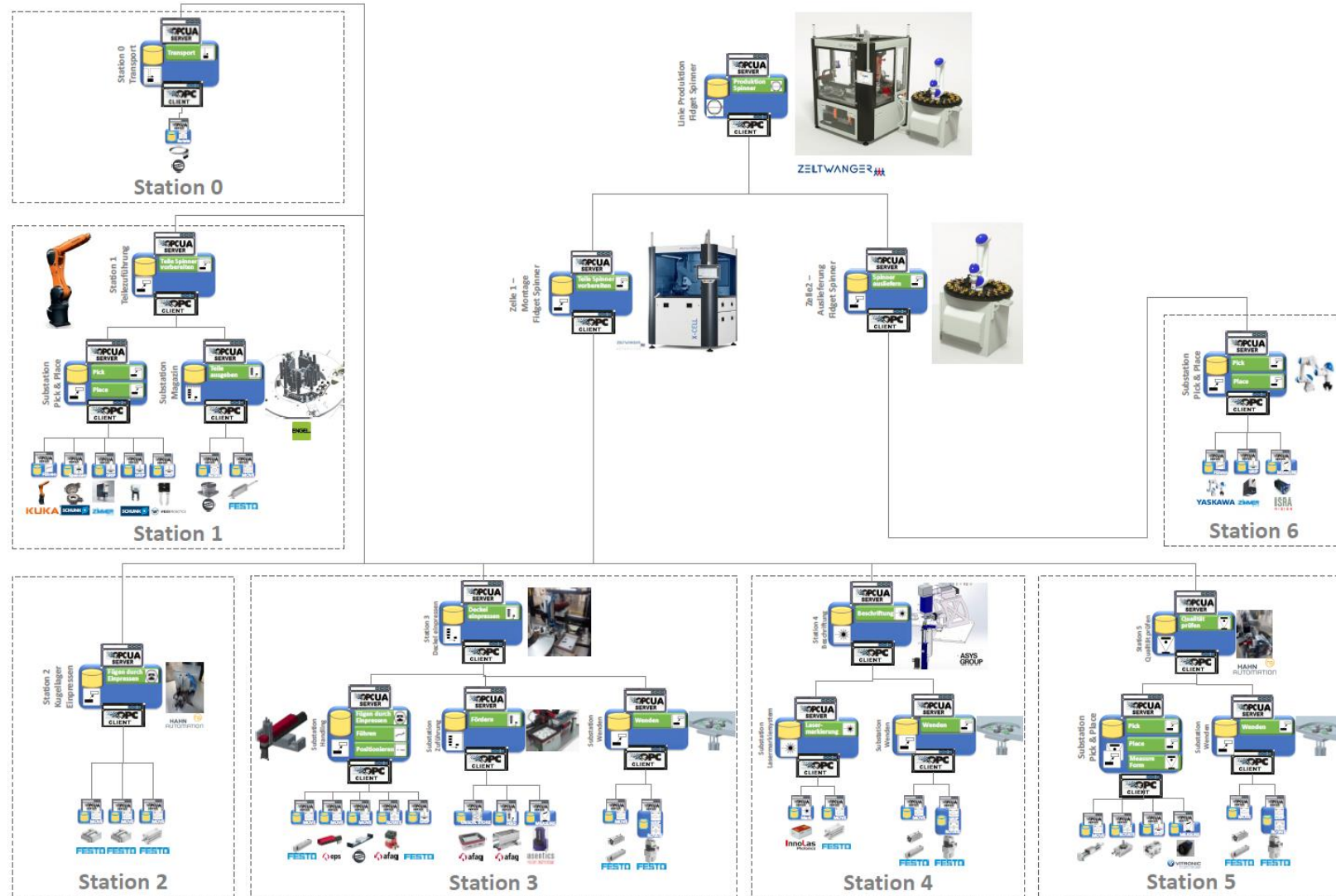


Maschinenbauer

Software/Kommunikation/  
Sicherheit

Steuerungs-  
hersteller





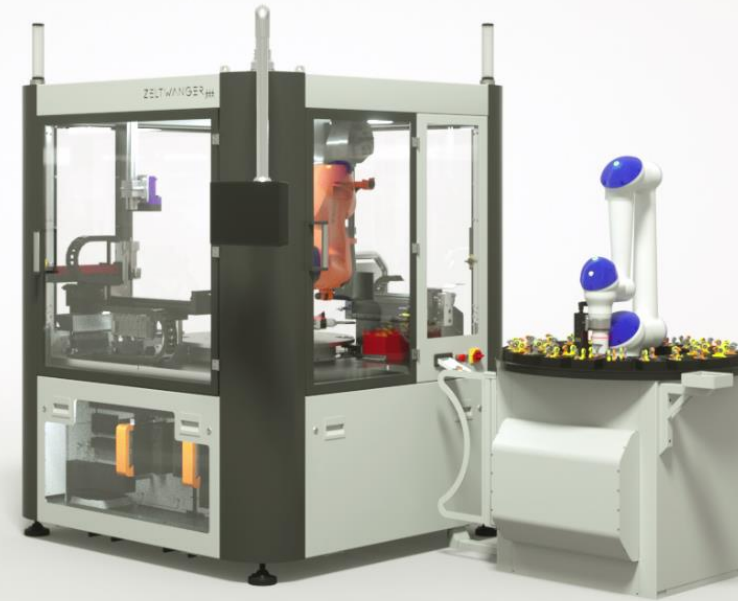
Vielen Dank  
für Ihre  
Aufmerksamkeit!

# OPC UA Demonstrator

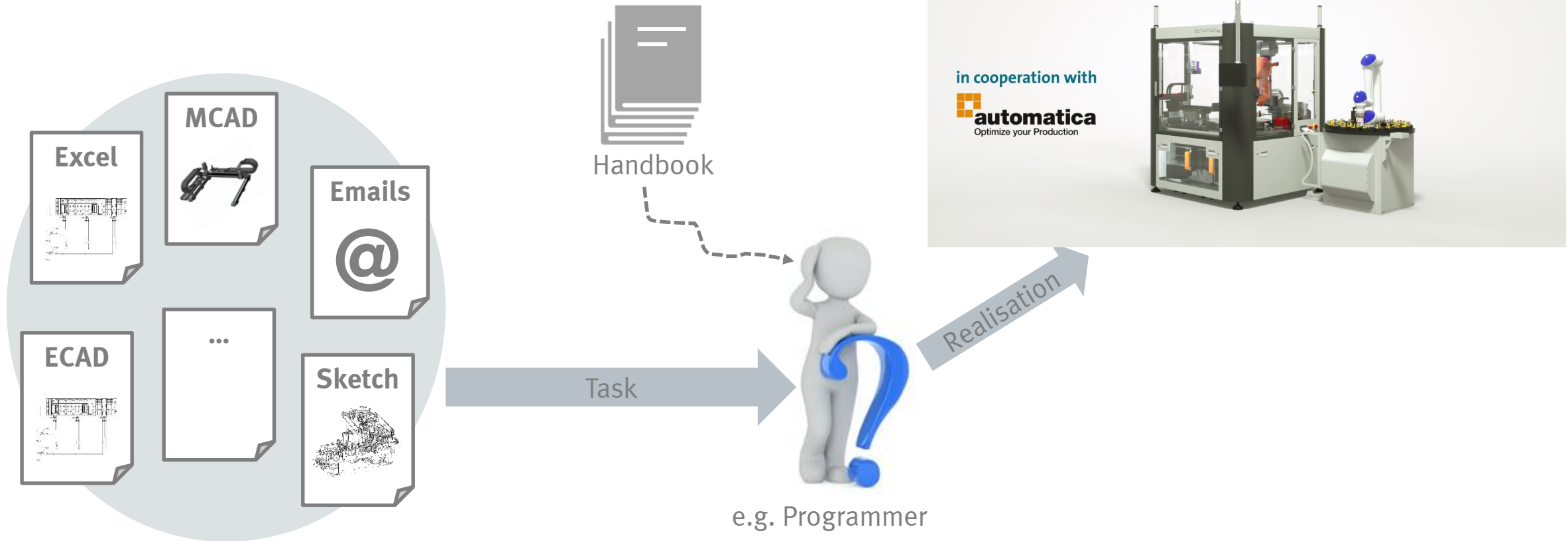


Robotik + Automation

in cooperation with



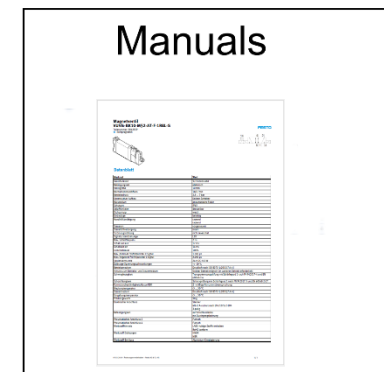
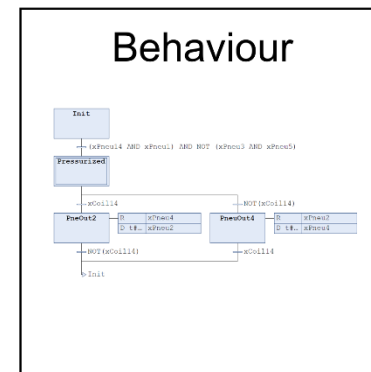
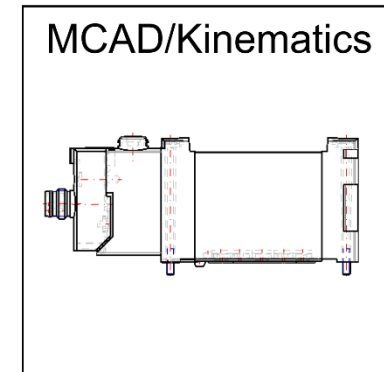
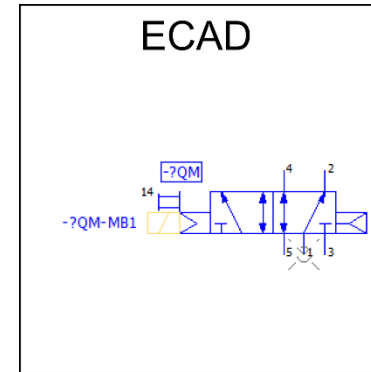
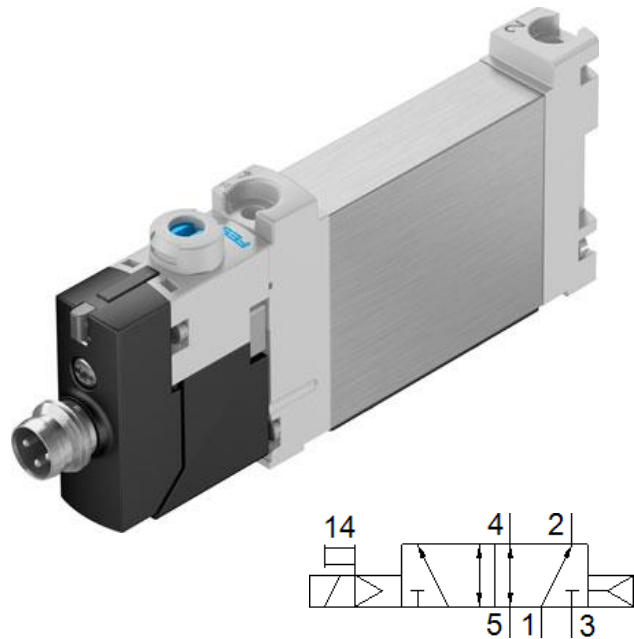
# Pains in Engineering



# Digital Representation for Engineering – state of the art

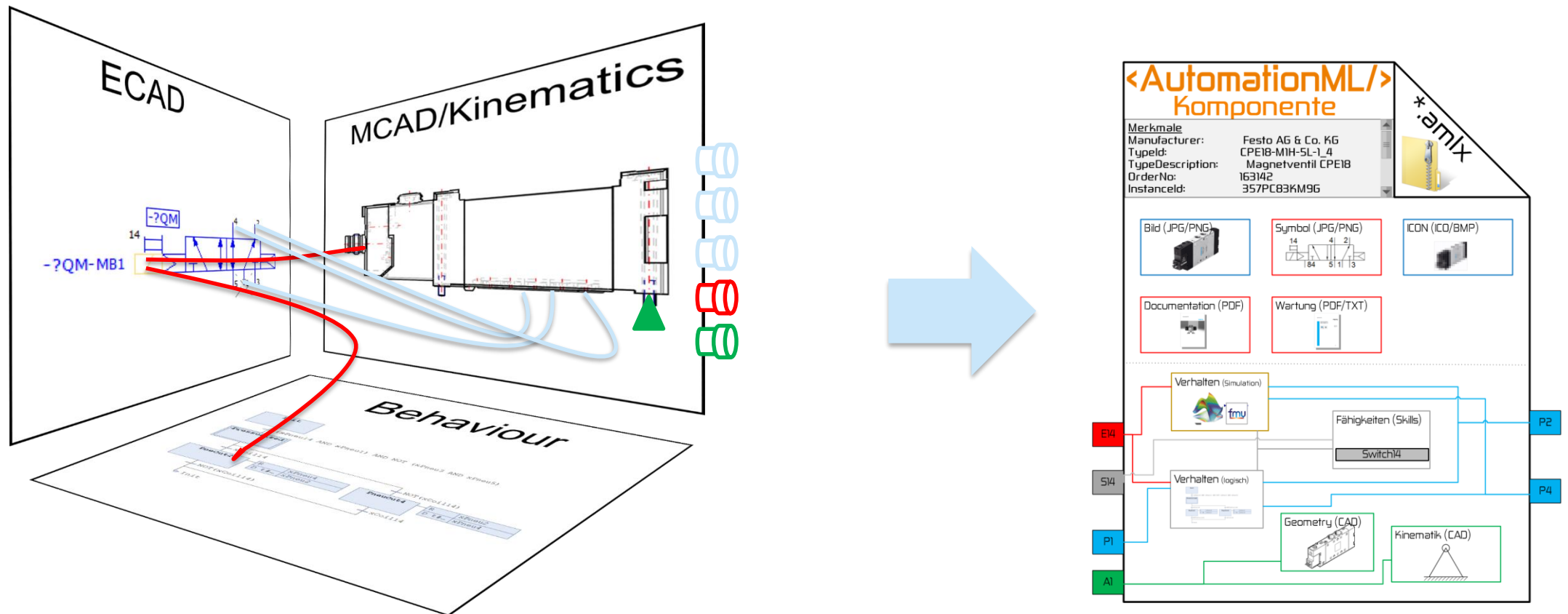
Festo solenoid valve VUVG-BK10-M52-AT-F-1R8L-S

Data (excerpt)

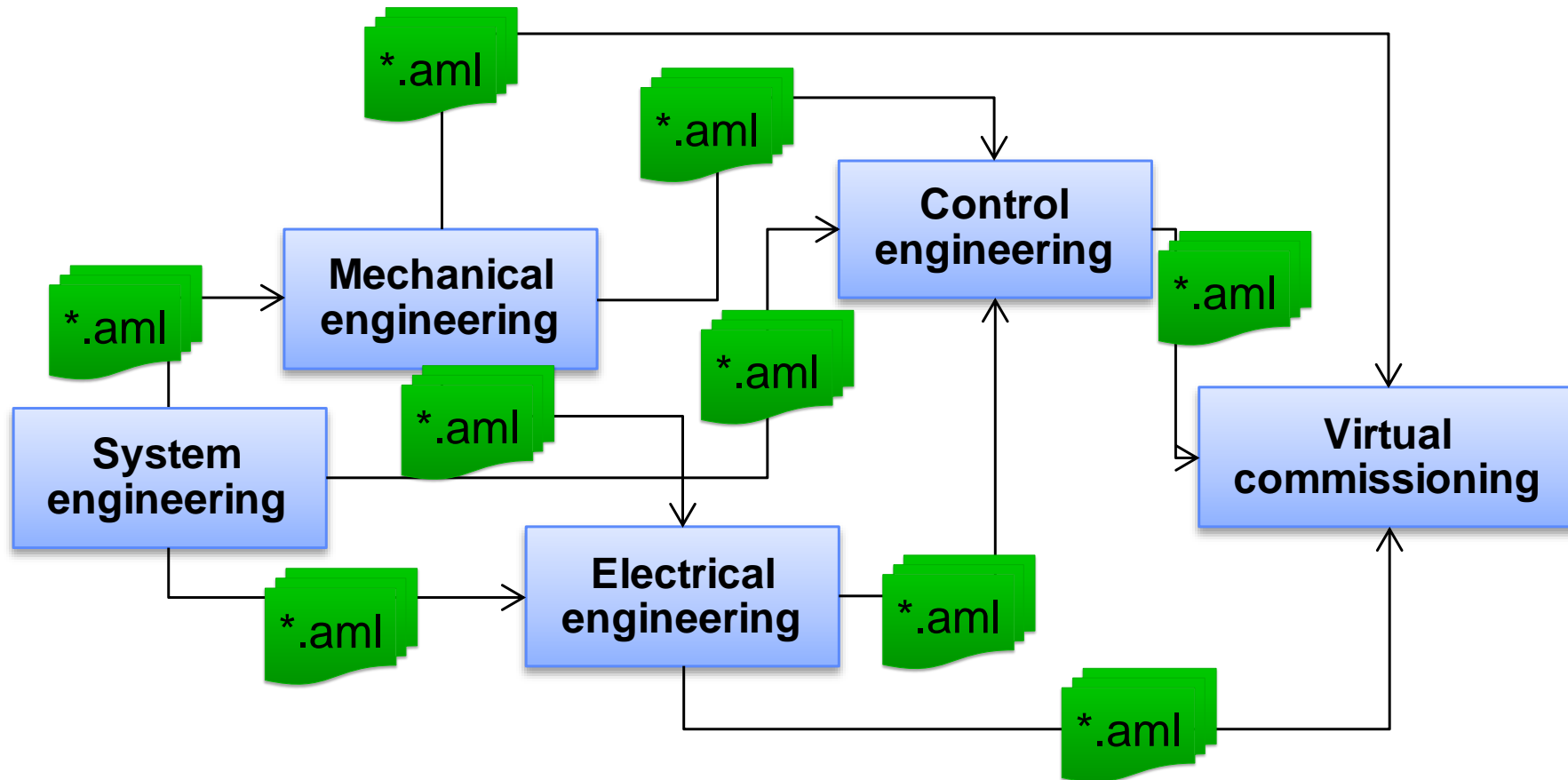




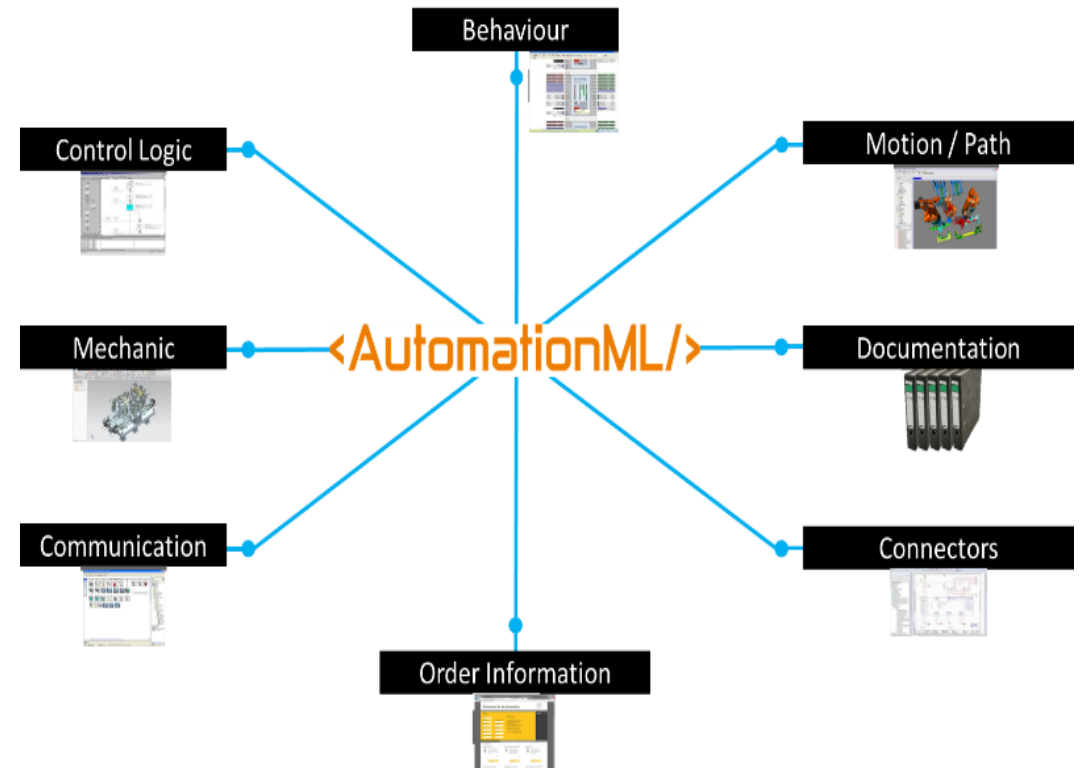
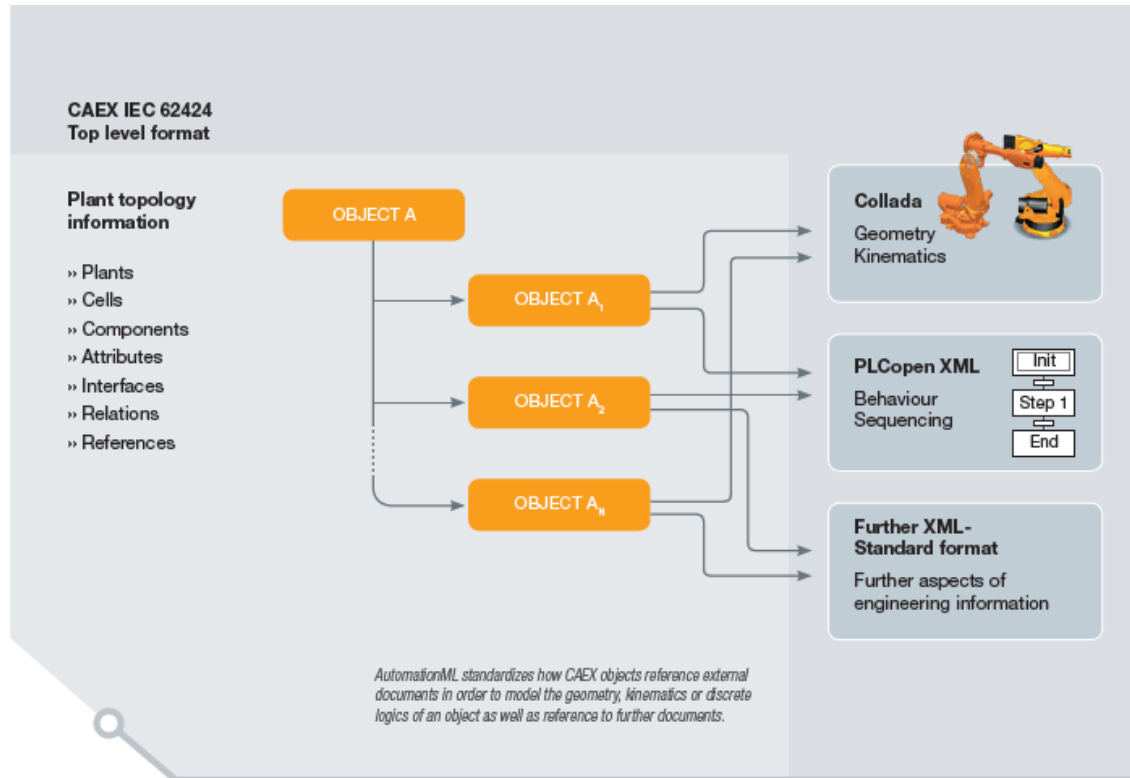
# Digital Representation for Engineering – future?



## Filling Toolchain Gaps with AutomationML



# AutomationML: Architecture und Content



<AutomationML\_e\_V\_Members num=52 />

**DAIMLER** **SIEMENS** **PROMOTER** **BMW GROUP** **VOLKSWAGEN AKTIENGESELLSCHAFT** **KUKA**

**ABB** **Lenze** **MURR ELEKTRONIK** stay connected **AIRBUS** **PHOENIX CONTACT** [SO:IT] SALT SOLUTIONS **SMS group**

**EDAG** PRODUCTION SOLUTIONS **NETALLIED SYSTEMS** **cenit** AmpereSoft **FESTO** Paradigma Software GmbH

**EKS** SAFETY NONSTOP **HIMA** **SICK** Sensor Intelligence. **CONTRIBUTOR** **COMAN SOFTWARE GMBH** **VISUAL COMPONENTS**

**BALLUFF** **OMRON** **MITSUBISHI ELECTRIC** Changes for the Better **ePLAN** **ThyssenKrupp System Engineering** Drusz Nothelfer | Krause | EGM **ThyssenKrupp**

**hilscher** COMPETENCE IN COMMUNICATION **Schneider Electric** **inpro** **tarakos** Virtual made Reality **logi.cals** ICARUS all the more power

**OTTO VON GUERICKE UNIVERSITÄT MAGDEBURG** **Fraunhofer IPA** HS PF **HELMUT SCHMIDT UNIVERSITÄT** **fortiss** **Fraunhofer IOSB** **LPS** LEHRSTUHL FÜR PRODUKTIONSSYSTEME **Lehrstuhl für Automatisierung und Informationssysteme**

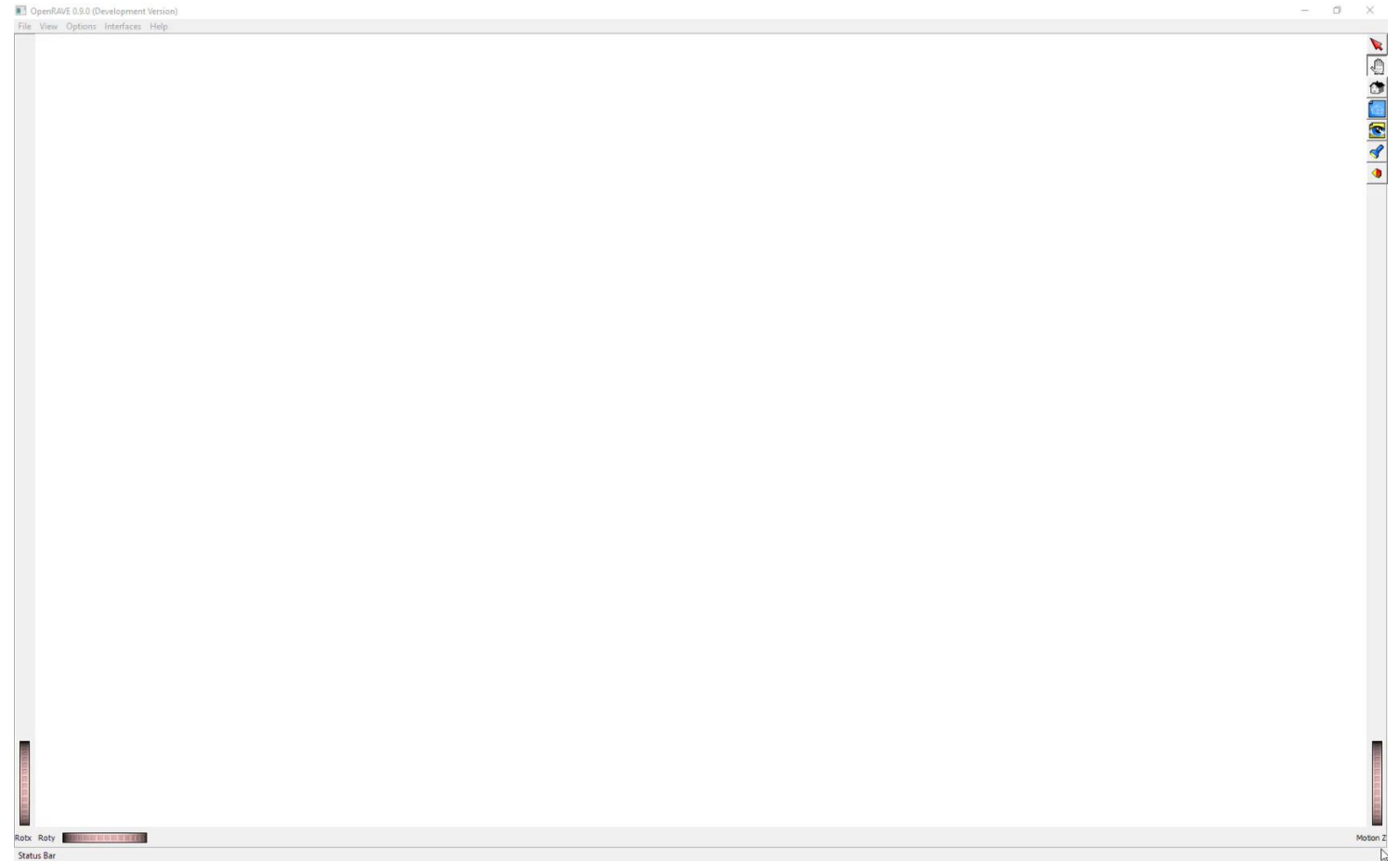
**KE TI** Korea Electronics Technology Institute **TU WIEN** **KIT** Karlsruhe Institute of Technology **Universidad del País Vasco** Euskal Herriko Unibertsitatea The University of the Basque Country **ACADEMIC** **TECHNISCHE HOCHSCHULE NÜRNBERG** GEORG SIMON OHM **SBA Research** **ifak** **iii** **RWTH** **FZI** **KAIST** KOREAN ADVANCED INSTITUTE OF SCIENCE AND TECHNOLOGY

# AutomationML Example of Use: Geometry und Kinematics



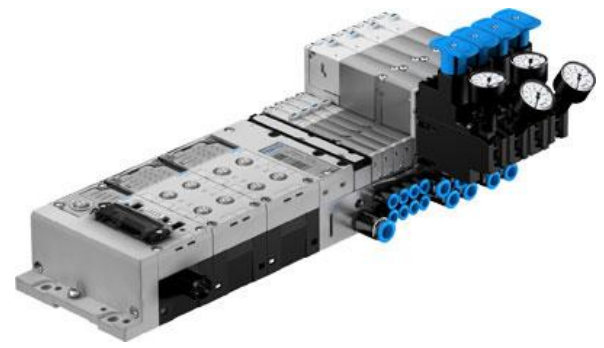
<AutomationML/>

COLLADA™

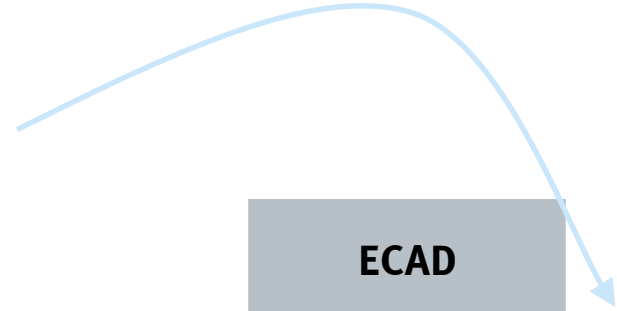


# AutomationML Example of Use: Correctly Configured and Open Engineering Data

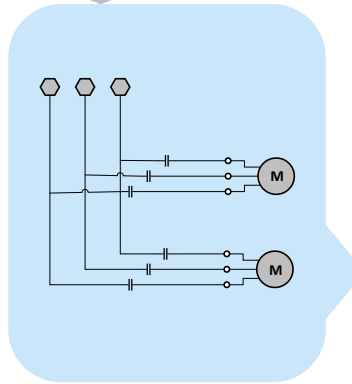
Exchange of PLC configuration between ECAD and PLC-Tool



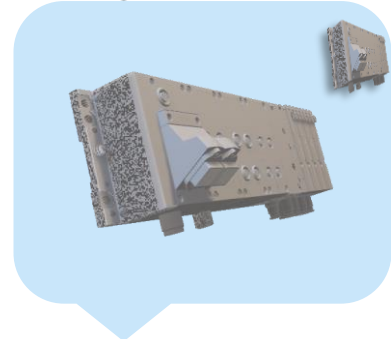
correctly configured!



ECAD



MCAD

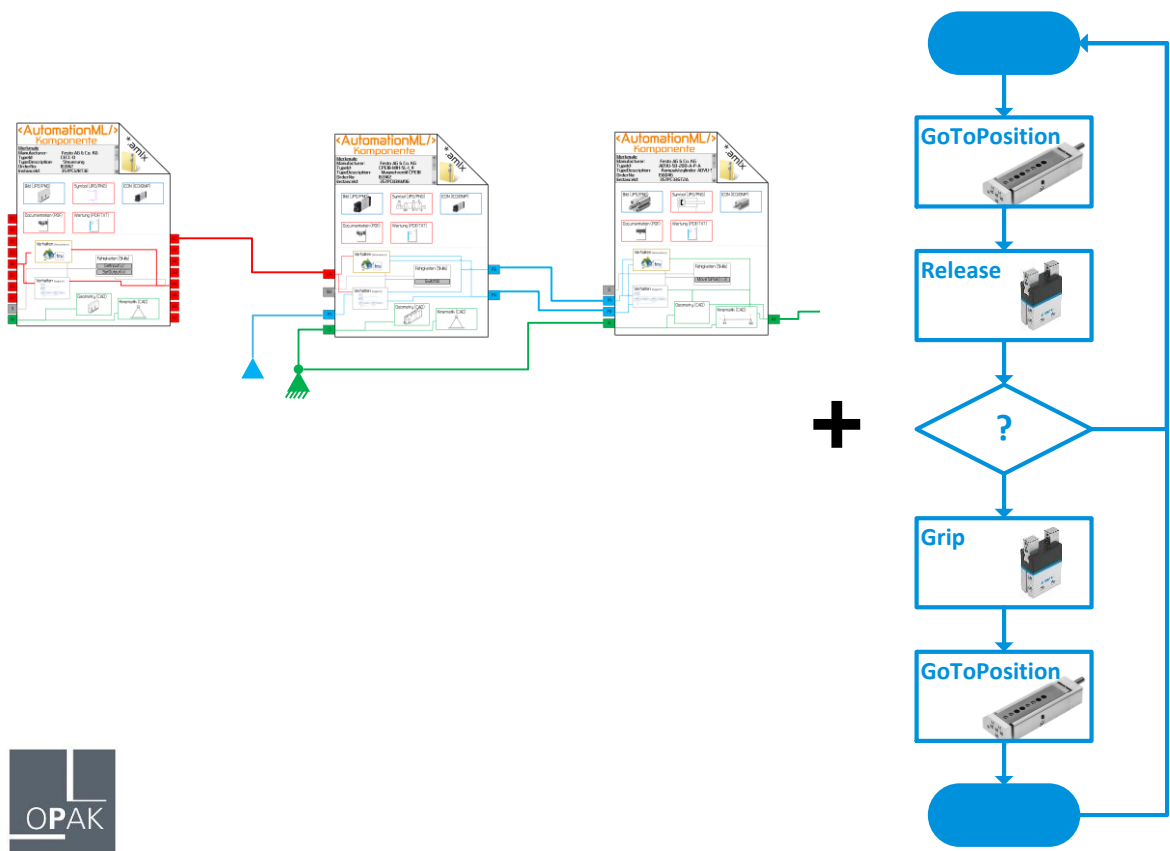


PLC-Tool

<AutomationML/>

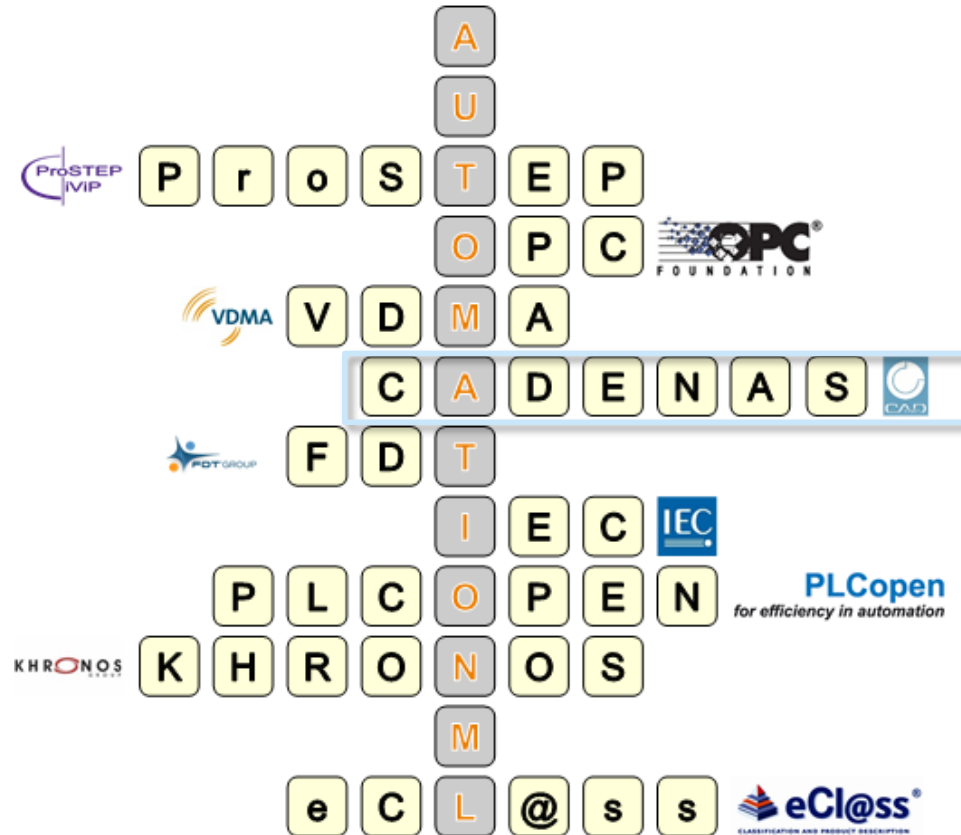
```
FUNCTION_BLOCK BehavPLC
VAR_INPUT
END_VAR
VAR_OUTPUT
END_VAR
VAR
  xPneu1 : BOOL := FALSE;
  xPneu2 : BOOL := FALSE;
END_VAR
```

# AutomationML Example of Use: Synthesis of PLC Code



The screenshot shows the CODESYS development environment. The 'Sequence Editor' displays a sequence of steps: GoToRecordPosition, WaitTime\_2, CloseGripper, WaitTime\_1, GoToRecordPosition\_1, WaitTime, GoToRecordPosition, WaitTime, GoToRecordPosition, WaitTime, GoToRecordPosition, WaitTime. The 'Depictor' shows a 3D model of a gripper.

# AutomationML e.V. cooperates with CADENAS





# Thank You!

