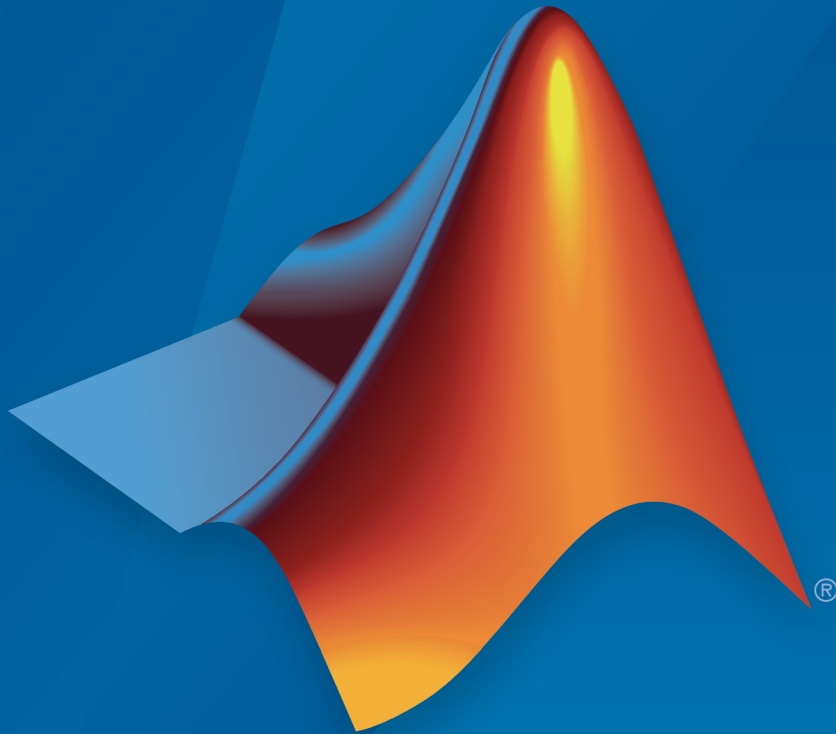


Simulink[®] PLC Coder[™]

User's Guide



MATLAB[®]&SIMULINK[®]

R2016a



How to Contact MathWorks



Latest news: www.mathworks.com
Sales and services: www.mathworks.com/sales_and_services
User community: www.mathworks.com/matlabcentral
Technical support: www.mathworks.com/support/contact_us



Phone: 508-647-7000



The MathWorks, Inc.
3 Apple Hill Drive
Natick, MA 01760-2098

Simulink[®] PLC Coder[™] User's Guide

© COPYRIGHT 2010–2016 by The MathWorks, Inc.

The software described in this document is furnished under a license agreement. The software may be used or copied only under the terms of the license agreement. No part of this manual may be photocopied or reproduced in any form without prior written consent from The MathWorks, Inc.

FEDERAL ACQUISITION: This provision applies to all acquisitions of the Program and Documentation by, for, or through the federal government of the United States. By accepting delivery of the Program or Documentation, the government hereby agrees that this software or documentation qualifies as commercial computer software or commercial computer software documentation as such terms are used or defined in FAR 12.212, DFARS Part 227.72, and DFARS 252.227-7014. Accordingly, the terms and conditions of this Agreement and only those rights specified in this Agreement, shall pertain to and govern the use, modification, reproduction, release, performance, display, and disclosure of the Program and Documentation by the federal government (or other entity acquiring for or through the federal government) and shall supersede any conflicting contractual terms or conditions. If this License fails to meet the government's needs or is inconsistent in any respect with federal procurement law, the government agrees to return the Program and Documentation, unused, to The MathWorks, Inc.

Trademarks

MATLAB and Simulink are registered trademarks of The MathWorks, Inc. See www.mathworks.com/trademarks for a list of additional trademarks. Other product or brand names may be trademarks or registered trademarks of their respective holders.

Patents

MathWorks products are protected by one or more U.S. patents. Please see www.mathworks.com/patents for more information.

Revision History

March 2010	Online only	New for Version 1.0 (Release 2010a)
September 2010	Online only	Revised for Version 1.1 (Release 2010b)
April 2011	Online only	Revised for Version 1.2 (Release 2011a)
September 2011	Online only	Revised for Version 1.2.1 (Release 2011b)
March 2012	Online only	Revised for Version 1.3 (Release 2012a)
September 2012	Online only	Revised for Version 1.4 (Release 2012b)
March 2013	Online only	Revised for Version 1.5 (Release 2013a)
September 2013	Online only	Revised for Version 1.6 (Release 2013b)
March 2014	Online only	Revised for Version 1.7 (Release 2014a)
October 2014	Online only	Revised for Version 1.8 (Release 2014b)
March 2015	Online only	Revised for Version 1.9 (Release 2015a)
September 2015	Online only	Revised for Version 2.0 (Release 2015b)
March 2016	Online only	Revised for Version 2.1 (Release 2016a)

Simulink PLC Coder Product Description	1-2
Key Features	1-2
PLC Code Generation in the Development Process	1-3
Expected Users	1-3
Glossary	1-4
System Requirements	1-4
Supported IDE Platforms	1-5
PLC Code Generation Workflow	1-6
Prepare Model for Structured Text Generation	1-7
Tasking Mode	1-7
Solvers	1-7
Configuring Simulink Models for Structured Text Code Generation	1-7
Checking System Compatibility for Structured Text Code Generation	1-11
Generate and Examine Structured Text Code	1-14
Generate Structured Text from the Model Window	1-14
Generate Structured Text with the MATLAB Interface	1-16
View Generated Code	1-17
Propagate Block Descriptions to Code Comments	1-19
Files Generated with Simulink PLC Coder	1-20
Specify Custom Names for Generated Files	1-23

Import Structured Text Code Automatically	1-24
PLC IDEs That Qualify for Importing Code Automatically .	1-24
Generate and Automatically Import Structured Text Code .	1-24
Troubleshoot Automatic Import Issues	1-25
Simulation and Code Generation of Motion Instructions . .	1-28
Workflow for Using Motion Instructions in Model	1-28
Library of Motion Instructions	1-30
Data Types for Motion Instructions	1-31
Limitations for MAM Instruction	1-31

2 | **Mapping Simulink Semantics to Structured Text**

Generated Code Structure for Simple Simulink Subsystems	2-2
Generated Code Structure for Reusable Subsystems	2-4
Generated Code Structure for Triggered Subsystems	2-6
Generated Code Structure for Stateflow Charts	2-8
Stateflow Chart with Event Based Transitions	2-8
Stateflow Chart with Absolute Time Temporal Logic	2-10
Generated Code Structure for MATLAB Function Block . .	2-13
Generated Code Structure for Multirate Models	2-15
Generated Code Structure for Subsystem Mask Parameters	2-17
Global Tunable Parameter Initialization for PC WORX . . .	2-22

Generating Test Bench Code

3

How Test Bench Verification Works	3-2
Integrate Generated Code into Custom Code	3-3
Import and Verify Structured Text Code	3-4
Generate, Import, and Verify Structured Text	3-4
Import and Verify Structured Text to KW-Software MULTIPROG 5.0 and Phoenix Contact PC WORX 6.0 IDEs	3-5
Verify Generated Code with Multiple Test Benches	3-7
Troubleshooting: Test Data Exceeds Target Data Size	3-9

Code Generation Reports

4

Information in Code Generation Reports	4-2
Create and Use Code Generation Reports	4-4
Generate a Traceability Report from Configuration Parameters	4-4
Keep the Report Current	4-6
Trace from Code to Model	4-7
Trace from Model to Code	4-8
Model Web View in Code Generation Report	4-10
Generate a Static Code Metrics Report	4-13
Generate a Traceability Report from the Command Line ...	4-14
View Requirements Links from Generated Code	4-16
Working with the Static Code Metrics Report	4-17
Workflow for Static Code Metrics Report	4-17
Report Contents	4-18
Function Block Information	4-19

Working with Tunable Parameters in the Simulink PLC Coder Environment

5

Block Parameters in Generated Code	5-2
Control Appearance of Block Parameters in Generated Code	5-5
Configure Tunable Parameters with <code>Simulink.Parameter</code> Objects	5-5
Make Parameters Tunable Using Configuration Parameters Dialog Box	5-8

Controlling Generated Code Partitions

6

Generate Global Variables	6-2
Control Code Partitions for Subsystem Block	6-3
Control Code Partitions Using Subsystem Block Parameters .	6-3
One Function Block for Atomic Subsystems	6-5
One Function Block for Virtual Subsystems	6-6
Multiple Function Blocks for Nonvirtual Subsystems	6-7
Control Code Partitions for MATLAB Functions in Stateflow Charts	6-9

Integrating Externally Defined Symbols

7

Integrate Externally Defined Symbols	7-2
Integrate Custom Function Block in Generated Code	7-3

Integrate Generated Code with Existing Projects in Siemens IDEs	8-2
Integrate Generated Code with Siemens SIMATIC STEP 7 Projects	8-2
Integrate Generated Code with Siemens TIA Portal Projects ..	8-2
Use Internal Signals for Debugging in RSLogix 5000 IDE ..	8-4
Rockwell Automation RSLogix Considerations	8-6
Add-On Instruction and Function Blocks	8-6
Double-Precision Data Types	8-6
Unsigned Integer Data Types	8-6
Unsigned Fixed-Point Data Types	8-6
Enumerated Data Types	8-7
Considerations for Siemens IDEs	8-8
Double-Precision Floating-Point Data Types	8-8
int8 and Unsigned Integer Types	8-8
Unsigned Fixed-Point Data Types	8-8
Enumerated Data Types	8-9

Supported Simulink and Stateflow Blocks

Supported Blocks	9-2
View Supported Blocks Library	9-2
Supported Simulink Blocks	9-3
Supported Stateflow Blocks	9-11
Blocks With Restricted Support	9-12

10

Coder Limitations	10-2
Current Limitations	10-2
Fixed-Point Data Type Limitations	10-2
Multirate Model Limitations	10-4
Permanent Limitations	10-5

Functions — Alphabetical List

11

Configuration Parameters for Simulink PLC Coder Models

12

PLC Coder: General	12-2
PLC Coder: General Tab Overview	12-3
Target IDE	12-4
Show full target list	12-7
Target IDE Path	12-9
Code Output Directory	12-11
Generate testbench for subsystem	12-12
PLC Coder: Comments	12-13
Comments Overview	12-14
Include comments	12-14
Include block description	12-15
Simulink block / Stateflow object comments	12-16
Show eliminated blocks	12-17
PLC Coder: Optimization	12-18
Optimization Overview	12-18
Signal storage reuse	12-19
Remove code from floating-point to integer conversions that wraps out-of-range values	12-21

Loop unrolling threshold	12-22
PLC Coder: Symbols	12-23
Symbols Overview	12-24
Maximum identifier length	12-25
Use the same reserved names as Simulation Target	12-26
Reserved names	12-27
Externally Defined Symbols	12-28
Preserve Alias Type Names for Data Types	12-28
PLC Coder: Report	12-31
Report Overview	12-31
Generate traceability report	12-31
Generate model Web view	12-33

Getting Started

- “Simulink PLC Coder Product Description” on page 1-2
- “PLC Code Generation in the Development Process” on page 1-3
- “Supported IDE Platforms” on page 1-5
- “PLC Code Generation Workflow” on page 1-6
- “Prepare Model for Structured Text Generation” on page 1-7
- “Generate and Examine Structured Text Code” on page 1-14
- “Propagate Block Descriptions to Code Comments” on page 1-19
- “Files Generated with Simulink PLC Coder” on page 1-20
- “Specify Custom Names for Generated Files” on page 1-23
- “Import Structured Text Code Automatically” on page 1-24
- “Simulation and Code Generation of Motion Instructions” on page 1-28

Simulink PLC Coder Product Description

Generate IEC 61131-3 Structured Text for PLCs and PACs

Simulink® PLC Coder™ generates hardware-independent IEC 61131-3 Structured Text from Simulink models, Stateflow® charts, and MATLAB® functions. The Structured Text is generated in PLCopen XML and other file formats supported by widely used integrated development environments (IDEs) including 3S-Smart Software Solutions CODESYS, Rockwell Automation® Studio 5000, Siemens® TIA Portal, and OMRON® Sysmac® Studio. As a result, you can compile and deploy your application to numerous programmable logic controller (PLC) and programmable automation controller (PAC) devices.

Simulink PLC Coder generates test benches that help you verify the Structured Text using PLC and PAC IDEs and simulation tools. It also provides code generation reports with static code metrics and bidirectional traceability between model and code. Support for industry standards is available through IEC Certification Kit (for IEC 61508 and IEC 61511).

Key Features

- Automatic generation of IEC 61131-3 Structured Text
- IDE support, including 3S-Smart Software Solutions CODESYS, Rockwell Automation Studio 5000, Siemens TIA Portal, OMRON Sysmac Studio, and PLCopen XML
- Simulink support, including reusable subsystems, PID controller blocks, and lookup tables
- Stateflow support, including state machines, graphical functions, and truth tables
- MATLAB support, including if-else statements, loop constructs, and math operations
- Support for multiple data types, including Boolean, integer, enumerated, and floating-point, as well as vectors, matrices, buses, and tunable parameters
- Test bench creation

PLC Code Generation in the Development Process

Simulink PLC Coder software lets you generate IEC 61131-3 compliant Structured Text code from Simulink models. This software brings the Model-Based Design approach into the domain of PLC and PAC development. Using the coder, system architects and designers can spend more time fine-tuning algorithms and models through rapid prototyping and experimentation, and less time on coding PLCs.

Typically, you use a Simulink model to simulate a design for realization in a PLC. Once satisfied that the model meets design requirements, run the Simulink PLC Coder compatibility checker utility. This utility verifies compliance of model semantics and blocks for PLC target IDE code generation compatibility. Next, invoke the Simulink PLC Coder tool, using either the command line or the graphical user interface. The coder generates Structured Text code that implements the design embodied in the model.

Usually, you also generate a corresponding test bench. You can use the test bench with PLC emulator tools to drive the generated Structured Text code and evaluate its behavior.

The test bench feature increases confidence in the generated code and saves time spent on test bench implementation. The design and test process are fully iterative. At any point, you can return to the original model, modify it, and regenerate code.

At completion of the design and test phase of the project, you can easily export the generated Structure Text code to your PLC development environment. You can then deploy the code.

Expected Users

The Simulink PLC Coder product is a tool for control and algorithm design and test engineers in the following applications:

- PLC manufacturing
- Machine manufacturing
- Systems integration

You should be familiar with:

- MATLAB and Simulink software and concepts
- PLCs

- Structured Text language

If you want to download generated code to a PLC IDE, you should also be familiar with your chosen PLC IDE platform. For a list of these platforms, see “Supported IDE Platforms” on page 1-5.

Glossary

Term	Definition
PAC	Programmable automation controller.
PLC	Programmable logic controller.
IEC 61131-3	IEC standard that defines the Structured Text language for which the Simulink PLC Coder software generates code.
PLCopen	Vendor- and product-independent organization that works with the IEC 61131-3 standard. The Simulink PLC Coder product can generate Structured Text using the PLCopen XML standard format. See http://www.plcopen.org/pages/tc6_xml/xml_intro/index.htm for details.
Structured Text	High-level textual language defined by IEC 61131-3 standard for the programming of PLCs.
function block	Structured Text language programming concept that allows the encapsulation and reuse of algorithmic functionality.

System Requirements

For a list of related products, see System Requirements at the MathWorks® website.

Supported IDE Platforms

The Simulink PLC Coder product is tested with the following IDE platforms:

- 3S-Smart Software Solutions CoDeSys Version 2.3 or 3.3 or 3.5 (SP4 or later)
- B&R Automation Studio® 3.0 or 4
- Beckhoff® TwinCAT® 2.11 or 3
- KW-Software MULTIPROG® 5.0 or 5.5

The Simulink PLC Coder software supports only the English version of KW-Software MULTIPROG target IDE.

- OMRON Sysmac Studio Version 1.04, 1.05, 1.09 or 1.12
- Phoenix Contact® PC WORX™ 6.0

The Simulink PLC Coder software supports only the English version of Phoenix Contact PC WORX target IDE.

- Rexroth IndraWorks version 13V12 IDE
- Rockwell Automation RSLogix™ 5000 Series Version 17, 18, 19 or 20 and Rockwell Studio 5000 Version 21 or 24

Simulink PLC Coder can generate code for Add-On instructions (AOIs) and routine code. The software supports automatic import and verification of generated code only for the RSLogix IDEs and not the Studio 5000 IDE.

- Siemens SIMATIC® STEP® 7 Version 5.4 or 5.5

The Simulink PLC Coder software assumes that English systems use English S7. It assumes that German systems use German S7.

- Siemens TIA Portal V13
- Generic
- PLCopen XML

For a list of supported IDEs and platforms, see Supported IDEs at the MathWorks website.

PLC Code Generation Workflow

Your basic Simulink PLC Coder workflow is:

- 1 Define and design a Simulink model from which you want to generate code.
- 2 Identify the model components for which you want to generate code for importing to a PLC.
- 3 Place the components in a Subsystem block.
- 4 Identify your target PLC IDE.
- 5 Select a solver.
- 6 Configure the Subsystem block to be atomic.
- 7 Check that the model is compatible with the Simulink PLC Coder software.
- 8 Simulate your model.
- 9 Configure model parameters to generate code for your PLC IDE.
- 10 Examine the generated code.
- 11 Import code to your PLC IDE.

Prepare Model for Structured Text Generation

In this section...

“Tasking Mode” on page 1-7

“Solvers” on page 1-7

“Configuring Simulink Models for Structured Text Code Generation” on page 1-7

“Checking System Compatibility for Structured Text Code Generation” on page 1-11

Tasking Mode

This step is only required if your Simulink model contains multi-rate signals. If your Simulink model does not contain multi-rate signals, you may proceed to solver selection.

Simulink PLC Coder only generates code for single-tasking subsystems. For multi-rate subsystems, you must first explicitly set the tasking mode to single-tasking before selecting a solver. In the model configuration, on the Solver pane, for the option **Tasking mode for periodic sample times**, select `SingleTasking`.

Solvers

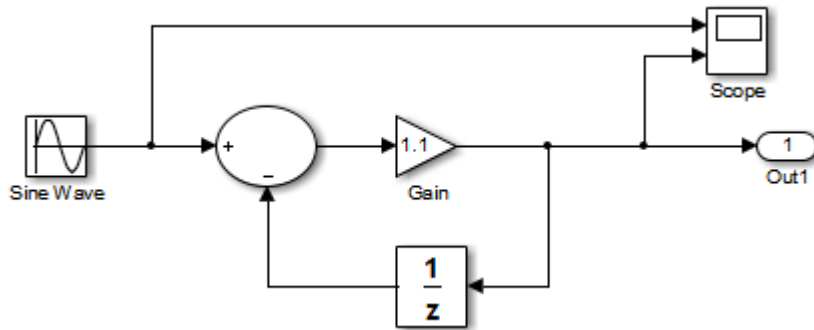
Choose a solver for your Simulink PLC Coder model.

Model	Solver Setting
Variable-step	Use a continuous solver. Configure a fixed sample time for the subsystem for which you generate code.
Fixed-step	Use a discrete fixed-step solver.

Configuring Simulink Models for Structured Text Code Generation

You must already have a model for which you want to generate and import code to a PLC IDE. Before you use this model, perform the following steps.

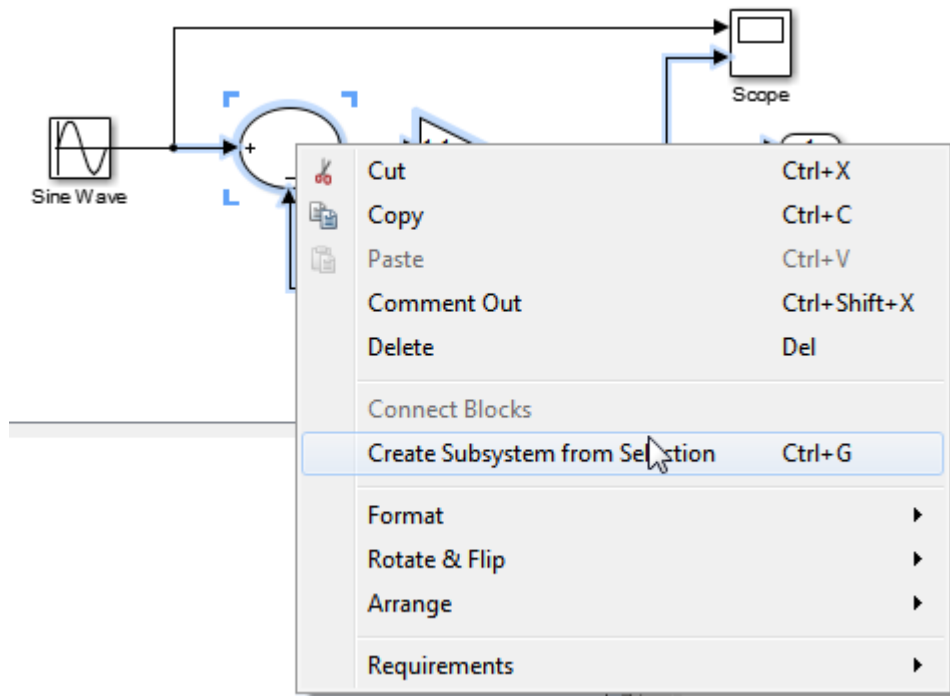
- 1 In the Command Window, open your model.



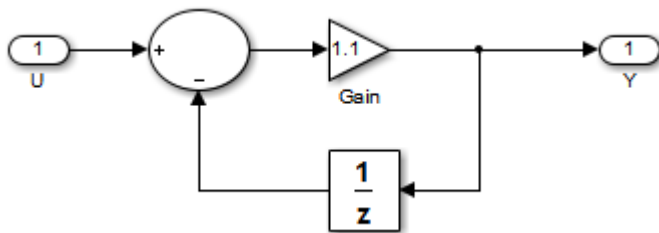
- 2 Configure the model to use the fixed-step discrete solver. Select **Simulation > Model Configuration Parameters** and in the Solver pane, set **Type** to **Fixed-step** and **Solver** to **discrete** (no continuous states).

If your model uses a continuous solver, has a subsystem, configure a fixed sample time for the subsystem for which you generate code.

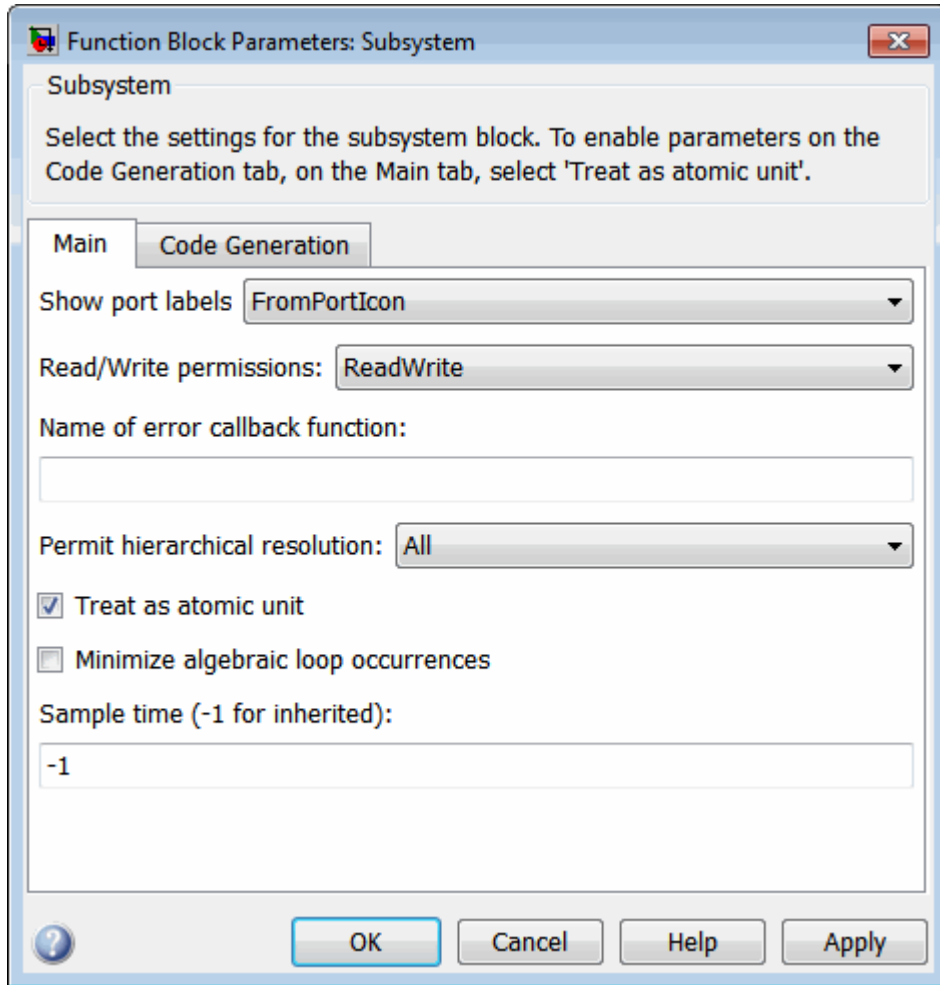
- 3 Save this model as `plcdemo_simple_subsystem1`.
- 4 Create a subsystem containing the components for which you want to generate Structured Text code.



Optionally, rename In1 and Out1 to U and Y respectively. This operation results in a subsystem like the following figure:



- 5 Save the model with the new subsystem.
- 6 In the top-level model, right-click the Subsystem block and select **Block Parameters (Subsystem)**.
- 7 In the resulting block dialog box, select **Treat as atomic unit**.



- 8 Click **OK**.
- 9 Simulate your model.
- 10 Save your model. In later procedures, you can use either this model, or the `plcdemo_simple_subsystem` model that comes with your software.

You are now ready to:

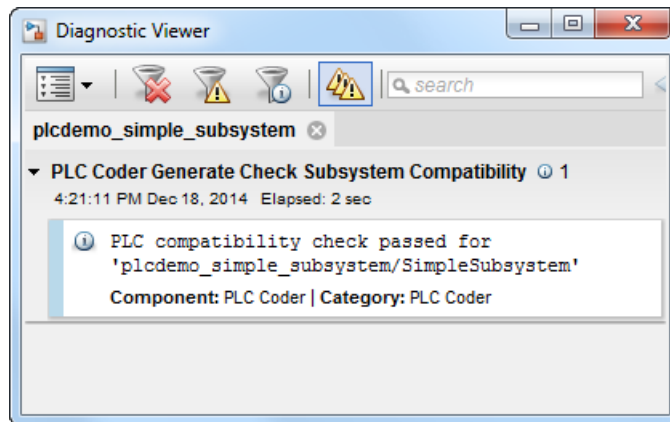
- Set up your subsystem to generate Structured Text code. See “Checking System Compatibility for Structured Text Code Generation” on page 1-11.
- Generate Structured Text code for your IDE. See “Generate and Examine Structured Text Code” on page 1-14.

Checking System Compatibility for Structured Text Code Generation

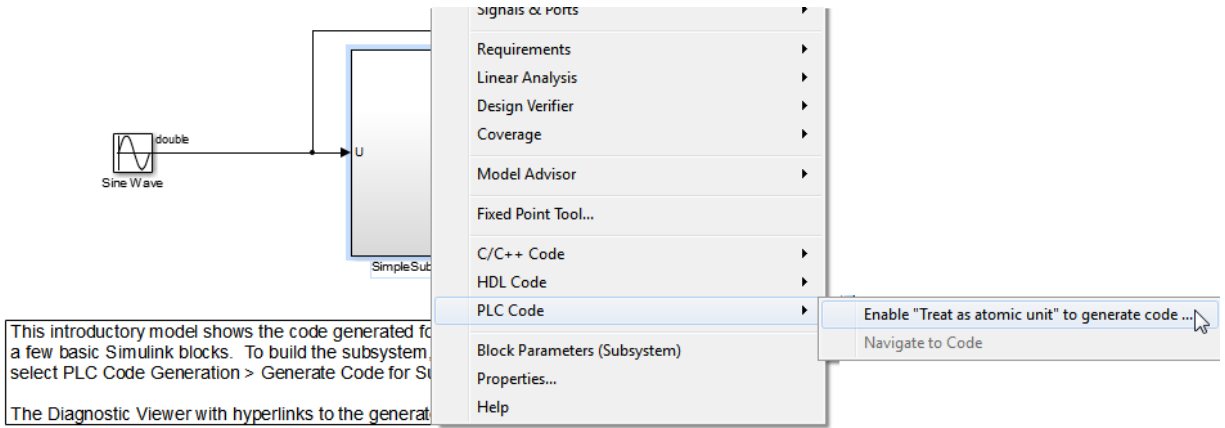
You must already have a model that you have configured to work with the Simulink PLC Coder software.

- 1 In your model, navigate to the subsystem for which you want to generate code.
- 2 Right-click that Subsystem block and select **PLC Code > Check Subsystem Compatibility**.

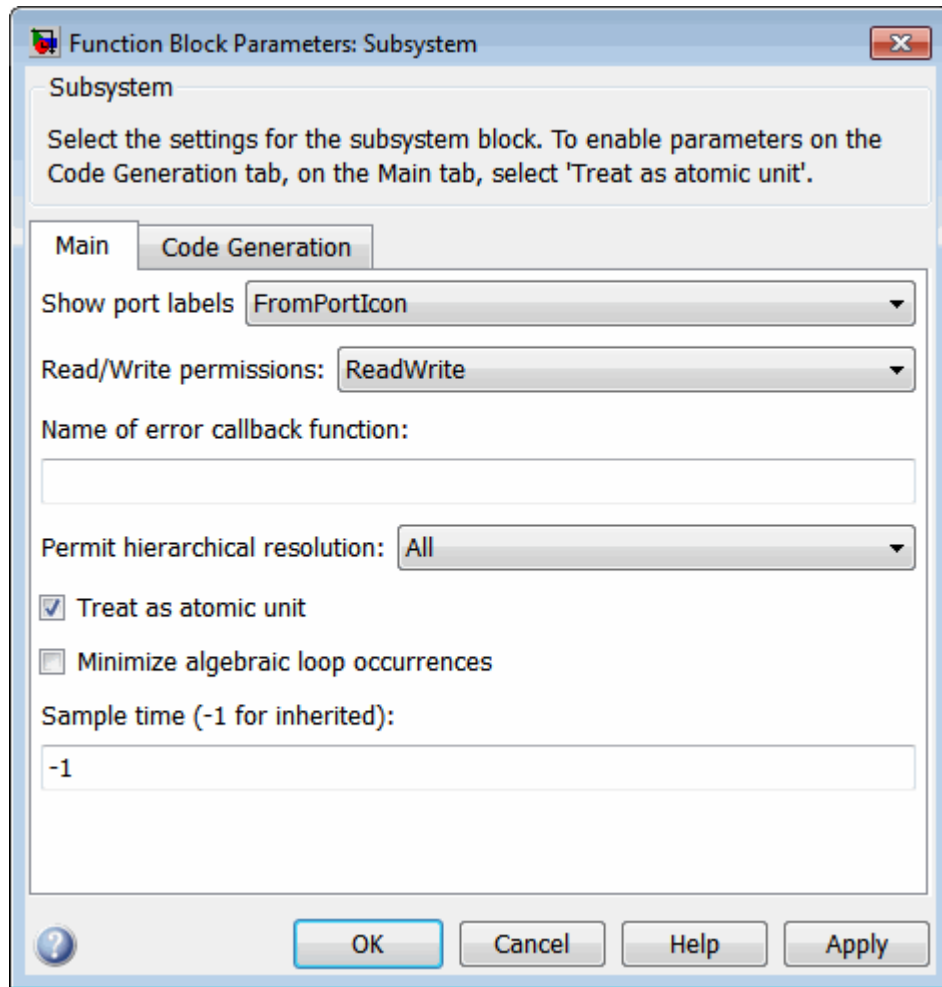
The coder checks whether your model satisfies the Simulink PLC Coder criteria. When the checking is complete, a **View diagnostics** hyperlink appears at the bottom of the model window. Click this hyperlink to open the Diagnostic Viewer window.



If the subsystem is not atomic, right-click the Subsystem block and select **PLC Code**, which prompts **Enable “Treat as atomic unit” to generate code**.



This command opens the block parameter dialog box. Select **Treat as atomic unit**.



You are now ready to generate Structured Text code for your IDE. See “Generate and Examine Structured Text Code” on page 1-14.

Generate and Examine Structured Text Code

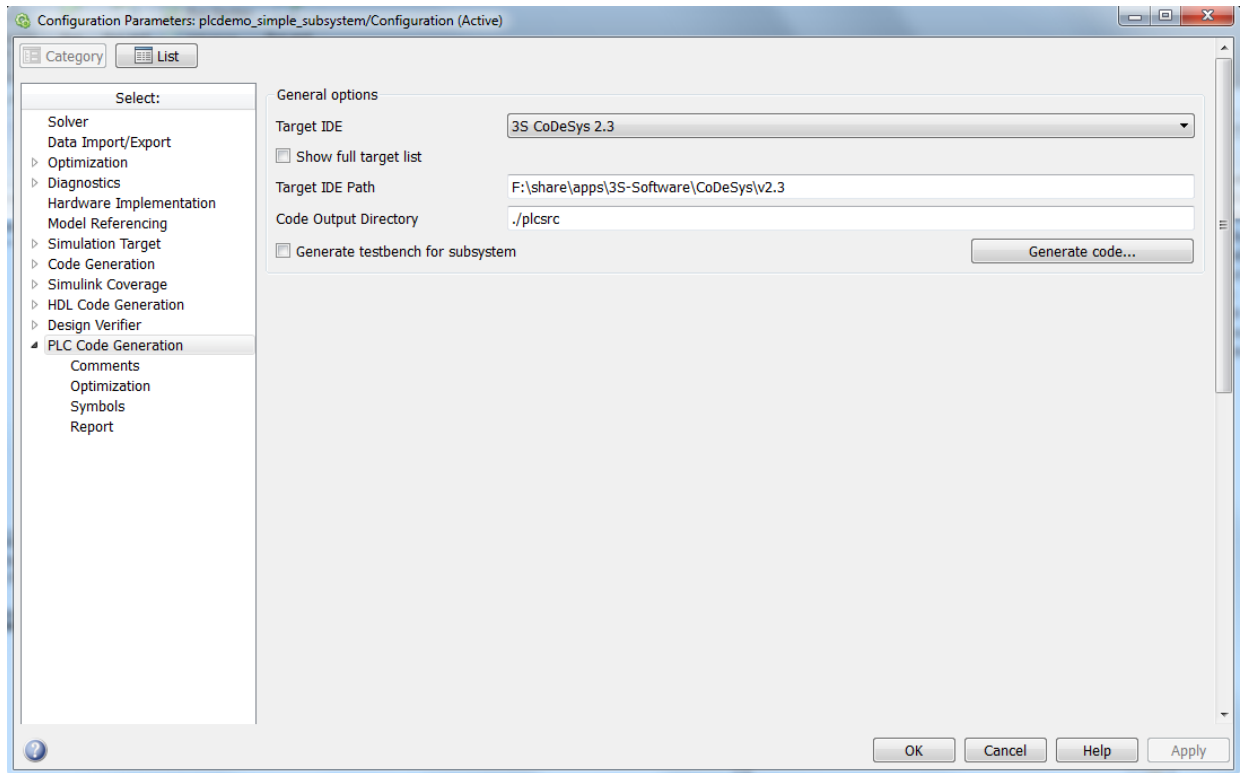
In this section...
“Generate Structured Text from the Model Window” on page 1-14
“Generate Structured Text with the MATLAB Interface” on page 1-16
“View Generated Code” on page 1-17

Generate Structured Text from the Model Window

You must already have set up your environment and Simulink model to use the Simulink PLC Coder software to generate Structured Text code. If you have not yet done so, see “Prepare Model for Structured Text Generation” on page 1-7.

- 1 If you do not have the `plcdemo_simple_subsystem` model open, open it now.
- 2 Right-click the Subsystem block and select **PLC Code > Options**.

The Configuration Parameters dialog box is displayed.



- 3 On the **PLC Code Generation** pane, select an option from the **Target IDE** list, for example, **3S CoDeSys 2.3**.

The default **Target IDE** list shows a reduced subset of targets. To customize this list, use the `plccoderpref` function. To see all target IDEs supported by Simulink PLC Coder, select **Show full target list**.

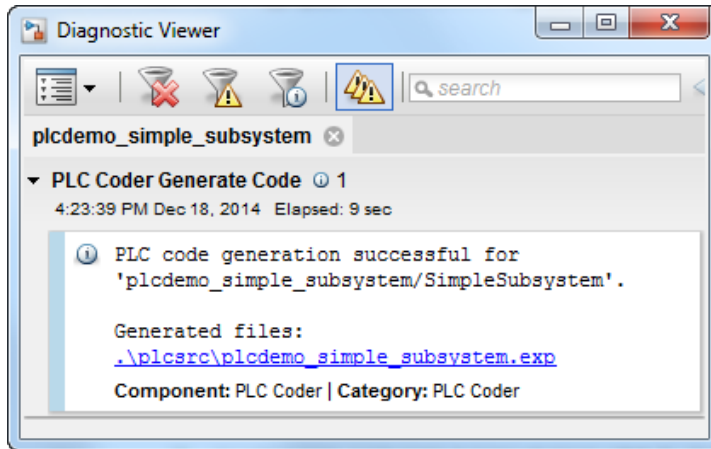
- 4 Click **Apply**.
- 5 Click **Generate code**.

This button:

- Generates Structured Text code (same as the **PLC Code > Generate Code for Subsystem** option)

- Stores generated code in *model_name.exp* (for example, `plcdemo_simple_subsystem.exp`)

When code generation is complete, a **View diagnostics** hyperlink appears at the bottom of the model window. Click this hyperlink to open the Diagnostic Viewer window.



This window has links that you can click to open the associated files. For more information, see “Files Generated with Simulink PLC Coder” on page 1-20.

Generate Structured Text with the MATLAB Interface

You can generate Structured Text code for a subsystem in the Command Window with the `plcgeneratecode` function. You must have already configured the parameters for the model or, alternatively, you may use the default settings.

For example, to generate code from the `SimpleSubsystem` subsystem in the `plcdemo_simple_subsystem` model:

- 1 Open the `plcdemo_simple_subsystem` model:
`plcdemo_simple_subsystem`
- 2 Open the Configuration Parameters dialog box using the `plcopenconfigset` function:
`plcopenconfigset('plcdemo_simple_subsystem/SimpleSubsystem')`

- 3 Select a target IDE.
- 4 Configure the subsystem as described in “Prepare Model for Structured Text Generation” on page 1-7.
- 5 Generate code for the subsystem:

```
generatedfiles = plcgeneratecode('plcdemo_simple_subsystem/SimpleSubsystem')
```

View Generated Code

After generating the code, you can view it in the MATLAB Editor. For a description of how the generated code for the Simulink components map to Structured Text components, see “PLC Code Generation Basics”. In addition, note the following:

- Matrix data types: The coder converts matrix data types to single-dimensional vectors (column-major) in the generated Structured Text.
- Generated code header: If your model has author names, creation dates, and model descriptions, the generated code contains these items in the header comments. The header also lists fundamental sample times for the model and the subsystem block for which you generate code.
- Code comments: You can choose to propagate block descriptions to comments in generated code. See “Propagate Block Descriptions to Code Comments” on page 1-19.

The figure illustrates generated code for the CoDeSys Version 2.3 PLC IDE. Generated code for other platforms, such as Rockwell Automation RSLogix 5000, is in XML or other format and looks different.

```
15 FUNCTION_BLOCK SimpleSubsystem
16 VAR_INPUT
17     ssMethodType: SINT;
18     U: LREAL;
19 END_VAR
20 VAR_OUTPUT
21     Y: LREAL;
22 END_VAR
23 VAR
24     UnitDelay_DSTATE: LREAL;
25 END_VAR
26 VAR_TEMP
27     rtb_Gain: LREAL;
28 END_VAR
29 CASE ssMethodType OF
30     SS_INITIALIZE:
31         (* InitializeConditions for UnitDelay: '<S1>/Unit Delay' *)
32         UnitDelay_DSTATE := 0;
33
34     SS_OUTPUT:
35         (* Gain: '<S1>/Gain' incorporates:
36          * Inport: '<Root>/U'
37          * Sum: '<S1>/Sum'
38          * UnitDelay: '<S1>/Unit Delay'
39          *)
40         rtb_Gain := (U - UnitDelay_DSTATE) * 0.5;
41
42         (* Output: '<Root>/Y' *)
43         Y := rtb_Gain;
44
45         (* Update for UnitDelay: '<S1>/Unit Delay' *)
46         UnitDelay_DSTATE := rtb_Gain;
47
48     END_CASE;
49 END FUNCTION_BLOCK
```

If you are confident that the generated Structured Text is good, optionally change your workflow to automatically generate and import code to the target IDE. For more information, see “Import Structured Text Code Automatically” on page 1-24.

Propagate Block Descriptions to Code Comments

You can propagate block descriptions from the model to comments in your generated code.

For specific IDEs, you can propagate the block descriptions into specific XML tags in the generated code. The IDEs use the tags to create a readable description of the function blocks in the IDE.

- For Rockwell Automation RSLogix 5000 AOI/routine target IDEs, the coder propagates block descriptions from the model into the `L5X AdditionalHelpText` XML tag. The IDE can then import the tag as part of AOI and routine definition in the generated code.
- For CoDeSys 3.5 IDE, the coder propagates block descriptions from the model into the `documentation` XML tag. When you import the generated code into the CoDeSys 3.5 IDE, the IDE parses the content of this tag and provides readable descriptions of the function blocks in your code.

To propagate block descriptions to comments:

- 1 Enter a description for the block.
 - a Right-click the block for which you want to write a description and select **Properties**.
 - b On the **General** tab, enter a block description.
- 2 Before code generation, specify that block descriptions must propagate to code comments.
 - a Right-click the subsystem for which you are generating code and select **PLC Code > Options**.
 - b Select the option “Include block description” on page 12-15.

Your block description appears as comments in the generated code.

Files Generated with Simulink PLC Coder

The Simulink PLC Coder software generates Structured Text code and stores it according to the target IDE platform. These platform-specific paths are default locations for the generated code. To customize generated file names, see “Specify Custom Names for Generated Files” on page 1-23.

Platform	Generated Files
3S-Smart Software Solutions CoDeSys 2.3	<i>current_folder</i> \plcsrc\model_name.exp — Structured Text file for importing to the target IDE.
3S-Smart Software Solutions CoDeSys 3.3	<i>current_folder</i> \plcsrc\model_name.xml — Structured Text file for importing to the target IDE.
3S-Smart Software Solutions CoDeSys 3.5	<i>current_folder</i> \plcsrc\model_name.xml — Structured Text file for importing to the target IDE.
B&R Automation Studio IDE	<p>The following files in <i>current_folder</i>\plcsrc\model_name — Files for importing to the target IDE:</p> <ul style="list-style-type: none"> • <code>Package.pkg</code> — (If test bench is generated) Top-level package file for function blocks library and test bench main program in XML format. <p>In the main folder (if test bench is generated):</p> <ul style="list-style-type: none"> • <code>IEC.prg</code> — Test bench main program definition file in XML format. • <code>mainInit.st</code> — Text file. Test bench init program file in Structured Text. • <code>mainCyclic.st</code> — Text file. Test bench cyclic program file in Structured Text. • <code>mainExit.st</code> — Text file. Test bench exit program file in Structured Text. • <code>main.typ</code> — Text file. Main program type definitions file in Structured Text. • <code>main.var</code> — Text file. Main program variable definitions file in Structured Text.

Platform	Generated Files
Beckhoff TwinCAT 2.11	<i>current_folder</i> \plcsrc\model_name.exp — Structured Text file for importing to the target IDE.
KW-Software MULTIPROG 5.0	<i>current_folder</i> \plcsrc\model_name.xml — Structured Text file, in XML format, for importing to the target IDE.
Phoenix Contact PC WORX 6.0	<i>current_folder</i> \plcsrc\model_name.xml — Structured Text file, in XML format, for importing to the target IDE.
Rockwell Automation RSLogix 5000 IDE: AOI	<i>current_folder</i> \plcsrc\model_name.L5X — (If test bench is generated) Structured Text file for importing to the target IDE using Add-On Instruction (AOI) constructs. This file is in XML format and contains the generated Structured Text code for your model.
Rockwell Automation RSLogix 5000 IDE: Routine	<p><i>current_folder</i>\plcsrc\model_name.L5X — (If test bench is generated) Structured Text file for importing to the target IDE using routine constructs. This file is in XML format and contains the generated Structured Text code for your model.</p> <p>In <i>current_folder</i>\plcsrc\model_name (if test bench is not generated), the following files are generated:</p> <ul style="list-style-type: none"> • <i>subsystem_block_name</i>.L5X — Structured Text file in XML format. Contains program tag and UDT type definitions and the routine code for the top-level subsystem block. • <i>routine_name</i>.L5X — Structured Text files in XML format. Contains routine code for other subsystem blocks.
Siemens SIMATIC STEP 7 IDE	<p><i>current_folder</i>\plcsrc\model_name\model_name.scl — Structured Text file for importing to the target IDE.</p> <p><i>current_folder</i>\plcsrc\model_name\model_name.asc — (If test bench is generated) Text file. Structured Text file and symbol table for generated test bench code.</p>
Siemens TIA Portal IDE	<i>current_folder</i> \plcsrc\model_name\model_name.scl — Structured Text file for importing to the target IDE.

Platform	Generated Files
Generic	<i>current_folder\plcsrc\model_name.st</i> — Pure Structured Text file. If your target IDE is not available for the Simulink PLC Coder product, consider generating and importing a generic Structured Text file.
PLCopen XML	<i>current_folder\plcsrc\model_name.xml</i> — Structured Text file formatted using the PLCopen XML standard. If your target IDE is not available for the Simulink PLC Coder product, but uses a format like this standard, consider generating and importing a PLCopen XML Structured Text file.

Specify Custom Names for Generated Files

The Simulink PLC Coder software generates Structured Text code and stores it according to the target IDE platform. These platform-specific paths are default locations for the generated code. For more information, see “Files Generated with Simulink PLC Coder” on page 1-20.

To specify a different name for the generated files, set the **Function name options** parameter in the Subsystem block:

- 1 Right-click the Subsystem block for which you want to generate code and select **Subsystem Parameters**.
- 2 In the **Main** tab, select the **Treat as atomic unit** check box.
- 3 Click the **Code Generation** tab.
- 4 From the **Function Packaging** parameter list, select either **Nonreusable function** or **Reusable Function**.

These options enable the **Function name options** and **File name options** parameters.

- 5 Select the option that you want to use for generating the file name.

Function name options	Generated File Name
Auto	Default. Uses the model name, as listed in “Prepare Model for Structured Text Generation” on page 1-7, for example, <code>plcdemo_simple_subsystem</code> .
Use subsystem name	Uses the subsystem name, for example, <code>SimpleSubsystem</code> .
User specified	Uses the custom name that you specify in the Function name parameter, for example, <code>SimpleSubsystem</code> .

Import Structured Text Code Automatically

In this section...
“PLC IDEs That Qualify for Importing Code Automatically” on page 1-24
“Generate and Automatically Import Structured Text Code” on page 1-24
“Troubleshoot Automatic Import Issues” on page 1-25

PLC IDEs That Qualify for Importing Code Automatically

If you are confident that your model produces Structured Text that does not require visual examination, you can generate and automatically import Structured Text code to one of the following target PLC IDEs:

- 3S-Smart Software Solutions CoDeSys Version 2.3
- KW-Software MULTIPROG Version 5.0
- Phoenix Contact PC WORX Version 6.0
- Rockwell Automation RSLogix 5000 Version 17, 18, or 19

For the Rockwell Automation RSLogix routine format, you must generate testbench code for automatic import and verification.

- Siemens SIMATIC STEP 7 Version 5.4 only for the following versions:
 - Siemens SIMATIC Manager: Version V5.4+SP5+HF1, Revision K5.4.5.1
 - S7-SCL: Version V5.3+SP5, Revision K5.3.5.0
 - S7-PLCSIM: Version V5.4+SP3, Revision K5.4.3.0

Working with the default CoDeSys Version 2.3 IDE should require additional changes for only the KW-Software MULTIPROG 5.0 and Phoenix Contact PC WORX 6.0 IDE. For information about automatically importing Structured Text code to these IDEs, see “Import and Verify Structured Text to KW-Software MULTIPROG 5.0 and Phoenix Contact PC WORX 6.0 IDEs” on page 3-5.

Generate and Automatically Import Structured Text Code

You can generate and automatically import Structured Text code. Before you start:

- In the target IDE, save your current project.

- Close open projects.
- Close the target IDE and target IDE-related windows.

Note: While the automatic import process is in progress, do not touch your mouse or keyboard. Doing so might disrupt the process. When the process completes, you can resume normal operations.

You must have already installed your target PLC IDE in a default location, and it must use the CoDeSys V2.3 IDE. If you installed the target PLC IDE in a nondefault location, open the Configuration Parameters dialog box. In the PLC Coder node, set the **Target IDE Path** parameter to the installation folder of your PLC IDE. See “Target IDE Path” on page 12-9.

- 1 If it is not already started, open the Command Window.
- 2 Open the `plcdemo_simple_subsystem` model.
- 3 Right-click the Subsystem block and select **PLC Code > Generate and Import Code for Subsystem**.

The software:

- a Generates the code.
- b Starts the target IDE interface.
- c Creates a new project.
- d Imports the generated code to the target IDE.

If you want to generate, import, and run the Structured Text code, see “Import and Verify Structured Text Code” on page 3-4.

Troubleshoot Automatic Import Issues

Following are guidelines, hints, and tips for questions or issues you might have while using the automatic import capability of the Simulink PLC Coder product.

Supported Target IDEs

The Simulink PLC Coder software supports only the following versions of target IDEs for automatic import and verification:

- 3S-Smart Software Solutions CoDeSys Version 2.3
- KW-Software MULTIPROG 5.0 (English)
- Phoenix Contact PC WORX 6.0 (English)
- Rockwell Automation RSLogix 5000 Series Version 17, 18, 19 (English)

For the Rockwell Automation RSLogix routine format, you must generate testbench code for automatic import and verification.

- Siemens SIMATIC STEP 7 Version 5.4 (English and German)

Unsupported Target IDEs

The following target IDEs currently do not support automatic import. For these target IDEs, the automatic import menu items (**Generate and Import Code for Subsystem** and **Generate, Import, and Verify Code for Subsystem**) are disabled.

- 3S-Smart Software Solutions CoDeSys Version 3.3
- 3S-Smart Software Solutions CoDeSys Version 3.5
- B&R Automation Studio IDE
- Beckhoff TwinCAT 2.11
- Generic
- PLCopen

Possible Automatic Import Issues

When the Simulink PLC Coder software fails to finish automatically importing for the target IDE, it reports an issue in a message dialog box. To remedy the issue, try the following actions:

- Check that the coder supports the target IDE version and language setting combination.
- Check that you have specified the target IDE path in the subsystem Configuration Parameters dialog box.
- Close currently open projects in the target IDE, close the target IDE completely, and try again.
- Some target IDEs can have issues supporting the large data sets the coder test bench generates. In these cases, try to shorten the simulation cycles to reduce the data set size, then try the automatic import again.

- Other applications can interfere with automatic importing to a target IDE. Try to close other unrelated applications on the system and try the automatic import again.

Simulation and Code Generation of Motion Instructions

In this section...
“Workflow for Using Motion Instructions in Model” on page 1-28
“Library of Motion Instructions” on page 1-30
“Data Types for Motion Instructions” on page 1-31
“Limitations for MAM Instruction” on page 1-31

The Simulink PLC Coder software supports a workflow for the behavioral simulation and code generation of motion instructions for the Rockwell Automation RSLogix 5000 IDE.

Workflow for Using Motion Instructions in Model

This workflow uses `plcdemo_motion_control` in the `plcdemos` folder. This example provides a template that you can use with motion instructions. It contains the following subsystems.

Subsystem	Description
Controller	<p>Contains an example Stateflow chart with motion instructions. The controller subsystem sends input to the Command Profile subsystem (part of the template).</p> <p>Replace this subsystem with your own controller subsystem.</p>
Command Profile	<p>Contains a utility subsystem in which the coder calculates the position data based on the parameters of the motion instructions MAM command.</p>
Drive Model	<p>Contains a minimalistic drive model.</p> <p>Replace this subsystem with your own drive model subsystem.</p>
Drive Status	<p>Contains a utility subsystem that reads drive status and returns that status to the Controller subsystem.</p> <p>Typically, you do not need to modify or replace this subsystem.</p>

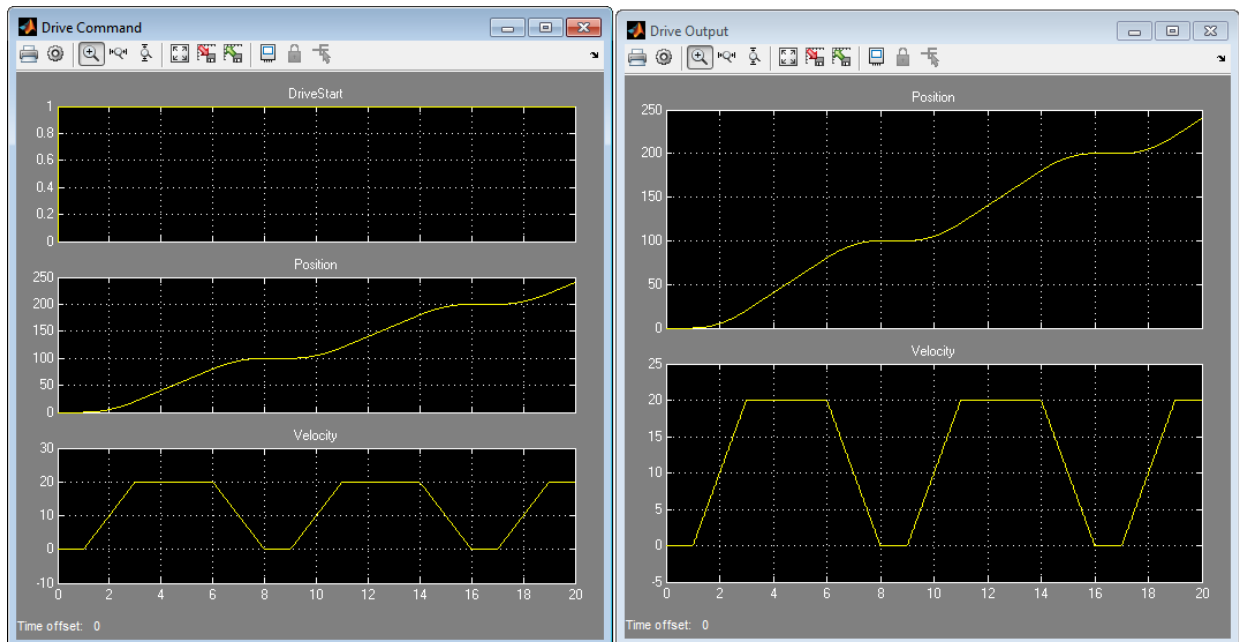
Before you start, create:

- A custom controller subsystem. This subsystem contains motion instructions. The controller subsystem sends input to the Command Profile subsystem.
- A custom drive (plant) model subsystem. The subsystem sends input to a Drive Status subsystem. Design the subsystem to work with the inputs and outputs.

To modify the `plcdemo_motion_control` example:

- 1 Open the `plcdemo_motion_control` example template.
- 2 In the Controller subsystem, replace the ExampleController chart with your controller subsystem.
- 3 In the template, replace the Drive Model subsystem with your drive (plant) model.
- 4 Simulate the model.
- 5 Observe the simulation results in the model scopes.

The following plots show the output from `plcdemo_motion_control` without modification.



- 6 Generate code for the example model. To view the code in “Generate a Traceability Report from Configuration Parameters” on page 4-4, in the coder configuration parameters, select the **PLC Code Generation > Report > Generate traceability report** check box and click **Apply**.

Navigate to the **PLC Code Generation** node and click **Generate code**.

An HTML file of the generated code is displayed.

- 7 Observe the generated code for MAM, MAFR, and MSO.

```
ELSE
(* During 'Init': '<S2>:1' *)
IF NOT Axis.ServoActionStatus THEN
(* Transition: '<S2>:5' *)
MAFR(Axis, MC_MAFR_STAxis);
MSO(Axis, MSO_STAxis);
is_c1_Controller := 2;
PLC_CODER_TIMER(temporalCounter_i1, 1, 0, temp1);
(* Entry 'Init': '<S2>:1' *)
(* A very simple controller that will check if the axis is ready to move
and if so will execute a move cmd.
If the axis is off or in error it will try to reset and restart.
MAM_1 is the instance tag of the move cmd
Axis_1 is the axis tag (need to be passes by reference) *)
dMoveType := 1;
rPosition := 100.0;
rSpeed := 20.0;
rAccRate := 10.0;
rDecRate := rAccRate;
rAccJerk := 20.0;
rDecJerk := rAccJerk;
ELSE
PLC_CODER_TIMER(temporalCounter_i1, 2, 1000, temp1);
IF (Axis.ServoActionStatus AND ( NOT MC_MAM_Axis.IP)) AND temp1 THEN
(* Transition: '<S2>:3' *)
is_c1_Controller := 1;
(* Entry 'DoMove': '<S2>:2' *)
(* Motion Axis Move Command *)
MAM(Axis, MC_MAM_Axis, dMoveType, rPosition, rSpeed, 0, rAccRate, 0, rDecRate, 0, 1, rAccJerk, rDecJerk, 1, 0, 0);
```

MAFR and MSO

MAM

Library of Motion Instructions

The `plcdemo_motion_control` example uses a motion instructions library that contains a Motion Stub Functions Stateflow chart. This chart defines stub functions for only the following motion instructions:

- MAM
- MAFR
- MSO

To use other Rockwell Automation RSLogix motion instructions in the model, you must define your own stub functions to correspond to the RSLogix motion instructions in the Motion Stub Functions chart.

Data Types for Motion Instructions

The `plcdemo_motion_control` example uses Simulink bus data types (`Simulink.Bus`). These data types correspond to the motion instruction `AXIS` and `MOTION_INSTRUCTION` user-defined data types (UDTs) in the Rockwell Automation RSLogix 5000 IDE. For these UDTs, the example defines only the fields used in the `ExampleController` chart of the `plcdemo_motion_control` example. When you generate code, the coder maps the bus data types to the motion instruction UDTs. If your controller subsystem uses other fields of motion instruction UDTs, you must add them to the definition of the corresponding Simulink bus data types. The `/toolbox/plccoder/plccoderdemos/PLCMotionType.mat` file contains the definitions of the Simulink bus data types. You can add more fields to these definitions as required by your controller.

Name	Size	Bytes	Class	Attributes
<code>AXIS_SERVO_DRIVE</code>	1x1		<code>Simulink.Bus</code>	
<code>MOTION_INSTRUCTION</code>	1x1		<code>Simulink.Bus</code>	

Limitations for MAM Instruction

In the `plcdemo_motion_control` example, the MAM instruction has the following limitations:

- Direction parameter is always forward.
- The software supports only the Trapezoidal profile.
- The software ignores units parameters.
- The software does not support Merge and Merge speed.

Mapping Simulink Semantics to Structured Text

- “Generated Code Structure for Simple Simulink Subsystems” on page 2-2
- “Generated Code Structure for Reusable Subsystems” on page 2-4
- “Generated Code Structure for Triggered Subsystems” on page 2-6
- “Generated Code Structure for Stateflow Charts” on page 2-8
- “Generated Code Structure for MATLAB Function Block” on page 2-13
- “Generated Code Structure for Multirate Models” on page 2-15
- “Generated Code Structure for Subsystem Mask Parameters” on page 2-17
- “Global Tunable Parameter Initialization for PC WORX” on page 2-22

Generated Code Structure for Simple Simulink Subsystems

This topic assumes that you have generated Structured Text code from a Simulink model. If you have not yet done so, see “Generate Structured Text from the Model Window” on page 1-14.

The example in this topic shows generated code for the CoDeSys Version 2.3 IDE. Generated code for other IDE platforms looks different.

- 1 If you do not have the `plcdemo_simple_subsystem.exp` file open, open it in the MATLAB editor. In the folder that contains the file, type:

```
edit plcdemo_simple_subsystem.exp
```

A file like the following is displayed.

The following figure illustrates the mapping of the generated code to Structured Text components for a simple Simulink subsystem. The Simulink subsystem corresponds to the Structured Text function block, **Subsystem**.

Note: The coder maps alias data types to the base data type in the generated code.

Input parameter for subsystem method type

Atomic subsystem name

Subsystem

Subsystem inputs and outputs

Subsystem State (DWork) variables

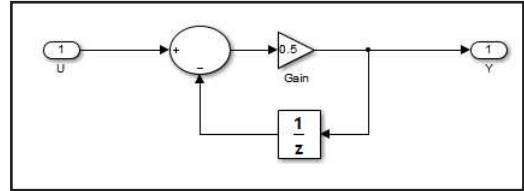
Initialize and step methods

Inlined parameters

```

16 FUNCTION_BLOCK SimpleSubsystem
17 VAR_INPUT
18   ssMethodType: SINT;
19   U: LREAL;
20 END_VAR
21 VAR_OUTPUT
22   Y: LREAL;
23 END_VAR
24 VAR
25   UnitDelay_DSTATE: LREAL;
26 END_VAR
27 VAR_TEMP
28   rtb_Gain: LREAL;
29 END_VAR
30 CASE ssMethodType OF
31   SS_INITIALIZE:
32
33     (* InitializeConditions for UnitDelay: '<S1>/Unit Delay' *)
34     UnitDelay_DSTATE := 0;
35   SS_STEP:
36
37     (* Gain: '<S1>/Gain' incorporates:
38      * Inport: '<Root>/U'
39      * Sum: '<S1>/Sum'
40      * UnitDelay: '<S1>/Unit Delay' *)
41     rtb_Gain := (U - UnitDelay_DSTATE) * 0.5;
42
43     (* Output: '<Root>/Y' *)
44     Y := rtb_Gain;
45
46     (* Update for UnitDelay: '<S1>/Unit Delay' *)
47     UnitDelay_DSTATE := rtb_Gain;

```



- 2 Inspect this code as you ordinarily do for PLC code. Check the generated code.

Generated Code Structure for Reusable Subsystems

This topic assumes that you have generated Structured Text code from a Simulink model. If you have not yet done so, see “Generate Structured Text from the Model Window” on page 1-14.

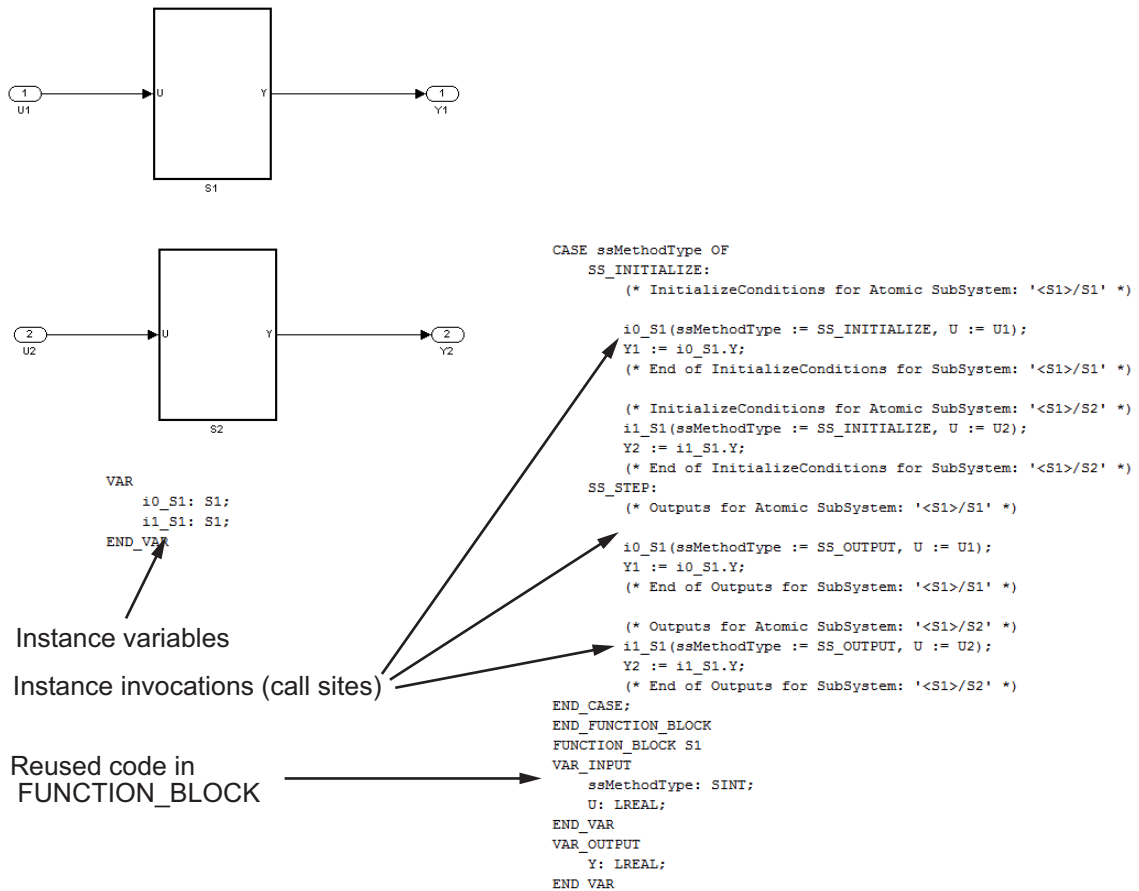
The example in this topic shows generated code for the CoDeSys Version 2.3 IDE. Generated code for other IDE platforms looks different.

- 1 Open the `plcdemo_reusable_subsystem` model.
- 2 Right-click the Subsystem block and select **PLC Code > Generate Code for Subsystem**.

The Simulink PLC Coder software generates Structured Text code and places it in *current_folder/plcsrc/plcdemo_reusable_subsystem.exp*.

- 3 If you do not have the `plcdemo_reusable_subsystem.exp` file open, open it in the MATLAB editor.

The following figure illustrates the mapping of the generated code to Structured Text components for a reusable Simulink subsystem . This graphic contains a copy of the hierarchical subsystem, `ReusableSubsystem`. This subsystem contains two identical subsystems, `S1` and `S2`. This configuration enables code reuse between the two instances (look for the `ReusableSubsystem` string in the code).



- Examine the generated Structured Text code. The code defines FUNCTION_BLOCK ReusableSubsystem_S1 once.

Look for two instance variables that correspond to the two instances declared inside the parent FUNCTION_BLOCK ReusableSubsystem (_instance_ReusableSubsystem_S1_1: ReusableSubsystem_S1 and _instance_ReusableSubsystem_S1_0: ReusableSubsystem_S1). The code invokes these two instances separately by passing in different inputs. The code invokes the outputs per the Simulink execution semantics.

Generated Code Structure for Triggered Subsystems

This topic assumes that you have generated Structured Text code from a Simulink model. If you have not yet done so, see “Generate Structured Text from the Model Window” on page 1-14.

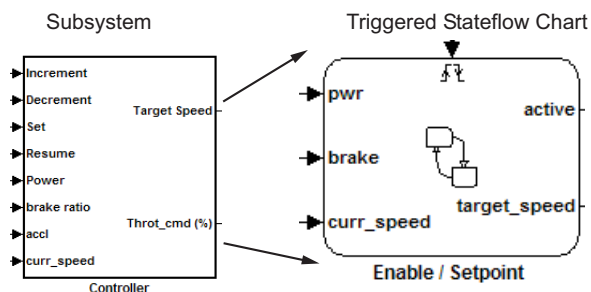
The example in this topic shows generated code for the CoDeSys Version 2.3 PLC IDE. Generated code for other IDE platforms looks different.

- 1 Open the `plcdemo_cruise_control` model.
- 2 Right-click the Controller subsystem block and select **PLC Code > Generate Code for Subsystem**.

The Simulink PLC Coder software generates Structured Text code and places it in `current_folder/plcsrc/plcdemo_cruise_control.exp`.

- 3 If you do not have the `plcdemo_cruise_control.exp` file open, open it in the MATLAB editor.

The following figure illustrates the mapping of the generated code to Structured Text components for a triggered Simulink subsystem. The first part of the figure shows the Controller subsystem and the triggered Stateflow chart that it contains. The second part of the figure shows excerpts of the generated code. Notice the zero-crossing functions that implement the triggered subsystem semantics.



Generated code

```

EnableSetpoint_Trig_ZCE: ARRAY [0..6] OF USINT := 3,3,3,3,3,3,3;
i0_ZCFCN_d_ANY: ZCFCN_d_ANY;
END_VAR
...
...
...
SS_STEP:

  (* DiscretePulseGenerator: '<S1>/Pulse Generator' *)
  IF (clockTickCounter < 1) AND (clockTickCounter >= 0) THEN
    temp1 := 1.0;
  ELSE
    temp1 := 0.0;
  END_IF;
  rtb_PulseGenerator := temp1;
  IF clockTickCounter >= 1 THEN
    clockTickCounter := 0;
  ELSE
    clockTickCounter := clockTickCounter + 1;
  END_IF;
  (* End of DiscretePulseGenerator: '<S1>/Pulse Generator' *)

  (* Chart: '<S1>/Enable // Setpoint ' incorporates:
   * TriggerPort: '<S2>/ input events ' *)
  tempInputSignal[0] := rtb_PulseGenerator;
  (* Inport: '<Root>/Increment' *)
  tempInputSignal[1] := Increment;
  tempInputSignal[2] := Increment;
  (* Inport: '<Root>/Decrement' *)
  tempInputSignal[3] := Decrement;
  tempInputSignal[4] := Decrement;
  (* Inport: '<Root>/Set' *)
  tempInputSignal[5] := Set;
  (* Inport: '<Root>/Resume' *)
  tempInputSignal[6] := Resume;
  (* Chart: '<S1>/Enable // Setpoint ' incorporates:
   * TriggerPort: '<S2>/ input events ' *)
  FOR inputEventIndex := 0 TO 6 DO
    i0_ZCFCN_d_ANY(u0 := EnableSetpoint_Trig_ZCE[inputEventIndex],
    callChartStep := i0_ZCFCN_d_ANY.y0,
    tmp := i0_ZCFCN_d_ANY.y1;
    tempOutEvent[inputEventIndex] := callChartStep;
    outState[inputEventIndex] := tmp;
  ...
  ...
  ...
FUNCTION_BLOCK ZCFCN_d_ANY
...
...
...
END_FUNCTION_BLOCK

```

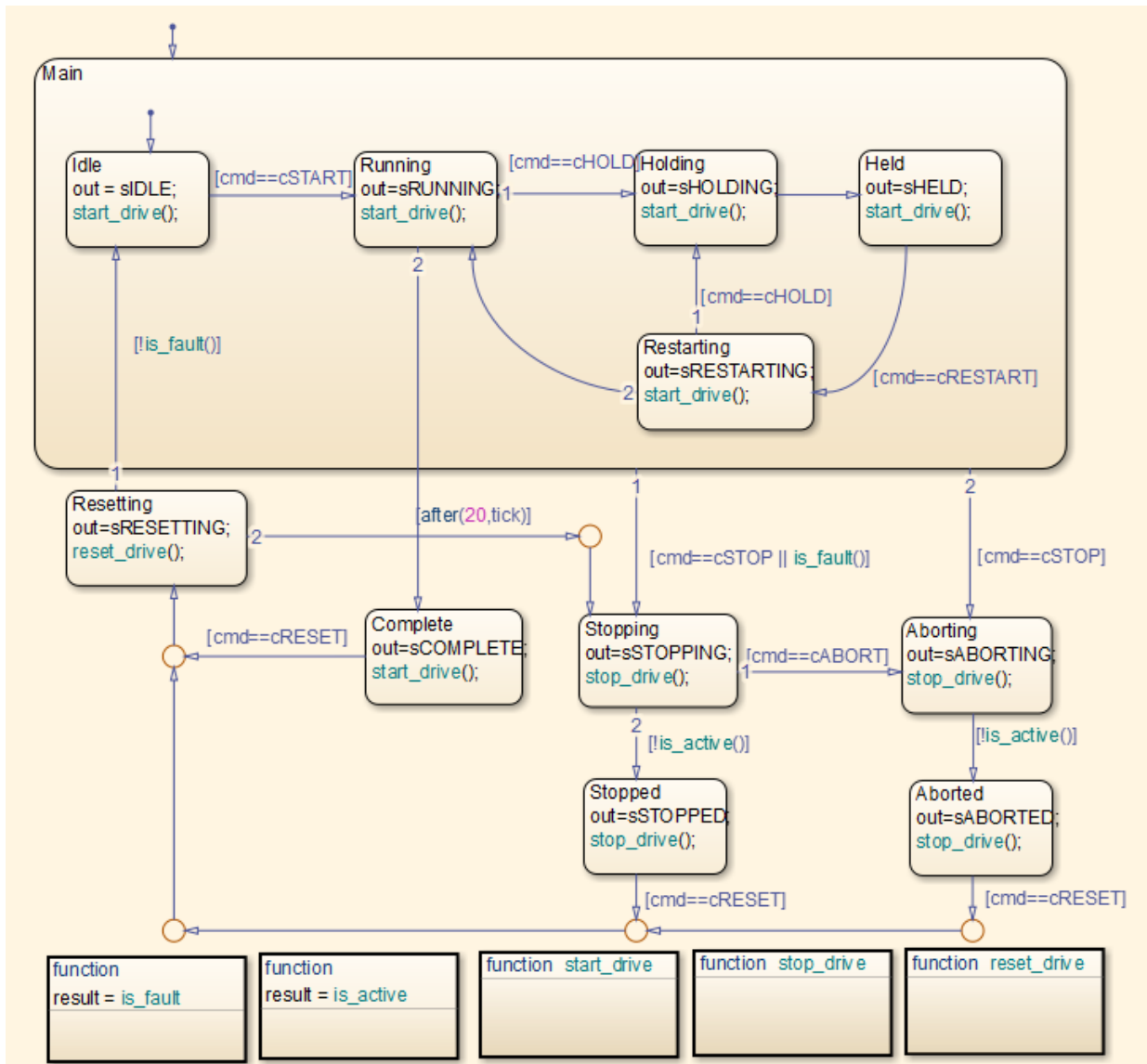
Triggered subsystem semantics

Generated Code Structure for Stateflow Charts

The examples in this topic show generated code for the CoDeSys Version 2.3 PLC IDE. Generated code for other IDE platforms looks different.

Stateflow Chart with Event Based Transitions

Generate code for the Stateflow chart `ControlModule` in the model `plcdemo_stateflow_controller`. Here is the chart:



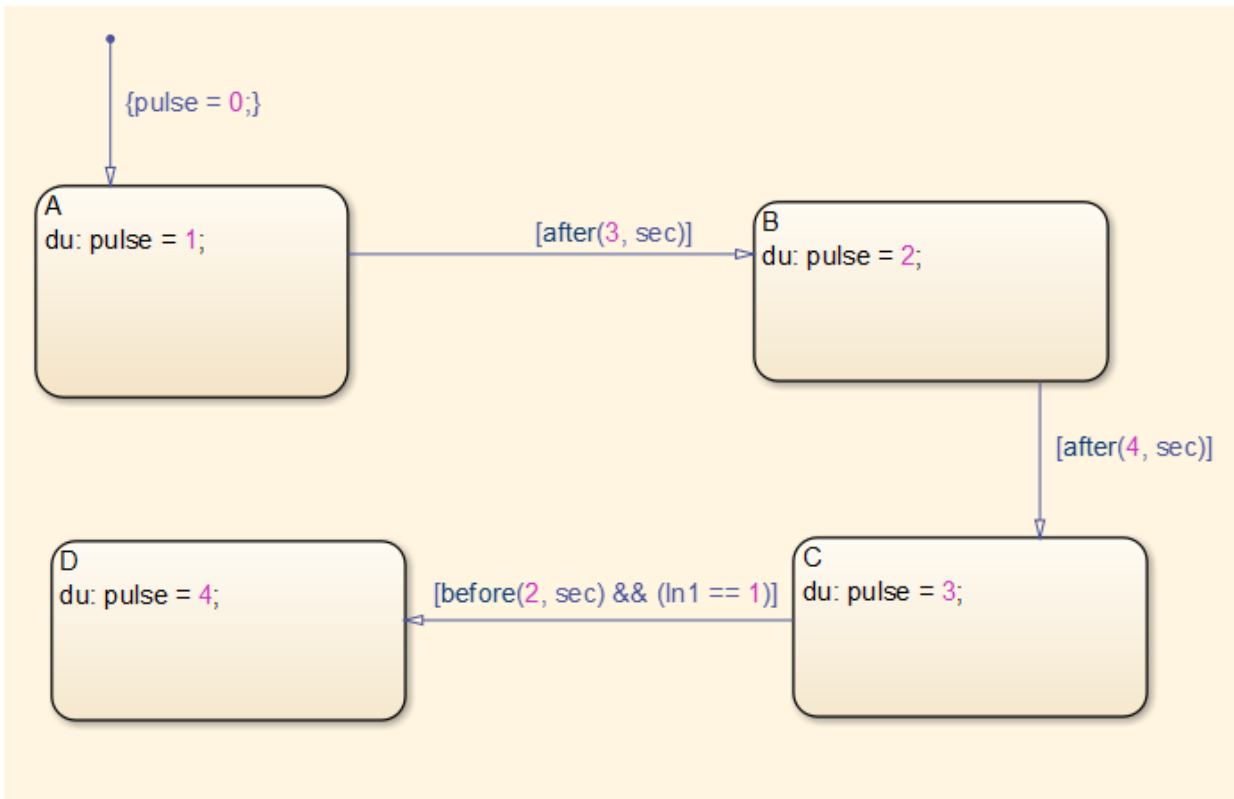
You can map the states and transitions in the chart to the generated code. For instance, the transition from the state `Aborting` to `Aborted` appears in the generated code as:

```
ControlModule_IN_Aborting:
    (* During 'Aborting': '<S1>:11' *)
    (* Graphical Function 'is_active': '<S1>:73' *)
    (* Transition: '<S1>:75' *)
    IF NOT drive_state.Active THEN
        (* Transition: '<S1>:31' *)
        is_c2_ControlModule := ControlModule_IN_Aborted;
        (* Outport: '<Root>/out' *)
        (* Entry 'Aborted': '<S1>:12' *)
        out := sABORTED;
        (* Graphical Function 'stop_drive': '<S1>:88' *)
        (* Transition: '<S1>:90' *)
        driveOut.Start := FALSE;
        driveOut.Stop := TRUE;
        driveOut.Reset := FALSE;
    END_IF;
```

For more information on the inlining of functions such as `start_drive`, `stop_drive`, and `reset_drive` in the generated code, see “Control Code Partitions for MATLAB Functions in Stateflow Charts” on page 6-9.

Stateflow Chart with Absolute Time Temporal Logic

Generate code for the Stateflow chart Temporal in the model `plcdemo_sf_abs_time`. Here is the chart:



You can map states and transitions in the chart to the generated code. For instance, the transition from state B to C appears as:

Temporal_IN_B:

```

(* During 'B': '<S1>:2' *)
temporalCounter_i1(timerAction := 2, maxTime := 4000);
IF temporalCounter_i1.done THEN
  (* Transition: '<S1>:8' *)
  is_c2_Temporal := Temporal_IN_C;
  temporalCounter_i1(timerAction := 1, maxTime := 0);
ELSE
  (* Output: '<Root>/pulse' *)
  pulse := 2.0;
END_IF;
  
```

The variable `temporalCounter_i1` is an instance of the function block `PLC_CODER_TIMER` defined as:

```
FUNCTION_BLOCK PLC_CODER_TIMER
VAR_INPUT
    timerAction: INT;
    maxTime: DINT;
END_VAR
VAR_OUTPUT
    done: BOOL;
END_VAR
VAR
    plcTimer: TON;
    plcTimerExpired: BOOL;
END_VAR
VAR_TEMP
END_VAR
CASE timerAction OF
    1:
        (* RESET *)
        plcTimer(IN:=FALSE, PT:=T#0s);
        plcTimerExpired := FALSE;
        done := FALSE;
    2:
        (* AFTER *)
        IF (NOT(plcTimerExpired)) THEN
            plcTimer(IN:=TRUE, PT:=DINT_TO_TIME(maxTime));
        END_IF;
        plcTimerExpired := plcTimer.Q;
        done := plcTimerExpired;
    3:
        (* BEFORE *)
        IF (NOT(plcTimerExpired)) THEN
            plcTimer(IN:=TRUE, PT:=DINT_TO_TIME(maxTime));
        END_IF;
        plcTimerExpired := plcTimer.Q;
        done := NOT(plcTimerExpired);
END_CASE;
END_FUNCTION_BLOCK
```


Generated Code Structure for MATLAB Function Block

This topic assumes that you have generated Structured Text code from a Simulink model. If you have not yet done so, see “Generate Structured Text from the Model Window” on page 1-14.

The example in this topic shows generated code for the CoDeSys Version 2.3 IDE. Generated code for other IDE platforms looks different.

- 1 Open the `plcdemo_eml_tankcontrol` model.
- 2 Right-click the TankControl block and select **PLC Code > Generate Code for Subsystem**.

The Simulink PLC Coder software generates Structured Text code and places it in `current_folder/plcsrc/plcdemo_eml_tankcontrol.exp`.

- 3 If you do not have the `plcdemo_eml_tankcontrol.exp` file open, open it in the MATLAB editor.

The following figure illustrates the mapping of the generated code to Structured Text components for a Simulink Subsystem block that contains a MATLAB Function block. The coder tries to perform inline optimization on the generated code for MATLAB local functions. If the coder determines that it is more efficient to leave the local function as is, it places the generated code in a Structured Text construct called **FUNCTION**.

- 4 Examine the generated Structured Text code.

```
function [InFlow, OutFlow, StirSpeed] = TankControl(C:
%%eml
% Check the vessel state
if(Height >= FullHeight)
    % Is it full ?
    vessel = PLCVesselState.FULL;
elseif(Height <= EmptyHeight)
    % Is it empty ?
    vessel = PLCVesselState.EMPTIED;
else
    vessel = PLCVesselState.NOT_FULL;
end
```

MATLAB code

Generated code
for MATLAB
subfunctions

```
FUNCTION_BLOCK TankControl
VAR_INPUT
    Command: PLCCommandState;
    Height: LREAL;
END_VAR
VAR_OUTPUT
    InFlow: LREAL;
    OutFlow: LREAL;
    StirSpeed: LREAL;
END_VAR
VAR
    vessel: PLCVesselState;
    EmptyValve: PLCValveState;
    FillValve: PLCValveState;
END_VAR
(* Check the vessel state *)
IF Height >= 10.0 THEN
    (* Is it full ? *)
    vessel := FULL;
ELSIF Height <= 2.0 THEN
    (* Is it empty ? *)
    vessel := EMPTIED;
ELSE
    vessel := NOT_FULL;
END_IF;
(* Process the command mode *)
CASE Command OF
    FILL:
        (* Fill Tank *)
        EmptyValve := SHUT;
        IF vessel = FULL THEN
            FillValve := SHUT;
        ELSE
            FillValve := OPEN;
        END_IF;
    HOLD:
        (* Hold Contents *)
        EmptyValve := SHUT;
        FillValve := SHUT;
    EMPTY:
        (* Empty Tank *)
        FillValve := SHUT;
        IF vessel = EMPTIED THEN
            EmptyValve := SHUT;
        ELSE
            EmptyValve := OPEN;
        END_IF;
    ELSE
        EmptyValve := SHUT;
        FillValve := SHUT;
    END_CASE;
(* compute inflow and outflow *)
```

Generated Code Structure for Multirate Models

This example assumes that you have generated Structured Text code from a Simulink model. If you have not yet done so, see “Generate Structured Text from the Model Window” on page 1-14.

The example in this topic shows generated code for the CoDeSys Version 2.3 IDE. Generated code for other IDE platforms looks different.

- 1 Open the `plcdemo_multirate` model. This model has two sample rates.
- 2 Right-click the `SimpleSubsystem` block and select **PLC Code > Generate Code for Subsystem**.

The Simulink PLC Coder software generates Structured Text code and places it in `current_folder/plcsrc/plcdemo_multirate.exp`.

- 3 If you do not have the `plcdemo_multirate.exp` file open, open it in the MATLAB editor and examine the Structured Text code.

The generated code contains a global time step counter variable:

```
VAR_GLOBAL
    plc_ts_counter1: DINT;
END_VAR
```

In this example, there are two rates, and the fast rate is twice as fast as the slow rate, so the time step counter counts to 1, then resets:

```
IF plc_ts_counter1 >= 1 THEN
    plc_ts_counter1 := 0;
ELSE
    plc_ts_counter1 := plc_ts_counter1 + 1;
END_IF;
```

The generated code for blocks running at slower rates executes conditionally based on the corresponding time step counter values. In this example, the generated code for `Gain1`, `Unit Delay1`, and `Sum1` executes every other time step, when `plc_ts_counter1 = 0`, because those blocks run at the slow rate. The generated code for `Gain`, `Unit Delay`, `Sum`, and `Sum2` executes every time step because those blocks run at the fast rate.

```
SS_STEP:
```

```
(* Gain: '<S1>/Gain' incorporates:
 * Inport: '<Root>/U1'
 * Sum: '<S1>/Sum'
 * UnitDelay: '<S1>/Unit Delay' *)
rtb_Gain := (U1 - UnitDelay_DSTATE) * 0.5;

(* Output: '<Root>/Y1' *)
Y1 := rtb_Gain;
IF plc_ts_counter1 = 0 THEN

    (* UnitDelay: '<S1>/Unit Delay1' *)
    UnitDelay1 := UnitDelay1_DSTATE;

    (* Gain: '<S1>/Gain1' incorporates:
     * Inport: '<Root>/U2'
     * Sum: '<S1>/Sum1' *)
    rtb_Gain1 := (U2 - UnitDelay1) * 0.5;

    (* Output: '<Root>/Y2' *)
    Y2 := rtb_Gain1;
END_IF;

(* Output: '<Root>/Y3' incorporates:
 * Sum: '<S1>/Sum2'
 * UnitDelay: '<S1>/Unit Delay' *)
Y3 := UnitDelay_DSTATE - UnitDelay1;

(* Update for UnitDelay: '<S1>/Unit Delay' *)
UnitDelay_DSTATE := rtb_Gain;

IF plc_ts_counter1 = 0 THEN

    (* Update for UnitDelay: '<S1>/Unit Delay1' *)
    UnitDelay1_DSTATE := rtb_Gain1;

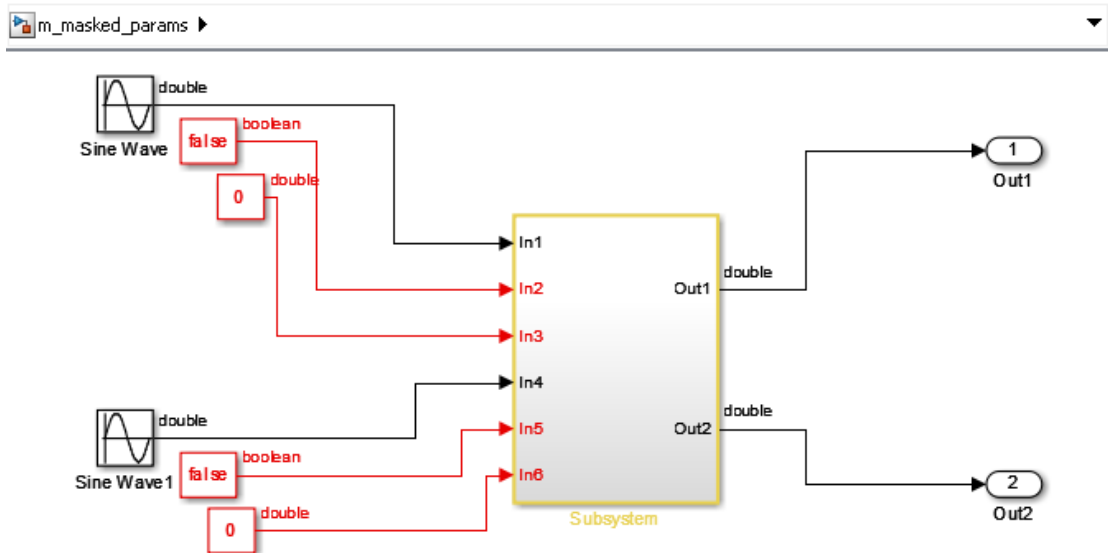
END_IF;
```

In general, for a subsystem with n different sample times, the generated code has $n-1$ time step counter variables, corresponding to the $n-1$ slower rates. Code generated from parts of the model running at the slower rates executes conditionally, based on the corresponding time step counter values.

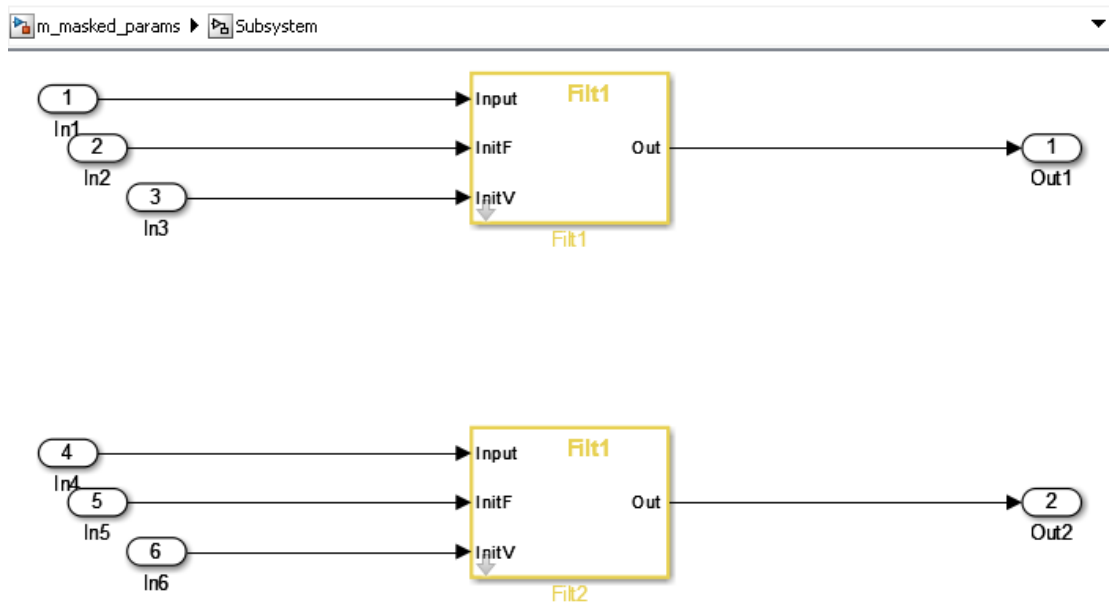
Generated Code Structure for Subsystem Mask Parameters

In the generated code for masked subsystems, the mask parameters map to function block inputs. The values you specify in the subsystem mask are assigned to these function block inputs in the generated code.

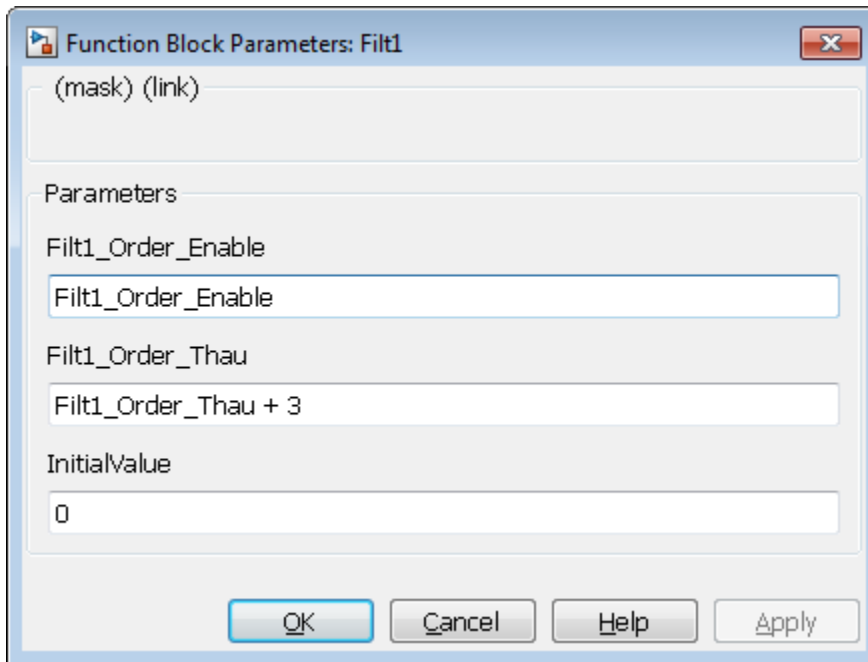
For example, the following subsystem, `Subsystem`, contains two instances, `Filt1` and `Filt2`, of the same masked subsystem.

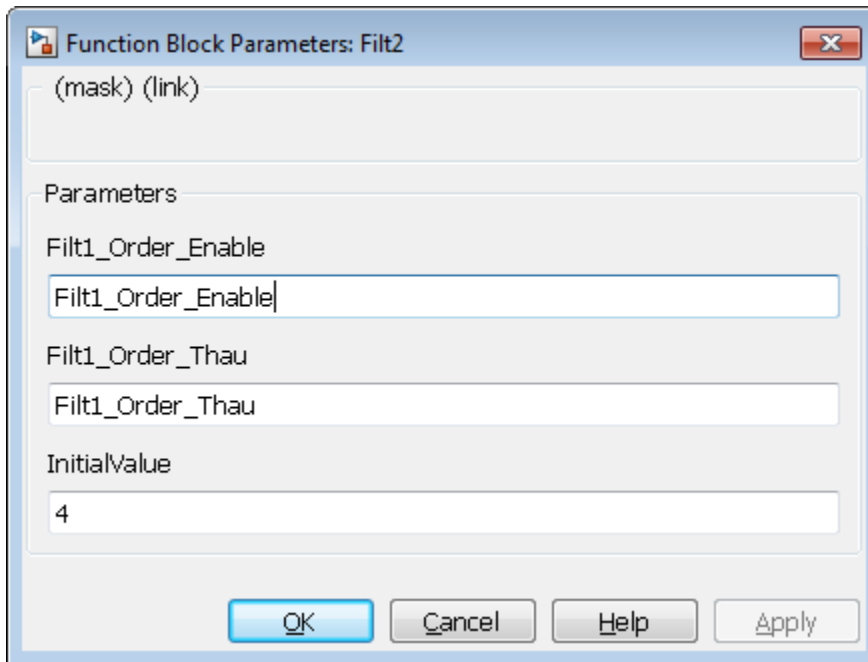


2 Mapping Simulink Semantics to Structured Text



The two subsystems, Filt1 and Filt2, have different values assigned to their mask parameters. In this example, Filt1_Order_Thau is a constant with a value of 5.





Therefore, for the `Filt1` subsystem, the `Filt1_Order_Thau` parameter has a value of 8, and for the `Filt2` subsystem, the `Filt1_Order_Thau` parameter has a value of 5.

The following generated code shows the `Filt1` function block inputs. The `rtp_Filt1_Order_Thau` input was generated for the `Filt1_Order_Thau` mask parameter.

```
FUNCTION_BLOCK Filt1
VAR_INPUT
    ssMethodType: SINT;
    InitV: LREAL;
    InitF: BOOL;
    Input: LREAL;
    rtp_Filt1_Order_Thau: LREAL;
    rtp_InitialValue: LREAL;
    rtp_Filt1_Order_Enable: BOOL;
END_VAR
```

The following generated code is from the `FUNCTION_BLOCK` Subsystem. The function block assigns a value of 8 to the `rtp_Filt1_Order_Thau` input for the `i0_Filt1`

instance, and assigns a value of 5 to the rtp_Filt1_Order_Thau input for the i1_Filt1 instance.

```
SS_INITIALIZE:
    (* InitializeConditions for Atomic SubSystem: '<S1>/Filt1' *)

    i0_Filt1(ssMethodType := SS_INITIALIZE, InitV := In3,
             InitF := In2, Input := In1,
             rtp_Filt1_Order_Thau := 8.0,
             rtp_InitialValue := 0.0,
             rtp_Filt1_Order_Enable := TRUE);
    Out1 := i0_Filt1.Out;

    (* End of InitializeConditions for SubSystem: '<S1>/Filt1' *)

    (* InitializeConditions for Atomic SubSystem: '<S1>/Filt2' *)
    i1_Filt1(ssMethodType := SS_INITIALIZE, InitV := In6,
             InitF := In5, Input := In4,
             rtp_Filt1_Order_Thau := 5.0,
             rtp_InitialValue := 4.0,
             rtp_Filt1_Order_Enable := TRUE);
    Out2 := i1_Filt1.Out;

    (* End of InitializeConditions for SubSystem: '<S1>/Filt2' *)
SS_STEP:
    (* Outputs for Atomic SubSystem: '<S1>/Filt1' *)

    i0_Filt1(ssMethodType := SS_OUTPUT, InitV := In3, InitF := In2,
             Input := In1, rtp_Filt1_Order_Thau := 8.0,
             rtp_InitialValue := 0.0,
             rtp_Filt1_Order_Enable := TRUE);
    Out1 := i0_Filt1.Out;

    (* End of Outputs for SubSystem: '<S1>/Filt1' *)

    (* Outputs for Atomic SubSystem: '<S1>/Filt2' *)
    i1_Filt1(ssMethodType := SS_OUTPUT, InitV := In6, InitF := In5,
             Input := In4, rtp_Filt1_Order_Thau := 5.0,
             rtp_InitialValue := 4.0,
             rtp_Filt1_Order_Enable := TRUE);
    Out2 := i1_Filt1.Out;

    (* End of Outputs for SubSystem: '<S1>/Filt2' *)
```

Global Tunable Parameter Initialization for PC WORX

For PC WORX, the coder generates an initialization function, `PLC_INIT_PARAMETERS`, to initialize global tunable parameters that are arrays and structures. This initialization function is called in the top-level initialization method.

For example, suppose your model has a global array variable, `ParArrayXLUT`:

```
ParArrayXLUT=[0,2,6,10];
```

In the generated code, the `PLC_INIT_PARAMETERS` function contains the following code to initialize `ParArrayXLUT`:

```
(* parameter initialization function starts *)<br/>  
ParArrayXLUT[0] := LREAL#0.0;<br/>  
ParArrayXLUT[1] := LREAL#2.0;<br/>  
ParArrayXLUT[2] := LREAL#6.0;<br/>  
ParArrayXLUT[3] := LREAL#10.0;<br/>  
(* parameter initialization function ends *)<br/></div></html>
```

The `PLC_INIT_PARAMETERS` function is renamed `iO_PLC_INIT_PARAMETERS`, and called in the top-level initialization method:

```
CASE SINT_TO_INT(ssMethodType) OF<br/>  
0: <br/>  
    iO_PLC_INIT_PARAMETERS();<br/>
```

Generating Test Bench Code

- “How Test Bench Verification Works” on page 3-2
- “Integrate Generated Code into Custom Code” on page 3-3
- “Import and Verify Structured Text Code” on page 3-4
- “Verify Generated Code with Multiple Test Benches” on page 3-7

How Test Bench Verification Works

The Simulink PLC Coder software simulates your model and automatically captures the input and output signals for the subsystem that contains your algorithm. This set of input and output signal data is the test bench data. The coder also automatically generates a test bench, or test harness, using the test bench data.

The test bench runs the generated code to verify that the output is functionally and numerically equivalent to the output from the execution of a Simulink model. The following table shows how the test bench compares the expected and actual data values.

Data type	Comparison	Error tolerance
integer	absolute	0
boolean	absolute	0
single	relative	0.0001
double	relative	0.00001

The relative tolerance comparison for single or double data types uses the following logic:

```
IF ABS(actual_value - expected_value) > (ERROR_TOLERANCE * expected_value) THEN
    testVerify := FALSE;
END_IF;
```

To verify the generated code using the test bench, import the generated Structured Text and the test bench data into your target IDE. You can import test bench code:

- Manually, as described in .
- Automatically, including running the test bench, as described in “Import and Verify Structured Text Code” on page 3-4

Depending on the target IDE platform, the Simulink PLC Coder software generates code into one or more files. See “Files Generated with Simulink PLC Coder” on page 1-20 for list of the target IDE platforms and the possible generated files.

Integrate Generated Code into Custom Code

For the top-level subsystem that has internal state, the generated `FUNCTION_BLOCK` code has `ssMethodType`. `ssMethodType` is a special input argument that the coder adds to the input variables section of the `FUNCTION_BLOCK` section during code generation. `ssMethodType` enables you to execute code for Simulink Subsystem block methods such as initialization and computation steps. The generated code executes the associated CASE statement based on the value passed in for this argument.

To use `ssMethodType` with a `FUNCTION_BLOCK` for your model, in the generated code, the top-level subsystem function block prototype has one of the following formats:

Has Internal State	<code>ssMethodType</code> Contains...
Yes	The generated function block for the block will have an extra first parameter <code>ssMethodType</code> of integer type. This extra parameter is in addition to the function block I/O parameters mapped from Simulink block I/O ports. To use the function block, first initialize the block by calling the function block with <code>ssMethodType</code> set to integer constant <code>SS_INITIALIZE</code> . If the IDE does not support symbolic constants, set <code>ssMethodType</code> to integer value 0. For each follow-up invocation, call the function block with <code>ssMethodType</code> set to constant <code>SS_STEP</code> . If the IDE does not support symbolic constants, set <code>ssMethodType</code> to integer value 1. These settings cause the function block to initialize or compute and return output for each time step.
No	The function block interface only has parameters mapped from Simulink block I/O ports. There is no <code>ssMethodType</code> parameter. To use the function block in this case, call the function block with I/O arguments.

For non top-level subsystems, in the generated code, the subsystem function block prototype has one of the following formats:

Has Internal State	<code>ssMethodType</code> Contains...
Yes	The function block interface has the <code>ssMethodType</code> parameter. The generated code might have <code>SS_INITIALIZE</code> , <code>SS_OUTPUT</code> , or other <code>ssMethodType</code> constants to implement Simulink semantics.
No	The function block interface only has parameters mapped from Simulink block I/O ports. There is no <code>ssMethodType</code> parameter.

Import and Verify Structured Text Code

After you generate code and test benches for your subsystem, you can import them to your target IDE. Using the test bench data, you can verify that the results from your generated code match your simulation results.

If you want to only import the generated code, see “Generate and Automatically Import Structured Text Code” on page 1-24.

Generate, Import, and Verify Structured Text

If you are working with the KW-Software MULTIPROG 5.0 or Phoenix Contact PC WORX 6.0 IDE, see “Import and Verify Structured Text to KW-Software MULTIPROG 5.0 and Phoenix Contact PC WORX 6.0 IDEs” on page 3-5.

Otherwise, to generate, import and verify structured text code:

- 1 Specify that test bench code must be generated for the subsystem.
 - a Right-click your subsystem and select **PLC Code > Options**.
 - b Select “Generate testbench for subsystem” on page 12-12.

If you do not specify that test bench code must be generated, when you automatically verify the generated code, you see the error `Testbench not selected`.

- 2 You can generate the code and testbench, and manually import them to your target IDE. For information on how to import generated code, see the user manual for your target IDE.

Alternatively, after code generation, import and verify the generated code automatically. Right-click the subsystem and select **PLC Code > Generate, Import, and Verify Code for Subsystem**. The software:

- a Generates the code and test bench.
- b Starts the target IDE.
- c Creates a new project.
- d Imports the generated code and test bench to the new project in the target IDE.
- e Runs the generated code on the target IDE to verify it.

Import and Verify Structured Text to KW-Software MULTIPROG 5.0 and Phoenix Contact PC WORX 6.0 IDEs

Before you can automatically import generated code to this IDE, create an **Empty** template. You must have already set your target IDE to KW-Software MULTIPROG 5.0 or Phoenix Contact PC WORX 6.0.

- 1 Start the KW-Software MULTIPROG 5.0 or Phoenix Contact PC WORX 6.0 IDE.
- 2 Select **File > Delete Template**. Delete any template named **Empty**, and click **OK** when done.
- 3 Select **File > New Project**, select **Project Wizard**, then click **OK**.
 - a In the **Project Name** field, type **Empty**,
 - b In the **Project Path** field, type or select a path to which you have write privileges.
 - c Click **Next**.
 - d In the remaining wizard pages, click **Next** to leave the default selections. At the end of the wizard, click **Finish**.

The IDE is updated with the new **Empty** project tree.

- 4 In the project, delete everything under the following nodes:
 - Logical POU
 - Physical Hardware
- 5 Verify that the project tree has only top-level nodes for **Libraries**, **Data Types**, **Logical POU**, and **Physical Hardware**. There must not be any subtree nodes.
- 6 In the IDE, select **File > Save As Template**.
- 7 In **Template Name**, type **Empty**.
- 8 Click **OK**.
- 9 Close the IDE interface.

Open your model, right-click the **Subsystem** block, and select one of the following:

- **PLC Code > Generate and Import Code for Subsystem**
- **PLC Code > Generate, Import, and Verify Code for Subsystem**

If you automatically generate, import, and verify code, the software:

- 1 Generates the code and test bench.
- 2 Starts the target IDE.
- 3 Creates a new project.
- 4 Imports the generated code and test bench to the new project in the target IDE.
- 5 Runs the generated code on the target IDE to verify it.

Verify Generated Code with Multiple Test Benches

You can generate code with multiple test benches from your subsystem. For the generated code to have multiple test benches, the input to your subsystem must consist of multiple signal groups.

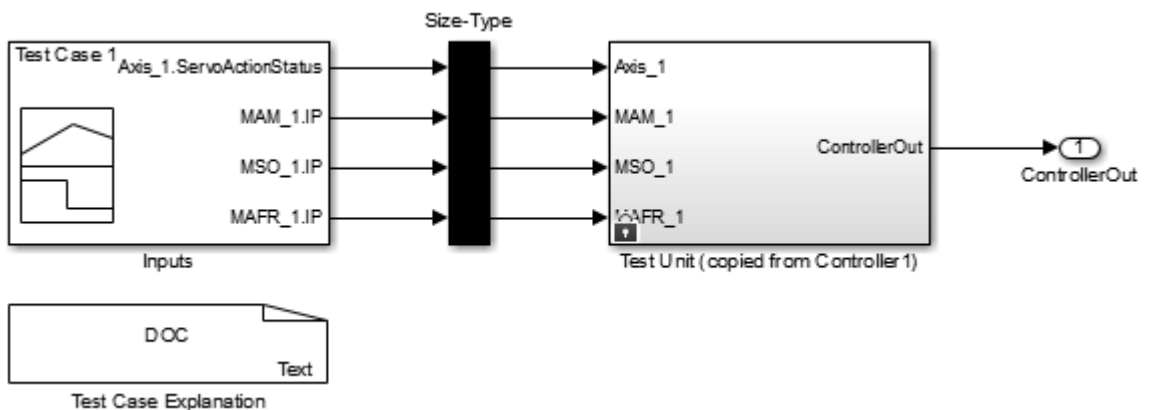
To generate multiple test benches for your subsystem:

- 1 Provide multiple signal groups as inputs by using a **Signal Builder** block with multiple signal groups.

Instead of manually entering a Signal Builder block and creating multiple signal groups, you can use Simulink Design Verifier™ to create a test harness model from the subsystem. In the test harness model, a Signal Builder block with one or more signal groups provides input to the subsystem. You can use this Signal Builder block to provide inputs to your subsystem. However, if your model is complex, Simulink Design Verifier can create large number of signal groups. See “Troubleshooting: Test Data Exceeds Target Data Size” on page 3-9.

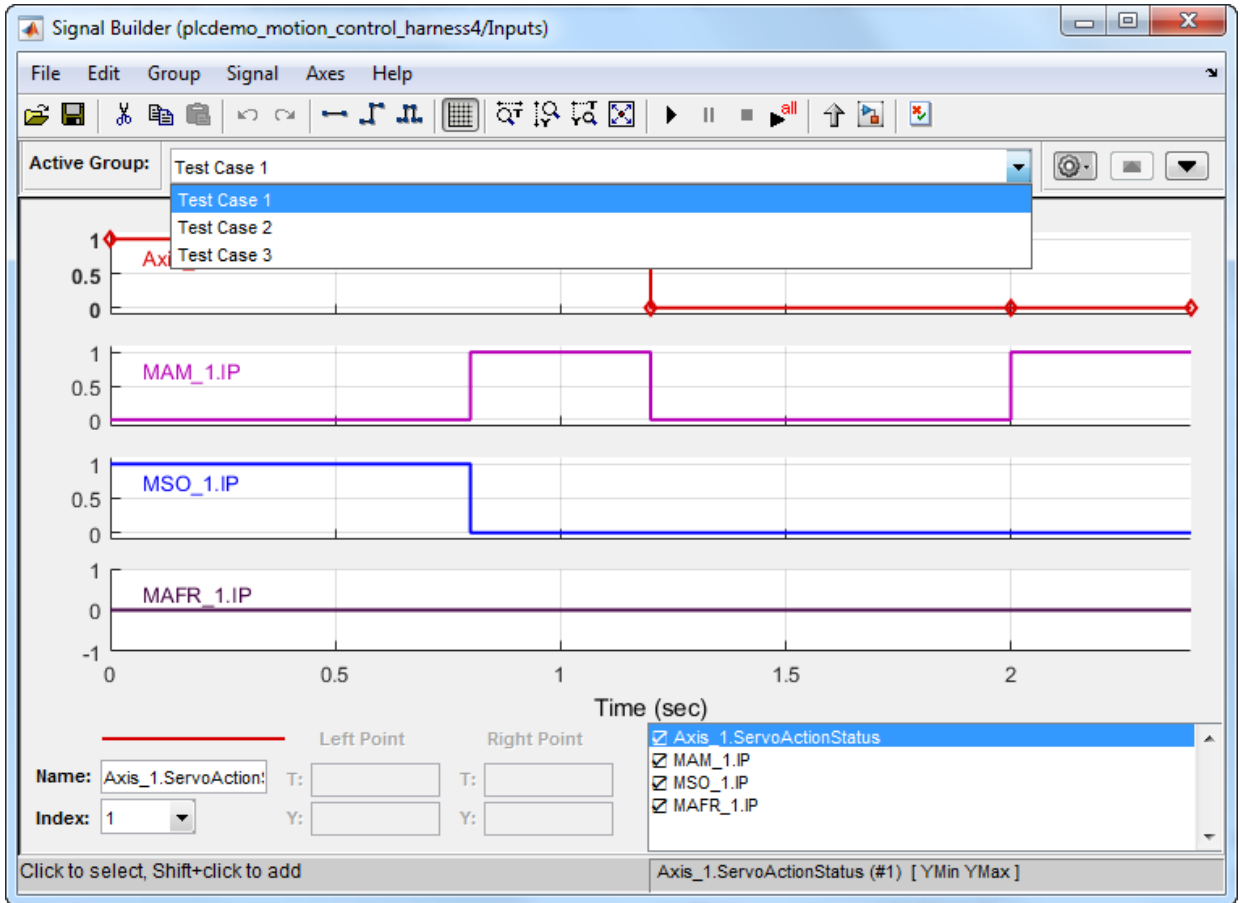
To create your Signal Builder block with Simulink Design Verifier:

- a Right-click the subsystem and select **Design Verifier > Generate Tests for Subsystem**.
- b In the Simulink Design Verifier Results Summary window, select **Create harness model**.



- c Open the Inputs block in the test harness model. The Inputs block is a Signal Builder block that can have one or more signal groups.

In the Signal Builder window, make sure that more than one signal group is available in the **Active Group** drop-down list.



- d Copy the Signal Builder block from the test harness model and use this block to provide inputs to your original subsystem.
- 2 Specify that test benches must be generated for the subsystem.
- a Right-click your subsystem and select **PLC Code > Options**.

- b** Select “Generate testbench for subsystem” on page 12-12.
- 3** Right-click the subsystem and select **PLC Code > Generate, Import and Verify Code for Subsystem**.

In your target IDE, you can see multiple test benches. Each test bench corresponds to a signal group.

Troubleshooting: Test Data Exceeds Target Data Size

If the test data from the multiple signal groups exceeds the maximum data size on your target, you can encounter compilation errors. If you encounter compilation errors when generating multiple test benches, try one of the following:

- Reduce the number of signal groups in the Signal Builder block and regenerate the test benches.
- Increase the simulation step size for the subsystem.

Code Generation Reports

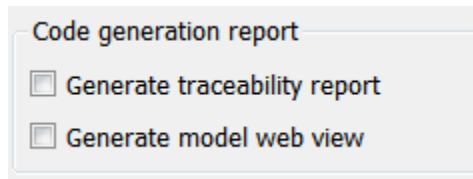
- “Information in Code Generation Reports” on page 4-2
- “Create and Use Code Generation Reports” on page 4-4
- “View Requirements Links from Generated Code” on page 4-16
- “Working with the Static Code Metrics Report” on page 4-17

Information in Code Generation Reports

The coder creates and displays a Traceability Report file when you select one or more of these options:

GUI Option	Command-Line Property	Description
Generate traceability report	PLC_GenerateReport	Specify whether to create code generation report.
Generate model Web view	PLC_GenerateWebview	Include the model Web view in the code generation report to navigate between the code and model within the same window. You can share your model and generated code outside of the MATLAB environment.

In the Configuration Parameters dialog box, in the **Report** panel, you see these options.



Note: You must have a Simulink Report Generator™ license to generate traceability reports.

The coder provides the traceability report to help you navigate more easily between the generated code and your source model. When you enable code generation report, the coder creates and displays an HTML code generation report. You can generate reports from the Configuration Parameters dialog box or the command line. A typical traceability report looks something like this figure:

Code Generation Report

system/plcdemo_simple_subsystem_codegen_rpt.html?useExternalBrowser=false&loaded=true Find: Match Case

Back Forward Search...

Traceability Report

[Code Metrics Report](#)

Generated Files

[plcdemo_simple_subsystem.exp](#)

Traceability Report for plcdemo_simple_subsystem

Table of Contents

- [Eliminated / Virtual Blocks](#)
- [Traceable Simulink Blocks / Stateflow Objects / MATLAB Functions](#)
 - [plcdemo_simple_subsystem/SimpleSubsystem](#)

Eliminated / Virtual Blocks

Block Name	Comment
<S1>/U	Inport
<S1>/Y	Outport

Traceable Simulink Blocks / Stateflow Objects / MATLAB Functions

Subsystem: [plcdemo_simple_subsystem/SimpleSubsystem](#)

Object Name	Code Location
<S1>/Gain	plcdemo_simple_subsystem.exp:43
<S1>/Sum	plcdemo_simple_subsystem.exp:45
<S1>/Unit Delay	plcdemo_simple_subsystem.exp:39, 46, 52

OK Help

Create and Use Code Generation Reports

In this section...

“Generate a Traceability Report from Configuration Parameters” on page 4-4

“Keep the Report Current” on page 4-6

“Trace from Code to Model” on page 4-7

“Trace from Model to Code” on page 4-8

“Model Web View in Code Generation Report” on page 4-10

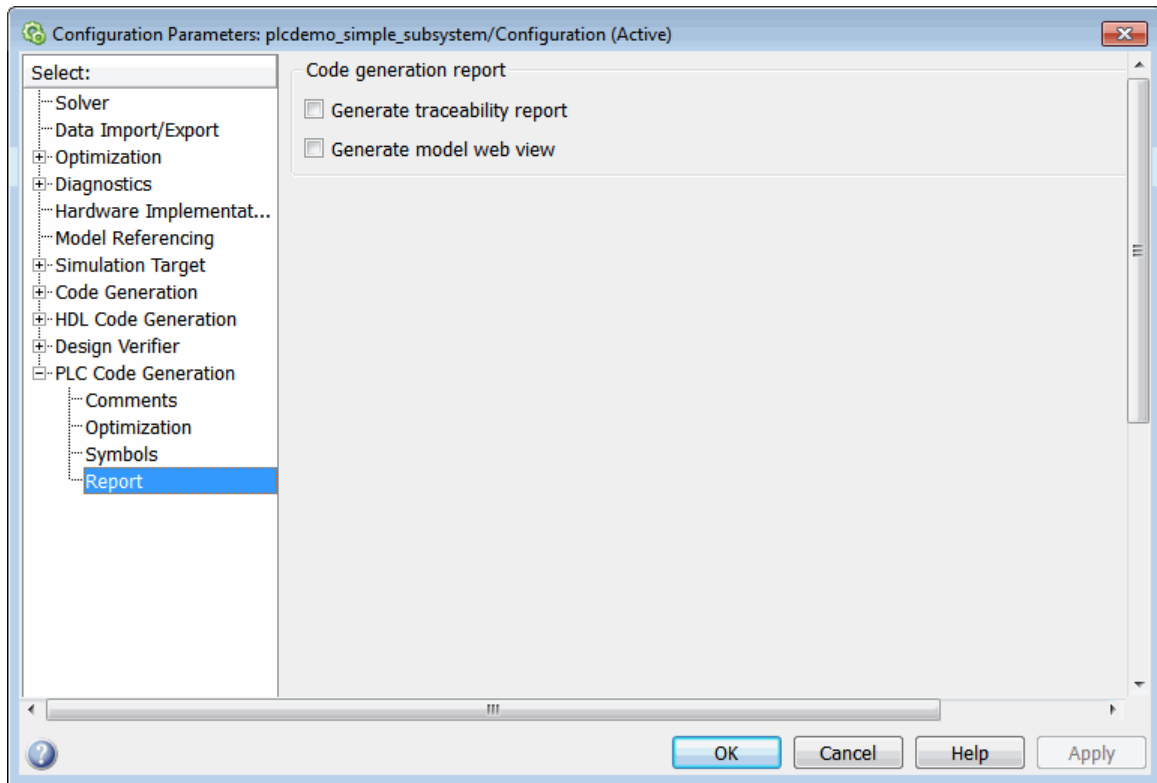
“Generate a Static Code Metrics Report” on page 4-13

“Generate a Traceability Report from the Command Line” on page 4-14

Generate a Traceability Report from Configuration Parameters

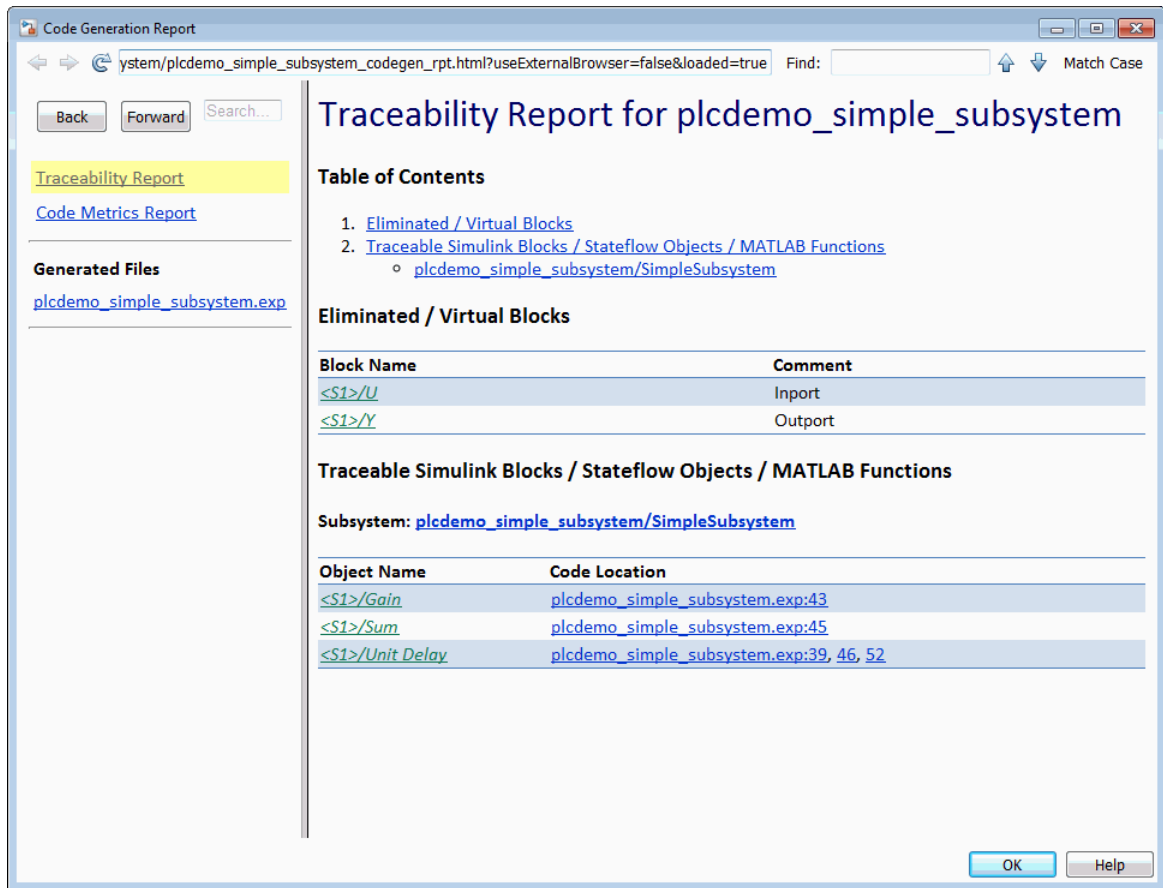
To generate a Simulink PLC Coder code generation report from the Configuration Parameters dialog box:

- 1 Verify that the model is open.
- 2 Open the Configuration Parameters dialog box and navigate to the **PLC Code Generation** pane.
- 3 To enable report generation, select **Report > Generate traceability report**.
- 4 Click **Apply**.



- 5 Click **PLC Code Generation** > **Generate code** to initiate code and report generation. The coder generates HTML report files as part of the code generation process.

The HTML report appears:



For more information, see:

- “Trace from Code to Model” on page 4-7
- “Trace from Model to Code” on page 4-8

Keep the Report Current

If you generate a code generation report for a model, and subsequently make changes to the model, the report might become invalid. To keep your code generation report current,

after modifying the source model, regenerate code and the report. If you close and then reopen a model, regenerate the report.

Trace from Code to Model

You must have already generated code with a traceability report. If not, see “Generate a Traceability Report from Configuration Parameters” on page 4-4 or “Generate a Traceability Report from the Command Line” on page 4-14.

To trace generated code to your model:

- 1 In the generated code HTML report display, look for `<S1>/Gain`.

```

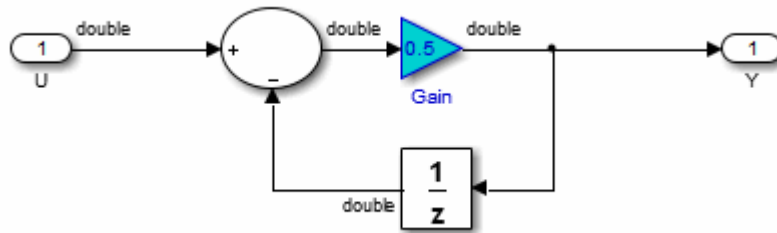
32  END_VAR
33  VAR_TEMP
34      rtb_Gain: LREAL;
35  END_VAR
36  CASE ssMethodType OF
37      SS_INITIALIZE:
38
39          (* InitializeConditions for UnitDelay: '<S1>/Unit Delay' *)
40          UnitDelay_DSTATE := 0.0;
41      SS_STEP:
42
43          (* Gain: '<S1>/Gain' incorporates:
44             * Inport: '<Root>/U'
45             * Sum: '<S1>/Sum'
46             * UnitDelay: '<S1>/Unit Delay' *)
47          rtb_Gain := (U - UnitDelay_DSTATE) * 0.5;
48
49          (* Output: '<Root>/Y' *)
50          Y := rtb_Gain;
51
52          (* Update for UnitDelay: '<S1>/Unit Delay' *)
53          UnitDelay_DSTATE := rtb_Gain;
54  END_CASE;
55  END_FUNCTION_BLOCK

```

S1/Gain

- 2 In the HTML report window, click a link to highlight the corresponding source block. For example, in the HTML report shown in the previous figure, you click the

hyperlink for the Gain block (highlighted) to view that block in the model. Clicking the hyperlink locates and displays the corresponding block in the model editor window. You can use the same method to trace other block from the HTML report.



Trace from Model to Code

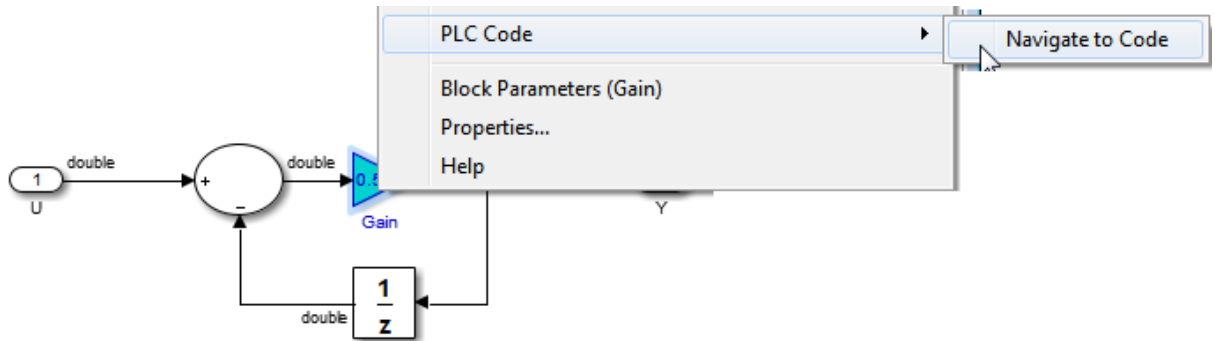
You can select a component at any level of the model with model-to-code traceability. You can also view the code references to that component in the HTML code generation report. You can select the following objects for tracing:

- Subsystem
- Simulink block
- MATLAB Function block
- Truth Table block
- State Transition Table block
- Stateflow chart, or the following elements of a Stateflow chart:
 - State
 - Transition
 - Graphical function
 - MATLAB function
 - Truth table function

You must have already generated code with a traceability report to trace a model component to the generated code. If not, see “Generate a Traceability Report from Configuration Parameters” on page 4-4 or “Generate a Traceability Report from the Command Line” on page 4-14.

To trace a model component to the generated code:

- 1 In the model window, right-click the component and select **PLC Code > Navigate to Code**.



- 2 Selecting **Navigate to Code** activates the HTML code generation report. The following figure shows the result of tracing the Gain block within the subsystem.

```

40         UnitDelay_DSTATE := 0.0;
41     SS_STEP:
42
43     (* Gain: '<S1>/Gain' incorporates:
44        * Inport: '<Root>/U'
45        * Sum: '<S1>/Sum'
46        * UnitDelay: '<S1>/Unit Delay' *)
47     rtb_Gain := (U - UnitDelay_DSTATE) * 0.5;
48

```

In the report, the highlighted tag S1/Gain indicates the beginning of the generated code for the block. You can use the same method to trace from other Simulink, Stateflow and MATLAB objects to the generated traceability report.

Model Web View in Code Generation Report

Model Web Views

To review and analyze the generated code, it is helpful to navigate between the code and model. You can include a Web view of the model within the HTML code generation report. You can then share your model and generated code outside of the MATLAB environment. You need a Simulink Report Generator license to include a Web view of the model in the code generation report.

Browser Requirements for Web Views

Web views require a Web browser that supports Scalable Vector Graphics (SVG). Web views use SVG to render and navigate models.

You can use the following Web browsers:

- Mozilla® Firefox® Version 1.5 or later, which has native support for SVG. To download the Firefox browser, go to www.mozilla.com/.
- Apple Safari Web browser
- The Microsoft® Internet Explorer® Web browser with the Adobe® SVG Viewer plug-in. To download the Adobe SVG Viewer plug-in, go to www.adobe.com/svg/.

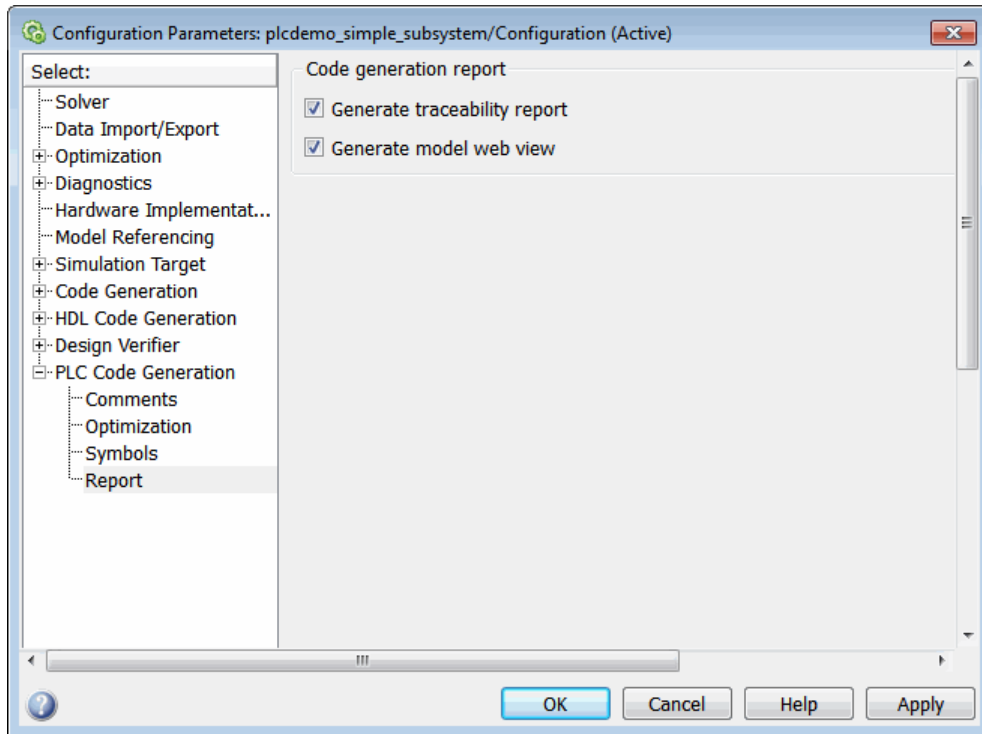
Note: Web views do not currently support Microsoft Internet Explorer 9.

Generate HTML Code Generation Report with Model Web View

This example shows how to create an HTML code generation report which includes a Web view of the model diagram.

- 1 Open the `plcdemo_simple_subsystem` model.
- 2 Open the Configuration Parameters dialog box and navigate to the Code Generation pane.
- 3 To enable report generation, select **Report > Create report code generation report**.
- 4 To enable model web view, select **Report > Generate model Web view**.
- 5 Click **Apply**.

The dialog box looks something like this:



- 6 Click **PLC Code Generation** > **Generate code** to initiate code and report generation. The code generation report for the top model opens in a MATLAB Web browser.

The screenshot displays a web browser window titled "Code Generation Report" showing a "Traceability Report for plcdemo_simple_subsystem". The left navigation pane contains links for "Traceability Report" (highlighted), "Code Metrics Report", and "Generated Files" (listing "plcdemo_simple_subsystem.exp"). The main content area features a "Table of Contents" with two items: "1. [Eliminated / Virtual Blocks](#)" and "2. [Traceable Simulink Blocks / Stateflow Objects / MATLAB Functions](#)" (with a sub-link "o [plcdemo_simple_subsystem/SimpleSubsystem](#)"). Below this is the "Eliminated / Virtual Blocks" section, which contains a table:

Block Name	Comment
<S1>/U	Inport

At the bottom of the report, a Simulink block diagram for "SimpleSubsystem" is shown. It includes an input block "U", a summing junction with a plus sign, a gain block "0.5", a feedback block "1/z", and an output block "Y".

- 7 In the left navigation pane, select a source code file. The corresponding traceable source code is displayed in the right pane and includes hyperlinks.
- 8 Click a link in the code. The model Web view displays and highlights the corresponding block in the model.
- 9 To go back to the code generation report for the top model, at the top of the left navigation pane, click the Back button until the top model's report is displayed.

For more information about navigating between the generated code and the model diagram, see:

- “Trace from Code to Model” on page 4-7

- “Trace from Model to Code” on page 4-8

Model Web View Limitations

When you are using the model Web view, the HTML code generation report includes the following limitations :

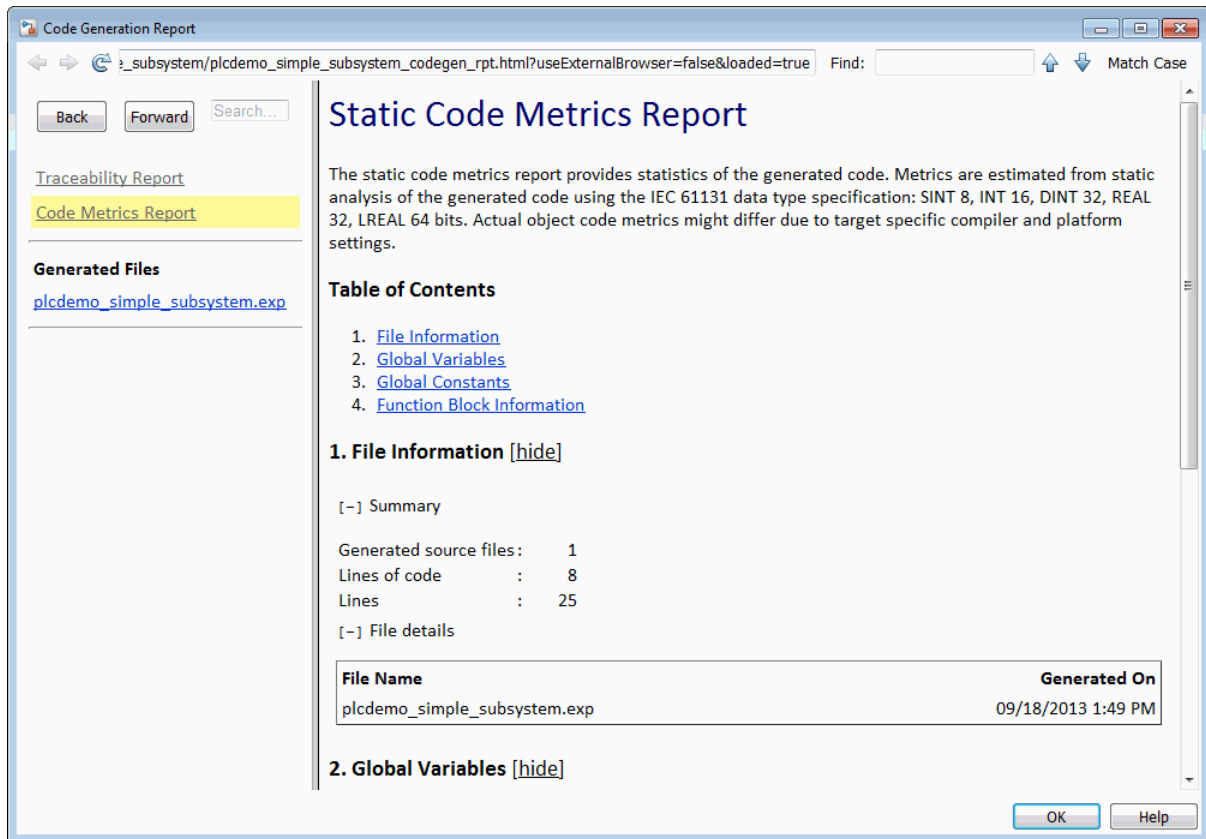
- Code is not generated for virtual blocks. In the model Web view, if you click a virtual block, the code generation report clears highlighting in the source code files.
- Stateflow truth tables, events, and links to library charts are not supported in the model Web view.
- Searching in the code generation report does not find or highlight text in the model Web view.
- In a subsystem build, the traceability hyperlinks of the root-level inports and outports blocks are disabled.
- If you navigate from the actual model diagram (not the model Web view in the report), to the source code in the HTML code generation report, the model Web view is disabled and not visible. To enable the model Web view, open the report again, see “Open Code Generation Report”.

Generate a Static Code Metrics Report

The PLC Coder Static Code Metrics report provides statistics of the generated code. The report is generated when you select **Generate Traceability Report** in the Configuration Parameters dialog box. You can use the Static Code Metrics Report to evaluate the generated PLC code before implementation in your IDE. For more information, see “Working with the Static Code Metrics Report” on page 4-17.

The procedure is the same as generating the Traceability Report.

- 1 Open the Configuration Parameters dialog box and navigate to the **PLC Code Generation** pane.
- 2 To enable report generation, select **Report > Generate traceability report**.
- 3 Click **Apply**.
- 4 Click **PLC Code Generation > Generate code** to initiate code and report generation. The coder generates HTML report files as part of the code generation process. The Code Metrics Report is shown on the left navigation pane.



Generate a Traceability Report from the Command Line

To generate a Simulink PLC Coder code generation report from the command line code for the subsystem, `plcdemo_simple_subsystem/SimpleSubsystem`:

- 1 Open a Simulink PLC Coder model, for example:


```
open_system('plcdemo_simple_subsystem');
```
- 2 Enable the code generation parameter `PLC_GenerateReport`. To view the output in the model Web view, also enable `PLC_GenerateWebview`:

```
set_param('plcdemo_simple_subsystem', 'PLC_GenerateReport', 'on');
set_param('plcdemo_simple_subsystem', 'PLC_GenerateWebview', 'on');
```

3 Generate the code.

```
generatedfiles = plcgeneratecode('plcdemo_simple_subsystem/SimpleSubsystem')
```

A traceability report is displayed. In your model, a **View diagnostics** hyperlink appears at the bottom of the model window. Click this hyperlink to open the Diagnostic Viewer window.

If the model Web view is also enabled, that view is displayed.

View Requirements Links from Generated Code

For requirements reviews, design reviews, traceability analysis, or project documentation, you can create links to requirements documents from your model with the Simulink Verification and Validation™ software. If your model has links to requirements documents, you can also view the links from the generated code.

Note: The requirement links must be associated with a model object. If requirements links are associated with the code in a MATLAB Function block, they do not appear in generated code comments.

To view requirements from generated code:

- 1 From your model, create links to requirements documents.

See “Requirements Traceability”.

- 2 For the subsystem for which you want to generate code, specify the following configuration parameters.

Option	Purpose
“Include comments” on page 12-14	Model information must appear in code comments.
“Generate traceability report” on page 12-31	After code is generated, a Code Generation Report must be produced.

- 3 Generate code.

The Code Generation Report opens. The links to requirements documents appear in generated code comments. When you view the code in the Code Generation Report, you can open the links from the comments.

Working with the Static Code Metrics Report

In this section...
“Workflow for Static Code Metrics Report” on page 4-17
“Report Contents” on page 4-18
“Function Block Information” on page 4-19

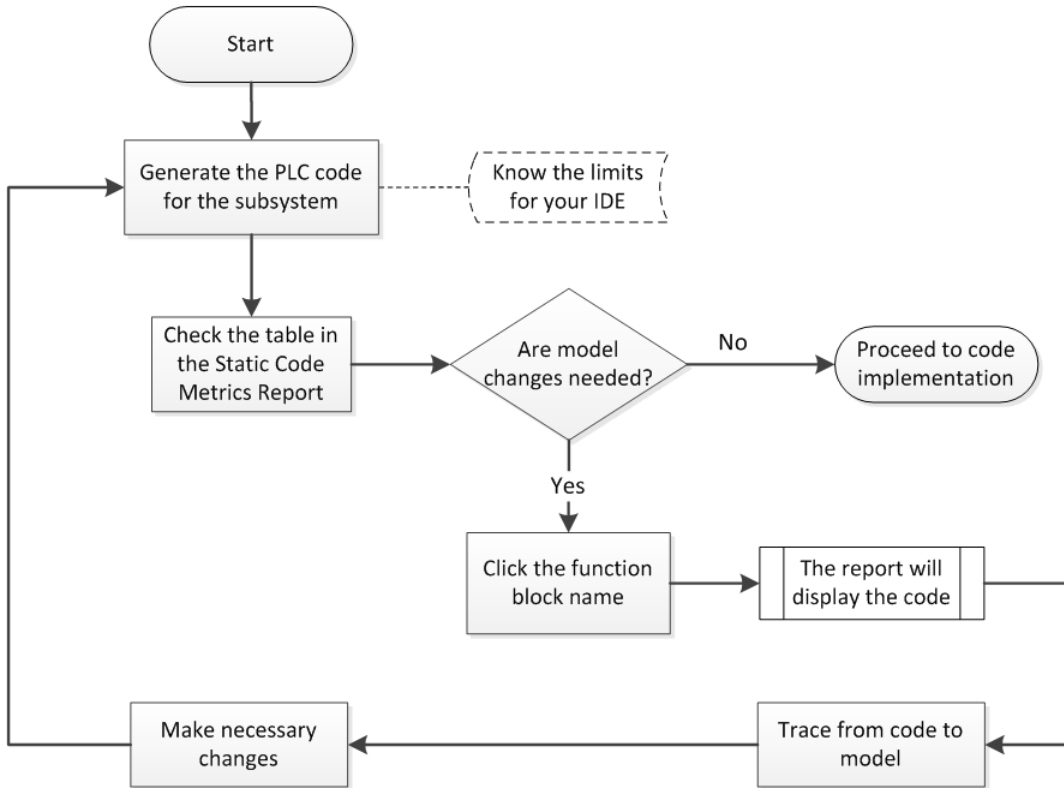
You can use the information in the Static Code Metrics Report to assess the generated code and make model changes before code implementation in your target IDE.

Before starting, you should familiarize yourself with potential code limitations of your IDE. For example, some IDE's might have limits on the number of variables or lines of code in a function block.

For detailed instructions on generating the report, see “Generate a Static Code Metrics Report” on page 4-13.

Workflow for Static Code Metrics Report

This is the basic workflow for using the Static Code Metrics Report with your model.



Report Contents

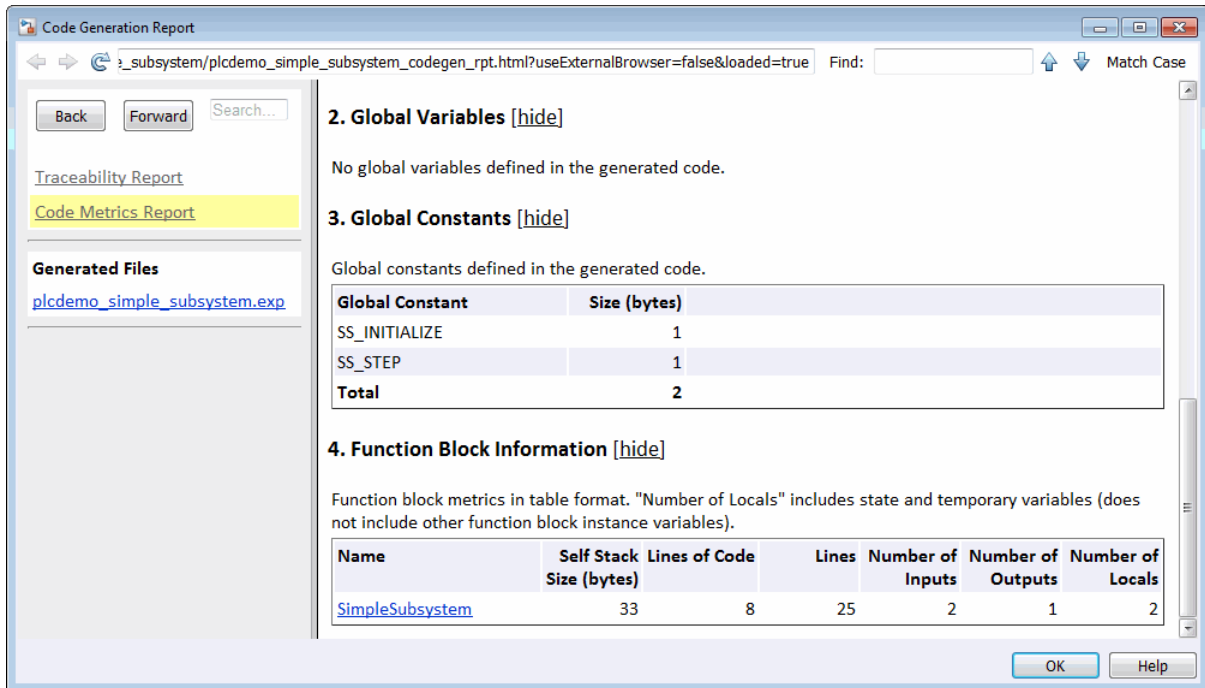
The Static Code Metrics Report is divided into the following sections:

- **File Information:** Reports high-level information about generated files, such as lines and lines of code.
- **Global Variables:** Reports information about global variables defined in the generated code.
- **Global Constants:** Reports information about global constants defined in the generated code.

- **Function Block Information:** Reports a table of metrics for each function block generated from your model.

Function Block Information

You can use the information in the Function Block Information table to assess the generated code prior to implementation in your IDE. The leftmost column of the table lists function blocks with hyperlinks. Clicking on a function block name will lead you to the function block location in the generated code. From here, you can trace from the code to the model. For more information, see “Trace from Code to Model” on page 4-7.



The screenshot shows a web browser window titled "Code Generation Report". The address bar contains the URL: `..._subsystem/plcdemo_simple_subsystem_codegen_rpt.html?useExternalBrowser=false&loaded=true`. The page has a navigation sidebar on the left with buttons for "Back", "Forward", and "Search...", and links for "Traceability Report" and "Code Metrics Report" (which is highlighted). Below the sidebar, there is a "Generated Files" section with a link to `plcdemo_simple_subsystem.exp`.

The main content area displays the following sections:

- 2. Global Variables [hide]**: No global variables defined in the generated code.
- 3. Global Constants [hide]**: Global constants defined in the generated code.

Global Constant	Size (bytes)
SS_INITIALIZE	1
SS_STEP	1
Total	2
- 4. Function Block Information [hide]**: Function block metrics in table format. "Number of Locals" includes state and temporary variables (does not include other function block instance variables).

Name	Self Stack Size (bytes)	Lines of Code	Lines	Number of Inputs	Number of Outputs	Number of Locals
SimpleSubsystem	33	8	25	2	1	2

At the bottom right of the window, there are "OK" and "Help" buttons.

Working with Tunable Parameters in the Simulink PLC Coder Environment

- “Block Parameters in Generated Code” on page 5-2
- “Control Appearance of Block Parameters in Generated Code” on page 5-5

Block Parameters in Generated Code

Block parameters appear in the generated code as variables. You can choose how the variables appear in the generated code. For instance, you can control the following variable characteristics:

- Whether the variables are inlined in generated code.
- Whether the variables are local to a function block, global, or not defined.

To control how the block parameters appear in the generated code, you can either define the parameters as `Simulink.Parameter` objects in the MATLAB workspace or use the Model Parameter Configuration dialog box. For more information, see “Control Appearance of Block Parameters in Generated Code” on page 5-5.

Simulink PLC Coder exports tunable parameters as exported symbols and preserves the names of these parameters in the generated code. It does not mangle these names. As a result, if you use a reserved IDE keyword as a tunable parameter name, the code generation can cause compilation errors in the IDE. As a best practice, do not use IDE keywords as tunable parameter names.

The coder maps tunable parameters in the generated code as listed in the following table:

Target IDE	Parameter Storage Class			
	<code>SimulinkGlobal</code>	<code>ExportedGlobal</code>	<code>ImportedExtern</code>	<code>Imported-ExternPointer</code>
CoDeSys 2.3	Local function block variables	Global variable	Variable is not defined in generated code and expected to be defined externally.	Ignored. If you set the parameter to this value, the software treats it the same as <code>ImportedExtern</code> .
CoDeSys 3.3	Local function block variables	Global variable	Variable is not defined in generated code and expected to be defined externally.	Ignored. If you set the parameter to this value, the software treats it the same as <code>ImportedExtern</code> .
CoDeSys 3.5	Local function block variables	Global variable	Variable is not defined in	Ignored. If you set the parameter

Target IDE	Parameter Storage Class			
	SimulinkGlobal	ExportedGlobal	ImportedExtern	Imported-ExternPointer
			generated code and expected to be defined externally.	to this value, the software treats it the same as ImportedExtern.
B&R Automation Studio 3.0	Local function block variable	Local function block variable	Local function block variable.	Ignored. If you set the parameter to this value, the software treats it the same as ImportedExtern.
Beckhoff TwinCAT 2.11	Local function block variable	Global variable	Variable is not defined in generated code and expected to be defined externally.	Ignored. If you set the parameter to this value, the software treats it the same as ImportedExtern.
KW-Software MULTIPROG 5.0	Local function block variable	Local function block variable	Local function block variable.	Ignored. If you set the parameter to this value, the software treats it the same as ImportedExtern.
Phoenix Contact PC WORX 6.0	Local function block variable	Global variable	Variable is not defined in generated code and expected to be defined externally.	Ignored. If you set the parameter to this value, the software treats it the same as ImportedExtern.
RSLogix 5000 17, 18: AOI	AOI local tags	AOI input tags	AOI input tags.	Ignored. If you set the parameter to this value, the software treats it the same as ImportedExtern.

Target IDE	Parameter Storage Class			
	SimulinkGlobal	ExportedGlobal	ImportedExtern	Imported-ExternPointer
RSLogix 5000 17, 18: Routine	Instance fields of program UDT tags	Program tags	Variable is not defined in generated code and expected to be defined externally.	Ignored. If you set the parameter to this value, the software treats it the same as ImportedExtern.
Siemens SIMATIC STEP 7 5.4	Local function block variable	Local function block variable	Local function block variable.	Ignored. If you set the parameter to this value, the software treats it the same as ImportedExtern.
Generic	Local function block variable	Global variable	Variable is not defined in generated code and expected to be defined externally.	Ignored. If you set the parameter to this value, the software treats it the same as ImportedExtern.
PLCopen	Local function block variable	Global variable	Variable is not defined in generated code and expected to be defined externally.	Ignored. If you set the parameter to this value, the software treats it the same as ImportedExtern.

Control Appearance of Block Parameters in Generated Code

Unless you use constants for block parameters in your model, they appear in the generated code as variables. You can choose how these variables appear in the generated code. For instance, you can control the following variable characteristics:

- Whether the variables are inlined in generated code.
- Whether the variables are local to a function block, global, or not defined.

For more information, see “Block Parameters in Generated Code” on page 5-2.

To control how the block parameters appear in the generated code:

- 1 Use variables instead of constants for block parameters.
- 2 Define these parameters in the MATLAB workspace in one of the following ways:
 - Use a MATLAB script to create a `Simulink.Parameter` object. Run the script every time that the model loads.

Simulink stores `Simulink.Parameter` objects outside the model. You can then share `Simulink.Parameter` objects between multiple models.

- Use the Model Configuration Parameters dialog box to make the parameters tunable.

Simulink stores global tunable parameters specified using the Configuration Parameters dialog box with the model. You cannot share these parameters between multiple models.

Configure Tunable Parameters with `Simulink.Parameter` Objects

This example shows how to create and modify a `Simulink.Parameter` object.

The model `plcdemo_tunable_params_slparamobj` illustrates these steps. The model contains a Subsystem block `SimpleSubsystem` that has three Gain blocks with tunable parameters, `K1`, `K2`, and `K3`.

- 1 Write a MATLAB script that defines the tunable parameters.

The following script `setup_tunable_params.m` creates the constants `K1`, `K2`, and `K3` as `Simulink.Parameter` objects, assigns values, and sets the storage classes for

these constants. For more information on the storage classes, see “Block Parameters in Generated Code” on page 5-2.

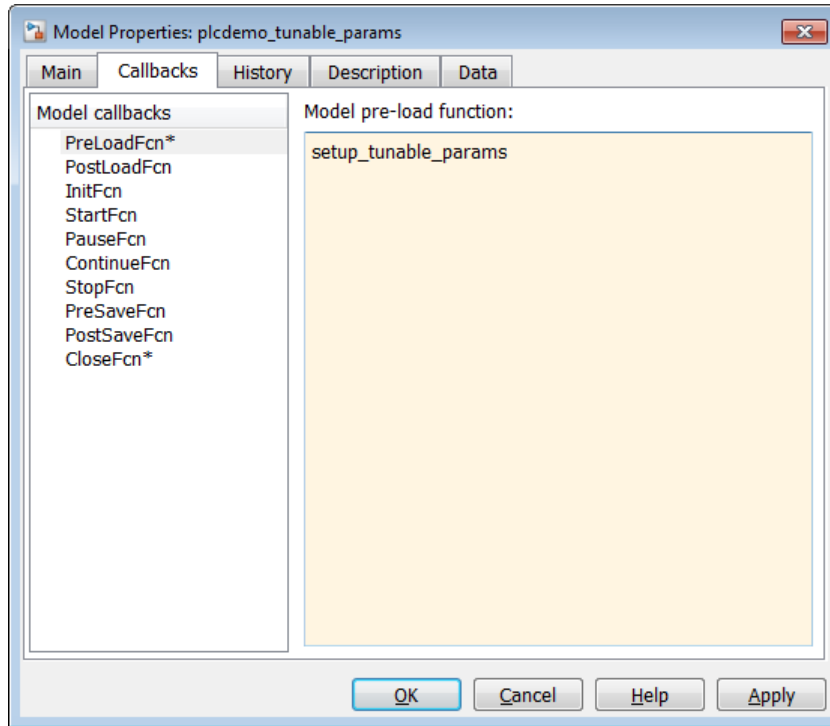
```
% define tunable parameters in base workspace as
% Simulink.Parameter objects

% tunable parameter mapped to local variable
K1 = Simulink.Parameter;
K1.Value = 0.1;
K1.StorageClass = 'SimulinkGlobal';

% tunable parameter mapped to global variable
K2 = Simulink.Parameter;
K2.Value = 0.2;
K2.StorageClass = 'ExportedGlobal';
K2.CoderInfo.CustomStorageClass = 'Default';

% tunable parameter mapped to global const
K3 = Simulink.Parameter;
K3.Value = 0.3;
K3.StorageClass = 'ExportedGlobal';
K3.CoderInfo.CustomStorageClass = 'Const';
```

- 2 Specify that the script `setup_tunable_params.m` must execute before the model loads and that the MATLAB workspace must be cleared before the model closes.
 - a In the model window, select **File > Model Properties > Model Properties**.
 - b In the Model Properties dialog box, on the **Callbacks** tab, select `PreLoadFcn`. Enter `setup_tunable_params` for **Model pre-load function**.



- c On the **Callbacks** tab, select **CloseFcn**. Enter `clear K1 K2 K3;` for **Model close function**.

Every time that you open the model, the variables K1, K2, and K3 are loaded into the base workspace. You can view the variables and their storage classes in the Model Explorer.

- 3 Generate code and inspect it.

Variable	Storage Class	Generated Code (3S CoDeSys 2.3)
K1	SimulinkGlobal	K1 is a local function block variable. FUNCTION_BLOCK SimpleSubsystem . . VAR K1: LREAL := 0.1;

Variable	Storage Class	Generated Code (3S CoDeSys 2.3)
		<pre> . . END_VAR . . END_FUNCTION_BLOCK </pre>
K2	ExportedGlobal	<p>K2 is a global variable.</p> <pre> VAR_GLOBAL K2: LREAL := 0.2; END_VAR </pre>
K3	ExportedGlobal and CoderInfo.CustomStorageClass set to Const.	<p>K3 is a global constant.</p> <pre> VAR_GLOBAL CONSTANT SS_INITIALIZE: SINT := 0; K3: LREAL := 0.3; SS_STEP: SINT := 1; END_VAR </pre>

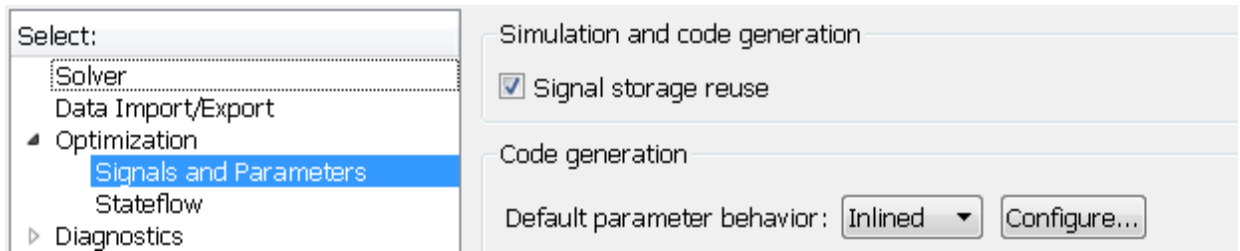
Make Parameters Tunable Using Configuration Parameters Dialog Box

This example shows how to make parameters tunable using the Model Configuration Parameters dialog box.

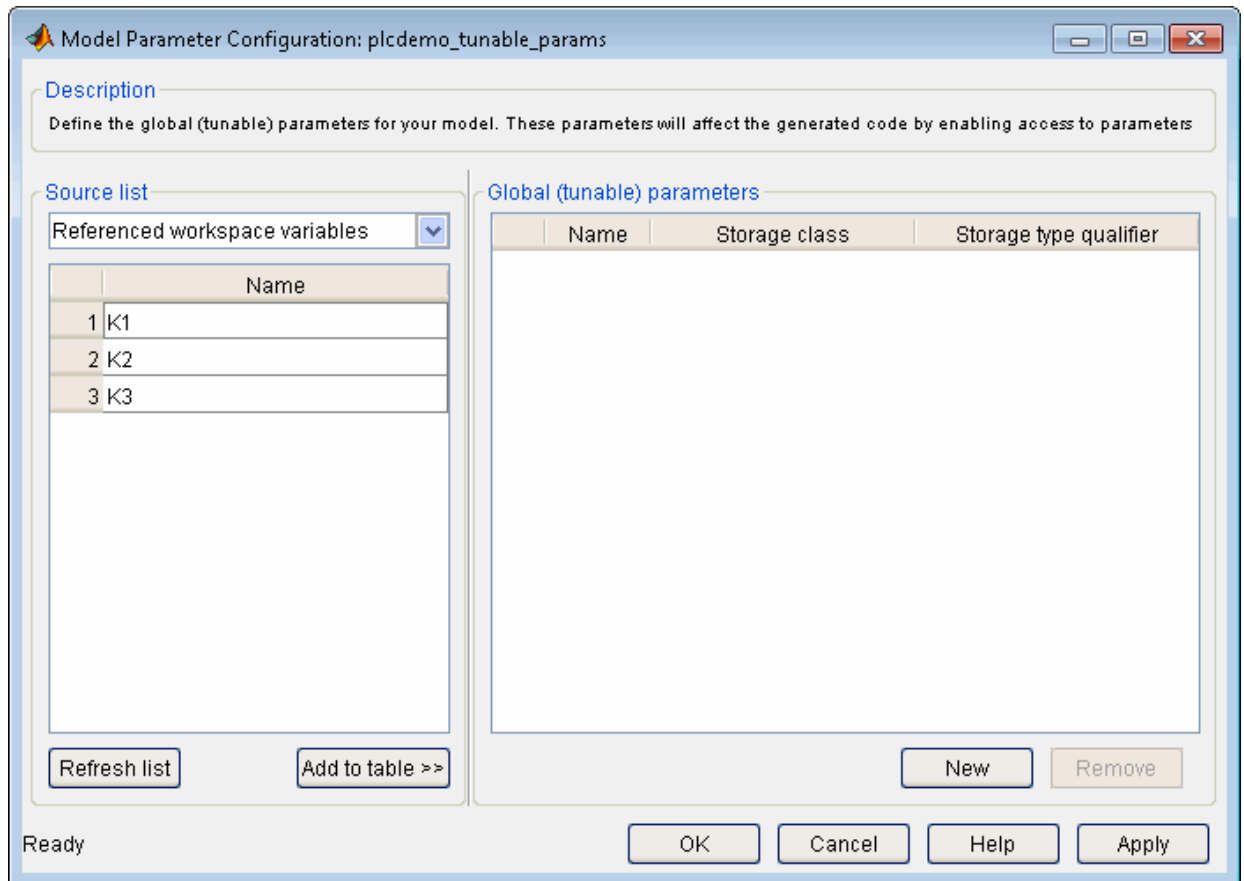
The model `plcdemo_tunable_params` illustrates these steps. The model contains a Subsystem block `SimpleSubsystem` that has three Gain blocks with tunable parameters, K1, K2, and K3.

- 1 Specify that the variables K1, K2, and K3 must be initialized before the model loads and that the MATLAB workspace must be cleared before the model closes.
 - a Select **File > Model Properties > Model Properties**.
 - b In the Model Properties dialog box, on the **Callbacks** tab, select `PreLoadFcn`. Enter `K1=0.1; K2=0.2; K3=0.3;` for **Model pre-load function**.
 - c On the **Callbacks** tab, select `CloseFcn`. Enter `clear K1 K2 K3;` for **Model close function**.
- 2 Select **Simulation > Model Configuration Parameters**.

- 3 Navigate to **Optimization > Signals and Parameters**. In the **Simulation and code generation** section, specify that all parameters must be inlined in the generated code. Select **Inlined** for **Default Parameter Behavior**.

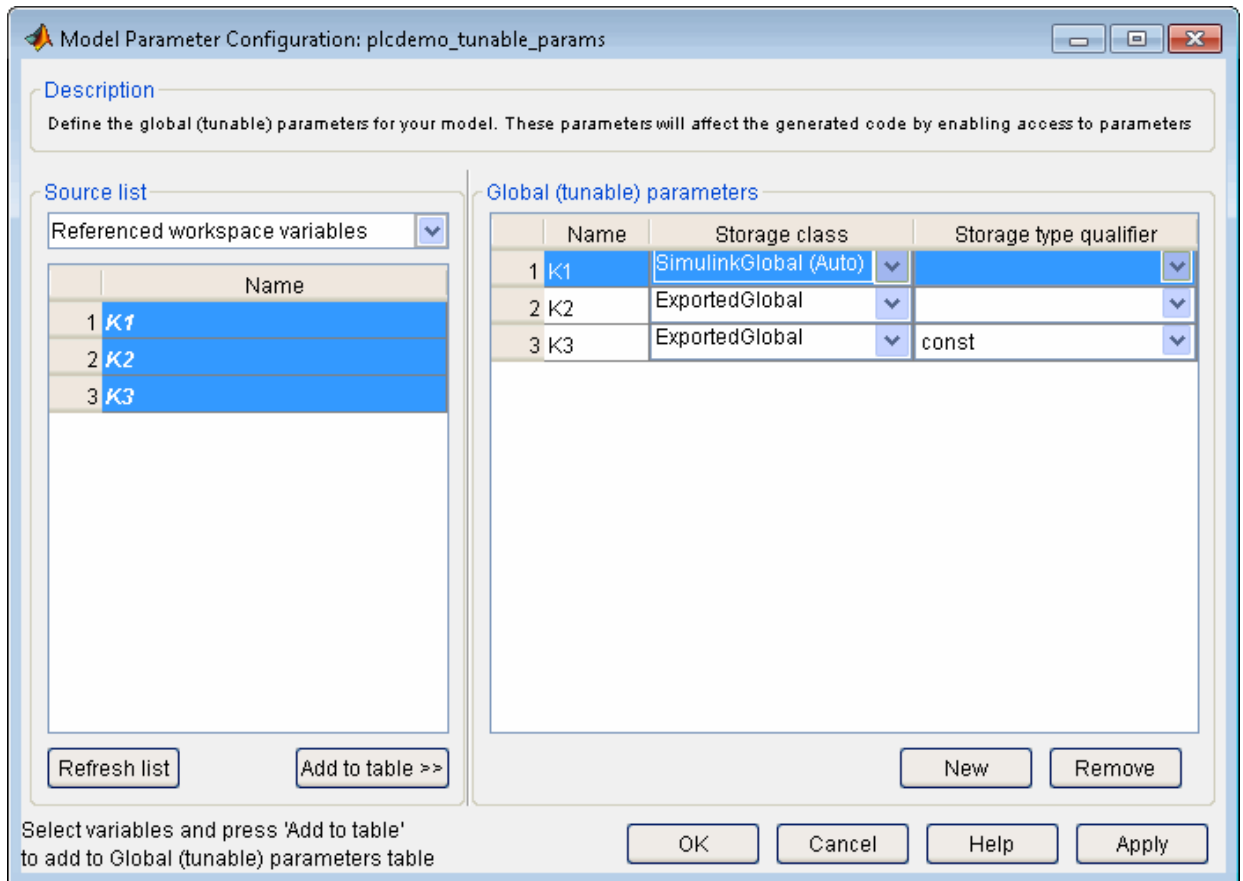


- 4 To override the inlining and make individual parameters tunable, click **Configure**. In the Model Parameter Configuration dialog box, from the **Source list**, select **Referenced workspace variables**.



- 5 **Ctrl**+select the parameters and click **Add to table >>**.

By default, this dialog box sets all parameters to the `SimulinkGlobal` storage class. Set the **Storage class** and **Storage type qualifier** as shown in this figure. For more information on the storage classes, see “Block Parameters in Generated Code” on page 5-2.



6 Generate code and inspect it.

Variable	Storage Class	Generated Code (3S CoDeSys 2.3)
K1	SimulinkGlobal	<pre> K1 is a local function block variable. FUNCTION_BLOCK SimpleSubsystem . . VAR K1: LREAL := 0.1; . </pre>

Variable	Storage Class	Generated Code (3S CoDeSys 2.3)
		<pre> . END_VAR . . END_FUNCTION_BLOCK </pre>
K2	ExportedGlobal	<p>K2 is a global variable.</p> <pre> VAR_GLOBAL K2: LREAL := 0.2; END_VAR </pre>
K3	ExportedGlobal and Storage type qualifier set to Const.	<p>K3 is a global constant.</p> <pre> VAR_GLOBAL CONSTANT SS_INITIALIZE: SINT := 0; K3: LREAL := 0.3; SS_STEP: SINT := 1; END_VAR </pre>

Controlling Generated Code Partitions

- “Generate Global Variables” on page 6-2
- “Control Code Partitions for Subsystem Block” on page 6-3
- “Control Code Partitions for MATLAB Functions in Stateflow Charts” on page 6-9

Generate Global Variables

If you want to generate a global variable in your code, use a global **Data Store Memory** block based on a `Simulink.Signal` object in your model. The workflow does not apply to the Rockwell Automation RSLogix 5000 IDE.

- 1 Set up a data store in your model by using a **Data Store Memory** block.
- 2 Associate a `Simulink.Signal` object with the data store.
 - a In the model workspace, define a `Simulink.Signal` object with the same name as the data store. Set the storage class of the object to `ExportedGlobal` or `ImportedExtern`.
 - b In the **Data Store Memory** block parameters, on the **Signal Attributes** tab, select **Data store name must resolve to Simulink signal object**.
- 3 In your model, attach the signals that you want to **Data Store Read** blocks that read from the data store and **Data Store Write** blocks that write to the data store.

The `Simulink.Signal` object that is associated with the global **Data Store Memory** block appears as a global variable in generated code.

Control Code Partitions for Subsystem Block

Simulink PLC Coder converts subsystems to function block units according to the following rules:

- Generates a function block for the top-level atomic subsystem for which you generate code.
- Generates a function block for an atomic subsystem whose **Function packaging** parameter is set to **Nonreusable function** or **Reusable function**.
- Inlines generated code from atomic subsystems, whose **Function packaging** parameter is set to **Inline**, into the function block that corresponds to the nearest ancestor subsystem. This nearest ancestor cannot be inlined.

These topics use code generated with CoDeSys Version 2.3.

Control Code Partitions Using Subsystem Block Parameters

You can partition generated code using the following **Subsystem** block parameters on the Code Generation tab. See the **Subsystem** block documentation for details.

- **Function packaging**
- **Function name options**

Leave the **File name options** set to the default, **Auto**.

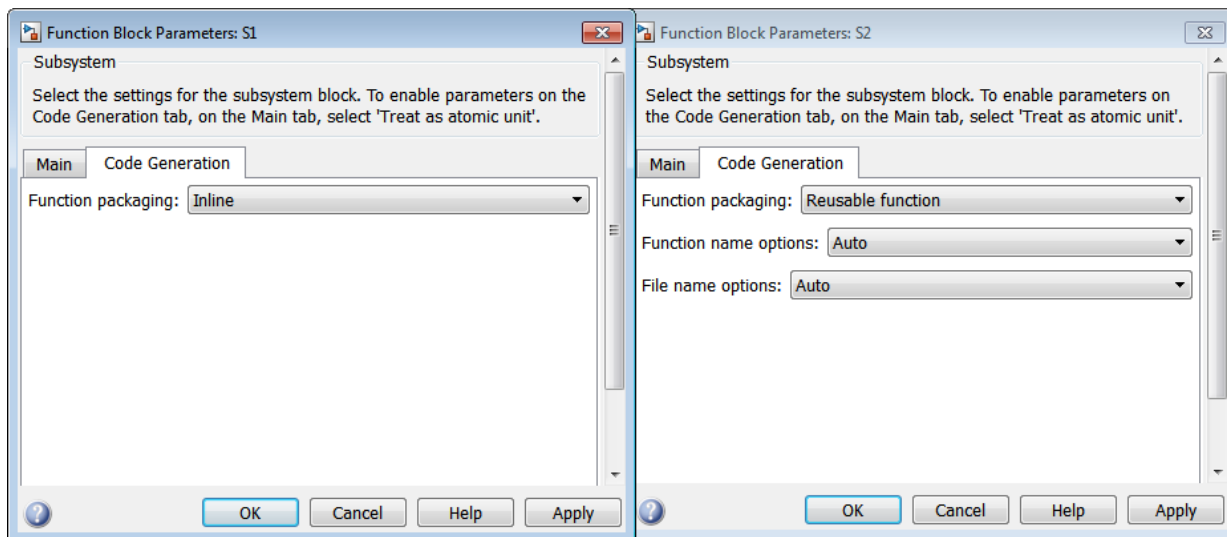
Generating Separate Partitions and Inlining Subsystem Code

Use the **Function packaging** parameter to specify the code format to generate for an atomic (nonvirtual) subsystem. The Simulink PLC Coder software interprets this parameter depending on the setting that you choose:

Setting	Coder Interpretation
Auto	Uses the optimal format based on the type and number of subsystem instances in the model.
Reusable function, Nonreusable function	Generates a function with arguments that allows the subsystem code to be shared by other instances of it in the model.
Inline	Inlines the subsystem unconditionally.

For example, in the `plcdemo_hierarchical_virtual_subsystem`, you can:

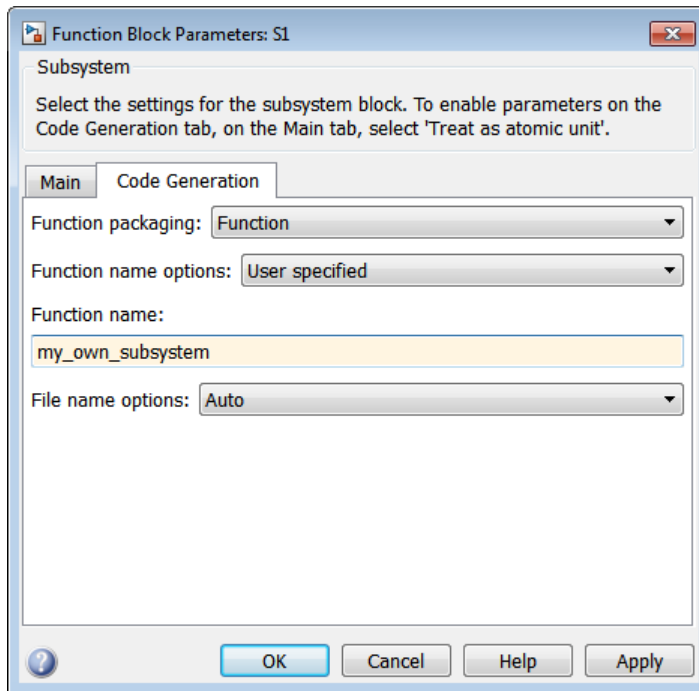
- Inline the S1 subsystem code by setting **Function packaging** to **Inline**. This setting creates one function block for the parent with the S1 subsystem inlined.
- Create a function block for the S2 subsystem by setting **Function packaging** to **Reusable function**, **Auto**, or **Nonreusable function**. This setting creates two function blocks, one for the parent, one for S2.



Changing the Name of a Subsystem

You can use the **Function name options** parameter to change the name of a subsystem from the one on the block label. When the Simulink PLC Coder generates software, it uses the string you specify for this parameter as the subsystem name. For example, see `plcdemo_hierarchical_virtual_subsystem`:

- 1 Open the S1 subsystem block parameter dialog box.
- 2 If the **Treat as atomic unit** check box is not yet selected, select it.
- 3 Click the Code Generation tab.
- 4 Set **Function packaging** to **Nonreusable function**.
- 5 Set **Function name options** to **User specified**.
- 6 In the **Function name** field, specify a custom name. For example, type `my_own_subsystem`.



- 7 Save the new settings.
- 8 Generate code for the parent subsystem.
- 9 Observe the renamed function block.

```

FUNCTION_BLOCK my_own_subsystem
VAR_INPUT
    ssMethodType: SINT;
    U: LREAL;
END_VAR

```

One Function Block for Atomic Subsystems

The code for `plcdemo_simple_subsystem` is an example of generating code with one function block. The atomic subsystem for which you generate code does not contain other subsystems.

```
FUNCTION_BLOCK SimpleSubsystem
VAR_INPUT
    ssMethodType: SINT;
    U: LREAL;
END_VAR
VAR_OUTPUT
    Y: LREAL;
END_VAR
VAR
    UnitDelay_DSTATE: LREAL;
END_VAR
VAR_TEMP
    rtb_Gain: LREAL;
END_VAR
CASE ssMethodType OF
    SS_INITIALIZE:
        (* InitializeConditions for UnitDelay: '<S1>/Unit Delay' *)
        UnitDelay_DSTATE := 0.0;
    SS_STEP:
        (* Gain: '<S1>/Gain' incorporates:
        *   Inport: '<Root>/U'
        *   Sum: '<S1>/Sum'
        *   UnitDelay: '<S1>/Unit Delay' *)
        rtb_Gain := (U - UnitDelay_DSTATE) * 0.5;

        (* Outport: '<Root>/Y' *)
        Y := rtb_Gain;

        (* Update for UnitDelay: '<S1>/Unit Delay' *)
        UnitDelay_DSTATE := rtb_Gain;
END_CASE;
END_FUNCTION_BLOCK
```

One Function Block for Virtual Subsystems

The `plcdemo_hierarchical_virtual_subsystem` example contains an atomic subsystem that has two virtual subsystems, S1 and S2, inlined. A virtual subsystem does not have the **Treat as atomic unit** parameter selected. When you generate code for the hierarchical subsystem, the code contains only the `FUNCTION_BLOCK HierarchicalSubsystem` component. There are no additional function blocks for the S1 and S2 subsystems.

```

FUNCTION_BLOCK HierarchicalSubsystem
VAR_INPUT
    ssMethodType: SINT;
    In1: LREAL;
    In2: LREAL;
    In3: UINT;
    In4: LREAL;
END_VAR
VAR_OUTPUT
    Out1: LREAL;
    Out2: LREAL;
END_VAR
VAR
    UnitDelay_DSTATE: LREAL;
    UnitDelay1_DSTATE: LREAL;
    UnitDelay_DSTATE_j: LREAL;
    UnitDelay_DSTATE_a: LREAL;
END_VAR
VAR_TEMP
    rtb_Gain: LREAL;
    rtb_Gain_c: LREAL;
END_VAR
CASE ssMethodType OF
    SS_INITIALIZE:
        (* InitializeConditions for UnitDelay: '<S1>/Unit Delay' *)
        UnitDelay_DSTATE := 0.0;

```

Multiple Function Blocks for Nonvirtual Subsystems

The `plcdemo_hierarchical_subsystem` example contains an atomic subsystem that has two nonvirtual subsystems, S1 and S2. Virtual subsystems have the **Treat as atomic unit** parameter selected. When you generate code for the hierarchical subsystem, that code contains the `FUNCTION_BLOCK HierarchicalSubsystem`, `FUNCTION_BLOCK HierarchicalSubsystem_S1`, and `FUNCTION_BLOCK HierarchicalSubsystem_S2` components.

Function Block for Hierarchical Subsystem

```
FUNCTION_BLOCK HierarchicalSubsystem
VAR_INPUT
    ssMethodType: SINT;
    In1: LREAL;
    In2: LREAL;
    In3: UINT;
    In4: LREAL;
END_VAR
```

Function Block for Hierarchical S1

```
FUNCTION_BLOCK S1
VAR_INPUT
    ssMethodType: SINT;
    U: LREAL;
```

Function Block for Hierarchical S2

```
FUNCTION_BLOCK S2
VAR_INPUT
    ssMethodType: SINT;
    U: LREAL;
```

Control Code Partitions for MATLAB Functions in Stateflow Charts

Simulink PLC Coder inlines MATLAB functions in generated code based on your inlining specifications. To specify whether to inline a function:

- 1 Right click the MATLAB function and select **Properties**.
- 2 For **Function Inline Option**, select **Inline** if you want the function to be inlined. Select **Function** if you do not want the function to be inlined. For more information, see “Specify MATLAB Function Properties in a Chart”.

However, Simulink PLC Coder does not follow your inlining specifications exactly in the following cases:

- If a MATLAB function accesses data that is local to the chart, it is inlined in generated code even if you specify that the function must not be inlined.

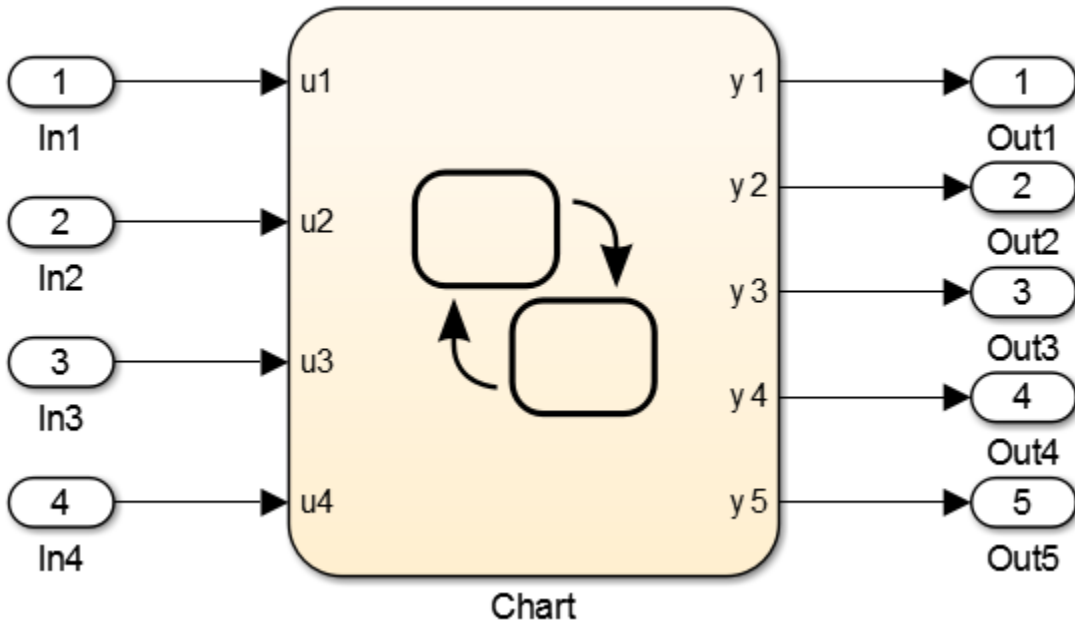
Explanation: The chart is converted to a function block in generated code. If the MATLAB function in the chart is converted to a structured text function, it cannot access the data of an instance of the function block. Therefore, the MATLAB function cannot be converted to a structured text function in generated code and is inlined.

- If a MATLAB function has multiple outputs and you specify that the function must not be inlined, it is converted to a function block in generated code.

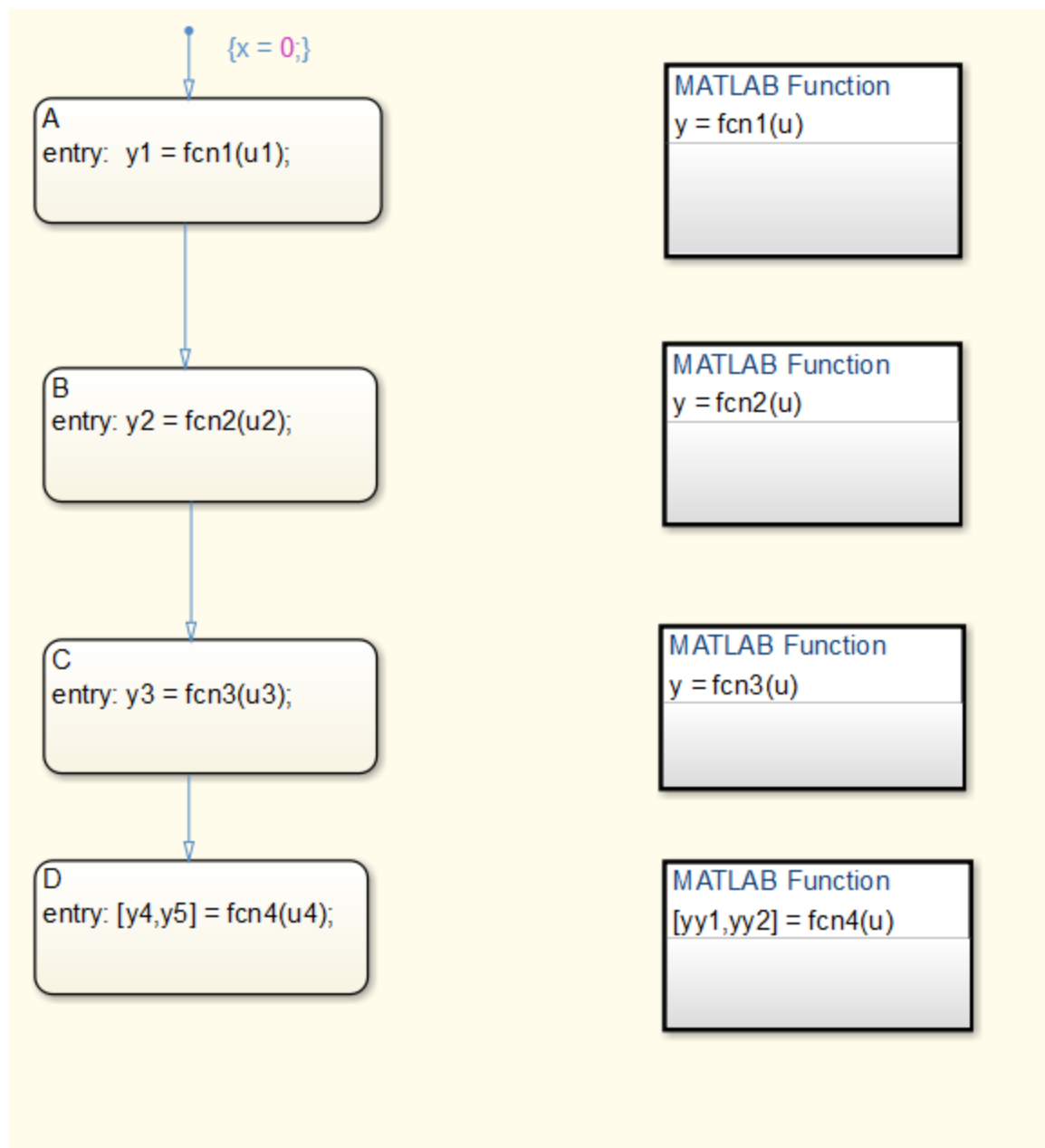
Explanation: A structured text function cannot have multiple outputs, therefore the MATLAB function cannot be converted to a structured text function.

The following simple example illustrates the different cases. The model used here has a Stateflow chart that contains four MATLAB functions `fcn1` to `fcn4`.

Here is the model.



Here is the Stateflow chart.



The functions fcn1 to fcn4 are defined as follows.

Function	Inlining Specification	Generated Code
<pre>fcn1: function y = fcn1(u) y = u+1;</pre>	<p>Specify that the function must be inlined.</p>	<p>fcn1 is inlined in the generated code.</p> <pre>is_c3_Chart := Chart_IN_A; (* Output: '<Root>/y1' incorporates: * Inport: '<Root>/u1' *) (* Entry 'A': '<S1>:10' *) (* MATLAB Function 'fcn1': '<S1>:1' *) (* '<S1>:1:3' *) y1 := u1 + 1.0;</pre>
<pre>fcn2: function y = fcn2(u) y = u+2;</pre>	<p>Specify that the function must not be inlined.</p>	<p>fcn2 is not inlined in the generated code.</p> <pre>is_c3_Chart := Chart_IN_B; (* Output: '<Root>/y2' incorporates: * Inport: '<Root>/u2' *) (* Entry 'B': '<S1>:11' *) y2 := fcn2(u := u2); . . . FUNCTION fcn2: LREAL VAR_INPUT u: LREAL; END_VAR VAR_TEMP END_VAR (* MATLAB Function 'fcn2': '<S1>:4' *) (* '<S1>:4:3' *) fcn2 := u + 2.0; END_FUNCTION</pre>
<pre>fcn3: function y = fcn3(u) % The function accesses % local data x of</pre>	<p>Specify that the function must not be inlined.</p>	<p>fcn3 is inlined in the generated code because it accesses local data from the Stateflow chart.</p> <pre>is_c3_Chart := Chart_IN_C;</pre>

Function	Inlining Specification	Generated Code
<pre>% parent chart y = u+3+x;</pre>		<pre>(* Output: '<Root>/y3' incorporates: * Inport: '<Root>/u3' *) (* Entry 'C': '<S1>:15' *) (* MATLAB Function 'fcn3': '<S1>:9' *) (* The function accesses local data x of parent chart *) (* '<S1>:9:4' *) y3 := (u3 + 3.0) + x;</pre>

Function	Inlining Specification	Generated Code
<pre> fcN4: function [yy1,yy2] = fcN4(u) yy1 = u+4; yy2 = u+5; </pre>	<p>Specify that the function must not be inlined.</p>	<pre> fcN4 is converted to a function block in the generated code because it has multiple outputs. is_c3_Chart := Chart_IN_D; (* Entry 'D': '<S1>:28' *) i0_fcN4(u := u4); b_y4 := i0_fcN4.yy1; b_y5 := i0_fcN4.yy2; (* Output: '<Root>/y4' incorporates: * Inport: '<Root>/u4' *) y4 := b_y4; (* Output: '<Root>/y5' *) y5 := b_y5; . . . FUNCTION_BLOCK fcN4 VAR_INPUT u: LREAL; END_VAR VAR_OUTPUT yy1: LREAL; yy2: LREAL; END_VAR VAR END_VAR VAR_TEMP END_VAR (* MATLAB Function 'fcN4': '<S1>:26' *) (* '<S1>:26:3' *) yy1 := u + 4.0; (* '<S1>:26:4' *) yy2 := u + 5.0; END_FUNCTION_BLOCK </pre>

Integrating Externally Defined Symbols

- “Integrate Externally Defined Symbols” on page 7-2
- “Integrate Custom Function Block in Generated Code” on page 7-3

Integrate Externally Defined Symbols

The coder allows you to suppress symbol definitions in the generated code. This suppression allows you to integrate a custom element, such as user defined function blocks, function blocks, data types, and named global variable and constants, in place of one generated from a Simulink subsystem. You must then provide these definitions when importing the code into the target IDE. You must:

- Define the custom element in the subsystem for which you want to generate code.
- Name the custom element.
- In the Configuration Parameters dialog box, add the name of the custom element to **PLC Code Generation > Symbols > Externally Defined Symbols** in the Configuration Parameters dialog box.
- Generate code.

For a description of how to integrate a custom function block, see “Integrate Custom Function Block in Generated Code” on page 7-3. For a description of the **Externally Defined Symbols** parameter, see “Externally Defined Symbols” on page 12-28.

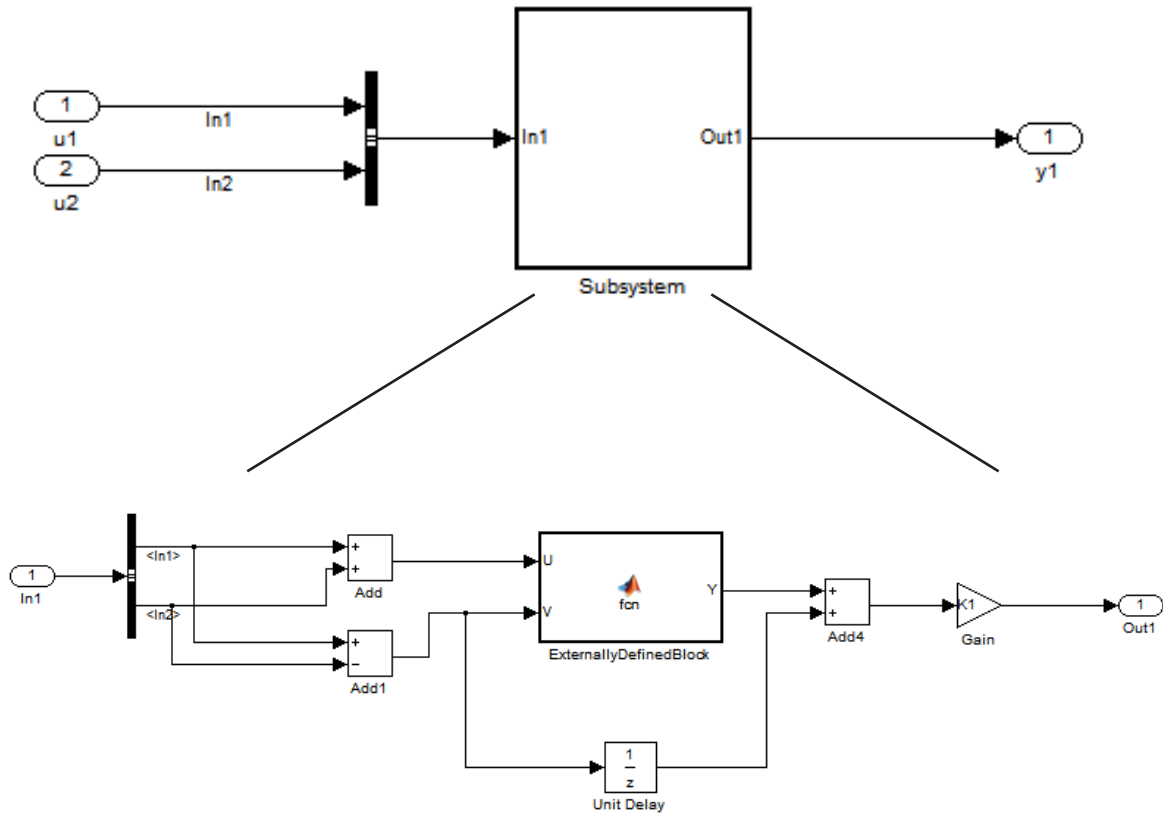
Integrate Custom Function Block in Generated Code

To integrate a custom function block, `ExternallyDefinedBlock`, this procedure uses the example `plcdemo_external_symbols`.

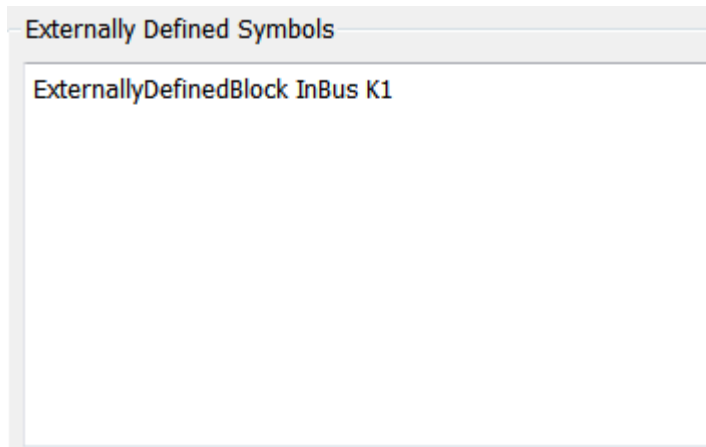
- 1 In a Simulink model, add a MATLAB Function block.
- 2 Double-click the MATLAB Function block.
- 3 In the MATLAB editor, minimally define inputs, outputs, and stubs. For example:

```
function Y = fcn(U,V)
% Stub behavior for simulation. This block
% is replaced during code generation
Y = U + V;
```

- 4 Change the MATLAB Function block name to `ExternallyDefinedBlock`.
- 5 Create a subsystem from this MATLAB Function block.
- 6 Complete the model to look like `plcdemo_external_symbols`.



- 7 Open the Configuration Parameters dialog box for the model.
- 8 Add ExternallyDefinedBlock to **PLC Code Generation > Symbols > Externally Defined Symbols**.
- 9 The plcdemo_external_symbols model also suppresses K1 and InBus. Add these symbol names to the **Externally Defined Symbols** field, separated by spaces or commas. For other settings, see the plcdemo_external_symbols model.



- 10 Save and close your new model. For example, save it as `plcdemo_external_symbols_mine`.
- 11 Generate code for the model.
- 12 In the generated code, look for instances of `ExternallyDefinedBlock`.

The reference of `ExternallyDefinedBlock` is:

```
VAR
    UnitDelay_DSTATE: LREAL;
    i0_ExternallyDefinedBlock: ExternallyDefinedBlock;
END_VAR
```

The omission of `ExternallyDefinedBlock` is:

```
(* MATLAB Function: '<S1>/ExternallyDefinedBlock' *)
i0_ExternallyDefinedBlock(U := rtb_Add, V := rtb_Add1);
rtb_Y := i0_ExternallyDefinedBlock.Y;
```


IDE-Specific Considerations

- “Integrate Generated Code with Existing Projects in Siemens IDEs” on page 8-2
- “Use Internal Signals for Debugging in RSLogix 5000 IDE” on page 8-4
- “Rockwell Automation RSLogix Considerations” on page 8-6
- “Considerations for Siemens IDEs” on page 8-8

Integrate Generated Code with Existing Projects in Siemens IDEs

You can integrate generated code with an existing Siemens SIMATIC STEP 7 or Siemens TIA Portal project. For more information on:

- How to generate code, see “Generate and Examine Structured Text Code” on page 1-14.
- The location of generated code, see “Files Generated with Simulink PLC Coder” on page 1-20.

Integrate Generated Code with Siemens SIMATIC STEP 7 Projects

- 1 In the Siemens SIMATIC STEP 7 project, right-click the **Sources** node and select **Insert New Object > External Source**.
- 2 Navigate to the folder containing the generated code and open the file.

Unless you assigned a custom name, the file is called *model_name.scl*. After you open the file, a new entry called *model_name.scl* appears under the **Sources** node.

- 3 Double-click the new entry. The generated code is listed in the SCL editor window.
- 4 In the SCL editor window, select **Options > Customize**.
- 5 In the customize window, select **Create block numbers automatically** and click **OK**.

Symbol addresses are automatically generated for Subsystem blocks.

- 6 In the SCL editor window, compile the *model_name.scl* file for the Subsystem block.

The new Function Block is now integrated and available for use with the existing Siemens SIMATIC STEP 7 project.

Integrate Generated Code with Siemens TIA Portal Projects

- 1 In the **Project tree** pane, on the **Devices** tab, under the **External source files** node in your project, select **Add new external file**.
- 2 Navigate to the folder containing the generated code and open the file.

Unless you assigned a custom name, the file is called *model_name.scl*. After you open the file, a new entry called *model_name.scl* appears under the **External source files** node.

- 3** Right-click the new entry and select **Generate blocks from source**.

The Siemens TIA Portal IDE compiles the new file and generates TIA Portal program blocks from the code. The program blocks appear under the **Program blocks** node. They are available for use with the existing Siemens TIA Portal project.

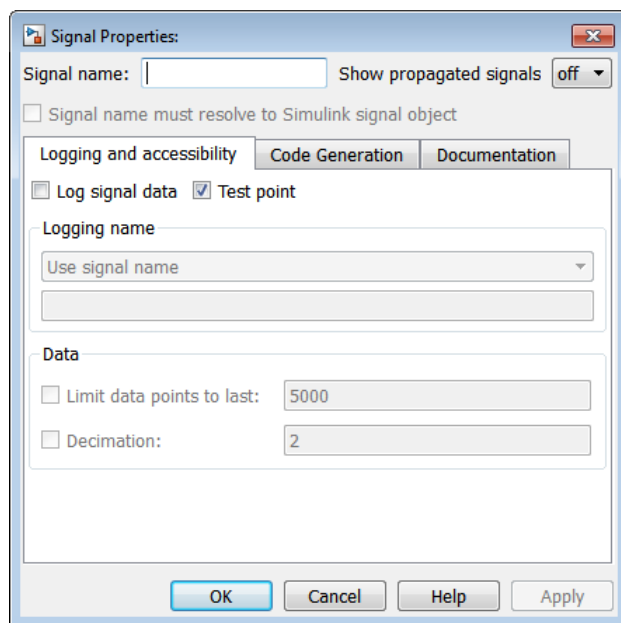
Use Internal Signals for Debugging in RSLogix 5000 IDE

For debugging, you can generate code for test point outputs from the top level subsystem of your model. The coder generates code that maps the test pointed output to optional AOI output parameters for RSLogix 5000 IDEs. In the generated code, the variable tags that correspond to the test points have the property `Required=false`. This example assumes that you have a model appropriately configured for the coder, such as `plcdemo_simple_subsystem`.

- 1 Open the `plcdemo_simple_subsystem` model.
`plcdemo_simple_subsystem`
- 2 In the Configuration Parameters dialog box, set **Target IDE** to Rockwell RSLogix 5000: AOI.
- 3 In the top level subsystem of the model, right-click the output signal of `SimpleSubsystem` and select **Properties**.

The Signal Properties dialog box is displayed.

- 4 On the **Logging and accessibility** tab, click the **Test point** check box.



- 5** Click **OK**.
- 6** Generate code for the top level subsystem.
- 7** Inspect the generated code for the string `Required=false`.

For more information on signals with test points, see “What Is a Test Point?”.

Rockwell Automation RSLogix Considerations

Following are considerations for this target IDE platform.

Add-On Instruction and Function Blocks

The Structured Text concept of function block exists for Rockwell Automation RSLogix target IDEs as an Add-On instruction (AOI). The Simulink PLC Coder software generates AOIs for Add-On instruction format, not FUNCTION_BLOCK.

Double-Precision Data Types

The Rockwell Automation RSLogix target IDE does not support double-precision data types. At code generation, the Simulink PLC Coder converts this data type to single-precision data types in generated code.

Design your model to use single-precision data type (single) as much as possible instead of double-precision data type (double). If you must use doubles in your model, the numerical results produced by the generated Structured Text can differ from Simulink results. This difference is due to double-single conversion in the generated code.

Unsigned Integer Data Types

The Rockwell Automation RSLogix target IDE does not support unsigned integer data types. At code generation, the Simulink PLC Coder converts this data type to signed integer data types in generated code.

Design your model to use signed integer data types (int8, int16, int32) as much as possible instead of unsigned integer data types (uint8, uint16, uint32). Doing so avoids overflow issues that unsigned-to-signed integer conversions can cause in the generated code.

Unsigned Fixed-Point Data Types

In the generated code, Simulink PLC Coder converts fixed-point data types to target IDE integer data types. Because the Rockwell Automation RSLogix target IDE does not support unsigned integer data types, do not use unsigned fixed-point data types in the model. For more information about coder limitations for fixed-point data type support, see “Fixed-Point Data Type Limitations” on page 10-2.

Enumerated Data Types

The Rockwell Automation RSLogix target IDE does not support enumerated data types. At code generation, the Simulink PLC Coder converts this data type to 32-bit signed integer data type in generated code.

Considerations for Siemens IDEs

Following are considerations for this target IDE platform.

Double-Precision Floating-Point Data Types

The Siemens SIMATIC STEP 7 target IDE does not support double-precision floating-point data types. At code generation, the Simulink PLC Coder converts this data type to single-precision real data types in the generated code. Design your model so that the possible precision loss of numerical results of the generated code does not change the expected semantics of the model.

For Siemens PLC devices that support double-precision floating point types, use **Siemens TIA Portal: Double Precision** as **Target IDE** for generating code. The generated code uses the LREAL type for double-precision floating point types in the model. For more information, see “Target IDE” on page 12-4.

int8 and Unsigned Integer Types

The SCL language for Siemens IDEs does not support int8 and unsigned integer data types. At code generation, the Simulink PLC Coder converts int8 and unsigned integer data types to int16 or int32 in the generated code.

Design your model to use int16 and int32 data types as much as possible instead of int8 or unsigned integer data types. The Simulink numerical results using int8 or unsigned integer data types can differ from the numerical results produced by the generated Structured Text.

Design your model so that effects of integer data type conversion of the generated code do not change the expected semantics of the model.

Unsigned Fixed-Point Data Types

In the generated code, Simulink PLC Coder converts fixed-point data types to target IDE integer data types. Because the Siemens target IDEs do not support unsigned integer data types, do not use unsigned fixed-point data types in the model. For more information about coder limitations for fixed-point data type support, see “Fixed-Point Data Type Limitations” on page 10-2.

Enumerated Data Types

The Siemens SIMATIC STEP 7 target IDE does not support enumerated data types. The Siemens SIMATIC STEP 7 converts this data type to 16-bit signed integer data type in the generated code.

Supported Simulink and Stateflow Blocks

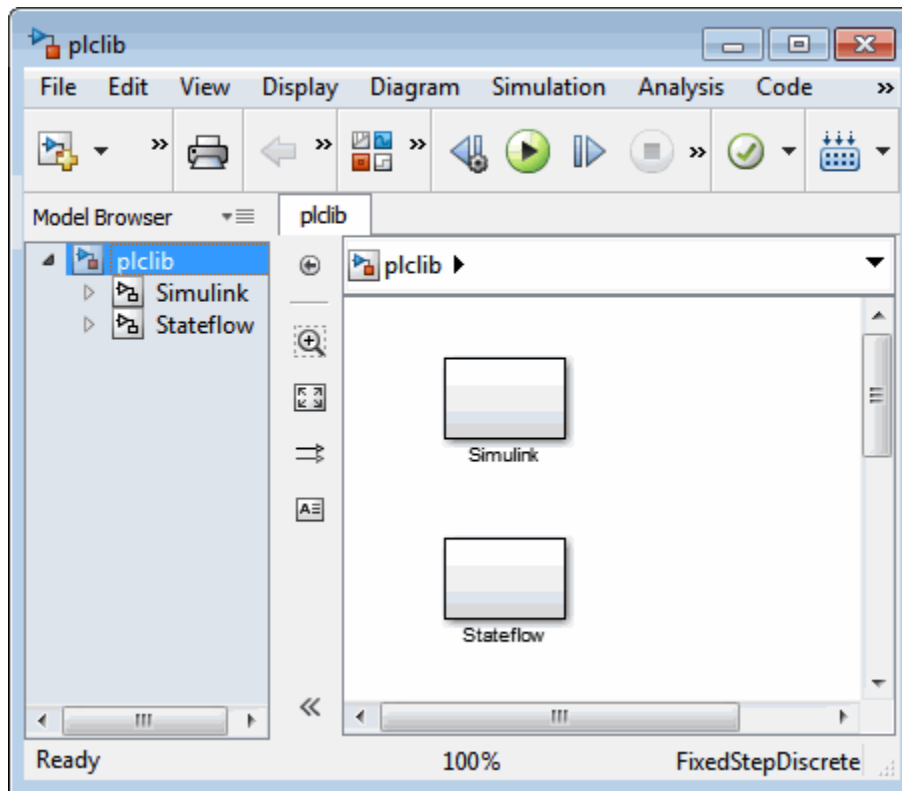
Supported Blocks

For Simulink semantics not supported by Simulink PLC Coder, see “Coder Limitations” on page 10-2.

In this section...
“View Supported Blocks Library” on page 9-2
“Supported Simulink Blocks” on page 9-3
“Supported Stateflow Blocks” on page 9-11
“Blocks With Restricted Support” on page 9-12

View Supported Blocks Library

To view a Simulink library of blocks that the Simulink PLC Coder software supports, type `plclib` in the Command Window. The coder can generate Structured Text code for subsystems that contain these blocks. The library window is displayed.



This library contains two sublibraries, Simulink and Stateflow. Each sublibrary contains the blocks that you can include in a Simulink PLC Coder model.

Supported Simulink Blocks

The coder supports the following Simulink blocks.

Additional Math & Discrete/Additional Discrete

Transfer Fcn Direct Form II

Transfer Fcn Direct Form II Time Varying

Unit Delay Enabled

Unit Delay Enabled External IC

Unit Delay Enabled Resettable

Unit Delay Enabled Resettable External IC

Unit Delay External IC

Unit Delay Resettable

Unit Delay Resettable External IC

Unit Delay With Preview Enabled

Unit Delay With Preview Enabled Resettable

Unit Delay With Preview Enabled Resettable External RV

Unit Delay With Preview Resettable

Unit Delay With Preview Resettable External RV

Commonly Used Blocks

Inport

Bus Creator

Bus Selector

Constant

Data Type Conversion

Demux

Discrete-Time Integrator

Gain

Ground

Logical Operator

Mux

Product

Relational Operator

Saturation

Scope

Subsystem

Inport

Outport

Sum

Switch

Terminator

Unit Delay

Discontinuities

Coulomb and Viscous Friction

Dead Zone Dynamic

Rate Limiter

Rate Limiter Dynamic

Relay

Saturation

Saturation Dynamic

Wrap To Zero

Discrete

Difference

Discrete Transfer Fcn

Discrete Derivative

Discrete FIR Filter

Discrete Filter

PID Controller

PID Controller (2 DOF)

Discrete State-Space

Discrete-Time Integrator

Integer Delay

Memory

Tapped Delay

Transfer Fcn First Order

Transfer Fcn Lead or Lag

Transfer Fcn Real Zero

Unit Delay

Zero-Order Hold

Logic and Bit Operations

Bit Clear

Bit Set

Bitwise Operator

Compare To Constant

Compare To Zero

Detect Change

Detect Decrease

Detect Increase

Detect Fall Negative

Detect Fall Nonpositive

Detect Rise Nonnegative

Detect Rise Positive

Extract Bits

Interval Test

Interval Test Dynamic

Logical Operator

Shift Arithmetic

Lookup Tables

Dynamic-Lookup

Interpolation Using Prelookup

PreLookup

n-D Lookup Table

Math Operations

Abs

Add

Assignment

Bias

Divide
Dot Product
Gain
Math Function
Matrix Concatenate
MinMax
MinMax Running Resettable
Permute Dimensions
Polynomial
Product
Product of Elements
Reciprocal Sqrt
Reshape
Rounding Function
Sign
Slider Gain
Sqrt
Squeeze
Subtract
Sum
Sum of Elements
Trigonometric Function

Unary Minus

Vector Concatenate

Model Verification

Assertion

Check Discrete Gradient

Check Dynamic Gap

Check Dynamic Range

Check Static Gap

Check Static Range

Check Dynamic Lower Bound

Check Dynamic Upper Bound

Check Input Resolution

Check Static Lower Bound

Check Static Upper Bound

Model-Wide Utilities

DocBlock

Model Info

Ports & Subsystems

Atomic Subsystem

CodeReuse Subsystem

Enabled Subsystem

Enable

Function-Call Subsystem

Subsystem

Inport

Outport

Signal Attributes

Data Type Conversion

Data Type Duplicate

Signal Conversion

Signal Routing

Bus Assignment

Bus Creator

Bus Selector

Data Store Memory

Demux

From

Goto

Goto Tag Visibility

Index Vector

Multipoint Switch

Mux

Selector

Sinks

Display

Floating Scope

Scope

Stop Simulation

Terminator

To File

To Workspace

XY Graph

Sources

Constant

Counter Free-Running

Counter Limited

Enumerated Constant

Ground

Pulse Generator

Repeating Sequence Interpolated

Repeating Sequence Stair

User-Defined Functions

MATLAB Function

Fcn

Supported Stateflow Blocks

The coder supports the following Stateflow blocks.

Stateflow

Chart

State Transition Table

Truth Table

Blocks With Restricted Support

Simulink Block Support Exceptions

The Simulink PLC Coder software supports the `plclib` blocks with the following exceptions. Also, see “Coder Limitations” on page 10-2 for a list of limitations of the software.

If you get unsupported fixed-point type messages during code generation, update the block parameter. Open the block parameter dialog box. Navigate to the **Signal Attributes** and **Parameter Attributes** tabs. Check that the **Output data type** and **Parameter data type** parameters are not **Inherit: Inherit via internal rule**. Set these parameters to either **Inherit: Same as input** or a desired non-fixed-point data type, such as `double` or `int8`.

Stateflow Chart Exceptions

If you receive a message about consistency between the original subsystem and the S-function generated from the subsystem build, and the model contains a Stateflow chart that contains one or more Simulink functions, use the following procedure to address the issue:

- 1 Open the model and double-click the Stateflow chart that causes the issue.

The chart Stateflow Editor dialog box is displayed.

- 2 Right-click in this dialog box.
- 3 In the context-sensitive menu, select **Properties**.

The Chart dialog box is displayed.

- 4 In the Chart dialog box, navigate to the **States When Enabling** parameter and select **Held**.
- 5 Click **Apply** and **OK** and save the model.

Data Store Memory Block

To generate PLC code for a model that uses a Data Store Memory block, first define a `Simulink.Signal` object in the base workspace. Then, in the **Signal Attributes** tab of the block parameters, set the data store name to resolve to that `Simulink.Signal` object.

For more information, see “Data Stores with Data Store Memory Blocks”.

Reciprocal Sqrt Block

The Simulink PLC Coder software does not support the Simulink Reciprocal Sqrt block `signedSqrt` and `rSqrt` functions.

Lookup Table Blocks

Simulink PLC Coder has limited support for lookup table blocks. The coder does not support:

- Number of dimensions greater than 2
- Cubic spline interpolation method
- Begin index search using a previous index mode
- Cubic spline extrapolation method

Note: The Simulink PLC Coder software does not support the Simulink Lookup Table Dynamic block. For your convenience, the `plclib/Simulink/Lookup Tables` library contains an implementation of a dynamic table lookup block using the `Prelookup` and `Interpolation Using Prelookup` blocks.

Limitations

Coder Limitations

In this section...
“Current Limitations” on page 10-2
“Fixed-Point Data Type Limitations” on page 10-2
“Multirate Model Limitations” on page 10-4
“Permanent Limitations” on page 10-5

Current Limitations

The Simulink PLC Coder software does not support the following Simulink semantics:

- Complex data types
- Model reference
- Absolute time temporal logic in Stateflow charts.
- Stateflow machine-parented data and events
- Limited support for math functions. For instance, the coder does not support the `rand` function.
- Merge block
- Signal and state storage classes
- Virtual buses at the input ports of the top-level `Atomic Subsystem` block
- `For Each Subsystem` block
- Variable-size signals
- Nonfinite data, for example `NaN` or `Inf`
- Objects defined in the Simulink data dictionary, including model parameters, signals and state objects.

Fixed-Point Data Type Limitations

Simulink PLC Coder software supports the fixed-point data type. To generate code for fixed-point data types, configure block and model parameters as described in this topic.

Note: If you do not configure the blocks and models as directed, the generated Structured Text might:

- Not compile.
- Compile, but return results that differ from the simulation results.

Block Parameters

Properly configure block parameters:

- 1 If the block in the subsystem has a **Signal Attributes** tab, navigate to that tab.
- 2 For the **Integer rounding mode** parameter, select Round.
- 3 Clear the **Saturate on integer overflow** check box.
- 4 For the **Output data type** parameter, select a fixed-point data type.
- 5 Click the **Data Type Assistant** button.
- 6 For the Word length parameter, enter 8, 16, or 32.
- 7 For the **Mode** parameter, select Fixed point.
- 8 For the **Scaling** parameter, select Binary point.

The screenshot shows the 'Parameter Attributes' tab of a block's configuration. The 'Output minimum' and 'Output maximum' fields are empty. The 'Output data type' is set to 'fixdt(1,16,0)'. The 'Data Type Assistant' is expanded, showing the following settings: Mode: Fixed point, Signedness: Signed, Word length: 16, Scaling: Binary point, Fraction length: 0. There is a 'Calculate Best-Precision Scaling' button. Below the assistant, the 'Lock output data type setting against changes by the fixed-point tools' checkbox is unchecked. The 'Integer rounding mode' is set to 'Round', and the 'Saturate on integer overflow' checkbox is unchecked.

- 9 Click **OK**.

Be sure to edit the model configuration parameters (see “Model Configuration Parameters” on page 10-4).

Model Configuration Parameters

Properly configure model configuration parameters:

- 1 In model Configuration Parameters dialog box, click the **Hardware Implementation** node.
- 2 For the **Device vendor** parameter, select **Generic**.
- 3 For the **Device type**, select **Custom**.
- 4 For the **Signed integer division rounds to**, select **Zero**.
- 5 For the **Number of bits**, set **char** to 16.

Embedded hardware (simulation and code generation)

Device vendor: **Generic** Device type: **Custom**

Number of bits

char: **16** short: **16** int: **32**

long: **32** float: **32** double: **64**

native: **32** pointer: **32**

Largest atomic size

integer: **Char**

floating-point: **None**

Byte ordering: **Unspecified** Signed integer division rounds to: **Zero**

Shift right on a signed integer as arithmetic shift

Emulation hardware (code generation only)

None

Multirate Model Limitations

To generate Structured Text from a multirate model, you must configure the model as follows:

- Change any continuous time input signals in the top-level subsystem to use discrete fixed sample times.
- For the solver, select single-tasking execution.

The following target IDEs are not supported for multirate model code generation:

- Rockwell Automation RSLogix 5000 AOI

- Siemens SIMATIC STEP 7
- B&R Automation Studio

When you deploy code generated from a multirate model, you must run the code at the fundamental sample rate.

Permanent Limitations

The Structured Text language has inherent restrictions. As a result, the Simulink PLC Coder software has the following restrictions:

- The Simulink PLC Coder software supports code generation only for atomic subsystems.
- The Simulink PLC Coder software supports automatic, inline, or reusable function packaging for code generation. Nonreusable function packaging is not supported.
- No blocks that require continuous time semantics. This restriction includes continuous integrators, zero-crossing blocks, physical modeling blocks, and so on.
- No pointer data types.
- No recursion (including recursive events).

Functions — Alphabetical List

plccoderdemos

Product examples

Syntax

`plccoderdemos`

Description

`plccoderdemos` displays the Simulink PLC Coder examples.

Examples

Display Simulink PLC Coder examples.

```
plccoderdemos
```

See Also

`plcopenconfigset`

Introduced in R2010a

plccoderpref

Manage user preferences

Syntax

```
plccoderpref
plccoderpref('plctargetide')
plccoderpref('plctargetide', preference_value)
plccoderpref('plctargetide', 'default')
plccoderpref('plctargetidepaths')
plccoderpref('plctargetidepaths', 'default')
plccoderpref('plctargetlist')
plccoderpref('plctargetlist', targetlist)
```

Description

plccoderpref displays the current set of user preferences, including the default target IDE.

plccoderpref('plctargetide') returns the current default target IDE. This default can be the target IDE set previously, or the factory default. The factory default is 'codesys23'.

plccoderpref('plctargetide', *preference_value*) sets the default target IDE to the one that you specify in *preference_value*. This command sets the *preference_value* to persist as the default target IDE for future MATLAB sessions.

plccoderpref('plctargetide', 'default') sets the default target IDE to the factory default target IDE ('codesys23').

plccoderpref('plctargetidepaths') returns a 1-by-1 structure of the installation paths of supported target IDEs.

plccoderpref('plctargetidepaths', 'default') sets the contents of the 1-by-1 structure of the installation paths to the default values.

plccoderpref('plctargetlist') displays the target IDEs that appear in the reduced **Target IDE** list in the Simulink Configuration Parameters dialog box. For

more information, see “Target IDE” on page 12-4 and “Show full target list” on page 12-7.

`plccoderpref('plctargetlist', targetlist)` sets the target IDEs that appear in the reduced **Target IDE** list to the values that you specify in *targetlist*.

Input Arguments

plctargetide

String directive that specifies the default target IDE.

Value	Description
codesys23	3S-Smart Software Solutions CoDeSys Version 2.3 (default) target IDE
codesys33	3S-Smart Software Solutions CoDeSys Version 3.3 target IDE
codesys35	3S-Smart Software Solutions CoDeSys Version 3.5 target IDE
brautomation30	B&R Automation Studio 3.0 target IDE
generic	Generic target IDE
multiprog50	KW-Software MULTIPROG 5.0 target IDE
omron	OMRON Sysmac Studio
plcopen	PLCopen XML target IDE
pcworx60	Phoenix Contact PC WORX 6.0
rslogix5000	Rockwell Automation RSLogix 5000 Series target IDE for AOI format
rslogix5000_routine	Rockwell Automation RSLogix 5000 Series target IDE for routine format
step7	Siemens SIMATIC STEP 7 Version 5 target IDE
twincat211	Beckhoff TwinCAT 2.11 target IDE
tiaportal	Siemens TIA Portal
tiaportal_double	Siemens TIA Portal with support for double precision (LREAL type)

Default: codesys23

plctargetidepaths

String that specifies the target IDE installation path. Contains a 1-by-1 structure of the installation paths of supported target IDEs.

```
codesys23: 'C:\Program Files\3S Software'
codesys33: 'C:\Program Files\3S CoDeSys'
codesys35: 'C:\Program Files\3S CoDeSys'
rslogix5000: 'C:\Program Files\Rockwell Software'
rslogix5000_routine: 'C:\Program Files\Rockwell Software'
brautomation30: 'C:\Program Files\BrAutomation'
multiprog50: 'C:\Program Files\KW-Software\MULTIPROG 5.0'
pcworx60: 'C:\Program Files\Phoenix Contact\Software Suite 150'
step7: 'C:\Program Files\Siemens'
plcopen: ''
twincat211: 'C:\TwinCAT'
generic: ''
```

default

String that sets your preferences to the factory default.

plctargetlist

Cell array of strings. Each string specifies a target IDE. You can specify any target IDE that is available for the `plctargetide` argument.

Use the string `default` to reset the reduced **Target IDE** list.

Examples

Return the current default target IDE.

```
plccoderpref('plctargetide')
```

Set `rslogix5000` as the new default target IDE.

```
plccoderpref('plctargetide', 'rslogix5000')
```

Assume that you have previously changed the installation path of the CoDeSys 2.3 target IDE. Return the current target IDE installation paths.

```
codesys23: 'C:\Program Files2\3S-Software\CoDeSys\v2.3'
codesys33: 'C:\Program Files\3S CoDeSys'
codesys35: 'C:\Program Files\3S CoDeSys'
```

```

rslogix5000: 'C:\Program Files\Rockwell Software'
rslogix5000_routine: 'C:\Program Files\Rockwell Software'
brautomation30: 'C:\Program Files\BrAutomation'
multiprog50: 'C:\Program Files\KW-Software\MULTIPROG 5.0'
pcworx60: 'C:\Program Files\Phoenix Contact\Software Suite 150'
  step7: 'C:\Program Files\Siemens'
  plcopen: ''
twincat211: 'C:\TwinCAT'
generic: ''

```

Set the installation path of all target IDEs, including CoDeSys 2.3, to factory default.

```
plccoderpref('plctargetidepaths', 'default')
```

ans =

```

codesys23: 'C:\Program Files\3S Software'
codesys33: 'C:\Program Files\3S CoDeSys'
codesys35: 'C:\Program Files\3S CoDeSys'
rslogix5000: 'C:\Program Files\Rockwell Software'
rslogix5000_routine: 'C:\Program Files\Rockwell Software'
brautomation30: 'C:\Program Files\BrAutomation'
multiprog50: 'C:\Program Files\KW-Software\MULTIPROG 5.0'
pcworx60: 'C:\Program Files\Phoenix Contact\Software Suite 150'
  step7: 'C:\Program Files\Siemens'
  plcopen: ''
twincat211: 'C:\TwinCAT'
generic: ''

```

Set the reduced **Target IDE** list to contain only the IDEs CoDeSys 2.3 and Rockwell Automation RSLogix 5000 Series for AOI format.

```
targetlist = {'codesys23', 'rslogix5000'};
plccoderpref('plctargetlist', targetlist)
```

ans =

```
'codesys23' 'rslogix5000'
```

Reset the reduced **Target IDE** list to the default subset.

```
plccoderpref('plctargetlist', 'default')
```

ans =

```
'codesys23' 'rslogix5000' 'step7' 'omron' 'plcopen'
```

Append the IDE CoDeSys 3.5 to the default reduced **Target IDE** list.

```
plccoderpref('plctargetlist', [plccoderpref('plctargetlist', 'default') 'codesys35'])
```

```
ans =  
    'codesys23'    'rslogix5000'    'step7'    'omron'    'plcopen'    'codesys35'
```

Append the IDE CoDeSys 3.5 to the current reduced **Target IDE** list.

```
plccoderpref('plctargetlist', [plccoderpref('plctargetlist') 'codesys35'])
```

More About

Tips

Use the Simulink Configuration Parameters dialog box to change the installation path of a target IDE (**Target IDE Path**).

Introduced in R2010a

plcgeneratecode

Generate Structured Text for subsystem

Syntax

```
generatedfiles = plcgeneratecode(subsystem)
```

Description

`generatedfiles = plcgeneratecode(subsystem)` generates Structured Text for the specified atomic subsystem in a model. *subsystem* is the fully qualified path name of the atomic subsystem. *generatedfiles* is a cell array of the generated file names. You must first load or start the model.

Examples

Generate code for the subsystem, `plcdemo_simple_subsystem/SimpleSubsystem`.

```
plcdemo_simple_subsystem  
generatedfiles = plcgeneratecode('plcdemo_simple_subsystem/SimpleSubsystem')
```

See Also

`plcopenconfigset`

Introduced in R2010a

plcopenconfigset

Open Configuration Parameters dialog box for subsystem

Syntax

```
plcopenconfigset(subsystem)
```

Description

`plcopenconfigset(subsystem)` opens the Configuration Parameters dialog box for the specified atomic subsystem in the model. *subsystem* is the fully qualified path name of the atomic subsystem.

Examples

Open the Configuration Parameters dialog box for the subsystem, `plcdemo_simple_subsystem/SimpleSubsystem`.

```
plcdemo_simple_subsystem  
plcopenconfigset('plcdemo_simple_subsystem/SimpleSubsystem')
```

See Also

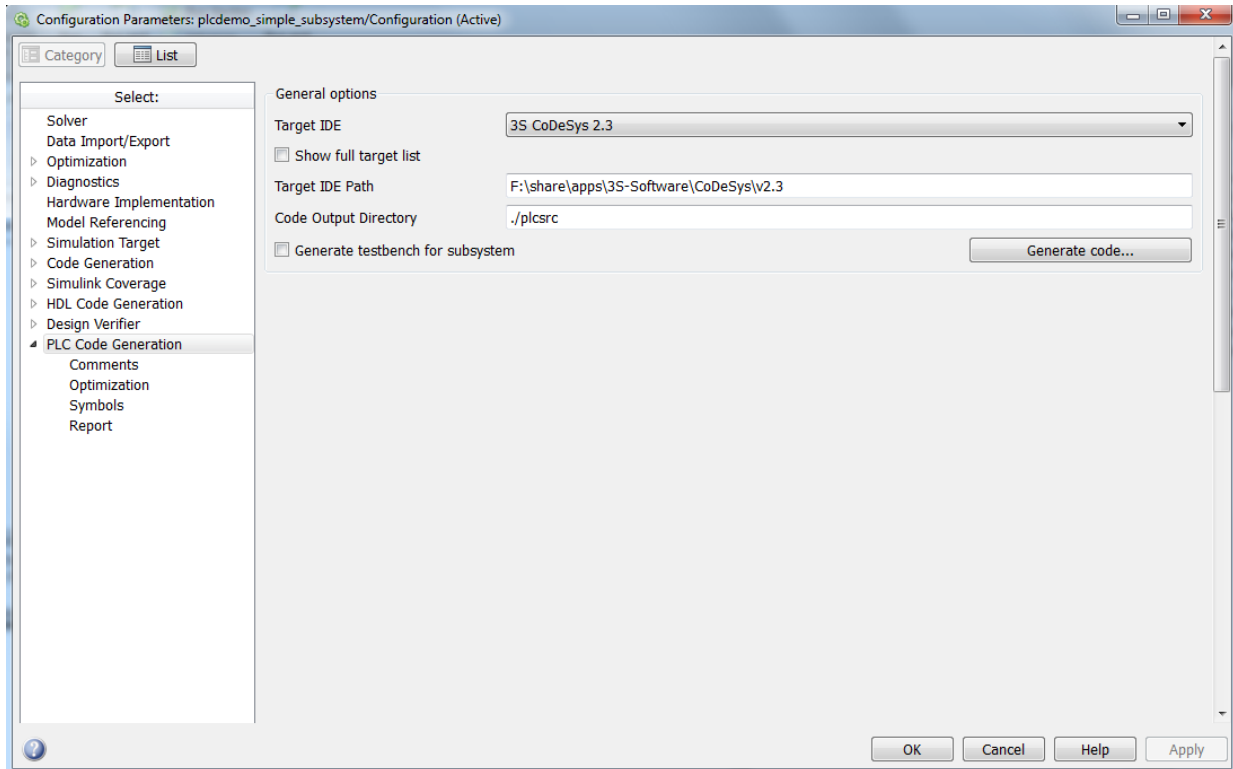
`plcgeneratecode`

Introduced in R2010a

Configuration Parameters for Simulink PLC Coder Models

- “PLC Coder: General” on page 12-2
- “PLC Coder: Comments” on page 12-13
- “PLC Coder: Optimization” on page 12-18
- “PLC Coder: Symbols” on page 12-23
- “PLC Coder: Report” on page 12-31

PLC Coder: General



In this section...

“PLC Coder: General Tab Overview” on page 12-3

“Target IDE” on page 12-4

“Show full target list” on page 12-7

“Target IDE Path” on page 12-9

“Code Output Directory” on page 12-11

“Generate testbench for subsystem” on page 12-12

PLC Coder: General Tab Overview

Set up general information about generating Structured Text code to download to target PLC IDEs.

Configuration

To enable the Simulink PLC Coder options pane, you must:

- 1 Create a model.
- 2 Add either an Atomic Subsystem block, or a Subsystem block for which you have selected the **Treat as atomic unit** check box.
- 3 Right-click the subsystem block and select **PLC Code > Options**.

Tip

In addition to configuring parameters for the Simulink PLC Coder model, you can also use this dialog box to generate Structured Text code and test bench code for the Subsystem block.

See Also

“Prepare Model for Structured Text Generation” on page 1-7

“Generate Structured Text from the Model Window” on page 1-14

Target IDE

Select the target IDE for which you want to generate code. This option is available on the **PLC Code Generation** node in the Configuration Parameters window.

The default **Target IDE** list shows a reduced subset of targets. To customize this list and specify IDEs that you use more frequently, use the `plccoderpref` function. See `plccoderpref`.

To see all supported target IDEs, select the option **Show full target list**. See “Show full target list” on page 12-7.

Settings

Default: 3S CoDeSys 2.3

3S CoDeSys 2.3

Generates Structured Text (IEC 61131-3) code for 3S-Smart Software Solutions CoDeSys Version 2.3.

3S CoDeSys 3.3

Generates Structured Text code in PLCopen XML for 3S-Smart Software Solutions CoDeSys Version 3.3.

3S CoDeSys 3.5

Generates Structured Text code in PLCopen XML for 3S-Smart Software Solutions CoDeSys Version 3.5.

B&R Automation Studio 3.0

Generates Structured Text code for B&R Automation Studio 3.0.

Beckhoff TwinCAT 2.11

Generates Structured Text code for Beckhoff TwinCAT 2.11 software.

KW-Software MULTIPROG 5.0

Generates Structured Text code in PLCopen XML for KW-Software MULTIPROG 5.0.

Phoenix Contact PC WORX 6.0

Generates Structured Text code in PLCopen XML for Phoenix Contact PC WORX 6.0.

Rockwell RSLogix 5000: AOI

Generates Structured Text code for Rockwell Automation RSLogix 5000 using Add-On Instruction (AOI) constructs.

Rockwell RSLogix 5000: Routine

Generates Structured Text code for Rockwell Automation RSLogix 5000 routine constructs.

Siemens SIMATIC Step 7 5.4

Generates Structured Text code for Siemens SIMATIC STEP 7 5.4.

Siemens TIA Portal

Generates Structured Text code for Siemens TIA Portal.

Siemens TIA Portal: Double Precision

Generates Structured Text code for Siemens TIA Portal. The code uses **LREAL** type for **double** data type in the model and can be used on Siemens PLC devices that support the **LREAL** type.

Generic

Generates a pure Structured Text file. If the target IDE that you want is not available for the Simulink PLC Coder product, consider generating and downloading a generic Structured Text file.

PLCopen XML

Generates Structured Text code formatted using PLCopen XML standard.

Rexroth Indraworks

Generates Structured Text code for Rexroth IndraWorks version 13V12 IDE.

OMRON Sysmac Studio

Generates Structured Text code for OMRON® Sysmac® Studio Version 1.04, 1.05, or 1.09.

Tip

- Rockwell Automation RSLogix 5000 routines represent the model hierarchy using hierarchical user-defined types (UDTs). UDT types preserve model hierarchy in the generated code.
- The coder generates code for reusable subsystems as separate routine instances. These subsystems access instance data in program tag fields.

Command-Line Information

Parameter: PLC_TargetIDE

Type: string

Value: 'codesys23' | 'codesys33' | 'codesys35' | 'rslogix5000' | 'rslogix5000_routine' | 'brautomation30' | 'multiprog50' | 'pcworx60' |

'step7' | 'plcopen' | 'twincat211' | 'generic' | 'indraworks' | 'omron' |
'tiaportal' | 'tiaportal_double'

Default: 'codesys23'

See Also

“Generate Structured Text from the Model Window” on page 1-14

Show full target list

View the full list of supported target IDEs in the **Target IDE** drop-down list. For more information, see “Target IDE” on page 12-4. This option is available on the **PLC Code Generation** node in the Configuration Parameters window.

Instead of viewing the full list each time to select an IDE that is not present in the reduced **Target IDE** list, you can add this IDE to the reduced list. To specify your own reduced **Target IDE** list, use the `plccoderpref` function. See `plccoderpref`.

Settings

Default: off

On

The **Target IDE** list displays all supported IDEs. For more information, see “Supported IDE Platforms” on page 1-5.

Off

The **Target IDE** list displays only the more commonly used IDEs. The default subset contains the following IDEs:

- `codesys23` — 3S-Smart Software Solutions CoDeSys Version 2.3 (default) target IDE
- `rslogix5000` — Rockwell Automation RSLogix 5000 Series target IDE for AOI format
- `step7` — Siemens SIMATIC STEP 7 Version 5 target IDE
- `omron` — OMRON Sysmac Studio
- `plcopen` — PLCopen XML target IDE

You can change this default reduced **Target IDE** list using the `plccoderpref` function.

Command-Line Information

Parameter: `PLC_ShowFullTargetList`

Type: string

Value: 'on' | 'off'

Default: 'off'

You can change the contents of the reduced **Target IDE** list using the `plccoderpref` function. See `plccoderpref`.

Target IDE Path

Specify the target IDE installation path. The path already specified is the default installation path for the target IDE. Change this path if your IDE is installed in a different location. This option is available on the **PLC Code Generation** node in the Configuration Parameters window.

Settings

Default: C:\Program Files\3S Software

C:\Program Files\3S Software

Default installation path for 3S-Smart Software Solutions CoDeSys software Version 2.3.

C:\Program Files\3S CoDeSys

Default installation path for 3S-Smart Software Solutions CoDeSys software Version 3.3.

C:\Program Files\BrAutomation

Default installation path for B&R Automation Studio 3.0 software.

C:\TwinCAT

Default installation path for Beckhoff TwinCAT 2.11 software.

C:\Program Files\KW-Software\MULTIPROG 5.0

Default installation path for KW-Software MULTIPROG 5.0 software.

C:\Program Files\Phoenix Contact\Software Suite 150

Default installation path for Phoenix Contact PC WORX 6.0 software.

C:\Program Files\Rockwell Software

Default installation path for Rockwell Automation RSLogix 5000 software.

C:\Program Files\Siemens

Default installation path for Siemens SIMATIC STEP 7 5.4 software.

C:\Program Files\Siemens\Automation

Default installation path for Siemens TIA Portal software.

Tip

- When you change the **Target IDE** value, the value of this parameter changes.

- If you right-click the Subsystem block, the **PLC Code > Generate and Import Code for Subsystem** command uses this value to import generated code.
- If your target IDE installation is standard, do not edit this parameter. Leave it as the default value.
- If your target IDE installation is nonstandard, edit this value to specify the actual installation path.
- If you change the path and click **Apply**, the changed path remains for that target IDE for other models and between MATLAB sessions. To reinstate the factory default, use the command:

```
plccoderpref('plctargetidepaths','default')
```

Command-Line Information

See `plccoderpref`.

See Also

“Import Structured Text Code Automatically” on page 1-24

Code Output Directory

Enter a path to the target folder into which code is generated. This option is available on the **PLC Code Generation** node in the Configuration Parameters window.

Settings

Default: plcsrc subfolder in your working folder

Command-Line Information

Parameter: PLC_OutputDir

Type: string

Value: string

Default: 'plcsrc'

See Also

“Generate Structured Text from the Model Window” on page 1-14

Generate testbench for subsystem

Specify the generation of test bench code for the subsystem. This option is available on the **PLC Code Generation** node in the Configuration Parameters window.

Settings

Default: off

On

Enables generation of test bench code for subsystem.

Disables generation of test bench code for subsystems.

Dependency

This parameter is disabled if your model has absolute time temporal logic.

Command-Line Information

Parameter: PLC_GenerateTestbench

Type: string

Value: 'on' | 'off'

Default: 'off'

See Also

“Generate Structured Text from the Model Window” on page 1-14

PLC Coder: Comments

Overall control
<input checked="" type="checkbox"/> Include comments
<input checked="" type="checkbox"/> Include block description
Auto generated comments
<input checked="" type="checkbox"/> Simulink block / Stateflow object comments
<input type="checkbox"/> Show eliminated blocks

In this section...

“Comments Overview” on page 12-14

“Include comments” on page 12-14

“Include block description” on page 12-15

“Simulink block / Stateflow object comments” on page 12-16

“Show eliminated blocks” on page 12-17

Comments Overview

Control the comments that the Simulink PLC Coder software automatically creates and inserts into the generated code.

See Also

“Generate Structured Text from the Model Window” on page 1-14

Include comments

Specify which comments are in generated files. This option is available on the **PLC Code Generation > Comments** node in the Configuration Parameters window.

Settings

Default: on

On

Places comments in the generated files based on the selections in the **Auto generated comments** pane.

If you create links to requirements documents from your model using the Simulink Verification and Validation software, the links also appear in generated code comments.

Off

Omits comments from the generated files.

Command-Line Information

Parameter: PLC_RTWGenerateComments

Type: string

Value: 'on' | 'off'

Default: 'on'

See Also

“Generate Structured Text from the Model Window” on page 1-14

Include block description

Specify which block description comments are in generated files. This option is available on the **PLC Code Generation > Comments** node in the Configuration Parameters window.

Settings

Default: on



On

Places comments in the generated files based on the contents of the block properties **General** tab.



Off

Omits block descriptions from the generated files.

Command-Line Information

Parameter: PLC_PLCEnableBlockDescription

Type: string

Value: 'on' | 'off'

Default: 'on'

See Also

- “Propagate Block Descriptions to Code Comments” on page 1-19
- “Generate Structured Text from the Model Window” on page 1-14

Simulink block / Stateflow object comments

Specify whether to insert Simulink block and Stateflow object comments. This option is available on the **PLC Code Generation > Comments** node in the Configuration Parameters window.

Settings

Default: on

On

Inserts automatically generated comments that describe block code and objects. The comments precede that code in the generated file.

Off

Suppresses comments.

Command-Line Information

Parameter: PLC_RTWSimulinkBlockComments

Type: string

Value: 'on' | 'off'

Default: 'on'

See Also

“Generate Structured Text from the Model Window” on page 1-14

Show eliminated blocks

Specify whether to insert eliminated block comments. This option is available on the **PLC Code Generation > Comments** node in the Configuration Parameters window.

Settings

Default: off

On

Inserts statements in the generated code from blocks eliminated as the result of optimizations (such as parameter inlining).

Off

Suppresses statements.

Command-Line Information

Parameter: PLC_RTWSHOWELIMINATEDSTATEMENT

Type: string

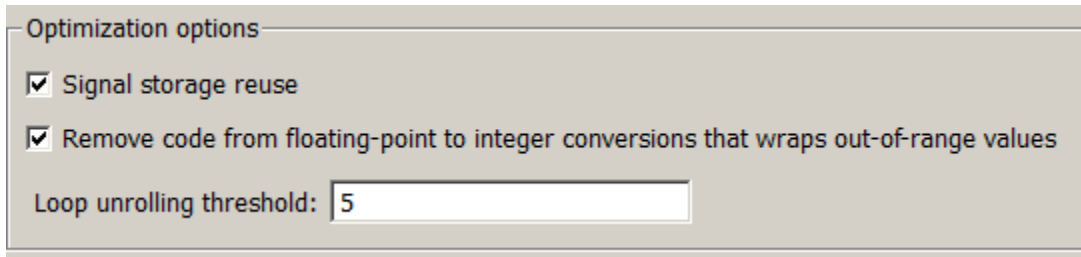
Value: 'on' | 'off'

Default: 'off'

See Also

“Generate Structured Text from the Model Window” on page 1-14

PLC Coder: Optimization



In this section...

“Optimization Overview” on page 12-18

“Signal storage reuse” on page 12-19

“Remove code from floating-point to integer conversions that wraps out-of-range values” on page 12-21

“Loop unrolling threshold” on page 12-22

Optimization Overview

Select the code generation optimization settings.

See Also

“Generate Structured Text from the Model Window” on page 1-14

Signal storage reuse

Reuse signal memory. This option is available on the **PLC Code Generation > Optimization** node in the Configuration Parameters window.

Settings

Default: on



On

Simulink PLC Coder software reuses memory buffers allocated to store block input and output signals, reducing the memory requirement of your real-time program.



Off

Simulink PLC Coder software allocates a separate memory buffer for each block's outputs. This allocation makes block outputs global and unique, which in many cases significantly increases RAM and ROM usage.

Tips

- This option applies only to signals with storage class **Auto**.
- Signal storage reuse can occur among only signals that have the same data type.
- Clearing this option can substantially increase the amount of memory required to simulate large models.
- Clear this option if you need to:
 - Debug a C-MEX S-function.
 - Use a **Floating Scope** or a **Display** block with the **Floating display** option selected to inspect signals in a model that you are debugging.
- If **Signal storage reuse** is enabled and you attempt to use a **Floating Scope** or **floating Display** block to display a signal whose buffer has been reused, Simulink PLC Coder software opens an error dialog.

Command-Line Information

Parameter: PLC_PLCEnableVarReuse

Type: string

Value: 'on' | 'off'

Default: 'on'

See Also

“Generate Structured Text from the Model Window” on page 1-14

Remove code from floating-point to integer conversions that wraps out-of-range values

Enable code removal for efficient casts. This option is available on the **PLC Code Generation > Optimization** node in the Configuration Parameters window.

Settings

Default: on



Simulink PLC Coder software removes code from floating-point to integer conversions.



Simulink PLC Coder software does not remove code from floating-point to integer conversions.

Tips

Use this parameter to optimize code generation.

Command-Line Information

Parameter: PLC_PLCEnableEfficientCast

Type: string

Value: 'on' | 'off'

Default: 'on'

See Also

“Generate Structured Text from the Model Window” on page 1-14

Loop unrolling threshold

Specify the minimum signal or parameter width for which a for loop is generated. This option is available on the **PLC Code Generation > Optimization** node in the Configuration Parameters window.

Settings

Default: 5

Specify the array size at which the code generator begins to use a for loop instead of separate assignment statements to assign values to the elements of a signal or parameter array.

When there are perfectly nested loops, the code generator uses a for loop if the product of the loop counts for all loops in the perfect loop nest is greater than or equal to the threshold.

Command-Line Information

Parameter: PLC_RollThreshold

Type: string

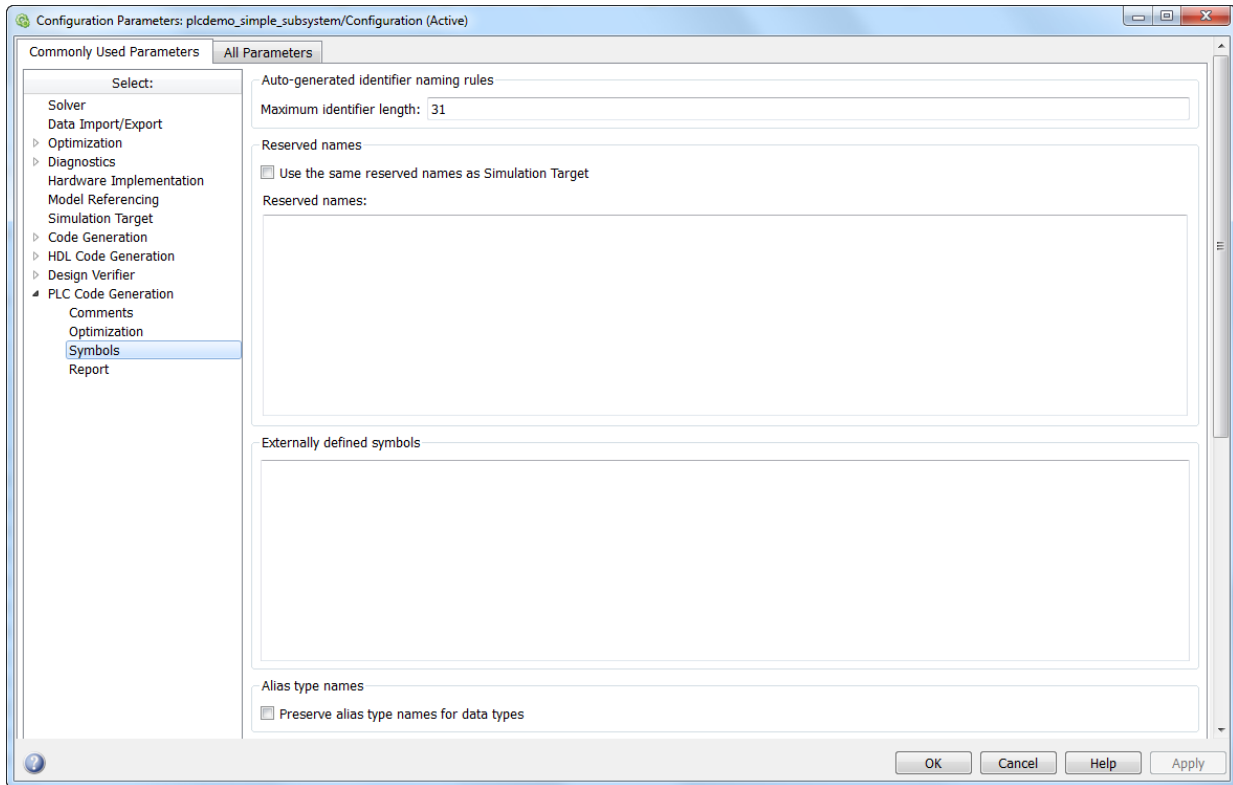
Value: any valid value

Default: '5'

See Also

“Generate Structured Text from the Model Window” on page 1-14

PLC Coder: Symbols



In this section...

“Symbols Overview” on page 12-24

“Maximum identifier length” on page 12-25

“Use the same reserved names as Simulation Target” on page 12-26

“Reserved names” on page 12-27

“Externally Defined Symbols” on page 12-28

“Preserve Alias Type Names for Data Types” on page 12-28

Symbols Overview

Select the automatically generated identifier naming rules.

See Also

“Generate Structured Text from the Model Window” on page 1-14

Maximum identifier length

Specify the maximum number of characters in generated function, type definition, and variable names. This option is available on the **PLC Code Generation > Symbols** node in the Configuration Parameters window.

Settings

Default: 31

Minimum: 31

Maximum: 256

You can use this parameter to limit the number of characters in function, type definition, and variable names. Many target IDEs have their own restrictions. The Simulink PLC Coder software complies with target IDE limitations.

Command-Line Information

Parameter: PLC_RTWMaxIdLength

Type: int

Value: 31 to 256

Default: 31

See Also

“Generate Structured Text from the Model Window” on page 1-14

Use the same reserved names as Simulation Target

Specify whether to use the same reserved names as those specified in the **Simulation Target > Symbols pane**. This option is available on the **PLC Code Generation > Symbols** node in the Configuration Parameters window.

Settings

Default: off



Enables using the same reserved names as those specified in the **Simulation Target > Symbols pane** pane.



Disables using the same reserved names as those specified in the **Simulation Target > Symbols pane** pane.

Command-Line Information

Parameter: PLC_RTWUseSimReservedNames

Type: string

Value: 'on' | 'off'

Default: 'off'

See Also

“Generate Structured Text from the Model Window” on page 1-14

Reserved names

Enter the names of variables or functions in the generated code that you do not want to be used. This option is available on the **PLC Code Generation > Symbols** node in the Configuration Parameters window.

Settings

Default: ()

This action changes the names of variables or functions in the generated code to avoid name conflicts with identifiers in custom code. Reserved names must be shorter than 256 characters.

Tips

- Start each reserved name with a letter or an underscore.
- Each reserved name must contain only letters, numbers, or underscores.
- Separate the reserved names using commas or spaces.

Command-Line Information

Parameter: PLC_RTWRReservedNames

Type: string

Value: string

Default: ''

See Also

“Generate Structured Text from the Model Window” on page 1-14

Externally Defined Symbols

Specify the names of identifiers for which you want to suppress definitions. This option is available on the **PLC Code Generation > Symbols** node in the Configuration Parameters window.

Settings

Default: ()

This action suppresses the definition of identifiers, such as those for function blocks, variables, constants, and user types in the generated code. This suppression allows the generated code to refer to these identifiers. When you import the generated code into the PLC IDE, you must provide these definitions.

Tips

- Start each name with a letter or an underscore.
- Each name must contain only letters, numbers, or underscores.
- Separate the names using spaces or commas.

Command-Line Information

Parameter: PLC_ExternalDefinedNames

Type: string

Value: string

Default: ''

See Also

- “Generate Structured Text from the Model Window” on page 1-14
- “Integrate Externally Defined Symbols” on page 7-2
- Integrating User Defined Function Blocks, Data Types, and Global Variables into Generated Structured Text

Preserve Alias Type Names for Data Types

Specify that the generated code must preserve alias data types from your model. This option is available on the **PLC Code Generation > Symbols** node in the Configuration Parameters window.

Using the `Simulink.AliasType` class, you can create an alias for a built-in Simulink data type. If you assign an alias data type to signals and parameters in your model, when you use this option, the generated code uses your alias data type to define variables corresponding to the signals and parameters.

For instance, you can create an alias `SAFEBOOL` from the base data type `boolean`. If you assign the type `SAFEBOOL` to signals and parameters in your model, the variables in the generated code corresponding to those signals and parameters also have the type `SAFEBOOL`. Using this alias type `SAFEBOOL`, you can conform to PLCOpen safety specifications that suggest using safe data types for differentiation between safety-relevant and standard signals.

Settings

Default: off

On

The generated code preserves alias data types from your model.

For your generated code to be successfully imported to your target IDE, the IDE must support your alias names.

Off

The generated code does not preserve alias types from your model. Instead, the base type of the `Simulink.AliasType` class determines the variable data type in generated code.

Tips

The alias you define for a Simulink type must have the same semantic meaning as the base Simulink type. It must not be a data type already supported in Structured Text and semantically different from the base Simulink type. For instance, `WORD` is a data type supported in Structured Text but is semantically different from an integer type. If you define an alias `WORD` for a Simulink built-in integer type, for instance `uint16`, and preserve the alias name, the type `WORD` that appears in your generated code will be used semantically as a `WORD` and not as an `INT`. The generated code will have a different meaning from that of the model.

Command-Line Information

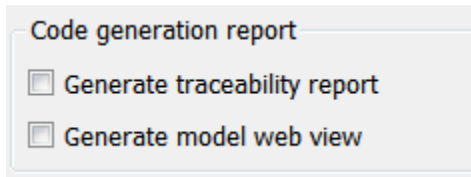
Parameter: `PLC_PreserveAliasType`

Type: string

Value: 'on' | 'off'

Default: 'off'

PLC Coder: Report



In this section...

“Report Overview” on page 12-31

“Generate traceability report” on page 12-31

“Generate model Web view” on page 12-33

Report Overview

Specify whether a report must be produced, following code generation. Control the appearance and contents of the report.

The code generation report shows a mapping between Simulink model objects and locations in the generated code. The report also shows static code metrics about files, global variables and function blocks.

See Also

“Generate Structured Text from the Model Window” on page 1-14

Generate traceability report

Specify whether to create a code generation report. This option is available on the **PLC Code Generation > Report** node in the Configuration Parameters window.

Settings

Default: off

On

Creates code generation report as HTML file.

Off

Suppresses creation of code generation report.

Command-Line Information

Parameter: PLC_GenerateReport

Type: string

Value: 'on' | 'off'

Default: 'off'

See Also

“Generate Structured Text from the Model Window” on page 1-14

Generate model Web view

Include the model Web view in the code generation report to navigate between the code and the model within the same window. This option is available on the **PLC Code Generation > Report** node in the Configuration Parameters window.

You can share your model and generated code outside of the MATLAB environment. You need a Simulink Report Generator license to include a Web view of the model in the code generation report.

Settings

Default: Off

On

Include model Web view in the code generation report.

Off

Omit model Web view in the code generation report.

Command-Line Information

Parameter: PLC_GenerateWebView

Type: string

Value: 'on' | 'off'

Default: 'off'

See Also

“Generate Structured Text from the Model Window” on page 1-14

