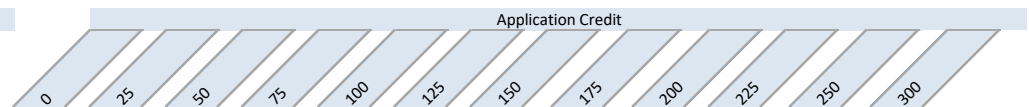
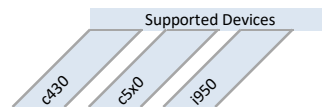


		Supported Devices			Application Credit													
		c430	C5x0	i950	0	25	50	75	100	125	150	175	200	225	250	300		
FAST Runtime		X	X	X	X													
FAST Motion (Kinematics see below)	Motion Control (L_MC1P, L_MC2P) *1)	X	X	X							X							
	Coordinated Motion (L_MC4P) *2)		X													X		
	Robot Kinematics (L_MK4P)		X															
	Robot Kinematics Export (L_MK4E)		X															
	FAST ApplicationTemplate 2.0	X	X		X													
i950 Base	Cia402 [0]			X	X													
FAST Technology Application (i950)	Cia402 Advanced [1]			X			X											
	Speed Control [10]			X			X											
	Table Positioning [20]			X			X											
	Electronic Gearbox [40]			X			X											
	Sync And Correction [41]			X					X									
	Winder Dancer-controlled [50]			X					X									
	Winder Tension-controlled [51]			X					X									
i950 PLC	User [10000]			X					X									
FAST Technology Application Project Template (i950)	Cia402 Advanced [10000]			X											X			
	Speed Control [10000]			X						X								
	Table Positioning [10000]			X							X							
	Electronic Gearbox [10000]			X							X							
	Sync And Correction [10000]			X										X				
	Winder Dancer-controlled [10000]			X									X					
	Winder Tension-controlled [1000]			X									X					

		Supported Devices			Application Credit												
		C430	C5x0	I950	0	25	50	75	100	125	150	175	200	225	250	300	
Selectable Fieldbus	EtherCAT Device	X								X							
	Profinet Device	X									X						
FAST Technology modules V2	Temperature Control (L_TP2P)	X	X	X			X										
	Basic Motion (L_TB2P)	X	X	X		X											
	FollowSetValues (TF2P)	X	X	X		X											
	Speed Control (L_TF2P)	X	X	X		X											
	Virtual Master (L_TF2P)	X	X	X		X											
	Table Positioning (L_TF2P)	X	X	X			X										
	Electronic Gearbox (L_TS2P)	X	X	X		X											
	SyncPos (L_TS2P)	X	X	X		X											
	FlexCam (L_TS2P)	X	X	X			X										
	CrossCutter (L_TS2P)	X	X	X					X								
	Sync & Correction (L_TS2P)	X	X	X					X								
	FlyingSaw (L_TS2P)	X	X	X					X								
	Traverser (L_TW2P) (only available in AKB)	X	X	X					X								
	Winder (L_TW2P)	X	X	X					X								
	StackerCraneAxisControl (L_TV2P)	X	X	X			X										
	PickAndPlace (L_TX2P; only on request))		X						X								
	CoordinatedMotion (L_TC2P; only on request)		X						X								

		Supported Devices				Application Credit													
		C430	C540	I950		0	25	50	75	100	125	150	175	200	225	250	300		
FAST Robot Kinematics	Portal (3 and 4 dof)		X			X													
	Belt Kinematic (2 dof)		X			X													
	Scara robot (3 and 4 dof)		X							X									
	Delta2 (2 dof)		X							X									
	Delta3 (3, 4 and 5 dof)		X							X									
	Linear Delta3 (3 and 4 dof)		X							X									
	ArticulatedP (Palletizer; 4 dof)		X							X									
	Linear Delta3 (3 and 4 dof) *3)		X							X									
	Portal (5 dof) *3)		X							X									
Additional	L_ICIA_CommunicationInterface *8)			X								X							
	L_CT1P_TorquePreControl	X	X	X			X												
	L_CT1P_TorquePreControl	X	X	X			X												
	L_CT1P_OnlineIdentStiffMechanics	X	X	X			X												
	L_CT1P_OnlineIdentStiffMechanicsDouble	X	X	X			X												
	L_MC4P_GroupTorquePreControl		X					X											
Add On	OPC UA extended 2 *5)	X								X									
	OPC UA extended 3 *7)		X									X							
	Additional EASY UI web clients *6)	X	X						X										

Green Application credits only required once (per use)
Blue Application credits required per instance



*1) Application credits are only calculated if one or more of the following FBs are used MC_Halt MC_HaltSuperimposed MC_Home MC_MoveAbsolute MC_MoveAdditive MC_MoveContinuousAbsolute MC_MoveContinuousRelative MC_MoveRelative MC_MoveSuperimposed MC_MoveVelocity MC_Stop L_MC1P_AxisBasicControl L_MC1P_AxisBasicControlV2 L_MC1P_FollowSetValues L_MC1P_ManualJog L_MC1P_TorqueControl L_MC1P_ControlSetValues L_MC2P_TappetRegister L_MC2P_ResetPhasing MC_CamIn MC_GearIn MC_GearInPos MC_PhasingAbsolute MC_PhasingRelative MC_CombineAxes
*8) Library L_ICIA_CommunicationInterface only available at AKB (Internet). Required for Migration of Global Drive Inverters.

*2) Application credits are only calculated if one or more of the following FBs are used MC_GroupHome MC_GroupStop MC_MovePath MC_TrackConveyorBelt L_MC4P_AxesGroupBasicControl MC_MoveCircularAbsolute MC_MoveCircularRelative MC_MoveDirectAbsolute MC_MoveDirectRelative MC_MoveLinearAbsolute MC_MoveLinearRelative L_MC4P_GroupWaitTime L_MC4P_MoveEllipticalAbsolute L_MC4P_MoveEllipticalAbsolutePnP L_MC4P_MoveEllipticalRelative L_MC4P_MoveSplineAbsolute L_MC4P_MoveSplinePnP L_MC4P_MoveSplineRelative
*3) Dual Use license required (0x2012:3 = Available [1])
*4) Since release V3.23 all technology modules V2 can now also be used on the controller 3200C, p500 and c300
*5) Basically one OPC UA client/server connection is possible. For more connections or pub/sub communication (incl. SKS), the extended package 2 is required. Then max. 4 connections each can be used in parallel.
*6) Two visualisation web clients are part of the standard license. Application credit needs to be respected per connected client starting from the third client
*7) Basically one OPC UA client/server connection is possible. For more connections or pub/sub communication (incl. SKS), the extended package 3 is required. Then max. 6 (for c520) respectively 12 (for c550) connections each can be used in parallel.