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**AMENDMENT 2**  
1997-12-15

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**Industrial automation systems —  
Manufacturing message specification —**

**Part 3:**

Companion standard for robotics

**AMENDMENT 2: Revision to conformance**

iTeh STANDARD PREVIEW

*Systèmes d'automatisation industrielle — Système de messagerie  
industrielle*

*Partie 3: Norme d'accompagnement pour la robotique*

ISO/IEC 9506-3:1991/Amd 2:1997

**AMENDEMENT 2: Révision pour conformité**

<https://standards.iteh.ai/catalog/standards/sis/9506-3-1991/amd-2-1997>  
459287baf8c1/iso-iec-9506-3-1991-amd-2-1997



## Foreword

ISO (the International Organization for Standardization) is a worldwide federation of national standards bodies (ISO member bodies). The work of preparing International Standards is normally carried out through ISO technical committees. Each member body interested in a subject for which a technical committee has been established has the right to be represented on that committee. International organizations, governmental and non-governmental, in liaison with ISO, also take part in the work. ISO collaborates closely with the International Electrotechnical Commission (IEC) on all matters of electrotechnical standardization.

Draft International Standards adopted by the technical committees are circulated to the member bodies for voting. Publication as an International Standard requires approval by at least 75 % of the member bodies casting a vote.

Amendment 2 to International Standard ISO/IEC 9506-3:1991 was prepared by Technical Committee ISO/TC 184, *Industrial automation systems and integration*.

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## Introduction

This Amendment details the textual changes to ISO/IEC 9506-3 to remove the definitions of the conformance classes from the standard and allow them to be specified by an International Standardized Profile (ISP). At the time the standard was developed, the ISP process was not yet in place for specifying profiles. Now that the ISP process has been established, it is appropriate to move the definition of conformance classes (profiles) from the base standard to the ISP document.

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# Industrial automation systems — Manufacturing message specification —

## Part 3:

### Companion standard for robotics

### AMENDMENT 2: Revision to conformance

*On page vi, in the Introduction, delete the third paragraph. The text should now read:*

#### Introduction

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This part of ISO/IEC 9506 is intended to be used in an open communication system employing robots and robotic systems connected to a communication network conforming to the OSI model (ISO 7498). This part of ISO/IEC 9506 also recognizes that the robot can act as a controller (client) to devices connected to it such as vision systems and grippers. Client conformance for communication to such devices is not defined by this part of ISO/IEC 9506. Conformance requirements for communication to such devices are defined by the companion Standard appropriate to that device or by ISO/IEC 9506-1 and ISO/IEC 9506-2.

This part of ISO/IEC 9506 does define conformance requirements for the robot when used in a network with multiple clients. The messages are described using the method defined in ISO 8824.

This part of ISO/IEC 9506 also recognizes that the robot can act as a controller to devices connected to it such as vision systems and grippers. This part of ISO/IEC 9506 identifies the requirements for communications in such a manner but does not identify MMS service and protocol conformance requirements for the robot when acting in a client role. These requirements are identified by the companion standard covering the device to which the robot intends to communicate.

MMS is intended to be used with yet other standards designed to achieve a systematic and uniform approach to Open Systems Interconnection of Information Processing Systems as defined in ISO 7498. As such, MMS is positioned within the application layer of the OSI model. It defines the Application Service Element and the protocol required to extend information systems networks to the programmable control devices of the automated factory environment. The services defined by MMS are generic and intended to be referenced by the companion standards, each of which is oriented towards a more specific class of application.

This part of ISO/IEC 9506 recognizes that safe operation of robots is required at all times. Safety requirements for robots are specified in ISO DIS 10218. All robot actions delineated in this part of ISO/IEC 9506 are permissible under the safety standard.

Implementation of this part of ISO/IEC 9506 requires a minimum implementation of MMS. This is covered in Clause 9 which references the conformance requirements of ISO/IEC 9506-1 and 2. Implementers of MMS for robots and robotic systems should have a thorough understanding of MMS for proper implementation of this part of ISO/IEC 9506. Implementers should also have a thorough understanding of the modeling, services and protocol defined in this part of ISO/IEC 9506. Users of robots and robotic systems are directed to the clauses on modeling and services found in this document.

For the purpose of this part of ISO/IEC 9506, the term "robot" means "manipulating industrial robot" as defined in ISO/TR 8373. As used in this part of ISO/IEC 9506, a robot will generally refer to the manipulator together with its control system and any ancillary equipment, devices, sensors, or communications links, necessary for the robot to perform its task. Figure 1 illustrates the elements of the robot system as described in this part of ISO/IEC 9506. Since the definitions of ISO/TR 8373 only describe robot systems with a single arm and this part of ISO/IEC 9506 anticipates robots with multiple arms operating in a coordinated fashion, these definitions have been generalized. The term "robot system controller" will refer to the (single) task program operating with the (possible multiple) control program of the robot arm(s) of the system.

"MMS services" refers to the abstract services defined in ISO/IEC 9506-1 and "MMS protocol" refers to the protocol defined in ISO/IEC 9506-2.

*On page 1, under Scope, delete item d).*

*On page 5, clause 5.1.1, delete the first sentence.*

*On page 94, clause 9, replace the text of 9.1, 9.2, and 9.3 in this clause with the following:*

<https://standards.iteh.ai/catalog/standards/sist/9c6ce758-5fa2-47f5-80a6-459287baf8c1/iso-iec-9506-3-1991-amd-2-1997>

**9 Robot conformance** <https://standards.iteh.ai/catalog/standards/sist/9c6ce758-5fa2-47f5-80a6-459287baf8c1/iso-iec-9506-3-1991-amd-2-1997>

#### 9.1 General

Flexible application of robots requires that they be connected to a network and have their activities coordinated with other equipment. As described earlier, there are two fundamental modes of operation of a robot - as a client device and as a server device. The robot may function in either or both modes simultaneously. However, the services and conformance requirements of the robot when acting as a client and responding as a server, are considered separately.

#### 9.2 Robot server conformance

##### 9.2.1 General requirements

Minimum requirements for all MMS responders are prescribed in 17.9 of ISO/IEC 9506-2:1990. These minimum requirements includes support for the responder role for

- Initiate,
- Conclude,
- Abort,
- Reject and
- Identify.

This requirement applies with equal force to any implementation claiming conformance to the abstract syntax defined in this part of ISO/IEC 9506.

### 9.2.2 Further requirements on Robot acting as a Server

Further requirements for robots acting as servers under the abstract syntax defined in this part of ISO/IEC 9506 will be found in the International Standardized Profiles referencing this standard.

### 9.3 Robot client conformance

#### 9.3.1 General requirements

In this case the robot system controller provides "host" services to attached devices. While it is not possible for this part of ISO/IEC 9506 to enumerate all such possible devices, several are obvious.

- vision and other sensors.
- grippers and other manipulators
- 'axis extenders' such as 'x-y' positioners
- AGVs and other robots

This part of ISO/IEC 9506 makes no statement about the conformance of attached devices (except in the case of a robot acting as a client to another robot in a server role). The conformance required of the robot acting in a 'host' capacity is described. The MMS requirements of such a robot system controller are complementary to those MMS services supported by the attached server device.

***Delete Annex B .***

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**ICS 25.040.30**

**Descriptors:** automation, automation engineering, manufacturing, messages, industrial robots, computer applications, data processing, information interchange, network interconnection, open systems interconnection, communication procedure.

Price based on 3 pages

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