# libximc

2.13.1

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# Contents


**1 libximc library** **1**

1.1 What the controller does. . . . 1

1.2 What can do libximc library . . . 1

1.3 Assistance. . . . 2

**2 Introduction** **3**

2.1 About library . . . 3

2.2 System requirements . . . 3

2.2.1 For rebuilding library . . . 3

2.2.2 For using library . . . 4

**3 How to rebuild library** **5**

3.1 Building on generic UNIX . . . 5

3.2 Building on debian-based linux systems . . . 5

3.3 Building on redhat-based linux systems . . . 5

3.4 Buliding on Mac OS X . . . 6

3.5 Buliding on Windows . . . 6

3.6 Source code access . . . 6

**4 How to use with...** **7**

4.1 Usage with C . . . 7

4.1.1 Visual C++ . . . 7

4.1.2 CodeBlocks . . . 7

4.1.3 MinGW . . . 7

4.1.4 C++ Builder . . . 8

4.1.5 XCode . . . 8

4.1.6 GCC . . . 8

4.2 .NET . . . 9

4.3 Delphi . . . 9

4.4 Java . . . 9

4.5 Python . . . 10

4.6 MATLAB . . . 10

4.7 Generic logging facility . . . 10
4.8 Required permissions . . . 11
4.9 C-profiles . . . 11

**5 Working with custom units** **12**
5.1 The structure of the conversion units calibration_t . . . 12
5.2 Alternative functions for working with custom units and data structures for them . . . 12
5.3 Coordinate correction table for more accurate positioning . . . 12

**6 Data Structure Documentation** **14**
6.1 accessories_settings_t Struct Reference . . . 14
6.1.1 Detailed Description . . . 14
6.1.2 Field Documentation . . . 15
6.1.2.1 LimitSwitchesSettings . . . 15
6.1.2.2 MagneticBrakeInfo . . . 15
6.1.2.3 MBRatedCurrent . . . 15
6.1.2.4 MBRatedVoltage . . . 15
6.1.2.5 MBSettings . . . 15
6.1.2.6 MBTorque . . . 15
6.1.2.7 TemperatureSensorInfo . . . 15
6.1.2.8 TSGrad . . . 15
6.1.2.9 TSMax . . . 15
6.1.2.10 TSMin . . . 15
6.1.2.11 TSSettings . . . 15
6.2 analog_data_t Struct Reference . . . 16
6.2.1 Detailed Description . . . 17
6.2.2 Field Documentation . . . 17
6.2.2.1 A1Voltage . . . 17
6.2.2.2 A1Voltage_ADC . . . 17
6.2.2.3 A2Voltage . . . 17
6.2.2.4 A2Voltage_ADC . . . 17
6.2.2.5 ACurrent . . . 17
6.2.2.6 ACurrent_ADC . . . 17
6.2.2.7 B1Voltage . . . 18
6.2.2.8 B1Voltage_ADC . . . 18
6.2.2.9 B2Voltage . . . 18
6.2.2.10 B2Voltage_ADC . . . 18
6.2.2.11 BCurrent . . . 18
6.2.2.12 BCurrent_ADC . . . 18
6.2.2.13 FullCurrent . . . 18
6.2.2.14 FullCurrent_ADC . . . 18

6.2.2.15 H5 . . . 18
6.2.2.16 Joy . . . 18
6.2.2.17 Joy_ADC . . . 18
6.2.2.18 L . . . 18
6.2.2.19 L5 . . . 19
6.2.2.20 L5_ADC . . . 19
6.2.2.21 Pot . . . 19
6.2.2.22 R . . . 19
6.2.2.23 SupVoltage . . . 19
6.2.2.24 SupVoltage_ADC . . . 19
6.2.2.25 Temp . . . 19
6.2.2.26 Temp_ADC . . . 19
6.3 brake_settings_t Struct Reference . . . 19
6.3.1 Detailed Description . . . 20
6.3.2 Field Documentation . . . 20
6.3.2.1 BrakeFlags . . . 20
6.3.2.2 t1 . . . 20
6.3.2.3 t2 . . . 20
6.3.2.4 t3 . . . 20
6.3.2.5 t4 . . . 20
6.4 calibration_settings_t Struct Reference . . . 20
6.4.1 Detailed Description . . . 21
6.4.2 Field Documentation . . . 21
6.4.2.1 CSS1_A . . . 21
6.4.2.2 CSS1_B . . . 21
6.4.2.3 CSS2_A . . . 21
6.4.2.4 CSS2_B . . . 21
6.4.2.5 FullCurrent_A . . . 21
6.4.2.6 FullCurrent_B . . . 21
6.5 calibration_t Struct Reference . . . 21
6.5.1 Detailed Description . . . 22
6.6 chart_data_t Struct Reference . . . 22
6.6.1 Detailed Description . . . 22
6.6.2 Field Documentation . . . 22
6.6.2.1 DutyCycle . . . 22
6.6.2.2 Joy . . . 23
6.6.2.3 Pot . . . 23
6.6.2.4 WindingCurrentA . . . 23
6.6.2.5 WindingCurrentB . . . 23
6.6.2.6 WindingCurrentC . . . 23

6.6.2.7 WindingVoltageA . . . 23
6.6.2.8 WindingVoltageB . . . 23
6.6.2.9 WindingVoltageC . . . 23
6.7 control_settings_calb_t Struct Reference . . . 23
6.7.1 Detailed Description . . . 24
6.7.2 Field Documentation . . . 24
6.7.2.1 Flags . . . 24
6.7.2.2 MaxClickTime . . . 24
6.7.2.3 MaxSpeed . . . 24
6.7.2.4 Timeout . . . 24
6.8 control_settings_t Struct Reference . . . 24
6.8.1 Detailed Description . . . 25
6.8.2 Field Documentation . . . 25
6.8.2.1 Flags . . . 25
6.8.2.2 MaxClickTime . . . 25
6.8.2.3 MaxSpeed . . . 25
6.8.2.4 Timeout . . . 26
6.8.2.5 uDeltaPosition . . . 26
6.8.2.6 uMaxSpeed . . . 26
6.9 controller_name_t Struct Reference . . . 26
6.9.1 Detailed Description . . . 26
6.9.2 Field Documentation . . . 26
6.9.2.1 ControllerName . . . 26
6.9.2.2 CtrlFlags . . . 26
6.10 ctp_settings_t Struct Reference . . . 27
6.10.1 Detailed Description . . . 27
6.10.2 Field Documentation . . . 27
6.10.2.1 CTPFlags . . . 27
6.10.2.2 CTPMinError . . . 27
6.11 debug_read_t Struct Reference . . . 27
6.11.1 Detailed Description . . . 28
6.11.2 Field Documentation . . . 28
6.11.2.1 DebugData . . . 28
6.12 debug_write_t Struct Reference . . . 28
6.12.1 Detailed Description . . . 28
6.12.2 Field Documentation . . . 28
6.12.2.1 DebugData . . . 28
6.13 device_information_t Struct Reference . . . 28
6.13.1 Detailed Description . . . 29
6.13.2 Field Documentation . . . 29

6.13.2.1 Major . . . 29
6.13.2.2 Minor . . . 29
6.13.2.3 Release . . . 29
6.14 device_network_information_t Struct Reference . . . 29
6.14.1 Detailed Description . . . 30
6.15 edges_settings_calb_t Struct Reference . . . 30
6.15.1 Detailed Description . . . 30
6.15.2 Field Documentation . . . 30
6.15.2.1 BorderFlags . . . 30
6.15.2.2 EnderFlags . . . 30
6.15.2.3 LeftBorder . . . 30
6.15.2.4 RightBorder . . . 31
6.16 edges_settings_t Struct Reference . . . 31
6.16.1 Detailed Description . . . 31
6.16.2 Field Documentation . . . 31
6.16.2.1 BorderFlags . . . 31
6.16.2.2 EnderFlags . . . 31
6.16.2.3 LeftBorder . . . 31
6.16.2.4 RightBorder . . . 32
6.16.2.5 uLeftBorder . . . 32
6.16.2.6 uRightBorder . . . 32
6.17 emf_settings_t Struct Reference . . . 32
6.17.1 Detailed Description . . . 32
6.17.2 Field Documentation . . . 32
6.17.2.1 BackEMFFlags . . . 32
6.17.2.2 Km . . . 33
6.17.2.3 L . . . 33
6.17.2.4 R . . . 33
6.18 encoder_information_t Struct Reference . . . 33
6.18.1 Detailed Description . . . 33
6.18.2 Field Documentation . . . 33
6.18.2.1 Manufacturer . . . 33
6.18.2.2 PartNumber . . . 33
6.19 encoder_settings_t Struct Reference . . . 33
6.19.1 Detailed Description . . . 34
6.19.2 Field Documentation . . . 34
6.19.2.1 EncoderSettings . . . 34
6.19.2.2 MaxCurrentConsumption . . . 34
6.19.2.3 MaxOperatingFrequency . . . 34
6.19.2.4 SupplyVoltageMax . . . 34

6.19.2.5 SupplyVoltageMin . . . 34
6.20 engine_advansed_setup_t Struct Reference . . . 35
6.20.1 Detailed Description . . . 35
6.20.2 Field Documentation . . . 35
6.20.2.1 stepcloseloop_Kp_high . . . 35
6.20.2.2 stepcloseloop_Kp_low . . . 35
6.20.2.3 stepcloseloop_Kw . . . 35
6.21 engine_settings_calb_t Struct Reference . . . 35
6.21.1 Detailed Description . . . 36
6.21.2 Field Documentation . . . 36
6.21.2.1 Antiplay . . . 36
6.21.2.2 EngineFlags . . . 36
6.21.2.3 MicrostepMode . . . 36
6.21.2.4 NomCurrent . . . 36
6.21.2.5 NomSpeed . . . 36
6.21.2.6 NomVoltage . . . 37
6.21.2.7 StepsPerRev . . . 37
6.22 engine_settings_t Struct Reference . . . 37
6.22.1 Detailed Description . . . 37
6.22.2 Field Documentation . . . 38
6.22.2.1 Antiplay . . . 38
6.22.2.2 EngineFlags . . . 38
6.22.2.3 MicrostepMode . . . 38
6.22.2.4 NomCurrent . . . 38
6.22.2.5 NomSpeed . . . 38
6.22.2.6 NomVoltage . . . 38
6.22.2.7 StepsPerRev . . . 38
6.22.2.8 uNomSpeed . . . 38
6.23 entype_settings_t Struct Reference . . . 38
6.23.1 Detailed Description . . . 39
6.23.2 Field Documentation . . . 39
6.23.2.1 DriverType . . . 39
6.23.2.2 EngineType . . . 39
6.24 extended_settings_t Struct Reference . . . 39
6.24.1 Detailed Description . . . 39
6.25 extio_settings_t Struct Reference . . . 40
6.25.1 Detailed Description . . . 40
6.25.2 Field Documentation . . . 40
6.25.2.1 EXTIOModeFlags . . . 40
6.25.2.2 EXTIOSetupFlags . . . 40

6.26 feedback_settings_t Struct Reference . . . 40
6.26.1 Detailed Description . . . 41
6.26.2 Field Documentation . . . 41
6.26.2.1 CountsPerTurn . . . 41
6.26.2.2 FeedbackFlags . . . 41
6.26.2.3 FeedbackType . . . 41
6.26.2.4 IPS . . . 41
6.27 gear_information_t Struct Reference . . . 41
6.27.1 Detailed Description . . . 41
6.27.2 Field Documentation . . . 42
6.27.2.1 Manufacturer . . . 42
6.27.2.2 PartNumber . . . 42
6.28 gear_settings_t Struct Reference . . . 42
6.28.1 Detailed Description . . . 42
6.28.2 Field Documentation . . . 42
6.28.2.1 Efficiency . . . 42
6.28.2.2 InputInertia . . . 43
6.28.2.3 MaxOutputBacklash . . . 43
6.28.2.4 RatedInputSpeed . . . 43
6.28.2.5 RatedInputTorque . . . 43
6.28.2.6 ReductionIn . . . 43
6.28.2.7 ReductionOut . . . 43
6.29 get_position_calb_t Struct Reference . . . 43
6.29.1 Detailed Description . . . 43
6.29.2 Field Documentation . . . 44
6.29.2.1 EncPosition . . . 44
6.29.2.2 Position . . . 44
6.30 get_position_t Struct Reference . . . 44
6.30.1 Detailed Description . . . 44
6.30.2 Field Documentation . . . 44
6.30.2.1 EncPosition . . . 44
6.30.2.2 uPosition . . . 44
6.31 globally_unique_identifier_t Struct Reference . . . 45
6.31.1 Detailed Description . . . 45
6.31.2 Field Documentation . . . 45
6.31.2.1 UniqueID0 . . . 45
6.31.2.2 UniqueID1 . . . 45
6.31.2.3 UniqueID2 . . . 45
6.31.2.4 UniqueID3 . . . 45
6.32 hallsensor_information_t Struct Reference . . . 45

6.32.1 Detailed Description . . . 46
6.32.2 Field Documentation . . . 46
6.32.2.1 Manufacturer . . . 46
6.32.2.2 PartNumber . . . 46
6.33 hallsensor_settings_t Struct Reference . . . 46
6.33.1 Detailed Description . . . 46
6.33.2 Field Documentation . . . 47
6.33.2.1 MaxCurrentConsumption . . . 47
6.33.2.2 MaxOperatingFrequency . . . 47
6.33.2.3 SupplyVoltageMax . . . 47
6.33.2.4 SupplyVoltageMin . . . 47
6.34 home_settings_calb_t Struct Reference . . . 47
6.34.1 Detailed Description . . . 47
6.34.2 Field Documentation . . . 48
6.34.2.1 FastHome . . . 48
6.34.2.2 HomeDelta . . . 48
6.34.2.3 HomeFlags . . . 48
6.34.2.4 SlowHome . . . 48
6.35 home_settings_t Struct Reference . . . 48
6.35.1 Detailed Description . . . 48
6.35.2 Field Documentation . . . 49
6.35.2.1 FastHome . . . 49
6.35.2.2 HomeDelta . . . 49
6.35.2.3 HomeFlags . . . 49
6.35.2.4 SlowHome . . . 49
6.35.2.5 uFastHome . . . 49
6.35.2.6 uHomeDelta . . . 49
6.35.2.7 uSlowHome . . . 49
6.36 init_random_t Struct Reference . . . 49
6.36.1 Detailed Description . . . 50
6.36.2 Field Documentation . . . 50
6.36.2.1 key . . . 50
6.37 joystick_settings_t Struct Reference . . . 50
6.37.1 Detailed Description . . . 50
6.37.2 Field Documentation . . . 51
6.37.2.1 DeadZone . . . 51
6.37.2.2 ExpFactor . . . 51
6.37.2.3 JoyCenter . . . 51
6.37.2.4 JoyFlags . . . 51
6.37.2.5 JoyHighEnd . . . 51

6.37.2.6 JoyLowEnd . . . 51
6.38 measurements_t Struct Reference . . . 51
6.38.1 Detailed Description . . . 51
6.38.2 Field Documentation . . . 52
6.38.2.1 Error . . . 52
6.38.2.2 Length . . . 52
6.38.2.3 Speed . . . 52
6.39 motor_information_t Struct Reference . . . 52
6.39.1 Detailed Description . . . 52
6.39.2 Field Documentation . . . 52
6.39.2.1 Manufacturer . . . 52
6.39.2.2 PartNumber . . . 53
6.40 motor_settings_t Struct Reference . . . 53
6.40.1 Detailed Description . . . 54
6.40.2 Field Documentation . . . 54
6.40.2.1 DetentTorque . . . 54
6.40.2.2 MaxCurrent . . . 54
6.40.2.3 MaxCurrentTime . . . 54
6.40.2.4 MaxSpeed . . . 54
6.40.2.5 MechanicalTimeConstant . . . 54
6.40.2.6 MotorType . . . 55
6.40.2.7 NoLoadCurrent . . . 55
6.40.2.8 NoLoadSpeed . . . 55
6.40.2.9 NominalCurrent . . . 55
6.40.2.10 NominalPower . . . 55
6.40.2.11 NominalSpeed . . . 55
6.40.2.12 NominalTorque . . . 55
6.40.2.13 NominalVoltage . . . 55
6.40.2.14 Phases . . . 55
6.40.2.15 Poles . . . 55
6.40.2.16 RotorInertia . . . 56
6.40.2.17 SpeedConstant . . . 56
6.40.2.18 SpeedTorqueGradient . . . 56
6.40.2.19 StallTorque . . . 56
6.40.2.20 TorqueConstant . . . 56
6.40.2.21 WindingInductance . . . 56
6.40.2.22 WindingResistance . . . 56
6.41 move_settings_calb_t Struct Reference . . . 56
6.41.1 Detailed Description . . . 57
6.41.2 Field Documentation . . . 57

6.41.2.1 Accel . . . 57
6.41.2.2 AntiplaySpeed . . . 57
6.41.2.3 Decel . . . 57
6.41.2.4 MoveFlags . . . 57
6.41.2.5 Speed . . . 57
6.42 move_settings_t Struct Reference . . . 57
6.42.1 Detailed Description . . . 58
6.42.2 Field Documentation . . . 58
6.42.2.1 Accel . . . 58
6.42.2.2 AntiplaySpeed . . . 58
6.42.2.3 Decel . . . 58
6.42.2.4 MoveFlags . . . 58
6.42.2.5 Speed . . . 58
6.42.2.6 uAntiplaySpeed . . . 59
6.42.2.7 uSpeed . . . 59
6.43 nonvolatile_memory_t Struct Reference . . . 59
6.43.1 Detailed Description . . . 59
6.43.2 Field Documentation . . . 59
6.43.2.1 UserData . . . 59
6.44 pid_settings_t Struct Reference . . . 59
6.44.1 Detailed Description . . . 60
6.45 power_settings_t Struct Reference . . . 60
6.45.1 Detailed Description . . . 60
6.45.2 Field Documentation . . . 60
6.45.2.1 CurrentSetTime . . . 60
6.45.2.2 CurrReductDelay . . . 61
6.45.2.3 HoldCurrent . . . 61
6.45.2.4 PowerFlags . . . 61
6.45.2.5 PowerOffDelay . . . 61
6.46 secure_settings_t Struct Reference . . . 61
6.46.1 Detailed Description . . . 61
6.46.2 Field Documentation . . . 62
6.46.2.1 CriticalIpwr . . . 62
6.46.2.2 CriticalIusb . . . 62
6.46.2.3 CriticalT . . . 62
6.46.2.4 CriticalUpwr . . . 62
6.46.2.5 CriticalUusb . . . 62
6.46.2.6 Flags . . . 62
6.46.2.7 LowUpwrOff . . . 62
6.46.2.8 MinimumUusb . . . 62

6.47 serial_number_t Struct Reference . . . 62
6.47.1 Detailed Description . . . 63
6.47.2 Field Documentation . . . 63
6.47.2.1 Key . . . 63
6.47.2.2 Major . . . 63
6.47.2.3 Minor . . . 63
6.47.2.4 Release . . . 63
6.47.2.5 SN . . . 63
6.48 set_position_calb_t Struct Reference . . . 63
6.48.1 Detailed Description . . . 63
6.48.2 Field Documentation . . . 64
6.48.2.1 EncPosition . . . 64
6.48.2.2 PosFlags . . . 64
6.48.2.3 Position . . . 64
6.49 set_position_t Struct Reference . . . 64
6.49.1 Detailed Description . . . 64
6.49.2 Field Documentation . . . 64
6.49.2.1 EncPosition . . . 64
6.49.2.2 PosFlags . . . 64
6.49.2.3 uPosition . . . 65
6.50 stage_information_t Struct Reference . . . 65
6.50.1 Detailed Description . . . 65
6.50.2 Field Documentation . . . 65
6.50.2.1 Manufacturer . . . 65
6.50.2.2 PartNumber . . . 65
6.51 stage_name_t Struct Reference . . . 65
6.51.1 Detailed Description . . . 66
6.51.2 Field Documentation . . . 66
6.51.2.1 PositionerName . . . 66
6.52 stage_settings_t Struct Reference . . . 66
6.52.1 Detailed Description . . . 66
6.52.2 Field Documentation . . . 67
6.52.2.1 HorizontalLoadCapacity . . . 67
6.52.2.2 LeadScrewPitch . . . 67
6.52.2.3 MaxCurrentConsumption . . . 67
6.52.2.4 MaxSpeed . . . 67
6.52.2.5 SupplyVoltageMax . . . 67
6.52.2.6 SupplyVoltageMin . . . 67
6.52.2.7 TravelRange . . . 67
6.52.2.8 Units . . . 67

6.52.2.9 VerticalLoadCapacity . . . 67
6.53 status_calb_t Struct Reference . . . 68
6.53.1 Detailed Description . . . 68
6.53.2 Field Documentation . . . 69
6.53.2.1 CmdBufFreeSpace . . . 69
6.53.2.2 CurPosition . . . 69
6.53.2.3 CurSpeed . . . 69
6.53.2.4 CurT . . . 69
6.53.2.5 EncPosition . . . 69
6.53.2.6 EncSts . . . 69
6.53.2.7 Flags . . . 69
6.53.2.8 GPIOFlags . . . 69
6.53.2.9 Ipwr . . . 69
6.53.2.10 Iusb . . . 69
6.53.2.11 MoveSts . . . 69
6.53.2.12 MvCmdSts . . . 70
6.53.2.13 PWRSts . . . 70
6.53.2.14 Upwr . . . 70
6.53.2.15 Uusb . . . 70
6.53.2.16 WindSts . . . 70
6.54 status_t Struct Reference . . . 70
6.54.1 Detailed Description . . . 71
6.54.2 Field Documentation . . . 71
6.54.2.1 CmdBufFreeSpace . . . 71
6.54.2.2 CurPosition . . . 71
6.54.2.3 CurSpeed . . . 71
6.54.2.4 CurT . . . 71
6.54.2.5 EncPosition . . . 71
6.54.2.6 EncSts . . . 71
6.54.2.7 Flags . . . 72
6.54.2.8 GPIOFlags . . . 72
6.54.2.9 Ipwr . . . 72
6.54.2.10 Iusb . . . 72
6.54.2.11 MoveSts . . . 72
6.54.2.12 MvCmdSts . . . 72
6.54.2.13 PWRSts . . . 72
6.54.2.14 uCurPosition . . . 72
6.54.2.15 uCurSpeed . . . 72
6.54.2.16 Upwr . . . 72
6.54.2.17 Uusb . . . 72

6.54.2.18 WindSts . . . 73
6.55 sync_in_settings_calb_t Struct Reference . . . 73
6.55.1 Detailed Description . . . 73
6.55.2 Field Documentation . . . 73
6.55.2.1 ClutterTime . . . 73
6.55.2.2 Position . . . 73
6.55.2.3 Speed . . . 73
6.55.2.4 SyncInFlags . . . 73
6.56 sync_in_settings_t Struct Reference . . . 74
6.56.1 Detailed Description . . . 74
6.56.2 Field Documentation . . . 74
6.56.2.1 ClutterTime . . . 74
6.56.2.2 Speed . . . 74
6.56.2.3 SyncInFlags . . . 74
6.56.2.4 uPosition . . . 74
6.56.2.5 uSpeed . . . 75
6.57 sync_out_settings_calb_t Struct Reference . . . 75
6.57.1 Detailed Description . . . 75
6.57.2 Field Documentation . . . 75
6.57.2.1 Accuracy . . . 75
6.57.2.2 SyncOutFlags . . . 75
6.57.2.3 SyncOutPeriod . . . 75
6.57.2.4 SyncOutPulseSteps . . . 76
6.58 sync_out_settings_t Struct Reference . . . 76
6.58.1 Detailed Description . . . 76
6.58.2 Field Documentation . . . 76
6.58.2.1 Accuracy . . . 76
6.58.2.2 SyncOutFlags . . . 76
6.58.2.3 SyncOutPeriod . . . 76
6.58.2.4 SyncOutPulseSteps . . . 77
6.58.2.5 uAccuracy . . . 77
6.59 uart_settings_t Struct Reference . . . 77
6.59.1 Detailed Description . . . 77
6.59.2 Field Documentation . . . 77
6.59.2.1 UARTSetupFlags . . . 77

**7 File Documentation** **78**

7.1 ximc.h File Reference . . . 78
7.1.1 Detailed Description . . . 100
7.1.2 Macro Definition Documentation . . . 100

7.1.2.1 ALARM_ON_DRIVER_OVERHEATING . . . 100
7.1.2.2 BACK_EMF_INDUCTANCE_AUTO . . . 101
7.1.2.3 BACK_EMF_KM_AUTO . . . 101
7.1.2.4 BACK_EMF_RESISTANCE_AUTO . . . 101
7.1.2.5 BORDER_IS_ENCODER . . . 101
7.1.2.6 BORDER_STOP_LEFT . . . 101
7.1.2.7 BORDER_STOP_RIGHT . . . 101
7.1.2.8 BORDERS_SWAP_MISSET_DETECTION . . . 101
7.1.2.9 BRAKE_ENABLED . . . 101
7.1.2.10 BRAKE_ENG_PWROFF . . . 101
7.1.2.11 CONTROL_BTN_LEFT_PUSHED_OPEN . . . 101
7.1.2.12 CONTROL_BTN_RIGHT_PUSHED_OPEN . . . 101
7.1.2.13 CONTROL_MODE_BITS . . . 101
7.1.2.14 CONTROL_MODE_JOY . . . 102
7.1.2.15 CONTROL_MODE_LR . . . 102
7.1.2.16 CONTROL_MODE_OFF . . . 102
7.1.2.17 CTP_ALARM_ON_ERROR . . . 102
7.1.2.18 CTP_BASE . . . 102
7.1.2.19 CTP_ENABLED . . . 102
7.1.2.20 CTP_ERROR_CORRECTION . . . 102
7.1.2.21 DRIVER_TYPE_DISCRETE_FET . . . 102
7.1.2.22 DRIVER_TYPE_EXTERNAL . . . 102
7.1.2.23 DRIVER_TYPE_INTEGRATE . . . 102
7.1.2.24 EEPROM_PRECEDENCE . . . 102
7.1.2.25 ENC_STATE_ABSENT . . . 102
7.1.2.26 ENC_STATE_MALFUNC . . . 103
7.1.2.27 ENC_STATE_OK . . . 103
7.1.2.28 ENC_STATE_REVERS . . . 103
7.1.2.29 ENC_STATE_UNKNOWN . . . 103
7.1.2.30 ENDER_SW1_ACTIVE_LOW . . . 103
7.1.2.31 ENDER_SW2_ACTIVE_LOW . . . 103
7.1.2.32 ENDER_SWAP . . . 103
7.1.2.33 ENGINE_ACCEL_ON . . . 103
7.1.2.34 ENGINE_ANTIPLAY . . . 103
7.1.2.35 ENGINE_CURRENT_AS_RMS . . . 103
7.1.2.36 ENGINE_LIMIT_CURR . . . 103
7.1.2.37 ENGINE_LIMIT_RPM . . . 104
7.1.2.38 ENGINE_LIMIT_VOLT . . . 104
7.1.2.39 ENGINE_MAX_SPEED . . . 104
7.1.2.40 ENGINE_REVERSE . . . 104

7.1.2.41 ENGINE_TYPE_2DC . . . 104
7.1.2.42 ENGINE_TYPE_BRUSHLESS . . . 104
7.1.2.43 ENGINE_TYPE_DC . . . 104
7.1.2.44 ENGINE_TYPE_NONE . . . 104
7.1.2.45 ENGINE_TYPE_STEP . . . 104
7.1.2.46 ENGINE_TYPE_TEST . . . 104
7.1.2.47 ENUMERATE_PROBE . . . 104
7.1.2.48 EXTIO_SETUP_INVERT . . . 105
7.1.2.49 EXTIO_SETUP_MODE_IN_ALARM . . . 105
7.1.2.50 EXTIO_SETUP_MODE_IN_BITS . . . 105
7.1.2.51 EXTIO_SETUP_MODE_IN_HOME . . . 105
7.1.2.52 EXTIO_SETUP_MODE_IN_MOVR . . . 105
7.1.2.53 EXTIO_SETUP_MODE_IN_NOP . . . 105
7.1.2.54 EXTIO_SETUP_MODE_IN_PWOF . . . 105
7.1.2.55 EXTIO_SETUP_MODE_IN_STOP . . . 105
7.1.2.56 EXTIO_SETUP_MODE_OUT_ALARM . . . 105
7.1.2.57 EXTIO_SETUP_MODE_OUT_BITS . . . 105
7.1.2.58 EXTIO_SETUP_MODE_OUT_MOTOR_ON . . . 105
7.1.2.59 EXTIO_SETUP_MODE_OUT_MOVING . . . 105
7.1.2.60 EXTIO_SETUP_MODE_OUT_OFF . . . 106
7.1.2.61 EXTIO_SETUP_MODE_OUT_ON . . . 106
7.1.2.62 EXTIO_SETUP_OUTPUT . . . 106
7.1.2.63 FEEDBACK_EMF . . . 106
7.1.2.64 FEEDBACK_ENC_REVERSE . . . 106
7.1.2.65 FEEDBACK_ENC_TYPE_AUTO . . . 106
7.1.2.66 FEEDBACK_ENC_TYPE_BITS . . . 106
7.1.2.67 FEEDBACK_ENC_TYPE_DIFFERENTIAL . . . 106
7.1.2.68 FEEDBACK_ENC_TYPE_SINGLE_ENDED . . . 106
7.1.2.69 FEEDBACK_ENCODER . . . 106
7.1.2.70 FEEDBACK_ENCODER_MEDIATED . . . 106
7.1.2.71 FEEDBACK_NONE . . . 106
7.1.2.72 H_BRIDGE_ALERT . . . 107
7.1.2.73 HOME_DIR_FIRST . . . 107
7.1.2.74 HOME_DIR_SECOND . . . 107
7.1.2.75 HOME_HALF_MV . . . 107
7.1.2.76 HOME_MV_SEC_EN . . . 107
7.1.2.77 HOME_STOP_FIRST_BITS . . . 107
7.1.2.78 HOME_STOP_FIRST_LIM . . . 107
7.1.2.79 HOME_STOP_FIRST_REV . . . 107
7.1.2.80 HOME_STOP_FIRST_SYN . . . 107

7.1.2.81 HOME_STOP_SECOND_BITS . . . 107
7.1.2.82 HOME_STOP_SECOND_LIM . . . 107
7.1.2.83 HOME_STOP_SECOND_REV . . . 107
7.1.2.84 HOME_STOP_SECOND_SYN . . . 108
7.1.2.85 HOME_USE_FAST . . . 108
7.1.2.86 JOY_REVERSE . . . 108
7.1.2.87 LOW_UPWR_PROTECTION . . . 108
7.1.2.88 MICROSTEP_MODE_FRAC_128 . . . 108
7.1.2.89 MICROSTEP_MODE_FRAC_16 . . . 108
7.1.2.90 MICROSTEP_MODE_FRAC_2 . . . 108
7.1.2.91 MICROSTEP_MODE_FRAC_256 . . . 108
7.1.2.92 MICROSTEP_MODE_FRAC_32 . . . 108
7.1.2.93 MICROSTEP_MODE_FRAC_4 . . . 108
7.1.2.94 MICROSTEP_MODE_FRAC_64 . . . 108
7.1.2.95 MICROSTEP_MODE_FRAC_8 . . . 108
7.1.2.96 MICROSTEP_MODE_FULL . . . 109
7.1.2.97 MOVE_STATE_ANTIPLAY . . . 109
7.1.2.98 MOVE_STATE_MOVING . . . 109
7.1.2.99 MOVE_STATE_TARGET_SPEED . . . 109
7.1.2.100 MVCMD_ERROR . . . 109
7.1.2.101 MVCMD_HOME . . . 109
7.1.2.102 MVCMD_LEFT . . . 109
7.1.2.103 MVCMD_LOFT . . . 109
7.1.2.104 MVCMD_MOVE . . . 109
7.1.2.105 MVCMD_MOVR . . . 109
7.1.2.106 MVCMD_NAME_BITS . . . 109
7.1.2.107 MVCMD_RIGHT . . . 110
7.1.2.108 MVCMD_RUNNING . . . 110
7.1.2.109 MVCMD_SSTP . . . 110
7.1.2.110 MVCMD_STOP . . . 110
7.1.2.111 MVCMD_UKNWN . . . 110
7.1.2.112 POWER_OFF_ENABLED . . . 110
7.1.2.113 POWER_REDUCT_ENABLED . . . 110
7.1.2.114 POWER_SMOOTH_CURRENT . . . 110
7.1.2.115 PWR_STATE_MAX . . . 110
7.1.2.116 PWR_STATE_NORM . . . 110
7.1.2.117 PWR_STATE_OFF . . . 110
7.1.2.118 PWR_STATE_REDUCT . . . 110
7.1.2.119 PWR_STATE_UNKNOWN . . . 111
7.1.2.120 REV_SENS_INV . . . 111

7.1.2.121 RPM_DIV_1000 . . . 111
7.1.2.122 SETPOS_IGNORE_ENCODER . . . 111
7.1.2.123 SETPOS_IGNORE_POSITION . . . 111
7.1.2.124 STATE_ALARM . . . 111
7.1.2.125 STATE_BORDERS_SWAP_MISSET . . . 111
7.1.2.126 STATE_BRAKE . . . 111
7.1.2.127 STATE_BUTTON_LEFT . . . 111
7.1.2.128 STATE_BUTTON_RIGHT . . . 111
7.1.2.129 STATE_CONTR . . . 111
7.1.2.130 STATE_CONTROLLER_OVERHEAT . . . 112
7.1.2.131 STATE_CTP_ERROR . . . 112
7.1.2.132 STATE_DIG_SIGNAL . . . 112
7.1.2.133 STATE_EEPROM_CONNECTED . . . 112
7.1.2.134 STATE_ENC_A . . . 112
7.1.2.135 STATE_ENC_B . . . 112
7.1.2.136 STATE_ENGINE_RESPONSE_ERROR . . . 112
7.1.2.137 STATE_ERRC . . . 112
7.1.2.138 STATE_ERRD . . . 112
7.1.2.139 STATE_ERRV . . . 112
7.1.2.140 STATE_EXTIO_ALARM . . . 112
7.1.2.141 STATE_GPIO_LEVEL . . . 112
7.1.2.142 STATE_GPIO_PINOUT . . . 113
7.1.2.143 STATE_LEFT_EDGE . . . 113
7.1.2.144 STATE_LOW_USB_VOLTAGE . . . 113
7.1.2.145 STATE_OVERLOAD_POWER_CURRENT . . . 113
7.1.2.146 STATE_OVERLOAD_POWER_VOLTAGE . . . 113
7.1.2.147 STATE_OVERLOAD_USB_CURRENT . . . 113
7.1.2.148 STATE_OVERLOAD_USB_VOLTAGE . . . 113
7.1.2.149 STATE_POWER_OVERHEAT . . . 113
7.1.2.150 STATE_REV_SENSOR . . . 113
7.1.2.151 STATE_RIGHT_EDGE . . . 113
7.1.2.152 STATE_SECUR . . . 113
7.1.2.153 STATE_SYNC_INPUT . . . 113
7.1.2.154 STATE_SYNC_OUTPUT . . . 114
7.1.2.155 SYNCIN_ENABLED . . . 114
7.1.2.156 SYNCIN_GOTOPOSITION . . . 114
7.1.2.157 SYNCIN_INVERT . . . 114
7.1.2.158 SYNCOUT_ENABLED . . . 114
7.1.2.159 SYNCOUT_IN_STEPS . . . 114
7.1.2.160 SYNCOUT_INVERT . . . 114

7.1.2.161 SYNCOUT_ONPERIOD . . . 114
7.1.2.162 SYNCOUT_ONSTART . . . 114
7.1.2.163 SYNCOUT_ONSTOP . . . 114
7.1.2.164 SYNCOUT_STATE . . . 114
7.1.2.165 UART_PARITY_BITS . . . 114
7.1.2.166 WIND_A_STATE_ABSENT . . . 115
7.1.2.167 WIND_A_STATE_MALFUNC . . . 115
7.1.2.168 WIND_A_STATE_OK . . . 115
7.1.2.169 WIND_A_STATE_UNKNOWN . . . 115
7.1.2.170 WIND_B_STATE_ABSENT . . . 115
7.1.2.171 WIND_B_STATE_MALFUNC . . . 115
7.1.2.172 WIND_B_STATE_OK . . . 115
7.1.2.173 WIND_B_STATE_UNKNOWN . . . 115
7.1.2.174 XIMC_API . . . 115
7.1.3 Typedef Documentation . . . 115
7.1.3.1 logging_callback_t . . . 115
7.1.4 Function Documentation . . . 116
7.1.4.1 close_device . . . 116
7.1.4.2 command_clear_fram . . . 116
7.1.4.3 command_eeread_settings . . . 116
7.1.4.4 command_eesave_settings . . . 116
7.1.4.5 command_home . . . 116
7.1.4.6 command_homezero . . . 117
7.1.4.7 command_left . . . 117
7.1.4.8 command_loft . . . 117
7.1.4.9 command_move . . . 117
7.1.4.10 command_move_calb . . . 118
7.1.4.11 command_movr . . . 118
7.1.4.12 command_movr_calb . . . 118
7.1.4.13 command_power_off . . . 119
7.1.4.14 command_read_robust_settings . . . 119
7.1.4.15 command_read_settings . . . 119
7.1.4.16 command_reset . . . 119
7.1.4.17 command_right . . . 119
7.1.4.18 command_save_robust_settings . . . 120
7.1.4.19 command_save_settings . . . 120
7.1.4.20 command_sstp . . . 120
7.1.4.21 command_start_measurements . . . 120
7.1.4.22 command_stop . . . 120
7.1.4.23 command_update_firmware . . . 120

7.1.4.24 command_wait_for_stop . . . 121
7.1.4.25 command_zero . . . 121
7.1.4.26 enumerate_devices . . . 121
7.1.4.27 free_enumerate_devices . . . 122
7.1.4.28 get_accessories_settings . . . 122
7.1.4.29 get_analog_data . . . 122
7.1.4.30 get_bootloader_version . . . 122
7.1.4.31 get_brake_settings . . . 122
7.1.4.32 get_calibration_settings . . . 123
7.1.4.33 get_chart_data . . . 123
7.1.4.34 get_control_settings . . . 123
7.1.4.35 get_control_settings_calb . . . 123
7.1.4.36 get_controller_name . . . 124
7.1.4.37 get_ctp_settings . . . 124
7.1.4.38 get_debug_read . . . 124
7.1.4.39 get_device_count . . . 124
7.1.4.40 get_device_information . . . 125
7.1.4.41 get_device_name . . . 125
7.1.4.42 get_edges_settings . . . 125
7.1.4.43 get_edges_settings_calb . . . 125
7.1.4.44 get_emf_settings . . . 126
7.1.4.45 get_encoder_information . . . 126
7.1.4.46 get_encoder_settings . . . 126
7.1.4.47 get_engine_advansed_setup . . . 127
7.1.4.48 get_engine_settings . . . 127
7.1.4.49 get_engine_settings_calb . . . 127
7.1.4.50 get_entype_settings . . . 127
7.1.4.51 get_enumerate_device_controller_name . . . 128
7.1.4.52 get_enumerate_device_information . . . 128
7.1.4.53 get_enumerate_device_network_information . . . 128
7.1.4.54 get_enumerate_device_serial . . . 128
7.1.4.55 get_enumerate_device_stage_name . . . 129
7.1.4.56 get_extended_settings . . . 129
7.1.4.57 get_extio_settings . . . 129
7.1.4.58 get_feedback_settings . . . 129
7.1.4.59 get_firmware_version . . . 130
7.1.4.60 get_gear_information . . . 130
7.1.4.61 get_gear_settings . . . 130
7.1.4.62 get_globally_unique_identifier . . . 130
7.1.4.63 get_hallsensor_information . . . 131

7.1.4.64 get_hallsensor_settings . . . 131
7.1.4.65 get_home_settings . . . 131
7.1.4.66 get_home_settings_calb . . . 131
7.1.4.67 get_init_random . . . 132
7.1.4.68 get_joystick_settings . . . 132
7.1.4.69 get_measurements . . . 132
7.1.4.70 get_motor_information . . . 132
7.1.4.71 get_motor_settings . . . 133
7.1.4.72 get_move_settings . . . 133
7.1.4.73 get_move_settings_calb . . . 133
7.1.4.74 get_nonvolatile_memory . . . 133
7.1.4.75 get_pid_settings . . . 133
7.1.4.76 get_position . . . 134
7.1.4.77 get_position_calb . . . 134
7.1.4.78 get_power_settings . . . 134
7.1.4.79 get_secure_settings . . . 134
7.1.4.80 get_serial_number . . . 135
7.1.4.81 get_stage_information . . . 135
7.1.4.82 get_stage_name . . . 135
7.1.4.83 get_stage_settings . . . 135
7.1.4.84 get_status . . . 135
7.1.4.85 get_status_calb . . . 136
7.1.4.86 get_sync_in_settings . . . 136
7.1.4.87 get_sync_in_settings_calb . . . 136
7.1.4.88 get_sync_out_settings . . . 136
7.1.4.89 get_sync_out_settings_calb . . . 137
7.1.4.90 get_uart_settings . . . 137
7.1.4.91 goto_firmware . . . 137
7.1.4.92 has_firmware . . . 138
7.1.4.93 load_correction_table . . . 138
7.1.4.94 logging_callback_stderr_narrow . . . 138
7.1.4.95 logging_callback_stderr_wide . . . 139
7.1.4.96 msec_sleep . . . 139
7.1.4.97 open_device . . . 139
7.1.4.98 probe_device . . . 139
7.1.4.99 service_command_updf . . . 139
7.1.4.100 set_accessories_settings . . . 140
7.1.4.101 set_bindy_key . . . 140
7.1.4.102 set_brake_settings . . . 140
7.1.4.103 set_calibration_settings . . . 140

7.1.4.104 set_control_settings . . . 141
7.1.4.105 set_control_settings_calb . . . 141
7.1.4.106 set_controller_name . . . 141
7.1.4.107 set_correction_table . . . 141
7.1.4.108 set_ctp_settings . . . 142
7.1.4.109 set_debug_write . . . 142
7.1.4.110 set_edges_settings . . . 142
7.1.4.111 set_edges_settings_calb . . . 143
7.1.4.112 set_emf_settings . . . 143
7.1.4.113 set_encoder_information . . . 143
7.1.4.114 set_encoder_settings . . . 144
7.1.4.115 set_engine_advansed_setup . . . 144
7.1.4.116 set_engine_settings . . . 144
7.1.4.117 set_engine_settings_calb . . . 144
7.1.4.118 set_entype_settings . . . 145
7.1.4.119 set_extended_settings . . . 145
7.1.4.120 set_extio_settings . . . 145
7.1.4.121 set_feedback_settings . . . 146
7.1.4.122 set_gear_information . . . 146
7.1.4.123 set_gear_settings . . . 146
7.1.4.124 set_hallsensor_information . . . 146
7.1.4.125 set_hallsensor_settings . . . 147
7.1.4.126 set_home_settings . . . 147
7.1.4.127 set_home_settings_calb . . . 147
7.1.4.128 set_joystick_settings . . . 147
7.1.4.129 set_logging_callback . . . 148
7.1.4.130 set_motor_information . . . 148
7.1.4.131 set_motor_settings . . . 148
7.1.4.132 set_move_settings . . . 148
7.1.4.133 set_move_settings_calb . . . 149
7.1.4.134 set_nonvolatile_memory . . . 149
7.1.4.135 set_pid_settings . . . 149
7.1.4.136 set_position . . . 149
7.1.4.137 set_position_calb . . . 150
7.1.4.138 set_power_settings . . . 150
7.1.4.139 set_secure_settings . . . 150
7.1.4.140 set_serial_number . . . 150
7.1.4.141 set_stage_information . . . 150
7.1.4.142 set_stage_name . . . 151
7.1.4.143 set_stage_settings . . . 151

7.1.4.144 set_sync_in_settings . . . . . 151
7.1.4.145 set_sync_in_settings_calb . . . . . 151
7.1.4.146 set_sync_out_settings . . . . . 152
7.1.4.147 set_sync_out_settings_calb . . . . . 152
7.1.4.148 set_uart_settings . . . . . 152
7.1.4.149 write_key . . . . . 153
7.1.4.150 ximc_fix_usbser_sys . . . . . 153
7.1.4.151 ximc_version . . . . . 153

**Index** **153**

# Chapter 1

# libximc library

Documentation for libximc library.

Libximc is **thread safe**, cross-platform library for working with 8SMC4-USB and 8SMC5-USB controllers.

Full documentation about controllers is there

Full documentation about libximc API is available on the page ximc.h.

## 1.1 What the controller does.

- Supports input and output synchronization signals to ensure the joint operation of multiple devices within a complex system ;.
- Works with all compact stepper motors with a winding current of up to 3 A, without feedback, as well as with stepper motors equipped with an encoder in the feedback circuit, including a linear encoder on the positioner.
- Manages hardware using ready-made software or using libraries for programming languages: C / C ++, C #, JAVA, Visual Basic, Python 2/3, .NET, Delphi, integration with MS Visual Studio programming environments, gcc, Xcode.
- Works with scientific development environments by integrating LabVIEW and MATLAB;

## 1.2 What can do libximc library

- Libximc manages hardware using interfaces: USB 2.0., RS232 and Ethernet, also uses a common and proven virtual serial port interface, so you can work with motor control modules through this library under almost all operating systems, including Windows, Linux and Mac OS X
- Libximc library supports plug/unplug on the fly. Each device can be controlled only by one program at once. Multiple processes (programs) that control one device simultaneously are not allowed.

Warning

Libximc library opens the controller in exclusive access mode. Any controller opened with libximc (XiLab also uses this library) needs to be closed before it may be used by another process. So at first check that you have closed XiLab or other software dealing with the controller before trying to reopen the controller.

Please read the Introduction to start work with library.

To use libximc in your project please consult with How to use with...

## 1.3 Assistance.

Many thanks to everyone who sends suggestions, errors and ideas. We appreciate your suggestions and try to make our product better. Please post your questions here. Your ideas and comments send a e-mail: 8smc4@standa.lt

# Chapter 2

# Introduction

## 2.1 About library

This document contains all information about libximc library. It utilizes well known virtual COM-port interface, so you can use it on Windows 7, Windows, Vista, Windows XP, Windows Server 2003, Windows 2000, Linux, Mac OS X. Multi-platform programing library supports plug/unplug on the fly. Each device can be controlled only by one program at once. Multiple processes (programs) that control one device simultaneously are not allowed.

## 2.2 System requirements

### 2.2.1 For rebuilding library

On Windows:

- Windows 2000 or later, 64-bit system (if compiling both arhitectures) or 32-bit system.
- Microsoft Visual C++ 2013 or later
- cygwin with tar, bison, flex, curl installed
- 7z

On Linux:

- 64-bit or/and 32-bit system system
- gcc 4 or later
- common autotools: autoconf, autoheader, aclocal, automake, autoreconf, libtool
- gmake
- doxygen - for building docs
- LaTeX distribution (teTeX or texlive) - for building docs
- flex 2.5.30+
- bison
- mercurial (for building developer version from hg)

On Mac OS X:

- XCode 4
- doxygen
- mactex
- autotools
- mercurial (for building developer version from hg)

If mercurial is used, please enable 'purge' extension by adding to ∼/.hgrc following lines:

```
[extensions]
  hgext.purge=
```

### 2.2.2 For using library

Supported operating systems (32 or 64 bit) and environment requirements:

- Mac OS X 10.6
- Windows 2000 or later
- Autotools-compatible unix. Package is installed from sources.
- Linux debian-based 32 and 64 bit. DEB package is built against Debian Squeeze 7
- Linux debian-based ARM. DEB package is built on Ubuntu 14.04
- Linux rpm-based. RPM is built against OpenSUSE 12
- Java 7 64-bit or 32-bit
- .NET 2.0 (32-bit only)
- Delphi (32-bit only)

Build requirements:

- Windows: Microsoft Visual C++ 2013 or mingw (currently not supported)
- UNIX: gcc 4, gmake
- Mac OS X: XCode 4
- JDK 7

# Chapter 3

# How to rebuild library

## 3.1 Building on generic UNIX

Generic version could be built with standard autotools.

```
./build.sh lib
```

Built files (library, headers, documentation) are installed to ./dist/local directory. It is a generic developer build. Sometimes you need to specify additional parameters to command line for your machine. Please look to following OS sections.

## 3.2 Building on debian-based linux systems

Requirement: 64-bit and 32-bit debian system, ubuntu Typical set of packages: gcc, autotools, autoconf, libtool, dpkg-dev, flex, bison, doxygen, texlive, mercurial Full set of packages: apt-get install ruby1.9.1 debhelper vim sudo g++ mercurial git curl make cmake autotools-dev automake autoconf libtool default-jre-headless default-jdk openjdk-6-jdk dpkg-dev lintian texlive texlive-latex-extra texlive-lang-cyrillic dh-autoreconf hardening-wrapper bison flex doxygen lsb-release pkg-config check For ARM cross-compiling install gcc-arm-linux-gnueabihf from your ARM toolchain.

It's required to match library and host architecture: 64-bit library can be built only at 64-bit host, 32-bit library - only at 32-bit host. ARM library is built with armhf cross-compiler gcc-arm-linux-gnueabihf.

To build library and package invoke a script:

```
$ ./build.sh libdeb
```

For ARM library replace 'libdeb' with 'libdebarm'.

Grab packages from ./ximc/deb and locally installed binaries from ./dist/local.

## 3.3 Building on redhat-based linux systems

Requirement: 64-bit redhat-based system (Fedora, Red Hat, SUSE) Typical set of packages: gcc, autotools, autoconf, libtool, flex, bison, doxygen, texlive, mercurial Full set of packages: autoconf automake bison doxygen flex gcc gcc-32bit gcc-c++ gcc-c++-32bit java-1_7_0-openjdk java-1_7_0-openjdk-devel libtool lsb-release make mercurial rpm-build rpm-devel rpmlint texlive texlive-fonts-extra texlive-latex

It's possible to build both 32- and 64-bit libraries on 64-bit host system. 64-bit library can't be built on 32-bit system.

To build library and package invoke a script:

```
$ ./build.sh librpm
```

Grab packages from ./ximc/rpm and locally installed binaries from ./dist/local.

## 3.4 Buliding on Mac OS X

To build and package a script invoke a script:

```
$ ./build.sh libosx
```

Built library (classical and framework), examples (classical and .app), documentation are located at ./ximc/macosx, locally installed binaries from ./dist/local.

## 3.5 Buliding on Windows

Requirements: 64-bit windows (build script builds both architectures), cygwin (must be installed to a default path), mercurial.

Invoke a script:

```
$ ./build.bat
```

Grab packages from ./deb/win32 and ./deb/win64

To build debug version of the library set environment variable ”DEBUG” to ”true” before running the build script.

## 3.6 Source code access

XIMC source codes are given under special request.

# Chapter 4

# How to use with...

Library usage can be examinated from test application testapp. Non-C languages are supported because library supports stdcall calling convention and so can be used with a variety of languages.

C test project is located at 'examples/testapp' directory, C# test project - at 'examples/test_CSharp', VB.NET - 'examples/test_VBNET', Delphi 6 - 'examples/test_Delphi', sample bindings for MATLAB - 'examples/test_MATLAB', for Java - 'examples/test_Java', for Python - 'examples/test_Python'. Development kit also contains precompiled examples: testapp and testappeasy as 32 and 64-bit applications for Windows and 64-bit application for osx, test_CSharp, test_VBNET, test_Delphi - 32-bit only, test_Java is architecture-independent, test_MATLAB and test_Python are runtime-interpreted.

NOTE: SDK requires Microsoft Visual C++ Redistributable Package (provided with SDK - vcredist_x86 or vcredist_x64)

NOTE: On Linux both the libximc7_x.x.x and libximc7-dev_x.x need to be installed. For install packages, you can use the .deb command: dpkg -i filename.deb, where filename.deb is the name of the package (packages in Debian have the extension .deb). You must run dpkg with superuser privileges (root).

## 4.1 Usage with C

### 4.1.1 Visual C++

Testapp can be built using testapp.sln. Library must be compiled with MS Visual C++ too, mingw-library isn't supported. Make sure that Microsoft Visual C++ Redistributable Package is installed.

Open solution examples/testapp/testapp.sln, build and run from the IDE.

In case of the 8SMC4-USB-Eth1 Ethernet adapter usage it is necessary to set correct IP address of the Ethernet adapter in testapp.c file before build (see enumerate_hints variable).

### 4.1.2 CodeBlocks

Testapp can be built using test_CodeBlocks.cbp. Library must be compiled with MS Visual C++ too, mingw-library isn't supported. Make sure that Microsoft Visual C++ Redistributable Package is installed. $*$

Open solution examples/test_CodeBlocks/test_CodeBlocks.cbp, build and run from the IDE.

### 4.1.3 MinGW

MinGW is a port of GCC to win32 platform. It's required to install MinGW package. Currently not supported

MinGW-compiled testapp can be built with MS Visual C++ or mingw library.

```
$ mingw32-make -f Makefile.mingw all
```

Then copy library libximc.dll to current directory and launch testapp.exe.

In case of the 8SMC4-USB-Eth1 Ethernet adapter usage it is necessary to set correct IP address of the Ethernet adapter in testapp.c file before build (see enumerate_hints variable).

### 4.1.4 C++ Builder

First of all you should create C++ Builder-style import library. Visual C++ library is not compatible with BCB. Invoke:

```
$ implib libximc.lib libximc.def
```

Then compile test application:

```
$ bcc32 -I..\..\ximc\win32 -L..\..\ximc\win32 -DWIN32 -DNDEBUG -D_WINDOWS
      testapp.c libximc.lib
```

In case of the 8SMC4-USB-Eth1 Ethernet adapter usage it is necessary to set correct IP address of the Ethernet adapter in testapp.c file before build (see enumerate_hints variable).

### 4.1.5 XCode

Test app should be built with XCode project testapp.xcodeproj. Library is a Mac OS X framework, and at example application it's bundled inside testapp.app

Then launch application testapp.app and check activity output in Console.app.

In case of the 8SMC4-USB-Eth1 Ethernet adapter usage it is necessary to set correct IP address of the Ethernet adapter in testapp.c file before build (see enumerate_hints variable).

### 4.1.6 GCC

Make sure that libximc (rpm, deb, freebsd package or tarball) is installed at your system. Installation of package should be performed with a package manager of operating system. On OS X a framework is provided.

Note that user should belong to system group which allows access to a serial port (dip or serial, for example).

Copy file /usr/share/libximc/keyfile.sqlite project directory:

```
$ cp /usr/share/libximc/keyfile.sqlite .
```

Test application can be built with the installed library with the following script:

```
$ make
```

In case of cross-compilation (target architecture differs from the current system architecture) feed -m64 or -m32 flag to compiler. On OS X it's needed to use -arch flag instead to build an universal binary. Please consult a compiler documentation.

Then launch the application as:

```
$ make run
```

Note: make run on OS X copies a library to the current directory. If you want to use library from the custom directory please be sure to specify LD_LIBRARY_PATH or DYLD_LIBRARY_PATH to the directory with the library.

In case of the 8SMC4-USB-Eth1 Ethernet adapter usage it is necessary to set correct IP address of the Ethernet adapter in testapp.c file before build (see enumerate_hints variable).

## 4.2 .NET

Wrapper assembly for libximc.dll is wrappers/csharp/ximcnet.dll. It is provided with two different architectures. Supports the platform .NET from 2.0. to 4.0.

Test .NET applications for Visual Studio 2013 is located at test_CSharp (for C#) and test_VBNET (for VB.NET) respectively. Open solutions and build.

In case of the 8SMC4-USB-Eth1 Ethernet adapter usage it is necessary to set correct IP address of the Ethernet adapter in testapp.cs or testapp.vb file (depending on programming language) before build (see enumerate_hints variable for C# or enum_hints variable for VB).

## 4.3 Delphi

Wrapper for libximc.dll is a unit wrappers/delphi/ximc.pas

Console test application for is located at test_Delphi. Tested with Delphi 6 and only 32-bit version.

Just compile, place DLL near the executable and run program.

In case of the 8SMC4-USB-Eth1 Ethernet adapter usage it is necessary to set correct IP address of the Ethernet adapter in test_Delphi.dpr file before build (see enum_hints variable).

## 4.4 Java

How to run example on Linux. Navigate to ximc-2.x.x./examples/test_Java/compiled/ and run:

```
$ cp /usr/share/libximc/keyfile.sqlite .
$ java -cp /usr/share/java/libjximc.jar:test_Java.jar ru.ximc.TestJava
```

How to run example on Windows or Mac. Navigate to ximc-2.x.x./examples/test_Java/compiled/. Copy contents of ximc-2.x.x/ximc/win64 or ximc-2.x.x/ximc/macosx accordingly to the current directory. Then run:

```
$ java -classpath libjximc.jar -classpath test_Java.jar ru.ximc.TestJava
```

How to modify and recompile an example. Navigate to examples/test_Java/compiled. Sources are embedded in a test_Java.jar. Extract them:

```
$ jar xvf test_Java.jar ru META-INF
```

Then rebuild sources:

```
$ javac -classpath /usr/share/java/libjximc.jar -Xlint ru/ximc/TestJava.java
```

or for windows or mac

```
$ javac -classpath libjximc.jar -Xlint ru/ximc/TestJava.java
```

Then build a jar:

```
$ jar cmf META-INF/MANIFEST.MF test_Java.jar ru
```

In case of the 8SMC4-USB-Eth1 Ethernet adapter usage it is necessary to set correct IP address of the Ethernet adapter in TestJava.java file before build (see ENUM_HINTS variable).

## 4.5 Python

Change current directory to the examples/test_Python. For correct usage of the library libximc, the example uses the file wrapper, crossplatform\wrappers\python\pyximc.py with a description of the structures of the library.

Before launch:

On OS X: copy library ximc/macosx/libximc.framework to the current directory.

On Linux: you may need to set LD_LIBRARY_PATH so Python can locate libraries with RPATH. For example, you may need:

```
export LD_LIBRARY_PATH=$LD_LIBRARY_PATH:`pwd`
```

On Windows before the start nothing needs to be done. All necessary communication and dependencies are registered in the example code. Libraries used: bindy.dll libximc.dll xiwrapper.dll. Located in the folder for the respective versions of Windows.

Launch Python 2 or Python 3:

```
python test_Python.py
```

In case of the 8SMC4-USB-Eth1 Ethernet adapter usage it is necessary to set correct IP address of the Ethernet adapter in test_Python.py file before launch (see enum_hints variable).

## 4.6 MATLAB

Sample MATLAB program testximc.m is provided at the directory examples/test_MATLAB. On windows copy ximc.h, libximc.dll, bindy.dll, xiwrapper.dll and contents of ximc/(win32,win64)/wrappers/matlab/ directory to the current directory.

Before launch:

On OS X: copy ximc/macosx/libximc.framework, ximc/macosx/wrappers/ximcm.h, ximc/ximc.h * to the directory examples/matlab. Install XCode compatible with Matlab.

On Linux: install libximc*deb and libximc-dev*dev of target architecture. Then copy ximc/macosx/wrappers/ximcm.h to the directory examples/matlab. Install gcc compatible with Matlab.

For XCode and gcc version compability check document https://www.mathworks.com/content/dam/mathworks/mat SystemRequirements-Release2014a_SupportedCompilers.pdf or similar.

On Windows before the start nothing needs to be done

Change current directory in the MATLAB to the examples/matlab. Then launch in MATLAB prompt:

```
testximc
```

In case of the 8SMC4-USB-Eth1 Ethernet adapter usage it is necessary to set correct IP address of the Ethernet adapter in testximc.m file before launch (see enum_hints variable).

## 4.7 Generic logging facility

If you want to turn on file logging, you should run the program that uses libximc library with the "XILOG" environment variable set to desired file name. This file will be opened for writing on the first log event and will be closed when the program which uses libximc terminates. Data which is sent to/received from the controller is logged along with port open and close events.

## 4.8 Required permissions

libximc generally does not require special permissions to work, it only needs read/write access to USB-serial ports on the system. An exception to this rule is a Windows-only ”fix_usbser_sys()” function - it needs elevation and will produce null result if run as a regular user.

## 4.9 C-profiles

C-profiles are header files distributed with the libximc library. They enable one to set all controller settings for any of the supported stages with a single function call in a C/C++ program. You may see how to use C-profiles in ”testcprofile” example directory.

# Chapter 5

# Working with custom units

In addition to working in basic units(steps, encoder value), the library allows you to work with custom units. For this purpose are used:

- The structure of the conversion units calibration_t
- The functions of which have doubles for working with custom units, data structures for these functions
- Coordinate correction table for more accurate positioning

## 5.1 The structure of the conversion units calibration_t

To specify conversion of the basic units in the user and back, calibration_t structure is used. With the help of coefficients A and MicrostepMode, specified in this structure, steps and microsteps which are integers are converted into the user value of the real type and back.

Conversion formulas:

- The conversion to user units.

```
user_value = A*(step + mstep/pow(2,MicrostepMode-1))
```

- Conversion from custom units.

```
step = (int)(user_value/A)
mstep = (user_value/A - step)*pow(2,MicrostepMode-1)
```

## 5.2 Alternative functions for working with custom units and data structures for them

Structures and functions for working with custom units have the _calb postfix. The user using these functions can perform all actions in their own units without worrying about the computations of the controller. The data format of _calb structures is described in detail. For _calb functions particular descriptions are not used. They perform the same actions as the basic functions do. The difference between them and the basic functions is in the position, velocity, and acceleration of the data types defined as user-defined. If clarification for _calb functions is necessary, they are provided as notes in the description of the basic functions.

## 5.3 Coordinate correction table for more accurate positioning

Some functions for working with custom units support coordinate transformation using a correction table. To load a table from a file, the load_correction_table() function is used. Its description contains the functions and their data supporting correction.

Note

For data fields which are corrected in case of loading of the table in the description of the field is written - corrected by the table.

File format:

- two columns separated by tabs;
- column headers are string;
- real type data, point is a separator;
- the first column is the coordinate, the second is the deviation caused by a mechanical error;
- the deviation between coordinates is calculated linearly;
- constant is equal to the deviation at the boundary beyond the range;
- maximum length of the table is 100 lines.

Sample file:

```
X  dX
0  0
5.0         0.005
10.0        -0.01
```

# Chapter 6

# Data Structure Documentation

## 6.1 accessories_settings_t Struct Reference

Additional accessories information.

### Data Fields

- char MagneticBrakeInfo [25]

  *The manufacturer and the part number of magnetic brake, the maximum string length is 24 characters.*
- float MBRatedVoltage

  *Rated voltage for controlling the magnetic brake (B).*
- float MBRatedCurrent

  *Rated current for controlling the magnetic brake (A).*
- float MBTorque

  *Retention moment (mN m).*
- unsigned int MBSettings

  *Magnetic brake settings flags.*
- char TemperatureSensorInfo [25]

  *The manufacturer and the part number of the temperature sensor, the maximum string length: 24 characters.*
- float TSMin

  *The minimum measured temperature (degrees Celsius) Data type: float.*
- float TSMax

  *The maximum measured temperature (degrees Celsius) Data type: float.*
- float TSGrad

  *The temperature gradient (V/degrees Celsius).*
- unsigned int TSSettings

  *Temperature sensor settings flags.*
- unsigned int LimitSwitchesSettings

  *Temperature sensor settings flags.*

### 6.1.1 Detailed Description

Additional accessories information.

See Also

set_accessories_settings
get_accessories_settings
get_accessories_settings, set_accessories_settings

## 6.1.2 Field Documentation

### 6.1.2.1 unsigned int LimitSwitchesSettings

Temperature sensor settings flags.

### 6.1.2.2 char MagneticBrakeInfo[25]

The manufacturer and the part number of magnetic brake, the maximum string length is 24 characters.

### 6.1.2.3 float MBRatedCurrent

Rated current for controlling the magnetic brake (A).

Data type: float.

### 6.1.2.4 float MBRatedVoltage

Rated voltage for controlling the magnetic brake (B).

Data type: float.

### 6.1.2.5 unsigned int MBSettings

Magnetic brake settings flags.

### 6.1.2.6 float MBTorque

Retention moment (mN m).

Data type: float.

### 6.1.2.7 char TemperatureSensorInfo[25]

The manufacturer and the part number of the temperature sensor, the maximum string length: 24 characters.

### 6.1.2.8 float TSGrad

The temperature gradient (V/degrees Celsius).

Data type: float.

### 6.1.2.9 float TSMax

The maximum measured temperature (degrees Celsius) Data type: float.

### 6.1.2.10 float TSMin

The minimum measured temperature (degrees Celsius) Data type: float.

### 6.1.2.11 unsigned int TSSettings

Temperature sensor settings flags.

## 6.2 analog_data_t Struct Reference

Analog data.

### Data Fields

- unsigned int A1Voltage_ADC

  *"Voltage on pin 1 winding A" raw data from ADC.*
- unsigned int A2Voltage_ADC

  *"Voltage on pin 2 winding A" raw data from ADC.*
- unsigned int B1Voltage_ADC

  *"Voltage on pin 1 winding B" raw data from ADC.*
- unsigned int B2Voltage_ADC

  *"Voltage on pin 2 winding B" raw data from ADC.*
- unsigned int SupVoltage_ADC

  *"Voltage on the top of MOSFET full bridge" raw data from ADC.*
- unsigned int ACurrent_ADC

  *"Winding A current" raw data from ADC.*
- unsigned int BCurrent_ADC

  *"Winding B current" raw data from ADC.*
- unsigned int FullCurrent_ADC

  *"Full current" raw data from ADC.*
- unsigned int Temp_ADC

  *Voltage from temperature sensor, raw data from ADC.*
- unsigned int Joy_ADC

  *Joystick raw data from ADC.*
- unsigned int Pot_ADC

  *Voltage on analog input, raw data from ADC.*
- unsigned int L5_ADC

  *USB supply voltage after the current sense resistor, from ADC.*
- unsigned int H5_ADC

  *Power supply USB from ADC.*
- int A1Voltage

  *"Voltage on pin 1 winding A" calibrated data (in tens of mV).*
- int A2Voltage

  *"Voltage on pin 2 winding A" calibrated data (in tens of mV).*
- int B1Voltage

  *"Voltage on pin 1 winding B" calibrated data (in tens of mV).*
- int B2Voltage

  *"Voltage on pin 2 winding B" calibrated data (in tens of mV).*
- int SupVoltage

  *"Voltage on the top of MOSFET full bridge" calibrated data (in tens of mV).*
- int ACurrent

  *"Winding A current" calibrated data (in mA).*
- int BCurrent

  *"Winding B current" calibrated data (in mA).*
- int FullCurrent

  *"Full current" calibrated data (in mA).*
- int Temp

  *Temperature, calibrated data (in tenths of degrees Celcius).*

- int Joy

  *Joystick, calibrated data.*
- int Pot

  *Analog input, calibrated data.*
- int L5

  *USB supply voltage after the current sense resistor (in tens of mV).*
- int H5

  *Power supply USB (in tens of mV).*
- unsigned int **deprecated**
- int R

  *Motor winding resistance in mOhms(is only used with stepper motor).*
- int L

  *Motor winding pseudo inductance in uHn(is only used with stepper motor).*

### 6.2.1 Detailed Description

Analog data.

This structure contains raw analog data from ADC embedded on board. These data used for device testing and deep recalibraton by manufacturer only.

See Also

get_analog_data
get_analog_data

### 6.2.2 Field Documentation

#### 6.2.2.1 int A1Voltage

"Voltage on pin 1 winding A" calibrated data (in tens of mV).

#### 6.2.2.2 unsigned int A1Voltage_ADC

"Voltage on pin 1 winding A" raw data from ADC.

#### 6.2.2.3 int A2Voltage

"Voltage on pin 2 winding A" calibrated data (in tens of mV).

#### 6.2.2.4 unsigned int A2Voltage_ADC

"Voltage on pin 2 winding A" raw data from ADC.

#### 6.2.2.5 int ACurrent

"Winding A current" calibrated data (in mA).

#### 6.2.2.6 unsigned int ACurrent_ADC

"Winding A current" raw data from ADC.

#### 6.2.2.7 int B1Voltage

”Voltage on pin 1 winding B” calibrated data (in tens of mV).

#### 6.2.2.8 unsigned int B1Voltage_ADC

”Voltage on pin 1 winding B” raw data from ADC.

#### 6.2.2.9 int B2Voltage

”Voltage on pin 2 winding B” calibrated data (in tens of mV).

#### 6.2.2.10 unsigned int B2Voltage_ADC

”Voltage on pin 2 winding B” raw data from ADC.

#### 6.2.2.11 int BCurrent

”Winding B current” calibrated data (in mA).

#### 6.2.2.12 unsigned int BCurrent_ADC

”Winding B current” raw data from ADC.

#### 6.2.2.13 int FullCurrent

”Full current” calibrated data (in mA).

#### 6.2.2.14 unsigned int FullCurrent_ADC

”Full current” raw data from ADC.

#### 6.2.2.15 int H5

Power supply USB (in tens of mV).

#### 6.2.2.16 int Joy

Joystick, calibrated data.

Range: 0..10000

#### 6.2.2.17 unsigned int Joy_ADC

Joystick raw data from ADC.

#### 6.2.2.18 int L

Motor winding pseudo inductance in uHn(is only used with stepper motor).

#### 6.2.2.19 int L5

USB supply voltage after the current sense resistor (in tens of mV).

#### 6.2.2.20 unsigned int L5_ADC

USB supply voltage after the current sense resistor, from ADC.

#### 6.2.2.21 int Pot

Analog input, calibrated data.

Range: 0..10000

#### 6.2.2.22 int R

Motor winding resistance in mOhms(is only used with stepper motor).

#### 6.2.2.23 int SupVoltage

"Voltage on the top of MOSFET full bridge" calibrated data (in tens of mV).

#### 6.2.2.24 unsigned int SupVoltage_ADC

"Voltage on the top of MOSFET full bridge" raw data from ADC.

#### 6.2.2.25 int Temp

Temperature, calibrated data (in tenths of degrees Celcius).

#### 6.2.2.26 unsigned int Temp_ADC

Voltage from temperature sensor, raw data from ADC.

## 6.3 brake_settings_t Struct Reference

Brake settings.

### Data Fields

- unsigned int t1
  *Time in ms between turn on motor power and turn off brake.*
- unsigned int t2
  *Time in ms between turn off brake and moving readiness.*
- unsigned int t3
  *Time in ms between motor stop and turn on brake.*
- unsigned int t4
  *Time in ms between turn on brake and turn off motor power.*
- unsigned int BrakeFlags
  *Brake settings flags.*

### 6.3.1 Detailed Description

Brake settings.

This structure contains parameters of brake control.

See Also

set_brake_settings
get_brake_settings
get_brake_settings, set_brake_settings

### 6.3.2 Field Documentation

#### 6.3.2.1 unsigned int BrakeFlags

Brake settings flags.

#### 6.3.2.2 unsigned int t1

Time in ms between turn on motor power and turn off brake.

#### 6.3.2.3 unsigned int t2

Time in ms between turn off brake and moving readiness.

All moving commands will execute after this interval.

#### 6.3.2.4 unsigned int t3

Time in ms between motor stop and turn on brake.

#### 6.3.2.5 unsigned int t4

Time in ms between turn on brake and turn off motor power.

## 6.4 calibration_settings_t Struct Reference

Calibration settings.

### Data Fields

- float CSS1_A
  *Scaling factor for the analogue measurements of the winding A current.*
- float CSS1_B
  *Shift factor for the analogue measurements of the winding A current.*
- float CSS2_A
  *Scaling factor for the analogue measurements of the winding B current.*
- float CSS2_B
  *Shift factor for the analogue measurements of the winding B current.*
- float FullCurrent_A
  *Scaling factor for the analogue measurements of the full current.*

- float FullCurrent_B

  *Shift factor for the analogue measurements of the full current.*

### 6.4.1 Detailed Description

Calibration settings.

This structure contains calibration settings.

See Also

get_calibration_settings
set_calibration_settings
get_calibration_settings, set_calibration_settings

### 6.4.2 Field Documentation

#### 6.4.2.1 float CSS1_A

Scaling factor for the analogue measurements of the winding A current.

#### 6.4.2.2 float CSS1_B

Shift factor for the analogue measurements of the winding A current.

#### 6.4.2.3 float CSS2_A

Scaling factor for the analogue measurements of the winding B current.

#### 6.4.2.4 float CSS2_B

Shift factor for the analogue measurements of the winding B current.

#### 6.4.2.5 float FullCurrent_A

Scaling factor for the analogue measurements of the full current.

#### 6.4.2.6 float FullCurrent_B

Shift factor for the analogue measurements of the full current.

## 6.5 calibration_t Struct Reference

Calibration companion structure.

### Data Fields

- double A

  *Mulitiplier.*
- unsigned int MicrostepMode

  *Microstep mode.*

### 6.5.1 Detailed Description

Calibration companion structure.

## 6.6 chart_data_t Struct Reference

Additional device state.

### Data Fields

- int WindingVoltageA

  *In the case step motor, the voltage across the winding A (in tens of mV); in the case of a brushless, the voltage on the first coil, in the case of the only DC.*
- int WindingVoltageB

  *In the case step motor, the voltage across the winding B (in tens of mV); in case of a brushless, the voltage on the second winding, and in the case of DC is not used.*
- int WindingVoltageC

  *In the case of a brushless, the voltage on the third winding (in tens of mV), in the case step motor and DC is not used.*
- int WindingCurrentA

  *In the case step motor, the current in the coil A (in mA); brushless if the current in the first coil, and in the case of a single DC.*
- int WindingCurrentB

  *In the case step motor, the current in the coil B (in mA); brushless if the current in the second coil, and in the case of DC is not used.*
- int WindingCurrentC

  *In the case of a brushless, the current in the third winding (in mA), in the case step motor and DC is not used.*
- unsigned int Pot

  *Analog input value in ten-thousandths.*
- unsigned int Joy

  *The joystick position in the ten-thousandths.*
- int DutyCycle

  *Duty cycle of PWM.*

### 6.6.1 Detailed Description

Additional device state.

This structure contains additional values such as winding's voltages, currents and temperature.

See Also

get_chart_data
get_chart_data

### 6.6.2 Field Documentation

#### 6.6.2.1 int DutyCycle

Duty cycle of PWM.

#### 6.6.2.2 unsigned int Joy

The joystick position in the ten-thousandths.

Range: 0..10000

#### 6.6.2.3 unsigned int Pot

Analog input value in ten-thousandths.

Range: 0..10000

#### 6.6.2.4 int WindingCurrentA

In the case step motor, the current in the coil A (in mA); brushless if the current in the first coil, and in the case of a single DC.

#### 6.6.2.5 int WindingCurrentB

In the case step motor, the current in the coil B (in mA); brushless if the current in the second coil, and in the case of DC is not used.

#### 6.6.2.6 int WindingCurrentC

In the case of a brushless, the current in the third winding (in mA), in the case step motor and DC is not used.

#### 6.6.2.7 int WindingVoltageA

In the case step motor, the voltage across the winding A (in tens of mV); in the case of a brushless, the voltage on the first coil, in the case of the only DC.

#### 6.6.2.8 int WindingVoltageB

In the case step motor, the voltage across the winding B (in tens of mV); in case of a brushless, the voltage on the second winding, and in the case of DC is not used.

#### 6.6.2.9 int WindingVoltageC

In the case of a brushless, the voltage on the third winding (in tens of mV), in the case step motor and DC is not used.

## 6.7 control_settings_calb_t Struct Reference

Control settings which use user units.

### Data Fields

- float MaxSpeed [10]

  *Array of speeds using with joystick and button control.*
- unsigned int Timeout [9]

  *timeout[i] is time in ms, after that max_speed[i+1] is applying.*

- unsigned int MaxClickTime

  *Maximum click time (in ms).*
- unsigned int Flags

  *Control flags.*
- float DeltaPosition

  *Shift (delta) of position.*

### 6.7.1 Detailed Description

Control settings which use user units.

This structure contains control parameters. When choosing CTL_MODE=1 switches motor control with the joystick. In this mode, the joystick to the maximum engine tends Move at MaxSpeed [i], where i=0 if the previous use This mode is not selected another i. Buttons switch the room rate i. When CTL_MODE=2 is switched on motor control using the Left / right. When you click on the button motor starts to move in the appropriate direction at a speed MaxSpeed [0], at the end of time Timeout[i] motor move at a speed MaxSpeed [i+1]. at Transition from MaxSpeed [i] on MaxSpeed [i+1] to acceleration, as usual. The figure above shows the sensitivity of the joystick feature on its position.

See Also

set_control_settings_calb
get_control_settings_calb
get_control_settings, set_control_settings

### 6.7.2 Field Documentation

#### 6.7.2.1 unsigned int Flags

Control flags.

#### 6.7.2.2 unsigned int MaxClickTime

Maximum click time (in ms).

Prior to the expiration of this time the first speed isn't enabled.

#### 6.7.2.3 float MaxSpeed[10]

Array of speeds using with joystick and button control.

#### 6.7.2.4 unsigned int Timeout[9]

timeout[i] is time in ms, after that max_speed[i+1] is applying.

It is using with buttons control only.

## 6.8 control_settings_t Struct Reference

Control settings.

## Data Fields

- unsigned int MaxSpeed [10]

  *Array of speeds (full step) using with joystick and button control.*
- unsigned int uMaxSpeed [10]

  *Array of speeds (in microsteps) using with joystick and button control.*
- unsigned int Timeout [9]

  *timeout[i] is time in ms, after that max_speed[i+1] is applying.*
- unsigned int MaxClickTime

  *Maximum click time (in ms).*
- unsigned int Flags

  *Control flags.*
- int DeltaPosition

  *Shift (delta) of position (full step)*
- int uDeltaPosition

  *Fractional part of the shift in micro steps.*

### 6.8.1 Detailed Description

Control settings.

This structure contains control parameters. When choosing CTL_MODE=1 switches motor control with the joystick. In this mode, the joystick to the maximum engine tends Move at MaxSpeed [i], where i=0 if the previous use This mode is not selected another i. Buttons switch the room rate i. When CTL_MODE=2 is switched on motor control using the Left / right. When you click on the button motor starts to move in the appropriate direction at a speed MaxSpeed [0], at the end of time Timeout[i] motor move at a speed MaxSpeed [i+1]. at Transition from MaxSpeed [i] on MaxSpeed [i+1] to acceleration, as usual. The figure above shows the sensitivity of the joystick feature on its position.

See Also

set_control_settings
get_control_settings
get_control_settings, set_control_settings

### 6.8.2 Field Documentation

#### 6.8.2.1 unsigned int Flags

Control flags.

#### 6.8.2.2 unsigned int MaxClickTime

Maximum click time (in ms).

Prior to the expiration of this time the first speed isn't enabled.

#### 6.8.2.3 unsigned int MaxSpeed[10]

Array of speeds (full step) using with joystick and button control.

Range: 0..100000.

#### 6.8.2.4 unsigned int Timeout[9]

timeout[i] is time in ms, after that max_speed[i+1] is applying.

It is using with buttons control only.

#### 6.8.2.5 int uDeltaPosition

Fractional part of the shift in micro steps.

Is only used with stepper motor. Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings).

#### 6.8.2.6 unsigned int uMaxSpeed[10]

Array of speeds (in microsteps) using with joystick and button control.

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings).

## 6.9 controller_name_t Struct Reference

Controller user name and flags of setting.

### Data Fields

- char ControllerName [17]

  *User conroller name.*
- unsigned int CtrlFlags

  *Flags of internal controller settings.*

### 6.9.1 Detailed Description

Controller user name and flags of setting.

See Also

get_controller_name, set_controller_name

### 6.9.2 Field Documentation

#### 6.9.2.1 char ControllerName[17]

User conroller name.

Can be set by user for his/her convinience. Max string length: 16 chars.

#### 6.9.2.2 unsigned int CtrlFlags

Flags of internal controller settings.

## 6.10 ctp_settings_t Struct Reference

Control position settings(is only used with stepper motor).

### Data Fields

- unsigned int CTPMinError

  *Minimum contrast steps from step motor encoder position, wich set STATE_CTP_ERROR flag.*
- unsigned int CTPFlags

  *Position control flags.*

### 6.10.1 Detailed Description

Control position settings(is only used with stepper motor).

When controlling the step motor with encoder (CTP_BASE 0) it is possible to detect the loss of steps. The controller knows the number of steps per revolution (GENG :: StepsPerRev) and the encoder resolution (GFBS :: IPT). When the control (flag CTP_ENABLED), the controller stores the current position in the footsteps of SM and the current position of the encoder. Further, at each step of the position encoder is converted into steps and if the difference is greater CTPMinError, a flag STATE_CTP_ERROR and set ALARM state. When controlling the step motor with speed sensor (CTP_BASE 1), the position is controlled by him. The active edge of input clock controller stores the current value of steps. Further, at each turn checks how many steps shifted. When a mismatch CTPMinError a flag STATE_CTP_ERROR and set ALARM state.

See Also

set_ctp_settings
get_ctp_settings
get_ctp_settings, set_ctp_settings

### 6.10.2 Field Documentation

#### 6.10.2.1 unsigned int CTPFlags

Position control flags.

#### 6.10.2.2 unsigned int CTPMinError

Minimum contrast steps from step motor encoder position, wich set STATE_CTP_ERROR flag.

Measured in steps step motor.

## 6.11 debug_read_t Struct Reference

Debug data.

### Data Fields

- uint8_t DebugData [128]

  *Arbitrary debug data.*

### 6.11.1 Detailed Description

Debug data.

These data are used for device debugging by manufacturer only.

See Also

get_debug_read

### 6.11.2 Field Documentation

#### 6.11.2.1 uint8_t DebugData[128]

Arbitrary debug data.

## 6.12 debug_write_t Struct Reference

Debug data.

### Data Fields

- uint8_t DebugData [128]
  *Arbitrary debug data.*

### 6.12.1 Detailed Description

Debug data.

These data are used for device debugging by manufacturer only.

See Also

set_debug_write

### 6.12.2 Field Documentation

#### 6.12.2.1 uint8_t DebugData[128]

Arbitrary debug data.

## 6.13 device_information_t Struct Reference

Read command controller information.

### Data Fields

- char Manufacturer [5]
  *Manufacturer.*
- char ManufacturerId [3]
  *Manufacturer id.*

- char ProductDescription [9]

  *Product description.*
- unsigned int Major

  *The major number of the hardware version.*
- unsigned int Minor

  *Minor number of the hardware version.*
- unsigned int Release

  *Number of edits this release of hardware.*

### 6.13.1 Detailed Description

Read command controller information.

The controller responds to this command in any state. Manufacturer field for all XI∗∗ devices should contain the string ”XIMC” (validation is performed on it) The remaining fields contain information about the device.

See Also

get_device_information
get_device_information_impl

### 6.13.2 Field Documentation

#### 6.13.2.1 unsigned int Major

The major number of the hardware version.

#### 6.13.2.2 unsigned int Minor

Minor number of the hardware version.

#### 6.13.2.3 unsigned int Release

Number of edits this release of hardware.

## 6.14 device_network_information_t Struct Reference

Device network information structure.

### Data Fields

- uint32_t ipv4

  *IPv4 address, passed in network byte order (big-endian byte order)*
- char nodename [16]

  *Name of the Bindy node which hosts the device.*
- uint32_t axis_state

  *Flags representing device state.*
- char locker_username [16]

  *Name of the user who locked the device (if any)*
- char locker_nodename [16]

*Bindy node name, which was used to lock the device (if any)*

- time_t locked_time

  *Time the lock was acquired at (UTC, microseconds since the epoch)*

### 6.14.1 Detailed Description

Device network information structure.

## 6.15 edges_settings_calb_t Struct Reference

Edges settings which use user units.

### Data Fields

- unsigned int BorderFlags

  *Border flags.*
- unsigned int EnderFlags

  *Limit switches flags.*
- float LeftBorder

  *Left border position, used if BORDER_IS_ENCODER flag is set.*
- float RightBorder

  *Right border position, used if BORDER_IS_ENCODER flag is set.*

### 6.15.1 Detailed Description

Edges settings which use user units.

This structure contains border and limit switches settings. Please load new engine settings when you change positioner etc. Please note that wrong engine settings lead to device malfunction, can lead to irreversible damage of board.

See Also

set_edges_settings_calb
get_edges_settings_calb
get_edges_settings, set_edges_settings

### 6.15.2 Field Documentation

#### 6.15.2.1 unsigned int BorderFlags

Border flags.

#### 6.15.2.2 unsigned int EnderFlags

Limit switches flags.

#### 6.15.2.3 float LeftBorder

Left border position, used if BORDER_IS_ENCODER flag is set.

Corrected by the table.

#### 6.15.2.4 float RightBorder

Right border position, used if BORDER_IS_ENCODER flag is set.

Corrected by the table.

## 6.16 edges_settings_t Struct Reference

Edges settings.

### Data Fields

- unsigned int BorderFlags
  *Border flags.*
- unsigned int EnderFlags
  *Limit switches flags.*
- int LeftBorder
  *Left border position, used if BORDER_IS_ENCODER flag is set.*
- int uLeftBorder
  *Left border position in microsteps(used with stepper motor only).*
- int RightBorder
  *Right border position, used if BORDER_IS_ENCODER flag is set.*
- int uRightBorder
  *Right border position in microsteps.*

### 6.16.1 Detailed Description

Edges settings.

This structure contains border and limit switches settings. Please load new engine settings when you change positioner etc. Please note that wrong engine settings lead to device malfunction, can lead to irreversible damage of board.

See Also

set_edges_settings
get_edges_settings
get_edges_settings, set_edges_settings

### 6.16.2 Field Documentation

#### 6.16.2.1 unsigned int BorderFlags

Border flags.

#### 6.16.2.2 unsigned int EnderFlags

Limit switches flags.

#### 6.16.2.3 int LeftBorder

Left border position, used if BORDER_IS_ENCODER flag is set.

#### 6.16.2.4 int RightBorder

Right border position, used if BORDER_IS_ENCODER flag is set.

#### 6.16.2.5 int uLeftBorder

Left border position in microsteps(used with stepper motor only).

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings).

#### 6.16.2.6 int uRightBorder

Right border position in microsteps.

Used with stepper motor only. Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings).

## 6.17 emf_settings_t Struct Reference

EMF settings.

### Data Fields

- float L

  *The inductance of the windings of the motor.*
- float R

  *The resistance of the windings of the motor.*
- float Km

  *Electromechanical ratio of the motor.*
- unsigned int BackEMFFlags

  *Flags of auto-detection of characteristics of windings of the engine.*

### 6.17.1 Detailed Description

EMF settings.

This structure contains the data for Electromechanical characteristics(EMF) of the motor. They determine the inductance, resistance and Electromechanical coefficient of the motor. This data is stored in the flash memory of the controller. Please download the new settings when you change the motor. Remember that improper settings of the EMF may damage the equipment.

See Also

set_emf_settings
get_emf_settings
get_emf_settings, set_emf_settings

### 6.17.2 Field Documentation

#### 6.17.2.1 unsigned int BackEMFFlags

Flags of auto-detection of characteristics of windings of the engine.

#### 6.17.2.2 float Km

Electromechanical ratio of the motor.

#### 6.17.2.3 float L

The inductance of the windings of the motor.

#### 6.17.2.4 float R

The resistance of the windings of the motor.

## 6.18 encoder_information_t Struct Reference

Encoder information.

### Data Fields

- char Manufacturer [17]
  *Manufacturer.*
- char PartNumber [25]
  *Series and PartNumber.*

### 6.18.1 Detailed Description

Encoder information.

See Also

set_encoder_information
get_encoder_information
get_encoder_information, set_encoder_information

### 6.18.2 Field Documentation

#### 6.18.2.1 char Manufacturer[17]

Manufacturer.

Max string length: 16 chars.

#### 6.18.2.2 char PartNumber[25]

Series and PartNumber.

Max string length: 24 chars.

## 6.19 encoder_settings_t Struct Reference

Encoder settings.

## Data Fields

- float MaxOperatingFrequency
  *Max operation frequency (kHz).*
- float SupplyVoltageMin
  *Minimum supply voltage (V).*
- float SupplyVoltageMax
  *Maximum supply voltage (V).*
- float MaxCurrentConsumption
  *Max current consumption (mA).*
- unsigned int PPR
  *The number of counts per revolution.*
- unsigned int EncoderSettings
  *Encoder settings flags.*

### 6.19.1 Detailed Description

Encoder settings.

See Also

set_encoder_settings
get_encoder_settings
get_encoder_settings, set_encoder_settings

### 6.19.2 Field Documentation

#### 6.19.2.1 unsigned int EncoderSettings

Encoder settings flags.

#### 6.19.2.2 float MaxCurrentConsumption

Max current consumption (mA).

Data type: float.

#### 6.19.2.3 float MaxOperatingFrequency

Max operation frequency (kHz).

Data type: float.

#### 6.19.2.4 float SupplyVoltageMax

Maximum supply voltage (V).

Data type: float.

#### 6.19.2.5 float SupplyVoltageMin

Minimum supply voltage (V).

Data type: float.

## 6.20 engine_advansed_setup_t Struct Reference

EAS settings.

### Data Fields

- unsigned int stepcloseloop_Kw
  *Mixing ratio of the actual and set speed, range [0, 100], default value 50.*
- unsigned int stepcloseloop_Kp_low
  *Position feedback in the low-speed zone, range [0, 65535], default value 1000.*
- unsigned int stepcloseloop_Kp_high
  *Position feedback in the high-speed zone, range [0, 65535], default value 33.*

### 6.20.1 Detailed Description

EAS settings.

This structure is intended for setting parameters of algorithms that cannot be attributed to standard Kp, Ki, Kd, and L, R, Km.

See Also

set_engine_advansed_setup
get_engine_advansed_setup
get_engine_advansed_setup, set_engine_advansed_setup

### 6.20.2 Field Documentation

#### 6.20.2.1 unsigned int stepcloseloop_Kp_high

Position feedback in the high-speed zone, range [0, 65535], default value 33.

#### 6.20.2.2 unsigned int stepcloseloop_Kp_low

Position feedback in the low-speed zone, range [0, 65535], default value 1000.

#### 6.20.2.3 unsigned int stepcloseloop_Kw

Mixing ratio of the actual and set speed, range [0, 100], default value 50.

## 6.21 engine_settings_calb_t Struct Reference

Movement limitations and settings, related to the motor, which use user units.

### Data Fields

- unsigned int NomVoltage
  *Rated voltage in tens of mV.*
- unsigned int NomCurrent
  *Rated current (in mA).*
- float NomSpeed

*Nominal speed.*

- unsigned int EngineFlags

  *Flags of engine settings.*

- float Antiplay

  *Number of pulses or steps for backlash (play) compensation procedure.*

- unsigned int MicrostepMode

  *Flags of microstep mode.*

- unsigned int StepsPerRev

  *Number of full steps per revolution(Used with stepper motor only).*

### 6.21.1 Detailed Description

Movement limitations and settings, related to the motor, which use user units.

This structure contains useful motor settings. These settings specify motor shaft movement algorithm, list of limitations and rated characteristics. All boards are supplied with standard set of engine setting on controller's flash memory. Please load new engine settings when you change motor, encoder, positioner etc. Please note that wrong engine settings lead to device malfunction, can lead to irreversible damage of board.

See Also

set_engine_settings_calb
get_engine_settings_calb
get_engine_settings, set_engine_settings

### 6.21.2 Field Documentation

#### 6.21.2.1 float Antiplay

Number of pulses or steps for backlash (play) compensation procedure.

Used if ENGINE_ANTIPLAY flag is set.

#### 6.21.2.2 unsigned int EngineFlags

Flags of engine settings.

#### 6.21.2.3 unsigned int MicrostepMode

Flags of microstep mode.

#### 6.21.2.4 unsigned int NomCurrent

Rated current (in mA).

Controller will keep current consumed by motor below this value if ENGINE_LIMIT_CURR flag is set. Range: 15..8000

#### 6.21.2.5 float NomSpeed

Nominal speed.

Controller will keep motor speed below this value if ENGINE_LIMIT_RPM flag is set.

#### 6.21.2.6 unsigned int NomVoltage

Rated voltage in tens of mV.

Controller will keep the voltage drop on motor below this value if ENGINE_LIMIT_VOLT flag is set (used with DC only).

#### 6.21.2.7 unsigned int StepsPerRev

Number of full steps per revolution(Used with stepper motor only).

Range: 1..65535.

## 6.22 engine_settings_t Struct Reference

Movement limitations and settings, related to the motor.

### Data Fields

- unsigned int NomVoltage
  *Rated voltage in tens of mV.*
- unsigned int NomCurrent
  *Rated current (in mA).*
- unsigned int NomSpeed
  *Nominal (maximum) speed (in whole steps/s or rpm for DC and stepper motor as a master encoder).*
- unsigned int uNomSpeed
  *The fractional part of a nominal speed in microsteps (is only used with stepper motor).*
- unsigned int EngineFlags
  *Flags of engine settings.*
- int Antiplay
  *Number of pulses or steps for backlash (play) compensation procedure.*
- unsigned int MicrostepMode
  *Flags of microstep mode.*
- unsigned int StepsPerRev
  *Number of full steps per revolution(Used with stepper motor only).*

### 6.22.1 Detailed Description

Movement limitations and settings, related to the motor.

This structure contains useful motor settings. These settings specify motor shaft movement algorithm, list of limitations and rated characteristics. All boards are supplied with standard set of engine setting on controller's flash memory. Please load new engine settings when you change motor, encoder, positioner etc. Please note that wrong engine settings lead to device malfunction, can lead to irreversible damage of board.

See Also

set_engine_settings
get_engine_settings
get_engine_settings, set_engine_settings

### 6.22.2 Field Documentation

#### 6.22.2.1 int Antiplay

Number of pulses or steps for backlash (play) compensation procedure.

Used if ENGINE_ANTIPLAY flag is set.

#### 6.22.2.2 unsigned int EngineFlags

Flags of engine settings.

#### 6.22.2.3 unsigned int MicrostepMode

Flags of microstep mode.

#### 6.22.2.4 unsigned int NomCurrent

Rated current (in mA).

Controller will keep current consumed by motor below this value if ENGINE_LIMIT_CURR flag is set. Range: 15..8000

#### 6.22.2.5 unsigned int NomSpeed

Nominal (maximum) speed (in whole steps/s or rpm for DC and stepper motor as a master encoder).

Controller will keep motor shaft RPM below this value if ENGINE_LIMIT_RPM flag is set. Range: 1..100000.

#### 6.22.2.6 unsigned int NomVoltage

Rated voltage in tens of mV.

Controller will keep the voltage drop on motor below this value if ENGINE_LIMIT_VOLT flag is set (used with DC only).

#### 6.22.2.7 unsigned int StepsPerRev

Number of full steps per revolution(Used with stepper motor only).

Range: 1..65535.

#### 6.22.2.8 unsigned int uNomSpeed

The fractional part of a nominal speed in microsteps (is only used with stepper motor).

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings).

## 6.23 entype_settings_t Struct Reference

Engine type and driver type settings.

### Data Fields

- unsigned int EngineType

  *Flags of engine type.*
- unsigned int DriverType

  *Flags of driver type.*

### 6.23.1 Detailed Description

Engine type and driver type settings.

Parameters

| | |
|---|---|
| *id* | an identifier of device |
| *EngineType* | engine type |
| *DriverType* | driver type |

See Also

get_entype_settings, set_entype_settings

### 6.23.2 Field Documentation

#### 6.23.2.1 unsigned int DriverType

Flags of driver type.

#### 6.23.2.2 unsigned int EngineType

Flags of engine type.

## 6.24 extended_settings_t Struct Reference

EST settings.

### Data Fields

- unsigned int **Param1**

### 6.24.1 Detailed Description

EST settings.

This structure EST.

See Also

set_extended_settings
get_extended_settings
get_extended_settings, set_extended_settings

## 6.25 extio_settings_t Struct Reference

EXTIO settings.

### Data Fields

- unsigned int EXTIOSetupFlags
  *External IO setup flags.*
- unsigned int EXTIOModeFlags
  *External IO mode flags.*

### 6.25.1 Detailed Description

EXTIO settings.

This structure contains all EXTIO settings. By default input event are signalled through rising front and output states are signalled by high logic state.

See Also

get_extio_settings
set_extio_settings
get_extio_settings, set_extio_settings

### 6.25.2 Field Documentation

#### 6.25.2.1 unsigned int EXTIOModeFlags

External IO mode flags.

#### 6.25.2.2 unsigned int EXTIOSetupFlags

External IO setup flags.

## 6.26 feedback_settings_t Struct Reference

Feedback settings.

### Data Fields

- unsigned int IPS
  *The number of encoder counts per shaft revolution.*
- unsigned int FeedbackType
  *Feedback type.*
- unsigned int FeedbackFlags
  *Describes feedback flags.*
- unsigned int CountsPerTurn
  *The number of encoder counts per shaft revolution.*

### 6.26.1 Detailed Description

Feedback settings.

This structure contains feedback settings.

See Also

get_feedback_settings, set_feedback_settings

### 6.26.2 Field Documentation

#### 6.26.2.1 unsigned int CountsPerTurn

The number of encoder counts per shaft revolution.

Range: 1..4294967295. To use the CountsPerTurn field, write 0 in the IPS field, otherwise the value from the IPS field will be used.

#### 6.26.2.2 unsigned int FeedbackFlags

Describes feedback flags.

#### 6.26.2.3 unsigned int FeedbackType

Feedback type.

#### 6.26.2.4 unsigned int IPS

The number of encoder counts per shaft revolution.

Range: 1..655535. The field is obsolete, it is recommended to write 0 to IPS and use the extended CountsPerTurn field. You may need to update the controller firmware to the latest version.

## 6.27 gear_information_t Struct Reference

Gear information.

### Data Fields

- char Manufacturer [17]
  *Manufacturer.*
- char PartNumber [25]
  *Series and PartNumber.*

### 6.27.1 Detailed Description

Gear information.

See Also

set_gear_information
get_gear_information
get_gear_information, set_gear_information

### 6.27.2 Field Documentation

#### 6.27.2.1 char Manufacturer[17]

Manufacturer.

Max string length: 16 chars.

#### 6.27.2.2 char PartNumber[25]

Series and PartNumber.

Max string length: 24 chars.

## 6.28 gear_settings_t Struct Reference

Gear setings.

### Data Fields

- float ReductionIn
  *Input reduction coefficient.*
- float ReductionOut
  *Output reduction coefficient.*
- float RatedInputTorque
  *Max continuous torque (N m).*
- float RatedInputSpeed
  *Max speed on the input shaft (rpm).*
- float MaxOutputBacklash
  *Output backlash of the reduction gear(degree).*
- float InputInertia
  *Equivalent input gear inertia (g cm2).*
- float Efficiency
  *Reduction gear efficiency (%).*

### 6.28.1 Detailed Description

Gear setings.

See Also

set_gear_settings
get_gear_settings
get_gear_settings, set_gear_settings

### 6.28.2 Field Documentation

#### 6.28.2.1 float Efficiency

Reduction gear efficiency (%).

Data type: float.

#### 6.28.2.2 float InputInertia

Equivalent input gear inertia (g cm2).

Data type: float.

#### 6.28.2.3 float MaxOutputBacklash

Output backlash of the reduction gear(degree).

Data type: float.

#### 6.28.2.4 float RatedInputSpeed

Max speed on the input shaft (rpm).

Data type: float.

#### 6.28.2.5 float RatedInputTorque

Max continuous torque (N m).

Data type: float.

#### 6.28.2.6 float ReductionIn

Input reduction coefficient.

(Output = (ReductionOut / ReductionIn) $*$ Input) Data type: float.

#### 6.28.2.7 float ReductionOut

Output reduction coefficient.

(Output = (ReductionOut / ReductionIn) $*$ Input) Data type: float.

## 6.29 get_position_calb_t Struct Reference

Position information.

### Data Fields

- float Position
  *The position in the engine.*
- long_t EncPosition
  *Encoder position.*

### 6.29.1 Detailed Description

Position information.

Useful structure that contains position value in user units for stepper motor and encoder steps of all engines.

See Also

get_position

### 6.29.2 Field Documentation

#### 6.29.2.1 long_t EncPosition

Encoder position.

#### 6.29.2.2 float Position

The position in the engine.

Corrected by the table.

## 6.30 get_position_t Struct Reference

Position information.

### Data Fields

- int Position

  *The position of the whole steps in the engine.*
- int uPosition

  *Microstep position is only used with stepper motors.*
- long_t EncPosition

  *Encoder position.*

### 6.30.1 Detailed Description

Position information.

Useful structure that contains position value in steps and micro for stepper motor and encoder steps of all engines.

See Also

get_position

### 6.30.2 Field Documentation

#### 6.30.2.1 long_t EncPosition

Encoder position.

#### 6.30.2.2 int uPosition

Microstep position is only used with stepper motors.

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings).

## 6.31 globally_unique_identifier_t Struct Reference

Globally unique identifier.

### Data Fields

- unsigned int UniqueID0
  *Unique ID 0.*
- unsigned int UniqueID1
  *Unique ID 1.*
- unsigned int UniqueID2
  *Unique ID 2.*
- unsigned int UniqueID3
  *Unique ID 3.*

### 6.31.1 Detailed Description

Globally unique identifier.

See Also

get_globally_unique_identifier

### 6.31.2 Field Documentation

#### 6.31.2.1 unsigned int UniqueID0

Unique ID 0.

#### 6.31.2.2 unsigned int UniqueID1

Unique ID 1.

#### 6.31.2.3 unsigned int UniqueID2

Unique ID 2.

#### 6.31.2.4 unsigned int UniqueID3

Unique ID 3.

## 6.32 hallsensor_information_t Struct Reference

Hall sensor information.

### Data Fields

- char Manufacturer [17]
  *Manufacturer.*
- char PartNumber [25]
  *Series and PartNumber.*

### 6.32.1 Detailed Description

Hall sensor information.

See Also

set_hallsensor_information
get_hallsensor_information
get_hallsensor_information, set_hallsensor_information

### 6.32.2 Field Documentation

#### 6.32.2.1 char Manufacturer[17]

Manufacturer.

Max string length: 16 chars.

#### 6.32.2.2 char PartNumber[25]

Series and PartNumber.

Max string length: 24 chars.

## 6.33 hallsensor_settings_t Struct Reference

Hall sensor settings.

### Data Fields

- float MaxOperatingFrequency
  *Max operation frequency (kHz).*
- float SupplyVoltageMin
  *Minimum supply voltage (V).*
- float SupplyVoltageMax
  *Maximum supply voltage (V).*
- float MaxCurrentConsumption
  *Max current consumption (mA).*
- unsigned int PPR
  *The number of counts per revolution.*

### 6.33.1 Detailed Description

Hall sensor settings.

See Also

set_hallsensor_settings
get_hallsensor_settings
get_hallsensor_settings, set_hallsensor_settings

### 6.33.2 Field Documentation

#### 6.33.2.1 float MaxCurrentConsumption

Max current consumption (mA).

Data type: float.

#### 6.33.2.2 float MaxOperatingFrequency

Max operation frequency (kHz).

Data type: float.

#### 6.33.2.3 float SupplyVoltageMax

Maximum supply voltage (V).

Data type: float.

#### 6.33.2.4 float SupplyVoltageMin

Minimum supply voltage (V).

Data type: float.

## 6.34 home_settings_calb_t Struct Reference

Position calibration settings which use user units.

### Data Fields

- float FastHome
  *Speed used for first motion.*
- float SlowHome
  *Speed used for second motion.*
- float HomeDelta
  *Distance from break point.*
- unsigned int HomeFlags
  *Home settings flags.*

### 6.34.1 Detailed Description

Position calibration settings which use user units.

This structure contains settings used in position calibrating. It specify behaviour of calibrating position.

See Also

get_home_settings_calb
set_home_settings_calb
command_home
get_home_settings, set_home_settings

### 6.34.2 Field Documentation

#### 6.34.2.1 float FastHome

Speed used for first motion.

#### 6.34.2.2 float HomeDelta

Distance from break point.

#### 6.34.2.3 unsigned int HomeFlags

Home settings flags.

#### 6.34.2.4 float SlowHome

Speed used for second motion.

## 6.35 home_settings_t Struct Reference

Position calibration settings.

### Data Fields

- unsigned int FastHome
  *Speed used for first motion (full steps).*
- unsigned int uFastHome
  *Part of the speed for first motion, microsteps.*
- unsigned int SlowHome
  *Speed used for second motion (full steps).*
- unsigned int uSlowHome
  *Part of the speed for second motion, microsteps.*
- int HomeDelta
  *Distance from break point (full steps).*
- int uHomeDelta
  *Part of the delta distance, microsteps.*
- unsigned int HomeFlags
  *Home settings flags.*

### 6.35.1 Detailed Description

Position calibration settings.

This structure contains settings used in position calibrating. It specify behaviour of calibrating position.

See Also

get_home_settings
set_home_settings
command_home
get_home_settings, set_home_settings

### 6.35.2 Field Documentation

#### 6.35.2.1 unsigned int FastHome

Speed used for first motion (full steps).

Range: 0..100000.

#### 6.35.2.2 int HomeDelta

Distance from break point (full steps).

#### 6.35.2.3 unsigned int HomeFlags

Home settings flags.

#### 6.35.2.4 unsigned int SlowHome

Speed used for second motion (full steps).

Range: 0..100000.

#### 6.35.2.5 unsigned int uFastHome

Part of the speed for first motion, microsteps.

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings).

#### 6.35.2.6 int uHomeDelta

Part of the delta distance, microsteps.

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings).

#### 6.35.2.7 unsigned int uSlowHome

Part of the speed for second motion, microsteps.

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings).

## 6.36 init_random_t Struct Reference

Random key.

### Data Fields

- uint8_t key [16]
  *Random key.*

### 6.36.1 Detailed Description

Random key.

Structure that contains random key used in encryption of WKEY and SSER command contents.

See Also

get_init_random

### 6.36.2 Field Documentation

#### 6.36.2.1 uint8_t key[16]

Random key.

## 6.37 joystick_settings_t Struct Reference

Joystick settings.

### Data Fields

- unsigned int JoyLowEnd
  *Joystick lower end position.*
- unsigned int JoyCenter
  *Joystick center position.*
- unsigned int JoyHighEnd
  *Joystick higher end position.*
- unsigned int ExpFactor
  *Exponential nonlinearity factor.*
- unsigned int DeadZone
  *Joystick dead zone.*
- unsigned int JoyFlags
  *Joystick flags.*

### 6.37.1 Detailed Description

Joystick settings.

This structure contains joystick parameters. If joystick position is outside DeadZone limits from the central position a movement with speed, defined by the joystick DeadZone edge to 100% deviation, begins. Joystick positions inside DeadZone limits correspond to zero speed (soft stop of motion) and positions beyond Low and High limits correspond MaxSpeed [i] or -MaxSpeed [i] (see command SCTL), where i = 0 by default and can be changed with left/right buttons (see command SCTL). If next speed in list is zero (both integer and microstep parts), the button press is ignored. First speed in list shouldn't be zero. The relationship between the deviation and the rate is exponential, allowing no switching speed combine high mobility and accuracy.

See Also

set_joystick_settings
get_joystick_settings
get_joystick_settings, set_joystick_settings

### 6.37.2 Field Documentation

#### 6.37.2.1 unsigned int DeadZone

Joystick dead zone.

#### 6.37.2.2 unsigned int ExpFactor

Exponential nonlinearity factor.

#### 6.37.2.3 unsigned int JoyCenter

Joystick center position.

Range: 0..10000.

#### 6.37.2.4 unsigned int JoyFlags

Joystick flags.

#### 6.37.2.5 unsigned int JoyHighEnd

Joystick higher end position.

Range: 0..10000.

#### 6.37.2.6 unsigned int JoyLowEnd

Joystick lower end position.

Range: 0..10000.

## 6.38 measurements_t Struct Reference

The buffer holds no more than 25 points.

### Data Fields

- int Speed [25]

  *Current speed in microsteps per second (whole steps are recalculated taking into account the current step division mode) or encoder counts per second.*
- int Error [25]

  *Current error in microsteps per second (whole steps are recalculated taking into account the current step division mode) or encoder counts per second.*
- unsigned int Length

  *Length of actual data in buffer.*

### 6.38.1 Detailed Description

The buffer holds no more than 25 points.

The exact length of the received buffer is reflected in the Length field.

See Also

measurements
get_measurements

### 6.38.2 Field Documentation

#### 6.38.2.1 int Error[25]

Current error in microsteps per second (whole steps are recalculated taking into account the current step division mode) or encoder counts per second.

#### 6.38.2.2 unsigned int Length

Length of actual data in buffer.

#### 6.38.2.3 int Speed[25]

Current speed in microsteps per second (whole steps are recalculated taking into account the current step division mode) or encoder counts per second.

## 6.39 motor_information_t Struct Reference

motor information.

### Data Fields

- char Manufacturer [17]
  *Manufacturer.*
- char PartNumber [25]
  *Series and PartNumber.*

### 6.39.1 Detailed Description

motor information.

See Also

set_motor_information
get_motor_information
get_motor_information, set_motor_information

### 6.39.2 Field Documentation

#### 6.39.2.1 char Manufacturer[17]

Manufacturer.

Max string length: 16 chars.

#### 6.39.2.2 char PartNumber[25]

Series and PartNumber.

Max string length: 24 chars.

## 6.40 motor_settings_t Struct Reference

Physical characteristics and limitations of the motor.

### Data Fields

- unsigned int MotorType

  *Motor Type flags.*
- unsigned int ReservedField

  *Reserved.*
- unsigned int Poles

  *Number of pole pairs for DC or BLDC motors or number of steps per rotation for stepper motor.*
- unsigned int Phases

  *Number of phases for BLDC motors.*
- float NominalVoltage

  *Nominal voltage on winding (B).*
- float NominalCurrent

  *Maximum direct current in winding for DC and BLDC engines, nominal current in windings for stepper motor (A).*
- float NominalSpeed

  *Not used.*
- float NominalTorque

  *Nominal torque(mN m).*
- float NominalPower

  *Nominal power(W).*
- float WindingResistance

  *Resistance of windings for DC engine, each of two windings for stepper motor or each of there windings for BLDC engine(Ohm).*
- float WindingInductance

  *Inductance of windings for DC engine, each of two windings for stepper motor or each of there windings for BLDC engine(mH).*
- float RotorInertia

  *Rotor inertia(g cm2).*
- float StallTorque

  *Torque hold position for a stepper motor or torque at a motionless rotor for other types of engines (mN m).*
- float DetentTorque

  *Holding torque position with un-powered coils (mN m).*
- float TorqueConstant

  *Torque constant, which determines the aspect ratio of maximum moment of force from the rotor current flowing in the coil (mN m / A).*
- float SpeedConstant

  *Velocity constant, which determines the value or amplitude of the induced voltage on the motion of DC or BLDC motor (rpm / V) or stepper motor (steps/s / V).*
- float SpeedTorqueGradient

  *Speed torque gradient (rpm / mN m).*
- float MechanicalTimeConstant

*Mechanical time constant (ms).*

- float MaxSpeed

  *The maximum speed for stepper motors (steps/s) or DC and BLDC motors (rmp).*
- float MaxCurrent

  *The maximum current in the winding (A).*
- float MaxCurrentTime

  *Safe duration of overcurrent in the winding (ms).*
- float NoLoadCurrent

  *The current consumption in idle mode (A).*
- float NoLoadSpeed

  *Idle speed (rpm).*

## 6.40.1 Detailed Description

Physical characteristics and limitations of the motor.

See Also

set_motor_settings
get_motor_settings
get_motor_settings, set_motor_settings

## 6.40.2 Field Documentation

### 6.40.2.1 float DetentTorque

Holding torque position with un-powered coils (mN m).

Data type: float.

### 6.40.2.2 float MaxCurrent

The maximum current in the winding (A).

Data type: float.

### 6.40.2.3 float MaxCurrentTime

Safe duration of overcurrent in the winding (ms).

Data type: float.

### 6.40.2.4 float MaxSpeed

The maximum speed for stepper motors (steps/s) or DC and BLDC motors (rmp).

Data type: float.

### 6.40.2.5 float MechanicalTimeConstant

Mechanical time constant (ms).

Data type: float.

#### 6.40.2.6 unsigned int MotorType

Motor Type flags.

#### 6.40.2.7 float NoLoadCurrent

The current consumption in idle mode (A).

Used for DC and BLDC motors. Data type: float.

#### 6.40.2.8 float NoLoadSpeed

Idle speed (rpm).

Used for DC and BLDC motors. Data type: float.

#### 6.40.2.9 float NominalCurrent

Maximum direct current in winding for DC and BLDC engines, nominal current in windings for stepper motor (A).

Data type: float.

#### 6.40.2.10 float NominalPower

Nominal power(W).

Used for DC and BLDC engine. Data type: float.

#### 6.40.2.11 float NominalSpeed

Not used.

Nominal speed(rpm). Used for DC and BLDC engine. Data type: float.

#### 6.40.2.12 float NominalTorque

Nominal torque(mN m).

Used for DC and BLDC engine. Data type: float.

#### 6.40.2.13 float NominalVoltage

Nominal voltage on winding (B).

Data type: float

#### 6.40.2.14 unsigned int Phases

Number of phases for BLDC motors.

#### 6.40.2.15 unsigned int Poles

Number of pole pairs for DC or BLDC motors or number of steps per rotation for stepper motor.

#### 6.40.2.16 float RotorInertia

Rotor inertia(g cm2).

Data type: float.

#### 6.40.2.17 float SpeedConstant

Velocity constant, which determines the value or amplitude of the induced voltage on the motion of DC or BLDC motor (rpm / V) or stepper motor (steps/s / V).

Data type: float.

#### 6.40.2.18 float SpeedTorqueGradient

Speed torque gradient (rpm / mN m).

Data type: float.

#### 6.40.2.19 float StallTorque

Torque hold position for a stepper motor or torque at a motionless rotor for other types of engines (mN m).

Data type: float.

#### 6.40.2.20 float TorqueConstant

Torque constant, which determines the aspect ratio of maximum moment of force from the rotor current flowing in the coil (mN m / A).

Used mainly for DC motors. Data type: float.

#### 6.40.2.21 float WindingInductance

Inductance of windings for DC engine, each of two windings for stepper motor or each of there windings for BLDC engine(mH).

Data type: float.

#### 6.40.2.22 float WindingResistance

Resistance of windings for DC engine, each of two windings for stepper motor or each of there windings for BLDC engine(Ohm).

Data type: float.

## 6.41 move_settings_calb_t Struct Reference

Move settings which use user units.

### Data Fields

- float Speed

  *Target speed.*

- float Accel

  *Motor shaft acceleration, steps/s^2(stepper motor) or RPM/s(DC).*
- float Decel

  *Motor shaft deceleration, steps/s^2(stepper motor) or RPM/s(DC).*
- float AntiplaySpeed

  *Speed in antiplay mode.*
- unsigned int MoveFlags

  *Flags of the motion parameters.*

### 6.41.1 Detailed Description

Move settings which use user units.

See Also

set_move_settings_calb
get_move_settings_calb
get_move_settings, set_move_settings

### 6.41.2 Field Documentation

#### 6.41.2.1 float Accel

Motor shaft acceleration, steps/s^2(stepper motor) or RPM/s(DC).

#### 6.41.2.2 float AntiplaySpeed

Speed in antiplay mode.

#### 6.41.2.3 float Decel

Motor shaft deceleration, steps/s^2(stepper motor) or RPM/s(DC).

#### 6.41.2.4 unsigned int MoveFlags

Flags of the motion parameters.

#### 6.41.2.5 float Speed

Target speed.

## 6.42 move_settings_t Struct Reference

Move settings.

### Data Fields

- unsigned int Speed

  *Target speed (for stepper motor: steps/s, for DC: rpm).*
- unsigned int uSpeed

*Target speed in microstep fractions/s.*

- unsigned int Accel

  *Motor shaft acceleration, steps/s^2(stepper motor) or RPM/s(DC).*
- unsigned int Decel

  *Motor shaft deceleration, steps/s^2(stepper motor) or RPM/s(DC).*
- unsigned int AntiplaySpeed

  *Speed in antiplay mode, full steps/s(stepper motor) or RPM(DC).*
- unsigned int uAntiplaySpeed

  *Speed in antiplay mode, microsteps/s.*
- unsigned int MoveFlags

  *Flags of the motion parameters.*

## 6.42.1 Detailed Description

Move settings.

See Also

set_move_settings
get_move_settings
get_move_settings, set_move_settings

## 6.42.2 Field Documentation

### 6.42.2.1 unsigned int Accel

Motor shaft acceleration, steps/s^2(stepper motor) or RPM/s(DC).

Range: 1..65535.

### 6.42.2.2 unsigned int AntiplaySpeed

Speed in antiplay mode, full steps/s(stepper motor) or RPM(DC).

Range: 0..100000.

### 6.42.2.3 unsigned int Decel

Motor shaft deceleration, steps/s^2(stepper motor) or RPM/s(DC).

Range: 1..65535.

### 6.42.2.4 unsigned int MoveFlags

Flags of the motion parameters.

### 6.42.2.5 unsigned int Speed

Target speed (for stepper motor: steps/s, for DC: rpm).

Range: 0..100000.

#### 6.42.2.6 unsigned int uAntiplaySpeed

Speed in antiplay mode, microsteps/s.

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings). Used with stepper motor only.

#### 6.42.2.7 unsigned int uSpeed

Target speed in microstep fractions/s.

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings). Using with stepper motor only.

## 6.43 nonvolatile_memory_t Struct Reference

Userdata for save into FRAM.

### Data Fields

- unsigned int UserData [7]
  *User data.*

### 6.43.1 Detailed Description

Userdata for save into FRAM.

See Also

get_nonvolatile_memory, set_nonvolatile_memory

### 6.43.2 Field Documentation

#### 6.43.2.1 unsigned int UserData[7]

User data.

Can be set by user for his/her convinience. Each element of the array stores only 32 bits of user data. This is important on systems where an int type contains more than 4 bytes. For example that all amd64 systems.

## 6.44 pid_settings_t Struct Reference

PID settings.

### Data Fields

- unsigned int KpU
  *Proportional gain for voltage PID routine.*
- unsigned int KiU
  *Integral gain for voltage PID routine.*
- unsigned int KdU
  *Differential gain for voltage PID routine.*

- float Kpf

  *Proportional gain for BLDC position PID routine.*
- float Kif

  *Integral gain for BLDC position PID routine.*
- float Kdf

  *Differential gain for BLDC position PID routine.*

### 6.44.1 Detailed Description

PID settings.

This structure contains factors for PID routine. It specify behaviour of PID routine for voltage. These factors are slightly different for different positioners. All boards are supplied with standard set of PID setting on controller's flash memory. Please load new PID settings when you change positioner. Please note that wrong PID settings lead to device malfunction.

See Also

set_pid_settings
get_pid_settings
get_pid_settings, set_pid_settings

## 6.45 power_settings_t Struct Reference

Step motor power settings.

### Data Fields

- unsigned int HoldCurrent

  *Current in holding regime, percent of nominal.*
- unsigned int CurrReductDelay

  *Time in ms from going to STOP state to reducting current.*
- unsigned int PowerOffDelay

  *Time in s from going to STOP state to turning power off.*
- unsigned int CurrentSetTime

  *Time in ms to reach nominal current.*
- unsigned int PowerFlags

  *Flags of power settings of stepper motor.*

### 6.45.1 Detailed Description

Step motor power settings.

See Also

set_move_settings
get_move_settings
get_power_settings, set_power_settings

### 6.45.2 Field Documentation

#### 6.45.2.1 unsigned int CurrentSetTime

Time in ms to reach nominal current.

#### 6.45.2.2 unsigned int CurrReductDelay

Time in ms from going to STOP state to reducting current.

#### 6.45.2.3 unsigned int HoldCurrent

Current in holding regime, percent of nominal.

Range: 0..100.

#### 6.45.2.4 unsigned int PowerFlags

Flags of power settings of stepper motor.

#### 6.45.2.5 unsigned int PowerOffDelay

Time in s from going to STOP state to turning power off.

## 6.46 secure_settings_t Struct Reference

This structure contains raw analog data from ADC embedded on board.

### Data Fields

- unsigned int LowUpwrOff
  *Lower voltage limit to turn off the motor, tens of mV.*
- unsigned int CriticalIpwr
  *Maximum motor current which triggers ALARM state, in mA.*
- unsigned int CriticalUpwr
  *Maximum motor voltage which triggers ALARM state, tens of mV.*
- unsigned int CriticalT
  *Maximum temperature, which triggers ALARM state, in tenths of degrees Celcius.*
- unsigned int CriticalIusb
  *Maximum USB current which triggers ALARM state, in mA.*
- unsigned int CriticalUusb
  *Maximum USB voltage which triggers ALARM state, tens of mV.*
- unsigned int MinimumUusb
  *Minimum USB voltage which triggers ALARM state, tens of mV.*
- unsigned int Flags
  *Flags of secure settings.*

### 6.46.1 Detailed Description

This structure contains raw analog data from ADC embedded on board.

These data used for device testing and deep recalibraton by manufacturer only.

See Also

get_secure_settings
set_secure_settings
get_secure_settings, set_secure_settings

### 6.46.2 Field Documentation

#### 6.46.2.1 unsigned int CriticalIpwr

Maximum motor current which triggers ALARM state, in mA.

#### 6.46.2.2 unsigned int CriticalIusb

Maximum USB current which triggers ALARM state, in mA.

#### 6.46.2.3 unsigned int CriticalT

Maximum temperature, which triggers ALARM state, in tenths of degrees Celcius.

#### 6.46.2.4 unsigned int CriticalUpwr

Maximum motor voltage which triggers ALARM state, tens of mV.

#### 6.46.2.5 unsigned int CriticalUusb

Maximum USB voltage which triggers ALARM state, tens of mV.

#### 6.46.2.6 unsigned int Flags

Flags of secure settings.

#### 6.46.2.7 unsigned int LowUpwrOff

Lower voltage limit to turn off the motor, tens of mV.

#### 6.46.2.8 unsigned int MinimumUusb

Minimum USB voltage which triggers ALARM state, tens of mV.

## 6.47 serial_number_t Struct Reference

Serial number structure and hardware version.

### Data Fields

- unsigned int SN
  *New board serial number.*
- uint8_t Key [32]
  *Protection key (256 bit).*
- unsigned int Major
  *The major number of the hardware version.*
- unsigned int Minor
  *Minor number of the hardware version.*
- unsigned int Release
  *Number of edits this release of hardware.*

### 6.47.1 Detailed Description

Serial number structure and hardware version.

The structure keep new serial number, hardware version and valid key. The SN and hardware version are changed and saved when transmitted key matches stored key. Can be used by manufacturer only.

See Also

set_serial_number

### 6.47.2 Field Documentation

#### 6.47.2.1 uint8_t Key[32]

Protection key (256 bit).

#### 6.47.2.2 unsigned int Major

The major number of the hardware version.

#### 6.47.2.3 unsigned int Minor

Minor number of the hardware version.

#### 6.47.2.4 unsigned int Release

Number of edits this release of hardware.

#### 6.47.2.5 unsigned int SN

New board serial number.

## 6.48 set_position_calb_t Struct Reference

Position information which use user units.

### Data Fields

- float Position
  *The position in the engine.*
- long_t EncPosition
  *Encoder position.*
- unsigned int PosFlags
  *Position setting flags.*

### 6.48.1 Detailed Description

Position information which use user units.

Useful structure that contains position value in steps and micro for stepper motor and encoder steps of all engines.

See Also

set_position

### 6.48.2 Field Documentation

#### 6.48.2.1 long_t EncPosition

Encoder position.

#### 6.48.2.2 unsigned int PosFlags

Position setting flags.

#### 6.48.2.3 float Position

The position in the engine.

## 6.49 set_position_t Struct Reference

Position information.

### Data Fields

- int Position
  *The position of the whole steps in the engine.*
- int uPosition
  *Microstep position is only used with stepper motors.*
- long_t EncPosition
  *Encoder position.*
- unsigned int PosFlags
  *Position setting flags.*

### 6.49.1 Detailed Description

Position information.

Useful structure that contains position value in steps and micro for stepper motor and encoder steps of all engines.

See Also

set_position

### 6.49.2 Field Documentation

#### 6.49.2.1 long_t EncPosition

Encoder position.

#### 6.49.2.2 unsigned int PosFlags

Position setting flags.

#### 6.49.2.3 int uPosition

Microstep position is only used with stepper motors.

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings).

## 6.50 stage_information_t Struct Reference

Stage information.

### Data Fields

- char Manufacturer [17]
  *Manufacturer.*
- char PartNumber [25]
  *Series and PartNumber.*

### 6.50.1 Detailed Description

Stage information.

See Also

set_stage_information
get_stage_information
get_stage_information, set_stage_information

### 6.50.2 Field Documentation

#### 6.50.2.1 char Manufacturer[17]

Manufacturer.

Max string length: 16 chars.

#### 6.50.2.2 char PartNumber[25]

Series and PartNumber.

Max string length: 24 chars.

## 6.51 stage_name_t Struct Reference

Stage user name.

### Data Fields

- char PositionerName [17]
  *User positioner name.*

### 6.51.1 Detailed Description

Stage user name.

See Also

get_stage_name, set_stage_name

### 6.51.2 Field Documentation

#### 6.51.2.1 char PositionerName[17]

User positioner name.

Can be set by user for his/her convinience. Max string length: 16 chars.

## 6.52 stage_settings_t Struct Reference

Stage settings.

### Data Fields

- float LeadScrewPitch
  *Lead screw pitch (mm).*
- char Units [9]
  *Units for MaxSpeed and TravelRange fields of the structure (steps, degrees, mm, ...).*
- float MaxSpeed
  *Max speed (Units/c).*
- float TravelRange
  *Travel range (Units).*
- float SupplyVoltageMin
  *Supply voltage minimum (V).*
- float SupplyVoltageMax
  *Supply voltage maximum (V).*
- float MaxCurrentConsumption
  *Max current consumption (A).*
- float HorizontalLoadCapacity
  *Horizontal load capacity (kg).*
- float VerticalLoadCapacity
  *Vertical load capacity (kg).*

### 6.52.1 Detailed Description

Stage settings.

See Also

set_stage_settings
get_stage_settings
get_stage_settings, set_stage_settings

## 6.52.2 Field Documentation

### 6.52.2.1 float HorizontalLoadCapacity

Horizontal load capacity (kg).

Data type: float.

### 6.52.2.2 float LeadScrewPitch

Lead screw pitch (mm).

Data type: float.

### 6.52.2.3 float MaxCurrentConsumption

Max current consumption (A).

Data type: float.

### 6.52.2.4 float MaxSpeed

Max speed (Units/c).

Data type: float.

### 6.52.2.5 float SupplyVoltageMax

Supply voltage maximum (V).

Data type: float.

### 6.52.2.6 float SupplyVoltageMin

Supply voltage minimum (V).

Data type: float.

### 6.52.2.7 float TravelRange

Travel range (Units).

Data type: float.

### 6.52.2.8 char Units[9]

Units for MaxSpeed and TravelRange fields of the structure (steps, degrees, mm, ...).

Max string length: 8 chars.

### 6.52.2.9 float VerticalLoadCapacity

Vertical load capacity (kg).

Data type: float.

## 6.53 status_calb_t Struct Reference

Device state which use user units.

### Data Fields

- unsigned int MoveSts
  *Flags of move state.*
- unsigned int MvCmdSts
  *Move command state.*
- unsigned int PWRSts
  *Flags of power state of stepper motor.*
- unsigned int EncSts
  *Encoder state.*
- unsigned int WindSts
  *Winding state.*
- float CurPosition
  *Current position.*
- long_t EncPosition
  *Current encoder position.*
- float CurSpeed
  *Motor shaft speed.*
- int Ipwr
  *Engine current, mA.*
- int Upwr
  *Power supply voltage, tens of mV.*
- int Iusb
  *USB current, mA.*
- int Uusb
  *USB voltage, tens of mV.*
- int CurT
  *Temperature in tenths of degrees C.*
- unsigned int Flags
  *Status flags.*
- unsigned int GPIOFlags
  *Status flags of the GPIO outputs.*
- unsigned int CmdBufFreeSpace
  *This field is a service field.*

### 6.53.1 Detailed Description

Device state which use user units.

Useful structure that contains current controller state, including speed, position and boolean flags.

See Also

get_status_impl

## 6.53.2 Field Documentation

### 6.53.2.1 unsigned int CmdBufFreeSpace

This field is a service field.

It shows the amount of free cells buffer synchronization chain.

### 6.53.2.2 float CurPosition

Current position.

Corrected by the table.

### 6.53.2.3 float CurSpeed

Motor shaft speed.

### 6.53.2.4 int CurT

Temperature in tenths of degrees C.

### 6.53.2.5 long_t EncPosition

Current encoder position.

### 6.53.2.6 unsigned int EncSts

Encoder state.

### 6.53.2.7 unsigned int Flags

Status flags.

### 6.53.2.8 unsigned int GPIOFlags

Status flags of the GPIO outputs.

### 6.53.2.9 int Ipwr

Engine current, mA.

### 6.53.2.10 int Iusb

USB current, mA.

### 6.53.2.11 unsigned int MoveSts

Flags of move state.

#### 6.53.2.12 unsigned int MvCmdSts

Move command state.

#### 6.53.2.13 unsigned int PWRSts

Flags of power state of stepper motor.

#### 6.53.2.14 int Upwr

Power supply voltage, tens of mV.

#### 6.53.2.15 int Uusb

USB voltage, tens of mV.

#### 6.53.2.16 unsigned int WindSts

Winding state.

## 6.54 status_t Struct Reference

Device state.

### Data Fields

- unsigned int MoveSts
  *Flags of move state.*
- unsigned int MvCmdSts
  *Move command state.*
- unsigned int PWRSts
  *Flags of power state of stepper motor.*
- unsigned int EncSts
  *Encoder state.*
- unsigned int WindSts
  *Winding state.*
- int CurPosition
  *Current position.*
- int uCurPosition
  *Step motor shaft position in microsteps.*
- long_t EncPosition
  *Current encoder position.*
- int CurSpeed
  *Motor shaft speed in steps/s or rpm.*
- int uCurSpeed
  *Part of motor shaft speed in microsteps.*
- int Ipwr
  *Engine current, mA.*
- int Upwr

*Power supply voltage, tens of mV.*

- int Iusb

  *USB current, mA.*

- int Uusb

  *USB voltage, tens of mV.*

- int CurT

  *Temperature in tenths of degrees C.*

- unsigned int Flags

  *Status flags.*

- unsigned int GPIOFlags

  *Status flags of the GPIO outputs.*

- unsigned int CmdBufFreeSpace

  *This field is a service field.*

## 6.54.1 Detailed Description

Device state.

Useful structure that contains current controller state, including speed, position and boolean flags.

See Also

get_status_impl

## 6.54.2 Field Documentation

### 6.54.2.1 unsigned int CmdBufFreeSpace

This field is a service field.

It shows the amount of free cells buffer synchronization chain.

### 6.54.2.2 int CurPosition

Current position.

### 6.54.2.3 int CurSpeed

Motor shaft speed in steps/s or rpm.

### 6.54.2.4 int CurT

Temperature in tenths of degrees C.

### 6.54.2.5 long_t EncPosition

Current encoder position.

### 6.54.2.6 unsigned int EncSts

Encoder state.

#### 6.54.2.7 unsigned int Flags

Status flags.

#### 6.54.2.8 unsigned int GPIOFlags

Status flags of the GPIO outputs.

#### 6.54.2.9 int Ipwr

Engine current, mA.

#### 6.54.2.10 int Iusb

USB current, mA.

#### 6.54.2.11 unsigned int MoveSts

Flags of move state.

#### 6.54.2.12 unsigned int MvCmdSts

Move command state.

#### 6.54.2.13 unsigned int PWRSts

Flags of power state of stepper motor.

#### 6.54.2.14 int uCurPosition

Step motor shaft position in microsteps.

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings). Used only with stepper motor.

#### 6.54.2.15 int uCurSpeed

Part of motor shaft speed in microsteps.

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings). Used only with stepper motor.

#### 6.54.2.16 int Upwr

Power supply voltage, tens of mV.

#### 6.54.2.17 int Uusb

USB voltage, tens of mV.

#### 6.54.2.18 unsigned int WindSts

Winding state.

## 6.55 sync_in_settings_calb_t Struct Reference

Synchronization settings which use user units.

### Data Fields

- unsigned int SyncInFlags
  *Flags for synchronization input setup.*
- unsigned int ClutterTime
  *Input synchronization pulse dead time (mks).*
- float Position
  *Desired position or shift.*
- float Speed
  *Target speed.*

### 6.55.1 Detailed Description

Synchronization settings which use user units.

This structure contains all synchronization settings, modes, periods and flags. It specifes behaviour of input synchronization. All boards are supplied with standard set of these settings.

See Also

get_sync_in_settings_calb
set_sync_in_settings_calb
get_sync_in_settings, set_sync_in_settings

### 6.55.2 Field Documentation

#### 6.55.2.1 unsigned int ClutterTime

Input synchronization pulse dead time (mks).

#### 6.55.2.2 float Position

Desired position or shift.

#### 6.55.2.3 float Speed

Target speed.

#### 6.55.2.4 unsigned int SyncInFlags

Flags for synchronization input setup.

# 6.56 sync_in_settings_t Struct Reference

Synchronization settings.

## Data Fields

- unsigned int SyncInFlags

  *Flags for synchronization input setup.*
- unsigned int ClutterTime

  *Input synchronization pulse dead time (mks).*
- int Position

  *Desired position or shift (full steps)*
- int uPosition

  *The fractional part of a position or shift in microsteps.*
- unsigned int Speed

  *Target speed (for stepper motor: steps/s, for DC: rpm).*
- unsigned int uSpeed

  *Target speed in microsteps/s.*

## 6.56.1 Detailed Description

Synchronization settings.

This structure contains all synchronization settings, modes, periods and flags. It specifes behaviour of input synchronization. All boards are supplied with standard set of these settings.

See Also

get_sync_in_settings
set_sync_in_settings
get_sync_in_settings, set_sync_in_settings

## 6.56.2 Field Documentation

### 6.56.2.1 unsigned int ClutterTime

Input synchronization pulse dead time (mks).

### 6.56.2.2 unsigned int Speed

Target speed (for stepper motor: steps/s, for DC: rpm).

Range: 0..100000.

### 6.56.2.3 unsigned int SyncInFlags

Flags for synchronization input setup.

### 6.56.2.4 int uPosition

The fractional part of a position or shift in microsteps.

Is used with stepper motor. Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings).

#### 6.56.2.5 unsigned int uSpeed

Target speed in microsteps/s.

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings). Using with stepper motor only.

## 6.57 sync_out_settings_calb_t Struct Reference

Synchronization settings which use user units.

### Data Fields

- unsigned int SyncOutFlags

  *Flags of synchronization output.*
- unsigned int SyncOutPulseSteps

  *This value specifies duration of output pulse.*
- unsigned int SyncOutPeriod

  *This value specifies number of encoder pulses or steps between two output synchronization pulses when SYNCOUT_ONPERIOD is set.*
- float Accuracy

  *This is the neighborhood around the target coordinates (in encoder pulses or motor steps), which is getting hit in the target position and the momentum generated by the stop.*

### 6.57.1 Detailed Description

Synchronization settings which use user units.

This structure contains all synchronization settings, modes, periods and flags. It specifes behaviour of output synchronization. All boards are supplied with standard set of these settings.

See Also

get_sync_out_settings_calb
set_sync_out_settings_calb
get_sync_out_settings, set_sync_out_settings

### 6.57.2 Field Documentation

#### 6.57.2.1 float Accuracy

This is the neighborhood around the target coordinates (in encoder pulses or motor steps), which is getting hit in the target position and the momentum generated by the stop.

#### 6.57.2.2 unsigned int SyncOutFlags

Flags of synchronization output.

#### 6.57.2.3 unsigned int SyncOutPeriod

This value specifies number of encoder pulses or steps between two output synchronization pulses when SYNCOUT_ONPERIOD is set.

#### 6.57.2.4 unsigned int SyncOutPulseSteps

This value specifies duration of output pulse.

It is measured milliseconds when SYNCOUT_IN_STEPS flag is cleared or in encoder pulses or motor steps when SYNCOUT_IN_STEPS is set.

## 6.58 sync_out_settings_t Struct Reference

Synchronization settings.

### Data Fields

- unsigned int SyncOutFlags
  *Flags of synchronization output.*
- unsigned int SyncOutPulseSteps
  *This value specifies duration of output pulse.*
- unsigned int SyncOutPeriod
  *This value specifies number of encoder pulses or steps between two output synchronization pulses when SYNCOUT_ONPERIOD is set.*
- unsigned int Accuracy
  *This is the neighborhood around the target coordinates, which is getting hit in the target position and the momentum generated by the stop.*
- unsigned int uAccuracy
  *This is the neighborhood around the target coordinates in microsteps (only used with stepper motor).*

### 6.58.1 Detailed Description

Synchronization settings.

This structure contains all synchronization settings, modes, periods and flags. It specifes behaviour of output synchronization. All boards are supplied with standard set of these settings.

See Also

get_sync_out_settings
set_sync_out_settings
get_sync_out_settings, set_sync_out_settings

### 6.58.2 Field Documentation

#### 6.58.2.1 unsigned int Accuracy

This is the neighborhood around the target coordinates, which is getting hit in the target position and the momentum generated by the stop.

#### 6.58.2.2 unsigned int SyncOutFlags

Flags of synchronization output.

#### 6.58.2.3 unsigned int SyncOutPeriod

This value specifies number of encoder pulses or steps between two output synchronization pulses when SYNCOUT_ONPERIOD is set.

#### 6.58.2.4 unsigned int SyncOutPulseSteps

This value specifies duration of output pulse.

It is measured milliseconds when SYNCOUT_IN_STEPS flag is cleared or in encoder pulses or motor steps when SYNCOUT_IN_STEPS is set.

#### 6.58.2.5 unsigned int uAccuracy

This is the neighborhood around the target coordinates in microsteps (only used with stepper motor).

Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings).

## 6.59 uart_settings_t Struct Reference

UART settings.

### Data Fields

- unsigned int Speed
  *UART speed (in bauds)*
- unsigned int UARTSetupFlags
  *UART parity flags*.

### 6.59.1 Detailed Description

UART settings.

This structure contains UART settings.

See Also

get_uart_settings
set_uart_settings
get_uart_settings, set_uart_settings

### 6.59.2 Field Documentation

#### 6.59.2.1 unsigned int UARTSetupFlags

UART parity flags.

# Chapter 7

# File Documentation

## 7.1 ximc.h File Reference

Header file for libximc library.

### Data Structures

- struct calibration_t
  *Calibration companion structure.*
- struct device_network_information_t
  *Device network information structure.*
- struct feedback_settings_t
  *Feedback settings.*
- struct home_settings_t
  *Position calibration settings.*
- struct home_settings_calb_t
  *Position calibration settings which use user units.*
- struct move_settings_t
  *Move settings.*
- struct move_settings_calb_t
  *Move settings which use user units.*
- struct engine_settings_t
  *Movement limitations and settings, related to the motor.*
- struct engine_settings_calb_t
  *Movement limitations and settings, related to the motor, which use user units.*
- struct entype_settings_t
  *Engine type and driver type settings.*
- struct power_settings_t
  *Step motor power settings.*
- struct secure_settings_t
  *This structure contains raw analog data from ADC embedded on board.*
- struct edges_settings_t
  *Edges settings.*
- struct edges_settings_calb_t
  *Edges settings which use user units.*
- struct pid_settings_t
  *PID settings.*

- struct sync_in_settings_t
  *Synchronization settings.*
- struct sync_in_settings_calb_t
  *Synchronization settings which use user units.*
- struct sync_out_settings_t
  *Synchronization settings.*
- struct sync_out_settings_calb_t
  *Synchronization settings which use user units.*
- struct extio_settings_t
  *EXTIO settings.*
- struct brake_settings_t
  *Brake settings.*
- struct control_settings_t
  *Control settings.*
- struct control_settings_calb_t
  *Control settings which use user units.*
- struct joystick_settings_t
  *Joystick settings.*
- struct ctp_settings_t
  *Control position settings(is only used with stepper motor).*
- struct uart_settings_t
  *UART settings.*
- struct calibration_settings_t
  *Calibration settings.*
- struct controller_name_t
  *Controller user name and flags of setting.*
- struct nonvolatile_memory_t
  *Userdata for save into FRAM.*
- struct emf_settings_t
  *EMF settings.*
- struct engine_advansed_setup_t
  *EAS settings.*
- struct extended_settings_t
  *EST settings.*
- struct get_position_t
  *Position information.*
- struct get_position_calb_t
  *Position information.*
- struct set_position_t
  *Position information.*
- struct set_position_calb_t
  *Position information which use user units.*
- struct status_t
  *Device state.*
- struct status_calb_t
  *Device state which use user units.*
- struct measurements_t
  *The buffer holds no more than 25 points.*
- struct chart_data_t
  *Additional device state.*
- struct device_information_t

*Read command controller information.*

- struct serial_number_t

  *Serial number structure and hardware version.*
- struct analog_data_t

  *Analog data.*
- struct debug_read_t

  *Debug data.*
- struct debug_write_t

  *Debug data.*
- struct stage_name_t

  *Stage user name.*
- struct stage_information_t

  *Stage information.*
- struct stage_settings_t

  *Stage settings.*
- struct motor_information_t

  *motor information.*
- struct motor_settings_t

  *Physical characteristics and limitations of the motor.*
- struct encoder_information_t

  *Encoder information.*
- struct encoder_settings_t

  *Encoder settings.*
- struct hallsensor_information_t

  *Hall sensor information.*
- struct hallsensor_settings_t

  *Hall sensor settings.*
- struct gear_information_t

  *Gear information.*
- struct gear_settings_t

  *Gear setings.*
- struct accessories_settings_t

  *Additional accessories information.*
- struct init_random_t

  *Random key.*
- struct globally_unique_identifier_t

  *Globally unique identifier.*

## Macros

- #define XIMC_API

  *Library import macro Macros allows to automatically import function from shared library.*
- #define XIMC_CALLCONV

  *Library calling convention macros.*
- #define XIMC_RETTYPE void*

  *Thread return type.*
- #define device_undefined -1

  *Handle specified undefined device.*

### Result statuses

- #define result_ok 0
  *success*
- #define result_error -1
  *generic error*
- #define result_not_implemented -2
  *function is not implemented*
- #define result_value_error -3
  *value error*
- #define result_nodevice -4
  *device is lost*

### Logging level

- #define LOGLEVEL_ERROR 0x01
  *Logging level - error.*
- #define LOGLEVEL_WARNING 0x02
  *Logging level - warning.*
- #define LOGLEVEL_INFO 0x03
  *Logging level - info.*
- #define LOGLEVEL_DEBUG 0x04
  *Logging level - debug.*

### Enumerate devices flags

- #define ENUMERATE_PROBE 0x01
  *Check if a device with OS name name is XIMC device.*
- #define ENUMERATE_ALL_COM 0x02
  *Check all COM devices.*
- #define ENUMERATE_NETWORK 0x04
  *Check network devices.*

### Flags of move state

*Specify move states.*

See Also

*get_status*
*status_t::MoveSts*, *get_status_impl*

- #define MOVE_STATE_MOVING 0x01
  *This flag indicates that controller is trying to move the motor.*
- #define MOVE_STATE_TARGET_SPEED 0x02
  *Target speed is reached, if flag set.*
- #define MOVE_STATE_ANTIPLAY 0x04
  *Motor is playing compensation, if flag set.*

### Flags of internal controller settings

See Also

*set_controller_name*
*get_controller_name*
*controller_name_t::CtrlFlags*, *get_controller_name*, *set_controller_name*

- #define EEPROM_PRECEDENCE 0x01
  *If the flag is set settings from external EEPROM override controller settings.*

### Flags of power state of stepper motor

*Specify power states.*

See Also

*get_status*
*status_t::PWRSts*, *get_status_impl*

- #define PWR_STATE_UNKNOWN 0x00
  *Unknown state, should never happen.*
- #define PWR_STATE_OFF 0x01
  *Motor windings are disconnected from the driver.*
- #define PWR_STATE_NORM 0x03
  *Motor windings are powered by nominal current.*
- #define PWR_STATE_REDUCT 0x04
  *Motor windings are powered by reduced current to lower power consumption.*
- #define PWR_STATE_MAX 0x05
  *Motor windings are powered by maximum current driver can provide at this voltage.*

**Status flags**

*Controller flags returned by device query. Contains boolean part of controller state. May be combined with bitwise OR.*

See Also

*get_status*
*status_t::Flags*, *get_status_impl*

- #define STATE_CONTR 0x000003F
  *Flags of controller states.*
- #define STATE_ERRC 0x0000001
  *Command error encountered.*
- #define STATE_ERRD 0x0000002
  *Data integrity error encountered.*
- #define STATE_ERRV 0x0000004
  *Value error encountered.*
- #define STATE_EEPROM_CONNECTED 0x0000010
  *EEPROM with settings is connected.*
- #define STATE_IS_HOMED 0x0000020
  *Calibration performed.*
- #define STATE_SECUR 0x1B3FFC0
  *Flags of security.*
- #define STATE_ALARM 0x0000040
  *Controller is in alarm state indicating that something dangerous had happened.*
- #define STATE_CTP_ERROR 0x0000080
  *Control position error(is only used with stepper motor).*
- #define STATE_POWER_OVERHEAT 0x0000100
  *Power driver overheat.*
- #define STATE_CONTROLLER_OVERHEAT 0x0000200
  *Controller overheat.*
- #define STATE_OVERLOAD_POWER_VOLTAGE 0x0000400
  *Power voltage exceeds safe limit.*
- #define STATE_OVERLOAD_POWER_CURRENT 0x0000800
  *Power current exceeds safe limit.*
- #define STATE_OVERLOAD_USB_VOLTAGE 0x0001000
  *USB voltage exceeds safe limit.*
- #define STATE_LOW_USB_VOLTAGE 0x0002000
  *USB voltage is insufficient for normal operation.*
- #define STATE_OVERLOAD_USB_CURRENT 0x0004000
  *USB current exceeds safe limit.*
- #define STATE_BORDERS_SWAP_MISSET 0x0008000
  *Engine stuck at the wrong edge.*
- #define STATE_LOW_POWER_VOLTAGE 0x0010000

*Power voltage is lower than Low Voltage Protection limit.*

- #define STATE_H_BRIDGE_FAULT 0x0020000
  *Signal from the driver that fault happened.*
- #define STATE_WINDING_RES_MISMATCH 0x0100000
  *The difference between winding resistances is too large.*
- #define STATE_ENCODER_FAULT 0x0200000
  *Signal from the encoder that fault happened.*
- #define STATE_ENGINE_RESPONSE_ERROR 0x0800000
  *Error response of the engine control action.*
- #define STATE_EXTIO_ALARM 0x1000000
  *The error is caused by the input signal.*

### Status flags of the GPIO outputs

*GPIO state flags returned by device query. Contains boolean part of controller state. May be combined with bitwise OR.*

See Also

*get_status*
*status_t::GPIOFlags*, *get_status_impl*

- #define STATE_DIG_SIGNAL 0xFFFF
  *Flags of digital signals.*
- #define STATE_RIGHT_EDGE 0x0001
  *Engine stuck at the right edge.*
- #define STATE_LEFT_EDGE 0x0002
  *Engine stuck at the left edge.*
- #define STATE_BUTTON_RIGHT 0x0004
  *Button "right" state (1 if pressed).*
- #define STATE_BUTTON_LEFT 0x0008
  *Button "left" state (1 if pressed).*
- #define STATE_GPIO_PINOUT 0x0010
  *External GPIO works as Out, if flag set; otherwise works as In.*
- #define STATE_GPIO_LEVEL 0x0020
  *State of external GPIO pin.*
- #define STATE_BRAKE 0x0200
  *State of Brake pin.*
- #define STATE_REV_SENSOR 0x0400
  *State of Revolution sensor pin.*
- #define STATE_SYNC_INPUT 0x0800
  *State of Sync input pin.*
- #define STATE_SYNC_OUTPUT 0x1000
  *State of Sync output pin.*
- #define STATE_ENC_A 0x2000
  *State of encoder A pin.*
- #define STATE_ENC_B 0x4000
  *State of encoder B pin.*

### Encoder state

*Encoder state returned by device query.*

See Also

*get_status*
*status_t::EncSts*, *get_status_impl*

- #define ENC_STATE_ABSENT 0x00
  *Encoder is absent.*
- #define ENC_STATE_UNKNOWN 0x01

*Encoder state is unknown.*
- #define ENC_STATE_MALFUNC 0x02
  *Encoder is connected and malfunctioning.*
- #define ENC_STATE_REVERS 0x03
  *Encoder is connected and operational but counts in other direction.*
- #define ENC_STATE_OK 0x04
  *Encoder is connected and working properly.*

### Winding state

*Motor winding state returned by device query.*

See Also

*get_status*
*status_t::WindSts*, *get_status_impl*

- #define WIND_A_STATE_ABSENT 0x00
  *Winding A is disconnected.*
- #define WIND_A_STATE_UNKNOWN 0x01
  *Winding A state is unknown.*
- #define WIND_A_STATE_MALFUNC 0x02
  *Winding A is short-circuited.*
- #define WIND_A_STATE_OK 0x03
  *Winding A is connected and working properly.*
- #define WIND_B_STATE_ABSENT 0x00
  *Winding B is disconnected.*
- #define WIND_B_STATE_UNKNOWN 0x10
  *Winding B state is unknown.*
- #define WIND_B_STATE_MALFUNC 0x20
  *Winding B is short-circuited.*
- #define WIND_B_STATE_OK 0x30
  *Winding B is connected and working properly.*

### Move command state

*Move command (command_move, command_movr, command_left, command_right, command_stop, command_home, command_loft, command_sstp) and its state (run, finished, error).*

See Also

*get_status*
*status_t::MvCmdSts*, *get_status_impl*

- #define MVCMD_NAME_BITS 0x3F
  *Move command bit mask.*
- #define MVCMD_UKNWN 0x00
  *Unknown command.*
- #define MVCMD_MOVE 0x01
  *Command move.*
- #define MVCMD_MOVR 0x02
  *Command movr.*
- #define MVCMD_LEFT 0x03
  *Command left.*
- #define MVCMD_RIGHT 0x04
  *Command rigt.*
- #define MVCMD_STOP 0x05
  *Command stop.*
- #define MVCMD_HOME 0x06
  *Command home.*
- #define MVCMD_LOFT 0x07
  *Command loft.*

- #define MVCMD_SSTP 0x08
  *Command soft stop.*
- #define MVCMD_ERROR 0x40
  *Finish state (1 - move command have finished with an error, 0 - move command have finished correctly).*
- #define MVCMD_RUNNING 0x80
  *Move command state (0 - move command have finished, 1 - move command is being executed).*

### Flags of the motion parameters

*Specify motor shaft movement algorithm and list of limitations. Flags returned by query of get_move_settings.*

See Also

*set_move_settings*
*get_move_settings*
*move_settings_t::MoveFlags*, *get_move_settings*, *set_move_settings*

- #define RPM_DIV_1000 0x01
  *This flag indicates that the operating speed specified in the command is set in milli rpm.*

### Flags of engine settings

*Specify motor shaft movement algorithm and list of limitations. Flags returned by query of engine settings. May be combined with bitwise OR.*

See Also

*set_engine_settings*
*get_engine_settings*
*engine_settings_t::EngineFlags*, *get_engine_settings*, *set_engine_settings*

- #define ENGINE_REVERSE 0x01
  *Reverse flag.*
- #define ENGINE_CURRENT_AS_RMS 0x02
  *Engine current meaning flag.*
- #define ENGINE_MAX_SPEED 0x04
  *Max speed flag.*
- #define ENGINE_ANTIPLAY 0x08
  *Play compensation flag.*
- #define ENGINE_ACCEL_ON 0x10
  *Acceleration enable flag.*
- #define ENGINE_LIMIT_VOLT 0x20
  *Maximum motor voltage limit enable flag(is only used with DC motor).*
- #define ENGINE_LIMIT_CURR 0x40
  *Maximum motor current limit enable flag(is only used with DC motor).*
- #define ENGINE_LIMIT_RPM 0x80
  *Maximum motor speed limit enable flag.*

### Flags of microstep mode

*Specify settings of microstep mode. Using with step motors. Flags returned by query of engine settings. May be combined with bitwise OR*

See Also

*engine_settings_t::flags*
*set_engine_settings*
*get_engine_settings*
*engine_settings_t::MicrostepMode*, *get_engine_settings*, *set_engine_settings*

- #define MICROSTEP_MODE_FULL 0x01
  *Full step mode.*
- #define MICROSTEP_MODE_FRAC_2 0x02

*1/2 step mode.*
- #define MICROSTEP_MODE_FRAC_4 0x03
  *1/4 step mode.*
- #define MICROSTEP_MODE_FRAC_8 0x04
  *1/8 step mode.*
- #define MICROSTEP_MODE_FRAC_16 0x05
  *1/16 step mode.*
- #define MICROSTEP_MODE_FRAC_32 0x06
  *1/32 step mode.*
- #define MICROSTEP_MODE_FRAC_64 0x07
  *1/64 step mode.*
- #define MICROSTEP_MODE_FRAC_128 0x08
  *1/128 step mode.*
- #define MICROSTEP_MODE_FRAC_256 0x09
  *1/256 step mode.*

#### Flags of engine type

*Specify motor type. Flags returned by query of engine settings.*

See Also

*engine_settings_t::flags*
*set_entype_settings*
*get_entype_settings*
*entype_settings_t::EngineType, get_entype_settings, set_entype_settings*

- #define ENGINE_TYPE_NONE 0x00
  *A value that shouldn't be used.*
- #define ENGINE_TYPE_DC 0x01
  *DC motor.*
- #define ENGINE_TYPE_2DC 0x02
  *2 DC motors.*
- #define ENGINE_TYPE_STEP 0x03
  *Step motor.*
- #define ENGINE_TYPE_TEST 0x04
  *Duty cycle are fixed.*
- #define ENGINE_TYPE_BRUSHLESS 0x05
  *Brushless motor.*

#### Flags of driver type

*Specify driver type. Flags returned by query of engine settings.*

See Also

*engine_settings_t::flags*
*set_entype_settings*
*get_entype_settings*
*entype_settings_t::DriverType, get_entype_settings, set_entype_settings*

- #define DRIVER_TYPE_DISCRETE_FET 0x01
  *Driver with discrete FET keys.*
- #define DRIVER_TYPE_INTEGRATE 0x02
  *Driver with integrated IC.*
- #define DRIVER_TYPE_EXTERNAL 0x03
  *External driver.*

#### Flags of power settings of stepper motor

*Specify power settings. Flags returned by query of power settings.*

See Also

*get_power_settings*
*set_power_settings*
*power_settings_t::PowerFlags*, *get_power_settings*, *set_power_settings*

- #define POWER_REDUCT_ENABLED 0x01
  *Current reduction enabled after CurrReductDelay, if this flag is set.*
- #define POWER_OFF_ENABLED 0x02
  *Power off enabled after PowerOffDelay, if this flag is set.*
- #define POWER_SMOOTH_CURRENT 0x04
  *Current ramp-up/down is performed smoothly during current_set_time, if this flag is set.*

**Flags of secure settings**

*Specify secure settings. Flags returned by query of secure settings.*

See Also

*get_secure_settings*
*set_secure_settings*
*secure_settings_t::Flags*, *get_secure_settings*, *set_secure_settings*

- #define ALARM_ON_DRIVER_OVERHEATING 0x01
  *If this flag is set enter Alarm state on driver overheat signal.*
- #define LOW_UPWR_PROTECTION 0x02
  *If this flag is set turn off motor when voltage is lower than LowUpwrOff.*
- #define H_BRIDGE_ALERT 0x04
  *If this flag is set then turn off the power unit with a signal problem in one of the transistor bridge.*
- #define ALARM_ON_BORDERS_SWAP_MISSET 0x08
  *If this flag is set enter Alarm state on borders swap misset.*
- #define ALARM_FLAGS_STICKING 0x10
  *If this flag is set only a STOP command can turn all alarms to 0.*
- #define USB_BREAK_RECONNECT 0x20
  *If this flag is set USB brake reconnect module will be enable.*
- #define ALARM_WINDING_MISMATCH 0x40
  *If this flag is set enter Alarm state when windings mismatch.*
- #define ALARM_ENGINE_RESPONSE 0x80
  *If this flag is set enter Alarm state on response of the engine control action.*

**Position setting flags**

*Flags used in setting of position.*

See Also

*get_position*
*set_position*
*set_position_t::PosFlags*, *set_position*

- #define SETPOS_IGNORE_POSITION 0x01
  *Will not reload position in steps/microsteps if this flag is set.*
- #define SETPOS_IGNORE_ENCODER 0x02
  *Will not reload encoder state if this flag is set.*

**Feedback type.**

See Also

*set_feedback_settings*
*get_feedback_settings*
*feedback_settings_t::FeedbackType*, *get_feedback_settings*, *set_feedback_settings*

- #define FEEDBACK_ENCODER 0x01
  *Feedback by encoder.*
- #define FEEDBACK_EMF 0x04
  *Feedback by EMF.*
- #define FEEDBACK_NONE 0x05
  *Feedback is absent.*
- #define FEEDBACK_ENCODER_MEDIATED 0x06
  *Feedback by encoder mediated by mechanical transmission (for example leadscrew).*

**Describes feedback flags.**

See Also

*set_feedback_settings*
*get_feedback_settings*
*feedback_settings_t::FeedbackFlags*, *get_feedback_settings*, *set_feedback_settings*

- #define FEEDBACK_ENC_REVERSE 0x01
  *Reverse count of encoder.*
- #define FEEDBACK_ENC_TYPE_BITS 0xC0
  *Bits of the encoder type.*
- #define FEEDBACK_ENC_TYPE_AUTO 0x00
  *Auto detect encoder type.*
- #define FEEDBACK_ENC_TYPE_SINGLE_ENDED 0x40
  *Single ended encoder.*
- #define FEEDBACK_ENC_TYPE_DIFFERENTIAL 0x80
  *Differential encoder.*

**Flags for synchronization input setup**

See Also

*sync_in_settings_t::SyncInFlags*, *get_sync_in_settings*, *set_sync_in_settings*

- #define SYNCIN_ENABLED 0x01
  *Synchronization in mode is enabled, if this flag is set.*
- #define SYNCIN_INVERT 0x02
  *Trigger on falling edge if flag is set, on rising edge otherwise.*
- #define SYNCIN_GOTOPOSITION 0x04
  *The engine is go to position specified in Position and uPosition, if this flag is set.*

**Flags of synchronization output**

See Also

*sync_out_settings_t::SyncOutFlags*, *get_sync_out_settings*, *set_sync_out_settings*

- #define SYNCOUT_ENABLED 0x01
  *Synchronization out pin follows the synchronization logic, if set.*
- #define SYNCOUT_STATE 0x02
  *When output state is fixed by negative SYNCOUT_ENABLED flag, the pin state is in accordance with this flag state.*
- #define SYNCOUT_INVERT 0x04
  *Low level is active, if set, and high level is active otherwise.*
- #define SYNCOUT_IN_STEPS 0x08
  *Use motor steps/encoder pulses instead of milliseconds for output pulse generation if the flag is set.*

- #define SYNCOUT_ONSTART 0x10
  *Generate synchronization pulse when movement starts.*
- #define SYNCOUT_ONSTOP 0x20
  *Generate synchronization pulse when movement stops.*
- #define SYNCOUT_ONPERIOD 0x40
  *Generate synchronization pulse every SyncOutPeriod encoder pulses.*

### External IO setup flags

See Also

*get_extio_settings*
*set_extio_settings*
*extio_settings_t::EXTIOSetupFlags, get_extio_settings, set_extio_settings*

- #define EXTIO_SETUP_OUTPUT 0x01
  *EXTIO works as output if flag is set, works as input otherwise.*
- #define EXTIO_SETUP_INVERT 0x02
  *Interpret EXTIO states and fronts inverted if flag is set.*

### External IO mode flags

See Also

*extio_settings_t::extio_mode_flags*
*get_extio_settings*
*set_extio_settings*
*extio_settings_t::EXTIOModeFlags, get_extio_settings, set_extio_settings*

- #define EXTIO_SETUP_MODE_IN_BITS 0x0F
  *Bits of the behaviour selector when the signal on input goes to the active state.*
- #define EXTIO_SETUP_MODE_IN_NOP 0x00
  *Do nothing.*
- #define EXTIO_SETUP_MODE_IN_STOP 0x01
  *Issue STOP command, ceasing the engine movement.*
- #define EXTIO_SETUP_MODE_IN_PWOF 0x02
  *Issue PWOF command, powering off all engine windings.*
- #define EXTIO_SETUP_MODE_IN_MOVR 0x03
  *Issue MOVR command with last used settings.*
- #define EXTIO_SETUP_MODE_IN_HOME 0x04
  *Issue HOME command.*
- #define EXTIO_SETUP_MODE_IN_ALARM 0x05
  *Set Alarm when the signal goes to the active state.*
- #define EXTIO_SETUP_MODE_OUT_BITS 0xF0
  *Bits of the output behaviour selection.*
- #define EXTIO_SETUP_MODE_OUT_OFF 0x00
  *EXTIO pin always set in inactive state.*
- #define EXTIO_SETUP_MODE_OUT_ON 0x10
  *EXTIO pin always set in active state.*
- #define EXTIO_SETUP_MODE_OUT_MOVING 0x20
  *EXTIO pin stays active during moving state.*
- #define EXTIO_SETUP_MODE_OUT_ALARM 0x30
  *EXTIO pin stays active during Alarm state.*
- #define EXTIO_SETUP_MODE_OUT_MOTOR_ON 0x40
  *EXTIO pin stays active when windings are powered.*

### Border flags

*Specify types of borders and motor behaviour on borders. May be combined with bitwise OR.*

See Also

*get_edges_settings*
*set_edges_settings*
*edges_settings_t::BorderFlags*, *get_edges_settings*, *set_edges_settings*

- #define BORDER_IS_ENCODER 0x01
  *Borders are fixed by predetermined encoder values, if set; borders position on limit switches, if not set.*
- #define BORDER_STOP_LEFT 0x02
  *Motor should stop on left border.*
- #define BORDER_STOP_RIGHT 0x04
  *Motor should stop on right border.*
- #define BORDERS_SWAP_MISSET_DETECTION 0x08
  *Motor should stop on both borders.*

**Limit switches flags**

*Specify electrical behaviour of limit switches like order and pulled positions. May be combined with bitwise OR.*

See Also

*get_edges_settings*
*set_edges_settings*
*edges_settings_t::EnderFlags*, *get_edges_settings*, *set_edges_settings*

- #define ENDER_SWAP 0x01
  *First limit switch on the right side, if set; otherwise on the left side.*
- #define ENDER_SW1_ACTIVE_LOW 0x02
  *1 - Limit switch connnected to pin SW1 is triggered by a low level on pin.*
- #define ENDER_SW2_ACTIVE_LOW 0x04
  *1 - Limit switch connnected to pin SW2 is triggered by a low level on pin.*

**Brake settings flags**

*Specify behaviour of brake. May be combined with bitwise OR.*

See Also

*get_brake_settings*
*set_brake_settings*
*brake_settings_t::BrakeFlags*, *get_brake_settings*, *set_brake_settings*

- #define BRAKE_ENABLED 0x01
  *Brake control is enabled, if this flag is set.*
- #define BRAKE_ENG_PWROFF 0x02
  *Brake turns off power of step motor, if this flag is set.*

**Control flags**

*Specify motor control settings by joystick or buttons. May be combined with bitwise OR.*

See Also

*get_control_settings*
*set_control_settings*
*control_settings_t::Flags*, *get_control_settings*, *set_control_settings*

- #define CONTROL_MODE_BITS 0x03
  *Bits to control engine by joystick or buttons.*
- #define CONTROL_MODE_OFF 0x00
  *Control is disabled.*
- #define CONTROL_MODE_JOY 0x01
  *Control by joystick.*
- #define CONTROL_MODE_LR 0x02

*Control by left/right buttons.*

- #define CONTROL_BTN_LEFT_PUSHED_OPEN 0x04
  *Pushed left button corresponds to open contact, if this flag is set.*
- #define CONTROL_BTN_RIGHT_PUSHED_OPEN 0x08
  *Pushed right button corresponds to open contact, if this flag is set.*

### Joystick flags

*Control joystick states.*

See Also

*set_joystick_settings*
*get_joystick_settings*
*joystick_settings_t::JoyFlags, get_joystick_settings, set_joystick_settings*

- #define JOY_REVERSE 0x01
  *Joystick action is reversed.*

### Position control flags

*Specify settings of position control. May be combined with bitwise OR.*

See Also

*get_ctp_settings*
*set_ctp_settings*
*ctp_settings_t::CTPFlags, get_ctp_settings, set_ctp_settings*

- #define CTP_ENABLED 0x01
  *Position control is enabled, if flag set.*
- #define CTP_BASE 0x02
  *Position control is based on revolution sensor, if this flag is set; otherwise it is based on encoder.*
- #define CTP_ALARM_ON_ERROR 0x04
  *Set ALARM on mismatch, if flag set.*
- #define REV_SENS_INV 0x08
  *Sensor is active when it 0 and invert makes active level 1.*
- #define CTP_ERROR_CORRECTION 0x10
  *Correct errors which appear when slippage if the flag is set.*

### Home settings flags

*Specify behaviour for home command. May be combined with bitwise OR.*

See Also

*get_home_settings*
*set_home_settings*
*command_home*
*home_settings_t::HomeFlags, get_home_settings, set_home_settings*

- #define HOME_DIR_FIRST 0x001
  *Flag defines direction of 1st motion after execution of home command.*
- #define HOME_DIR_SECOND 0x002
  *Flag defines direction of 2nd motion.*
- #define HOME_MV_SEC_EN 0x004
  *Use the second phase of calibration to the home position, if set; otherwise the second phase is skipped.*
- #define HOME_HALF_MV 0x008
  *If the flag is set, the stop signals are ignored in start of second movement the first half-turn.*
- #define HOME_STOP_FIRST_BITS 0x030
  *Bits of the first stop selector.*
- #define HOME_STOP_FIRST_REV 0x010
  *First motion stops by revolution sensor.*

- #define HOME_STOP_FIRST_SYN 0x020
  *First motion stops by synchronization input.*
- #define HOME_STOP_FIRST_LIM 0x030
  *First motion stops by limit switch.*
- #define HOME_STOP_SECOND_BITS 0x0C0
  *Bits of the second stop selector.*
- #define HOME_STOP_SECOND_REV 0x040
  *Second motion stops by revolution sensor.*
- #define HOME_STOP_SECOND_SYN 0x080
  *Second motion stops by synchronization input.*
- #define HOME_STOP_SECOND_LIM 0x0C0
  *Second motion stops by limit switch.*
- #define HOME_USE_FAST 0x100
  *Use the fast algorithm of calibration to the home position, if set; otherwise the traditional algorithm.*

### UART parity flags

See Also

*uart_settings_t::UARTSetupFlags*, *get_uart_settings*, *set_uart_settings*

- #define UART_PARITY_BITS 0x03
  *Bits of the parity.*
- #define UART_PARITY_BIT_EVEN 0x00
  *Parity bit 1, if even.*
- #define UART_PARITY_BIT_ODD 0x01
  *Parity bit 1, if odd.*
- #define UART_PARITY_BIT_SPACE 0x02
  *Parity bit always 0.*
- #define UART_PARITY_BIT_MARK 0x03
  *Parity bit always 1.*
- #define UART_PARITY_BIT_USE 0x04
  *None parity.*
- #define UART_STOP_BIT 0x08
  *If set - one stop bit, else two stop bit.*

### Motor Type flags

See Also

*motor_settings_t::MotorType*, *get_motor_settings*, *set_motor_settings*

- #define MOTOR_TYPE_UNKNOWN 0x00
  *Unknown type of engine.*
- #define MOTOR_TYPE_STEP 0x01
  *Step engine.*
- #define MOTOR_TYPE_DC 0x02
  *DC engine.*
- #define MOTOR_TYPE_BLDC 0x03
  *BLDC engine.*

### Encoder settings flags

See Also

*encoder_settings_t::EncoderSettings*, *get_encoder_settings*, *set_encoder_settings*

- #define ENCSET_DIFFERENTIAL_OUTPUT 0x001
  *If flag is set the encoder has differential output, else single ended output.*
- #define ENCSET_PUSHPULL_OUTPUT 0x004
  *If flag is set the encoder has push-pull output, else open drain output.*
- #define ENCSET_INDEXCHANNEL_PRESENT 0x010
  *If flag is set the encoder has index channel, else encoder hasn't it.*
- #define ENCSET_REVOLUTIONSENSOR_PRESENT 0x040
  *If flag is set the encoder has revolution sensor, else encoder hasn't it.*
- #define ENCSET_REVOLUTIONSENSOR_ACTIVE_HIGH 0x100
  *If flag is set the revolution sensor active state is high logic state, else active state is low logic state.*

**Magnetic brake settings flags**

See Also

*accessories_settings_t::MBSettings*, *get_accessories_settings*, *set_accessories_settings*

- #define MB_AVAILABLE 0x01
  *If flag is set the magnetic brake is available.*
- #define MB_POWERED_HOLD 0x02
  *If this flag is set the magnetic brake is on when powered.*

**Temperature sensor settings flags**

See Also

*accessories_settings_t::LimitSwitchesSettings*, *get_accessories_settings*, *set_accessories_settings*

- #define TS_TYPE_BITS 0x07
  *Bits of the temperature sensor type.*
- #define TS_TYPE_UNKNOWN 0x00
  *Unknow type of sensor.*
- #define TS_TYPE_THERMOCOUPLE 0x01
  *Thermocouple.*
- #define TS_TYPE_SEMICONDUCTOR 0x02
  *The semiconductor temperature sensor.*
- #define TS_AVAILABLE 0x08
  *If flag is set the temperature sensor is available.*
- #define LS_ON_SW1_AVAILABLE 0x01
  *If flag is set the limit switch connnected to pin SW1 is available.*
- #define LS_ON_SW2_AVAILABLE 0x02
  *If flag is set the limit switch connnected to pin SW2 is available.*
- #define LS_SW1_ACTIVE_LOW 0x04
  *If flag is set the limit switch connnected to pin SW1 is triggered by a low level on pin.*
- #define LS_SW2_ACTIVE_LOW 0x08
  *If flag is set the limit switch connnected to pin SW2 is triggered by a low level on pin.*
- #define LS_SHORTED 0x10
  *If flag is set the Limit switches is shorted.*

**Flags of auto-detection of characteristics of windings of the engine.**

See Also

*set_emf_settings*
*get_emf_settings*
*emf_settings_t::BackEMFFlags*, *get_emf_settings*, *set_emf_settings*

- #define BACK_EMF_INDUCTANCE_AUTO 0x01
  *Flag of auto-detection of inductance of windings of the engine.*
- #define BACK_EMF_RESISTANCE_AUTO 0x02
  *Flag of auto-detection of resistance of windings of the engine.*
- #define BACK_EMF_KM_AUTO 0x04
  *Flag of auto-detection of electromechanical coefficient of the engine.*

## Typedefs

- typedef unsigned long long **ulong_t**
- typedef long long **long_t**
- typedef int device_t

  *Type describes device identifier.*
- typedef int result_t

  *Type specifies result of any operation.*
- typedef uint32_t device_enumeration_t

  *Type describes device enumeration structure.*
- typedef struct calibration_t calibration_t

  *Calibration companion structure.*
- typedef struct device_network_information_t device_network_information_t

  *Device network information structure.*

## Functions

### Controller settings setup

*Functions for adjusting engine read/write almost all controller settings.*

- result_t XIMC_API set_feedback_settings (device_t id, const feedback_settings_t *feedback_settings)

  *Feedback settings.*
- result_t XIMC_API get_feedback_settings (device_t id, feedback_settings_t *feedback_settings)

  *Feedback settings.*
- result_t XIMC_API set_home_settings (device_t id, const home_settings_t *home_settings)

  *Set home settings.*
- result_t XIMC_API set_home_settings_calb (device_t id, const home_settings_calb_t *home_settings_calb, const calibration_t *calibration)

  *Set home settings which use user units.*
- result_t XIMC_API get_home_settings (device_t id, home_settings_t *home_settings)

  *Read home settings.*
- result_t XIMC_API get_home_settings_calb (device_t id, home_settings_calb_t *home_settings_calb, const calibration_t *calibration)

  *Read home settings which use user units.*
- result_t XIMC_API set_move_settings (device_t id, const move_settings_t *move_settings)

  *Set command setup movement (speed, acceleration, threshold and etc).*
- result_t XIMC_API set_move_settings_calb (device_t id, const move_settings_calb_t *move_settings_calb, const calibration_t *calibration)

  *Set command setup movement which use user units (speed, acceleration, threshold and etc).*
- result_t XIMC_API get_move_settings (device_t id, move_settings_t *move_settings)

  *Read command setup movement (speed, acceleration, threshold and etc).*
- result_t XIMC_API get_move_settings_calb (device_t id, move_settings_calb_t *move_settings_calb, const calibration_t *calibration)

  *Read command setup movement which use user units (speed, acceleration, threshold and etc).*
- result_t XIMC_API set_engine_settings (device_t id, const engine_settings_t *engine_settings)

  *Set engine settings.*
- result_t XIMC_API set_engine_settings_calb (device_t id, const engine_settings_calb_t *engine_settings_calb, const calibration_t *calibration)

  *Set engine settings which use user units.*
- result_t XIMC_API get_engine_settings (device_t id, engine_settings_t *engine_settings)

  *Read engine settings.*
- result_t XIMC_API get_engine_settings_calb (device_t id, engine_settings_calb_t *engine_settings_calb, const calibration_t *calibration)

  *Read engine settings which use user units.*
- result_t XIMC_API set_entype_settings (device_t id, const entype_settings_t *entype_settings)

*Set engine type and driver type.*

- result_t XIMC_API get_entype_settings (device_t id, entype_settings_t *entype_settings)
  *Return engine type and driver type.*
- result_t XIMC_API set_power_settings (device_t id, const power_settings_t *power_settings)
  *Set settings of step motor power control.*
- result_t XIMC_API get_power_settings (device_t id, power_settings_t *power_settings)
  *Read settings of step motor power control.*
- result_t XIMC_API set_secure_settings (device_t id, const secure_settings_t *secure_settings)
  *Set protection settings.*
- result_t XIMC_API get_secure_settings (device_t id, secure_settings_t *secure_settings)
  *Read protection settings.*
- result_t XIMC_API set_edges_settings (device_t id, const edges_settings_t *edges_settings)
  *Set border and limit switches settings.*
- result_t XIMC_API set_edges_settings_calb (device_t id, const edges_settings_calb_t *edges_settings_calb, const calibration_t *calibration)
  *Set border and limit switches settings which use user units.*
- result_t XIMC_API get_edges_settings (device_t id, edges_settings_t *edges_settings)
  *Read border and limit switches settings.*
- result_t XIMC_API get_edges_settings_calb (device_t id, edges_settings_calb_t *edges_settings_calb, const calibration_t *calibration)
  *Read border and limit switches settings which use user units.*
- result_t XIMC_API set_pid_settings (device_t id, const pid_settings_t *pid_settings)
  *Set PID settings.*
- result_t XIMC_API get_pid_settings (device_t id, pid_settings_t *pid_settings)
  *Read PID settings.*
- result_t XIMC_API set_sync_in_settings (device_t id, const sync_in_settings_t *sync_in_settings)
  *Set input synchronization settings.*
- result_t XIMC_API set_sync_in_settings_calb (device_t id, const sync_in_settings_calb_t *sync_in_settings_calb, const calibration_t *calibration)
  *Set input synchronization settings which use user units.*
- result_t XIMC_API get_sync_in_settings (device_t id, sync_in_settings_t *sync_in_settings)
  *Read input synchronization settings.*
- result_t XIMC_API get_sync_in_settings_calb (device_t id, sync_in_settings_calb_t *sync_in_settings_calb, const calibration_t *calibration)
  *Read input synchronization settings which use user units.*
- result_t XIMC_API set_sync_out_settings (device_t id, const sync_out_settings_t *sync_out_settings)
  *Set output synchronization settings.*
- result_t XIMC_API set_sync_out_settings_calb (device_t id, const sync_out_settings_calb_t *sync_out_settings_calb, const calibration_t *calibration)
  *Set output synchronization settings which use user units.*
- result_t XIMC_API get_sync_out_settings (device_t id, sync_out_settings_t *sync_out_settings)
  *Read output synchronization settings.*
- result_t XIMC_API get_sync_out_settings_calb (device_t id, sync_out_settings_calb_t *sync_out_settings_calb, const calibration_t *calibration)
  *Read output synchronization settings which use user units.*
- result_t XIMC_API set_extio_settings (device_t id, const extio_settings_t *extio_settings)
  *Set EXTIO settings.*
- result_t XIMC_API get_extio_settings (device_t id, extio_settings_t *extio_settings)
  *Read EXTIO settings.*
- result_t XIMC_API set_brake_settings (device_t id, const brake_settings_t *brake_settings)
  *Set settings of brake control.*
- result_t XIMC_API get_brake_settings (device_t id, brake_settings_t *brake_settings)
  *Read settings of brake control.*
- result_t XIMC_API set_control_settings (device_t id, const control_settings_t *control_settings)
  *Set settings of motor control.*
- result_t XIMC_API set_control_settings_calb (device_t id, const control_settings_calb_t *control_settings_calb, const calibration_t *calibration)
  *Set settings of motor control which use user units.*
- result_t XIMC_API get_control_settings (device_t id, control_settings_t *control_settings)

*Read settings of motor control.*

- result_t XIMC_API get_control_settings_calb (device_t id, control_settings_calb_t *control_settings_calb, const calibration_t *calibration)

  *Read settings of motor control which use user units.*
- result_t XIMC_API set_joystick_settings (device_t id, const joystick_settings_t *joystick_settings)

  *Set settings of joystick.*
- result_t XIMC_API get_joystick_settings (device_t id, joystick_settings_t *joystick_settings)

  *Read settings of joystick.*
- result_t XIMC_API set_ctp_settings (device_t id, const ctp_settings_t *ctp_settings)

  *Set settings of control position(is only used with stepper motor).*
- result_t XIMC_API get_ctp_settings (device_t id, ctp_settings_t *ctp_settings)

  *Read settings of control position(is only used with stepper motor).*
- result_t XIMC_API set_uart_settings (device_t id, const uart_settings_t *uart_settings)

  *Set UART settings.*
- result_t XIMC_API get_uart_settings (device_t id, uart_settings_t *uart_settings)

  *Read UART settings.*
- result_t XIMC_API set_calibration_settings (device_t id, const calibration_settings_t *calibration_settings)

  *Set calibration settings.*
- result_t XIMC_API get_calibration_settings (device_t id, calibration_settings_t *calibration_settings)

  *Read calibration settings.*
- result_t XIMC_API set_controller_name (device_t id, const controller_name_t *controller_name)

  *Write user controller name and flags of setting from FRAM.*
- result_t XIMC_API get_controller_name (device_t id, controller_name_t *controller_name)

  *Read user controller name and flags of setting from FRAM.*
- result_t XIMC_API set_nonvolatile_memory (device_t id, const nonvolatile_memory_t *nonvolatile_memory)

  *Write userdata into FRAM.*
- result_t XIMC_API get_nonvolatile_memory (device_t id, nonvolatile_memory_t *nonvolatile_memory)

  *Read userdata from FRAM.*
- result_t XIMC_API set_emf_settings (device_t id, const emf_settings_t *emf_settings)

  *Set electromechanical coefficients.*
- result_t XIMC_API get_emf_settings (device_t id, emf_settings_t *emf_settings)

  *Read electromechanical settings.*
- result_t XIMC_API set_engine_advansed_setup (device_t id, const engine_advansed_setup_t *engine_advansed_setup)

  *Set engine advansed settings.*
- result_t XIMC_API get_engine_advansed_setup (device_t id, engine_advansed_setup_t *engine_advansed_setup)

  *Read engine advansed settings.*
- result_t XIMC_API set_extended_settings (device_t id, const extended_settings_t *extended_settings)

  *Set extended settings.*
- result_t XIMC_API get_extended_settings (device_t id, extended_settings_t *extended_settings)

  *Read extended settings.*

### Group of commands movement control

- result_t XIMC_API command_stop (device_t id)

  *Immediately stop the engine, the transition to the STOP, mode key BREAK (winding short-circuited), the regime "retention" is deactivated for DC motors, keeping current in the windings for stepper motors (with Power management settings).*
- result_t XIMC_API command_power_off (device_t id)

  *Immediately power off motor regardless its state.*
- result_t XIMC_API command_move (device_t id, int Position, int uPosition)

  *Upon receiving the command "move" the engine starts to move with pre-set parameters (speed, acceleration, retention), to the point specified to the Position, uPosition.*
- result_t XIMC_API command_move_calb (device_t id, float Position, const calibration_t *calibration)

  *Move to position which use user units.*
- result_t XIMC_API command_movr (device_t id, int DeltaPosition, int uDeltaPosition)

  *Move to offset.*

- result_t XIMC_API command_movr_calb (device_t id, float DeltaPosition, const calibration_t *calibration)
  *Move to offset using user units.*
- result_t XIMC_API command_home (device_t id)
  *The positive direction is to the right.*
- result_t XIMC_API command_left (device_t id)
  *Start continous moving to the left.*
- result_t XIMC_API command_right (device_t id)
  *Start continous moving to the right.*
- result_t XIMC_API command_loft (device_t id)
  *Upon receiving the command "loft" the engine is shifted from the current point to a distance GENG :: Antiplay, then move to the same point.*
- result_t XIMC_API command_sstp (device_t id)
  *Soft stop engine.*
- result_t XIMC_API get_position (device_t id, get_position_t *the_get_position)
  *Reads the value position in steps and micro for stepper motor and encoder steps all engines.*
- result_t XIMC_API get_position_calb (device_t id, get_position_calb_t *the_get_position_calb, const calibration_t *calibration)
  *Reads position value in user units for stepper motor and encoder steps all engines.*
- result_t XIMC_API set_position (device_t id, const set_position_t *the_set_position)
  *Sets any position value in steps and micro for stepper motor and encoder steps of all engines.*
- result_t XIMC_API set_position_calb (device_t id, const set_position_calb_t *the_set_position_calb, const calibration_t *calibration)
  *Sets any position value and encoder value of all engines which use user units.*
- result_t XIMC_API command_zero (device_t id)
  *Sets the current position and the position in which the traffic moves by the move command and movr zero for all cases, except for movement to the target position.*

### Group of commands to save and load settings

- result_t XIMC_API command_save_settings (device_t id)
  *Save all settings from controller's RAM to controller's flash memory, replacing previous data in controller's flash memory.*
- result_t XIMC_API command_read_settings (device_t id)
  *Read all settings from controller's flash memory to controller's RAM, replacing previous data in controller's RAM.*
- result_t XIMC_API command_save_robust_settings (device_t id)
  *Save important settings (calibration coefficients and etc.) from controller's RAM to controller's flash memory, replacing previous data in controller's flash memory.*
- result_t XIMC_API command_read_robust_settings (device_t id)
  *Read important settings (calibration coefficients and etc.) from controller's flash memory to controller's RAM, replacing previous data in controller's RAM.*
- result_t XIMC_API command_eesave_settings (device_t id)
  *Save settings from controller's RAM to stage's EEPROM memory, which spontaneity connected to stage and it isn't change without it mechanical reconstruction.*
- result_t XIMC_API command_eeread_settings (device_t id)
  *Read settings from controller's RAM to stage's EEPROM memory, which spontaneity connected to stage and it isn't change without it mechanical reconstruction.*
- result_t XIMC_API command_start_measurements (device_t id)
  *Start measurements and buffering of speed, following error.*
- result_t XIMC_API get_measurements (device_t id, measurements_t *measurements)
  *A command to read the data buffer to build a speed graph and a sequence error.*
- result_t XIMC_API get_chart_data (device_t id, chart_data_t *chart_data)
  *Return device electrical parameters, useful for charts.*
- result_t XIMC_API get_serial_number (device_t id, unsigned int *SerialNumber)
  *Read device serial number.*
- result_t XIMC_API get_firmware_version (device_t id, unsigned int *Major, unsigned int *Minor, unsigned int *Release)
  *Read controller's firmware version.*
- result_t XIMC_API service_command_updf (device_t id)
  *Command puts the controller to update the firmware.*

### Service commands

- result_t XIMC_API set_serial_number (device_t id, const serial_number_t *serial_number)
  *Write device serial number and hardware version to controller's flash memory.*
- result_t XIMC_API get_analog_data (device_t id, analog_data_t *analog_data)
  *Read analog data structure that contains raw analog data from ADC embedded on board.*
- result_t XIMC_API get_debug_read (device_t id, debug_read_t *debug_read)
  *Read data from firmware for debug purpose.*
- result_t XIMC_API set_debug_write (device_t id, const debug_write_t *debug_write)
  *Write data to firmware for debug purpose.*

### Group of commands to work with EEPROM

- result_t XIMC_API set_stage_name (device_t id, const stage_name_t *stage_name)
  *Write user stage name from EEPROM.*
- result_t XIMC_API get_stage_name (device_t id, stage_name_t *stage_name)
  *Read user stage name from EEPROM.*
- result_t XIMC_API set_stage_information (device_t id, const stage_information_t *stage_information)
  *Set stage information to EEPROM.*
- result_t XIMC_API get_stage_information (device_t id, stage_information_t *stage_information)
  *Read stage information from EEPROM.*
- result_t XIMC_API set_stage_settings (device_t id, const stage_settings_t *stage_settings)
  *Set stage settings to EEPROM.*
- result_t XIMC_API get_stage_settings (device_t id, stage_settings_t *stage_settings)
  *Read stage settings from EEPROM.*
- result_t XIMC_API set_motor_information (device_t id, const motor_information_t *motor_information)
  *Set motor information to EEPROM.*
- result_t XIMC_API get_motor_information (device_t id, motor_information_t *motor_information)
  *Read motor information from EEPROM.*
- result_t XIMC_API set_motor_settings (device_t id, const motor_settings_t *motor_settings)
  *Set motor settings to EEPROM.*
- result_t XIMC_API get_motor_settings (device_t id, motor_settings_t *motor_settings)
  *Read motor settings from EEPROM.*
- result_t XIMC_API set_encoder_information (device_t id, const encoder_information_t *encoder_information)
  *Set encoder information to EEPROM.*
- result_t XIMC_API get_encoder_information (device_t id, encoder_information_t *encoder_information)
  *Read encoder information from EEPROM.*
- result_t XIMC_API set_encoder_settings (device_t id, const encoder_settings_t *encoder_settings)
  *Set encoder settings to EEPROM.*
- result_t XIMC_API get_encoder_settings (device_t id, encoder_settings_t *encoder_settings)
  *Read encoder settings from EEPROM.*
- result_t XIMC_API set_hallsensor_information (device_t id, const hallsensor_information_t *hallsensor_information)
  *Set hall sensor information to EEPROM.*
- result_t XIMC_API get_hallsensor_information (device_t id, hallsensor_information_t *hallsensor_information)
  *Read hall sensor information from EEPROM.*
- result_t XIMC_API set_hallsensor_settings (device_t id, const hallsensor_settings_t *hallsensor_settings)
  *Set hall sensor settings to EEPROM.*
- result_t XIMC_API get_hallsensor_settings (device_t id, hallsensor_settings_t *hallsensor_settings)
  *Read hall sensor settings from EEPROM.*
- result_t XIMC_API set_gear_information (device_t id, const gear_information_t *gear_information)
  *Set gear information to EEPROM.*
- result_t XIMC_API get_gear_information (device_t id, gear_information_t *gear_information)
  *Read gear information from EEPROM.*
- result_t XIMC_API set_gear_settings (device_t id, const gear_settings_t *gear_settings)
  *Set gear settings to EEPROM.*
- result_t XIMC_API get_gear_settings (device_t id, gear_settings_t *gear_settings)

*Read gear settings from EEPROM.*

- result_t XIMC_API set_accessories_settings (device_t id, const accessories_settings_t *accessories_settings)

  *Set additional accessories information to EEPROM.*
- result_t XIMC_API get_accessories_settings (device_t id, accessories_settings_t *accessories_settings)

  *Read additional accessories information from EEPROM.*
- result_t XIMC_API get_bootloader_version (device_t id, unsigned int *Major, unsigned int *Minor, unsigned int *Release)

  *Read controller's firmware version.*
- result_t XIMC_API get_init_random (device_t id, init_random_t *init_random)

  *Read random number from controller.*
- result_t XIMC_API get_globally_unique_identifier (device_t id, globally_unique_identifier_t *globally_unique_identifier)

  *This value is unique to each individual die but is not a random value.*
- result_t XIMC_API goto_firmware (device_t id, uint8_t *ret)

  *Reboot to firmware.*
- result_t XIMC_API has_firmware (const char *uri, uint8_t *ret)

  *Check for firmware on device.*
- result_t XIMC_API command_update_firmware (const char *uri, const uint8_t *data, uint32_t data_size)

  *Update firmware.*
- result_t XIMC_API write_key (const char *uri, uint8_t *key)

  *Write controller key.*
- result_t XIMC_API command_reset (device_t id)

  *Reset controller.*
- result_t XIMC_API command_clear_fram (device_t id)

  *Clear controller FRAM.*

## Boards and drivers control

Functions for searching and opening/closing devices

- typedef char * pchar

  *Nevermind.*
- typedef void(XIMC_CALLCONV * logging_callback_t )(int loglevel, const wchar_t *message, void *user_data)

  *Logging callback prototype.*
- device_t XIMC_API open_device (const char *uri)

  *Open a device with OS uri uri and return identifier of the device which can be used in calls.*
- result_t XIMC_API close_device (device_t *id)

  *Close specified device.*
- result_t XIMC_API load_correction_table (device_t *id, const char *namefile)

  *Command of loading a correction table from a text file.*
- result_t XIMC_API set_correction_table (device_t id, const char *namefile)

  *Command of loading a correction table from a text file.*
- result_t XIMC_API probe_device (const char *uri)

  *Check if a device with OS uri uri is XIMC device.*
- result_t XIMC_API set_bindy_key (const char *keyfilepath)

  *Set network encryption layer (bindy) key.*
- device_enumeration_t XIMC_API enumerate_devices (int enumerate_flags, const char *hints)

  *Enumerate all devices that looks like valid.*
- result_t XIMC_API free_enumerate_devices (device_enumeration_t device_enumeration)

  *Free memory returned by enumerate_devices.*
- int XIMC_API get_device_count (device_enumeration_t device_enumeration)

  *Get device count.*

- pchar XIMC_API get_device_name (device_enumeration_t device_enumeration, int device_index)

  *Get device name from the device enumeration.*
- result_t XIMC_API get_enumerate_device_serial (device_enumeration_t device_enumeration, int device_index, uint32_t *serial)

  *Get device serial number from the device enumeration.*
- result_t XIMC_API get_enumerate_device_information (device_enumeration_t device_enumeration, int device_index, device_information_t *device_information)

  *Get device information from the device enumeration.*
- result_t XIMC_API get_enumerate_device_controller_name (device_enumeration_t device_enumeration, int device_index, controller_name_t *controller_name)

  *Get controller name from the device enumeration.*
- result_t XIMC_API get_enumerate_device_stage_name (device_enumeration_t device_enumeration, int device_index, stage_name_t *stage_name)

  *Get stage name from the device enumeration.*
- result_t XIMC_API get_enumerate_device_network_information (device_enumeration_t device_enumeration, int device_index, device_network_information_t *device_network_information)

  *Get device network information from the device enumeration.*
- result_t XIMC_API reset_locks ()

  *Reset library locks in a case of deadlock.*
- result_t XIMC_API ximc_fix_usbser_sys (const char *device_uri)

  *Fix for errors in Windows USB driver stack.*
- void XIMC_API msec_sleep (unsigned int msec)

  *Sleeps for a specified amount of time.*
- void XIMC_API ximc_version (char *version)

  *Returns a library version.*
- void XIMC_API logging_callback_stderr_wide (int loglevel, const wchar_t *message, void *user_data)

  *Simple callback for logging to stderr in wide chars.*
- void XIMC_API logging_callback_stderr_narrow (int loglevel, const wchar_t *message, void *user_data)

  *Simple callback for logging to stderr in narrow (single byte) chars.*
- void XIMC_API set_logging_callback (logging_callback_t logging_callback, void *user_data)

  *Sets a logging callback.*
- result_t XIMC_API get_status (device_t id, status_t *status)

  *Return device state.*
- result_t XIMC_API get_status_calb (device_t id, status_calb_t *status, const calibration_t *calibration)

  *Return device state.*
- result_t XIMC_API get_device_information (device_t id, device_information_t *device_information)

  *Return device information.*
- result_t XIMC_API command_wait_for_stop (device_t id, uint32_t refresh_interval_ms)

  *Wait for stop.*
- result_t XIMC_API command_homezero (device_t id)

  *Make home command, wait until it is finished and make zero command.*

### 7.1.1 Detailed Description

Header file for libximc library.

### 7.1.2 Macro Definition Documentation

#### 7.1.2.1 #define ALARM_ON_DRIVER_OVERHEATING 0x01

If this flag is set enter Alarm state on driver overheat signal.

#### 7.1.2.2 #define BACK_EMF_INDUCTANCE_AUTO 0x01

Flag of auto-detection of inductance of windings of the engine.

#### 7.1.2.3 #define BACK_EMF_KM_AUTO 0x04

Flag of auto-detection of electromechanical coefficient of the engine.

#### 7.1.2.4 #define BACK_EMF_RESISTANCE_AUTO 0x02

Flag of auto-detection of resistance of windings of the engine.

#### 7.1.2.5 #define BORDER_IS_ENCODER 0x01

Borders are fixed by predetermined encoder values, if set; borders position on limit switches, if not set.

#### 7.1.2.6 #define BORDER_STOP_LEFT 0x02

Motor should stop on left border.

#### 7.1.2.7 #define BORDER_STOP_RIGHT 0x04

Motor should stop on right border.

#### 7.1.2.8 #define BORDERS_SWAP_MISSET_DETECTION 0x08

Motor should stop on both borders.
Need to save motor then wrong border settings is set

#### 7.1.2.9 #define BRAKE_ENABLED 0x01

Brake control is enabled, if this flag is set.

#### 7.1.2.10 #define BRAKE_ENG_PWROFF 0x02

Brake turns off power of step motor, if this flag is set.

#### 7.1.2.11 #define CONTROL_BTN_LEFT_PUSHED_OPEN 0x04

Pushed left button corresponds to open contact, if this flag is set.

#### 7.1.2.12 #define CONTROL_BTN_RIGHT_PUSHED_OPEN 0x08

Pushed right button corresponds to open contact, if this flag is set.

#### 7.1.2.13 #define CONTROL_MODE_BITS 0x03

Bits to control engine by joystick or buttons.

#### 7.1.2.14 #define CONTROL_MODE_JOY 0x01

Control by joystick.

#### 7.1.2.15 #define CONTROL_MODE_LR 0x02

Control by left/right buttons.

#### 7.1.2.16 #define CONTROL_MODE_OFF 0x00

Control is disabled.

#### 7.1.2.17 #define CTP_ALARM_ON_ERROR 0x04

Set ALARM on mismatch, if flag set.

#### 7.1.2.18 #define CTP_BASE 0x02

Position control is based on revolution sensor, if this flag is set; otherwise it is based on encoder.

#### 7.1.2.19 #define CTP_ENABLED 0x01

Position control is enabled, if flag set.

#### 7.1.2.20 #define CTP_ERROR_CORRECTION 0x10

Correct errors which appear when slippage if the flag is set.

It works only with the encoder. Incompatible with flag CTP_ALARM_ON_ERROR.

#### 7.1.2.21 #define DRIVER_TYPE_DISCRETE_FET 0x01

Driver with discrete FET keys.

Default option.

#### 7.1.2.22 #define DRIVER_TYPE_EXTERNAL 0x03

External driver.

#### 7.1.2.23 #define DRIVER_TYPE_INTEGRATE 0x02

Driver with integrated IC.

#### 7.1.2.24 #define EEPROM_PRECEDENCE 0x01

If the flag is set settings from external EEPROM override controller settings.

#### 7.1.2.25 #define ENC_STATE_ABSENT 0x00

Encoder is absent.

#### 7.1.2.26 #define ENC_STATE_MALFUNC 0x02

Encoder is connected and malfunctioning.

#### 7.1.2.27 #define ENC_STATE_OK 0x04

Encoder is connected and working properly.

#### 7.1.2.28 #define ENC_STATE_REVERS 0x03

Encoder is connected and operational but counts in other direction.

#### 7.1.2.29 #define ENC_STATE_UNKNOWN 0x01

Encoder state is unknown.

#### 7.1.2.30 #define ENDER_SW1_ACTIVE_LOW 0x02

1 - Limit switch connnected to pin SW1 is triggered by a low level on pin.

#### 7.1.2.31 #define ENDER_SW2_ACTIVE_LOW 0x04

1 - Limit switch connnected to pin SW2 is triggered by a low level on pin.

#### 7.1.2.32 #define ENDER_SWAP 0x01

First limit switch on the right side, if set; otherwise on the left side.

#### 7.1.2.33 #define ENGINE_ACCEL_ON 0x10

Acceleration enable flag.

If it set, motion begins with acceleration and ends with deceleration.

#### 7.1.2.34 #define ENGINE_ANTIPLAY 0x08

Play compensation flag.

If it set, engine makes backlash (play) compensation procedure and reach the predetermined position accurately on low speed.

#### 7.1.2.35 #define ENGINE_CURRENT_AS_RMS 0x02

Engine current meaning flag.

If the flag is unset, then engine current value is interpreted as maximum amplitude value. If the flag is set, then engine current value is interpreted as root mean square current value (for stepper) or as the current value calculated from the maximum heat dissipation (bldc).

#### 7.1.2.36 #define ENGINE_LIMIT_CURR 0x40

Maximum motor current limit enable flag(is only used with DC motor).

#### 7.1.2.37 #define ENGINE_LIMIT_RPM 0x80

Maximum motor speed limit enable flag.

#### 7.1.2.38 #define ENGINE_LIMIT_VOLT 0x20

Maximum motor voltage limit enable flag(is only used with DC motor).

#### 7.1.2.39 #define ENGINE_MAX_SPEED 0x04

Max speed flag.

If it is set, engine uses maximum speed achievable with the present engine settings as nominal speed.

#### 7.1.2.40 #define ENGINE_REVERSE 0x01

Reverse flag.

It determines motor shaft rotation direction that corresponds to feedback counts increasing. If not set (default), motor shaft rotation direction under positive voltage corresponds to feedback counts increasing and vice versa. Change it if you see that positive directions on motor and feedback are opposite.

#### 7.1.2.41 #define ENGINE_TYPE_2DC 0x02

2 DC motors.

#### 7.1.2.42 #define ENGINE_TYPE_BRUSHLESS 0x05

Brushless motor.

#### 7.1.2.43 #define ENGINE_TYPE_DC 0x01

DC motor.

#### 7.1.2.44 #define ENGINE_TYPE_NONE 0x00

A value that shouldn't be used.

#### 7.1.2.45 #define ENGINE_TYPE_STEP 0x03

Step motor.

#### 7.1.2.46 #define ENGINE_TYPE_TEST 0x04

Duty cycle are fixed.

Used only manufacturer.

#### 7.1.2.47 #define ENUMERATE_PROBE 0x01

Check if a device with OS name name is XIMC device.

Be carefuly with this flag because it sends some data to the device.

#### 7.1.2.48 #define EXTIO_SETUP_INVERT 0x02

Interpret EXTIO states and fronts inverted if flag is set.

Falling front as input event and low logic level as active state.

#### 7.1.2.49 #define EXTIO_SETUP_MODE_IN_ALARM 0x05

Set Alarm when the signal goes to the active state.

#### 7.1.2.50 #define EXTIO_SETUP_MODE_IN_BITS 0x0F

Bits of the behaviour selector when the signal on input goes to the active state.

#### 7.1.2.51 #define EXTIO_SETUP_MODE_IN_HOME 0x04

Issue HOME command.

#### 7.1.2.52 #define EXTIO_SETUP_MODE_IN_MOVR 0x03

Issue MOVR command with last used settings.

#### 7.1.2.53 #define EXTIO_SETUP_MODE_IN_NOP 0x00

Do nothing.

#### 7.1.2.54 #define EXTIO_SETUP_MODE_IN_PWOF 0x02

Issue PWOF command, powering off all engine windings.

#### 7.1.2.55 #define EXTIO_SETUP_MODE_IN_STOP 0x01

Issue STOP command, ceasing the engine movement.

#### 7.1.2.56 #define EXTIO_SETUP_MODE_OUT_ALARM 0x30

EXTIO pin stays active during Alarm state.

#### 7.1.2.57 #define EXTIO_SETUP_MODE_OUT_BITS 0xF0

Bits of the output behaviour selection.

#### 7.1.2.58 #define EXTIO_SETUP_MODE_OUT_MOTOR_ON 0x40

EXTIO pin stays active when windings are powered.

#### 7.1.2.59 #define EXTIO_SETUP_MODE_OUT_MOVING 0x20

EXTIO pin stays active during moving state.

#### 7.1.2.60 #define EXTIO_SETUP_MODE_OUT_OFF 0x00

EXTIO pin always set in inactive state.

#### 7.1.2.61 #define EXTIO_SETUP_MODE_OUT_ON 0x10

EXTIO pin always set in active state.

#### 7.1.2.62 #define EXTIO_SETUP_OUTPUT 0x01

EXTIO works as output if flag is set, works as input otherwise.

#### 7.1.2.63 #define FEEDBACK_EMF 0x04

Feedback by EMF.

#### 7.1.2.64 #define FEEDBACK_ENC_REVERSE 0x01

Reverse count of encoder.

#### 7.1.2.65 #define FEEDBACK_ENC_TYPE_AUTO 0x00

Auto detect encoder type.

#### 7.1.2.66 #define FEEDBACK_ENC_TYPE_BITS 0xC0

Bits of the encoder type.

#### 7.1.2.67 #define FEEDBACK_ENC_TYPE_DIFFERENTIAL 0x80

Differential encoder.

#### 7.1.2.68 #define FEEDBACK_ENC_TYPE_SINGLE_ENDED 0x40

Single ended encoder.

#### 7.1.2.69 #define FEEDBACK_ENCODER 0x01

Feedback by encoder.

#### 7.1.2.70 #define FEEDBACK_ENCODER_MEDIATED 0x06

Feedback by encoder mediated by mechanical transmission (for example leadscrew).

#### 7.1.2.71 #define FEEDBACK_NONE 0x05

Feedback is absent.

#### 7.1.2.72 #define H_BRIDGE_ALERT 0x04

If this flag is set then turn off the power unit with a signal problem in one of the transistor bridge.

#### 7.1.2.73 #define HOME_DIR_FIRST 0x001

Flag defines direction of 1st motion after execution of home command.

Direction is right, if set; otherwise left.

#### 7.1.2.74 #define HOME_DIR_SECOND 0x002

Flag defines direction of 2nd motion.

Direction is right, if set; otherwise left.

#### 7.1.2.75 #define HOME_HALF_MV 0x008

If the flag is set, the stop signals are ignored in start of second movement the first half-turn.

#### 7.1.2.76 #define HOME_MV_SEC_EN 0x004

Use the second phase of calibration to the home position, if set; otherwise the second phase is skipped.

#### 7.1.2.77 #define HOME_STOP_FIRST_BITS 0x030

Bits of the first stop selector.

#### 7.1.2.78 #define HOME_STOP_FIRST_LIM 0x030

First motion stops by limit switch.

#### 7.1.2.79 #define HOME_STOP_FIRST_REV 0x010

First motion stops by revolution sensor.

#### 7.1.2.80 #define HOME_STOP_FIRST_SYN 0x020

First motion stops by synchronization input.

#### 7.1.2.81 #define HOME_STOP_SECOND_BITS 0x0C0

Bits of the second stop selector.

#### 7.1.2.82 #define HOME_STOP_SECOND_LIM 0x0C0

Second motion stops by limit switch.

#### 7.1.2.83 #define HOME_STOP_SECOND_REV 0x040

Second motion stops by revolution sensor.

#### 7.1.2.84 #define HOME_STOP_SECOND_SYN 0x080

Second motion stops by synchronization input.

#### 7.1.2.85 #define HOME_USE_FAST 0x100

Use the fast algorithm of calibration to the home position, if set; otherwise the traditional algorithm.

#### 7.1.2.86 #define JOY_REVERSE 0x01

Joystick action is reversed.

Joystick deviation to the upper values correspond to negative speeds and vice versa.

#### 7.1.2.87 #define LOW_UPWR_PROTECTION 0x02

If this flag is set turn off motor when voltage is lower than LowUpwrOff.

#### 7.1.2.88 #define MICROSTEP_MODE_FRAC_128 0x08

1/128 step mode.

#### 7.1.2.89 #define MICROSTEP_MODE_FRAC_16 0x05

1/16 step mode.

#### 7.1.2.90 #define MICROSTEP_MODE_FRAC_2 0x02

1/2 step mode.

#### 7.1.2.91 #define MICROSTEP_MODE_FRAC_256 0x09

1/256 step mode.

#### 7.1.2.92 #define MICROSTEP_MODE_FRAC_32 0x06

1/32 step mode.

#### 7.1.2.93 #define MICROSTEP_MODE_FRAC_4 0x03

1/4 step mode.

#### 7.1.2.94 #define MICROSTEP_MODE_FRAC_64 0x07

1/64 step mode.

#### 7.1.2.95 #define MICROSTEP_MODE_FRAC_8 0x04

1/8 step mode.

#### 7.1.2.96 #define MICROSTEP_MODE_FULL 0x01

Full step mode.

#### 7.1.2.97 #define MOVE_STATE_ANTIPLAY 0x04

Motor is playing compensation, if flag set.

#### 7.1.2.98 #define MOVE_STATE_MOVING 0x01

This flag indicates that controller is trying to move the motor.

Don't use this flag for waiting of completion of the movement command. Use MVCMD_RUNNING flag from the MvCmdSts field instead.

#### 7.1.2.99 #define MOVE_STATE_TARGET_SPEED 0x02

Target speed is reached, if flag set.

#### 7.1.2.100 #define MVCMD_ERROR 0x40

Finish state (1 - move command have finished with an error, 0 - move command have finished correctly).

This flags is actual when MVCMD_RUNNING signals movement finish.

#### 7.1.2.101 #define MVCMD_HOME 0x06

Command home.

#### 7.1.2.102 #define MVCMD_LEFT 0x03

Command left.

#### 7.1.2.103 #define MVCMD_LOFT 0x07

Command loft.

#### 7.1.2.104 #define MVCMD_MOVE 0x01

Command move.

#### 7.1.2.105 #define MVCMD_MOVR 0x02

Command movr.

#### 7.1.2.106 #define MVCMD_NAME_BITS 0x3F

Move command bit mask.

#### 7.1.2.107 #define MVCMD_RIGHT 0x04

Command rigt.

#### 7.1.2.108 #define MVCMD_RUNNING 0x80

Move command state (0 - move command have finished, 1 - move command is being executed).

#### 7.1.2.109 #define MVCMD_SSTP 0x08

Command soft stop.

#### 7.1.2.110 #define MVCMD_STOP 0x05

Command stop.

#### 7.1.2.111 #define MVCMD_UKNWN 0x00

Unknown command.

#### 7.1.2.112 #define POWER_OFF_ENABLED 0x02

Power off enabled after PowerOffDelay, if this flag is set.

#### 7.1.2.113 #define POWER_REDUCT_ENABLED 0x01

Current reduction enabled after CurrReductDelay, if this flag is set.

#### 7.1.2.114 #define POWER_SMOOTH_CURRENT 0x04

Current ramp-up/down is performed smoothly during current_set_time, if this flag is set.

#### 7.1.2.115 #define PWR_STATE_MAX 0x05

Motor windings are powered by maximum current driver can provide at this voltage.

#### 7.1.2.116 #define PWR_STATE_NORM 0x03

Motor windings are powered by nominal current.

#### 7.1.2.117 #define PWR_STATE_OFF 0x01

Motor windings are disconnected from the driver.

#### 7.1.2.118 #define PWR_STATE_REDUCT 0x04

Motor windings are powered by reduced current to lower power consumption.

#### 7.1.2.119 #define PWR_STATE_UNKNOWN 0x00

Unknown state, should never happen.

#### 7.1.2.120 #define REV_SENS_INV 0x08

Sensor is active when it 0 and invert makes active level 1.

That is, if you do not invert, it is normal logic - 0 is the activation.

#### 7.1.2.121 #define RPM_DIV_1000 0x01

This flag indicates that the operating speed specified in the command is set in milli rpm.

Applicable only for ENCODER feedback mode and only for BLDC motors.

#### 7.1.2.122 #define SETPOS_IGNORE_ENCODER 0x02

Will not reload encoder state if this flag is set.

#### 7.1.2.123 #define SETPOS_IGNORE_POSITION 0x01

Will not reload position in steps/microsteps if this flag is set.

#### 7.1.2.124 #define STATE_ALARM 0x0000040

Controller is in alarm state indicating that something dangerous had happened.

Most commands are ignored in this state. To reset the flag a STOP command must be issued.

#### 7.1.2.125 #define STATE_BORDERS_SWAP_MISSET 0x0008000

Engine stuck at the wrong edge.

#### 7.1.2.126 #define STATE_BRAKE 0x0200

State of Brake pin.

Flag ”1” - if the pin state brake is not powered(brake is clamped), ”0” - if the pin state brake is powered(brake is unclamped).

#### 7.1.2.127 #define STATE_BUTTON_LEFT 0x0008

Button ”left” state (1 if pressed).

#### 7.1.2.128 #define STATE_BUTTON_RIGHT 0x0004

Button ”right” state (1 if pressed).

#### 7.1.2.129 #define STATE_CONTR 0x000003F

Flags of controller states.

#### 7.1.2.130 #define STATE_CONTROLLER_OVERHEAT 0x0000200

Controller overheat.

#### 7.1.2.131 #define STATE_CTP_ERROR 0x0000080

Control position error(is only used with stepper motor).

#### 7.1.2.132 #define STATE_DIG_SIGNAL 0xFFFF

Flags of digital signals.

#### 7.1.2.133 #define STATE_EEPROM_CONNECTED 0x0000010

EEPROM with settings is connected.

#### 7.1.2.134 #define STATE_ENC_A 0x2000

State of encoder A pin.

#### 7.1.2.135 #define STATE_ENC_B 0x4000

State of encoder B pin.

#### 7.1.2.136 #define STATE_ENGINE_RESPONSE_ERROR 0x0800000

Error response of the engine control action.

#### 7.1.2.137 #define STATE_ERRC 0x0000001

Command error encountered.

#### 7.1.2.138 #define STATE_ERRD 0x0000002

Data integrity error encountered.

#### 7.1.2.139 #define STATE_ERRV 0x0000004

Value error encountered.

#### 7.1.2.140 #define STATE_EXTIO_ALARM 0x1000000

The error is caused by the input signal.

#### 7.1.2.141 #define STATE_GPIO_LEVEL 0x0020

State of external GPIO pin.

#### 7.1.2.142 #define STATE_GPIO_PINOUT 0x0010

External GPIO works as Out, if flag set; otherwise works as In.

#### 7.1.2.143 #define STATE_LEFT_EDGE 0x0002

Engine stuck at the left edge.

#### 7.1.2.144 #define STATE_LOW_USB_VOLTAGE 0x0002000

USB voltage is insufficient for normal operation.

#### 7.1.2.145 #define STATE_OVERLOAD_POWER_CURRENT 0x0000800

Power current exceeds safe limit.

#### 7.1.2.146 #define STATE_OVERLOAD_POWER_VOLTAGE 0x0000400

Power voltage exceeds safe limit.

#### 7.1.2.147 #define STATE_OVERLOAD_USB_CURRENT 0x0004000

USB current exceeds safe limit.

#### 7.1.2.148 #define STATE_OVERLOAD_USB_VOLTAGE 0x0001000

USB voltage exceeds safe limit.

#### 7.1.2.149 #define STATE_POWER_OVERHEAT 0x0000100

Power driver overheat.

#### 7.1.2.150 #define STATE_REV_SENSOR 0x0400

State of Revolution sensor pin.

#### 7.1.2.151 #define STATE_RIGHT_EDGE 0x0001

Engine stuck at the right edge.

#### 7.1.2.152 #define STATE_SECUR 0x1B3FFC0

Flags of security.

#### 7.1.2.153 #define STATE_SYNC_INPUT 0x0800

State of Sync input pin.

#### 7.1.2.154 #define STATE_SYNC_OUTPUT 0x1000

State of Sync output pin.

#### 7.1.2.155 #define SYNCIN_ENABLED 0x01

Synchronization in mode is enabled, if this flag is set.

#### 7.1.2.156 #define SYNCIN_GOTOPOSITION 0x04

The engine is go to position specified in Position and uPosition, if this flag is set.

And it is shift on the Position and uPosition, if this flag is unset

#### 7.1.2.157 #define SYNCIN_INVERT 0x02

Trigger on falling edge if flag is set, on rising edge otherwise.

#### 7.1.2.158 #define SYNCOUT_ENABLED 0x01

Synchronization out pin follows the synchronization logic, if set.

It governed by SYNCOUT_STATE flag otherwise.

#### 7.1.2.159 #define SYNCOUT_IN_STEPS 0x08

Use motor steps/encoder pulses instead of milliseconds for output pulse generation if the flag is set.

#### 7.1.2.160 #define SYNCOUT_INVERT 0x04

Low level is active, if set, and high level is active otherwise.

#### 7.1.2.161 #define SYNCOUT_ONPERIOD 0x40

Generate synchronization pulse every SyncOutPeriod encoder pulses.

#### 7.1.2.162 #define SYNCOUT_ONSTART 0x10

Generate synchronization pulse when movement starts.

#### 7.1.2.163 #define SYNCOUT_ONSTOP 0x20

Generate synchronization pulse when movement stops.

#### 7.1.2.164 #define SYNCOUT_STATE 0x02

When output state is fixed by negative SYNCOUT_ENABLED flag, the pin state is in accordance with this flag state.

#### 7.1.2.165 #define UART_PARITY_BITS 0x03

Bits of the parity.

#### 7.1.2.166 #define WIND_A_STATE_ABSENT 0x00

Winding A is disconnected.

#### 7.1.2.167 #define WIND_A_STATE_MALFUNC 0x02

Winding A is short-circuited.

#### 7.1.2.168 #define WIND_A_STATE_OK 0x03

Winding A is connected and working properly.

#### 7.1.2.169 #define WIND_A_STATE_UNKNOWN 0x01

Winding A state is unknown.

#### 7.1.2.170 #define WIND_B_STATE_ABSENT 0x00

Winding B is disconnected.

#### 7.1.2.171 #define WIND_B_STATE_MALFUNC 0x20

Winding B is short-circuited.

#### 7.1.2.172 #define WIND_B_STATE_OK 0x30

Winding B is connected and working properly.

#### 7.1.2.173 #define WIND_B_STATE_UNKNOWN 0x10

Winding B state is unknown.

#### 7.1.2.174 #define XIMC_API

Library import macro Macros allows to automatically import function from shared library.

It automatically expands to dllimport on msvc when including header file

### 7.1.3 Typedef Documentation

#### 7.1.3.1 typedef void(**XIMC_CALLCONV** * logging_callback_t)(int loglevel, const wchar_t *message, void *user_data)

Logging callback prototype.

Parameters

| | |
|---|---|
| *loglevel* | a loglevel |
| *message* | a message |

### 7.1.4 Function Documentation

#### 7.1.4.1 result_t XIMC_API close_device ( device_t * id )

Close specified device.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

Note

The id parameter in this function is a C pointer, unlike most library functions that use this parameter

#### 7.1.4.2 result_t XIMC_API command_clear_fram ( device_t id )

Clear controller FRAM.

Can be used by manufacturer only

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.3 result_t XIMC_API command_eeread_settings ( device_t id )

Read settings from controller's RAM to stage's EEPROM memory, which spontaneity connected to stage and it isn't change without it mechanical reconstruction.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.4 result_t XIMC_API command_eesave_settings ( device_t id )

Save settings from controller's RAM to stage's EEPROM memory, which spontaneity connected to stage and it isn't change without it mechanical reconstruction.

Can be used by manufacturer only.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.5 result_t XIMC_API command_home ( device_t id )

The positive direction is to the right.

A value of zero reverses the direction of the direction of the flag, the set speed. Restriction imposed by the trailer, act the same, except that the limit switch contact does not stop. Limit the maximum speed, acceleration and deceleration function. 1) moves the motor according to the speed FastHome, uFastHome and flag HOME_DIR_FAST until limit switch, if the flag is set HOME_STOP_ENDS, until the signal from the input synchronization if the flag HOME_STOP_SYNC (as accurately as possible is important to catch the moment of operation limit switch) or until the signal is received from the speed sensor, if the flag HOME_STOP_REV_SN 2) then moves according to the speed SlowHome, uSlowHome and flag HOME_DIR_SLOW until signal from the clock input, if the flag HOM-

E_MV_SEC. If the flag HOME_MV_SEC reset skip this paragraph. 3) then move the motor according to the speed FastHome, uFastHome and flag HOME_DIR_SLOW a distance HomeDelta, uHomeDelta. description of flags and variable see in description for commands GHOM/SHOM

Parameters

| | |
|---|---|
| *id* | an identifier of device |

See Also

home_settings_t
get_home_settings
set_home_settings

#### 7.1.4.6 **result_t XIMC_API** command_homezero ( **device_t** id )

Make home command, wait until it is finished and make zero command.

This is a convinient way to calibrate zero position.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *ret* | RESULT_OK if controller has finished home & zero correctly or result of first controller query that returned anything other than RESULT_OK. |

#### 7.1.4.7 **result_t XIMC_API** command_left ( **device_t** id )

Start continous moving to the left.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.8 **result_t XIMC_API** command_loft ( **device_t** id )

Upon receiving the command ”loft” the engine is shifted from the current point to a distance GENG :: Antiplay, then move to the same point.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.9 **result_t XIMC_API** command_move ( **device_t** id, int Position, int uPosition )

Upon receiving the command ”move” the engine starts to move with pre-set parameters (speed, acceleration, retention), to the point specified to the Position, uPosition.

For stepper motor uPosition sets the microstep, for DC motor this field is not used.

Parameters

| | |
|---|---|
| *id* | an identifier of device |
| *Position* | position to move. |

| | |
|---|---|
| *uPosition* | part of the position to move, microsteps. Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings). |

#### 7.1.4.10 **result_t XIMC_API** command_move_calb ( **device_t** id, float Position, const **calibration_t** * calibration )

Move to position which use user units.

Upon receiving the command ”move” the engine starts to move with pre-set parameters (speed, acceleration, retention), to the point specified to the Position.

Parameters

| | |
|---|---|
| *id* | an identifier of device |
| *Position* | position to move. |
| *calibration* | user unit settings |

Note

The parameter Position is adjusted by the correction table.

#### 7.1.4.11 **result_t XIMC_API** command_movr ( **device_t** id, int DeltaPosition, int uDeltaPosition )

Move to offset.

Upon receiving the command ”movr” engine starts to move with pre-set parameters (speed, acceleration, hold), left or right (depending on the sign of DeltaPosition) by the number of pulses specified in the fields DeltaPosition, uDeltaPosition. For stepper motor uDeltaPosition sets the microstep, for DC motor this field is not used.

Parameters

| | |
|---|---|
| *DeltaPosition* | shift from initial position. |
| *uDeltaPosition* | part of the offset shift, microsteps. Microstep size and the range of valid values for this field depend on selected step division mode (see MicrostepMode field in engine_settings). |
| *id* | an identifier of device |

#### 7.1.4.12 **result_t XIMC_API** command_movr_calb ( **device_t** id, float DeltaPosition, const **calibration_t** * calibration )

Move to offset using user units.

Upon receiving the command ”movr” engine starts to move with pre-set parameters (speed, acceleration, hold), left or right (depending on the sign of DeltaPosition) the distance specified in the field DeltaPosition.

Parameters

| | |
|---|---|
| *DeltaPosition* | shift from initial position. |
| *id* | an identifier of device |
| *calibration* | user unit settings |

Note

The end coordinate is calculated using DeltaPosition, is adjusted by the correction table. To calculate coordinates correctly, when using a correction table, you do not need to execute movr commands in batches.

#### 7.1.4.13 result_t XIMC_API command_power_off ( device_t id )

Immediately power off motor regardless its state.

Shouldn't be used during motion as the motor could be power on again automatically to continue movement. The command is designed for manual motor power off. When automatic power off after stop is required, use power management system.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

See Also

get_power_settings
set_power_settings

#### 7.1.4.14 result_t XIMC_API command_read_robust_settings ( device_t id )

Read important settings (calibration coefficients and etc.) from controller's flash memory to controller's RAM, replacing previous data in controller's RAM.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.15 result_t XIMC_API command_read_settings ( device_t id )

Read all settings from controller's flash memory to controller's RAM, replacing previous data in controller's RAM.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.16 result_t XIMC_API command_reset ( device_t id )

Reset controller.

Can be used by manufacturer only

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.17 result_t XIMC_API command_right ( device_t id )

Start continous moving to the right.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.18 result_t XIMC_API command_save_robust_settings ( device_t id )

Save important settings (calibration coefficients and etc.) from controller's RAM to controller's flash memory, replacing previous data in controller's flash memory.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.19 result_t XIMC_API command_save_settings ( device_t id )

Save all settings from controller's RAM to controller's flash memory, replacing previous data in controller's flash memory.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.20 result_t XIMC_API command_sstp ( device_t id )

Soft stop engine.

The motor stops with deceleration speed.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.21 result_t XIMC_API command_start_measurements ( device_t id )

Start measurements and buffering of speed, following error.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.22 result_t XIMC_API command_stop ( device_t id )

Immediately stop the engine, the transition to the STOP, mode key BREAK (winding short-circuited), the regime "retention" is deactivated for DC motors, keeping current in the windings for stepper motors (with Power management settings).

Parameters

| | |
|---|---|
| *id* | an identifier of device |

#### 7.1.4.23 result_t XIMC_API command_update_firmware ( const char * uri, const uint8_t * data, uint32_t data_size )

Update firmware.

Service command

Parameters

| | |
|---|---|
| *uri* | a uri of device |
| *data* | firmware byte stream |
| *data_size* | size of byte stream |

### 7.1.4.24 **result_t XIMC_API** command_wait_for_stop ( **device_t** id, uint32_t refresh_interval_ms )

Wait for stop.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| | *refresh_interval_ms* | Status refresh interval. The function waits this number of milliseconds between get_status requests to the controller. Recommended value of this parameter is 10 ms. Use values of less than 3 ms only when necessary - small refresh interval values do not significantly increase response time of the function, but they create substantially more traffic in controller-computer data channel. |
| out | *ret* | RESULT_OK if controller has stopped and result of the first get_status command which returned anything other than RESULT_OK otherwise. |

### 7.1.4.25 **result_t XIMC_API** command_zero ( **device_t** id )

Sets the current position and the position in which the traffic moves by the move command and movr zero for all cases, except for movement to the target position.

In the latter case, set the zero current position and the target position counted so that the absolute position of the destination is the same. That is, if we were at 400 and moved to 500, then the command Zero makes the current position of 0, and the position of the destination - 100. Does not change the mode of movement that is if the motion is carried, it continues, and if the engine is in the ”hold”, the type of retention remains.

Parameters

| | |
|---|---|
| *id* | an identifier of device |

### 7.1.4.26 **device_enumeration_t XIMC_API** enumerate_devices ( int enumerate_flags, const char * hints )

Enumerate all devices that looks like valid.

Parameters

| | | |
|---|---|---|
| in | *enumerate_flags* | enumerate devices flags |
| in | *hints* | extended information hints is a string of form ”key=value \n key2=value2”. Unrecognized key-value pairs are ignored. Key list: addr - used together with ENUMERATE_NETWORK flag. Non-null value is a remote host name or a comma-separated list of host names which contain the devices to be found, absent value means broadcast discovery. adapter_addr - used together with ENUMERATE_NETWORK flag. Non-null value is a IP address of network adapter. Remote ximc device must be on the same local network as the adapter. When using the adapter_addr key, you must install the addr key. Example: ”addr= \n adapter_addr=192.168.0.100”. To enumerate network devices you must call set_bindy_key first. |

7.1.4.27 **result_t XIMC_API** free_enumerate_devices ( **device_enumeration_t** device_enumeration )

Free memory returned by *enumerate_devices*.

Parameters

| | | |
|---|---|---|
| in | *device_enumeration* | opaque pointer to an enumeration device data |

7.1.4.28 **result_t XIMC_API** get_accessories_settings ( **device_t** id, **accessories_settings_t** * accessories_settings )

Read additional accessories information from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *accessories_settings* | structure contains information about additional accessories |

7.1.4.29 **result_t XIMC_API** get_analog_data ( **device_t** id, **analog_data_t** * analog_data )

Read analog data structure that contains raw analog data from ADC embedded on board.

This function used for device testing and deep recalibraton by manufacturer only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *analog_data* | analog data coefficients |

7.1.4.30 **result_t XIMC_API** get_bootloader_version ( **device_t** id, unsigned int * Major, unsigned int * Minor, unsigned int * Release )

Read controller's firmware version.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *Major* | major version |
| out | *Minor* | minor version |
| out | *Release* | release version |

7.1.4.31 **result_t XIMC_API** get_brake_settings ( **device_t** id, **brake_settings_t** * brake_settings )

Read settings of brake control.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *brake_settings* | structure contains settings of brake control |

#### 7.1.4.32 result_t XIMC_API get_calibration_settings ( device_t id, calibration_settings_t * calibration_settings )

Read calibration settings.

This function fill structure with calibration settings.

See Also

calibration_settings_t

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *calibration_settings* | calibration settings |

#### 7.1.4.33 result_t XIMC_API get_chart_data ( device_t id, chart_data_t * chart_data )

Return device electrical parameters, useful for charts.

Useful function that fill structure with snapshot of controller voltages and currents.

See Also

chart_data_t

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *chart_data* | structure with snapshot of controller parameters. |

#### 7.1.4.34 result_t XIMC_API get_control_settings ( device_t id, control_settings_t * control_settings )

Read settings of motor control.

When choosing CTL_MODE = 1 switches motor control with the joystick. In this mode, the joystick to the maximum engine tends Move at MaxSpeed [i], where i = 0 if the previous use This mode is not selected another i. Buttons switch the room rate i. When CTL_MODE = 2 is switched on motor control using the Left / right. When you click on the button motor starts to move in the appropriate direction at a speed MaxSpeed [0], at the end of time Timeout [i] motor move at a speed MaxSpeed [i+1]. at Transition from MaxSpeed [i] on MaxSpeed [i +1] to acceleration, as usual.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *control_settings* | structure contains settings motor control by joystick or buttons left/right. |

#### 7.1.4.35 result_t XIMC_API get_control_settings_calb ( device_t id, control_settings_calb_t * control_settings_calb, const calibration_t * calibration )

Read settings of motor control which use user units.

When choosing CTL_MODE = 1 switches motor control with the joystick. In this mode, the joystick to the maximum engine tends Move at MaxSpeed [i], where i = 0 if the previous use This mode is not selected another i. Buttons switch the room rate i. When CTL_MODE = 2 is switched on motor control using the Left / right. When you click on

the button motor starts to move in the appropriate direction at a speed MaxSpeed [0], at the end of time Timeout [i] motor move at a speed MaxSpeed [i+1]. at Transition from MaxSpeed [i] on MaxSpeed [i +1] to acceleration, as usual.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *control_settings_calb* | structure contains settings motor control by joystick or buttons left/right. |
| | *calibration* | user unit settings |

7.1.4.36 **result_t XIMC_API** get_controller_name ( **device_t** id, **controller_name_t** * controller_name )

Read user controller name and flags of setting from FRAM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *controller_name* | structure contains previously set user controller name |

7.1.4.37 **result_t XIMC_API** get_ctp_settings ( **device_t** id, **ctp_settings_t** * ctp_settings )

Read settings of control position(is only used with stepper motor).

When controlling the step motor with encoder (CTP_BASE 0) it is possible to detect the loss of steps. The controller knows the number of steps per revolution (GENG :: StepsPerRev) and the encoder resolution (GFBS :: IPT). When the control (flag CTP_ENABLED), the controller stores the current position in the footsteps of SM and the current position of the encoder. Further, at each step of the position encoder is converted into steps and if the difference is greater CTPMinError, a flag STATE_CTP_ERROR. When controlling the step motor with speed sensor (CTP_BASE 1), the position is controlled by him. The active edge of input clock controller stores the current value of steps. Further, at each turn checks how many steps shifted. When a mismatch CTPMinError a flag STATE_CTP_ERROR.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *ctp_settings* | structure contains settings of control position |

7.1.4.38 **result_t XIMC_API** get_debug_read ( **device_t** id, **debug_read_t** * debug_read )

Read data from firmware for debug purpose.

Its use depends on context, firmware version and previous history.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *debug_read* | Debug data. |

7.1.4.39 int **XIMC_API** get_device_count ( **device_enumeration_t** device_enumeration )

Get device count.

Parameters

| | | |
|---|---|---|
| in | *device_enumeration* | opaque pointer to an enumeration device data |

7.1.4.40 **result_t XIMC_API** get_device_information ( **device_t** id, **device_information_t** * device_information )

Return device information.

All fields must point to allocated string buffers with at least 10 bytes. Works with both raw or initialized device.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *device_information* | device information Device information. |

See Also

get_device_information

7.1.4.41 **pchar XIMC_API** get_device_name ( **device_enumeration_t** device_enumeration, int device_index )

Get device name from the device enumeration.

Returns *device_index* device name.

Parameters

| | | |
|---|---|---|
| in | *device_enumeration* | opaque pointer to an enumeration device data |
| in | *device_index* | device index |

7.1.4.42 **result_t XIMC_API** get_edges_settings ( **device_t** id, **edges_settings_t** * edges_settings )

Read border and limit switches settings.

See Also

set_edges_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *edges_settings* | edges settings, specify types of borders, motor behaviour and electrical behaviour of limit switches |

7.1.4.43 **result_t XIMC_API** get_edges_settings_calb ( **device_t** id, **edges_settings_calb_t** * edges_settings_calb, const **calibration_t** * calibration )

Read border and limit switches settings which use user units.

See Also

set_edges_settings_calb

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *edges_settings_calb* | edges settings, specify types of borders, motor behaviour and electrical behaviour of limit switches |
| | *calibration* | user unit settings |

Note

Attention! Some parameters of the edges_settings_calb structure are corrected by the coordinate correction table.

#### 7.1.4.44 **result_t XIMC_API** get_emf_settings ( **device_t** id, **emf_settings_t** * emf_settings )

Read electromechanical settings.

The settings are different for different stepper motors.

See Also

set_emf_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *emf_settings* | EMF settings |

#### 7.1.4.45 **result_t XIMC_API** get_encoder_information ( **device_t** id, **encoder_information_t** * encoder_information )

Read encoder information from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *encoder_information* | structure contains information about encoder |

#### 7.1.4.46 **result_t XIMC_API** get_encoder_settings ( **device_t** id, **encoder_settings_t** * encoder_settings )

Read encoder settings from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *encoder_settings* | structure contains encoder settings |

7.1.4.47 **result_t XIMC_API** get_engine_advansed_setup ( **device_t** id, **engine_advansed_setup_t** * engine_advansed_setup )

Read engine advansed settings.

See Also

set_engine_advansed_setup

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *engine_advansed_setup* | EAS settings |

7.1.4.48 **result_t XIMC_API** get_engine_settings ( **device_t** id, **engine_settings_t** * engine_settings )

Read engine settings.

This function fill structure with set of useful motor settings stored in controller's memory. These settings specify motor shaft movement algorithm, list of limitations and rated characteristics.

See Also

set_engine_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *engine_settings* | engine settings |

7.1.4.49 **result_t XIMC_API** get_engine_settings_calb ( **device_t** id, **engine_settings_calb_t** * engine_settings_calb, const **calibration_t** * calibration )

Read engine settings which use user units.

This function fill structure with set of useful motor settings stored in controller's memory. These settings specify motor shaft movement algorithm, list of limitations and rated characteristics.

See Also

set_engine_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *engine_settings_calb* | engine settings |
| | *calibration* | user unit settings |

7.1.4.50 **result_t XIMC_API** get_entype_settings ( **device_t** id, **entype_settings_t** * entype_settings )

Return engine type and driver type.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *entype_settings* | structure contains settings motor type and power driver type |

7.1.4.51 **result_t XIMC_API** get_enumerate_device_controller_name ( **device_enumeration_t** device_enumeration, int device_index, **controller_name_t** * controller_name )

Get controller name from the device enumeration.

Returns *device_index* device controller name.

Parameters

| | | |
|---|---|---|
| in | *device_enumeration* | opaque pointer to an enumeration device data |
| in | *device_index* | device index |
| out | *controller_name* | controller name |

7.1.4.52 **result_t XIMC_API** get_enumerate_device_information ( **device_enumeration_t** device_enumeration, int device_index, **device_information_t** * device_information )

Get device information from the device enumeration.

Returns *device_index* device information.

Parameters

| | | |
|---|---|---|
| in | *device_enumeration* | opaque pointer to an enumeration device data |
| in | *device_index* | device index |
| out | *device_information* | device information data |

7.1.4.53 **result_t XIMC_API** get_enumerate_device_network_information ( **device_enumeration_t** device_enumeration, int device_index, **device_network_information_t** * device_network_information )

Get device network information from the device enumeration.

Returns *device_index* device network information.

Parameters

| | | |
|---|---|---|
| in | *device_enumeration* | opaque pointer to an enumeration device data |
| in | *device_index* | device index |
| out | *device_network_information* | device network information data |

7.1.4.54 **result_t XIMC_API** get_enumerate_device_serial ( **device_enumeration_t** device_enumeration, int device_index, uint32_t * serial )

Get device serial number from the device enumeration.

Returns *device_index* device serial number.

Parameters

| | | |
|---|---|---|
| in | *device_enumeration* | opaque pointer to an enumeration device data |
| in | *device_index* | device index |
| out | *serial* | device serial number |

7.1.4.55 **result_t XIMC_API** get_enumerate_device_stage_name ( **device_enumeration_t** device_enumeration, int device_index, **stage_name_t** * stage_name )

Get stage name from the device enumeration.

Returns *device_index* device stage name.

Parameters

| | | |
|---|---|---|
| in | *device_enumeration* | opaque pointer to an enumeration device data |
| in | *device_index* | device index |
| out | *stage_name* | stage name |

7.1.4.56 **result_t XIMC_API** get_extended_settings ( **device_t** id, **extended_settings_t** * extended_settings )

Read extended settings.

See Also

set_extended_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *extended_settings* | EST settings |

7.1.4.57 **result_t XIMC_API** get_extio_settings ( **device_t** id, **extio_settings_t** * extio_settings )

Read EXTIO settings.

This function reads a structure with a set of EXTIO settings from controller's memory.

See Also

set_extio_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *extio_settings* | EXTIO settings |

7.1.4.58 **result_t XIMC_API** get_feedback_settings ( **device_t** id, **feedback_settings_t** * feedback_settings )

Feedback settings.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *IPS* | number of encoder counts per shaft revolution. Range: 1..65535. The field is obsolete, it is recommended to write 0 to IPS and use the extended CountsPerTurn field. You may need to update the controller firmware to the latest version. |
| out | *FeedbackType* | type of feedback |
| out | *FeedbackFlags* | flags of feedback |
| out | *CountsPerTurn* | number of encoder counts per shaft revolution. Range: 1..4294967295. To use the CountsPerTurn field, write 0 in the IPS field, otherwise the value from the IPS field will be used. |

7.1.4.59 **result_t XIMC_API** get_firmware_version ( **device_t** id, unsigned int * Major, unsigned int * Minor, unsigned int * Release )

Read controller's firmware version.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *Major* | major version |
| out | *Minor* | minor version |
| out | *Release* | release version |

7.1.4.60 **result_t XIMC_API** get_gear_information ( **device_t** id, **gear_information_t** * gear_information )

Read gear information from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *gear_information* | structure contains information about step gearhead |

7.1.4.61 **result_t XIMC_API** get_gear_settings ( **device_t** id, **gear_settings_t** * gear_settings )

Read gear settings from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *gear_settings* | structure contains step gearhead settings |

7.1.4.62 **result_t XIMC_API** get_globally_unique_identifier ( **device_t** id, **globally_unique_identifier_t** * globally_unique_identifier )

This value is unique to each individual die but is not a random value.

This unique device identifier can be used to initiate secure boot processes or as a serial number for USB or other end applications.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *globally_unique_identifier* | the result of fields 0-3 concatenated defines the unique 128-bit device identifier. |

7.1.4.63 **result_t XIMC_API** get_hallsensor_information ( **device_t** id, **hallsensor_information_t** * hallsensor_information )

Read hall sensor information from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *hallsensor_information* | structure contains information about hall sensor |

7.1.4.64 **result_t XIMC_API** get_hallsensor_settings ( **device_t** id, **hallsensor_settings_t** * hallsensor_settings )

Read hall sensor settings from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *hallsensor_settings* | structure contains hall sensor settings |

7.1.4.65 **result_t XIMC_API** get_home_settings ( **device_t** id, **home_settings_t** * home_settings )

Read home settings.

This function fill structure with settings of calibrating position.

See Also

home_settings_t

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *home_settings* | calibrating position settings |

7.1.4.66 **result_t XIMC_API** get_home_settings_calb ( **device_t** id, **home_settings_calb_t** * home_settings_calb, const **calibration_t** * calibration )

Read home settings which use user units.

This function fill structure with settings of calibrating position.

See Also

home_settings_calb_t

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *home_settings_calb* | calibrating position settings |
| | *calibration* | user unit settings |

7.1.4.67 **result_t XIMC_API** get_init_random ( **device_t** id, **init_random_t** * init_random )

Read random number from controller.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *init_random* | random sequence generated by the controller |

7.1.4.68 **result_t XIMC_API** get_joystick_settings ( **device_t** id, **joystick_settings_t** * joystick_settings )

Read settings of joystick.

If joystick position is outside DeadZone limits from the central position a movement with speed, defined by the joystick DeadZone edge to 100% deviation, begins. Joystick positions inside DeadZone limits correspond to zero speed (soft stop of motion) and positions beyond Low and High limits correspond MaxSpeed [i] or -MaxSpeed [i] (see command SCTL), where i = 0 by default and can be changed with left/right buttons (see command SCTL). If next speed in list is zero (both integer and microstep parts), the button press is ignored. First speed in list shouldn't be zero. The DeadZone ranges are illustrated on the following picture. !/attachments/download/5563/range25p.png! The relationship between the deviation and the rate is exponential, allowing no switching speed combine high mobility and accuracy. The following picture illustrates this: !/attachments/download/3092/ExpJoystick.png! The nonlinearity parameter is adjustable. Setting it to zero makes deviation/speed relation linear.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *joystick_settings* | structure contains joystick settings |

7.1.4.69 **result_t XIMC_API** get_measurements ( **device_t** id, **measurements_t** * measurements )

A command to read the data buffer to build a speed graph and a sequence error.

Filling the buffer starts with the command "start_measurements". The buffer holds 25 points, the points are taken with a period of 1 ms. To create a robust system, read data every 20 ms, if the buffer is completely full, then it is recommended to repeat the readings every 5 ms until the buffer again becomes filled with 20 points.

See Also

measurements_t

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *measurements* | structure with buffer and its length. |

7.1.4.70 **result_t XIMC_API** get_motor_information ( **device_t** id, **motor_information_t** * motor_information )

Read motor information from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *motor_information* | structure contains motor information |

7.1.4.71 **result_t XIMC_API** get_motor_settings ( **device_t** id, **motor_settings_t** * motor_settings )

Read motor settings from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *motor_settings* | structure contains motor settings |

7.1.4.72 **result_t XIMC_API** get_move_settings ( **device_t** id, **move_settings_t** * move_settings )

Read command setup movement (speed, acceleration, threshold and etc).

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *move_settings* | structure contains move settings: speed, acceleration, deceleration etc. |

7.1.4.73 **result_t XIMC_API** get_move_settings_calb ( **device_t** id, **move_settings_calb_t** * move_settings_calb, const **calibration_t** * calibration )

Read command setup movement which use user units (speed, acceleration, threshold and etc).

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *move_settings_calb* | structure contains move settings: speed, acceleration, deceleration etc. |
| | *calibration* | user unit settings |

7.1.4.74 **result_t XIMC_API** get_nonvolatile_memory ( **device_t** id, **nonvolatile_memory_t** * nonvolatile_memory )

Read userdata from FRAM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *nonvolatile_memory* | structure contains previously set userdata |

7.1.4.75 **result_t XIMC_API** get_pid_settings ( **device_t** id, **pid_settings_t** * pid_settings )

Read PID settings.

This function fill structure with set of motor PID settings stored in controller's memory. These settings specify behaviour of PID routine for positioner. These factors are slightly different for different positioners. All boards are supplied with standard set of PID setting on controller's flash memory.

See Also

set_pid_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *pid_settings* | pid settings |

### 7.1.4.76 result_t XIMC_API get_position ( device_t id, get_position_t * the_get_position )

Reads the value position in steps and micro for stepper motor and encoder steps all engines.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *the_get_position* | structure contains move settings: speed, acceleration, deceleration etc. |

### 7.1.4.77 result_t XIMC_API get_position_calb ( device_t id, get_position_calb_t * the_get_position_calb, const calibration_t * calibration )

Reads position value in user units for stepper motor and encoder steps all engines.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *the_get_position-_calb* | structure contains move settings: speed, acceleration, deceleration etc. |
| | *calibration* | user unit settings |

Note

Attention! Some parameters of the the_get_position_calb structure are corrected by the coordinate correction table.

### 7.1.4.78 result_t XIMC_API get_power_settings ( device_t id, power_settings_t * power_settings )

Read settings of step motor power control.

Used with stepper motor only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *power_settings* | structure contains settings of step motor power control |

### 7.1.4.79 result_t XIMC_API get_secure_settings ( device_t id, secure_settings_t * secure_settings )

Read protection settings.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *secure_settings* | critical parameter settings to protect the hardware |

See Also

status_t::flags

7.1.4.80 **result_t XIMC_API** get_serial_number ( **device_t** id, unsigned int * SerialNumber )

Read device serial number.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *SerialNumber* | serial number |

7.1.4.81 **result_t XIMC_API** get_stage_information ( **device_t** id, **stage_information_t** * stage_information )

Read stage information from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *stage_information* | structure contains stage information |

7.1.4.82 **result_t XIMC_API** get_stage_name ( **device_t** id, **stage_name_t** * stage_name )

Read user stage name from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *stage_name* | structure contains previously set user stage name |

7.1.4.83 **result_t XIMC_API** get_stage_settings ( **device_t** id, **stage_settings_t** * stage_settings )

Read stage settings from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *stage_settings* | structure contains stage settings |

7.1.4.84 **result_t XIMC_API** get_status ( **device_t** id, **status_t** * status )

Return device state.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *status* | structure with snapshot of controller status Device state. Useful structure that contains current controller status, including speed, position and boolean flags. |

See Also

get_status

7.1.4.85 **result_t XIMC_API** get_status_calb ( **device_t** id, **status_calb_t** * status, const **calibration_t** * calibration )

Return device state.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *status* | structure with snapshot of controller status |
| | *calibration* | user unit settings Calibrated device state. Useful structure that contains current controller status, including speed, position and boolean flags. |

See Also

get_status

7.1.4.86 **result_t XIMC_API** get_sync_in_settings ( **device_t** id, **sync_in_settings_t** * sync_in_settings )

Read input synchronization settings.

This function fill structure with set of input synchronization settings, modes, periods and flags, that specify behaviour of input synchronization. All boards are supplied with standard set of these settings.

See Also

set_sync_in_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *sync_in_settings* | synchronization settings |

7.1.4.87 **result_t XIMC_API** get_sync_in_settings_calb ( **device_t** id, **sync_in_settings_calb_t** * sync_in_settings_calb, const **calibration_t** * calibration )

Read input synchronization settings which use user units.

This function fill structure with set of input synchronization settings, modes, periods and flags, that specify behaviour of input synchronization. All boards are supplied with standard set of these settings.

See Also

set_sync_in_settings_calb

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *sync_in_settings_calb* | synchronization settings |
| | *calibration* | user unit settings |

7.1.4.88 **result_t XIMC_API** get_sync_out_settings ( **device_t** id, **sync_out_settings_t** * sync_out_settings )

Read output synchronization settings.

This function fill structure with set of output synchronization settings, modes, periods and flags, that specify behaviour of output synchronization. All boards are supplied with standard set of these settings.

See Also

set_sync_out_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *sync_out_settings* | synchronization settings |

### 7.1.4.89 result_t XIMC_API get_sync_out_settings_calb ( device_t id, sync_out_settings_calb_t * sync_out_settings_calb, const calibration_t * calibration )

Read output synchronization settings which use user units.

This function fill structure with set of output synchronization settings, modes, periods and flags, that specify behaviour of output synchronization. All boards are supplied with standard set of these settings.

See Also

set_sync_in_settings_calb

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *sync_out_settings_calb* | synchronization settings |
| | *calibration* | user unit settings |

### 7.1.4.90 result_t XIMC_API get_uart_settings ( device_t id, uart_settings_t * uart_settings )

Read UART settings.

This function fill structure with UART settings.

See Also

uart_settings_t

Parameters

| | | |
|---|---|---|
| | *Speed* | UART speed |
| out | *uart_settings* | UART settings |

### 7.1.4.91 result_t XIMC_API goto_firmware ( device_t id, uint8_t * ret )

Reboot to firmware.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *ret* | RESULT_OK, if reboot to firmware is possible. Reboot is done after reply to this command. RESULT_NO_FIRMWARE, if firmware is not found. RESULT_ALREADY_IN_FIRMWARE, if this command was sent when controller is already in firmware. |

### 7.1.4.92 **result_t XIMC_API** has_firmware ( const char * uri, uint8_t * ret )

Check for firmware on device.

Parameters

| | | |
|---|---|---|
| | *uri* | a uri of device |
| out | *ret* | non-zero if firmware existed |

### 7.1.4.93 **result_t XIMC_API** load_correction_table ( **device_t** * id, const char * namefile )

Command of loading a correction table from a text file.

This function is deprecated. Use the function set_correction_table(device_t id, const char* namefile). The correction table is used for position correction in case of mechanical inaccuracies. It works for some parameters in _calb commands.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier the device |
| in | *namefile* | - the file name must be fully qualified. If the short name is used, the file must be located in the application directory. If the file name is set to NULL, the correction table will be cleared. File format: two tab-separated columns. Column headers are string. Data is real, the point is a determiter. The first column is a coordinate. The second one is the deviation caused by a mechanical error. The maximum length of a table is 100 rows. |

Note

The id parameter in this function is a C pointer, unlike most library functions that use this parameter

See Also

command_move
get_position_calb
get_position_calb_t
get_status_calb
status_calb_t
get_edges_settings_calb
set_edges_settings_calb
edges_settings_calb_t

### 7.1.4.94 void **XIMC_API** logging_callback_stderr_narrow ( int loglevel, const wchar_t * message, void * user_data )

Simple callback for logging to stderr in narrow (single byte) chars.

Parameters

| | |
|---|---|
| *loglevel* | a loglevel |
| *message* | a message |

#### 7.1.4.95 void **XIMC_API** logging_callback_stderr_wide ( int loglevel, const wchar_t * message, void * user_data )

Simple callback for logging to stderr in wide chars.

Parameters

| | |
|---|---|
| *loglevel* | a loglevel |
| *message* | a message |

#### 7.1.4.96 void **XIMC_API** msec_sleep ( unsigned int msec )

Sleeps for a specified amount of time.

Parameters

| | |
|---|---|
| *msec* | time in milliseconds |

#### 7.1.4.97 **device_t XIMC_API** open_device ( const char * uri )

Open a device with OS uri *uri* and return identifier of the device which can be used in calls.

Parameters

| | | |
|---|---|---|
| in | *uri* | - a device uri. Device uri has form ”xi-com:port” or ”xi-net://host/serial” or ”xi-emu:///file”. In case of USB-COM port the ”port” is the OS device uri. For example ”xi-com:\\.\COM3” in Windows or ”xi-com:/dev/tty.s123” in Linux/Mac. In case of network device the ”host” is an IPv4 address or fully qualified domain uri (FQDN), ”serial” is the device serial number in hexadecimal system. For example ”xi-net://192.168.0.1/00001234” or ”xi-net://hostname.com/89ABCDEF”. Note: to open network device you must call set_bindy_key first. In case of virtual device the ”file” is the full filename with device memory state, if it doesn’t exist then it is initialized with default values. For example ”xi-emu:///C:/dir/file.bin” in Windows or ”xi-emu:///home/user/file.bin” in Linux/Mac. |

#### 7.1.4.98 **result_t XIMC_API** probe_device ( const char * uri )

Check if a device with OS uri *uri* is XIMC device.

Be carefuly with this call because it sends some data to the device.

Parameters

| | | |
|---|---|---|
| in | *uri* | - a device uri |

#### 7.1.4.99 **result_t XIMC_API** service_command_updf ( **device_t** id )

Command puts the controller to update the firmware.

After receiving this command, the firmware board sets a flag (for loader), sends echo reply and restarts the controller.

#### 7.1.4.100 result_t XIMC_API set_accessories_settings ( device_t id, const accessories_settings_t * accessories_settings )

Set additional accessories information to EEPROM.

Can be used by manufacturer only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *accessories_settings* | structure contains information about additional accessories |

#### 7.1.4.101 result_t XIMC_API set_bindy_key ( const char * keyfilepath )

Set network encryption layer (bindy) key.

Parameters

| | | |
|---|---|---|
| in | *keyfilepath* | full path to the bindy keyfile When using network-attached devices this function must be called before enumerate_devices and open_device functions. |

#### 7.1.4.102 result_t XIMC_API set_brake_settings ( device_t id, const brake_settings_t * brake_settings )

Set settings of brake control.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *brake_settings* | structure contains settings of brake control |

#### 7.1.4.103 result_t XIMC_API set_calibration_settings ( device_t id, const calibration_settings_t * calibration_settings )

Set calibration settings.

This function send structure with calibration settings to controller's memory.

See Also

calibration_settings_t

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *calibration_settings* | calibration settings |

7.1.4.104 **result_t XIMC_API** set_control_settings ( **device_t** id, const **control_settings_t** * control_settings )

Set settings of motor control.

When choosing CTL_MODE = 1 switches motor control with the joystick. In this mode, the joystick to the maximum engine tends Move at MaxSpeed [i], where i = 0 if the previous use This mode is not selected another i. Buttons switch the room rate i. When CTL_MODE = 2 is switched on motor control using the Left / right. When you click on the button motor starts to move in the appropriate direction at a speed MaxSpeed [0], at the end of time Timeout [i] motor move at a speed MaxSpeed [i+1]. at Transition from MaxSpeed [i] on MaxSpeed [i +1] to acceleration, as usual.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *control_settings* | structure contains settings motor control by joystick or buttons left/right. |

7.1.4.105 **result_t XIMC_API** set_control_settings_calb ( **device_t** id, const **control_settings_calb_t** * control_settings_calb, const **calibration_t** * calibration )

Set settings of motor control which use user units.

When choosing CTL_MODE = 1 switches motor control with the joystick. In this mode, the joystick to the maximum engine tends Move at MaxSpeed [i], where i = 0 if the previous use This mode is not selected another i. Buttons switch the room rate i. When CTL_MODE = 2 is switched on motor control using the Left / right. When you click on the button motor starts to move in the appropriate direction at a speed MaxSpeed [0], at the end of time Timeout [i] motor move at a speed MaxSpeed [i+1]. at Transition from MaxSpeed [i] on MaxSpeed [i +1] to acceleration, as usual.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *control_settings_calb* | structure contains settings motor control by joystick or buttons left/right. |
| | *calibration* | user unit settings |

7.1.4.106 **result_t XIMC_API** set_controller_name ( **device_t** id, const **controller_name_t** * controller_name )

Write user controller name and flags of setting from FRAM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *controller_name* | structure contains previously set user controller name |

7.1.4.107 **result_t XIMC_API** set_correction_table ( **device_t** id, const char * namefile )

Command of loading a correction table from a text file.

The correction table is used for position correction in case of mechanical inaccuracies. It works for some parameters in _calb commands.

Parameters

| | *id* | an identifier the device |
|---|---|---|
| in | *namefile* | - the file name must be fully qualified. If the short name is used, the file must be located in the application directory. If the file name is set to NULL, the correction table will be cleared. File format: two tab-separated columns. Column headers are string. Data is real, the point is a determiter. The first column is a coordinate. The second one is the deviation caused by a mechanical error. The maximum length of a table is 100 rows. |

See Also

command_move
get_position_calb
get_position_calb_t
get_status_calb
status_calb_t
get_edges_settings_calb
set_edges_settings_calb
edges_settings_calb_t

### 7.1.4.108 result_t XIMC_API set_ctp_settings ( device_t id, const ctp_settings_t * ctp_settings )

Set settings of control position(is only used with stepper motor).

When controlling the step motor with encoder (CTP_BASE 0) it is possible to detect the loss of steps. The controller knows the number of steps per revolution (GENG :: StepsPerRev) and the encoder resolution (GFBS :: IPT). When the control (flag CTP_ENABLED), the controller stores the current position in the footsteps of SM and the current position of the encoder. Further, at each step of the position encoder is converted into steps and if the difference is greater CTPMinError, a flag STATE_CTP_ERROR. When controlling the step motor with speed sensor (CTP_BASE 1), the position is controlled by him. The active edge of input clock controller stores the current value of steps. Further, at each turn checks how many steps shifted. When a mismatch CTPMinError a flag STATE_CTP_ERROR.

Parameters

| | *id* | an identifier of device |
|---|---|---|
| in | *ctp_settings* | structure contains settings of control position |

### 7.1.4.109 result_t XIMC_API set_debug_write ( device_t id, const debug_write_t * debug_write )

Write data to firmware for debug purpose.

Parameters

| | *id* | an identifier of device |
|---|---|---|
| in | *debug_write* | Debug data. |

### 7.1.4.110 result_t XIMC_API set_edges_settings ( device_t id, const edges_settings_t * edges_settings )

Set border and limit switches settings.

See Also

get_edges_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *edges_settings* | edges settings, specify types of borders, motor behaviour and electrical behaviour of limit switches |

7.1.4.111 **result_t XIMC_API** set_edges_settings_calb ( **device_t** id, const **edges_settings_calb_t** * edges_settings_calb, const **calibration_t** * calibration )

Set border and limit switches settings which use user units.

See Also

get_edges_settings_calb

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *edges_settings_calb* | edges settings, specify types of borders, motor behaviour and electrical behaviour of limit switches |
| | *calibration* | user unit settings |

Note

Attention! Some parameters of the edges_settings_calb structure are corrected by the coordinate correction table.

7.1.4.112 **result_t XIMC_API** set_emf_settings ( **device_t** id, const **emf_settings_t** * emf_settings )

Set electromechanical coefficients.

The settings are different for different stepper motors. Please download the new settings when you change the motor.

See Also

get_emf_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *emf_settings* | EMF settings |

7.1.4.113 **result_t XIMC_API** set_encoder_information ( **device_t** id, const **encoder_information_t** * encoder_information )

Set encoder information to EEPROM.

Can be used by manufacturer only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *encoder_information* | structure contains information about encoder |

7.1.4.114 **result_t XIMC_API** set_encoder_settings ( **device_t** id, const **encoder_settings_t** * encoder_settings )

Set encoder settings to EEPROM.

Can be used by manufacturer only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *encoder_settings* | structure contains encoder settings |

7.1.4.115 **result_t XIMC_API** set_engine_advansed_setup ( **device_t** id, const **engine_advansed_setup_t** * engine_advansed_setup )

Set engine advansed settings.

See Also

get_engine_advansed_setup

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *engine_advansed_setup* | EAS settings |

7.1.4.116 **result_t XIMC_API** set_engine_settings ( **device_t** id, const **engine_settings_t** * engine_settings )

Set engine settings.

This function send structure with set of engine settings to controller's memory. These settings specify motor shaft movement algorithm, list of limitations and rated characteristics. Use it when you change motor, encoder, positioner etc. Please note that wrong engine settings lead to device malfunction, can lead to irreversible damage of board.

See Also

get_engine_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *engine_settings* | engine settings |

7.1.4.117 **result_t XIMC_API** set_engine_settings_calb ( **device_t** id, const **engine_settings_calb_t** * engine_settings_calb, const **calibration_t** * calibration )

Set engine settings which use user units.

This function send structure with set of engine settings to controller's memory. These settings specify motor shaft movement algorithm, list of limitations and rated characteristics. Use it when you change motor, encoder, positioner etc. Please note that wrong engine settings lead to device malfunction, can lead to irreversible damage of board.

See Also

get_engine_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *engine_settings_calb* | engine settings |
| | *calibration* | user unit settings |

7.1.4.118 **result_t XIMC_API** set_entype_settings ( **device_t** id, const **entype_settings_t** * entype_settings )

Set engine type and driver type.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *entype_settings* | structure contains settings motor type and power driver type |

7.1.4.119 **result_t XIMC_API** set_extended_settings ( **device_t** id, const **extended_settings_t** * extended_settings )

Set extended settings.

See Also

get_extended_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *extended_settings* | EST settings |

7.1.4.120 **result_t XIMC_API** set_extio_settings ( **device_t** id, const **extio_settings_t** * extio_settings )

Set EXTIO settings.

This function writes a structure with a set of EXTIO settings to controller's memory. By default input event are signalled through rising front and output states are signalled by high logic state.

See Also

get_extio_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *extio_settings* | EXTIO settings |

7.1.4.121 **result_t XIMC_API** set_feedback_settings ( **device_t** id, const **feedback_settings_t** * feedback_settings )

Feedback settings.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *IPS* | number of encoder counts per shaft revolution. Range: 1..65535. The field is obsolete, it is recommended to write 0 to IPS and use the extended CountsPerTurn field. You may need to update the controller firmware to the latest version. |
| in | *FeedbackType* | type of feedback |
| in | *FeedbackFlags* | flags of feedback |
| in | *CountsPerTurn* | number of encoder counts per shaft revolution. Range: 1..4294967295. To use the CountsPerTurn field, write 0 in the IPS field, otherwise the value from the IPS field will be used. |

7.1.4.122 **result_t XIMC_API** set_gear_information ( **device_t** id, const **gear_information_t** * gear_information )

Set gear information to EEPROM.

Can be used by manufacturer only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *gear_information* | structure contains information about step gearhead |

7.1.4.123 **result_t XIMC_API** set_gear_settings ( **device_t** id, const **gear_settings_t** * gear_settings )

Set gear settings to EEPROM.

Can be used by manufacturer only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *gear_settings* | structure contains step gearhead settings |

7.1.4.124 **result_t XIMC_API** set_hallsensor_information ( **device_t** id, const **hallsensor_information_t** * hallsensor_information )

Set hall sensor information to EEPROM.

Can be used by manufacturer only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *hallsensor_information* | structure contains information about hall sensor |

7.1.4.125 **result_t XIMC_API** set_hallsensor_settings ( **device_t** id, const **hallsensor_settings_t** * hallsensor_settings )

Set hall sensor settings to EEPROM.

Can be used by manufacturer only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *hallsensor_settings* | structure contains hall sensor settings |

7.1.4.126 **result_t XIMC_API** set_home_settings ( **device_t** id, const **home_settings_t** * home_settings )

Set home settings.

This function send structure with calibrating position settings to controller's memory.

See Also

home_settings_t

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *home_settings* | calibrating position settings |

7.1.4.127 **result_t XIMC_API** set_home_settings_calb ( **device_t** id, const **home_settings_calb_t** * home_settings_calb, const **calibration_t** * calibration )

Set home settings which use user units.

This function send structure with calibrating position settings to controller's memory.

See Also

home_settings_calb_t

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *home_settings_calb* | calibrating position settings |
| | *calibration* | user unit settings |

7.1.4.128 **result_t XIMC_API** set_joystick_settings ( **device_t** id, const **joystick_settings_t** * joystick_settings )

Set settings of joystick.

If joystick position is outside DeadZone limits from the central position a movement with speed, defined by the joystick DeadZone edge to 100% deviation, begins. Joystick positions inside DeadZone limits correspond to zero speed (soft stop of motion) and positions beyond Low and High limits correspond MaxSpeed [i] or -MaxSpeed [i] (see command SCTL), where i = 0 by default and can be changed with left/right buttons (see command SCTL). If next speed in list is zero (both integer and microstep parts), the button press is ignored. First speed in list shouldn't be

zero. The DeadZone ranges are illustrated on the following picture. !/attachments/download/5563/range25p.png! The relationship between the deviation and the rate is exponential, allowing no switching speed combine high mobility and accuracy. The following picture illustrates this: !/attachments/download/3092/ExpJoystick.png! The nonlinearity parameter is adjustable. Setting it to zero makes deviation/speed relation linear.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *joystick_settings* | structure contains joystick settings |

#### 7.1.4.129 void **XIMC_API** set_logging_callback ( **logging_callback_t** logging_callback, void * user_data )

Sets a logging callback.

Call resets a callback to default (stderr, syslog) if NULL passed.

Parameters

| | |
|---|---|
| *logging_callback* | a callback for log messages |

#### 7.1.4.130 **result_t XIMC_API** set_motor_information ( **device_t** id, const **motor_information_t** * motor_information )

Set motor information to EEPROM.

Can be used by manufacturer only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *motor_information* | structure contains motor information |

#### 7.1.4.131 **result_t XIMC_API** set_motor_settings ( **device_t** id, const **motor_settings_t** * motor_settings )

Set motor settings to EEPROM.

Can be used by manufacturer only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *motor_settings* | structure contains motor information |

#### 7.1.4.132 **result_t XIMC_API** set_move_settings ( **device_t** id, const **move_settings_t** * move_settings )

Set command setup movement (speed, acceleration, threshold and etc).

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *move_settings* | structure contains move settings: speed, acceleration, deceleration etc. |

7.1.4.133 **result_t XIMC_API** set_move_settings_calb ( **device_t** id, const **move_settings_calb_t** * move_settings_calb, const **calibration_t** * calibration )

Set command setup movement which use user units (speed, acceleration, threshold and etc).

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *move_settings_calb* | structure contains move settings: speed, acceleration, deceleration etc. |
| | *calibration* | user unit settings |

7.1.4.134 **result_t XIMC_API** set_nonvolatile_memory ( **device_t** id, const **nonvolatile_memory_t** * nonvolatile_memory )

Write userdata into FRAM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *nonvolatile_memory* | structure contains previously set userdata |

7.1.4.135 **result_t XIMC_API** set_pid_settings ( **device_t** id, const **pid_settings_t** * pid_settings )

Set PID settings.

This function send structure with set of PID factors to controller's memory. These settings specify behaviour of PID routine for positioner. These factors are slightly different for different positioners. All boards are supplied with standard set of PID setting on controller's flash memory. Please use it for loading new PID settings when you change positioner. Please note that wrong PID settings lead to device malfunction.

See Also

get_pid_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *pid_settings* | pid settings |

7.1.4.136 **result_t XIMC_API** set_position ( **device_t** id, const **set_position_t** * the_set_position )

Sets any position value in steps and micro for stepper motor and encoder steps of all engines.

It means, that changing main indicator of position.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *the_set_position* | structure contains move settings: speed, acceleration, deceleration etc. |

7.1.4.137 **result_t XIMC_API** set_position_calb ( **device_t** id, const **set_position_calb_t** * the_set_position_calb, const **calibration_t** * calibration )

Sets any position value and encoder value of all engines which use user units.

It means, that changing main indicator of position.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| out | *the_set_position_calb* | structure contains move settings: speed, acceleration, deceleration etc. |
| | *calibration* | user unit settings |

7.1.4.138 **result_t XIMC_API** set_power_settings ( **device_t** id, const **power_settings_t** * power_settings )

Set settings of step motor power control.

Used with stepper motor only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *power_settings* | structure contains settings of step motor power control |

7.1.4.139 **result_t XIMC_API** set_secure_settings ( **device_t** id, const **secure_settings_t** * secure_settings )

Set protection settings.

Parameters

| | |
|---|---|
| *id* | an identifier of device |
| *secure_settings* | structure with secure data |

See Also

status_t::flags

7.1.4.140 **result_t XIMC_API** set_serial_number ( **device_t** id, const **serial_number_t** * serial_number )

Write device serial number and hardware version to controller's flash memory.

Along with the new serial number and hardware version a "Key" is transmitted. The SN and hardware version are changed and saved when keys match. Can be used by manufacturer only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *serial_number* | structure contains new serial number and secret key. |

7.1.4.141 **result_t XIMC_API** set_stage_information ( **device_t** id, const **stage_information_t** * stage_information )

Set stage information to EEPROM.

Can be used by manufacturer only.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *stage_information* | structure contains stage information |

7.1.4.142 **result_t XIMC_API** set_stage_name ( **device_t** id, const **stage_name_t** * stage_name )

Write user stage name from EEPROM.

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *stage_name* | structure contains previously set user stage name |

7.1.4.143 **result_t XIMC_API** set_stage_settings ( **device_t** id, const **stage_settings_t** * stage_settings )

Set stage settings to EEPROM.

Can be used by manufacturer only

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *stage_settings* | structure contains stage settings |

7.1.4.144 **result_t XIMC_API** set_sync_in_settings ( **device_t** id, const **sync_in_settings_t** * sync_in_settings )

Set input synchronization settings.

This function send structure with set of input synchronization settings, that specify behaviour of input synchronization, to controller's memory. All boards are supplied with standard set of these settings.

See Also

get_sync_in_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *sync_in_settings* | synchronization settings |

7.1.4.145 **result_t XIMC_API** set_sync_in_settings_calb ( **device_t** id, const **sync_in_settings_calb_t** * sync_in_settings_calb, const **calibration_t** * calibration )

Set input synchronization settings which use user units.

This function send structure with set of input synchronization settings, that specify behaviour of input synchronization, to controller's memory. All boards are supplied with standard set of these settings.

See Also

get_sync_in_settings_calb

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *sync_in_settings_calb* | synchronization settings |
| | *calibration* | user unit settings |

7.1.4.146 **result_t XIMC_API** set_sync_out_settings ( **device_t** id, const **sync_out_settings_t** * sync_out_settings )

Set output synchronization settings.

This function send structure with set of output synchronization settings, that specify behaviour of output synchronization, to controller's memory. All boards are supplied with standard set of these settings.

See Also

get_sync_out_settings

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *sync_out_settings* | synchronization settings |

7.1.4.147 **result_t XIMC_API** set_sync_out_settings_calb ( **device_t** id, const **sync_out_settings_calb_t** * sync_out_settings_calb, const **calibration_t** * calibration )

Set output synchronization settings which use user units.

This function send structure with set of output synchronization settings, that specify behaviour of output synchronization, to controller's memory. All boards are supplied with standard set of these settings.

See Also

get_sync_in_settings_calb

Parameters

| | | |
|---|---|---|
| | *id* | an identifier of device |
| in | *sync_out_settings_calb* | synchronization settings |
| | *calibration* | user unit settings |

7.1.4.148 **result_t XIMC_API** set_uart_settings ( **device_t** id, const **uart_settings_t** * uart_settings )

Set UART settings.

This function send structure with UART settings to controller's memory.

See Also

uart_settings_t

Parameters

| | | |
|---|---|---|
| | *Speed* | UART speed |
| in | *uart_settings* | UART settings |

#### 7.1.4.149 result_t XIMC_API write_key ( const char * uri, uint8_t * key )

Write controller key.

Can be used by manufacturer only

Parameters

| | | |
|---|---|---|
| | *uri* | a uri of device |
| in | *key* | protection key. Range: 0..4294967295 |

#### 7.1.4.150 result_t XIMC_API ximc_fix_usbser_sys ( const char * device_uri )

Fix for errors in Windows USB driver stack.

USB subsystem on Windows does not always work correctly. The following bugs are possible: the device cannot be opened at all, or the device can be opened and written to, but it will not respond with data. These errors can be fixed by device reconnection or removal-rescan in device manager. ximc_fix_usbser_sys() is a shortcut function to do the remove-rescan process. You should call this function if libximc library cannot open the device which was not physically removed from the system or if the device does not respond.

#### 7.1.4.151 void XIMC_API ximc_version ( char * version )

Returns a library version.

Parameters

| | |
|---|---|
| *version* | a buffer to hold a version string, 32 bytes is enough |

# Index


A1Voltage
    analog_data_t, 17
A1Voltage_ADC
    analog_data_t, 17
A2Voltage
    analog_data_t, 17
A2Voltage_ADC
    analog_data_t, 17
ACurrent
    analog_data_t, 17
ACurrent_ADC
    analog_data_t, 17
Accel
    move_settings_calb_t, 57
    move_settings_t, 58
accessories_settings_t, 14
    LimitSwitchesSettings, 15
    MBRatedCurrent, 15
    MBRatedVoltage, 15
    MBSettings, 15
    MBTorque, 15
    MagneticBrakeInfo, 15
    TSGrad, 15
    TSMax, 15
    TSMin, 15
    TSSettings, 15
    TemperatureSensorInfo, 15
Accuracy
    sync_out_settings_calb_t, 75
    sync_out_settings_t, 76
analog_data_t, 16
    A1Voltage, 17
    A1Voltage_ADC, 17
    A2Voltage, 17
    A2Voltage_ADC, 17
    ACurrent, 17
    ACurrent_ADC, 17
    B1Voltage, 17
    B1Voltage_ADC, 18
    B2Voltage, 18
    B2Voltage_ADC, 18
    BCurrent, 18
    BCurrent_ADC, 18
    FullCurrent, 18
    FullCurrent_ADC, 18
    H5, 18
    Joy, 18
    Joy_ADC, 18
    L, 18
    L5, 18
    L5_ADC, 19
    Pot, 19
    R, 19
    SupVoltage, 19
    SupVoltage_ADC, 19
    Temp, 19
    Temp_ADC, 19
Antiplay
    engine_settings_calb_t, 36
    engine_settings_t, 38
AntiplaySpeed
    move_settings_calb_t, 57
    move_settings_t, 58

B1Voltage
    analog_data_t, 17
B1Voltage_ADC
    analog_data_t, 18
B2Voltage
    analog_data_t, 18
B2Voltage_ADC
    analog_data_t, 18
BACK_EMF_KM_AUTO
    ximc.h, 101
BCurrent
    analog_data_t, 18
BCurrent_ADC
    analog_data_t, 18
BORDER_IS_ENCODER
    ximc.h, 101
BORDER_STOP_LEFT
    ximc.h, 101
BORDER_STOP_RIGHT
    ximc.h, 101
BRAKE_ENABLED
    ximc.h, 101
BRAKE_ENG_PWROFF
    ximc.h, 101
BackEMFFlags
    emf_settings_t, 32
BorderFlags
    edges_settings_calb_t, 30
    edges_settings_t, 31
brake_settings_t, 19
    BrakeFlags, 20
    t1, 20
    t2, 20
    t3, 20
    t4, 20

BrakeFlags
brake_settings_t, 20

CONTROL_MODE_BITS
ximc.h, 101
CONTROL_MODE_JOY
ximc.h, 101
CONTROL_MODE_LR
ximc.h, 102
CONTROL_MODE_OFF
ximc.h, 102
CSS1_A
calibration_settings_t, 21
CSS1_B
calibration_settings_t, 21
CSS2_A
calibration_settings_t, 21
CSS2_B
calibration_settings_t, 21
CTP_ALARM_ON_ERROR
ximc.h, 102
CTP_BASE
ximc.h, 102
CTP_ENABLED
ximc.h, 102
CTP_ERROR_CORRECTION
ximc.h, 102
CTPFlags
ctp_settings_t, 27
CTPMinError
ctp_settings_t, 27
calibration_settings_t, 20
CSS1_A, 21
CSS1_B, 21
CSS2_A, 21
CSS2_B, 21
FullCurrent_A, 21
FullCurrent_B, 21
calibration_t, 21
chart_data_t, 22
DutyCycle, 22
Joy, 22
Pot, 23
WindingCurrentA, 23
WindingCurrentB, 23
WindingCurrentC, 23
WindingVoltageA, 23
WindingVoltageB, 23
WindingVoltageC, 23
close_device
ximc.h, 116
ClutterTime
sync_in_settings_calb_t, 73
sync_in_settings_t, 74
CmdBufFreeSpace
status_calb_t, 69
status_t, 71
command_clear_fram
ximc.h, 116
command_eeread_settings
ximc.h, 116
command_eesave_settings
ximc.h, 116
command_home
ximc.h, 116
command_homezero
ximc.h, 117
command_left
ximc.h, 117
command_loft
ximc.h, 117
command_move
ximc.h, 117
command_move_calb
ximc.h, 118
command_movr
ximc.h, 118
command_movr_calb
ximc.h, 118
command_power_off
ximc.h, 118
command_read_robust_settings
ximc.h, 119
command_read_settings
ximc.h, 119
command_reset
ximc.h, 119
command_right
ximc.h, 119
command_save_robust_settings
ximc.h, 119
command_save_settings
ximc.h, 120
command_sstp
ximc.h, 120
command_start_measurements
ximc.h, 120
command_stop
ximc.h, 120
command_update_firmware
ximc.h, 120
command_wait_for_stop
ximc.h, 121
command_zero
ximc.h, 121
control_settings_calb_t, 23
Flags, 24
MaxClickTime, 24
MaxSpeed, 24
Timeout, 24
control_settings_t, 24
Flags, 25
MaxClickTime, 25
MaxSpeed, 25
Timeout, 25
uDeltaPosition, 26
uMaxSpeed, 26

controller_name_t, 26
    ControllerName, 26
    CtrlFlags, 26
ControllerName
    controller_name_t, 26
CountsPerTurn
    feedback_settings_t, 41
CriticalIpwr
    secure_settings_t, 62
CriticalIusb
    secure_settings_t, 62
CriticalT
    secure_settings_t, 62
CriticalUpwr
    secure_settings_t, 62
CriticalUusb
    secure_settings_t, 62
ctp_settings_t, 27
    CTPFlags, 27
    CTPMinError, 27
CtrlFlags
    controller_name_t, 26
CurPosition
    status_calb_t, 69
    status_t, 71
CurSpeed
    status_calb_t, 69
    status_t, 71
CurT
    status_calb_t, 69
    status_t, 71
CurrReductDelay
    power_settings_t, 60
CurrentSetTime
    power_settings_t, 60

DRIVER_TYPE_EXTERNAL
    ximc.h, 102
DeadZone
    joystick_settings_t, 51
debug_read_t, 27
    DebugData, 28
debug_write_t, 28
    DebugData, 28
DebugData
    debug_read_t, 28
    debug_write_t, 28
Decel
    move_settings_calb_t, 57
    move_settings_t, 58
DetentTorque
    motor_settings_t, 54
device_information_t, 28
    Major, 29
    Minor, 29
    Release, 29
device_network_information_t, 29
DriverType
    entype_settings_t, 39
DutyCycle
    chart_data_t, 22

EEPROM_PRECEDENCE
    ximc.h, 102
ENC_STATE_ABSENT
    ximc.h, 102
ENC_STATE_MALFUNC
    ximc.h, 102
ENC_STATE_OK
    ximc.h, 103
ENC_STATE_REVERS
    ximc.h, 103
ENC_STATE_UNKNOWN
    ximc.h, 103
ENDER_SW1_ACTIVE_LOW
    ximc.h, 103
ENDER_SW2_ACTIVE_LOW
    ximc.h, 103
ENDER_SWAP
    ximc.h, 103
ENGINE_ACCEL_ON
    ximc.h, 103
ENGINE_ANTIPLAY
    ximc.h, 103
ENGINE_LIMIT_CURR
    ximc.h, 103
ENGINE_LIMIT_RPM
    ximc.h, 103
ENGINE_LIMIT_VOLT
    ximc.h, 104
ENGINE_MAX_SPEED
    ximc.h, 104
ENGINE_REVERSE
    ximc.h, 104
ENGINE_TYPE_2DC
    ximc.h, 104
ENGINE_TYPE_DC
    ximc.h, 104
ENGINE_TYPE_NONE
    ximc.h, 104
ENGINE_TYPE_STEP
    ximc.h, 104
ENGINE_TYPE_TEST
    ximc.h, 104
ENUMERATE_PROBE
    ximc.h, 104
EXTIO_SETUP_INVERT
    ximc.h, 104
EXTIO_SETUP_OUTPUT
    ximc.h, 106
EXTIOModeFlags
    extio_settings_t, 40
EXTIOSetupFlags
    extio_settings_t, 40
edges_settings_calb_t, 30
    BorderFlags, 30
    EnderFlags, 30
    LeftBorder, 30

RightBorder, 30
edges_settings_t, 31
BorderFlags, 31
EnderFlags, 31
LeftBorder, 31
RightBorder, 31
uLeftBorder, 32
uRightBorder, 32
Efficiency
gear_settings_t, 42
emf_settings_t, 32
BackEMFFlags, 32
Km, 32
L, 33
R, 33
EncPosition
get_position_calb_t, 44
get_position_t, 44
set_position_calb_t, 64
set_position_t, 64
status_calb_t, 69
status_t, 71
EncSts
status_calb_t, 69
status_t, 71
encoder_information_t, 33
Manufacturer, 33
PartNumber, 33
encoder_settings_t, 33
EncoderSettings, 34
MaxCurrentConsumption, 34
MaxOperatingFrequency, 34
SupplyVoltageMax, 34
SupplyVoltageMin, 34
EncoderSettings
encoder_settings_t, 34
EnderFlags
edges_settings_calb_t, 30
edges_settings_t, 31
engine_advansed_setup_t, 35
stepcloseloop_Kp_high, 35
stepcloseloop_Kp_low, 35
stepcloseloop_Kw, 35
engine_settings_calb_t, 35
Antiplay, 36
EngineFlags, 36
MicrostepMode, 36
NomCurrent, 36
NomSpeed, 36
NomVoltage, 36
StepsPerRev, 37
engine_settings_t, 37
Antiplay, 38
EngineFlags, 38
MicrostepMode, 38
NomCurrent, 38
NomSpeed, 38
NomVoltage, 38
StepsPerRev, 38
uNomSpeed, 38
EngineFlags
engine_settings_calb_t, 36
engine_settings_t, 38
EngineType
entype_settings_t, 39
entype_settings_t, 38
DriverType, 39
EngineType, 39
enumerate_devices
ximc.h, 121
Error
measurements_t, 52
ExpFactor
joystick_settings_t, 51
extended_settings_t, 39
extio_settings_t, 40
EXTIOModeFlags, 40
EXTIOSetupFlags, 40

FEEDBACK_EMF
ximc.h, 106
FEEDBACK_ENC_REVERSE
ximc.h, 106
FEEDBACK_ENCODER
ximc.h, 106
FEEDBACK_NONE
ximc.h, 106
FastHome
home_settings_calb_t, 48
home_settings_t, 49
feedback_settings_t, 40
CountsPerTurn, 41
FeedbackFlags, 41
FeedbackType, 41
IPS, 41
FeedbackFlags
feedback_settings_t, 41
FeedbackType
feedback_settings_t, 41
Flags
control_settings_calb_t, 24
control_settings_t, 25
secure_settings_t, 62
status_calb_t, 69
status_t, 71
free_enumerate_devices
ximc.h, 121
FullCurrent
analog_data_t, 18
FullCurrent_A
calibration_settings_t, 21
FullCurrent_ADC
analog_data_t, 18
FullCurrent_B
calibration_settings_t, 21

GPIOFlags

status_calb_t, 69
status_t, 72
gear_information_t, 41
Manufacturer, 42
PartNumber, 42
gear_settings_t, 42
Efficiency, 42
InputInertia, 42
MaxOutputBacklash, 43
RatedInputSpeed, 43
RatedInputTorque, 43
ReductionIn, 43
ReductionOut, 43
get_accessories_settings
ximc.h, 122
get_analog_data
ximc.h, 122
get_bootloader_version
ximc.h, 122
get_brake_settings
ximc.h, 122
get_calibration_settings
ximc.h, 122
get_chart_data
ximc.h, 123
get_control_settings
ximc.h, 123
get_control_settings_calb
ximc.h, 123
get_controller_name
ximc.h, 124
get_ctp_settings
ximc.h, 124
get_debug_read
ximc.h, 124
get_device_count
ximc.h, 124
get_device_information
ximc.h, 125
get_device_name
ximc.h, 125
get_edges_settings
ximc.h, 125
get_edges_settings_calb
ximc.h, 125
get_emf_settings
ximc.h, 126
get_encoder_information
ximc.h, 126
get_encoder_settings
ximc.h, 126
get_engine_advansed_setup
ximc.h, 126
get_engine_settings
ximc.h, 127
get_engine_settings_calb
ximc.h, 127
get_entype_settings
ximc.h, 127
get_enumerate_device_controller_name
ximc.h, 128
get_enumerate_device_information
ximc.h, 128
get_enumerate_device_network_information
ximc.h, 128
get_enumerate_device_serial
ximc.h, 128
get_enumerate_device_stage_name
ximc.h, 129
get_extended_settings
ximc.h, 129
get_extio_settings
ximc.h, 129
get_feedback_settings
ximc.h, 129
get_firmware_version
ximc.h, 130
get_gear_information
ximc.h, 130
get_gear_settings
ximc.h, 130
get_globally_unique_identifier
ximc.h, 130
get_hallsensor_information
ximc.h, 131
get_hallsensor_settings
ximc.h, 131
get_home_settings
ximc.h, 131
get_home_settings_calb
ximc.h, 131
get_init_random
ximc.h, 131
get_joystick_settings
ximc.h, 132
get_measurements
ximc.h, 132
get_motor_information
ximc.h, 132
get_motor_settings
ximc.h, 132
get_move_settings
ximc.h, 133
get_move_settings_calb
ximc.h, 133
get_nonvolatile_memory
ximc.h, 133
get_pid_settings
ximc.h, 133
get_position
ximc.h, 134
get_position_calb
ximc.h, 134
get_position_calb_t, 43
EncPosition, 44
Position, 44

get_position_t, 44
EncPosition, 44
uPosition, 44
get_power_settings
ximc.h, 134
get_secure_settings
ximc.h, 134
get_serial_number
ximc.h, 134
get_stage_information
ximc.h, 135
get_stage_name
ximc.h, 135
get_stage_settings
ximc.h, 135
get_status
ximc.h, 135
get_status_calb
ximc.h, 135
get_sync_in_settings
ximc.h, 136
get_sync_in_settings_calb
ximc.h, 136
get_sync_out_settings
ximc.h, 136
get_sync_out_settings_calb
ximc.h, 137
get_uart_settings
ximc.h, 137
globally_unique_identifier_t, 45
UniqueID0, 45
UniqueID1, 45
UniqueID2, 45
UniqueID3, 45
goto_firmware
ximc.h, 137

H5
analog_data_t, 18
H_BRIDGE_ALERT
ximc.h, 106
HOME_DIR_FIRST
ximc.h, 107
HOME_DIR_SECOND
ximc.h, 107
HOME_HALF_MV
ximc.h, 107
HOME_MV_SEC_EN
ximc.h, 107
HOME_STOP_FIRST_LIM
ximc.h, 107
HOME_STOP_FIRST_REV
ximc.h, 107
HOME_STOP_FIRST_SYN
ximc.h, 107
HOME_USE_FAST
ximc.h, 108
hallsensor_information_t, 45
Manufacturer, 46
PartNumber, 46
hallsensor_settings_t, 46
MaxCurrentConsumption, 47
MaxOperatingFrequency, 47
SupplyVoltageMax, 47
SupplyVoltageMin, 47
has_firmware
ximc.h, 138
HoldCurrent
power_settings_t, 61
home_settings_calb_t, 47
FastHome, 48
HomeDelta, 48
HomeFlags, 48
SlowHome, 48
home_settings_t, 48
FastHome, 49
HomeDelta, 49
HomeFlags, 49
SlowHome, 49
uFastHome, 49
uHomeDelta, 49
uSlowHome, 49
HomeDelta
home_settings_calb_t, 48
home_settings_t, 49
HomeFlags
home_settings_calb_t, 48
home_settings_t, 49
HorizontalLoadCapacity
stage_settings_t, 67

IPS
feedback_settings_t, 41
init_random_t, 49
key, 50
InputInertia
gear_settings_t, 42
Ipwr
status_calb_t, 69
status_t, 72
Iusb
status_calb_t, 69
status_t, 72

JOY_REVERSE
ximc.h, 108
Joy
analog_data_t, 18
chart_data_t, 22
Joy_ADC
analog_data_t, 18
JoyCenter
joystick_settings_t, 51
JoyFlags
joystick_settings_t, 51
JoyHighEnd
joystick_settings_t, 51
JoyLowEnd

joystick_settings_t, 51
joystick_settings_t, 50
DeadZone, 51
ExpFactor, 51
JoyCenter, 51
JoyFlags, 51
JoyHighEnd, 51
JoyLowEnd, 51

Key
serial_number_t, 63
key
init_random_t, 50
Km
emf_settings_t, 32

L
analog_data_t, 18
emf_settings_t, 33
L5
analog_data_t, 18
L5_ADC
analog_data_t, 19
LOW_UPWR_PROTECTION
ximc.h, 108
LeadScrewPitch
stage_settings_t, 67
LeftBorder
edges_settings_calb_t, 30
edges_settings_t, 31
Length
measurements_t, 52
LimitSwitchesSettings
accessories_settings_t, 15
load_correction_table
ximc.h, 138
logging_callback_stderr_narrow
ximc.h, 138
logging_callback_stderr_wide
ximc.h, 139
logging_callback_t
ximc.h, 115
LowUpwrOff
secure_settings_t, 62

MBRatedCurrent
accessories_settings_t, 15
MBRatedVoltage
accessories_settings_t, 15
MBSettings
accessories_settings_t, 15
MBTorque
accessories_settings_t, 15
MICROSTEP_MODE_FULL
ximc.h, 108
MOVE_STATE_ANTIPLAY
ximc.h, 109
MOVE_STATE_MOVING
ximc.h, 109
MVCMD_ERROR
ximc.h, 109
MVCMD_HOME
ximc.h, 109
MVCMD_LEFT
ximc.h, 109
MVCMD_LOFT
ximc.h, 109
MVCMD_MOVE
ximc.h, 109
MVCMD_MOVR
ximc.h, 109
MVCMD_NAME_BITS
ximc.h, 109
MVCMD_RIGHT
ximc.h, 109
MVCMD_RUNNING
ximc.h, 110
MVCMD_SSTP
ximc.h, 110
MVCMD_STOP
ximc.h, 110
MVCMD_UKNWN
ximc.h, 110
MagneticBrakeInfo
accessories_settings_t, 15
Major
device_information_t, 29
serial_number_t, 63
Manufacturer
encoder_information_t, 33
gear_information_t, 42
hallsensor_information_t, 46
motor_information_t, 52
stage_information_t, 65
MaxClickTime
control_settings_calb_t, 24
control_settings_t, 25
MaxCurrent
motor_settings_t, 54
MaxCurrentConsumption
encoder_settings_t, 34
hallsensor_settings_t, 47
stage_settings_t, 67
MaxCurrentTime
motor_settings_t, 54
MaxOperatingFrequency
encoder_settings_t, 34
hallsensor_settings_t, 47
MaxOutputBacklash
gear_settings_t, 43
MaxSpeed
control_settings_calb_t, 24
control_settings_t, 25
motor_settings_t, 54
stage_settings_t, 67
measurements_t, 51
Error, 52

Length, 52
Speed, 52
MechanicalTimeConstant
motor_settings_t, 54
MicrostepMode
engine_settings_calb_t, 36
engine_settings_t, 38
MinimumUusb
secure_settings_t, 62
Minor
device_information_t, 29
serial_number_t, 63
motor_information_t, 52
Manufacturer, 52
PartNumber, 52
motor_settings_t, 53
DetentTorque, 54
MaxCurrent, 54
MaxCurrentTime, 54
MaxSpeed, 54
MechanicalTimeConstant, 54
MotorType, 54
NoLoadCurrent, 55
NoLoadSpeed, 55
NominalCurrent, 55
NominalPower, 55
NominalSpeed, 55
NominalTorque, 55
NominalVoltage, 55
Phases, 55
Poles, 55
RotorInertia, 55
SpeedConstant, 56
SpeedTorqueGradient, 56
StallTorque, 56
TorqueConstant, 56
WindingInductance, 56
WindingResistance, 56
MotorType
motor_settings_t, 54
move_settings_calb_t, 56
Accel, 57
AntiplaySpeed, 57
Decel, 57
MoveFlags, 57
Speed, 57
move_settings_t, 57
Accel, 58
AntiplaySpeed, 58
Decel, 58
MoveFlags, 58
Speed, 58
uAntiplaySpeed, 58
uSpeed, 59
MoveFlags
move_settings_calb_t, 57
move_settings_t, 58
MoveSts
status_calb_t, 69
status_t, 72
msec_sleep
ximc.h, 139
MvCmdSts
status_calb_t, 69
status_t, 72

NoLoadCurrent
motor_settings_t, 55
NoLoadSpeed
motor_settings_t, 55
NomCurrent
engine_settings_calb_t, 36
engine_settings_t, 38
NomSpeed
engine_settings_calb_t, 36
engine_settings_t, 38
NomVoltage
engine_settings_calb_t, 36
engine_settings_t, 38
NominalCurrent
motor_settings_t, 55
NominalPower
motor_settings_t, 55
NominalSpeed
motor_settings_t, 55
NominalTorque
motor_settings_t, 55
NominalVoltage
motor_settings_t, 55
nonvolatile_memory_t, 59
UserData, 59

open_device
ximc.h, 139

POWER_OFF_ENABLED
ximc.h, 110
POWER_REDUCT_ENABLED
ximc.h, 110
POWER_SMOOTH_CURRENT
ximc.h, 110
PWR_STATE_MAX
ximc.h, 110
PWR_STATE_NORM
ximc.h, 110
PWR_STATE_OFF
ximc.h, 110
PWR_STATE_REDUCT
ximc.h, 110
PWR_STATE_UNKNOWN
ximc.h, 110
PWRSts
status_calb_t, 70
status_t, 72
PartNumber
encoder_information_t, 33
gear_information_t, 42

hallsensor_information_t, 46
motor_information_t, 52
stage_information_t, 65
Phases
motor_settings_t, 55
pid_settings_t, 59
Poles
motor_settings_t, 55
PosFlags
set_position_calb_t, 64
set_position_t, 64
Position
get_position_calb_t, 44
set_position_calb_t, 64
sync_in_settings_calb_t, 73
PositionerName
stage_name_t, 66
Pot
analog_data_t, 19
chart_data_t, 23
power_settings_t, 60
CurrReductDelay, 60
CurrentSetTime, 60
HoldCurrent, 61
PowerFlags, 61
PowerOffDelay, 61
PowerFlags
power_settings_t, 61
PowerOffDelay
power_settings_t, 61
probe_device
ximc.h, 139

R
analog_data_t, 19
emf_settings_t, 33
REV_SENS_INV
ximc.h, 111
RPM_DIV_1000
ximc.h, 111
RatedInputSpeed
gear_settings_t, 43
RatedInputTorque
gear_settings_t, 43
ReductionIn
gear_settings_t, 43
ReductionOut
gear_settings_t, 43
Release
device_information_t, 29
serial_number_t, 63
RightBorder
edges_settings_calb_t, 30
edges_settings_t, 31
RotorInertia
motor_settings_t, 55

SN
serial_number_t, 63
STATE_ALARM
ximc.h, 111
STATE_BRAKE
ximc.h, 111
STATE_BUTTON_LEFT
ximc.h, 111
STATE_BUTTON_RIGHT
ximc.h, 111
STATE_CONTR
ximc.h, 111
STATE_CTP_ERROR
ximc.h, 112
STATE_DIG_SIGNAL
ximc.h, 112
STATE_ENC_A
ximc.h, 112
STATE_ENC_B
ximc.h, 112
STATE_ERRC
ximc.h, 112
STATE_ERRD
ximc.h, 112
STATE_ERRV
ximc.h, 112
STATE_EXTIO_ALARM
ximc.h, 112
STATE_GPIO_LEVEL
ximc.h, 112
STATE_GPIO_PINOUT
ximc.h, 112
STATE_LEFT_EDGE
ximc.h, 113
STATE_POWER_OVERHEAT
ximc.h, 113
STATE_REV_SENSOR
ximc.h, 113
STATE_RIGHT_EDGE
ximc.h, 113
STATE_SECUR
ximc.h, 113
STATE_SYNC_INPUT
ximc.h, 113
STATE_SYNC_OUTPUT
ximc.h, 113
SYNCIN_ENABLED
ximc.h, 114
SYNCIN_GOTOPOSITION
ximc.h, 114
SYNCIN_INVERT
ximc.h, 114
SYNCOUT_ENABLED
ximc.h, 114
SYNCOUT_IN_STEPS
ximc.h, 114
SYNCOUT_INVERT
ximc.h, 114
SYNCOUT_ONPERIOD
ximc.h, 114

SYNCOUT_ONSTART
ximc.h, 114
SYNCOUT_ONSTOP
ximc.h, 114
SYNCOUT_STATE
ximc.h, 114
secure_settings_t, 61
CriticalIpwr, 62
CriticalIusb, 62
CriticalT, 62
CriticalUpwr, 62
CriticalUusb, 62
Flags, 62
LowUpwrOff, 62
MinimumUusb, 62
serial_number_t, 62
Key, 63
Major, 63
Minor, 63
Release, 63
SN, 63
service_command_updf
ximc.h, 139
set_accessories_settings
ximc.h, 140
set_bindy_key
ximc.h, 140
set_brake_settings
ximc.h, 140
set_calibration_settings
ximc.h, 140
set_control_settings
ximc.h, 140
set_control_settings_calb
ximc.h, 141
set_controller_name
ximc.h, 141
set_correction_table
ximc.h, 141
set_ctp_settings
ximc.h, 142
set_debug_write
ximc.h, 142
set_edges_settings
ximc.h, 142
set_edges_settings_calb
ximc.h, 143
set_emf_settings
ximc.h, 143
set_encoder_information
ximc.h, 143
set_encoder_settings
ximc.h, 143
set_engine_advansed_setup
ximc.h, 144
set_engine_settings
ximc.h, 144
set_engine_settings_calb
ximc.h, 144
set_entype_settings
ximc.h, 145
set_extended_settings
ximc.h, 145
set_extio_settings
ximc.h, 145
set_feedback_settings
ximc.h, 145
set_gear_information
ximc.h, 146
set_gear_settings
ximc.h, 146
set_hallsensor_information
ximc.h, 146
set_hallsensor_settings
ximc.h, 146
set_home_settings
ximc.h, 147
set_home_settings_calb
ximc.h, 147
set_joystick_settings
ximc.h, 147
set_logging_callback
ximc.h, 148
set_motor_information
ximc.h, 148
set_motor_settings
ximc.h, 148
set_move_settings
ximc.h, 148
set_move_settings_calb
ximc.h, 148
set_nonvolatile_memory
ximc.h, 149
set_pid_settings
ximc.h, 149
set_position
ximc.h, 149
set_position_calb
ximc.h, 149
set_position_calb_t, 63
EncPosition, 64
PosFlags, 64
Position, 64
set_position_t, 64
EncPosition, 64
PosFlags, 64
uPosition, 64
set_power_settings
ximc.h, 150
set_secure_settings
ximc.h, 150
set_serial_number
ximc.h, 150
set_stage_information
ximc.h, 150
set_stage_name

ximc.h, 151
set_stage_settings
ximc.h, 151
set_sync_in_settings
ximc.h, 151
set_sync_in_settings_calb
ximc.h, 151
set_sync_out_settings
ximc.h, 152
set_sync_out_settings_calb
ximc.h, 152
set_uart_settings
ximc.h, 152
SlowHome
home_settings_calb_t, 48
home_settings_t, 49
Speed
measurements_t, 52
move_settings_calb_t, 57
move_settings_t, 58
sync_in_settings_calb_t, 73
sync_in_settings_t, 74
SpeedConstant
motor_settings_t, 56
SpeedTorqueGradient
motor_settings_t, 56
stage_information_t, 65
Manufacturer, 65
PartNumber, 65
stage_name_t, 65
PositionerName, 66
stage_settings_t, 66
HorizontalLoadCapacity, 67
LeadScrewPitch, 67
MaxCurrentConsumption, 67
MaxSpeed, 67
SupplyVoltageMax, 67
SupplyVoltageMin, 67
TravelRange, 67
Units, 67
VerticalLoadCapacity, 67
StallTorque
motor_settings_t, 56
status_calb_t, 68
CmdBufFreeSpace, 69
CurPosition, 69
CurSpeed, 69
CurT, 69
EncPosition, 69
EncSts, 69
Flags, 69
GPIOFlags, 69
Ipwr, 69
Iusb, 69
MoveSts, 69
MvCmdSts, 69
PWRSts, 70
Upwr, 70
Uusb, 70
WindSts, 70
status_t, 70
CmdBufFreeSpace, 71
CurPosition, 71
CurSpeed, 71
CurT, 71
EncPosition, 71
EncSts, 71
Flags, 71
GPIOFlags, 72
Ipwr, 72
Iusb, 72
MoveSts, 72
MvCmdSts, 72
PWRSts, 72
uCurPosition, 72
uCurSpeed, 72
Upwr, 72
Uusb, 72
WindSts, 72
stepcloseloop_Kp_high
engine_advansed_setup_t, 35
stepcloseloop_Kp_low
engine_advansed_setup_t, 35
stepcloseloop_Kw
engine_advansed_setup_t, 35
StepsPerRev
engine_settings_calb_t, 37
engine_settings_t, 38
SupVoltage
analog_data_t, 19
SupVoltage_ADC
analog_data_t, 19
SupplyVoltageMax
encoder_settings_t, 34
hallsensor_settings_t, 47
stage_settings_t, 67
SupplyVoltageMin
encoder_settings_t, 34
hallsensor_settings_t, 47
stage_settings_t, 67
sync_in_settings_calb_t, 73
ClutterTime, 73
Position, 73
Speed, 73
SyncInFlags, 73
sync_in_settings_t, 74
ClutterTime, 74
Speed, 74
SyncInFlags, 74
uPosition, 74
uSpeed, 74
sync_out_settings_calb_t, 75
Accuracy, 75
SyncOutFlags, 75
SyncOutPeriod, 75
SyncOutPulseSteps, 75

sync_out_settings_t, 76
Accuracy, 76
SyncOutFlags, 76
SyncOutPeriod, 76
SyncOutPulseSteps, 76
uAccuracy, 77
SyncInFlags
sync_in_settings_calb_t, 73
sync_in_settings_t, 74
SyncOutFlags
sync_out_settings_calb_t, 75
sync_out_settings_t, 76
SyncOutPeriod
sync_out_settings_calb_t, 75
sync_out_settings_t, 76
SyncOutPulseSteps
sync_out_settings_calb_t, 75
sync_out_settings_t, 76

t1
brake_settings_t, 20
t2
brake_settings_t, 20
t3
brake_settings_t, 20
t4
brake_settings_t, 20
TSGrad
accessories_settings_t, 15
TSMax
accessories_settings_t, 15
TSMin
accessories_settings_t, 15
TSSettings
accessories_settings_t, 15
Temp
analog_data_t, 19
Temp_ADC
analog_data_t, 19
TemperatureSensorInfo
accessories_settings_t, 15
Timeout
control_settings_calb_t, 24
control_settings_t, 25
TorqueConstant
motor_settings_t, 56
TravelRange
stage_settings_t, 67

UART_PARITY_BITS
ximc.h, 114
UARTSetupFlags
uart_settings_t, 77
uAccuracy
sync_out_settings_t, 77
uAntiplaySpeed
move_settings_t, 58
uCurPosition
status_t, 72
uCurSpeed
status_t, 72
uDeltaPosition
control_settings_t, 26
uFastHome
home_settings_t, 49
uHomeDelta
home_settings_t, 49
uLeftBorder
edges_settings_t, 32
uMaxSpeed
control_settings_t, 26
uNomSpeed
engine_settings_t, 38
uPosition
get_position_t, 44
set_position_t, 64
sync_in_settings_t, 74
uRightBorder
edges_settings_t, 32
uSlowHome
home_settings_t, 49
uSpeed
move_settings_t, 59
sync_in_settings_t, 74
uart_settings_t, 77
UARTSetupFlags, 77
UniqueID0
globally_unique_identifier_t, 45
UniqueID1
globally_unique_identifier_t, 45
UniqueID2
globally_unique_identifier_t, 45
UniqueID3
globally_unique_identifier_t, 45
Units
stage_settings_t, 67
Upwr
status_calb_t, 70
status_t, 72
UserData
nonvolatile_memory_t, 59
Uusb
status_calb_t, 70
status_t, 72

VerticalLoadCapacity
stage_settings_t, 67

WIND_A_STATE_ABSENT
ximc.h, 114
WIND_A_STATE_OK
ximc.h, 115
WIND_B_STATE_ABSENT
ximc.h, 115
WIND_B_STATE_OK
ximc.h, 115
WindSts
status_calb_t, 70

status_t, 72
WindingCurrentA
chart_data_t, 23
WindingCurrentB
chart_data_t, 23
WindingCurrentC
chart_data_t, 23
WindingInductance
motor_settings_t, 56
WindingResistance
motor_settings_t, 56
WindingVoltageA
chart_data_t, 23
WindingVoltageB
chart_data_t, 23
WindingVoltageC
chart_data_t, 23
write_key
ximc.h, 153

XIMC_API
ximc.h, 115
ximc.h, 78
BACK_EMF_KM_AUTO, 101
BORDER_IS_ENCODER, 101
BORDER_STOP_LEFT, 101
BORDER_STOP_RIGHT, 101
BRAKE_ENABLED, 101
BRAKE_ENG_PWROFF, 101
CONTROL_MODE_BITS, 101
CONTROL_MODE_JOY, 101
CONTROL_MODE_LR, 102
CONTROL_MODE_OFF, 102
CTP_ALARM_ON_ERROR, 102
CTP_BASE, 102
CTP_ENABLED, 102
close_device, 116
command_clear_fram, 116
command_eeread_settings, 116
command_eesave_settings, 116
command_home, 116
command_homezero, 117
command_left, 117
command_loft, 117
command_move, 117
command_move_calb, 118
command_movr, 118
command_movr_calb, 118
command_power_off, 118
command_read_robust_settings, 119
command_read_settings, 119
command_reset, 119
command_right, 119
command_save_robust_settings, 119
command_save_settings, 120
command_sstp, 120
command_start_measurements, 120
command_stop, 120
command_update_firmware, 120
command_wait_for_stop, 121
command_zero, 121
EEPROM_PRECEDENCE, 102
ENC_STATE_ABSENT, 102
ENC_STATE_MALFUNC, 102
ENC_STATE_OK, 103
ENC_STATE_REVERS, 103
ENC_STATE_UNKNOWN, 103
ENDER_SWAP, 103
ENGINE_ACCEL_ON, 103
ENGINE_ANTIPLAY, 103
ENGINE_LIMIT_CURR, 103
ENGINE_LIMIT_RPM, 103
ENGINE_LIMIT_VOLT, 104
ENGINE_MAX_SPEED, 104
ENGINE_REVERSE, 104
ENGINE_TYPE_2DC, 104
ENGINE_TYPE_DC, 104
ENGINE_TYPE_NONE, 104
ENGINE_TYPE_STEP, 104
ENGINE_TYPE_TEST, 104
ENUMERATE_PROBE, 104
EXTIO_SETUP_INVERT, 104
EXTIO_SETUP_OUTPUT, 106
enumerate_devices, 121
FEEDBACK_EMF, 106
FEEDBACK_ENCODER, 106
FEEDBACK_NONE, 106
free_enumerate_devices, 121
get_accessories_settings, 122
get_analog_data, 122
get_bootloader_version, 122
get_brake_settings, 122
get_calibration_settings, 122
get_chart_data, 123
get_control_settings, 123
get_control_settings_calb, 123
get_controller_name, 124
get_ctp_settings, 124
get_debug_read, 124
get_device_count, 124
get_device_information, 125
get_device_name, 125
get_edges_settings, 125
get_edges_settings_calb, 125
get_emf_settings, 126
get_encoder_information, 126
get_encoder_settings, 126
get_engine_advansed_setup, 126
get_engine_settings, 127
get_engine_settings_calb, 127
get_entype_settings, 127
get_enumerate_device_controller_name, 128
get_enumerate_device_information, 128
get_enumerate_device_network_information, 128
get_enumerate_device_serial, 128
get_enumerate_device_stage_name, 129
get_extended_settings, 129

get_extio_settings, 129
get_feedback_settings, 129
get_firmware_version, 130
get_gear_information, 130
get_gear_settings, 130
get_globally_unique_identifier, 130
get_hallsensor_information, 131
get_hallsensor_settings, 131
get_home_settings, 131
get_home_settings_calb, 131
get_init_random, 131
get_joystick_settings, 132
get_measurements, 132
get_motor_information, 132
get_motor_settings, 132
get_move_settings, 133
get_move_settings_calb, 133
get_nonvolatile_memory, 133
get_pid_settings, 133
get_position, 134
get_position_calb, 134
get_power_settings, 134
get_secure_settings, 134
get_serial_number, 134
get_stage_information, 135
get_stage_name, 135
get_stage_settings, 135
get_status, 135
get_status_calb, 135
get_sync_in_settings, 136
get_sync_in_settings_calb, 136
get_sync_out_settings, 136
get_sync_out_settings_calb, 137
get_uart_settings, 137
goto_firmware, 137
H_BRIDGE_ALERT, 106
HOME_DIR_FIRST, 107
HOME_DIR_SECOND, 107
HOME_HALF_MV, 107
HOME_MV_SEC_EN, 107
HOME_USE_FAST, 108
has_firmware, 138
JOY_REVERSE, 108
LOW_UPWR_PROTECTION, 108
load_correction_table, 138
logging_callback_stderr_narrow, 138
logging_callback_stderr_wide, 139
logging_callback_t, 115
MICROSTEP_MODE_FULL, 108
MOVE_STATE_ANTIPLAY, 109
MOVE_STATE_MOVING, 109
MVCMD_ERROR, 109
MVCMD_HOME, 109
MVCMD_LEFT, 109
MVCMD_LOFT, 109
MVCMD_MOVE, 109
MVCMD_MOVR, 109
MVCMD_NAME_BITS, 109
MVCMD_RIGHT, 109
MVCMD_RUNNING, 110
MVCMD_SSTP, 110
MVCMD_STOP, 110
MVCMD_UKNWN, 110
msec_sleep, 139
open_device, 139
POWER_OFF_ENABLED, 110
PWR_STATE_MAX, 110
PWR_STATE_NORM, 110
PWR_STATE_OFF, 110
PWR_STATE_REDUCT, 110
PWR_STATE_UNKNOWN, 110
probe_device, 139
REV_SENS_INV, 111
RPM_DIV_1000, 111
STATE_ALARM, 111
STATE_BRAKE, 111
STATE_BUTTON_LEFT, 111
STATE_BUTTON_RIGHT, 111
STATE_CONTR, 111
STATE_CTP_ERROR, 112
STATE_DIG_SIGNAL, 112
STATE_ENC_A, 112
STATE_ENC_B, 112
STATE_ERRC, 112
STATE_ERRD, 112
STATE_ERRV, 112
STATE_EXTIO_ALARM, 112
STATE_GPIO_LEVEL, 112
STATE_GPIO_PINOUT, 112
STATE_LEFT_EDGE, 113
STATE_REV_SENSOR, 113
STATE_RIGHT_EDGE, 113
STATE_SECUR, 113
STATE_SYNC_INPUT, 113
STATE_SYNC_OUTPUT, 113
SYNCIN_ENABLED, 114
SYNCIN_GOTOPOSITION, 114
SYNCIN_INVERT, 114
SYNCOUT_ENABLED, 114
SYNCOUT_IN_STEPS, 114
SYNCOUT_INVERT, 114
SYNCOUT_ONPERIOD, 114
SYNCOUT_ONSTART, 114
SYNCOUT_ONSTOP, 114
SYNCOUT_STATE, 114
service_command_updf, 139
set_accessories_settings, 140
set_bindy_key, 140
set_brake_settings, 140
set_calibration_settings, 140
set_control_settings, 140
set_control_settings_calb, 141
set_controller_name, 141
set_correction_table, 141
set_ctp_settings, 142
set_debug_write, 142

set_edges_settings, 142
set_edges_settings_calb, 143
set_emf_settings, 143
set_encoder_information, 143
set_encoder_settings, 143
set_engine_advansed_setup, 144
set_engine_settings, 144
set_engine_settings_calb, 144
set_entype_settings, 145
set_extended_settings, 145
set_extio_settings, 145
set_feedback_settings, 145
set_gear_information, 146
set_gear_settings, 146
set_hallsensor_information, 146
set_hallsensor_settings, 146
set_home_settings, 147
set_home_settings_calb, 147
set_joystick_settings, 147
set_logging_callback, 148
set_motor_information, 148
set_motor_settings, 148
set_move_settings, 148
set_move_settings_calb, 148
set_nonvolatile_memory, 149
set_pid_settings, 149
set_position, 149
set_position_calb, 149
set_power_settings, 150
set_secure_settings, 150
set_serial_number, 150
set_stage_information, 150
set_stage_name, 151
set_stage_settings, 151
set_sync_in_settings, 151
set_sync_in_settings_calb, 151
set_sync_out_settings, 152
set_sync_out_settings_calb, 152
set_uart_settings, 152
UART_PARITY_BITS, 114
WIND_A_STATE_OK, 115
WIND_B_STATE_OK, 115
write_key, 153
XIMC_API, 115
ximc_fix_usbser_sys, 153
ximc_version, 153
ximc_fix_usbser_sys
ximc.h, 153
ximc_version
ximc.h, 153