

libximc
2.3.2

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Chapter 1

Introduction

1.1 About

Congratulations on choosing XIMC multi-platform programming library! This document contains all information about XIMC 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. XIMC multi-platform programming library supports plug/unplug on the fly. One program can control one device. Multiple processes (programs) that control one device simultaneously are not allowed.

1.2 System requirements

1.2.1 For rebuilding library

On Windows:

- Windows 2000 or later, 64-bit system (if compiling both architectures) or 32-bit system.
- Microsoft Visual C++ 2008 or later
- cygwin with tar, bison, flex installed

On Linux or FreeBSD:

- 64-bit or/and 32-bit system
- gcc 4 or later
- common autotools: autoconf, autoheader, aclocal, automake, autoreconf, libtool
- gmake
- doxygen - for building docs
- LaTeX distribution (TeX 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=
```

1.2.2 For using library

Supported operating systems (32 or 64 bit):

- Mac OS X 10.6
- Windows 2000 or later
- Autotools-compatible unix. Package is installed from sources.
- Linux debian-based. DEB package is built against Debian Squeeze 6
- Linux rpm-based. RPM is built against OpenSUSE 10
- FreeBSD 9. Package is provided.

Build requirements:

- Windows: Microsoft Visual C++ 2008 or mingw (currently not supported)
- UNIX: gcc 4, gmake
- Mac OS X: XCode 4

Chapter 2

How to rebuild library

2.1 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.

2.2 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

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.

To build library and package Invoke a script:

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

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

2.3 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

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 `./dist/latest/rpm` and locally installed binaries from `./dist/local`.

2.4 Building on FreeBSD

Requirement: 64-bit or 32-bit FreeBSD Typical set of packages: gcc, autotools, autoconf, libtool, flex, bison, doxygen, teTeX, mercurial

It's required to match library and host architecture. Also you need to fix a configure.ac to exclude SOVER from the package name (freebsd does not use linux conventions on library versioning).

Attention! It's needed to specify additional parameters for a simple build.

```
$ ./build.sh lib LEX=/usr/local/bin/flex CXXFLAGS=-I/usr/local/include/flex
```

To build a library and package invoke following command. It requires sudo privileges for port installing and specially crafted /usr/ports/local tree. Consult a script for details.

```
$ ./build.sh libfreebsd
```

Grab packages from ./dist/latest/freebsd.

2.5 Building 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 ./dist/latest/mac-osx, locally installed binaries from ./dist/local.

2.6 Building 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 ./dist/latest/win32 and ./dist/latest/win64

2.7 Source code access

XIMC source codes are given under special request.

Chapter 3

How to use with...

Library usage can be examined 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/testcs', VB.NET - 'examples/testvbnet', Delphi 6 - 'examples/testdelphi', sample bindings for MATLAB - 'examples/testmatlab'

3.1 Usage with C

3.1.1 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.

NOTE: Example compiled with (MS Visual C++ 2008 SP1 and needs package 9.0.307291 (provided with SDK - vc_redist.x86 or vc_redist.x64)

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

3.1.2 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.

3.1.3 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 -DWINDOWS  
testapp.c libximc.lib
```

3.1.4 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.

3.1.5 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 plain dylib library and a framework is provided.

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

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.

3.2 .NET

Wrapper assembly for libximc.dll is wrappers/csharp/ximcnet.dll. It is provided with two different architectures and depends on .NET 2.0.

Test .NET applications for Visual Studio 2008 is located at testcs (for C#) and testvbnet (for VB.NET) respectively. Open solutions, build and run.

3.3 Delphi

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

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

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

3.4 MATLAB

Sample MATLAB program testximc.m is provided at the directory examples/testmatlab. Fix first lines with the actual location of the XIMC library and launch M-file as:

```
$ testximc
```

Chapter 4

Data Structure Documentation

4.1 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.

4.1.1 Detailed Description

Additional accessories information.

See also

[set_accessories_settings](#)
[get_accessories_settings](#)
[get_accessories_settings](#), [set_accessories_settings](#)

4.1.2 Field Documentation

4.1.2.1 float MBRatedCurrent

Rated current for controlling the magnetic brake (A).

Data type: float.

4.1.2.2 float MBRatedVoltage

Rated voltage for controlling the magnetic brake (B).

Data type: float.

4.1.2.3 float MBTorque

Retention moment (mN m).

Data type: float.

4.1.2.4 float TSGrad

The temperature gradient (V/degrees Celsius).

Data type: float.

4.2 `add_sync_in_action_calb_t` Struct Reference

Data Fields

- float [Position](#)
Desired position or shift.
- float [Speed](#)
Target speed.

4.3 `add_sync_in_action_t` Struct Reference

This command adds one element of the FIFO commands.

Data Fields

- int [Position](#)
Desired position or shift (whole steps)
- int [uPosition](#)
The fractional part of a position or shift in microsteps (-255 .
- unsigned int [Speed](#)
Target speed(for stepper motor: steps / c, for DC: rpm).
- unsigned int [uSpeed](#)
Target speed in microsteps/s.

4.3.1 Detailed Description

This command adds one element of the FIFO commands.

See also

[set_add_sync_in_action](#)

4.3.2 Field Documentation

4.3.2.1 unsigned int Speed

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

Range: 0..1000000.

4.3.2.2 int uPosition

The fractional part of a position or shift in microsteps (-255 . . 255)(is only used with stepper motor)

4.3.2.3 unsigned int uSpeed

Target speed in microsteps/s.

Using with stepper motor only. Range: 0..255.

4.4 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 "Potentiometer", 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.
- int [A2Voltage](#)
"Voltage on pin 2 winding A" calibrated data.
- int [B1Voltage](#)
"Voltage on pin 1 winding B" calibrated data.
- int [B2Voltage](#)
"Voltage on pin 2 winding B" calibrated data.
- int [SupVoltage](#)
"Voltage on the top of MOSFET full bridge" calibrated data.
- int [ACurrent](#)
"Winding A current" calibrated data.
- int [BCurrent](#)
"Winding B current" calibrated data.
- int [FullCurrent](#)
"Full current" calibrated data.
- int [Temp](#)
Temperature, calibrated data.
- int [Joy](#)
Joystick, calibrated data.
- int [Pot](#)
Potentiometer, calibrated data.
- int [L5](#)
USB supply voltage after the current sense resistor.
- int [H5](#)
Power supply USB.
- 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).

4.4.1 Detailed Description

Analog data.

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

See also

[get_analog_data](#)
[get_analog_data](#)

4.5 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.

4.5.1 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](#)

4.5.2 Field Documentation

4.5.2.1 unsigned int t1

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

Range: 0..65535.

4.5.2.2 unsigned int t2

Time in ms between turn off brake and moving readiness.

All moving commands will execute after this interval. Range: 0..65535.

4.5.2.3 unsigned int t3

Time in ms between motor stop and turn on brake.

Range: 0..65535.

4.5.2.4 unsigned int t4

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

Range: 0..65535.

4.6 calibration_t Struct Reference

Calibration companion structure.

Data Fields

- double [A](#)
Multitplier.
- unsigned int [MicrostepMode](#)
Microstep mode.

4.6.1 Detailed Description

Calibration companion structure.

4.7 chart_data_t Struct Reference

Additional device state.

Data Fields

- int [WindingVoltageA](#)
In the case step motor, the voltage across the winding A; 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 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 the case step motor and DC is not used.
- int [WindingCurrentA](#)
In the case step motor, the current in the coil A; 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; 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 the case step motor and DC is not used.
- unsigned int [Pot](#)
Potentiometer in ten-thousandths of [0, 10000].
- unsigned int [Joy](#)
The joystick to the ten-thousandths [0, 10000].
- int [DutyCycle](#)
Duty cycle of PWM.

4.7.1 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](#)

4.8 control_settings_calb_t Struct Reference

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.
- unsigned int [Flags](#)
Control flags.
- float [DeltaPosition](#)
Shift (delta) of position.

4.8.1 Field Documentation

4.8.1.1 unsigned int MaxClickTime

Maximum click time.

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

4.8.1.2 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. Range: 0..65535.

4.9 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 (1/256 microstep) 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.
- unsigned int [Flags](#)
Control flags.
- int [DeltaPosition](#)
Shift (delta) of position.
- int [uDeltaPosition](#)
Fractional part of the shift in micro steps (-255 .

4.9.1 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](#)

4.9.2 Field Documentation

4.9.2.1 unsigned int MaxClickTime

Maximum click time.

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

4.9.2.2 unsigned int MaxSpeed[10]

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

Range: 0..1000000.

4.9.2.3 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. Range: 0..65535.

4.9.2.4 int uDeltaPosition

Fractional part of the shift in micro steps (-255 .

. 255) is only used with stepper motor

4.9.2.5 unsigned int uMaxSpeed[10]

Array of speeds (1/256 microstep) using with joystick and button control.

Range: 0..255.

4.10 controller_name_t Struct Reference

Controller user name and flags of setting.

Data Fields

- char [ControllerName](#) [17]
User controller name.
- unsigned int [CtrlFlags](#)
Flags of internal controller settings.

4.10.1 Detailed Description

Controller user name and flags of setting.

See also

[get_controller_name](#), [set_controller_name](#)

4.10.2 Field Documentation

4.10.2.1 char ControllerName[17]

User controller name.

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

4.11 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.

4.11.1 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](#)

4.11.2 Field Documentation

4.11.2.1 unsigned int CTPMinError

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

Measured in steps step motor. Range: 0..255.

4.12 debug_read_t Struct Reference

Debug data.

Data Fields

- unsigned int [DebugData](#) [128]
Arbitrary debug data.

4.12.1 Detailed Description

Debug data.

These data are used for device debugging by manufacturer only.

See also

[get_debug_read](#)

4.13 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.

4.13.1 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](#)

4.14 edges_settings_calb_t Struct Reference

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.

4.15 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 1/256 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 1/256 microsteps.

4.15.1 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](#)

4.15.2 Field Documentation

4.15.2.1 int LeftBorder

Left border position, used if BORDER.IS.ENCODER flag is set.

Range: -2147483647..2147483647.

4.15.2.2 int RightBorder

Right border position, used if BORDER_IS_ENCODER flag is set.

Range: -2147483647..2147483647.

4.15.2.3 int uLeftBorder

Left border position in 1/256 microsteps(used with stepper motor only).

Range: -255..255.

4.15.2.4 int uRightBorder

Right border position in 1/256 microsteps.

Range: -255..255(used with stepper motor only).

4.16 encoder_information_t Struct Reference

Encoder information.

Data Fields

- char [Manufacturer](#) [17]
Manufacturer.
- char [PartNumber](#) [25]
Series and PartNumber.

4.16.1 Detailed Description

Encoder information.

See also

[set_encoder_information](#)
[get_encoder_information](#)
[get_encoder_information](#), [set_encoder_information](#)

4.16.2 Field Documentation

4.16.2.1 char Manufacturer[17]

Manufacturer.

Max string length: 16 chars.

4.16.2.2 char PartNumber[25]

Series and PartNumber.

Max string length: 24 chars.

4.17 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.

4.17.1 Detailed Description

Encoder settings.

See also

[set_encoder_settings](#)
[get_encoder_settings](#)
[get_encoder_settings](#), [set_encoder_settings](#)

4.17.2 Field Documentation

4.17.2.1 float MaxCurrentConsumption

Max current consumption (mA).

Data type: float.

4.17.2.2 float MaxOperatingFrequency

Max operation frequency (kHz).

Data type: float.

4.17.2.3 float SupplyVoltageMax

Maximum supply voltage (V).

Data type: float.

4.17.2.4 float SupplyVoltageMin

Minimum supply voltage (V).

Data type: float.

4.18 engine_settings_calb_t Struct Reference

Data Fields

- unsigned int [NomVoltage](#)
Rated voltage.
- unsigned int [NomCurrent](#)
Rated current.
- 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 steper motor only).

4.18.1 Field Documentation

4.18.1.1 float Antiplay

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

Used if ENGINE_ANTIPLAY flag is set.

4.18.1.2 unsigned int NomCurrent

Rated current.

Controller will keep current consumed by motor below this value if ENGINE_LIMIT_CURR flag is set. Range: 1..65535

4.18.1.3 float NomSpeed

Nominal speed.

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

4.18.1.4 unsigned int NomVoltage

Rated voltage.

Controller will keep the voltage drop on motor below this value if ENGINE_LIMIT_VOLT flag is set(Used with DC only). Range: 1..65535

4.18.1.5 unsigned int StepsPerRev

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

Range: 1..65535.

4.19 engine_settings_t Struct Reference

Engine settings.

Data Fields

- unsigned int [NomVoltage](#)
Rated voltage.
- unsigned int [NomCurrent](#)
Rated current.
- unsigned int [NomSpeed](#)
Nominal 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).

4.19.1 Detailed Description

Engine settings.

This structure contains useful motor settings. These settings specify motor shaft movement algorithm, list of limitations and rated characteristics. All boards are supplied with standart 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](#)

4.19.2 Field Documentation

4.19.2.1 int Antiplay

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

Used if ENGINE_ANTIPLAY flag is set. Range: -32768..32767

4.19.2.2 unsigned int NomCurrent

Rated current.

Controller will keep current consumed by motor below this value if ENGINE_LIMIT_CURR flag is set. Range: 1..65535

4.19.2.3 unsigned int NomSpeed

Nominal 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..1000000.

4.19.2.4 unsigned int NomVoltage

Rated voltage.

Controller will keep the voltage drop on motor below this value if ENGINE_LIMIT_VOLT flag is set(Used with DC only). Range: 1..65535

4.19.2.5 unsigned int StepsPerRev

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

Range: 1..65535.

4.19.2.6 unsigned int uNomSpeed

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

Range: 0..255

4.20 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.

4.20.1 Detailed Description

Engine type and driver type settings.

Parameters

<i>id</i>	an identifier of device
<i>EngineType</i>	engine type
<i>DriverType</i>	driver type

See also

[get_entype_settings](#), [set_entype_settings](#)

4.21 extio_settings_t Struct Reference

EXTIO settings.

Data Fields

- unsigned int [EXTIOSetupFlags](#)
External IO setup flags.
- unsigned int [EXTIOModeFlags](#)
External IO mode flags.

4.21.1 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](#)

4.22 feedback_settings_t Struct Reference

Feedback settings.

Data Fields

- unsigned int [IPS](#)
The number of measured counts per revolution encoder.
- unsigned int [FeedbackType](#)
Feedback type.
- unsigned int [FeedbackFlags](#)
Describes feedback flags.
- unsigned int [HallSPR](#)
The number of hall steps per revolution.
- int [HallShift](#)
Phase shift between output signal on BLDC engine and hall sensor input(0 - when only active the Hall sensor, the output state is a positive voltage on the winding A and a negative voltage on the winding B).

4.22.1 Detailed Description

Feedback settings.

This structure contains feedback settings.

See also

[get_feedback_settings](#), [set_feedback_settings](#)

4.23 gear_information_t Struct Reference

Gear information.

Data Fields

- char [Manufacturer](#) [17]
Manufacturer.
- char [PartNumber](#) [25]
Series and PartNumber.

4.23.1 Detailed Description

Gear information.

See also

[set_gear_information](#)
[get_gear_information](#)
[get_gear_information](#), [set_gear_information](#)

4.23.2 Field Documentation

4.23.2.1 char Manufacturer[17]

Manufacturer.

Max string length: 16 chars.

4.23.2.2 char PartNumber[25]

Series and PartNumber.

Max string length: 24 chars.

4.24 gear_settings_t Struct Reference

Gear settings.

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 (%).

4.24.1 Detailed Description

Gear settings.

See also

[set_gear_settings](#)
[get_gear_settings](#)
[get_gear_settings](#), [set_gear_settings](#)

4.24.2 Field Documentation

4.24.2.1 float Efficiency

Reduction gear efficiency (%).

Data type: float.

4.24.2.2 float InputInertia

Equivalent input gear inertia (g cm²).

Data type: float.

4.24.2.3 float MaxOutputBacklash

Output backlash of the reduction gear(degree).

Data type: float.

4.24.2.4 float RatedInputSpeed

Max speed on the input shaft (rpm).

Data type: float.

4.24.2.5 float RatedInputTorque

Max continuous torque (N m).

Data type: float.

4.24.2.6 float ReductionIn

Input reduction coefficient.

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

4.24.2.7 float ReductionOut

Output reduction coefficient.

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

4.25 `get_position_calb_t` Struct Reference

Data Fields

- float [Position](#)
The position in the engine.
- long_t [EncPosition](#)
Encoder position.

4.26 `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.

4.26.1 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](#)

4.27 `hallsensor_information_t` Struct Reference

Hall sensor information.

Data Fields

- char [Manufacturer](#) [17]
Manufacturer.
- char [PartNumber](#) [25]
Series and PartNumber.

4.27.1 Detailed Description

Hall sensor information.

See also

[set_hallsensor_information](#)
[get_hallsensor_information](#)
[get_hallsensor_information](#), [set_hallsensor_information](#)

4.27.2 Field Documentation

4.27.2.1 char Manufacturer[17]

Manufacturer.

Max string length: 16 chars.

4.27.2.2 char PartNumber[25]

Series and PartNumber.

Max string length: 24 chars.

4.28 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.

4.28.1 Detailed Description

Hall sensor settings.

See also

[set_hallsensor_settings](#)
[get_hallsensor_settings](#)
[get_hallsensor_settings](#), [set_hallsensor_settings](#)

4.28.2 Field Documentation

4.28.2.1 float MaxCurrentConsumption

Max current consumption (mA).

Data type: float.

4.28.2.2 float MaxOperatingFrequency

Max operation frequency (kHz).

Data type: float.

4.28.2.3 float SupplyVoltageMax

Maximum supply voltage (V).

Data type: float.

4.28.2.4 float SupplyVoltageMin

Minimum supply voltage (V).

Data type: float.

4.29 home_settings_calb_t Struct Reference

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.

4.30 home_settings_t Struct Reference

Position calibration settings.

Data Fields

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

4.30.1 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](#)

4.30.2 Field Documentation

4.30.2.1 unsigned int FastHome

Speed used for first motion.

Range: 0..1000000.

4.30.2.2 int HomeDelta

Distance from break point.

Range: -2147483647..2147483647.

4.30.2.3 unsigned int SlowHome

Speed used for second motion.

Range: 0..1000000.

4.30.2.4 unsigned int uFastHome

Part of the speed for first motion, microsteps.

Range: 0..255.

4.30.2.5 int uHomeDelta

Part of the delta distance, microsteps.

Range: -255..255.

4.30.2.6 unsigned int uSlowHome

Part of the speed for second motion, microsteps.

Range: 0..255.

4.31 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.

4.31.1 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](#)

4.32 motor_information_t Struct Reference

motor information.

Data Fields

- char [Manufacturer](#) [17]
Manufacturer.
- char [PartNumber](#) [25]
Series and PartNumber.

4.32.1 Detailed Description

motor information.

See also

[set_motor_information](#)
[get_motor_information](#)
[get_motor_information](#), [set_motor_information](#)

4.32.2 Field Documentation

4.32.2.1 char Manufacturer[17]

Manufacturer.

Max string length: 16 chars.

4.32.2.2 char PartNumber[25]

Series and PartNumber.

Max string length: 24 chars.

4.33 motor_settings_t Struct Reference

motor settings.

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 (V).
- float [NominalCurrent](#)
Maximum direct current in winding for DC and BLDC engines, nominal current in windings for stepper motor (A).
- float [NominalSpeed](#)
Nominal speed(rpm).
- 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 (rpm).

- 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).

4.33.1 Detailed Description

motor settings.

See also

[set_motor_settings](#)

[get_motor_settings](#)

[get_motor_settings](#), [set_motor_settings](#)

4.33.2 Field Documentation

4.33.2.1 float DetentTorque

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

Data type: float.

4.33.2.2 float MaxCurrent

The maximum current in the winding (A).

Data type: float.

4.33.2.3 float MaxCurrentTime

Safe duration of overcurrent in the winding (ms).

Data type: float.

4.33.2.4 float MaxSpeed

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

Data type: float.

4.33.2.5 float MechanicalTimeConstant

Mechanical time constant (ms).

Data type: float.

4.33.2.6 float NoLoadCurrent

The current consumption in idle mode (A).

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

4.33.2.7 float NoLoadSpeed

Idle speed (rpm).

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

4.33.2.8 float NominalCurrent

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

Data type: float.

4.33.2.9 float NominalPower

Nominal power(W).

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

4.33.2.10 float NominalSpeed

Nominal speed(rpm).

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

4.33.2.11 float NominalTorque

Nominal torque(mN m).

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

4.33.2.12 float NominalVoltage

Nominal voltage on winding (B).

Data type: float

4.33.2.13 float RotorInertia

Rotor inertia(g cm²).

Data type: float.

4.33.2.14 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.

4.33.2.15 float SpeedTorqueGradient

Speed torque gradient (rpm / mN m).

Data type: float.

4.33.2.16 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.

4.33.2.17 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.

4.33.2.18 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.

4.33.2.19 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.

4.34 move_settings_calb_t Struct Reference

Data Fields

- float [Speed](#)
Target speed.
- float [Accel](#)
Motor shaft acceleration, steps/s²(stepper motor) or RPM/s(DC).
- float [Decel](#)
Motor shaft deceleration, steps/s²(stepper motor) or RPM/s(DC).
- float [AntiplaySpeed](#)
Speed in antiplay mode.

4.35 move_settings_t Struct Reference

Move settings.

Data Fields

- unsigned int [Speed](#)
Target speed(for stepper motor: steps / c, for DC: rpm).
- unsigned int [uSpeed](#)
Target speed in 1/256 microsteps/s.
- unsigned int [Accel](#)
Motor shaft acceleration, steps/s²(stepper motor) or RPM/s(DC).
- unsigned int [Decel](#)
Motor shaft deceleration, steps/s²(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, 1/256 microsteps/s.

4.35.1 Detailed Description

Move settings.

See also

[set_move_settings](#)
[get_move_settings](#)
[get_move_settings](#), [set_move_settings](#)

4.35.2 Field Documentation

4.35.2.1 unsigned int Accel

Motor shaft acceleration, steps/s²(stepper motor) or RPM/s(DC).

Range: 0..65535.

4.35.2.2 unsigned int AntiplaySpeed

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

Range: 0..1000000.

4.35.2.3 unsigned int Decel

Motor shaft deceleration, steps/s²(stepper motor) or RPM/s(DC).

Range: 0..65535.

4.35.2.4 unsigned int Speed

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

Range: 0..1000000.

4.35.2.5 unsigned int uAntiplaySpeed

Speed in antiplay mode, 1/256 microsteps/s.

Used with stepper motor only. Range: 0..255.

4.35.2.6 unsigned int uSpeed

Target speed in 1/256 microsteps/s.

Using with stepper motor only. Range: 0..255.

4.36 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.

4.36.1 Detailed Description

PID settings.

This structure contains factors for PID routine. Range: 0..65535. It specify behaviour of PID routine for voltage. These factors are slightly different for different positioners. All boards are supplied with standart 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](#)

4.37 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 reducing 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.

4.37.1 Detailed Description

Step motor power settings.

See also

[set_move_settings](#)
[get_move_settings](#)
[get_power_settings](#), [set_power_settings](#)

4.37.2 Field Documentation

4.37.2.1 unsigned int `CurrentSetTime`

Time in ms to reach nominal current.

Range: 0..65535.

4.37.2.2 unsigned int `CurrReductDelay`

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

Range: 0..65535.

4.37.2.3 unsigned int `HoldCurrent`

Current in holding regime, percent of nominal.

Range: 0..100.

4.37.2.4 unsigned int `PowerOffDelay`

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

Range: 0..65535.

4.38 `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, in mV.
- unsigned int [CriticalIpwr](#)
Maximum motor current which triggers ALARM state, in mA.
- unsigned int [CriticalUpwr](#)
Maximum motor voltage which triggers ALARM state, in 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, in mV.
- unsigned int [MinimumUusb](#)
Minimum USB voltage which triggers ALARM state, in mV.
- unsigned int [Flags](#)
Flags of secure settings.

4.38.1 Detailed Description

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

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

See also

[get_secure_settings](#)
[set_secure_settings](#)
[get_secure_settings, set_secure_settings](#)

4.38.2 Field Documentation

4.38.2.1 unsigned int CriticalIpwr

Maximum motor current which triggers ALARM state, in mA.

Range: 0..65535.

4.38.2.2 unsigned int CriticalIusb

Maximum USB current which triggers ALARM state, in mA.

Range: 0..65535.

4.38.2.3 unsigned int CriticalT

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

Range: 0..65535.

4.38.2.4 unsigned int CriticalUpwr

Maximum motor voltage which triggers ALARM state, in mV.

Range: 0..65535.

4.38.2.5 unsigned int CriticalUusb

Maximum USB voltage which triggers ALARM state, in mV.

Range: 0..65535.

4.38.2.6 unsigned int LowUpwrOff

Lower voltage limit to turn off the motor, in mV.

Range: 0..65535.

4.38.2.7 unsigned int MinimumUusb

Minimum USB voltage which triggers ALARM state, in mV.

Range: 0..65535.

4.39 serial_number_t Struct Reference

Serial number structure.

Data Fields

- unsigned int [SN](#)
New board serial number.
- unsigned int [Key](#) [32]
Protection key (256 bit).

4.39.1 Detailed Description

Serial number structure.

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

See also

[set_serial_number](#)

4.40 set_position_calb_t Struct Reference

Data Fields

- float [Position](#)
The position in the engine.
- long_t [EncPosition](#)
Encoder position.
- unsigned int [PosFlags](#)
Position setting flags.

4.41 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.

4.41.1 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](#)

4.42 stage_information_t Struct Reference

Stage information.

Data Fields

- char [Manufacturer](#) [17]
Manufacturer.
- char [PartNumber](#) [25]
Series and PartNumber.

4.42.1 Detailed Description

Stage information.

See also

[set_stage_information](#)
[get_stage_information](#)
[get_stage_information](#), [set_stage_information](#)

4.42.2 Field Documentation

4.42.2.1 char Manufacturer[17]

Manufacturer.

Max string length: 16 chars.

4.42.2.2 char PartNumber[25]

Series and PartNumber.

Max string length: 24 chars.

4.43 stage_name_t Struct Reference

Stage user name.

Data Fields

- char [PositionerName](#) [17]
User positioner name.

4.43.1 Detailed Description

Stage user name.

See also

[get_stage_name](#), [set_stage_name](#)

4.43.2 Field Documentation

4.43.2.1 char PositionerName[17]

User positioner name.

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

4.44 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).

4.44.1 Detailed Description

Stage settings.

See also

[set_stage_settings](#)
[get_stage_settings](#)
[get_stage_settings](#), [set_stage_settings](#)

4.44.2 Field Documentation

4.44.2.1 float HorizontalLoadCapacity

Horizontal load capacity (kg).

Data type: float.

4.44.2.2 float LeadScrewPitch

Lead screw pitch (mm).

Data type: float.

4.44.2.3 float MaxCurrentConsumption

Max current consumption (A).

Data type: float.

4.44.2.4 float MaxSpeed

Max speed (Units/c).

Data type: float.

4.44.2.5 float SupplyVoltageMax

Supply voltage maximum (V).

Data type: float.

4.44.2.6 float SupplyVoltageMin

Supply voltage minimum (V).

Data type: float.

4.44.2.7 float TravelRange

Travel range (Units).

Data type: float.

4.44.2.8 char Units[9]

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

Max string length: 8 chars.

4.44.2.9 float VerticalLoadCapacity

Vertical load capacity (kg).

Data type: float.

4.45 status_calb_t Struct Reference

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.
- int [Upwr](#)
Power supply voltage.
- int [Iusb](#)
USB current consumption.
- int [Uusb](#)
USB voltage.
- int [CurT](#)
Temperature in tenths of degrees C.
- unsigned int [Flags](#)
Status flags.
- unsigned int [GPIOFlags](#)
Status flags.
- unsigned int [CmdBufFreeSpace](#)
This field shows the amount of free cells buffer synchronization chain.

4.46 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 1/256 microsteps.
- long_t [EncPosition](#)
Current encoder position.
- int [CurSpeed](#)
Motor shaft speed.
- int [uCurSpeed](#)
Part of motor shaft speed in 1/256 microsteps.
- int [lpwr](#)
Engine current.
- int [Upwr](#)
Power supply voltage.
- int [lusb](#)
USB current consumption.
- int [Uusb](#)
USB voltage.
- int [CurT](#)
Temperature in tenths of degrees C.
- unsigned int [Flags](#)
Status flags.
- unsigned int [GPIOFlags](#)
Status flags.
- unsigned int [CmdBufFreeSpace](#)
This field shows the amount of free cells buffer synchronization chain.

4.46.1 Detailed Description

Device state.

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

See also

`get_status_impl`

4.46.2 Field Documentation

4.46.2.1 int uCurPosition

Step motor shaft position in 1/256 microsteps.

Used only with stepper motor.

4.46.2.2 int uCurSpeed

Part of motor shaft speed in 1/256 microsteps.

Used only with stepper motor.

4.47 sync_in_settings_calb_t Struct Reference

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.

4.47.1 Field Documentation

4.47.1.1 unsigned int ClutterTime

Input synchronization pulse dead time (mks).

Range: 0..65535

4.48 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 (whole steps)
- int [uPosition](#)
The fractional part of a position or shift in microsteps (-255 .
- unsigned int [Speed](#)
Target speed(for stepper motor: steps / c, for DC: rpm).

- unsigned int [uSpeed](#)
Target speed in microsteps/s.

4.48.1 Detailed Description

Synchronization settings.

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

See also

[get_sync_in_settings](#)
[set_sync_in_settings](#)
[get_sync_in_settings](#), [set_sync_in_settings](#)

4.48.2 Field Documentation

4.48.2.1 unsigned int ClutterTime

Input synchronization pulse dead time (mks).

Range: 0..65535

4.48.2.2 unsigned int Speed

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

Range: 0..1000000.

4.48.2.3 int uPosition

The fractional part of a position or shift in microsteps (-255 .
. 255)(is only used with stepper motor)

4.48.2.4 unsigned int uSpeed

Target speed in microsteps/s.

Using with stepper motor only. Range: 0..255.

4.49 sync_out_settings_calb_t Struct Reference

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, which is getting hit in the target position and the momentum generated by the stop.

4.49.1 Field Documentation

4.49.1.1 unsigned int SyncOutPeriod

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

Range: 0..65535

4.49.1.2 unsigned int SyncOutPulseSteps

This value specifies duration of output pulse.

It is measured microseconds when SYNCOUT_IN_STEPS flag is cleared or in encoder pulses or motor steps when SYNCOUT_IN_STEPS is set. Range: 0..65535

4.50 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 micro steps (only used with stepper motor).

4.50.1 Detailed Description

Synchronization settings.

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

See also

[get_sync_out_settings](#)
[set_sync_out_settings](#)
[get_sync_out_settings](#), [set_sync_out_settings](#)

4.50.2 Field Documentation

4.50.2.1 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.

Range: 0..4294967295.

4.50.2.2 unsigned int SyncOutPeriod

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

Range: 0..65535

4.50.2.3 unsigned int SyncOutPulseSteps

This value specifies duration of output pulse.

It is measured microseconds when SYNCOUT_IN_STEPS flag is cleared or in encoder pulses or motor steps when SYNCOUT_IN_STEPS is set. Range: 0..65535

4.50.2.4 unsigned int uAccuracy

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

Range: 0 .. 255.

4.51 `uart_settings_t` Struct Reference

UART settings.

Data Fields

- unsigned int [Speed](#)
UART speed.
- unsigned int [UARTSetupFlags](#)
UART parity flags.

4.51.1 Detailed Description

UART settings.

This structure contains UART settings.

See also

[get_uart_settings](#)
[set_uart_settings](#)
[get_uart_settings](#), [set_uart_settings](#)

Chapter 5

File Documentation

5.1 ximc.h File Reference

Header file for libximc library.

Data Structures

- struct [calibration_t](#)
Calibration companion structure.
- struct [feedback_settings_t](#)
Feedback settings.
- struct [home_settings_t](#)
Position calibration settings.
- struct [home_settings_calb_t](#)
- struct [move_settings_t](#)
Move settings.
- struct [move_settings_calb_t](#)
- struct [engine_settings_t](#)
Engine settings.
- struct [engine_settings_calb_t](#)
- 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](#)
- struct [pid_settings_t](#)
PID settings.
- struct [sync_in_settings_t](#)
Synchronization settings.
- struct [sync_in_settings_calb_t](#)
- struct [sync_out_settings_t](#)
Synchronization settings.
- struct [sync_out_settings_calb_t](#)

- struct [extio_settings_t](#)
EXTIO settings.
- struct [brake_settings_t](#)
Brake settings.
- struct [control_settings_t](#)
Control settings.
- struct [control_settings_calb_t](#)
- 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 [controller_name_t](#)
Controller user name and flags of setting.
- struct [add_sync_in_action_t](#)
This command adds one element of the FIFO commands.
- struct [add_sync_in_action_calb_t](#)
- struct [get_position_t](#)
Position information.
- struct [get_position_calb_t](#)
- struct [set_position_t](#)
Position information.
- struct [set_position_calb_t](#)
- struct [status_t](#)
Device state.
- struct [status_calb_t](#)
- struct [chart_data_t](#)
Additional device state.
- struct [device_information_t](#)
Read command controller information.
- struct [serial_number_t](#)
Serial number structure.
- struct [analog_data_t](#)
Analog data.
- struct [debug_read_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](#)
motor settings.
- 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 settings.
- struct [accessories_settings_t](#)
Additional accessories information.

Macros

- #define [XIMC_API](#)
Library import macro Macros allows to automatically import function from shared library.
- #define [XIMC_CALLCONV](#)
Library calling convention macros.
- #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.

Flags of move state

Specify move states.

See also

[get.status](#)

`status.t::move.state`

[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

`status.t::power.state`

[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

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

See also

`status.t::flags`

[get.status](#)

[status.t::GPIOFlags](#), [get.status_impl](#)

- #define [STATE.CONTR](#) 0x0003F
Flags of controller states.
- #define [STATE.ERRC](#) 0x00001
Command error encountered.
- #define [STATE.ERRD](#) 0x00002
Data integrity error encountered.

- #define `STATE_ERRV` 0x00004
Value error encountered.
- #define `STATE_EEPROM_CONNECTED` 0x00010
EEPROM with settings is connected.
- #define `STATE_SECUR` 0x3FFC0
Flags of security.
- #define `STATE_ALARM` 0x00040
Controller is in alarm state indicating that something dangerous had happened.
- #define `STATE_CTP_ERROR` 0x00080
Control position error(is only used with stepper motor).
- #define `STATE_POWER_OVERHEAT` 0x00100
Power driver overheat.
- #define `STATE_CONTROLLER_OVERHEAT` 0x00200
Controller overheat.
- #define `STATE_OVERLOAD_POWER_VOLTAGE` 0x00400
Power voltage exceeds safe limit.
- #define `STATE_OVERLOAD_POWER_CURRENT` 0x00800
Power current exceeds safe limit.
- #define `STATE_OVERLOAD_USB_VOLTAGE` 0x01000
USB voltage exceeds safe limit.
- #define `STATE_LOW_USB_VOLTAGE` 0x02000
USB voltage is insufficient for normal operation.
- #define `STATE_OVERLOAD_USB_CURRENT` 0x04000
USB current exceeds safe limit.
- #define `STATE_BORDERS_SWAP_MISSET` 0x08000
Engine stuck at the wrong edge.
- #define `STATE_LOW_POWER_VOLTAGE` 0x10000
Power voltage is lower than Low Voltage Protection limit.
- #define `STATE_H_BRIDGE_FAULT` 0x20000
Signal from the driver that fault happened.
- #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_HALL_A` 0x0040
State of Hall.a pin.
- #define `STATE_HALL_B` 0x0080
State of Hall.b pin.
- #define `STATE_HALL_C` 0x0100
State of Hall.c 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

[status_t::encsts](#)
[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 otyher direction.*
- #define [ENC_STATE_OK](#) 0x04
- Encoder is connected and working properly.*

Winding state

Motor winding state returned by device query.

See also

[status_t::windsts](#)
[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

`status_t::mvcmdsts`
[get.status](#)
[status_t::MvCmdSIs](#), [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 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

`engine_settings_t::flags`
[set_engine_settings](#)
[get_engine_settings](#)
[engine_settings_t::EngineFlags](#), [get_engine_settings](#), [set_engine_settings](#)

- #define [ENGINE_REVERSE](#) 0x01
Reverse 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
Maxumum motor voltage limit enable flag(is only used with DC motor).
- #define [ENGINE_LIMIT_CURR](#) 0x40
Maxumum motor current limit enable flag(is only used with DC motor).
- #define [ENGINE_LIMIT_RPM](#) 0x80
Maxumum 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

[power_settings_t::flags](#)
[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

[secure_settings_t::flags](#)
[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.

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_ENCODERHALL](#) 0x03
Feedback by Hall detector.
- #define [FEEDBACK_EMF](#) 0x04
Feedback by EMF.
- #define [FEEDBACK_NONE](#) 0x05
Feedback is absent.

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_HALL_REVERSE](#) 0x02
Reverse count position on the Hall sensor.

Flags for synchronization input setup

See also

[sync_settings.t::syncin_flags](#)
[get_sync_settings](#)
[set_sync_settings](#)
[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_settings.t::syncout_flags](#)

[get_sync_settings](#)

[set_sync_settings](#)

[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

[extio_settings.t::setup_flags](#)

[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_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_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.
- #define [EXTIO.SETUP_MODE_OUT_MOTOR_FOUND](#) 0x50
EXTIO pin stays active when motor is connected (first winding).

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 connected to pin SW1 is triggered by a low level on pin.
- #define [ENDER.SW2.ACTIVE.LOW](#) 0x04
1 - Limit switch connected 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.

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](#) 0x01

- *Flag defines direction of 1st motion after execution of home command.*
• #define [HOME_DIR_SECOND](#) 0x02
- *Flag defines direction of 2nd motion.*
• #define [HOME_MV_SEC_EN](#) 0x04
- *Use the second phase of calibration to the home position, if set; otherwise the second phase is skipped.*
• #define [HOME_HALF_MV](#) 0x08
- *If the flag is set, the stop signals are ignored in start of second movement the first half-turn.*
• #define [HOME_STOP_FIRST_BITS](#) 0x30
- *Bits of the first stop selector.*
• #define [HOME_STOP_FIRST_REV](#) 0x10
- *First motion stops by revolution sensor.*
• #define [HOME_STOP_FIRST_SYN](#) 0x20
- *First motion stops by synchronization input.*
• #define [HOME_STOP_FIRST_LIM](#) 0x30
- *First motion stops by limit switch.*
• #define [HOME_STOP_SECOND_BITS](#) 0xC0
- *Bits of the second stop selector.*
• #define [HOME_STOP_SECOND_REV](#) 0x40
- *Second motion stops by revolution sensor.*
• #define [HOME_STOP_SECOND_SYN](#) 0x80
- *Second motion stops by synchronization input.*
• #define [HOME_STOP_SECOND_LIM](#) 0xC0
- *Second motion stops by limit switch.*

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_PUSH_PULL_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_REOLUTIONSENSOR_PRESENT](#) 0x040
If flag is set the encoder has revolution sensor, else encoder hasn't it.
- #define [ENCSET_REOLUTIONSENSOR_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 connected to pin SW1 is available.
- #define [LS_ON_SW2_AVAILABLE](#) 0x02
If flag is set the limit switch connected to pin SW2 is available.
- #define [LS_SW1_ACTIVE_LOW](#) 0x04
If flag is set the limit switch connected to pin SW1 is triggered by a low level on pin.
- #define [LS_SW2_ACTIVE_LOW](#) 0x08
If flag is set the limit switch connected to pin SW2 is triggered by a low level on pin.
- #define [LS_SHORTED](#) 0x10
If flag is set the Limit switches is shorted.

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.

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)
Set feedback settings.
- **result_t** **XIMC_API get_feedback_settings** (**device_t** id, **feedback_settings_t** *feedback_settings)
Read 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)
- **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)
- **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)
- **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)
- **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)
- **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)
- **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)
- [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)
- [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)
- [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)
- [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)
- [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)
- [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)
- [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)
- [result_t XIMC.API set_joytick_settings](#) ([device_t](#) id, const [joytick_settings_t](#) *joytick_settings)
- Set settings of joytick.*
- [result_t XIMC.API get_joytick_settings](#) ([device_t](#) id, [joytick_settings_t](#) *joytick_settings)
- Read settings of joytick.*
- [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_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.

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 set_add_sync_in_action \(device_t id, const \[add_sync_in_action_t\]\(#\) *add_sync_in_action\)](#)
This command adds one element of the FIFO commands that are executed when input clock pulse.
- [result_t XIMC_API set_add_sync_in_action_calb \(device_t id, const \[add_sync_in_action_calb_t\]\(#\) *add_sync_in_action_calb, const \[calibration_t\]\(#\) *calibration\)](#)
- [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\)](#)
- [result_t XIMC_API command_movr \(device_t id, int DeltaPosition, int uDeltaPosition\)](#)
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.
- [result_t XIMC_API command_movr_calb \(device_t id, float DeltaPosition, const \[calibration_t\]\(#\) *calibration\)](#)
- [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 continuous moving to the left.
- [result_t XIMC_API command_right \(device_t id\)](#)
Start continuous 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 :: Antiploy, 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\)](#)
- [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\)](#)
- [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_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 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 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.

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 goto_firmware](#) ([device_t](#) id, uint8_t *ret)
- Reboot to firmware.*

 - [result_t XIMC_API has_firmware](#) (const char *name, uint8_t *ret)
- Check for firmware on device.*

 - [result_t XIMC_API command_update_firmware](#) (const char *name, const uint8_t *data, uint32_t data_size)
- Update firmware.*

 - [result_t XIMC_API write_key](#) (const char *name, 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)
 - Logging callback prototype.*
- [device_t XIMC_API open_device](#) (const char *name)
 - Open a device with OS name name 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 probe_device](#) (const char *name)
 - Check if a device with OS name name is XIMC device.*
- [device_enumeration_t XIMC_API enumerate_devices](#) (int probe_flags)
 - 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 reset_locks ()`
- Reset library locks in a case of deadlock.*
 - `result_t XIMC_API ximc_fix_usbser_sys (const char *device_name)`
- 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)`
- Simple callback for logging to stderr in wide chars.*
 - `void XIMC_API logging_callback_stderr_narrow (int loglevel, const wchar_t *message)`
- Simple callback for logging to stderr in narrow (single byte) chars.*
 - `void XIMC_API set_logging_callback (logging_callback_t logging_callback)`
- 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)`
- Calibrated device state.*
 - `result_t XIMC_API get_device_information (device_t id, device_information_t *device_information)`
- Return device information.*

5.1.1 Detailed Description

Header file for libximc library.

5.1.2 Macro Definition Documentation

5.1.2.1 `#define BORDERS_SWAP_MISSET_DETECTION 0x08`

Motor should stop on both borders.

Need to save motor then wrong border settings is set

5.1.2.2 `#define DRIVER_TYPE_DISCRETE_FET 0x01`

Driver with discrete FET keys.

Default option.

5.1.2.3 `#define ENGINE_ACCEL_ON 0x10`

Acceleration enable flag.

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

5.1.2.4 `#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.

5.1.2.5 `#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.

5.1.2.6 `#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.

5.1.2.7 `#define ENGINE_TYPE_TEST 0x04`

Duty cycle are fixed.

Used only manufacturer.

5.1.2.8 `#define ENUMERATE_PROBE 0x01`

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

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

5.1.2.9 `#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.

5.1.2.10 `#define HOME_DIR_FIRST 0x01`

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

Direction is right, if set; otherwise left.

5.1.2.11 `#define HOME_DIR_SECOND 0x02`

Flag defines direction of 2nd motion.

Direction is right, if set; otherwise left.

5.1.2.12 `#define JOY_REVERSE 0x01`

Joystick action is reversed.

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

5.1.2.13 `#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.

5.1.2.14 `#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.

5.1.2.15 `#define STATE_ALARM 0x00040`

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.

5.1.2.16 `#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

5.1.2.17 `#define SYNCOUT_ENABLED 0x01`

Synchronization out pin follows the synchronization logic, if set.

It governed by SYNCOUT_STATE flag otherwise.

5.1.2.18 `#define XIMC_API`

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

It automatically expands to `__declspec(dllexport)` on `msvc` when including header file

5.1.3 Typedef Documentation

5.1.3.1 `typedef void(XIMC_CALLCONV * logging_callback_t)(int loglevel, const wchar_t *message)`

Logging callback prototype.

Parameters

<i>loglevel</i>	a loglevel
<i>message</i>	a message

5.1.4 Function Documentation

5.1.4.1 `result_t XIMC_API close_device (device_t * id)`

Close specified device.

Parameters

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.2 **result_t XIMC_API** command_clear_fram (**device_t** id)

Clear controller FRAM.

Can be used by manufacturer only

Parameters

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.3 **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

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.4 **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

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.5 **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 HOME.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

<i>id</i>	an identifier of device
-----------	-------------------------

See also

[home_settings_t](#)
[get_home_settings](#)
[set_home_settings](#)

5.1.4.6 **result_t XIMC_API** command_loft (**device_t** id)

Start continous moving to the left.

Parameters

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.7 **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

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.8 **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

<i>Position</i>	position to move. Range: -2147483647..2147483647.
<i>uPosition</i>	part of the position to move, microsteps. Range: -255..255.
<i>id</i>	an identifier of device

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

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

<i>DeltaPosition</i>	shift from initial position. Range: -2147483647..2147483647.
<i>uDeltaPosition</i>	part of the offset shift, microsteps. Range: -255..255.
<i>id</i>	an identifier of device

5.1.4.10 **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

<i>id</i>	an identifier of device
-----------	-------------------------

See also

[get_power_settings](#)
[set_power_settings](#)

5.1.4.11 **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

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.12 **result_t XIMC_API** command_reset (**device_t** id)

Reset controller.

Can be used by manufacturer only

Parameters

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.13 **result_t XIMC_API** command_right (**device_t** id)

Start continuous moving to the right.

Parameters

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.14 **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

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.15 **result_t XIMC_API** command_sstp (**device_t** id)

soft stop engine.

The motor stops with deceleration speed.

Parameters

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.16 **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

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.17 **result_t XIMC_API** command_update_firmware (const char * name, const uint8_t * data, uint32_t data_size)

Update firmware.

Service command

Parameters

<i>name</i>	a name of device
<i>data</i>	firmware byte stream
<i>data_size</i>	size of byte stream

5.1.4.18 **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

<i>id</i>	an identifier of device
-----------	-------------------------

5.1.4.19 **device_enumeration_t XIMC_API** enumerate_devices (int probe_flags)

Enumerate all devices that looks like valid.

Parameters

<i>in</i>	<i>probe_flags</i>	enumerate devices flags
-----------	--------------------	-------------------------

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

Free memory returned by *enumerate_devices*.

Parameters

in	<i>device_Enumeration</i>	opaque pointer to an enumeration device data
----	---------------------------	--

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

Read additional accessories information from EEPROM.

Parameters

	<i>id</i>	an identifier of device
out	<i>accessories_settings</i>	structure contains information about additional accessories

5.1.4.22 **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 recalibration by manufacturer only.

Parameters

	<i>id</i>	an identifier of device
out	<i>analog_data</i>	analog data coefficients

5.1.4.23 **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

	<i>id</i>	an identifier of device
out	<i>Major</i>	major version
out	<i>Minor</i>	minor version
out	<i>Release</i>	release version

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

Read settings of brake control.

Parameters

	<i>id</i>	an identifier of device
out	<i>brake_settings</i>	structure contains settings of brake control

5.1.4.25 **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

	<i>id</i>	an identifier of device
out	<i>chart_data</i>	structure with snapshot of controller parameters.

5.1.4.26 **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

	<i>id</i>	an identifier of device
out	<i>control_settings</i>	structure contains settings motor control by joystick or buttons left/right.

5.1.4.27 **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

	<i>id</i>	an identifier of device
out	<i>controller_name</i>	structure contains previously set user controller name

5.1.4.28 **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

	<i>id</i>	an identifier of device
out	<i>ctp_settings</i>	structure contains settings of control position

5.1.4.29 **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

	<i>id</i>	an identifier of device
out	<i>DebugData[128]</i>	Debug data.

5.1.4.30 `int XIMC_API get_device_count (device_enumeration_t device_enumeration)`

Get device count.

Parameters

in	<i>device_enumeration</i>	opaque pointer to an enumeration device data
----	---------------------------	--

5.1.4.31 `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

	<i>id</i>	an identifier of device
out	<i>device_information</i>	device information Device information.

See also

[get_device_information](#)

5.1.4.32 `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	<i>device_enumeration</i>	opaque pointer to an enumeration device data
in	<i>device_index</i>	device index

5.1.4.33 `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

	<i>id</i>	an identifier of device
out	<i>edges_settings</i>	edges settings, specify types of borders, motor behaviour and electrical behaviour of limit switches

5.1.4.34 **result_t XIMC_API** get_encoder_information (**device_t** id, **encoder_information_t** * encoder_information)

Read encoder information from EEPROM.

Parameters

	<i>id</i>	an identifier of device
out	<i>encoder_information</i>	structure contains information about encoder

5.1.4.35 **result_t XIMC_API** get_encoder_settings (**device_t** id, **encoder_settings_t** * encoder_settings)

Read encoder settings from EEPROM.

Parameters

	<i>id</i>	an identifier of device
out	<i>encoder_settings</i>	structure contains encoder settings

5.1.4.36 **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

	<i>id</i>	an identifier of device
out	<i>engine_settings</i>	engine settings

5.1.4.37 **result_t XIMC_API** get_entype_settings (**device_t** id, **entype_settings_t** * entype_settings)

Return engine type and driver type.

Parameters

	<i>id</i>	an identifier of device
out	<i>EngineType</i>	engine type
out	<i>DriverType</i>	driver type

5.1.4.38 **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 serial number.

Parameters

in	<i>device_enumeration</i>	opaque pointer to an enumeration device data
in	<i>device_index</i>	device index
out	<i>device_information</i>	device information data

5.1.4.39 **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	<i>device_enumeration</i>	opaque pointer to an enumeration device data
in	<i>device_index</i>	device index
out	<i>serial</i>	device serial number

5.1.4.40 **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

	<i>id</i>	an identifier of device
out	<i>extio_settings</i>	EXTIO settings

5.1.4.41 **result_t XIMC_API** get_feedback_settings (**device_t** id, **feedback_settings_t** * feedback_settings)

Read feedback settings.

Parameters

	<i>id</i>	an identifier of device
out	<i>IPS</i>	number of encoder pulses per shaft revolution. Range: 1..65535
out	<i>FeedbackType</i>	type of feedback
out	<i>FeedbackFlags</i>	flags of feedback

5.1.4.42 **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

	<i>id</i>	an identifier of device
out	<i>Major</i>	major version
out	<i>Minor</i>	minor version
out	<i>Release</i>	release version

5.1.4.43 **result_t XIMC_API** get_gear_information (**device_t** id, **gear_information_t** * gear_information)

Read gear information from EEPROM.

Parameters

	<i>id</i>	an identifier of device
out	<i>gear_information</i>	structure contains information about step gearhead

5.1.4.44 **result_t XIMC_API** get_gear_settings (**device_t** id, **gear_settings_t** * gear_settings)

Read gear settings from EEPROM.

Parameters

	<i>id</i>	an identifier of device
out	<i>gear_settings</i>	structure contains step gearhead settings

5.1.4.45 **result_t XIMC_API** get_hallsensor_information (**device_t** id, **hallsensor_information_t** * hallsensor_information)

Read hall sensor information from EEPROM.

Parameters

	<i>id</i>	an identifier of device
out	<i>hallsensor_information</i>	structure contains information about hall sensor

5.1.4.46 **result_t XIMC_API** get_hallsensor_settings (**device_t** id, **hallsensor_settings_t** * hallsensor_settings)

Read hall sensor settings from EEPROM.

Parameters

	<i>id</i>	an identifier of device
out	<i>hallsensor_settings</i>	structure contains hall sensor settings

5.1.4.47 **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

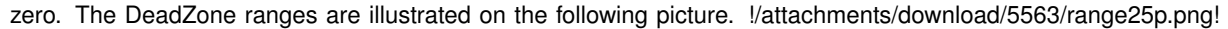
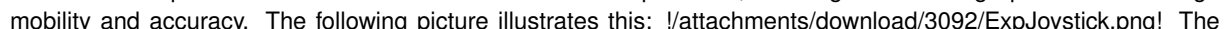
[home_settings_t](#)

Parameters

	<i>id</i>	an identifier of device
out	<i>home_settings</i>	calibrating position settings

5.1.4.48 **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.  The relationship between the deviation and the rate is exponential, allowing no switching speed combine high mobility and accuracy. The following picture illustrates this:  The nonlinearity parameter is adjustable. Setting it to zero makes deviation/speed relation linear.

Parameters

	<i>id</i>	an identifier of device
out	<i>joystick_settings</i>	structure contains joystick settings

5.1.4.49 **result_t XIMC_API** get_motor_information (**device_t** id, **motor_information_t** * motor_information)

Read motor information from EEPROM.

Parameters

	<i>id</i>	an identifier of device
out	<i>motor_information</i>	structure contains motor information

5.1.4.50 **result_t XIMC_API** get_motor_settings (**device_t** id, **motor_settings_t** * motor_settings)

Read motor settings from EEPROM.

Parameters

	<i>id</i>	an identifier of device
out	<i>motor_settings</i>	structure contains motor settings

5.1.4.51 **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

	<i>id</i>	an identifier of device
out	<i>move_settings</i>	structure contains move settings: speed, acceleration, deceleration etc.

5.1.4.52 **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 voltage. These factors are slightly different for different positioners. All boards are supplied with standart set of PID setting on controller's flash memory.

See also

[set_pid_settings](#)

Parameters

	<i>id</i>	an identifier of device
out	<i>pid_settings</i>	pid settings

5.1.4.53 **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

	<i>id</i>	an identifier of device
out	<i>position</i>	structure contains move settings: speed, acceleration, deceleration etc.

5.1.4.54 **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

	<i>id</i>	an identifier of device
out	<i>power_settings</i>	structure contains settings of step motor power control

5.1.4.55 **result_t XIMC_API** get_secure_settings (**device_t** id, **secure_settings_t** * secure_settings)

Read protection settings.

Parameters

	<i>id</i>	an identifier of device
out	<i>secure_settings</i>	critical parameter settings to protect the hardware

See also

`status_t::flags`

5.1.4.56 **result_t XIMC_API** `get_serial_number (device_t id, unsigned int * SerialNumber)`

Read device serial number.

Parameters

	<i>id</i>	an identifier of device
out	<i>serial</i>	serial number

5.1.4.57 **result_t XIMC_API** `get_stage_information (device_t id, stage_information_t * stage_information)`

Read stage information from EEPROM.

Parameters

	<i>id</i>	an identifier of device
out	<i>stage-information</i>	structure contains stage information

5.1.4.58 **result_t XIMC_API** `get_stage_name (device_t id, stage_name_t * stage_name)`

Read user stage name from EEPROM.

Parameters

	<i>id</i>	an identifier of device
out	<i>stage_name</i>	structure contains previously set user stage name

5.1.4.59 **result_t XIMC_API** `get_stage_settings (device_t id, stage_settings_t * stage_settings)`

Read stage settings from EEPROM.

Parameters

	<i>id</i>	an identifier of device
out	<i>stage_settings</i>	structure contains stage settings

5.1.4.60 **result_t XIMC_API** `get_status (device_t id, status_t * status)`

Return device state.

Parameters

	<i>id</i>	an identifier of device
out	<i>status</i>	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](#)

5.1.4.61 **result_t XIMC_API** `get_status_calb (device_t id, status_calb_t * status, const calibration_t * calibration)`

Calibrated device state.

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

See also

[get_status](#)

5.1.4.62 **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 standart set of these settings.

See also

[set_sync_in_settings](#)

Parameters

	<i>id</i>	an identifier of device
out	<i>sync_in_settings</i>	synchronization settings

5.1.4.63 **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 standart set of these settings.

See also

[set_sync_out_settings](#)

Parameters

	<i>id</i>	an identifier of device
out	<i>sync_out_settings</i>	synchronization settings

5.1.4.64 **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

	<i>Speed</i>	UART speed
out	<i>uart_settings</i>	UART settings

5.1.4.65 **result_t XIMC_API** goto_firmware (**device_t** id, uint8_t * ret)

Reboot to firmware.

Parameters

	<i>id</i>	an identifier of device
out	<i>ret</i>	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_ALR-EADY_IN_FIRMWARE, if this command was sent when controller is already in firmware.

5.1.4.66 **result_t XIMC_API** has_firmware (const char * name, uint8_t * ret)

Check for firmware on device.

Parameters

	<i>name</i>	a name of device
out	<i>ret</i>	non-zero if firmware existed

5.1.4.67 **void XIMC_API** logging_callback_stderr_narrow (int loglevel, const wchar_t * message)

Simple callback for logging to stderr in narrow (single byte) chars.

Parameters

<i>loglevel</i>	a loglevel
<i>message</i>	a message

5.1.4.68 **void XIMC_API** logging_callback_stderr_wide (int loglevel, const wchar_t * message)

Simple callback for logging to stderr in wide chars.

Parameters

<i>loglevel</i>	a loglevel
<i>message</i>	a message

5.1.4.69 **void XIMC_API** msec_sleep (unsigned int msec)

Sleeps for a specified amount of time.

Parameters

<i>msec</i>	time in milliseconds
-------------	----------------------

5.1.4.70 **device_t XIMC_API** open_device (const char * name)

Open a device with OS name *name* and return identifier of the device which can be used in calls.

Parameters

in	<i>name</i>	- a device name - e.g. COM3 or /dev/tty.s123
----	-------------	--

5.1.4.71 **result_t XIMC_API** probe_device (const char * name)

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

Be carefully with this call because it sends some data to the device.

Parameters

in	<i>name</i>	- a device name
----	-------------	-----------------

5.1.4.72 **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.

5.1.4.73 **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

	<i>id</i>	an identifier of device
in	<i>accessories_settings</i>	structure contains information about additional accessories

5.1.4.74 **result_t XIMC_API** set_add_sync_in_action (**device_t** id, const **add_sync_in_action_t** * add_sync_in_action)

This command adds one element of the FIFO commands that are executed when input clock pulse.

Each pulse synchronization or perform that action, which is described in SSNI, if the buffer is empty, or the oldest loaded into the buffer action to temporarily replace the speed and coordinate in SSNI. In the latter case this action is erased from the buffer. The number of remaining empty buffer elements can be found in the structure of GETS.

Parameters

	<i>id</i>	an identifier of device
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5.1.4.75 **result_t XIMC_API** set_brake_settings (**device_t** id, const **brake_settings_t** * brake_settings)

Set settings of brake control.

Parameters

	<i>id</i>	an identifier of device
in	<i>brake_settings</i>	structure contains settings of brake control

5.1.4.76 **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

	<i>id</i>	an identifier of device
in	<i>control_settings</i>	structure contains settings motor control by joystick or buttons left/right.

5.1.4.77 **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

	<i>id</i>	an identifier of device
in	<i>controller_name</i>	structure contains previously set user controller name

5.1.4.78 **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

	<i>id</i>	an identifier of device
in	<i>ctp_settings</i>	structure contains settings of control position

5.1.4.79 **result_t XIMC_API** set_edges_settings (**device_t** id, const **edges_settings_t** * edges_settings)

Set border and limit switches settings.

See also

[set_edges_settings](#)

Parameters

	<i>id</i>	an identifier of device
in	<i>edges_settings</i>	edges settings, specify types of borders, motor behaviour and electrical behaviour of limit switches

5.1.4.80 **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

	<i>id</i>	an identifier of device
in	<i>encoder_information</i>	structure contains information about encoder

5.1.4.81 **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

	<i>id</i>	an identifier of device
in	<i>encoder_settings</i>	structure contains encoder settings

5.1.4.82 **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

	<i>id</i>	an identifier of device
in	<i>engine_settings</i>	engine settings

5.1.4.83 **result_t XIMC_API** set_entype_settings (**device_t** id, const **entype_settings_t** * entype_settings)

Set engine type and driver type.

Parameters

	<i>id</i>	an identifier of device
in	<i>EngineType</i>	engine type
in	<i>DriverType</i>	driver type

5.1.4.84 **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

	<i>id</i>	an identifier of device
in	<i>extio_settings</i>	EXTIO settings

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

Set feedback settings.

Parameters

	<i>id</i>	an identifier of device
in	<i>IPS</i>	number of encoder pulses per shaft revolution. Range: 1..65535
in	<i>FeedbackType</i>	type of feedback
in	<i>FeedbackFlags</i>	flags of feedback

5.1.4.86 **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

	<i>id</i>	an identifier of device
in	<i>gear_information</i>	structure contains information about step gearhead

5.1.4.87 **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

	<i>id</i>	an identifier of device
in	<i>gear_settings</i>	structure contains step gearhead settings

5.1.4.88 **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

	<i>id</i>	an identifier of device
in	<i>hallsensor_information</i>	structure contains information about hall sensor

5.1.4.89 **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

	<i>id</i>	an identifier of device
in	<i>hallsensor_settings</i>	structure contains hall sensor settings

5.1.4.90 **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

	<i>id</i>	an identifier of device
in	<i>home_settings</i>	calibrating position settings

5.1.4.91 **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

	<i>id</i>	an identifier of device
<i>in</i>	<i>joystick_settings</i>	structure contains joystick settings

5.1.4.92 void **XIMC_API** set_logging_callback (**logging_callback_t** logging_callback)

Sets a logging callback.

Call resets a callback to default (stderr, syslog) if NULL passed.

Parameters

<i>logging_callback</i>	a callback for log messages
-------------------------	-----------------------------

5.1.4.93 **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

	<i>id</i>	an identifier of device
<i>in</i>	<i>motor_information</i>	structure contains motor information

5.1.4.94 **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

	<i>id</i>	an identifier of device
<i>in</i>	<i>motor_settings</i>	structure contains motor information

5.1.4.95 **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

	<i>id</i>	an identifier of device
<i>in</i>	<i>move_settings</i>	structure contains move settings: speed, acceleration, deceleration etc.

5.1.4.96 **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 voltage. These factors are slightly different for different positioners. All boards are supplied with standart 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

	<i>id</i>	an identifier of device
in	<i>pid_settings</i>	pid settings

5.1.4.97 **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

	<i>id</i>	an identifier of device
out	<i>position</i>	structure contains move settings: speed, acceleration, deceleration etc.

5.1.4.98 **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

	<i>id</i>	an identifier of device
in	<i>power_settings</i>	structure contains settings of step motor power control

5.1.4.99 **result_t XIMC_API** set_secure_settings (**device_t** id, const **secure_settings_t** * secure_settings)

Set protection settings.

Parameters

	<i>id</i>	an identifier of device
	<i>secure_settings</i>	structure with secure data

See also

`status_t::flags`

5.1.4.100 **result.t XIMC_API** set_serial_number (**device.t** id, const **serial_number.t** * serial_number)

Write device serial number to controller's flash memory.

Along with the new serial number a "Key" is transmitted. The SN is changed and saved when keys match. Can be used by manufacturer only.

Parameters

	<i>id</i>	an identifier of device
in	<i>serial</i>	number structure contains new serial number and secret key.

5.1.4.101 **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

	<i>id</i>	an identifier of device
in	<i>stage-information</i>	structure contains stage information

5.1.4.102 **result.t XIMC_API** set_stage_name (**device.t** id, const **stage_name.t** * stage_name)

Write user stage name from EEPROM.

Parameters

	<i>id</i>	an identifier of device
in	<i>stage_name</i>	structure contains previously set user stage name

5.1.4.103 **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

	<i>id</i>	an identifier of device
in	<i>stage_settings</i>	structure contains stage settings

5.1.4.104 **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 standart set of these settings.

See also

[get_sync_in_settings](#)

Parameters

	<i>id</i>	an identifier of device
<i>in</i>	<i>sync_in_settings</i>	synchronization settings

5.1.4.105 **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 standart set of these settings.

See also

[get_sync_out_settings](#)

Parameters

	<i>id</i>	an identifier of device
<i>in</i>	<i>sync_out_settings</i>	synchronization settings

5.1.4.106 **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

	<i>Speed</i>	UART speed
<i>in</i>	<i>uart_settings</i>	UART settings

5.1.4.107 **result.t XIMC_API** write_key (const char * name, uint8_t * key)

Write controller key.

Can be used by manufacturer only

Parameters

	<i>name</i>	a name of device
<i>in</i>	<i>key</i>	protection key. Range: 0..4294967295

5.1.4.108 **result_t XIMC_API** ximc_fix_usbser_sys (const char * device_name)

Fix for errors in Windows USB driver stack.

Resets a driver if a device exists and in a hanged state.

5.1.4.109 void **XIMC_API** ximc_version (char * version)

Returns a library version.

Parameters

<i>version</i>	a buffer to hold a version string, 32 bytes is enough
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