

Thorlabs APT Controllers

Host-Controller Communications Protocol

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Introduction

1. Purpose and Scope

This document describes the low-level communications protocol and commands used between the host PC and controller units within the APT family. The information contained in this document is intended to help third party system developers to write their own applications to interface to the Thorlabs range of controllers without the constraints of using a particular operating system or hardware platform. The commands described here are those which are necessary to control movement; there is an additional set of commands, used for calibration or test, which will not be detailed as these are not required for the external system developer.

2. Electrical interface

The APT family of controllers provides a USB and an RS-232 interface to communicate with the host PC. The communications protocol is identical in both cases but developers wishing to use the USB interface should be aware of the USB enumeration scheme used in the system.

2.1 USB Interface

The electrical interface within the APT controllers uses a Future Technology Devices International (FTDI), type FT232BM USB peripheral chip to communicate with the host PC. This is a USB2.0 compliant USB1.1 device. This USB interfacing chip provides a serial port interface to the embedded system (i.e. APT controller) and USB interface to the host control PC. While the overall communications protocol is independent of the transport layer (for example, Ethernet or serial communications could also be used to carry commands from the host to the controller), the initial enumeration scheme described below is specific to the USB environment.

FTDI supply device drivers and interfacing libraries (for Windows, Linux and other platforms) used to access the USB chip. Before any PC USB communication can be established with an APT controller, the client program is required to set up the necessary FTDI chip serial port settings used to communicate to the APT controller embedded system. Within the APT software itself the following FTDI library calls are made to set up the USB chip serial port for each APT USB device enumerated on the bus:-

```
// Set baud rate to 115200.  
ftStatus = FT_SetBaudRate(m_hFTDevice, (ULONG)uBaudRate);  
  
// 8 data bits, 1 stop bit, no parity  
ftStatus = FT_SetDataCharacteristics(m_hFTDevice, FT_BITS_8, FT_STOP_BITS_1,  
FT_PARITY_NONE);  
  
// Pre purge dwell 50ms.  
Sleep(uPrePurgeDwell);  
  
// Purge the device.  
ftStatus = FT_Purge(m_hFTDevice, FT_PURGE_RX | FT_PURGE_TX);  
  
// Post purge dwell 50ms.  
Sleep(uPostPurgeDwell);
```

```

// Reset device.
ftStatus = FT_ResetDevice(m_hFTDevice);

// Set flow control to RTS/CTS.
ftStatus = FT_SetFlowControl(m_hFTDevice, FT_FLOW_RTS_CTS, 0, 0);

// Set RTS.
ftStatus = FT_SetRts(m_hFTDevice);

```

2.2 USB Device Enumeration

The APT Server PC software supplied is designed to work with a number of different types of controller. The purpose of the enumeration phase is for the host to establish what devices are present in the system and initialise the GUI accordingly. Initially this is done by enumerating the USB devices connected to the system and reading the serial number information contained in the USB device descriptor.

For the Thorlabs range of controllers, this serial number is an 8-digit decimal number. The first two digits (referred to as the prefix) describe the type of controller, while the rest of the digits make up a unique serial number. By extracting the prefix, the host can therefore establish what type of hardware is connected to the system.

In most cases, specifically with benchtop controllers, the USB serial number contains sufficient information for the host to know the exact type of hardware is connected. There is a range of other controller products where several controller cards (without their own individual USB peripheral chip) can be plugged into a motherboard and it is only the motherboard that has USB connectivity. These are generally referred to as a card slot (or bay) type of system (for example, the BSC103 controller). In these systems, a second enumeration state is carried out; however, this second state is done within the protocol framework that will be detailed in this document.

For the controller types, the USB prefixes can be the following:

USB S/N	Type of product	Thorlabs code
20xxxxxx	Legacy single channel stepper driver	BSC001
25xxxxxx	Legacy single channel mini stepper driver	BMS001
30xxxxxx	Legacy dual channel stepper driver	BSC002
35xxxxxx	Legacy dual channel mini stepper driver	BMS002
40xxxxxx	Single channel stepper driver	BSC101
60xxxxxx	OptoSTDriver (mini stepper driver)	OST001
63xxxxxx	OptoDCDriver (mini DC servo driver)	ODC001
70xxxxxx	Three channel card slot stepper driver	BSC103
80xxxxxx	Stepper Driver T-Cube	TST001
83xxxxxx	DC servo driver T-Cube	TDC001
73xxxxxx	Brushless DC motherboard	BBD102/BBD103
94xxxxxx	Brushless DC motor card	BBD102/BBD103

Of these listed above, currently only the BSC103 (serial number prefix 70) and the BBD10x are card slot type of controllers.

2.3 RS-232 Interface

The RS-232 interface uses the 9-way D-Type male connector on the rear panel, marked 'INTERCONNECT'. Communications parameters are fixed at:

- 115200 bits/sec
- 8 data bits, 1 stop bit
- No parity
- No handshake

By nature, the RS-232 interface provides point-to-point communications, and therefore there is no device enumeration as there is with USB based communications.

3. Overview of the Communications Protocol

The communications protocol used in the Thorlabs controllers is based on the message structure that always starts with a fixed length, 6-byte *message header* which, in some cases, is followed by a variable length *data packet*. For simple commands, the 6-byte message header is sufficient to convey the entire command. For more complex commands, for example, when a set of parameters needs to be passed on, the 6 byte header is not enough and in this case the header is followed by the data packet.

The header part of the message always contains information that indicates whether or not a data packet follows the header and if so, the number of bytes that the data packet contains. In this way the receiving process is able to keep tracks of the beginning and the end of messages.

Note that in the section below describing the various byte sequences, the C-type of notation will be used for hexadecimal values (e.g. 0x55 means 55 hexadecimal) and logical operators (e.g. | means logic bitwise OR). Values that are longer than a byte follow the Intel little-endian format.

4. Description of the message header

The 6 bytes in the message header are shown below:

Byte:	byte 0	byte 1	byte 2	byte 3	byte 4	byte 5
Meaning if no data packet to follow	message ID	param1	param2	dest	source	
Meaning if data packet to follow	message ID	data packet length		dest 0x80	source	

The meaning of some of the fields depends on whether or not the message is followed by a data packet. This is indicated by the most significant bit in byte 4, called the destination byte, therefore the receiving process must first check if the MSB of byte 4 is set.

If this bit is not set, then the message is a header-only message and the interpretation of the bytes is as follows:

message ID: describes what the action the message requests
 param1: first parameter (if the command requires a parameter, otherwise 0)

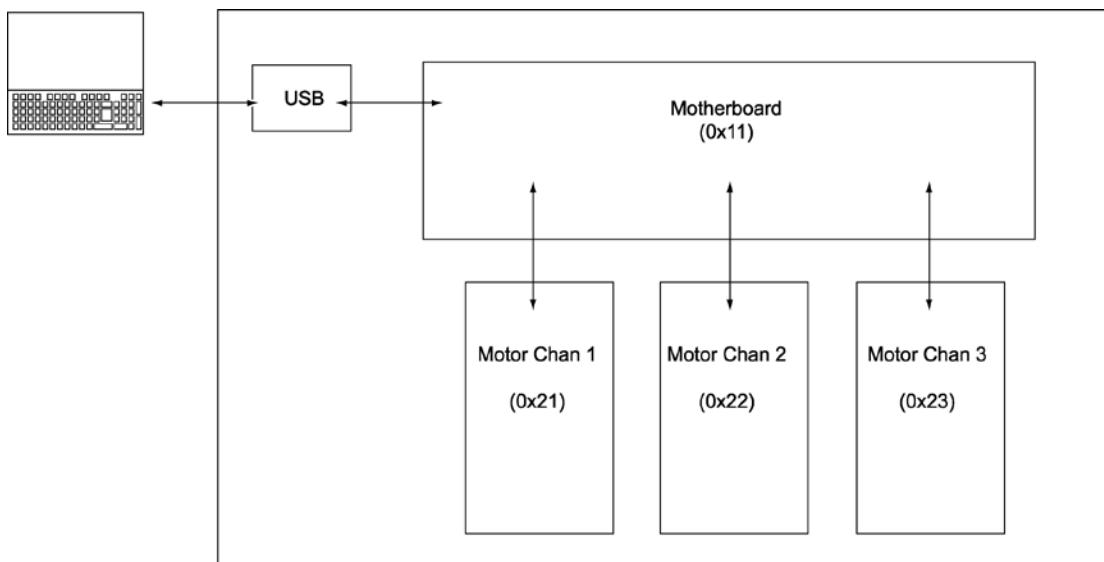
param2: second parameter (if the command requires a parameter, otherwise 0)
 dest: the destination module
 source: the source of the message

The meaning of the source and destination bytes will be detailed later.
 If the MSB of byte 4 is set, then the message will be followed by a data packet and the interpretation of the header is the following:

message ID: describes what the action the message requests
 datapacket length: number of bytes to follow after header
 Note: although this is a 2-byte long field, currently no datapacket exceeds 255 bytes in length.
 dest: | 0x80 the destination module logic OR'd with 0x80 (noted by d|)
 source: the source of the data

The source and destination fields require some further explanation. In general, as the name suggests, they are used to indicate the source and destination of the message. In non-card-slot type of systems the source and destination of messages is always unambiguous, as each module appears as a separate USB node in the system. In these systems, when the host sends a message to the module, it uses the source identification byte of 0x01 (meaning host) and the destination byte of 0x50 (meaning "generic USB unit"). (In messages that the module sends back to the host, the content of the source and destination bytes is swapped.)

In card-slot (bay) type of systems, there is only one USB node for a number of sub-modules, so this simple scheme cannot be used. Instead, the host sends a message to the motherboard that the sub-modules are plugged into, with the destination field of each message indicating which *slot* the message must be routed to. Likewise, when the host receives a message from a particular sub-module, it knows from the source byte which slot is the origin of the message – see Fig below.



Numerically, the following values are currently used for the source and destination bytes:

0x01	Host controller (i.e control PC)
0x11	Rack controller, motherboard in a card slot system or comms router board
0x21	Bay 0 in a card slot system
0x22	Bay 1 in a card slot system
0x23	etc.
0x24	etc.
0x25	etc.
0x26	etc.
...	
0x2A	Bay 9 in a card slot system
0x50	Generic USB hardware unit

In slot-type systems the host can also send messages to the motherboard that the sub-modules are plugged into (destination byte = 0x11). In fact, as a very first step in the communications process, the host must send a message to the motherboard to find out which slots are used in the system.

Note that although in theory this scheme would allow communication between individual sub-modules (the source of the message could be a sub-module and the destination another one), current systems do not use this option.

5. General message exchange rules

The type of messages used in the communications exchange between the host and the sub-modules can be divided into 4 general categories:

- (a) Host issues a command, sub-module carries out the command without acknowledgement (i.e. no response is sent back to the host).

Typically, these are commands which require no information from the sub-module, for example setting the digital outputs to a particular state.

- (b) Host issues a command (message request) and the sub-module responds by sending data back to the host.

For example, the host may request the sub-module to report the state of the digital inputs.

- (c) Following a command from the host, the sub-module periodically sends a message to the host without further prompting.

These messages are referred to as *status update messages*. These are typically sent automatically every 100 msec from the sub-module to the host, showing, amongst other things, the position of the stage the controller is connected to. The meters on the APT User GUI rely on these messages to show the up-to-date status of the stage.

- (d) Rarely – error messages, exceptions. These are spontaneously issued by the sub-module if some error occurs. For example, if the power supply fails in the sub-module, a message is sent to the host PC to inform the user.

Apart from the last two categories (status update messages and error messages), in general the message exchanges follow the SET -> REQUEST -> GET pattern, i.e. for most commands a trio of messages are defined. The SET part of the trio is used by the host (or, sometimes in card-slot systems the motherboard) to set some parameter or other. If then the host requires some information from the sub-module, then it may send a REQUEST for this information, and the sub-module responds with the GET part of the command. Obviously, there are cases when this general scheme does not apply and some part of this message trio is not defined. For consistency, in the description of the messages this SET->REQUEST->GET scheme will be used throughout.

Note that, as the scheme suggests, this is a master-slave type of system, so sub-modules never send SET and REQUEST messages to the host and GET messages are always sent to the host as a destination.

In all messages, where a parameter is longer than a single character, the bytes are encoded in the Intel format, least significant byte first.

6. Format Specifiers

format	encoding
word	Unsigned 16 bit integer (2 bytes) in the Intel (little-endian) format for example decimal 12345 (3039H) is encoded as the byte sequence 39, 30
short	Signed 16 bit integer (2 bytes) in 2's compliment format for example decimal -1 is encoded as the byte sequence FF, FF
dword	Unsigned 32 bit integer (4 bytes) in the Intel (little-endian) format for example decimal 123456789 (75BCD15H) is encoded as the byte sequence 15, CD, 5B, 07
long	Signed 32 bit integer (4 bytes) in 2's compliment format for example decimal -1 is encoded as the byte sequence FF, FF 4 bytes in the Intel (little-endian) format for example decimal -123456789 (FFFFFFF8A432EBH) is encoded as the byte sequence EB, 32, A4, F8,
char	1 byte (2 digits)
char[N]	string of N characters

7. Single Precision Floating Point Format

Single-precision floating-point format is a computer number format that occupies 4 bytes (32 bits) in computer memory and represents a wide dynamic range of values by using a floating point.

Where message parameters use floating point variables, the system uses the IEEE 754 standard.

8. Conversion between position, velocity and acceleration values in standard physical units and their equivalent APT parameters.

To convert between the position and encoder counters in the stage being driven, and real world units, (e.g. mm) the system uses certain conversion (scaling) factors. These conversion factors differ depending on the stage being driven and the controller being used.

Background

The principle described below is the same for all APT motion stepper and brushed or brushless DC controllers and stages, but the individual distance and time conversion factors will be typically different for each stage and/or controller.

In real life, the physical units needed to describe position, velocity and acceleration are related to position and time measurement units (millimetres/degrees and seconds). In motion controllers, however, normally the system only knows the distance travelled in encoder counts (pulses) as measured by an encoder fitted to the motor shaft. In most cases the motor shaft rotation is also scaled down further by a gearbox and a leadscrew. In any case, the result is a scaling factor between encoder counts and position. The value of this scaling factor depends on the stage. In the section below this scaling factor will be represented by the symbol EncCnt.

Time is related to the sampling interval of the system, and as a result, it depends on the motion controller. Therefore, this value is the same for all stages driven by a particular controller. In the sections below the sampling interval will be denoted by T.

The sections below describe the position, velocity and acceleration scaling factors for all the controllers and stages that are used with these controllers. The symbols POS_{APT}, VEL_{APT} and ACC_{APT} are used to denote the position, velocity and acceleration values used in APT commands, whereas the symbols Pos, Vel and Acc denote physical position, velocity and

acceleration values in mm, mm/sec and mm/sec² units for linear stages and degree, degree/sec and degree/sec² for rotational stages.

As APT parameters are integer values, the APT values calculated from the equations need to be rounded to the nearest integer.

Brushed DC Controller (TDC001) driven stages

Mathematically:

$$\text{POS}_{\text{APT}} = \text{EncCnt} \times \text{Pos}$$

$$\text{VEL}_{\text{APT}} = \text{EncCnt} \times T \times 65536 \times \text{Vel}$$

$$\text{ACC}_{\text{APT}} = \text{EncCnt} \times T^2 \times 65536 \times \text{Acc}$$

where $T = 2048 / 6 \times 10^6$

The value of EncCnt and the resulting conversion factors are listed below for each stage:

Stage	EncCnt	Scaling Factor		
		Position	Velocity	Acceleration
MTS25-Z8	34304	34304	767367.49	261.93
MTS50-Z8	34304	34304	767367.49	261.93
PRM1-Z8	1919.64	1919.64	42941.66	14.66
Z8xx	34304	34304	767367.49	261.93
Z6xx	24600	24600	550292.68	187.83

Brushless DC Controller (TBD001, BBD10X and BBD20X) driven stages

Mathematically:

$$\text{POS}_{\text{APT}} = \text{EncCnt} \times \text{Pos}$$

$$\text{VEL}_{\text{APT}} = \text{EncCnt} \times T \times 65536 \times \text{Vel}$$

$$\text{ACC}_{\text{APT}} = \text{EncCnt} \times T^2 \times 65536 \times \text{Acc}$$

where $T = 102.4 \times 10^{-6}$

The value of EncCnt and the resulting conversion factors are listed below for each stage:

Stage	EncCnt	Scaling Factor		
		Position	Velocity	Acceleration
DDSM100	2000	2000	13421.77	1.374
DDS220	20000	20000	134217.73	13.744
DDS300	20000	20000	134217.73	13.744
DDS600	20000	20000	134217.73	13.744
MLS203	20000	20000	134217.73	13.744

Stepper Motor Controller (TST001 BSC00x, BSC10x, MST601) Driven Stages

For these stepper controllers the server sends absolute micro-steps to the controllers. Depending on the stage and the stepper motor concerned there are different micro step values required to move either a linear distance in millimetres or a rotational distance in degrees.

In general for 200 full step motors (the majority of our motors) the above range of stepper controllers is designed to insert 128 micro steps for every full step of the stepper.

So for a 200 full step motor the number of micro steps per full turn is defined as follows

$$\text{Full turn micro steps} = \text{Motor full steps per turn} \times \text{Number of Micro steps per full step}$$

For a 200 full step motor this is given by :-

$$\text{Full turn micro steps} = 200 \times 128 = 25600$$

Each stage can either be a direct drive or driven through a gear box. The table below indicates the relationship between absolute micro steps and a positional output in millimetres or degrees

This table is relevant for the range of controllers listed above. Note that micro step values are for a position is 1mm, a velocity of 1mm/sec and an acceleration of 1mm/sec/sec

Stage	Gearing	Position	Micro Step Values		
			Position(μs)	Velocity(μs/sec)	Acceleration(μs/sec ²)
DRV001	0.5mm/turn	1mm	51200	51200	51200
DRV013	1mm/turn	1mm	25600	25600	25600
DRV014	1mm/turn	1mm	25600	25600	25600
NRT100	1mm/turn	1mm	25600	25600	25600
NRT150	1mm/turn	1mm	25600	25600	25600
LTS150	1mm/turn	1mm	25600	25600	25600
LTS300	1mm/turn	1mm	25600	25600	25600
DRV113	1.25mm/turn	1mm	20480	20480	20480
DRV114	1.25mm/turn	1mm	20480	20480	20480
FW103*	No gear	0.998deg	71	71	71
NR360**	5.4546deg/turn	0.999deg	4693	4693	4693

*Note that there is no exact value of micro steps to get to exactly 1 degree this is because 1 turn represents 360 degrees which is 25600 micro steps. So actual resolution is $360/25600 = 0.0140625$ degrees per micro step.

**Note that there is no exact value of micro steps to get to exactly 1 degree this is because 1 turn represents 5.4546 degrees which is 25600 micro steps. So actual resolution is $5.4546/25600 = 0.0002131$ degrees

Stepper Motor Controller (BSC20x, MST602) Driven Stages

The BSC20x series and MST602 stepper controllers include a Trinamics encoder with a resolution of 409600 micro-steps per revolution.

This table is relevant only for the Trinamic-based range of controllers listed above. Note that micro step values are for a position is 1mm, a velocity of 1mm/sec and an acceleration of 1mm/sec/sec

Or in degrees, deg/sec or deg/sec/sec

Stage	Gearing	Position	Trinamic converted Values		
			Position(μs)	Velocity(μs/sec)	Acceleration(μs/sec ²)
DRV001	0.5mm/turn	1mm	819200	43974656	9012
DRV013	1mm/turn	1mm	409600	21987328	4506
DRV014	1mm/turn	1mm	409600	21987328	4506
NRT100	1mm/turn	1mm	409600	21987328	4506
NRT150	1mm/turn	1mm	409600	21987328	4506
LTS150	1mm/turn	1mm	409600	21987328	4506
LTS300	1mm/turn	1mm	409600	21987328	4506
MLJ050	1mm/turn	1mm	409600	21987328	4506
DRV113	1.25mm/turn	1mm	327680	17589862	3605
DRV114	1.25mm/turn	1mm	327680	17589862	3605
FW103*	No gear	1.0002deg	1138	61088	13
NR360**	5.4546deg/turn	0.99997deg	75091	4030885	826

In the above table the numbers that need to be sent to the controllers are based upon the Trinamics chip set conversions. The position is just the absolute number of micro-steps as before, as compared with the BSC10X range, the only difference is the 16 times greater resolution. However for velocity and acceleration now need different conversion factors to get to correct motion profiles. For example, if a velocity of 409600 micro-steps per sec is required, then multiply by 53.68 i.e. $409600 * 53.68$ gives 21987328 which for a 1mm lead screw would give 1mm/sec.

To accelerate at a rate of 409600 micro-steps/sec/sec (1mm/sec/sec), divide 409600 by 90.9 which gives 4506.

Generic System Control Messages

Introduction

The messages described here are either system control messages, or else generic messages which apply to several or all controller types. Please see the list of controller specific commands for details on applicability to a specific controller type.

MGMSG_MOD_IDENTIFY**0x0223**

Function: Instruct hardware unit to identify itself (by flashing its front panel LEDs).

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
23	02	00	00	d	s

Example: Identify controller #1 (i.e. bay 0 of the TDC001 controller) by flashing its front panel LED.

TX 23, 02, 00, 00, 21, 01

MGMSG_MOD_SET_CHANENABLESTATE	0x0210
MGMSG_MOD_REQ_CHANENABLESTATE	0x0211
MGMSG_MOD_GET_CHANENABLESTATE	0x0212

Function Sent to enable or disable the specified drive channel.

SET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
10	02	Chan Ident	Enable State	d	s

Channel Idents

0x01 channel 1

0x02 channel 2

Enable States

0x01 enable channel

0x02 disable channel

For single channel controllers such as the BBD10X, TDC001, the Chan Ident byte is always set to CHAN1.

Note: Although the BBD102 is in fact a 2-channel controller, ‘channel’ in this sense means “motor output channel within this module”. Electrically, the BBD102 is a bay system, with two bays, each of them being a single channel controller, so only one channel can be addressed. There are controllers in the Thorlabs product range which indeed have multiple output channels (for example the MST601 module) for which the channel ident is used to address a particular channel.

Example: Enable the motor channel in bay 2

TX 10, 02, 01, 01, 22, 01

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
11	02	Chan Ident	0	d	s

As above, for single channel controllers such as the BBD10X, TDC001, the Chan Ident byte is always set to CHAN1.

GET:

Response structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
12	02	Chan Ident	Enable State	d	s

The meaning of the parameter bytes “Chan Ident” and “Enable State” is the same as for the SET version of the commands.

MGMSG_HW_DISCONNECT**0x0002**

Function: Sent by the hardware unit or host when either wants to disconnect from the Ethernet/USB bus.

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
02	00	00	00	d	s

Example: Disconnect the BBD103 from the USB bus

TX 02, 00, 00, 00, 11, 00

MGMSG_HW_RESPONSE**0x0080**

Function: Sent by the controllers to notify APT Server of some event that requires user intervention, usually some fault or error condition that needs to be handled before normal operation can resume. The message transmits the fault code as a numerical value – see Return Codes.

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
80	00	00	00	d	s

Example: The BBD103 unit has encountered an over current condition

TX 80, 00, 00, 00, 01, 11

MGMSG_HW_RICHRESPONSE**0x0081**

Function: Similarly to HW_RESPONSE, this message is sent by the controllers to notify APT Server of some event that requires user intervention, usually some fault or error condition that needs to be handled before normal operation can resume. However unlike HW_RESPONSE, this message also transmits a printable text string. Upon receiving the message, APT Server displays both the numerical value and the text information, which is useful in finding the cause of the problem.

REQ:

Response structure (74 bytes):

6 byte header followed by 68 byte (0x44) data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15
<i>header</i>						<i>data</i>									
81	00	44	00	d	s	MsgIdent	Code	<-----Notes----->							
16	17	18	19	20	21	22	23	24	25	26	27	28	29	30	31
<i>data</i>								-----Notes----->							
32	33	34	35	36	37	38	39	40	41	42	43	44	45	46	47
<i>data</i>								-----Notes----->							
48	49	50	51	52	53	54	55	56	57	58	59	60	61	62	63
<i>data</i>								-----Notes----->							
64	65	66	67	68	69	70	71	72	73						
<i>data</i>								-----Notes----->							

Data structure:

field	description	format
MsgIdent	If the message is sent in response to an APT message, these bytes show the APT message number that evoked the message. Most often though the message is transmitted as a result of some unexpected fault condition, in which case these bytes are 0x00, 0x00	word
Code	This is an internal Thorlabs specific code that specifies the condition that has caused the message (see Return Codes).	word]
Notes	This is a zero-terminated printable (ascii) text string that contains the textual information about the condition that has occurred. For example: "Hardware Time Out Error".	char[64 bytes]

MGMSG_HW_START_UPDATEMSGS**0x0011**

Function: Sent to start status updates from the embedded controller. Status update messages contain information about the position and status of the controller (for example limit switch status, motion indication, etc). The messages will be sent by the controller periodically until it receives a STOP STATUS UPDATE MESSAGES command. In applications where spontaneous messages (i.e. messages which are not received as a response to a specific command) must be avoided the same information can also be obtained by using the relevant GET_STATUTSUPDATES function.

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
11	00	Update Rate	Unused	d	s

The first data byte can be used to specify the update rate with which status updates are received from the controller. However, the parameter is ignored for the BBD101/102/103 controllers and the update rate is fixed at 10 regardless of the parameter sent.

REQUEST: N/A

MGMSG_HW_STOP_UPDATEMSGS**0x0012**

Function: Sent to stop status updates from the controller – usually called by a client application when it is shutting down, to instruct the controller to turn off status updates to prevent USB buffer overflows on the PC.

SET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
12	00	00	00	d	s

REQUEST: N/A

GET: N/A

MGMSG_HW_REQ_INFO
MGMSG_HW_GET_INFO
0x0005
0x0006

Function: Sent to request hardware information from the controller.

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
05	00	00	00	d	s

Example: Request hardware info from controller #1

TX 05, 00, 00, 00, 11, 01

GET:

Response structure (90 bytes):

6 byte header followed by 84 byte (0x54) data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15						
<i>header</i>						<i>data</i>															
06	00	54	00	d	s	<-Serial Number >	<-----Model Number----->														
16	17	18	19	20	21	22	23	24	25	26	27	28	29	30	31						
<i>data</i>																					
<Model> No		<Type>		<Firmware> Version >			<-----Notes----->														
32	33	34	35	36	37	38	39	40	41	42	43	44	45	46	47						
<i>data</i>																					
<----- Notes ----->																					
48	49	50	51	52	53	54	55	56	57	58	59	60	61	62	63						
<i>data</i>																					
<----- Notes ----->																					
64	65	66	67	68	69	70	71	72	73	74	75	76	77	78	79						
<i>data</i>																					
<----- Notes ----->								Empty Space													
80	81	82	83	84	85	86	87	88	89												
<i>data</i>																					
<----- Empty Space ----->				HW Version		Mod State		<-nchs-->													

Data structure:

field	description	format
serial number	unique 8-digit serial number	long
model number	alphanumeric model number	char[8]
type	hardware type: 45 = multi-channel controller motherboard 44 = brushless DC controller	word
firmware version	firmware version byte[20] = minor revision number byte[21] = interim revision number byte[22] = major revision number byte[23] = unused	byte[4]
notes	arbitrary alphanumeric information string	char[48]
Empty Space	Not Used	byte [12]
HW Version	The hardware version number	word
Mod State	The modification state of the hardware	word
nchs	number of channels	word

Example:

Returned hardware info from controller #1

RX 06, 00, 54, 00, 81, 22, 89, 53, 9A, 05, 49, 4F, 4E, 30, 30, 31, 20, 00, 2C, 00, 02, 01, 39, 00, 42, 72, 75, 73, 68, 6C, 65, 73, 73, 20, 44, 43, 20, 4D, 6F, 74, 6F, 72, 20, 49, 4F, 4E, 20, 44, 72, 69, 76, 65, 00, 00..., 11, 00, 01, 00, 00, 00, 01, 00

Header: 06, 00, 54, 00, 81, 22: Get Info, 54H (84) byte data packet, Motor Channel 2.

Serial Number: 89, 53, 9A, 05: 94000009

Model Number: 49, 4F, 4E, 30, 30, 31, 20, 00: ION001

Type: 2C, 00: 44 – Brushless DC Controller Card

firmware Version: 02, 01, 39, 00: 3735810

Notes: 42, 72, 75, 73, 68, 6C, 65, 73, 73, 20, 44, 43, 20, 4D, 6F, 74, 6F, 72, 20, 49, 4F, 4E, 20, 44, 72, 69, 76, 65, 00...: BRUSHLESS DC MOTOR ION DRIVE.....

Empty Space: 00, 00, 00, 00, 00, 00, 00, 00, 00, 00, 00, 00, 00, 00, 00, 00

HW Version: 01, 00 Hardware version 01

Mod State: 03, 00, Modification stage 03.

No Chan: 01, 00: 1 active channel

MGMSG_RACK_REQ_BAYUSED	0x0060
MGMSG_RACK_GET_BAYUSED	0x0061

Function: Sent to determine whether the specified bay in the controller is occupied.

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
60	00	Bay Ident	00	d	s

Bay Idents

- 0x01 Bay 1
- 0x02 Bay 2 to
- 0x09 Bay 10

Example: Is controller bay #1 (i.e. bay 0) occupied

TX 60, 00, 00, 00, 11, 01

GET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
61	00	Bay Ident	Bay State	d	s

Bay Idents

- 0x01 Bay 1
- 0x02 Bay 2 to
- 0x09 Bay 10

Bay States

- 0x01 Bay Occupied
- 0x02 Bay Empty (Unused)

Example: Controller bay #1 (i.e. bay 0) is occupied

RX 61, 00, 00, 01, 11, 01

MGMSG_HUB_REQ_BAYUSED
MGMSG_HUB_GET_BAYUSED

0x0065
0x0066

Function: Sent to determine which bay a specific T-Cube is fitted.

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
65	00	00	00	d	s

TX 65, 00, 00, 00, 50, 01

GET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
66	00	Bay Ident	00	d	s

Bay Idents

- 0x01 T-Cube being standalone, i.e. off the hub.
- 0x00 T-Cube on hub, but bay unknown
- 0x01 Bay 1
- 0x02 Bay 2 to
- 0x06 Bay 6

Example: Which hub bay is the T-Cube unit fitted

RX 66, 00, 06, 00, 01, 50

MGMSG_RACK_REQ_STATUSBITS
MGMSG_RACK_GET_STATUSBITS
0x0226
0x0227

This method is applicable only to the MMR modular rack, and 2- and 3-channel card slot type controllers such as the BSC103 and BPC202.

Function: The USER IO connector on the rear panel of these units exposes a number of digital inputs. This function returns a number of status flags pertaining to the status of the inputs on the rack modules, or the motherboard of the controller unit hosting the single channel controller card.
 These flags are returned in a single 32 bit integer parameter and can provide additional useful status information for client application development. The individual bits (flags) of the 32 bit integer value are described below.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
26	02	Status Bits	00	d	s

GET:

Response structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	7	8	9	10
<i>header</i>						<i>Data</i>			
27	02	04	00	d	s	StatusBits			

Data Structure:

field	description	format
StatusBits	The status bits for the associated controller channel. The meaning of the individual bits (flags) of the 32 bit integer value will depend on the controller and are described in the following table.	dword

Hex Value	Bit Number	Description
0x00000001	1	Digital output 1 state (1 - logic high, 0 - logic low).
0x00000002	2	Digital output 2 state (1 - logic high, 0 - logic low).
0x00000004	3	Digital output 3 state (1 - logic high, 0 - logic low).
0x00000008	4	Digital output 4 state (1 - logic high, 0 - logic low).

Example: With destination being 0x11 (motherboard – see Introduction) and bay being bay 1, slot 2 (0x22)

TX 27, 02, 04, 00, 01, 22, 00, 00, 00

Header: 27, 02, 04, 00, 01, 22: GetStatusBits, 04 byte data packet, bay 1 slot 2.

MGMSG_RACK_SET_DIGOUTPUTS	0x0228
MGMSG_RACK_REQ_DIGOUTPUTS	0x0229
MGMSG_RACK_GET_DIGOUTPUTS	0x0230

This method is applicable only to the MMR rack modules, and 2- and 3-channel card slot type controllers such as the BSC103 and BPC202.

Function: The USER IO connector on the rear panel of these units exposes a number of digital outputs. These functions set and return the status of the outputs on the rack modules, or the motherboard of the controller unit hosting the single channel controller card. These flags are returned in a single 32 bit integer parameter and can provide additional useful status information for client application development. The individual bits (flags) of the 32 bit integer value are described below.

SET:

Data structure (6 bytes)

0	1	2	3	4	5
<i>header only</i>					
28	02	Dig OP	00	d	s

Hex Value	Bit Number	Description
0x00000001	1	Digital input 1 state (1 - logic high, 0 - logic low).
0x00000002	2	Digital input 2 state (1 - logic high, 0 - logic low).
0x00000004	3	Digital input 3 state (1 - logic high, 0 - logic low).
0x00000008	4	Digital input 4 state (1 - logic high, 0 - logic low).

Example: With destination being 0x11 (motherboard – see Introduction) and bay being bay 1, slot 2 (0x22), set Digital output 1 high

TX 28, 02, 01, 22, 11, 01,

Header: 28, 02, 01, 22, 11, 01: SetDigOutputs, 01 OP1 High, bay 1 slot 2, d=motherboard, s=PC.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
29	02	00	00	d	s

GET:

Response structure (6 bytes)

0	1	2	3	4	5
<i>header only</i>					
30	02	00	00	d	s

See SET above for structure

MGMSG_MOD_SET_DIGOUTPUTS	0x0213
MGMSG_MOD_REQ_DIGOUTPUTS	0x0214
MGMSG_MOD_GET_DIGOUTPUTS	0x0215

Function: The CONTROL IO connector on the rear panel of the unit exposes a number of digital outputs. The number of outputs available depends on the type of unit. This message is used to configure these digital outputs.

SET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
00	05	Bit	00	d	s

Note. On brushless DC controllers (e.g. BBD201), the digital output and trigger output use a common pin. Before calling this message to set the digital output, the trigger functionality must be disabled by calling the [Set Trigger](#) message.

The outputs are set (and returned) in the bits of the Bits parameter, input No 1 being the least significant bit and input No 4 being the most significant. The number of bits used is dependent on the number of digital outputs present on the associated hardware unit.

For example, to turn on the digital output on a BSC201 motor controller, the least significant bit of the Bits parameter should be set to 1. Similarly, to turn on all four digital outputs on a BNT001 NanoTrak unit, the bits of the Bits parameter should be set to 1111 (15), and to turn the same outputs off, the Bits should be set to 0000.

Example: Set the digital input of the BSC201 controller on:

TX 13, 02, 01, 00, 50, 01

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
14	02	Bits	00	d	s

GET:

Response structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
15	02	Bit	00	d	s

For structure see SET message above.

Motor Control Messages

Introduction

The ‘Motor’ messages provide the functionality required for a client application to control one or more of the Thorlabs series of motor controller units. This range of motor controllers covers DC servo and stepper drivers in a variety of formats including compact Cube type controllers, benchtop units and 19" rack based modular drivers. Note for ease of description, the TSC001 T-Cube Solenoid Controller is considered here as a motor controller. The list of controllers covered by the motor messages includes:

BSC001 – 1 Channel Benchtop Stepper Driver
BSC002 – 2 Channel Benchtop Stepper Driver
BMS001 – 1 Channel Benchtop Low Power Stepper Driver
BMS002 – 2 Channel Benchtop Low Power Stepper Driver
MST601 – 2 Channel Modular Stepper Driver
MST602 – 2 Channel Modular Stepper Driver (2013 onwards)
BSC101 – 1 Channel Benchtop Stepper Driver (2006 onwards)
BSC102 – 2 Channel Benchtop Stepper Driver (2006 onwards)
BSC103 – 3 Channel Benchtop Stepper Driver (2006 onwards)
BSC201 – 1 Channel Benchtop Stepper Driver (2012 onwards)
BSC202 – 2 Channel Benchtop Stepper Driver (2012 onwards)
BSC203 – 3 Channel Benchtop Stepper Driver (2012 onwards)
BBD101 – 1 Channel Benchtop Brushless DC Motor Driver
BBD102 – 2 Channel Benchtop Brushless DC Motor Driver
BBD103 – 3 Channel Benchtop Brushless DC Motor Driver
BBD201 – 1 Channel Benchtop Brushless DC Motor Driver
BBD202 – 2 Channel Benchtop Brushless DC Motor Driver
BBD203 – 3 Channel Benchtop Brushless DC Motor Driver
OST001 – 1 Channel Cube Stepper Driver
ODC001 – 1 Channel Cube DC Servo Driver
TST001 – 1 Channel T-Cube Stepper Driver
TDC001 – 1 Channel T-Cube DC Servo Driver
TSC001 – 1 Channel T-Cube Solenoid Driver
TDIx – 2 Channel Brushless DC Motor Driver

The motor messages can be used to perform activities such as homing stages, absolute and relative moves, changing velocity profile settings and operation of the solenoid state (TSC001 T-Cube). With a few exceptions, these messages are generic and apply equally to both single and dual channel units.

Where applicable, the target channel is identified in the Chan Ident parameter and on single channel units, this must be set to CHAN1_ID. On dual channel units, this can be set to CHAN1_ID, CHAN2_ID or CHANBOTH_ID as required.

For details on the operation of the motor controller, and information on the principles of operation, refer to the handbook supplied with the unit.

MGMSG_HW_YES_FLASH_PROGRAMMING**0x0017**

Function: This message is sent by the server on start up, however, it is a deprecated message (i.e. has no function) and can be ignored.

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
17	00	Unused	Unused	d	s

REQUEST: N/A

MGMSG_HW_NO_FLASH_PROGRAMMING**0x0018**

Function: This message is sent on start up to notify the controller of the source and destination addresses. A client application must send this message as part of its initialization process.

SET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
18	00	00	00	d	s

REQUEST: N/A

GET: N/A

MGMSG_MOT_SET_POSCOUNTER	0x0410
MGMSG_MOT_REQ_POSCOUNTER	0x0411
MGMSG_MOT_GET_POSCOUNTER	0x0412

Function: Used to set the ‘live’ position count in the controller. In general, this command is not normally used. Instead, the stage is homed immediately after power-up (at this stage the position is unknown as the stage is free to move when the power is off); and after the homing process is completed the position counter is automatically updated to show the actual position. From this point onwards the position counter always shows the actual absolute position.

SET:

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
10	04	06	00	d	s	Chan Ident			Position		

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Position	The new value of the position counter as a 32-bit signed integer, encoded in the Intel format. The scaling between real time values and this parameter is detailed in section 7.1.	long

Example: MLS203 and BBD102: Set the position counter for channel 2 to 10.0 mm

TX 10, 04, 06, 00, A2, 01, 01, 00, 40, 0D, 03, 00

*Header: 10, 04, 06, 00, A2, 01: SetPosCounter, 06 byte data packet, Channel 2.**Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)**Position: 40, 0D, 03, 00: Set Counter to 10 mm (10 x 20,000)***REQUEST:**

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
11	04	Chan Ident	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
12	04	06	00	d	s	Chan Ident			Position		

For structure see SET message above.

MGMSG_MOT_SET_ENCCOUNTER	0x0409
MGMSG_MOT_REQ_ENCCOUNTER	0x040A
MGMSG_MOT_GET_ENCCOUNTER	0x040B

Function: Similarly to the PosCounter message described previously, this message is used to set the encoder count in the controller and is only applicable to stages and actuators fitted with an encoder. In general, this command is not normally used. Instead, the stage is homed immediately after power-up (at this stage the position is unknown as the stage is free to move when the power is off); and after the homing process is completed the position counter is automatically updated to show the actual position. From this point onwards the encoder counter always shows the actual absolute position.

SET:

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
09	04	06	00	d	s	Chan Ident		Encoder Count			

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Encoder Count	The new value of the encoder counter as a 32-bit signed integer, encoded in the Intel format. The scaling between real time values and this parameter is detailed in section 7.1.	long

Example: MLS203 and BBD102: Set the encoder counter for channel 2 to 10.0 mm

TX 09, 04, 06, 00, A2, 01, 01, 00, 40, 0D, 03, 00

*Header: 09, 04, 06, 00, A2, 01: SetEncCounter, 06 byte data packet, Channel 2.**Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)**Position: 40, 0D, 03, 00: Set Counter to 10 mm (10 x 20,000)***REQUEST:**

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
11	04	Chan Ident	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
0B	04	06	00	d	s	Chan Ident			Encoder Count		

For structure see SET message above.

MGMSG_MOT_SET_VELPARAMS	0x0413
MGMSG_MOT_REQ_VELPARAMS	0x0414
MGMSG_MOT_GET_VELPARAMS	0x0415

Function: Used to set the trapezoidal velocity parameters for the specified motor channel. For DC servo controllers, the velocity is set in encoder counts/sec and acceleration is set in encoder counts/sec/sec.
For stepper motor controllers the velocity is set in microsteps/sec and acceleration is set in microsteps/sec/sec.

SET:

Command structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
13	04	OE	00	d	s	Chan Ident			Min Velocity		
12	13	14	15	16	17	18	19				
<i>Data</i>											
Acceleration				Max Velocity							

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Minimum (Start) Vel	The minimum (start) velocity in encoder counts/sec Currently, this 4 byte value is always zero	long
Acceleration	The acceleration in encoder counts /sec/sec. 4 byte unsigned long value. If applicable, the scaling between real time values and this parameter is detailed in section 7.1.	long
Maximum Vel	The maximum (final) velocity in encoder counts /sec. 4 byte unsigned long value. If applicable, the scaling between real time values and this parameter is detailed in section 7.1.	long

Example: MLS203 and BBD102: Set the trapezoidal velocity parameters for chan 2 as follows:

Min Vel: zero
Acceleration: 10 mm/sec/sec
Max Vel: 99 mm/sec

TX 13, 04, OE, 00, A2, 01, 01, 00, 00, 00, 00, B0, 35, 00, 00, CD, CC, CC, 00

Header: 13, 04, OE, 00, A2, 01: Set Vel Params, OEH (14) byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

Min Vel: 00, 00, 00, 00: Set min velocity to zero

Accel: 89, 00, 00, 00: Set acceleration to 10 mm/sec/sec (13.744 x 10)

Max Vel: 9E, C0, CA, 00: Set max velocity to 99 mm/sec (134218 x 99)

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
14	04	Chan Ident	00	d	s

GET:

Response structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
15	04	0E	00	d	s	Chan Ident	Min Velocity				
12	13	14	15	16	17	18	19	<i>Data</i>			
Acceleration				Max Velocity							

For structure see SET message above.

MGMSG_MOT_SET_JOGPARAMS	0x0416
MGMSG_MOT_REQ_JOGPARAMS	0x0417
MGMSG_MOT_GET_JOGPARAMS	0x0418

Function: Used to set the velocity jog parameters for the specified motor channel, For DC servo controllers, values set in encoder counts. For stepper motor controllers the values is set in microsteps.

SET:

Command structure (28 bytes)

6 byte header followed by 22 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
16	04	16	00	d	s	Chan Ident	Jog Mode	Jog Step Size			
12	13	14	15	16	17	18	19	20	21		
<i>Data</i>											
Jog Step Size	Jog Min Velocity				Jog Acceleration						
22	23	24	25	26	27						
<i>Data</i>											
Jog Max Velocity	Stop Mode										

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Jog Mode	This 2 byte value can be 1 for continuous jogging or 2 for single step jogging. In continuous jogging mode the movement continues for as long as the jogging trigger (the jogging button on the GUI or an external signal) is being active. In single step mode triggering jogging initiates a single move whose step size is defined as the next parameter (see below).	word
Jog Step Size	The jog step size in encoder counts. The scaling between real time values and this parameter is detailed in section 7.1.	long
Jog Min Velocity	The minimum (start) velocity in encoder counts /sec. Currently, this 4 byte value is always zero.	long
Jog Acceleration	The acceleration in encoder counts /sec/sec The scaling between real time values and this parameter is detailed in section 7.1.	long
Jog Max Velocity	The maximum (final) velocity in encoder counts /sec. The scaling between real time values and this parameter is detailed in section 7.1.	long
Jog Stop Mode	The stop mode. This 16 bit word can be 1 for immediate (abrupt) stop or 2 for profiled stop (with controlled deceleration).	word

Example: MLS203 and BBD102: Set the jog parameters for channel 2 as follows:
 Jog Mode: Continuous
 Jog Step Size: 0.05 mm
 Jog Min Vel: Zero
 Jog Accel: 10 mm/sec/sec
 Jog Max Vel: 99 mm/sec
 Jog Stop Mode: Profiled

TX 16, 04, 16, 00, A2, 01, 01, 00, 01, 00, E8, 03, 00, 00, 00, 00, 00, B0, 35, 00, 00, CD, CC,
 CC, 00, 02, 00

Header: 16, 04, 16, 00, A2, 01: Set Jog Params, 16H (28) byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

Jog Mode: 01,00,: Set jog mode to ‘continuous’

Jog Step Size: E8, 03, 00, 00: Set jog step size to 0.05 mm (1,000 encoder counts).

Jog Min Vel: 00, 00, 00, 00: Set min jog velocity to zero

Jog Accel: 89, 00, 00, 00: Set acceleration to 10 mm/sec/sec (13.744 x 10)

Jog Max Vel: 9E, C0, CA, 00: Set max velocity to 99 mm/sec (134218 x 99)

Jog Stop Mode: 02, 00: Set jog stop mode to ‘Profiled Stop’.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
17	04	Chan Ident	00	d	s

GET:

Response structure (28 bytes)

6 byte header followed by 22 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
18	04	16	00	d	s	Chan Ident	Jog Mode	Jog Step Size			
12	13	14	15	16	17	18	19	20	21		
<i>Data</i>						<i>Jog Min Velocity</i>					
22	23	24	25	26	27						
<i>Data</i>						<i>Jog Acceleration</i>					
<i>Jog Max Velocity</i>						<i>Stop Mode</i>					

For structure see SET message above.

MGMSG_MOT_REQ_ADCINPUTS
MGMSG_MOT_GET_ADCINPUTS
0x042B
0x042C

Function: This message reads the voltage applied to the analog input on the rear panel CONTROL IO connector, and returns a value in the ADCInput1 parameter. The returned value is in the range 0 to 32768, which corresponds to zero to 5 V.

Note. The ADCInput2 parameter is not used at this time. In this way, a 0 to 5V signal generated by a client system could be read in by calling this method and monitored by a custom client application. When the signal reaches a specified value, the application could instigate further actions, such as a motor move.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
2B	04	Chan Ident	00	d	s

GET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
2B	04	04	00	d	s	ADCInput1	ADCInput2		

Data Structure:

field	description	format
ADCInput1	The voltage state of the analog input pin, in the range 0 to 32768, which corresponds to zero to 5 V.	word
ADCInput2	Not used	word

Example: Get the ADC input state

RX 2C, 04, 04, 00, A2, 01, 01, 00, 00,

Header: 2B, 04, 04, 00, A2, 01: GetADCInputs, 04 byte data packet, Channel 2.

ADCInput1: 00, 80: ADC Input 1 = 5V

ADCInput2: 00, 00: Not Used r

MGMSG_MOT_SET_POWERPARAMS	0x0426
MGMSG_MOT_REQ_POWERPARAMS	0x0427
MGMSG_MOT_GET_POWERPARAMS	0x0428

Note for BSC20x, MST602 and TST101 controller users

If the controllers listed above are used with APTServer, the ini file will typically have values set of 5 for the rest power and 30 for the move power. Although these values are loaded when the server boots only the rest power value is used. This allows the user to set the rest current as normal. The move power however is not used. The move power is set within the controller as a function of velocity. This command can be used only to set the rest power. The command MGMSG_MOT_REQ_POWERPARAMS will return the default values or the values that were set.

Function: The power needed to hold a motor in a fixed position is much smaller than that required for a move. It is good practice to decrease the power in a stationary motor in order to reduce heating, and thereby minimize thermal movements caused by expansion. This message sets a reduction factor for the rest power and the move power values as a percentage of full power. Typically, move power should be set to 100% and rest power to a value significantly less than this.

SET:

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
26	04	06	00	d	s	Chan Ident	RestFactor	MoveFactor			

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
RestFactor	The phase power value when the motor is at rest, in the range 1 to 100 (i.e. 1% to 100% of full power).	word
MoveFactor	The phase power value when the motor is moving, in the range 1 to 100 (i.e. 1% to 100% of full power).	word

Example: Set the phase powers for channel 2 for TST001 unit

TX 26, 04, 06, 00, A2, 01, 01, 00, 0A, 00, 64, 00

*Header: 26, 04, 06, 00, A2, 01: SetPowerParams, 06 byte data packet, Channel 2.**Chan Ident: 01, 00: Channel 1 (always set to 1 for TST001)**RestFactor: 0A, 00: Set rest power to 10% of full power**MoveFactor: 64, 00: Set move power to 100% of full power***REQUEST:**

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
27	04	Chan Ident	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
28	04	06	00	d	s	Chan Ident	RestFactor	MoveFactor			

For structure see SET message above.

MGMSG_MOT_SET_GENMOVEPARAMS	0x043A
MGMSG_MOT_REQ_GENMOVEPARAMS	0x043B
MGMSG_MOT_GET_GENMOVEPARAMS	0x043C

Function: Used to set the general move parameters for the specified motor channel. At this time this refers specifically to the backlash settings.

SET:

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
3A	04	06	00	d	s	Chan Ident		Backlash Distance			

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Backlash Distance	The value of the backlash distance as a 4 byte signed integer, which specifies the relative distance in position counts. The scaling between real time values and this parameter is detailed in section 7.1.	long

Example: MLS203 and BBD102: Set the backlash distance for chan 2 to 1 mm:

TX 3A, 04, 06, 00, A2, 01, 01, 00, 20, 4E, 00, 00,

Header: 3A, 04, 06, 00, A2, 01: SetGenMoveParams, 06 byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

Backlash Dist: 20, 4E, 00, 00: Set backlash distance to 1 mm (20,000 encoder counts).

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
3B	04	Chan Ident	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
3C	04	06	00	d	s	Chan Ident		Backlash Distance			

For structure see SET message above.

MGMSG_MOT_SET_MOVERELPARAMS	0x0445
MGMSG_MOT_REQ_MOVERELPARAMS	0x0446
MGMSG_MOT_GET_MOVERELPARAMS	0x0447

Function: Used to set the relative move parameters for the specified motor channel. The only significant parameter at this time is the relative move distance itself. This gets stored by the controller and is used the next time a relative move is initiated.

SET:

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
45	04	06	00	d	s	Chan Ident	Relative Distance				

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Relative Distance	The distance to move. This is a 4 byte signed integer that specifies the relative distance in position encoder counts. The scaling between real time values and this parameter is detailed in section 7.1.	long

Example: MLS203 and BBD102: Set the relative move distance for chan 2 to 10 mm:

TX 45, 04, 06, 00, A2, 01, 01, 00, 40, 0D, 03, 00,

Header: 45, 04, 06, 00, A2, 01: SetMoveRelParams, 06 byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

Rel Dist: 40, 0D, 03, 00: Set relative move distance to 10 mm (10 x 20,000 encoder counts).

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
46	04	Chan Ident	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
47	04	06	00	d	s	Chan Ident	Relative Distance				

For structure see SET message above.

MGMSG_MOT_SET_MOVEABSPARAMS	0x0450
MGMSG_MOT_REQ_MOVEABSPARAMS	0x0451
MGMSG_MOT_GET_MOVEABSPARAMS	0x0452

Function: Used to set the absolute move parameters for the specified motor channel. The only significant parameter at this time is the absolute move position itself. This gets stored by the controller and is used the next time an absolute move is initiated.

SET:

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
50	04	06	00	d	s	Chan Ident		Absolute Position			

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Absolute Position	The absolute position to move. This is a 4 byte signed integer that specifies the absolute position in position encoder counts. The scaling between real time values and this parameter is detailed in section 7.1.	long

Example: MLS203 and BBD102: Set the absolute move position for chan 2 to 10 mm:

TX 50, 04, 06, 00, A2, 01, 01, 00, 40, 0D, 03, 00,

Header: 50, 04, 06, 00, A2, 01: SetMoveAbsParams, 06 byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

Abs Pos: 40, 0D, 03, 00: Set absolute move position to 10 mm (200,000 encoder counts).

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
51	04	Chan Ident	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
52	04	06	00	d	s	Chan Ident		Absolute Position			

For structure see SET message above.

MGMSG_MOT_SET_HOMEPARAMS	0x0440
MGMSG_MOT_REQ_HOMEPARAMS	0x0441
MGMSG_MOT_GET_HOMEPARAMS	0x0442

Function: Used to set the home parameters for the specified motor channel.
These parameters are stage specific and for the MLS203 stage implementation the only parameter that can be changed is the homing velocity.

SET:

Command structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
40	04	OE	00	d	s	Chan Ident	Home Dir	Limit Switch			

12	13	14	15	16	17	18	19
<i>Data</i>							
Home Velocity						Offset Distance	

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Home Direction	Ignored in this implementation. Homing direction is always positive.	word
Limit Switch	Ignored in this implementation. The limit switches are not used for homing.	word
Home Velocity	The homing velocity. A 4 byte unsigned long value. The scaling between real time values and this parameter is detailed in section 7.1.	long
Offset Distance	Not used in this implementation.	long

Example: MLS203 and BBD102: Set the home parameters for chan 2 as follows:
 Home Direction: Not used (always positive).
 Limit Switch: Not used
 Home Vel: 24 mm/sec
 Offset Dist: Not used.

TX 40, 04, 0E, 00, A2, 01, 01, 00, 00, 00, 33, 33, 33, 00, 00, 00, 00, 00

Header: 40, 04, 0E, 00, A2, 01: SetHomeParams, 14 byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

Home Direction: 00, 00: Not Applicable

Limit Switch: 00, 00: Not Applicable

Home Velocity: 33, 33, 33, 00: 24 mm/sec (3355443/134218)

Offset Distance: 00, 00, 00, 00: Not used

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
41	04	Chan Ident	00	d	s

GET:

Response structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
42	04	0E	00	d	s	Chan Ident	Home Dir	Limit Switch			
12	13	14	15	16	17	18	19				
<i>Data</i>											
Home Velocity						Offset Distance					

For structure see SET message above.

MGMSG_MOT_SET_LIMSWITCHPARAMS	0x0423
MGMSG_MOT_REQ_LIMSWITCHPARAMS	0x0424
MGMSG_MOT_GET_LIMSWITCHPARAMS	0x0425

These functions are not applicable to BBD10x units

Function: Used to set the limit switch parameters for the specified motor channel.

SET:

Command structure (22 bytes)

6 byte header followed by 16 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
23	04	10	00	d	s	Chan Ident	CW Hardlimit	CCW Hardlimit			

12	13	14	15	16	17	18	19	20	21		
<i>Data</i>											
CW Soft Limit				CCW Soft Limit				Limit Mode			

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
CW Hard Limit	<p>The operation of the Clockwise hardware limit switch when contact is made.</p> <p>0x01 Ignore switch or switch not present. 0x02 Switch makes on contact. 0x03 Switch breaks on contact. 0x04 Switch makes on contact - only used for homes (e.g. limit switched rotation stages). 0x05 Switch breaks on contact - only used for homes (e.g. limit switched rotations stages). 0x06 For PMD based brushless servo controllers only - uses index mark for homing.</p> <p>Note. Set upper bit to swap CW and CCW limit switches in code. Both CWHardLimit and CCWHardLimit structure members will have the upper bit set when limit switches have been physically swapped.</p> <p>0x80 // bitwise OR'd with one of the settings above.</p>	word
CCW Hard Limit	The operation of the Counter Clockwise hardware limit switch when contact is made.	word
CW Soft Limit	Clockwise software limit in position steps. A 32 bit unsigned long value, the scaling factor between real time values and this parameter is 1 mm is equivalent to 134218. For example, to set the clockwise software limit switch to 100 mm, send a value of 13421800. (Not applicable to TDC001 units)	long
CCW Soft Limit	Counter Clockwise software limit in position steps (scaling as for CW limit). (Not applicable to TDC001 units)	long

Software Limit Mode	Software limit switch mode 0x01 Ignore Limit 0x02 Stop Immediate at Limit 0x03 Profiled Stop at limit 0x80 Rotation Stage Limit (bitwise OR'd with one of the settings above) (Not applicable to TDC001 units)	word
---------------------	---	------

Example: Set the limit switch parameters for chan 2 as follows:
 CW Hard Limit – switch makes.
 CCW Hard Limit - switch makes
 CW Soft Limit – set to 100 mm
 CCW Soft Limit - .set to 0 mm
 Software Limit Mode – Profiled Stop

TX 23, 04, 10, 00, A2, 01, 01, 00, 02, 00, 02, 00, E8, CC, CC, 00, 00, 00, 00, 00, 03, 00

Header: 23, 04, 10, 00, A2, 01: SetLimSwitchParams, 16 byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

CW Hard Limit: 02, 00: Switch Makes

CCW Hard Limit: 02, 00: Switch Makes

CW Soft Limit: E8, CC, CC, 00: 100 mm (13421800/134218)

CCW Soft Limit: 00, 00, 00, 00: 0 mm

Soft Limit Mode: 03, 00: Profiled Stop at Limit

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
24	04	Chan Ident	00	d	s

GET:

Response structure (20 bytes)

6 byte header followed by 16 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
25	04	10	00	d	s	Chan Ident	CW Hardlimit	CCW Hardlimit			
<i>Data</i>											
CW Soft Limit				CCW Soft Limit				Limit Mode			

For structure see SET message above.

MGMSG_MOT_MOVE_HOME
MGMSG_MOT_MOVE_HOMED
0x0443
0x0444

Function: Sent to start a home move sequence on the specified motor channel (in accordance with the home parameters above).

TX structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
43	04	Chan Ident	0x	d	s

Example: Home the motor channel in bay 2

TX 43, 04, 01, 00, 22, 01

HOMED:

Function: No response on initial message, but upon completion of home sequence controller sends a “homing completed” message:

RX structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
44	04	Chan Ident	0x	d	s

Example: The motor channel in bay 2 has been homed

RX 44, 04, 01, 00, 01, 22

MGMSG_MOT_MOVE_RELATIVE**0x0448**

Function: This command can be used to start a relative move on the specified motor channel (using the relative move distance parameter above). There are two versions of this command: a shorter (6-byte header only) version and a longer (6 byte header plus 6 data bytes) version. When the first one is used, the relative distance parameter used for the move will be the parameter sent previously by a MGMSG_MOT_SET_MOVERELPARAMS command. If the longer version of the command is used, the relative distance is encoded in the data packet that follows the header.

Short version:

TX structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
48	04	Chan Ident	0x	d	s

Example: Move the motor associated with channel 2 by 10 mm. (10 mm was previously set in the MGMSG_MOT_SET_MOVERELPARAMS method).

TX 48, 04, 01, 00, 22, 01

Long version:

The alternative way of using this command is by appending the relative move params structure (MOT_SET_MOVERELPARAMS) to this message header.

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
48	04	06	00	d	s	Chan Ident	Relative Distance				

Data Structure:

field	description	format
Chan Ident	The channel being addressed	Word
Relative Distance	The distance to move. This is a 4 byte signed integer that specifies the relative distance in position encoder counts. In the BBD10X series controllers the encoder resolution is 20,000 counts per mm, therefore to set a relative move distance of 1 mm, set this parameter to 20,000 (twenty thousand).	Long

Example: Move the motor associated with chan 2 by 10 mm:

TX 48, 04, 06, 00, A2, 01, 01, 00, 40, 0D, 03, 00,

Header: 45, 04, 06, 00, A2, 01: MoveRelative, 06 byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

Rel Dist: 40, 0D, 03, 00: Set absolute move distance to 10 mm (200,000 encoder counts).

Upon completion of the relative move the controller sends a Move Completed message as described following.

MGMSG_MOT_MOVE_COMPLETED**0x0464**

Function: No response on initial message, but upon completion of the relative or absolute move sequence, the controller sends a “move completed” message:

RX structure (20 bytes):

0	1	2	3	4	5
<i>header only</i>					
64	04	Chan Ident	0x	d	s

Followed by a 14-byte data packet described by the same status structures (i.e. MOTSTATUS and MOTDCSTATUS) described in the STATUS UPDATES section that follows.

MGMSG_MOT_MOVE_ABSOLUTE**0x0453**

Function: Used to start an absolute move on the specified motor channel (using the absolute move position parameter above). As previously described in the “MOVE RELATIVE” command, there are two versions of this command: a shorter (6-byte header only) version and a longer (6 byte header plus 6 data bytes) version. When the first one is used, the absolute move position parameter used for the move will be the parameter sent previously by a MGMSG_MOT_SET_MOVEABSPARAMS command. If the longer version of the command is used, the absolute position is encoded in the data packet that follows the header.

Short version:

TX structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
53	04	Chan Ident	0x	d	s

Example: Move the motor associated with channel 2 to 10 mm. (10 mm was previously set in the MGMSG_MOT_SET_MOVEABSPARAMS method).

TX 53, 04, 01, 00, 22, 01

Long version:

The alternative way of using this command by appending the absolute move params structure (MOTABSMOVEPARAMS) to this message header.

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
53	04	06	00	d	s	Chan Ident	Absolute Distance				

Data Structure:

field	description	format
Chan Ident	The channel being addressed	Word
Absolute Distance	The distance to move. This is a 4 byte signed integer that specifies the absolute distance in position encoder counts. In the BBD10X series controllers the encoder resolution is 20,000 counts per mm, therefore to set an absolute move distance of 100 mm, set this parameter to 2,000,000 (two million).	Long

Example: Move the motor associated with chan 2 to 10 mm:

TX 53, 04, 06, 00, A2, 01, 01, 00, 40, 0D, 03, 00,

Header: 45, 04, 06, 00, A2, 01: MoveAbsolute, 06 byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

Abs Dist: 40, 0D, 03, 00: Set the absolute move distance to 10 mm (200,000 encoder counts).

Upon completion of the absolute move the controller sends a Move Completed message as previously described.

MGMSG_MOT_MOVE JOG**0x046A**

Function: Sent to start a jog move on the specified motor channel.

TX structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
6A	04	Chan Ident	Direction	d	s

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Direction	The direction to Jog. Set this byte to 0x01 to jog forward, or to 0x02 to jog in the reverse direction.	word

Upon completion of the jog move the controller sends a Move Completed message as previously described.

Note. The direction of the jog move is device dependent, i.e. on some devices jog forward may be towards the home position while on other devices it could be the opposite.

MGMSG_MOT_MOVE_VELOCITY**0x0457**

Function: This command can be used to start a move on the specified motor channel. When this method is called, the motor will move continuously in the specified direction, using the velocity parameters set in the MGMSG_MOT_SET_MOVEVELPARAMS command until either a stop command (either StopImmediate or StopProfiled) is called, or a limit switch is reached.

TX structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
57	04	Chan Ident	Direction	d	s

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Direction	The direction to Jog. Set this byte to 0x01 to move forward, or to 0x02 to move in the reverse direction.	word

Upon completion of the move the controller sends a Move Completed message as previously described.

Example: Move the motor associated with channel 2 forwards.

TX 57, 04, 01, 01, 22, 01

MGMSG_MOT_MOVE_STOP**0x0465**

Function: Sent to stop any type of motor move (relative, absolute, homing or move at velocity) on the specified motor channel.

TX structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
65	04	Chan Ident	Stop Mode	d	s

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Stop Mode	The stop mode defines either an immediate (abrupt) or profiles tops. Set this byte to 0x01 to stop immediately, or to 0x02 to stop in a controller (profiled) manner.	word

Upon completion of the stop move the controller sends a Move Stopped message as described following

MGMSG_MOT_MOVE_STOPPED**0x0466**

Function: No response on initial message, but upon completion of the stop move, the controller sends a “move stopped” message:

RX structure (20 bytes):

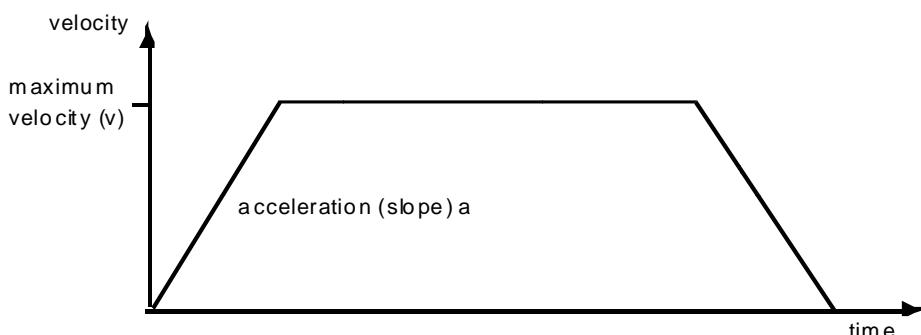
0	1	2	3	4	5
<i>header only</i>					
66	04	0E	0x	d	s

Followed by a 14-byte data packet described by the same status structures (i.e. MOTSTATUS and MOTDCSTATUS) described in the STATUS UPDATES section that follows.

MGMSG_MOT_SET_BOWINDEX	0x04F4
MGMSG_MOT_REQ_BOWINDEX	0x04F5
MGMSG_MOT_GET_BOWINDEX	0x04F6

Function: To prevent the motor from stalling, it must be ramped up gradually to its maximum velocity. Certain limits to velocity and acceleration result from the torque and speed limits of the motor, and the inertia and friction of the parts it drives. The system incorporates a trajectory generator, which performs calculations to determine the instantaneous position, velocity and acceleration of each axis at any given moment. During a motion profile, these values will change continuously. Once the move is complete, these parameters will then remain unchanged until the next move begins. The specific move profile created by the system depends on several factors, such as the profile mode and profile parameters presently selected, and other conditions such as whether a motion stop has been requested.

The Bow Index parameter is used to set the profile mode to either Trapezoidal or S-curve. A Bow Index of '0' selects a trapezoidal profile. An index value of '1' to '18' selects an S-curve profile. In either case, the velocity and acceleration of the profile are specified using the Velocity Profile parameters on the Moves/Jogs tab. The Trapezoidal profile is a standard, symmetrical acceleration/deceleration motion curve, in which the start velocity is always zero. This profile is selected when the Bow Index field is set to '0'.



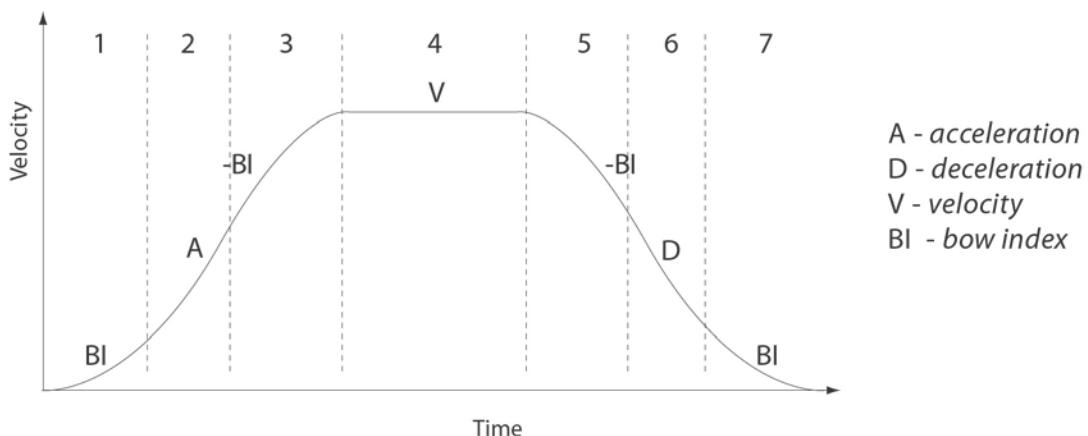
In a typical trapezoidal velocity profile, (see above), the stage is ramped at acceleration 'a' to a maximum velocity 'v'. As the destination is approached, the stage is decelerated at 'a' so that the final position is approached slowly in a controlled manner.

The S-curve profile is a trapezoidal curve with an additional 'Bow Value' parameter, which limits the rate of change of acceleration and smooths out the contours of the motion profile.

The Bow Value is applied in mm/s³ and is derived from the Bow Index as follows:

$$\text{Bow Value} = 2^{(\text{Bow Index} - 1)} \text{ within the range 1 to 262144 (Bow Index 1 to 18).}$$

In this profile mode, the acceleration increases gradually from 0 to the specified acceleration value, then decreases at the same rate until it reaches 0 again at the specified velocity. The same sequence in reverse brings the axis to a stop at the programmed destination position.

**Example**

The figure above shows a typical S-curve profile. In segment (1), the S-curve profile drives the axis at the specified Bow Index (BI) until the maximum acceleration (A) is reached. The axis continues to accelerate linearly (Bow Index = 0) through segment (2). The profile then applies the negative value of Bow Index to reduce the acceleration to 0 during segment (3). The axis is now at the maximum velocity (V), at which it continues through segment (4). The profile then decelerates in a similar manner to the acceleration phase, using the Bow Index to reach the maximum deceleration (D) and then bring the axis to a stop at the destination.

Note

The higher the Bow Index, then the shorter the BI phases of the curve, and the steeper the acceleration and deceleration phases. High values of Bow Index may cause a move to overshoot.

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
header						Data			
F4	04	04	00	d	s	Chan Ident	Bow Index		

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
BowIndex	This parameter is used to set the profile mode to either Trapezoidal or S-curve. A Bow Index of '0' selects a trapezoidal profile. An index value of '1' to '18' selects an S-curve profile.	word

Example: Set the Bow Index to 18 for Channel 1 as follows:

TX F4, 04, 04, 00, A2, 01, 01, 00, 12, 00,

Header: F4, 04, 04, 00, A2, 01: Set_BowIndex, 04 byte data packet,

Chan Ident: 01, 00: Channel 1

Bow Index: 12, 00,: Set the Bow Index to 18

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
F5	04	Chan Ident	00	d	s

GET:

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
F6	04	04	00	d	s	Chan Ident	Bow Index		

For structure see SET message above.

MGMSG_MOT_SET_DCPIDPARAMS	0x04A0
MGMSG_MOT_REQ_DCPIDPARAMS	0x04A1
MGMSG_MOT_GET_DCPIDPARAMS	0x04A2

Function: Used to set the position control loop parameters for the specified motor channel.

The motion processor within the controller uses a position control loop to determine the motor command output. The purpose of the position loop is to match the actual motor position and the demanded position. This is achieved by comparing the demanded position with the actual position to create a position error, which is then passed through a digital PID-type filter. The filtered value is the motor command output.

NOTE. These settings apply to LM628/629 based servo controllers (only TDC001 at this time). Refer to data sheet for National Semiconductor LM628/LM629 for further details on setting these PID related parameters.

SET:

Command structure (26 bytes)

6 byte header followed by 20 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11						
<i>header</i>						<i>Data</i>											
A0	04	14	00	d	s	Chan Ident	Proportional										
12	13	14	15	16	17	18	19	20	21	22	23						
<i>Data</i>						Integral			Differential								
24	25																
<i>Data</i>																	
FilterControl																	

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Proportional	The proportional gain. Together with the Integral and Differential, these terms determine the system response characteristics and accept values in the range 0 to 32767.	long
Integral	The integral gain. Together with the Proportional and Differential, these terms determine the system response characteristics and accept values in the range 0 to 32767.	long
Differential	The differential gain. Together with the Proportional and Integral, these terms determine the system response characteristics and accept values in the range 0 to 32767.	long
Integral Limit	The Integral Limit parameter is used to cap the value of the Integrator to prevent runaway of the integral sum at the output. It accepts values in the range 0 to 32767. If set to 0 then the integration term in the PID loop is ignored.	long
FilterControl	Identifies which of the above parameters are applied by	word

	setting the corresponding bit to '1'. By default, all parameters are applied, and this parameter is set to 0F (1111).	
--	---	--

Example: Set the PID parameters for TDC001 as follows:

Proportional: 65

Integral: 175

Differential: 600

Integral Limit: 20,000

FilterControl: 15

TX A0, 04, 14, 00, D0, 01, 01, 00, 41, 00, AF, 00, 58, 02, 20, 4E, 00, 00, 0F, 00

Header: A0, 04, 14, 00, D0, 01: Set_DCPIDParams, 20 byte data packet, Generic USB Device.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

Proportional: 41, 00,: Set the proportional term to 65

Integral: AF, 00,: Set the integral term to 175

Differential: 58, 02,: Set the differential term to 600

Integral Limit: 20, 4E, 00, 00,: Set the integral limit to 20,000

FilterControl: 0F, 00: Set all terms to active.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
A0	04	Chan Ident	00	d	s

GET:

6 byte header followed by 20 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11			
<i>header</i>						<i>Data</i>								
A0	04	14	00	d	s	Chan Ident	Proportional							
12	13	14	15	16	17	18	19	20	21	22	23			
<i>Data</i>						Integral			Differential					
24	25	<i>Data</i>						Integral Limit						
		FilterControl												

For structure see Set message above.

MGMSG_MOT_SET_AVMODES	0x04B3
MGMSG_MOT_REQ_AVMODES	0x04B4
MGMSG_MOT_GET_AVMODES	0x04B5

Function: The LED on the control keypad can be configured to indicate certain driver states.
All modes are enabled by default. However, it is recognised that in a light sensitive environment, stray light from the LED could be undesirable. Therefore it is possible to enable selectively, one or all of the LED indicator modes described below by setting the appropriate value in the Mode Bits parameter.

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>					<i>Data</i>				
B3	04	04	00	d	s	Chan Ident	ModeBits		

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
ModeBits	<p>The mode of operation for the LED is set according to the hex value entered in the mode bits.</p> <p>1 LEDMODE_IDENT: The LED will flash when the 'Ident' message is sent.</p> <p>2 LEDMODE_LIMITSWITCH: The LED will flash when the motor reaches a forward or reverse limit switch.</p> <p>8 LEDMODE_MOVING: The LED is lit when the motor is moving.</p>	word

Example: Set the LED to flash when the IDENT message is sent, and also when the motor is moving.

TX B3, 04, 04, 00, D0, 01, 01, 00, 09, 00,

Header: B3, 04, 04, 00, D0, 01: SetAVModes, 04 byte data packet, Generic USB Device.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

ModeBits: 09, 00 (i.e. 1 + 8)

Similarly, if the ModeBits parameter is set to '11' (1 + 2 + 8) all modes will be enabled.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
11	04	Chan Ident	00	d	s

GET:

Response structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
B5	04	04	00	d	s	Chan Ident	ModeBits		

For structure see SET message above.

MGMSG_MOT_SET_POTPARAMS	0x04B0
MGMSG_MOT_REQ_POTPARAMS	0x04B1
MGMSG_MOT_GET_POTPARAMS	0x04B2

Function: The potentiometer slider on the control panel panel is sprung, such that when released it returns to its central position. In this central position the motor is stationary. As the slider is moved away from the center, the motor begins to move; the speed of this movement increases as the slider deflection is increased. Bidirectional control of motor moves is possible by moving the slider in both directions. The speed of the motor increases by discrete amounts rather than continuously, as a function of slider deflection. These speed settings are defined by 4 pairs of parameters. Each pair specifies a pot deflection value (in the range 0 to 127) together with an associated velocity (set in encoder counts/sec) to be applied at or beyond that deflection. As each successive deflection is reached by moving the pot slider, the next velocity value is applied. These settings are applicable in either direction of pot deflection, i.e. 4 possible velocity settings in the forward or reverse motion directions.
Note. The scaling factor between encoder counts and mm/sec depends on the specific stage/actuator being driven.

SET:

Command structure (32 bytes)

6 byte header followed by 26 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
B0	04	1A	00	d	s	Chan Ident	ZeroWnd	Vel1			

12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>											
Vel1	Wnd1		Vel2			Wnd2		Vel3			

24	25	26	27	28	29	30	31				
<i>Data</i>											
Vel3	Wnd3		Vel4								

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
ZeroWnd	The deflection from the mid position (in ADC counts 0 to 127) before motion can start	word
Vel1	The velocity (in encoder counts /sec) to move when between Wnd0 and PotDef1	long
Wnd1	The deflection from the mid position (in ADC counts, Wnd0 to 127) to apply Vel1	word
Vel2	The velocity (in encoder counts /sec) to move when between PotDef1 and PotDef2	long
Wnd2	The deflection from the mid position (in ADC counts, PotDef1 to 127) to apply Vel2	word

Vel3	The velocity (in encoder counts/sec) to move when between PotDef2 and PotDef3	long
Wnd3	The deflection from the mid position (in ADC counts PotDef2 to 127) to apply Vel3	word
Vel4	The velocity (in encoder counts /sec) to move when beyond PotDef3	long

Example: For the Z8 series motors, there are 512 encoder counts per revolution of the motor. The output shaft of the motor goes into a 67:1 planetary gear head. This requires the motor to rotate 67 times to rotate the 1.0 mm pitch lead screw one revolution. The end result is the lead screw advances by 1.0 mm.

Therefore, a 1 mm linear displacement of the actuator is given by

$$512 \times 67 = 34,304 \text{ encoder counts}$$

whereas the linear displacement of the lead screw per encoder count is given by

$$1.0 \text{ mm} / 34,304 \text{ counts} = 2.9 \times 10^{-5} \text{ mm (29 nm)}.$$

Typical parameters settings Hex (decimal)

ZeroWnd – 14 (20)
 Vel1 – 66, 0D,00,00 (3430)
 Wnd1 – 32 (50)
 Vel2 – CC, 1A, 00, 00 (6860)
 Wnd2 – 50 (80)
 Vel3 – 32, 28, 00, 00 (10290)
 Wnd3 – 64 (100)
 Vel4 – 00, 43, 00, 00 (17152)

Using the parameters above, no motion will start until the pot has been deflected to 20 (approx 1/6 full scale deflection), when the motor will start to move at 0.1mm/sec. At a deflection of 50 (approx 2/5 full scale deflection) the motor velocity will increase to 0.2mm/sec, and at 80, velocity will increase to 0.3 mm/sec. When the pot is deflected to 100 and beyond, the velocity will be 0.5 mm/sec.

Note. It is acceptable to set velocities equal to each other to reduce the number of speeds, however this is not allowed for the deflection settings, whereby the Wnd3 Pot Deflection value must be greater than Wnd2 Pot Deflection value.

TX B0, 04, 1A, 00, D0, 01, 01, 00, 01, 00, E8, 03, 00, 00, 00, 00, 00, B0,35, 00, 00, CD, CC, CC, 00, 02, 00

Header: B0, 04, 1A, 00, D0, 01: Set Pot Params, 1AH (26) byte data packet, Generic USB Device.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

Wnd0: 14 (20 ADC Counts)

Vel1: 66, 0D,00,00 (3430 Encoder Counts/sec = 0.1 mm/sec)

PotDef1: 32 (50 ADC Counts)

Vel2: CC, 1A, 00, 00 (6860 Encoder Counts/sec = 0.2 mm/sec)

PotDef2: 50 (80 ADC Counts)

Vel3: 32, 28, 00, 00 (10290 Encoder Counts/sec = 0.3 mm/sec)

PotDef3: 64 (100 ADC Counts)

Vel4: 00, 43, 00, 00 (17152 Encoder Counts/sec = 0.5 mm/sec)

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
17	04	Chan Ident	00	d	s

GET:

Response structure (28 bytes)

6 byte header followed by 22 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
B0	04	1A	00	d	s	Chan Ident	ZeroWnd	Vel1			
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>											
Vel1	Wnd1		Vel2		Wnd2		Vel3				
24	25	26	27	28	29	30	31				
<i>Data</i>											
Vel3	Wnd3		Vel4								

For structure see SET message above.

MGMSG_MOT_SET_BUTTONPARAMS	0x04B6
MGMSG_MOT_REQ_BUTTONPARAMS	0x04B7
MGMSG_MOT_GET_BUTTONPARAMS	0x04B8

Function: The control keypad can be used either to jog the motor, or to perform moves to absolute positions. This function is used to set the front panel button functionality.

SET:

Command structure (22 bytes)

6 byte header followed by 16 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
B6	04	10	00	d	s	Chan Ident	Mode	Position1			

12	13	14	15	16	17	18	19	20	21		
<i>Data</i>											
Position1	Position2			TimeOut		Not Used					

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Mode	The buttons on the keypad can be used either to jog the motor (jog mode), or to perform moves to absolute positions (go to position mode). If set to 0x01, the buttons are used to jog the motor. Once set to this mode, the move parameters for the buttons are taken from the 'Jog' parameters set via the 'Move/Jogs' settings tab or the SetJogParams methods. If set to 0x02, each button can be programmed with a different position value (as set in the Position 1 and Position 2 parameters), such that the controller will move the motor to that position when the specific button is pressed.	word
Position1	The position (in encoder counts) to which the motor will move when the top button is pressed. This parameter is applicable only if 'Go to Position is selected in the 'Mode' parameter.	long
Position2	The position (in encoder counts) to which the motor will move when the bottom button is pressed. This parameter is applicable only if 'Go to Position is selected in the 'Mode' parameter.	long
TimeOut	A 'Home' move or can be performed by pressing and holding both buttons. Furthermore, the present position can be entered into the Position 1 or Position 2 parameter by holding down the associated button. The Time Out parameter specifies the time in ms that the button(s) must be depressed. This function is independent of the 'Mode' setting and in normal circumstances should not require adjustment. (Not applicable to TDC001 units)	word
Not Used		word

Example: Set the button parameters for TDC001 as follows:
 Mode: Go To Position
 Position1: 0.5 mm
 Position2: 1.2 mm
 TimeOut: 2 secs

TX B6, 04, 10, 00, D0, 01, 00, 02, 00, C0, 12, 00, 00, 00, 00, 00, 00, 00

Header: B6, 04, 10, 00, D0, 01: SetButtonParams, 10H (16) byte data packet, Generic USB Device

Chan Ident: 01, 00: Channel 1 (always set to 1 for TDC001)

Mode: 02, 00 (i.e. Go to position)

Position1: 00, 43, 00, 00 (17152 Encoder Counts = 0.5 mm)

Position2: CC, A0, 00, 00 (41164 encoder counts = 1.2 mm):

TimeOut: D0, 07: (2 seconds)

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
DB	04	Chan Ident	00	d	s

GET:

Response structure (20 bytes)

6 byte header followed by 16 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
B6	04	10	00	d	s	Chan Ident	Mode	Position1			
12	13	14	15	16	17	18	19	20	21		
<i>Data</i>											
Position1	Position2			TimeOut		Not Used					

For structure see SET message above.

MGMSG_MOT_SET_EEPROMPARAMS**0x04B9**

Function: Used to save the parameter settings for the specified message. These settings may have been altered either through the various method calls or through user interaction with the GUI (specifically, by clicking on the 'Settings' button found in the lower right hand corner of the user interface).

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>					<i>Data</i>				
B9	04	04	00	d	s	Chan Ident	MsgID		

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
MsgID	The message ID of the message containing the parameters to be saved.	word

Example:

TX B9, 04, 04, 00, D0, 01, 01, 00, B6, 04,

Header: B9, 04, 04, 00, D0, 01: Set_EEPROMPARAMS, 04 byte data packet, Generic USB Device.

Chan Ident: 01, 00: Channel 1

MsgID: Save parameters specified by message 04B6 (SetButtonParams).

MGMSG_MOT_SET_PMDPOSITIONLOOPPARAMS	0x04D7
MGMSG_MOT_REQ_PMDPOSITIONLOOPPARAMS	0x04D8
MGMSG_MOT_GET_PMDPOSITIONLOOPPARAMS	0x04D9

Function: Used to set the position control loop parameters for the specified motor channel.

The motion processors within the BBD series controllers use a position control loop to determine the motor command output. The purpose of the position loop is to match the actual motor position and the demanded position. This is achieved by comparing the demanded position with the actual encoder position to create a position error, which is then passed through a digital PID-type filter. The filtered value is the motor command output.

SET:

Command structure (34 bytes)

6 byte header followed by 28 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
D7	04	1C	00	d	s	Chan Ident	Kp Pos	Integral			
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>											
ILimPos			Differential		KdTimePos	KoutPos	KvffPos				
24	25	26	27	28	29	30	31	32	33		
<i>Data</i>											
KaffPos	PosErrLim			N/A		N/A					

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Kp Pos	The proportional gain. Together with the Integral and Differential, these terms determine the system response characteristics and accept values in the range 0 to 32767.	word
Integral	The integral gain. Together with the Proportional and Differential, these terms determine the system response characteristics and accept values in the range 0 to 32767.	word
ILimPos	The Integral Limit parameter is used to cap the value of the Integrator to prevent runaway of the integral sum at the output. It accepts values in the range 0 to 7FFFFFFF. If set to 0 then the integration term in the PID loop is ignored.	dword
Differential	The differential gain. Together with the Proportional and Integral, these terms determine the system response characteristics and accept values in the range 0 to 32767.	word
KdTimePos	Under normal circumstances, the derivative term of the PID loop is recalculated at every servo cycle. However, it may be desirable to reduce the sampling rate to a lower value, in order to increase stability or simplify tuning. The KdTimePos parameter is used to set the sampling rate. For example, if	word

	set to 10, the derivative term is calculated every 10 servo cycles. The value is set in cycles, in the range 1 to 32767.	
KoutPos	The KoutPos parameter is a scaling factor applied to the output of the PID loop. It accepts values in the range 0 to 65535, where 0 is 0% and 65535 is 100%.	word
KvffPos	The KvffPos and KaffPos parameters are velocity and acceleration feed-forward terms that are added to the output of the PID filter to assist in tuning the motor drive signal. They accept values in the range 0 to 32767.	word
KaffPos		word
PosErrLim	Under certain circumstances, the actual encoder position may differ from the demanded position by an excessive amount. Such a large position error is often indicative of a potentially dangerous condition such as motor failure, encoder failure or excessive mechanical friction. To warn of, and guard against this condition, a maximum position error can be set in the PosErrLim parameter, in the range 0 to 7FFFFFFF. The actual position error is continuously compared against the limit entered, and if exceeded, the Motion Error bit (bit 15) of the Status Register is set and the associated axis is stopped.	dword
Not Used		word
Not Used		word

Example: Set the PID parameters for chan 2 as follows:

Proportional: 65
 Integral: 175
 Integral Limit: 80,000
 Differential: 600
 KdTimePos: 5
 KoutPos: 5%
 KvffPos: 0
 KaffPos: 1000
 PosErrLim: 65535

TX D7, 04, 1C, 00, A2, 01, 01, 00, 41, 00, AF, 00, 80, 38, 01, 00, 58, 02, 05, 00, CD, 0C, 00, 00, E8, 03, FF, FF, 00, 00, 00

Header: D7, 04, 1C, 00, A2, 01: Set_PMDPositionLoopParams, 28 byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for BBD202)

Proportional: 41, 00,: Set the proportional term to 65

Integral: AF, 00,: Set the integral term to 175

Integral Limit: 80, 38, 01, 00,: Set the integral limit to 80,000

Differential: 58, 02,: Set the differential term to 600

KdTimePos: 05, 00,: Set the sampling rate to 5 cycles

KoutPos: CD, 0C,: Set the output scaling factor to 5% (i.e. 3277)

KvffPos: 00, 00,: Set the velocity feed forward value to zero

KaffPos: E8, 03,: Set the acceleration feed forward value to 1000

PosErrLim: FF, FF, 00, 00,: Set the position error limit to 65535.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
D8	04	Chan Ident	00	d	s

GET:

Response structure (34 bytes)

6 byte header followed by 28 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
D9	04	1C	00	d	s	Chan Ident	Kp Pos	Integral			
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>											
ILinPos				Differential	KdTimePos	KoutPos	KvffPos				
24	25	26	27	28	29	30	31	32	33		
<i>Data</i>											
KaffPos	PosErrLim				N/A	N/A	N/A	N/A	N/A		

For structure see SET message above.

MGMSG_MOT_SET_PMDMOTOROUTPUTPARAMS	0x04DA
MGMSG_MOT_REQ_PMDMOTOROUTPUTPARAMS	0x04DB
MGMSG_MOT_GET_PMDMOTOROUTPUTPARAMS	0x04DC

Function: Used to set certain limits that can be applied to the motor drive signal. The individual limits are described below.

SET:

Command structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
DA	04	0E	00	d	s	Chan Ident	Cont Current Lim	Energy Limit			
12	13	14	15	16	17	18	19				
<i>Data</i>						Motor Limit	Motor Bias	Not Used	Not Used		

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
ContCurrentLim	The system incorporates a current ‘foldback’ facility, whereby the continuous current level can be capped. The continuous current limit is set in the ContCurrentLim parameter, which accepts values as a percentage of maximum peak current, in the range 0 to 32767 (0 to 100%), which is the default maximum level set at the factory (this maximum value cannot be altered).	word
EnergyLim	When the current output of the drive exceeds the limit set in the ContCurrentLim parameter, accumulation of the excess current energy begins. The EnergyLim parameter specifies a limit for this accumulated energy, as a percentage of the factory set default maximum, in the range 0 to 32767 (0 to 100%). When the accumulated energy exceeds the value specified in the EnergyLim parameter, a ‘current foldback’ condition is said to exist, and the commanded current is limited to the value specified in the ContCurrentLim parameter. When this occurs, the Current Foldback status bit (bit 25) is set in the Status Register. When the accumulated energy above the ContCurrentLim value falls to 0, the limit is removed and the status bit is cleared.	word
MotorLim	The MotorLim parameter sets a limit for the motor drive signal and accepts values in the range 0 to 32767 (100%). If the system produces a value greater than the limit set, the motor command takes the limiting value. For example, if MotorLim is set to 30000 (91.6%), then signals greater than 30000 will be output as 30000 and values less than -30000 will be output as -30000.	word
MotorBias	When an axis is subject to a constant external force in one	word

	direction (such as a vertical axis pulled downwards by gravity) the servo filter can compensate by adding a constant DC bias to the output. This bias is set in the MotorBias parameter, which accepts values in the range -32767 to 32768. The default value is 0. Once set, the motor bias is applied while the position loop is enabled.	
Not Used		word
Not Used		word

Example: Set the motor output parameters for chan 2 as follows:

Continuous Current: 20%

Energy Limit: 14%

Motor Limit: 100%

Motor Bias: zero

TX DA, 04, 0E, 00, A2, 01, 01, 00, 99, 19, C0, 12, 00, 00, 00, 00, 00, 00, 00

Header: DA, 04, 0E, 00, A2, 01: Set MotorOutputParams, 0EH (14) byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for BBD202)

Cont Current Limit:

Energy Limit: 99, 19: Set the energy limit to 14%

Motor Limit: C0, 12: Set the motor limit to 100%

Motor Bias: 00, 00: Set the motor bias to zero

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
DB	04	Chan Ident	00	d	s

GET:

Response structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
DC	04	0E	00	d	s	Chan Ident	Cont Current Lim	Energy Limit			
12	13	14	15	16	17	18	19				
<i>Data</i>											
Motor Limit	Motor Bias	Not Used	Not Used								

For structure see SET message above.

MGMSG_MOT_SET_PMDTRACKSETLEPARAMS	0x04E0
MGMSG_MOT_REQ_PMDTRACKSETLEPARAMS	0x04E1
MGMSG_MOT_GET_PMDTRACKSETLEPARAMS	0x04E2

Function: Moves are generated by an internal profile generator, and are based on either a trapezoidal or S-curve trajectory. A move is considered complete when the profile generator has completed the calculated move and the axis has 'settled' at the demanded position. This command contains parameters which specify when the system is settled.

Further Information

The system incorporates a monitoring function, which continuously indicates whether or not the axis has 'settled'. The 'Settled' indicator is bit 14 in the Status Register and is set when the associated axis is settled. Note that the status bit is controlled by the processor, and cannot be set or cleared manually.

The axis is considered to be 'settled' when the following conditions are met:

- * the axis is at rest (i.e. not performing a move),
- * the error between the demanded position and the actual motor position is less than or equal to a specified number of encoder counts (0 to 65535) set in the *SettleWnd* parameter (Settle Window),
- * the above two conditions have been met for a specified number of cycles (settle time, 1 cycle = 102.4 µs), set in the *SettleTime* parameter (range 0 to 32767).

The above settings are particularly important when performing a sequence of moves. If the PID parameters are set such that the settle window cannot be reached, the first move in the sequence will never complete, and the sequence will stall. The settle window and settle time values should be specified carefully, based on the required positional accuracy of the application. If positional accuracy is not a major concern, the settle time should be set to '0'. In this case, a move will complete when the motion calculated by the profile generator is completed, irrespective of the actual position attained, and the settle parameters described above will be ignored.

The processor also provides a 'tracking window', which is used to monitor servo performance outside the context of motion error. The tracking window is a programmable position error limit within which the axis must remain, but unlike the position error limit set in the SetDCPositionLoopParams method, the axis is not stopped if it moves outside the specified tracking window. This function is useful for processes that rely on the motor's correct tracking of a set trajectory within a specific range. The tracking window may also be used as an early warning for performance problems that do not yet qualify as motion error.

The size of the tracking window (i.e. the maximum allowable position error while remaining within the tracking window) is specified in the *TrackWnd* parameter, in the range 0 to 65535. If the position error of the axis exceeds this value, the Tracking Indicator status bit (bit 13) is

set to 0 in the Status Register. When the position error returns to within the window boundary, the status bit is set to 1.

SET:

Command structure (18 bytes)

6 byte header followed by 12 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
E0	04	0C	00	d	s	Chan Ident	Time	Settle Window			
12	13	14	15	16	17	<i>Data</i>					
Track Window	Not Used	Not Used									

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Time	The time that the associated axis must be settled before the 'Settled' status bit is set. The time is set in cycles, in the range 0 to 32767, 1 cycle = 102.4 µs.	word
Settle Window	The position error is defined as the error between the demanded position and the actual motor position. This parameter specifies the number of encoder counts (in the range 0 to 65535) that the position error must be less than or equal to, before the axis is considered 'settled'.	word
Track Window	The maximum allowable position error (in the range 0 to 65535) whilst tracking .	word
Not Used		word
Not Used		word

Example: Set the track and settle parameters for chan 2 as follows:

Settle Time: 20%

Settle Window: 14%

Track Window: 100%

s

TX E0, 04, 0C, 00, A2, 01, 01, 00, 00, 14, 00, 00, 00, 00, 00, 00, 00, 00

Header: E0, 04, 0C, 00, A2, 01: Set MotorOutputParams, 0CH (12) byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for BBD202)

Time: 00, 00: Set the Settle time to zero

Settle Window: 14, 00: Set the settle window to 20 encoder counts

Track Window: 00, 00: Set the track window to zero

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
E1	04	Chan Ident	00	d	s

GET:

Response structure (18 bytes)

6 byte header followed by 12 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
E2	04	0C	00	d	s	Chan Ident	Time	Settle Window			
12	13	14	15	16	17	<i>Data</i>					
Track Window	Not Used	Not Used									

For structure see SET message above.

MGMSG_MOT_SET_PMDPROFILEMODEPARAMS	0x04E3
MGMSG_MOT_REQ_PMDPROFILEMODEPARAMS	0x04E4
MGMSG_MOT_GET_PMDPROFILEMODEPARAMS	0x04E5

Function: The system incorporates a trajectory generator, which performs calculations to determine the instantaneous position, velocity and acceleration of each axis at any given moment. During a motion profile, these values will change continuously. Once the move is complete, these parameters will then remain unchanged until the next move begins.

The specific move profile created by the system depends on several factors, such as the profile mode and profile parameters presently selected, and other conditions such as whether a motion stop has been requested. This method is used to set the profile mode to either 'Trapezoidal' or 'S-curve'.

SET:

Command structure (18 bytes)

6 byte header followed by 12 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
E3	04	0C	00	d	s	Chan Ident	Mode	Jerk			
12	13	14	15	16	17	<i>Data</i>					
Jerk	Not Used	Not Used									

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Mode	The move profile to be used: Trapezoidal: 0 S-Curve: 2 The Trapezoidal profile is a standard, symmetrical acceleration/deceleration motion curve, in which the start velocity is always zero. The S-curve profile is a trapezoidal curve with an additional 'Jerk' parameter, which limits the rate of change of acceleration and smooths out the contours of the motion profile. In this profile mode, the acceleration increases gradually from 0 to the specified acceleration value, then decreases at the same rate until it reaches 0 again at the specified velocity. The same sequence in reverse brings the axis to a stop at the programmed destination position.	word
Jerk	The Jerk value is specified in mm/s ³ in the Jerk parameter, and accepts values in the range 0 to 4294967295. It is used to specify the maximum rate of change in acceleration in a single cycle of the basic trapezoidal curve. 1.0 mm/s ³ is equal to 92.2337 jerk units.	dword
Not Used		word
Not Used		word

Example: Set the profile mode parameters for chan 2 as follows:

Profile Mode: S-curve

Jerk: 10,000 mm³

TX E3, 04, 0C, 00, A2, 01, 01, 00, 02, 00, E1, 12, 0E, 00, 00, 00, 00, 00,

Header: E3, 04, 0C, 00, A2, 01: Set ProfileModeParams, 0CH (12) byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for BBD202)

Profile Mode: 02, 00: Set the profile mode to S-Curve

Jerk: E1, 12, 0E, 00: Set the jerk value to 10,000 mm/sec³ (i.e. 922337)

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
E4	04	Chan Ident	00	d	s

GET:

Response structure (18 bytes)

6 byte header followed by 12 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
E5	04	0C	00	d	s	Chan Ident	Mode	Jerk			
<i>Data</i>											
Jerk		Not Used		Not Used							

For structure see SET message above.

MGMSG_MOT_SET_PMDJOYSTICKPARAMS	0x04E6
MGMSG_MOT_REQ_PMDJOYSTICKPARAMS	0x04E7
MGMSG_MOT_GET_PMDJOYSTICKPARAMS	0x04E8

Function: The MJC001 joystick console has been designed for use by microscopists to provide intuitive, tactile, manual positioning of the stage. The console consists of a two axis joystick for XY control which features both low and high gear modes. This message is used to set max velocity and acceleration values for these modes.

SET:

Command structure (26 bytes)

6 byte header followed by 20 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
E6	04	14	00	d	s	Chan Ident	JSGearLowMaxVel				
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>						JSGearHighMaxVel	JSGearHighLowAccn	JSGearHighHighAccn			
24	25										
<i>Data</i>											
DirSense											

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
JSGearLowMaxVel	Specifies the max velocity (in encoder counts/cycle) of a joystick move when low gear mode is selected. It accepts values in the range 0 to 4294967295. 1 mm / sec equals 134218 PMD units	long
JSGearHighMaxVel	Specifies the max velocity (in encoder counts/cycle) of a joystick move when high gear mode is selected. It accepts values in the range 0 to 4294967295. 1 mm / sec equals 134218 PMD units	long
JSGearLowAccn	Specifies the acceleration (in encoder counts/cycle) of a joystick move when low gear mode is selected. It accepts values in the range 0 to 4294967295. 1 mm / sec ² equals 13.7439 PMD units.	long
JSGearHighAccn	Specifies the acceleration (in encoder counts/cycle) of a joystick move when high gear mode is selected. It accepts values in the range 0 to 4294967295. 1 mm / sec ² equals 13.7439 PMD units.	long
DirSense	The actual direction sense of any joystick initiated move is dependent upon the application. This parameter can be used to reverse the sense of direction for a particular application and is useful when matching joystick direction sense to actual stage direction sense. DIRSENSE_POS 0X0001 Direction Positive DIRSENSE_NEG 0X0002 Direction Negative	word

Example: Set the joystick parameters for bay 2 as follows:

JSGearLowMaxVel: 1 mm/sec
 JSGearHighMaxVel: 10 mm/sec
 JSGearLowAccn: 0.5 mm /sec²
 JSGearHighAccn: 5.0 mm /sec²
 DirSens: Positive

TX E6, 04, 14, 00, A2, 01, 01, 00, 4A, 0C, 02, 00, E4, 7A, 14, 00, 07, 00, 00, 00, 46, 00, 00, 00, 01, 00

Header: E6, 04, 14, 00, A2, 01: SetPMDJoystickParams, 14H (20) byte data packet, bay 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for BBD202)

JSGearLowMaxVel: 4A, 0C, 02, 00 (134218)

JSGearHighMaxVel: E4, 7A, 14, 00 (1342180)

JSGearLowAccn: 07, 00, 00, 00 (7.0)

JSGearHighAccn: 46, 00, 00, 00 (70.0)

DirSens: 01, 00

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
E7	04	Chan Ident	00	d	s

GET:

Response structure (26 bytes)

6 byte header followed by 20 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11																		
<i>header</i>						<i>Data</i>																							
E8	04	14	00	d	s	Chan Ident	JSGearLowMaxVel																						
<i>Data</i>																													
12	13	14	15	16	17	18	19	20	21	22	23																		
JSGearHighMaxVel				JSGearHighLowAccn				JSGearHighHighAccn																					
24	25																												
<i>Data</i>																													
DirSense																													

For structure see SET message above.

MGMSG_MOT_SET_PMDCURRENTLOOPPARAMS	0x04D4
MGMSG_MOT_REQ_PMDCURRENTLOOPPARAMS	0x04D5
MGMSG_MOT_GET_PMDCURRENTLOOPPARAMS	0x04D6

Function: Used to set the current control loop parameters for the specified motor channel.

The motion processors within the BBD series controllers use digital current control as a technique to control the current through each phase winding of the motors. In this way, response times are improved and motor efficiency is increased. This is achieved by comparing the required (demanded) current with the actual current to create a current error, which is then passed through a digital PI-type filter. The filtered current value is used to develop an output voltage for each motor coil.

This method sets various constants and limits for the current feedback loop.

SET:

Command structure (24 bytes)

6 byte header followed by 18 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
D4	04	12	00	d	s	Chan Ident	Phase	KpCurrent			
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>						KiCurrent	ILimCurrent	DeadBand	Kff	Not Used	Not Used

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Phase	The current phase to set: PHASEA 0 PHASEB 1 PHASEA AND B 2	word
KpCurrent	The proportional gain. Together with the KiCurrent this term determines the system response characteristics and accept values in the range 0 to 32767.	word
KiCurrent	The integral gain. Together with the KpCurrent this term determines the system response characteristics and accept values in the range 0 to 32767.	word
ILimCurrent	The ILimCurrent parameter is used to cap the value of the Integrator to prevent runaway of the integral sum at the output. It accepts values in the range 0 to 32767. If set to 0 then the integration term in the PID loop is ignored.	word
IDeadBand	The IDeadBand parameter allows an integral dead band to be set, such that when the error is within this dead band, the integral action stops, and the move is completed using the proportional term only. It accepts values in the range 0	word

	to 32767.	
Kff	The Kff parameter is a feed-forward term that is added to the output of the PID filter to assist in tuning the motor drive signal. It accepts values in the range 0 to 32767.	word
Not Used		word
Not Used		word

Example: Set the limit switch parameters for chan 2 as follows:

Phase: A and B

KpCurrent: 35

KiCurrent: 80

ILimCurrent: 32,767

DeadBand: 50

Kff: 0

TX D4, 04, 12, 00, A2, 01, 01, 00, 02, 00, 23, 00, 50, 00, FF, 7F, 32, 00, 00, 00, 00, 00, 00,

Header: D4, 04, 12, 00, A2, 01: Set_PMDCurrentLoopParams, 18 byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for BBD202)

Phase: 02, 00: Set Phase A and Phase B

KpCurrent: 23, 00,: Set the proportional term to 35

KiCurrent: 50, 00,: Set the integral term to 80

ILimCurrent: FF, 7F,: Set the integral limit to 32767

IDeadBand: 32, 00,: Set the deadband to 50

Kff: 00, 00: Set the feed forward value to zero

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
D8	04	Chan Ident	00	d	s

GET:

Command structure (24 bytes)

6 byte header followed by 18 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
D6	04	12	00	d	s	Chan Ident	Phase	KpCurrent			
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>						KiCurrent	ILimCurrent	DeadBand	Kff	Not Used	Not Used

For structure see SET message above.

MGMSG_MOT_SET_PMDSETTLEDCURRENTLOOPPARAMS	0x04E9
MGMSG_MOT_REQ_PMDSETTLEDCURRENTLOOPPARAMS	0x04EA
MGMSG_MOT_GET_PMDSETTLEDCURRENTLOOPPARAMS	0x04EB

Function: These commands assist in maintaining stable operation and reducing noise at the demanded position. They allow the system to be tuned such that errors caused by external vibration and manual handling (e.g. loading of samples) are minimized, and are applicable only when the stage is settled, i.e. the Axis Settled status bit (bit 14) is set.

SET:

Command structure (24 bytes)

6 byte header followed by 18 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
E9	04	12	00	d	s	Chan Ident	Phase	KpSettled			
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>											
KiSettled	ILimSettled	DeadBandSet	KffSettled	Not Used	Not Used						

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Phase	The current phase to set: PHASEA 0 PHASEB 1 PHASEA AND B 2	word
KpSettled	The proportional gain. Together with the KiSettled this term determines the system response characteristics and accept values in the range 0 to 32767.	word
KiSettled	The integral gain. Together with the KpSettled this term determines the system response characteristics and accept values in the range 0 to 32767.	word
ILimSettled	The ILimSettled parameter is used to cap the value of the Integrator to prevent runaway of the integral sum at the output. It accepts values in the range 0 to 32767. If set to 0 then the integration term in the PID loop is ignored.	word
IDeadBandSettled	The IDeadBandSettled parameter allows an integral dead band to be set, such that when the error is within this dead band, the integral action stops, and the move is completed using the proportional term only. It accepts values in the range 0 to 32767.	word
KffSettled	The KffSettled parameter is a feed-forward term that is added to the output of the PID filter to assist in tuning the motor drive signal. It accepts values in the range 0 to 32767.	word
Not Used		word
Not Used		word

Example: Set the limit switch parameters for chan 2 as follows:

Phase: A and B
 KpSettled: 0
 KiSettled: 40
 ILimSettled: 30,000
 DeadBandSettled: 50
 KffSettled:500

TX E9, 04, 12, 00, A2, 01, 01, 00, 02, 00, 00, 00, 28, 00, 30, 75, 32, 00, F4, 01, 00, 00, 00, 00,

Header: D4, 04, 12, 00, A2, 01: Set_PMDSettledCurrentLoopParams, 18 byte data packet, Channel 2.

Chan Ident: 01, 00: Channel 1 (always set to 1 for BBD202)

Phase: 02, 00: Set Phase A and Phase B

KpCurrent: 00, 00,: Set the proportional term to zero

KiCurrent: 28, 00,: Set the integral term to 40

ILimCurrent: 30, 75,: Set the integral limit to 30,000

IDeadBand: 32, 00,: Set the deadband to 50

Kff: F4, 01: Set the feed forward value to 500

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
D8	04	Chan Ident	00	d	s

GET:

Command structure (24 bytes)

6 byte header followed by 18 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
EB	04	12	00	d	s	Chan Ident	Phase	KpSettled			
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>						KiSettled	ILimSettled	DeadBandSet	KffSettled	Not Used	Not Used

For structure see SET message above.

MGMSG_MOT_SET_PMDSTAGEAXISPARAMS	0x04F0
MGMSG_MOT_REQ_PMDSTAGEAXISPARAMS	0x04F1
MGMSG_MOT_GET_PMDSTAGEAXISPARAMS	0x04F2

Function: The REQ and GET commands are used to obtain various parameters pertaining to the particular stage being driven. Most of these parameters are inherent in the design of the stage and cannot be altered. The SET command can only be used to increase the Minimum position value and decrease the Maximum position value, thereby reducing the overall travel of the stage.

SET:

Command structure (80 bytes)

6 byte header followed by 74 byte data packet – see Get for structure

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
F1	04	Chan Ident	00	d	s

GET:

Command structure (80 bytes)

6 byte header followed by 74 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
F2	04	4A	00	d	s	Chan ID	Stage ID	Axis ID			
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>						Part No/Axis					
24	25	26	27	28	29	30	31	32	33	34	35
<i>Data</i>						Part No/Axis	Serial Number	Counts per Unit			
36	37	38	39	40	41	42	43	44	45	46	47
<i>Data</i>						MinPos	Max Pos	Max Accn			
48	49	50	51	52	53	54	55	56	57	58	59
<i>Data</i>						Max Dec	Max Vel	Reserved	Reserved		
60	61	62	63	64	65	66	67	68	69	70	71
<i>Data</i>						Reserved	Reserved	Reserved	Reserved		
72	73	74	75	76	77	78	79				
<i>Data</i>						Reserved	Reserved				

Data Structure:

field	description	format
Stage ID	This 2 byte parameter identifies the stage and axis: 00, 10 - MLS203_X_AXIS 00, 11 - MLS203_Y_AXIS	word
AxisID	Not used for the BBD series controllers	word
PartNoAxis	A 16 byte character string used to identify the stage type and axis being driven.	char
SerialNum	The Serial number of the stage	dword
CntsPerUnit	The number of encoder counts per real world unit (either mm or degrees).	dword
MinPos	The minimum position of the stage, typically zero	long
MaxPos	The maximum position of the stage in encoder counts	long
MaxAccn	The maximum acceleration of the stage in encoder counts per cycle per cycle	long
MaxDec	The maximum deceleration of the stage in encoder counts per cycle per cycle	long
MaxVel	The maximum velocity of the stage in encoder counts per cycle.	long
Reserved		word
Reserved		dword

Example: Get the stage and axis parameters for chan 2:

Header: F2, 04, 4A, 00, 81, 22: Get PMDStageAxisParams, 74 byte data packet, Bay 1.

Chan Ident: 01, 00: Channel 1 (always set to 1 for BBD202)

Stage ID: 11, 00: MLS203 Y Axis

Axis ID: 00, 00,: Not used

PartNo Axis: 4D, 4C, 53, 32, 30, 33, 20, 59, 20, 41, 78, 69, 73, 00, 00, 00, :

MLS203 Y AXIS

SerialNum: 81.96.98.00

CntsPerUnit 20 4F 00 00

MinPos: 00_00_00_00: the feed minimum position is set to zero

MaxPos: 60 E3 16.00: the maximum position is set to 1500000

MaxAccn: 60, 6B, 00, 00: the maximum acceleration is set to 274

MaxDec: 60_6B_00_00: the maximum deceleration is set to 27488

MaxVel: 00, 0B, 00, 00; the maximum deceleration is set to 27488

Muxver. 9A, 99, 99, 01. the maximum velocity is set to 20845540

MGMSG_MOT_SET_TSTACTUATORTYPE**0x04FE****Function:**

This command is for use only with the TST101 driver, and is used to define an actuator type so that the TST driver knows the effective length of the stage. This information is used if a user wishes to home the stage to the far travel end. In this case, once the stage is homed the APT GUI count will be set to the far travel value. For example, in the case of a ZFS25 the user will see 25mm once homed. The TST holds this value as a number of Trinamic microsteps, which will be a function of the gearbox ratio, the lead screw pitch, and the motor type. So for example the number stored in the TST for the ZFS25 is 54613333.

SET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
FE	04	Actuator Ident	00	d	s

Actuator Idents:

ZST_LEGACY_6MM	0x20
ZST_LEGACY_13MM	0x21
ZST_LEGACY_25MM	0x22
ZST_NEW_6MM	0x30
ZST_NEW_13MM	0x31
ZST_NEW_25MM	0x32
ZFS_NEW_6MM	0x40
ZFS_NEW_13MM	0x41
ZFS_NEW_25MM	0x42
DRV013_25MM	0x50
DRV014_50MM	0x51

Example: Set the actuator type to New ZFS 13 mm Travel:

Header: FE, 04, 31, 00, 50, 01:

MGMSG_MOT_GET_STATUSUPDATE**0x0481**

Function: This message is returned when a status update is requested for the specified motor channel. This request can be used instead of enabling regular updates as described above.

GET:

Status update messages are received with the following format:-

Response structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
81	04	0E	00	d	s	Chan Ident	Position				
12	13	14	15	16	17	18	<i>Data</i>				
EncCount			Status Bits								

Data Structure:

field	description	format
Chan Ident	The channel being addressed is always P_MOD_CHAN1 (0x01) encoded as a 16-bit word (0x01 0x00)	word
Position	The position encoder count. In the APT Stepper Motor controllers the encoder resolution is 25,600 counts per mm, therefore a position change of 1 mm would be seen as this parameter changing by 25,600. The LONG variable is a 32 bit value, encoded in the data stream in the Intel format.	long
EncCount	For use with encoded stages only.	long
Status Bits	The meaning of individual bits in this 32-bit variable is described in the bit mask table below (1 = active, 0 = inactive).	dword

bit mask	meaning
0x00000001	forward (CW) hardware limit switch is active
0x00000002	reverse (CCW) hardware limit switch is active
0x00000004	forward (CW) software limit switch is active
0x00000008	reverse (CCW) software limit switch is active
0x00000010	in motion, moving forward (CW)
0x00000020	in motion, moving reverse (CCW)
0x00000040	in motion, jogging forward (CW)
0x00000080	in motion, jogging reverse (CCW)
0x00000100	motor connected
0x00000200	in motion, homing
0x00000400	homed (homing has been completed)
0x00001000	interlock state (1 = enabled)

This is not full list of all the bits but the remaining bits reflect information about the state of the hardware that in most cases does not affect motion.

MGMSG_MOT_REQ_STATUSUPDATE**0x0480**

Function: Used to request a status update for the specified motor channel.
This request can be used instead of enabling regular updates as described above.

REQUEST:**Command structure (6 bytes):**

0	1	2	3	4	5
<i>header only</i>					
80	04	Chan Ident	00	d	s

GET:

See previous details on [MGMSG_MOT_GET_STATUSUPDATE 0x0481](#).

MGMSG_MOT_GET_DCSTATUSUPDATE**0x0491**

Function: This message is returned when a status update is requested for the specified motor channel. This request can be used instead of enabling regular updates as described above.

GET:

Status update messages are received with the following format:-

Response structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
91	04	0E	00	d	s	Chan Ident	Position				
12	13	14	15	16	17	18	19	<i>Data</i>			
Velocity	Reserved	Status Bits									

Data Structure:

field	description	format
Chan Ident	The channel being addressed is always P_MOD_CHAN1 (0x01) encoded as a 16-bit word (0x01 0x00)	word
Position	The position encoder count. In the BBD10X series controllers the encoder resolution is 20,000 counts per mm, therefore a position change of 1 mm would be seen as this parameter changing by 20,000 (twenty thousand). The LONG variable is a 32 bit value, encoded in the data stream in the Intel format, so for example a position of 1 million encoder counts (equivalent to 50 mm) would be sent as byte stream 0x40, 0x42, 0x0F, 0x00 since 1 million is hexadecimal 0xF4240.	long
Velocity	The actual velocity. Scaling is 204.8 per mm/sec, so a real-life measured speed of 100 mm/sec is read as 205. Again, the two-byte data stream will be encoded in the Intel format.	word
Reserved	Currently Not Used	Word
Status Bits	The meaning of individual bits in this 32-bit variable is described in the bit mask table below	dword

bit mask	meaning
0x00000001	forward hardware limit switch is active
0x00000002	reverse hardware limit switch is active
0x00000010	in motion, moving forward
0x00000020	in motion, moving reverse
0x00000040	in motion, jogging forward
0x00000080	in motion, jogging reverse
0x00000200	in motion, homing

0x00000400	homed (homing has been completed)
0x00001000	tracking
0x00002000	settled
0x00004000	motion error (excessive position error)
0x01000000	motor current limit reached
0x80000000	channel is enabled

This is not full list of all the bits but the remaining bits reflect information about the state of the hardware that in most cases does not affect motion.

MGMSG_MOT_REQ_DCSTATUSUPDATE

0x0490

Function: Used to request a status update for the specified motor channel.
This request can be used instead of enabling regular updates as described above.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
90	04	Chan Ident	00	d	s

GET:

See previous details on [MGMSG_MOT_GET_DCSTATUSUPDATE 0x0491](#).

MGMSG_MOT_ACK_DCSTATUSUPDATE

0x0492

Only Applicable If Using USB COMMS. Does not apply to RS-232 COMMS

Function: If using the USB port, this message called "server alive" must be sent by the server to the controller at least once a second or the controller will stop responding after ~50 commands.
The controller keeps track of the number of "status update" type of messages (e.g. move complete message) and if it has sent 50 of these without the server sending a "server alive" message, it will stop sending any more "status update" messages.
This function is used by the controller to check that the PC/Server has not crashed or switched off. There is no response.

Structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
92	04	00	00	d	s

TX 92, 04, 00, 00, 21, 01

MGMSG_MOT_REQ_STATUSBITS
MGMSG_MOT_GET_STATUSBITS
0x0429
0x042A

Function: Used to request a “cut down” version of the status update message, only containing the status bits, without data about position and velocity.

SET: N/A

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
29	04	Chan Ident	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
2A	04	06	00	d	s	Chan Ident	Status Bits				

Data Structure:

field	description	format
Chan Ident	The channel being addressed	Word
Status Bits	The status bits are assigned exactly as described in the section detailing the MGMSG_MOT_GET_DCSTATUSUPDATE command.	DWord

MGMSG_MOT_SUSPEND_ENDOFMOVEMSGS**0x046B**

Function: Sent to disable all unsolicited end of move messages and error messages returned by the controller, i.e.

MGMSG_MOT_MOVE_STOPPED
MGMSG_MOT_MOVE_COMPLETED
MGMSG_MOT_MOVE_HOMED

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
6B	04	00	00	d	s

MGMSG_MOT_RESUME_ENDOFMOVEMSGS**0x046C**

Function: Sent to resume all unsolicited end of move messages and error messages returned by the controller, i.e.

MGMSG_MOT_MOVE_STOPPED
MGMSG_MOT_MOVE_COMPLETED
MGMSG_MOT_MOVE_HOMED

The command also disables the error messages that the controller sends when an error conditions is detected:

MGMSG_HW_RESPONSE
MGMSG_HW_RICHRESPONSE

This is the default state when the controller is powered up.

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
6C	04	00	00	d	s

MGMSG_MOT_SET_TRIGGER	0x0500
MGMSG_MOT_REQ_TRIGGER	0x0501
MGMSG_MOT_GET_TRIGGER	0x0502

Function: This message is used to configure the Motor controller for triggered move operation. It is possible to configure a particular controller to respond to trigger inputs, generate trigger outputs or both respond to and generate a trigger output. When a trigger input is received, the unit can be set to initiate a move (relative, absolute or home). Similarly the unit can be set to generate a trigger output signal when a specified event (e.g move initiated) occurs. For those units configured for both input and output triggering, a move can be initiated via a trigger input while at the same time, a trigger output can be generated to initiate a move on another unit. The trigger settings can be used to configure multiple units in a master – slave set up, thereby allowing multiple channels of motion to be synchronized. Multiple moves can then be initiated via a single software or hardware trigger command.

SET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
00	05	Chan Ident	Mode	d	s

Note. This message operates differently when used with brushless DC controllers (e.g. BBD20x and TBD001) as opposed to other motor controllers as described in the following paragraphs.

All benchtop stepper controllers (BSC20x),

field	description	format
Chan Ident	The channel being addressed	char
Mode	<p>This parameter sets the trigger mode and move type to be initiated according to the numerical value entered in bits 0 to 7 as follows</p> <p>Bit 0 (0x01): TRIGIN_ENABLE set to enable physical trigger input</p> <p>Bit 1 (0x02): TRIGOUT_ENABLE set to enable trigger output function (mode set by BIT2 or BIT3 below)</p> <p>Bit 2 (0x04): TRIGOUT_MODEFOLLOW set to enable physical trigger output to mirror trig in</p> <p>Bit 3 (0x08): TRIGOUT_MODEMOVEEND set to enable physical trigger output, remains active (high) until move end</p> <p>Bit 4 (0x10): TRIG_RELMOVE set for relative move on trigger</p> <p>Bit 5 (0x20): TRIG_ABSMOVE set for absolute move on trigger</p> <p>Bit 6 (0x40): TRIG_HOMEMOVE set for home sequence on</p>	char

	trigger Bit 7 (0x80): TRIGOUT_NOTRIGIN set to enable physical trigger output with no physical trigger in (i.e. sw initiated trigger)	
--	---	--

Brushless DC controllers only (BBD20x and TBD001)

field	description	format
Chan Ident	The channel being addressed	char
Mode	<p>This parameter sets the trigger mode and move type according to the numerical value entered in bits 0 to 7 as follows</p> <p>Bit 0 (0x01): TRIGIN_HIGH The Trigger input can be configured to initiate a relative, absolute or homing home, either on the rising or falling edge of the signal driving it. As the trigger input is edge sensitive, it needs to see a logic LOW to HIGH transition ("rising edge") or a logic HIGH to LOW transition ("falling edge") for the move to be started.</p> <p>Additionally, the move parameters must be downloaded to the unit prior to the move using the relevant relative move or absolute move methods as described below. A move already in progress will not be interrupted; therefore external triggering will not work until the previous move has been completed. If this bit is set, the logic state is set HIGH.</p> <p>Bit 1 (0x02): TRIGIN_RELMOVE set to enable trigger in and initiate a relative move (specified using the latest MoveRelative or MoveRelativeEx settings) when a trigger input signal is received.</p> <p>Bit 2 (0x04): TRIGIN_ABSMOVE set to enable trigger in and initiate an absolute move (specified using the latest MoveAbsolute or MoveAbsoluteEx settings) when a trigger input signal is received.</p> <p>Bit 3 (0x08): TRIGIN_HOMEMOVE set to enable trigger in and initiate a home move (specified using the latest MoveHome settings) when a trigger input signal is received.</p> <p>Bit 4 (0x10): TRIGOUT_HIGH The Trigger output can be configured to be asserted to either logic HIGH or LOW as a function of certain motion-related conditions, such as when a move is in progress (In Motion), complete (Move Complete) or reaches the constant velocity phase on its trajectory (Max Vel). The logic state of the output will remain the same for as long as the chosen condition is true. If this bit is set, the logic state is set HIGH when the following conditions are true.</p> <p>Bit 5 (0x20): TRIGOUT_INMOTION set to enable trigger out (triggered when in motion)</p> <p>Bit 6 (0x40): TRIGOUT_MOTIONCOMPLETE set to enable trigger out (triggered when motion complete)</p> <p>Bit 7 (0x80): TRIGOUT_MAXVELOCITY set to enable trigger out (triggered when axis at maximum velocity)</p>	char

Example: Set the trigger mode for channel 1 of the BBD201 controller as follows:

- Trigger Input Rising Edge (High)
- Enable trigger input and initiate a Relative Move
- Trigger Output Rising Edge (High)
- Enable trigger output when move complete.

TX 00, 05, 01, 53, 50, 01

00,05 SET_TRIGGER

01, Channel 1

53, i.e. 01010011

50, destination Generic USB device

01, Source PC

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
01	05	Chan Ident	00	d	s

Example: Request the trigger mode

TX 01, 05, 01, 00, 50, 01

GET:

Response structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
02	05	Chan Ident	Mode	d	s

For structure see SET message above.

Filter Flipper Control Messages

Introduction

The APT Filter Flipper drive uses the Motor server control instance control its functionality. The messages listed here provide the extra functionality required for a client application to control one or more of the Thorlabs series of MFF series flipper units.

MGMSG_MOT_SET_MFF_OPERPARAMS	0x0510
MGMSG_MOT_REQ_MFF_OPERPARAMS	0x0511
MGMSG_MOT_GET_MFF_OPERPARAMS	0x0512

Function: Used to set various operating parameters that dictate the function of the MFF series flipper unit.

SET:

Command structure (40 bytes)

6 byte header followed by 34 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
10	05	22	00	d	s	Chan Ident	lTransitTime				
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>											
lTransitTimeADC				OperMode1		SigMode1	PulseWidth1				
24	25	26	27	28	29	30	31	32	33	34	35
<i>Data</i>											
OperMode2	SigMode2		PulseWidth2				Not Used				
36	37	38	39								
Not Used											

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
lTransitTime	The time taken (in milliseconds) for the flipper to move from position 1 to position 2 and vice versa. Values must be entered in the range 300 to 2800 ms.	long
lTransitTimeADC	<p>The time taken (in ADC counts) for the flipper to move from position 1 to position 2 and vice versa.</p> <p>The number of ADC counts is calculated from an equation that relates actual time of flight in milliseconds to the ADC value required by the flipper code.</p> <p>The equation relating the two variables is defined as follows</p> $\text{TransitTimeADC} = 10000000 \times \text{TransitTime}^{-1.591}$ <p>Example</p> <p>A transit time of 500 ms would be calculated as</p> $\text{TransitTimeADC} = 10000000 \times 500^{-1.591} = 10000000 \times 0.00005080877 = 508.0877$ <p>so a user requiring 500ms motion time needs to set 508 as the ADC value in the structure. This value is then used by the flipper to give a reasonable approximation for the actual time of flight.</p>	long

wDigIO1OperMode	<p>Specifies the operating mode of the DIG IO 1 input/output signal as follows:</p> <p>01 Sets IO connector to input and 'toggle position' mode. In this mode, the input signal causes flipper to move to other position).</p> <p>02 Sets IO connector to input and 'goto position' mode. In this mode, the input signal dictates flipper position, POS 1 or POS 2. as dictated by the Button Input or Button Input (Swap Pos) parameters set in the DigIOSigMode parameter below.</p> <p>03 Sets IO connector to output mode, where the O/P signal indicates the flipper is 'at position'.</p> <p>04 Sets IO connector to output mode, where the O/P signal indicates the flipper is in motion (i.e. between positions).</p>	word
wDigIO1SigMode	<p>Specifies the functionality of the input/output signal. as follows:</p> <p>01 The connector can be short circuited (e.g. with button). If the Operating Mode is set to Input:Toggle Position then a short circuit causes the flipper to toggle position. If the Operating Mode is set to Input: Goto Position then a short circuit causes the flipper to move to Pos 1 and open circuit causes flipper to move to POS</p> <p>02. The connector is set to logic input where a logic transition (edge) dictates flipper operation. If the Operating Mode above set to Input:Toggle Position, then a LO to HI edge causes flipper to toggle position. If the Operating Mode is set to Input: Goto Position, then a LO to HI edge causes the flipper to move to POS 1 and a HI to LO edge causes the flipper to move to POS 2.</p> <p>04 This parameter can be 'Bitwise Ored' with either the button or the logic parameters above, such that the open circuit and short circuit or the edge functionality is swapped.</p> <p>10 The connector is set to a logic output where the logic transition (edge) represents flipper position. If the Operating Mode above is set to Output: At Position, then a LO to HI edge (HI level) indicates flipper is at POS 1 and a HI to LO edge (LO level) indicates the flipper is at POS 2. If the Operating Mode above is set to Output: InMotion, then a LO to HI edge (HI level) indicates the flipper is moving between positions and a HI to LO edge (LO level) indicates the flipper has stopped moving.</p> <p>20 MFFSIGMODE_OP_PULSE The connector is set to</p>	word

	a logic output where a logic pulse indicates flipper operation. If the Operating Mode above is set to Output: At Position, then a logic HI pulse indicates the flipper has reached a position. If the Operating Mode above is set to Output: InMotion, then a logic HI pulse indicates the flipper has started moving. The Pulse width is set in the Signal Width parameter below.	
	40 This parameter can be 'Bitwise Ored' with either the level (edge) or the pulse parameters above, such that the level or pulse functionality is swapped.	
IDigIO1PulseWidth	The pulse width in ms when the Digital Signal Mode described previously is set to Logic Pulse Output or Logic Pulse Output (Inverted). The pulse width is set within the range 10 to 200 ms.	long
wDigIO2OperMode	As DigIO1	word
wDigIO2SigMode	As DigIO1	word
IDigIO2PulseWidth	As DigIO1	long
Not Used		long
Not Used		dword

Example: Set the MFF parameters for chan 1 as follows:

TransitTime	500 ms
TransitTimeADC	508 counts
DigIO1OperMode	Toggle Position
DigIO1SigMode	Button Mode Input
DigIO1PulseWidth	200 ms
DigIO2OperMode	Toggle Position
DigIO2SigMode	Button Mode Input
DigIO2PulseWidth	200 ms
Not Used	
Not Used	

TX 10,05,22,00,D0,01,
01,00,F4,01,00,00,FC,01,00,00,01,00,01,00,C8,00,00,00,01,00,01,00,C8,00,00,00,00,00,00,00,
,00,00,00,00

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
11	05	Chan Ident	00	d	s

Example: Request the MFF operating modes

TX 11, 05, 01, 00, 50, 01

GET:

Response structure (40 bytes):

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
10	05	22	00	d	s	Chan Ident	ITransitTime				
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>						OperMode1	SigMode1	PulseWidth1			
24	25	26	27	28	29	30	31	32	33	34	35
<i>Data</i>						OperMode2	SigMode2	PulseWidth2			Not Used
36	37	38	39								
Not Used											

See SET for structure

Solenoid Control Messages

Introduction

The APT Solenoid drive uses the Motor server control instance control its functionality. The messages listed here provide the extra functionality required for a client application to control one or more of the Thorlabs series of TSC001 T-Cube solenoid driver units.

MGMSG_MOT_SET_SOL_OPERATINGMODE	0x04C0
MGMSG_MOT_REQ_SOL_OPERATINGMODE	0x04C1
MGMSG_MOT_GET_SOL_OPERATINGMODE	0x04C2

Function: This message sets the operating mode of the solenoid driver.

SET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
C0	04	Chan Ident	Mode	d	s

Data Structure:

field	description	format
Chan Ident	The channel being addressed	char
Operating Mode	<p>The operating mode of the unit as a 4 bit integer:</p> <p>0x01 SOLENOID_MANUAL - In this mode, operation of the solenoid is via the front panel 'Enable' button, or by the 'Output' buttons on the GUI panel.</p> <p>0x02 SOLENOID_SINGLE - In this mode, the solenoid will open and close each time the front panel 'Enable' button is pressed, or the 'Output ON' button on the GUI panel is clicked. The ON and OFF times are specified by calling the MGMSG_MOT_SET_SOL_CYCLEPARAMS message.</p> <p>0x03 SOLENOID_AUTO - In this mode, the solenoid will open and close continuously after the front panel 'Enable' button is pressed, or the 'Output ON' button on the GUI panel is clicked. The ON and OFF times, and the number of cycles performed, are specified by calling the MGMSG_MOT_SET_SOL_CYCLEPARAMS message.</p> <p>0x04 SOLENOID_TRIGGER - In Triggered mode, a rising edge on rear panel TRIG IN BNC input will start execution of the parameters programmed on the unit (On Time, Off Time, Num Cycles - see MGMSG_MOT_SET_SOL_CYCLEPARAMS message.). The unit must be primed (i.e. the ENABLE button pressed and the ENABLED LED lit) before the unit can respond to the external trigger.</p>	char

Example: Set the control mode to 'Single'.

TX C0, 04, 01, 02, 50, 01

C0,04 SET_SOL_OPERATINGMODE
 01, Channel 1
 02, Set mode to 'Single'
 50, destination Generic USB device
 01, Source PC

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
C1	04	Chan Ident	00	d	s

Example:

Request the control mode

TX C1, 04, 01, 00, 50, 01

GET:

Response structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
C2	04	Chan Ident	Mode	d	s

Example:

Get the control mode currently set.

RX C2, 04, 01, 01, 01, 50

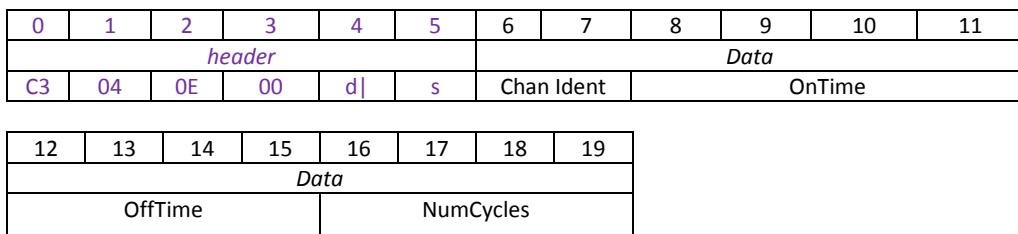
MGMSG_MOT_SET_SOL_CYCLEPARAMS	0x04C3
MGMSG_MOT_REQ_SOL_CYCLEPARAMS	0x04C4
MGMSG_MOT_GET_SOL_CYCLEPARAMS	0x04C5

Function: Used to set the cycle parameters that are applicable when the solenoid controller is operating in one of the non-manual modes.

SET:

Command structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:



Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
OnTime	The time which the solenoid is activated (100ms to 10,000s in 250 µs steps)	long
OffTime	The time which the solenoid is de-activated (100ms to 10,000s in 250 µs steps)	long
NumCycles	If the unit is operating in 'Auto' mode, the number of Open/Close cycles to perform. (0 to 1,000,000) is specified in the NumCycles parameter. If set to '0' the unit cycles indefinitely. If the unit is not operating in 'Auto' mode, the NumCycles parameter is ignored.	long

Example: Set the cycle parameters parameters for chan 1 as follows:

OnTime: 1000ms

OffTime: 1000ms

NumCycles: 20

TX C3, 04, OE, 00, D0, 01, 01, 00, A0, OF, 00, 00, A0, OF, 00, 00, 14, 00, 00, 00

Header: C3, 04, OE, 00, D0, 01: Set Cycle Params, D0H (14) byte data packet, Generic USB Device.

Chan Ident: 01, 00: Channel 1 (always set to 1 for TSC001)

OnTime: A0, OF, 00, 00: Set on time to 1000 ms (i.e. 4000 x 250 µs)

OffTime: A0, OF, 00, 00: Set off time to 1000 ms (i.e. 4000 x 250 µs)

NumCycles: 14, 00, 00, 00: Set number of cycles to 20

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
C4	04	Chan Ident	00	d	s

GET:

Response structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11					
<i>header</i>						<i>Data</i>										
C5	04	0E	00	d	s	Chan Ident	OnTime									
<i>Data</i>																
OffTime						NumCycles										

For structure see SET message above.

MGMSG_MOT_SET_SOL_INTERLOCKMODE	0x04C6
MGMSG_MOT_REQ_SOL_INTERLOCKMODE	0x04C7
MGMSG_MOT_GET_SOL_INTERLOCKMODE	0x04C8

Function: The solenoid unit features a hardware interlock jackplug. This message specifies whether the solenoid driver requires the hardware interlock to be fitted before it can operate.

SET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
C6	04	Chan Ident	Mode	d	s

Data Structure:

field	description	format
Chan Ident	The channel being addressed	char
Interlock Mode	The operating mode of the unit as a 4 bit integer: 0x01 SOLENOID_ENABLED – The hardware interlock must be fitted before the unit can be operated. 0x02 SOLENOID_DISABLED – The hardware interlock is not required.	char

Example: Set the interlock mode to ‘Enabled’.

TX C6, 04, 01, 01, 50, 01

C0,06 SET_SOL_INTERLOCKMODE
 01, Channel 1
 01, Set mode to ‘Enabled’
 50, destination Generic USB device
 01, Source PC

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
C7	04	Chan Ident	00	d	s

Example:

Request the control mode

TX C7, 04, 01, 00, 50, 01

GET:

Response structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
C8	04	Chan Ident	Mode	d	s

Example:

Get the control mode currently set.

RX C8, 04, 01, 01, 01, 50

MGMSG_MOT_SET_SOL_STATE	0x04CB
MGMSG_MOT_REQ_SOL_STATE	0x04CC
MGMSG_MOT_GET_SOL_STATE	0x04CD

Function: This message sets the output state of the solenoid unit, and overrides any existing settings. It can also be operated by the [SET_CHANENABLESTATE](#) message.

SET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
CB	04	Chan Ident	State	d	s

Data Structure:

field	description	format
Chan Ident	The channel being addressed	char
Interlock Mode	The operating mode of the unit as a 4 bit integer: 0x01 SOLENOID_ON – The solenoid is active. 0x02 SOLENOID_OFF – The solenoid is de-activated.	char

Example: Set the solenoid to 'ON'.

TX CB, 04, 01, 01, 50, 01

CB,06 SET_SOL_STATE
 01, Channel 1
 01, Set state to 'ON'
 50, destination Generic USB device
 01, Source PC

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
CC	04	Chan Ident	00	d	s

Example:

Request the control mode

TX CC, 04, 01, 00, 50, 01

GET:

Response structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
CD	04	Chan Ident	Mode	d	s

Example:

Get the control mode currently set.

RX CD, 04, 01, 01, 01, 50

Piezo Control Messages

Introduction

The ‘Piezo’ control messages provide the functionality required for a client application to control one or more of the Thorlabs series of piezo controller units. This range of controllers covers both open and closed loop piezo control in a variety of formats including compact Cube type controllers, benchtop units and 19” rack based modular drivers. **Note.** For ease of description, the TSG001 T-Cube Strain Gauge reader is considered here as a piezo controller. The list of controllers covered by the piezo messages includes:-

BPC001 – 1 Channel Benchtop Piezo Driver
BPC002 – 2 Channel Benchtop Piezo Driver
MPZ601 – 2 Channel Modular Piezo Driver
BPC101 – 1 Channel Benchtop Piezo Driver (2006 onwards)
BPC102 – 2 Channel Benchtop Piezo Driver (2006 onwards)
BPC103 – 3 Channel Benchtop Piezo Driver (2006 onwards)
BPC201 – 1 Channel Benchtop Piezo Driver (2007 onwards)
BPC202 – 2 Channel Benchtop Piezo Driver (2007 onwards)
BPC203 – 3 Channel Benchtop Piezo Driver (2007 onwards)
BPC301 – 1 Channel Benchtop Piezo Driver (2011 onwards)
BPC303 – 3 Channel Benchtop Piezo Driver (2012 onwards)
TPZ001 – 1 Channel T-Cube Piezo Driver
TSG001 – 1 Channel T-Cube Strain Gauge Reader

The piezo messages can be used to perform activities such as selecting output voltages, reading the strain gauge position feedback, operating open and closed loop modes and enabling force sensing mode. With a few exceptions, these messages are generic and apply equally to both single and dual channel units.

Where applicable, the target channel is identified in the IChanID parameter and on single channel units, this must be set to CHAN1_ID. On dual channel units, this can be set to CHAN1_ID, CHAN2_ID or CHANBOTH_ID as required.

For details on the operation of the Piezo Controller, and information on the principles of operation, refer to the handbook supplied with the unit.

MGMSG_PZ_SET_POSCONTROLMODE	0x0640
MGMSG_PZ_REQ_POSCONTROLMODE	0x0641
MGMSG_PZ_GET_POSCONTROLMODE	0x0642

Function: When in closed-loop mode, position is maintained by a feedback signal from the piezo actuator. This is only possible when using actuators equipped with position sensing.
This method sets the control loop status. The Control Mode is specified in the Mode parameter as follows:

- 0x01 Open Loop (no feedback)
- 0x02 Closed Loop (feedback employed)
- 0x03 Open Loop Smooth
- 0x04 Closed Loop Smooth

If set to Open Loop Smooth or Closed Loop Smooth is selected, the feedback status is the same as above however the transition from open to closed loop (or vice versa) is achieved over a longer period in order to minimize voltage transients (spikes).

SET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
40	06	Chan Ident	Mode	d	s

Example: Set the control mode to closed loop.

TX 40, 06, 01, 02, 50, 01

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
41	06	Chan Ident	00	d	s

Example: Request the control mode

TX 41, 06, 01, 00, 50, 01

GET:

Response structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
42	06	Chan Ident	Mode	d	s

Example:

Get the control mode currently set.

RX 42, 06, 01, 02, 01, 50

MGMSG_PZ_SET_OUTPUTVOLTS	0x0643
MGMSG_PZ_REQ_OUTPUTVOLTS	0x0644
MGMSG_PZ_GET_OUTPUTVOLTS	0x0645

Function: Used to set the output voltage applied to the piezo actuator. This command is applicable only in Open Loop mode. If called when in Closed Loop mode it is ignored.

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
43	06	04	00	d	s	Chan Ident	Voltage		

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Voltage	The output voltage applied to the piezo when operating in open loop mode. The voltage is set in the range -32768 to 32767 (-7FFF to 7FFF) to which corresponds to -100% to 100% of the maximum output voltage as set using the TPZ_IOSETTINGS command.	short

Example: Set the drive voltage to 70V

TX 43, 06, 04, 00, D0, 01, 00, 77, 77,

Header: 43, 06, 04, 00, D0, 01: SetPZOutputVolts, 04 byte data packet, Generic USB Device.

Chan Ident: 01, 00: Channel 1

Voltage: 77, 77: corresponds to 70 V (30583) for a max 75 V unit

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
44	6	Chan Ident	00	d	s

GET:

Response structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
45	06	04	00	d	s	Chan Ident	Voltage		

For structure see SET message above.

MGMSG_PZ_SET_OUTPUTPOS	0x0646
MGMSG_PZ_REQ_OUTPUTPOS	0x0647
MGMSG_PZ_GET_OUTPUTPOS	0x0648

Function: Used to set the output position of piezo actuator. This command is applicable only in Closed Loop mode. If called when in Open Loop mode it is ignored. The position of the actuator is relative to the datum set for the arrangement using the [ZeroPosition](#) method.

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
46	06	04	00	d	s	Chan Ident	PositionSW		

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
PositionSW	The output position of the piezo relative to the zero position. The voltage is set in the range 0 to 32767 (0 to 7FFF) or 0 to 65535 (0 to FFFF) depending on the unit. This corresponds to 0 to 100% of the maximum piezo extension.	word

Example: Set the drive position to 15 µm (when total travel = 100 µm).

TX 46, 06, 04, 00, D0, 01, 01, 00, 66, 26,

Header: 46, 06, 04, 00, D0, 01: SetPZOutputPos, 04 byte data packet, Generic USB Device.

Chan Ident: 01, 00: Channel 1

PositionSW: 33, 13: corresponds to 15 µm for a max 100 µm unit

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
47	06	Chan Ident	00	d	s

GET:

Response structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
48	06	04	00	d	s	Chan Ident	PositionSW		

For structure see SET message above.

MGMSG_PZ_SET_INPUTVOLTSSRC	0x0652
MGMSG_PZ_REQ_INPUTVOLTSSRC	0x0653
MGMSG_PZ_GET_INPUTVOLTSSRC	0x0654

Function: Used to set the input source(s) which controls the output from the HV amplifier circuit (i.e. the drive to the piezo actuators).

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>					<i>Data</i>				
52	06	04	00	d	s	Chan Ident	VoltSrc		

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
VoltSrc	<p>The following values are entered into the VoltSrc parameter to select the various analog sources.</p> <p><i>0x00 Software Only:</i> Unit responds only to software inputs and the HV amp output is that set using the SetVoltOutput method or via the GUI panel.</p> <p><i>0x01 External Signal:</i> Unit sums the differential signal on the rear panel EXT IN (+) and EXT IN (-)connectors with the voltage set using the SetVoltOutput method</p> <p><i>0x02 Potentiometer:</i> The HV amp output is controlled by a potentiometer input (either on the control panel, or connected to the rear panel User I/O D-type connector) summed with the voltage set using the SetVoltOutput method.</p> <p>The values can be ‘bitwise or’ to sum the software source with either or both of the other source options.</p>	word

Example: Set the input source to software and potentiometer.

TX 52, 06, 04, 00, D0, 01, 01, 00, 02, 00,

Header: 52, 06, 04, 00, D0, 01: SetVoltsSrc, 04 byte data packet, Generic USB Device.

Chan Ident: 01, 00: Channel 1

VoltSrc: 02, 00: selects software and potentiometer inputs

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
53	06	Chan Ident	00	d	s

GET:

Response structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>					<i>Data</i>				
54	06	04	00	d	s	Chan Ident	VoltsSrc		

For structure see SET message above.

MGMSG_PZ_SET_PICONSTS	0x0655
MGMSG_PZ_REQ_PICONSTS	0x0656
MGMSG_PZ_GET_PICONSTS	0x0657

Function: Used to set the proportional and integration feedback loop constants. These parameters determine the response characteristics when operating in closed loop mode. The processors within the controller compare the required (demanded) position with the actual position to create an error, which is then passed through a digital PI-type filter. The filtered value is used to develop an output voltage to drive the piezo.

SET:

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
55	06	06	00	d	s	Chan Ident	PropConst	IntConst			

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
PropConst	The value of the proportional term in the range 0 to 255.	word
IntConst	The value of the Integral term.in the range 0 to 255	word

Example: Set the PI constants for a TPZ001 unit.

TX 55, 06, 06, 00, D0, 01, 01, 00, 64, 00, 0F, 00

Header: 55, 06, 05, 00, D0, 01: SetPIConsts, 06 byte data packet, Generic USB Device.

Chan Ident: 01, 00: Channel 1

PropConst: 64, 00: sets the proportional constant to 100

IntConst: 0F, 00: sets the integral constant to 15

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
56	06	Chan Ident	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
57	06	06	00	d	s	Chan Ident	PropConst	IntConst			

For structure see SET message above.

**MGMSG_PZ_REQ_PZSTATUSBITS
MGMSG_PZ_GET_PZSTATUSBITS**
**0x065B
0x065C**

Function: Returns a number of status flags pertaining to the operation of the piezo controller channel specified in the Chan Ident parameter. These flags are returned in a single 32 bit integer parameter and can provide additional useful status information for client application development. The individual bits (flags) of the 32 bit integer value are described in the following tables.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
5B	06	Chan Ident	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
5C	06	06	00	d	s	Chan Ident					StatusBits

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
StatusBits	The status bits for the associated controller channel. The meaning of the individual bits (flags) of the 32 bit integer value will depend on the controller and are described in the following tables.	dword

TPZ001 controller

Hex Value	Bit Number	Description
0x00000001	1	Piezo actuator connected (1 - connected, 0 - not connected).
	2 to 4	For Future Use
0x00000010	5	Piezo channel has been zero'd (1 - zero'd, 0 not zero'd).
0x00000020	6	Piezo channel is zeroing (1 - zeroing, 0 - not zeroing).
0x00000040	7 to 8	For Future Use
0x00000100	9	Strain gauge feedback connected (1 - connected, 0 - not connected).
	10	For Future Use
0x00000400	11	Position control mode (1 - closed loop, 0 - open loop).
	12 to 20	For Future Use

BPC series controllers

Hex Value	Bit Number	Description
0x00000001	1	Piezo actuator connected (1 - connected, 0 - not connected).
	2 to 4	For Future Use
0x00000010	5	Piezo channel has been zero'd (1 - zero'd, 0 not zero'd).
0x00000020	6	Piezo channel is zeroing (1 - zeroing, 0 - not zeroing).
0x00000040	7 to 8	For Future Use
0x00000100	9	Strain gauge feedback connected (1 - connected, 0 - not connected).
	10	For Future Use
0x00000400	11	Position control mode (1 - closed loop, 0 - open loop).
	12	For Future Use
Note. Bits 13, 14 and 15 are applicable only to BPC30x series controllers.		
0x00001000	13	Hardware set to 75 V max output voltage
0x00002000	14	Hardware set to 100 V max output voltage
0x00004000	15	Hardware set to 150 V max output voltage
	16 to 20	For Future Use
Note. Bits 21 to 28 (Digital Input States) are only applicable if the associated digital input is fitted to your controller – see the relevant handbook for more details		
0x00100000	21	Digital input 1 state (1 - logic high, 0 - logic low).
0x00200000	22	Digital input 2 state (1 - logic high, 0 - logic low).
0x00400000	23	Digital input 3 state (1 - logic high, 0 - logic low).
0x00800000	24	Digital input 4 state (1 - logic high, 0 - logic low).
0x01000000	25	Digital input 5 state (1 - logic high, 0 - logic low).
0x02000000	26	Digital input 6 state (1 - logic high, 0 - logic low).
0x04000000	27	Digital input 7 state (1 - logic high, 0 - logic low).
0x08000000	28	Digital input 8 state (1 - logic high, 0 - logic low).
	29	For Future Use
0x20000000	30	Active (1 – indicates unit is active, 0 – not active)
0x40000000	31	For Future Use
0x80000000	32	Channel enabled (1 – enabled, 0- disabled)

MGMSG_PZ_GET_PZSTATUSUPDATE**0x0661**

Function: This function is used in applications where spontaneous status messages (i.e. messages sent using the START_STATUSUPDATES command) must be avoided. There is no REQ message. Status update messages contain information about the position and status of the controller (for example position and O/P voltage). The messages will be sent by the controller each time the function is called.

NOTE. This message is also returned by the NanoTrak control when it is operating in piezo mode.

GET:

Status update messages are received with the following format:-

Response structure (16 bytes)

6 byte header followed by 10 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
61	06	0A	00	d	s	Chan Ident	OPVoltage	Position			
12	13	14	15								
				Status Bits							

Data Structure:

field	description	format
Chan Ident	The channel being addressed is always P_MOD_CHAN1 (0x01) encoded as a 16-bit word (0x01 0x00)	word
OPVoltage	The output voltage applied to the piezo. The voltage is returned in the range -32768 to 32767 (-7FFF to 7FFF) which corresponds to -100% to 100% of the maximum output voltage as set using the TPZ_IOSETTINGS command.	short
Position	The position of the piezo. The position is returned in the range 0 to 32767 (0 to 7FFF) which corresponds to 0 to 100% of the maximum position.	short
Status Bits	The meaning of the individual bits (flags) of the 32 bit integer value will depend on the controller and are described in the following tables.	dword

TPZ001 controller

Hex Value	Bit Number	Description
0x00000001	1	Piezo actuator connected (1 - connected, 0 - not connected).
	2 to 4	For Future Use
0x00000010	5	Piezo channel has been zero'd (1 - zero'd, 0 not zero'd).
0x00000020	6	Piezo channel is zeroing (1 - zeroing, 0 - not zeroing).
0x00000040	7 to 8	For Future Use
0x00000100	9	Strain gauge feedback connected (1 - connected, 0 - not connected).
	10	For Future Use
0x00000400	11	Position control mode (1 - closed loop, 0 - open loop).
	12 to 20	For Future Use

BPC series controllers

Hex Value	Bit Number	Description
0x00000001	1	Piezo actuator connected (1 - connected, 0 - not connected).
	2 to 4	For Future Use
0x00000010	5	Piezo channel has been zero'd (1 - zero'd, 0 not zero'd).
0x00000020	6	Piezo channel is zeroing (1 - zeroing, 0 - not zeroing).
0x00000040	7 to 8	For Future Use
0x00000100	9	Strain gauge feedback connected (1 - connected, 0 - not connected).
	10	For Future Use
0x00000400	11	Position control mode (1 - closed loop, 0 - open loop).
	12 to 20	For Future Use
Note. Bits 21 to 28 (Digital Input States) are only applicable if the associated digital input is fitted to your controller – see the relevant handbook for more details		
0x00100000	21	Digital input 1 state (1 - logic high, 0 - logic low).
0x00200000	22	Digital input 2 state (1 - logic high, 0 - logic low).
0x00400000	23	Digital input 3 state (1 - logic high, 0 - logic low).
0x00800000	24	Digital input 4 state (1 - logic high, 0 - logic low).
0x01000000	25	Digital input 5 state (1 - logic high, 0 - logic low).
0x02000000	26	Digital input 6 state (1 - logic high, 0 - logic low).
0x04000000	27	Digital input 7 state (1 - logic high, 0 - logic low).
0x08000000	28	Digital input 8 state (1 - logic high, 0 - logic low).
	29	For Future Use
0x20000000	30	Active (1 – indicates unit is active, 0 – not active)
0x40000000	31	For Future Use
0x80000000	32	Channel enabled (1 – enabled, 0- disabled)

MGMSG_PZ_ACK_PZSTATUSUPDATE**0x0662****Only Applicable If Using USB COMMS. Does not apply to RS-232 COMMS**

Function: If using the USB port, this message called "server alive" must be sent by the server to the controller at least once a second or the controller will stop responding after ~50 commands. The controller keeps track of the number of "status update" type of messages (e.g. move complete message) and if it has sent 50 of these without the server sending a "server alive" message, it will stop sending any more "status update" messages. This function is used by the controller to check that the PC/Server has not crashed or switched off. There is no response.

Structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
62	06	00	00	d	s

TX 62, 06, 00, 00, 50, 01

MGMSG_PZ_SET_OUTPUTLUT	0x0700
MGMSG_PZ_REQ_OUTPUTLUT	0x0701
MGMSG_PZ_GET_OUTPUTLUT	0x0702

Function: It is possible to use the controller in an arbitrary Waveform Generator Mode (WGM). Rather than the unit outputting an adjustable but static voltage or position, the WGM allows the user to define a voltage or position sequence to be output, either periodically or a fixed number of times, with a selectable interval between adjacent samples.

This waveform generation function is particularly useful for operations such as scanning over a particular area, or in any other application that requires a predefined movement sequence.

The waveform is stored as values in an array, with a maximum of 8000 samples per channel. The samples can have the meaning of voltage or position; if open loop operation is specified when the samples are output, then their meaning is voltage and vice versa, if the channel is set to closed loop operation, the samples are interpreted as position values. If the waveform to be output requires less than 8000 samples, it is sufficient to download the desired number of samples.

This function is used to load the LUT array with the required output waveform. The applicable channel is specified by the Chan Ident parameter

If only a sub set of the array is being used (as specified by the cyclelength parameter of the [SetOutputLUTParams](#) function), then only the first cyclelength values need to be set. In this manner, any arbitrary voltage waveform can be programmed into the LUT.

Note. The LUT values are output by the system at a maximum bandwidth of 7KHz, e.g. 500 LUT values will take approximately 71 ms to be clocked out and the full 8000 LUT values will take approximately 1.14 secs.

SET:

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
00	07	06	00	d	s	Chan Ident	Index	Output			

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Index	The position in the array of the value to be set (0 to 7999 for BPC, 0 to 512 for TPZ).	word
Output	The voltage value to be set. Values are set in the range -32768 to 32767 which corresponds to -100% to 100% of the max HV output (piezo drive voltage).	short

Example: Set output LUT value of 10V (for 150V piezo) in array position 2.

TX 00, 07, 06, 00, D0, 01, 01, 00, 02, 00, 88, 08

Header: 00, 07, 06, 00, D0, 01: SETOUTPUTLUT, 06 byte data packet, Generic USB Device.

Chan Ident: 01, 00: Channel 1

Index: 02, 00: sets the value of array position 2

IntConst: 88, 08: sets the value to 10V. (i.e. 150/10=15, 32767/15=2184, 2184=0888H)

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
01	07	Chan Ident	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
02	07	06	00	d	s	Chan Ident	Index	Output			

For structure see SET message above.

MGMSG_PZ_SET_OUTPUTLUTPARAMS	0x0703
MGMSG_PZ_REQ_OUTPUTLUTPARAMS	0x0704
MGMSG_PZ_GET_OUTPUTLUTPARAMS	0x0705

Function: It is possible to use the controller in an arbitrary Waveform Generator Mode (WGM). Rather than the unit outputting an adjustable but static voltage or position, the WGM allows the user to define a voltage or position sequence to be output, either periodically or a fixed number of times, with a selectable interval between adjacent samples.
 This waveform generation function is particularly useful for operations such as scanning over a particular area, or in any other application that requires a predefined movement sequence.
 This function is used to set parameters which control the output of the LUT array.

SET:

Command structure (36 bytes)

6 byte header followed by 30 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
03	07	1E	00	d	s	Chan Ident	Mode	CycleLength			
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>						NumCycles					
<i>Data</i>						DelayTime	PreCycleRest				
24	25	26	27	28	29	30	31	32	33	34	35
<i>Data</i>						OPTrigStart	OPTrigWidth	TrigRepCycle			

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Mode	<p>Specifies the output mode of the LUT waveform as follows. Values can be ‘bitwise or’d together as required.</p> <p>0x01 - OUTPUTLUT_CONTINUOUS – The waveform is output continuously (i.e. until a StopOPLUT command is received).</p> <p>0x02 - OUTPUTLUT_FIXED – A fixed number of waveform cycles are output (as specified in the NumCycles parameter).</p> <p>The following values are not applicable to the TPZ001 unit because it has no triggering functionality.</p> <p>0x04 - OUTPUTLUT_OUTPUTTRIG – Enables Output Triggering. With OP Triggering enabled, the system can be configured to generate one or more hardware trigger pulses during a LUT (waveform) cycle output, as specified in the OPTrigStart parameter below.</p>	word

	<p>0x08 - OUTPUTLUT_INPUTTRIG –Enables Input Triggering. With INPUTTRIG set to ‘False’, the waveform generator will start as soon as it receives a StartOPLUT command. If however, INPUTTRIG is set to ‘True, waveform generation will only start if a software command is received AND the trigger input is in its active state. In most cases, the trigger input will be used to synchronize waveform generation to an external event. In this case, the StartOPLUT command can be viewed as a command to "arm" the waveform generator and the waveform will start as soon as the input becomes active.</p> <p>The trigger input can be used to trigger a single channel or multiple channels. In this latter case ensure that input triggering is enabled on all the desired channels. Using the trigger input for multiple channels is particularly useful to synchronize all channels to the same event.</p> <p>0x10 - OUTPUTLUT_OUTPUTTRIG_SENSE_HI – determines the voltage sense and edge of the O/P trigger. If this bit is set, the units responds to a rising edge (0V to 5V) trigger. If not set it responds to a falling edge (5V to 0V).</p> <p>0x20 - OUTPUTLUT_INPUTTRIG_SENSE_HI – determines the voltage sense and edge of the I/P trigger. If this bit is set, the units responds to a rising edge (0V to 5V) trigger. If not set it responds to a falling edge (5V to 0V).</p> <p>0x40 - OUTPUTLUT_LUTGATED – If set to ‘1’ the trigger acts as a gate, if set to ‘0’ acts as trigger.</p> <p>0x80 - OUTPUTLUT_OUTPUTTRIG_REPEAT – This parameter is a flag which determines if repeated O/P triggering is enabled. If set, the output trigger is repeated by the interval set in the TrigRepeatCycle parameter. This is useful for multiple triggering during a single voltage O/P sweep.</p>	
CycleLength	Specifies how many samples will be output in each cycle of the waveform. It can be set in the range 0 to 7999 for BPC and MPZ units, and 0 to 512 for TPZ units. It must be less than or equal to the total number of samples that were loaded. (To set the LUT array values for a particular channel, see the SetOutputLUT function).	word
NumCycles	Specifies the number of cycles (1 to 2147483648) to be output when the Mode parameter is set to fixed. If Mode is set to Continuous, the NumCycles parameter is ignored. In both cases, the waveform is not output until a StartOPLUT command is received.	long
DelayTime	<p>Specifies the delay (in sample intervals) that the system waits after setting each LUT output value. By default, the time the system takes to output LUT values (sampling interval) is set at the maximum bandwidth possible, i.e. 7KHz (0.14 ms) for MPZ models, 1kHz(1.0 ms) for BPC and 4 kHz (0.25 ms) for TPZ units.</p> <p>The DelayTime parameter specifies the time interval between neighbouring samples, i.e. for how long the</p>	long

	<p>sample will remain at its present value.</p> <p>To increase the time between samples, set the DelayTime parameter to the required additional delay (1 to 2147483648 sample intervals). In this way, the user can stretch or shrink the waveform without affecting its overall shape.</p>	
PreCycleRest	<p>In some applications, during waveform generation the first and the last samples may need to be handled differently from the rest of the waveform. For example, in a positioning system it may be necessary to start the movement by staying at a certain position for a specified length of time, then perform a movement, then remain at the last position for another specified length of time. This is the purpose of PreCycleRest and PostCycleRest parameters, i.e. they specify the length of time that the first and last samples are output for, independently of the DelayTime parameter.</p> <p>The PreCycleRest parameter allows a delay time to be set before the system starts to clock out the LUT values. The delay can be set between 0 and 2147483648 sample intervals. The system then outputs the first value in the LUT until the PreCycleRest time has expired.</p>	long
PostCycleRest	<p>In a similar way to PreCycleRest, the PostCycleRest parameter specifies the delay imposed by the system after a LUT table has been output. The delay can be set between 0 and 2147483648 sample intervals. The system then outputs the last value in the cycle until the PostCycleRest time has expired.</p>	long
OPTrigStart	<p>Output triggering is enabled by setting the value 0x04 in the MODE parameter. With Op Triggering enabled, the system can be configured to generate one or more hardware trigger pulses during a LUT (waveform) cycle output. The OPTrigStart parameter specifies the LUT value (position in the LUT array) at which to initiate an output trigger. In this way, it is possible to synchronize an output trigger with the output of a particular voltage value. Values are set in the range 1 to 8000 but must also be less than the CycleLength parameter.</p>	word
OPTrigWidth	sets the width of the output trigger. Values are entered in 1ms increments for BPC20x models.	long
TrigRepeatCycle	specifies the repeat interval between O/P triggers when OUTPUTTRIG_REPEAT is set to True. This parameter is specified in the number of LUT values between triggers (0 to 7999 for MPZ and BPC units, 0 to 512 for TPZ units). If this value is greater than the ICycleLength parameter (set in the SetOPLUTParams method) then by definition, a repeated trigger will not occur during a single waveform cycle output.	word

Example: Set output LUT parameters as follows:

Channel: 1

Mode: OUTPUTLUT continuous

CycleLength: 40

NumCycles: 20

DelayTime: 10

PreCycleRest: 10

PostCycleRest: 10

OPTrigStart: 0

OPTrigWidth: 1

TrigRepeatCycle: 100

TX 03, 07, 1E, 00, D0, 01, 01, 00, 01, 00, 28, 00, 14, 00, 00, 00, 0A, 00, 00, 00, 0A, 00, 00, 00,
0A, 00, 00, 00, 00, 01, 00, 00, 00, 64, 00

Header: 03, 07, 06, 00, D0, 01: SETOUTPUTLUTPARAMS, 30 byte data packet, Generic USB Device.

Channel: 1

Mode: OUTPUTLUT continuous

CycleLength: 00, 28

NumCycles: 00, 00, 00, 14

DelayTime: 00, 00, 00, 0A

PreCycleRest: 00, 00, 00, 0A

PostCycleRest: 00, 00, 00, 0A

OPTrigStart: 00, 00

OPTrigWidth: 00, 00, 00, 01

TrigRepeatCycle: 00, 64

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
04	07	Chan Ident	00	d	s

GET:

Response structure (36 bytes)

6 byte header followed by 30 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
03	07	1E	00	d	s	Chan Ident	Mode	CycleLength			
<i>Data</i>											
12	13	14	15	16	17	18	19	20	21	22	23
<i>NumCycles</i>				<i>DelayTime</i>				<i>PreCycleRest</i>			
24	25	26	27	28	29	30	31	32	33	34	35
<i>Data</i>											
<i>PostCycleRest</i>				<i>OPTrigStart</i>		<i>OPTrigWidth</i>			<i>TrigRepCycle</i>		

For structure see SET message above.

MGMSG_PZ_START_LUTOUTPUT**0x0706****Function:**

This function is used to start the voltage waveform (LUT) outputs. Note. If the IPTrig flag of the SetOPLUTTrigParams function is set to false, this method initiates the waveform immediately. If the IPTrig flag is set to true, then this method ‘arms’ the system, in readiness for receipt of an input trigger.

TX structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
06	07	Chan Ident	00	d	s

MGMSG_PZ_STOP_LUTOUTPUT**0x0707****Function:**

This function is used to stop the voltage waveform (LUT) outputs.

TX structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
07	07	Chan Ident	00	d	s

MGMSG_PZ_SET_EEPROMPARAMS**0x07D0**

Function: Used to save the parameter settings for the specified message. These settings may have been altered either through the various method calls or through user interaction with the GUI (specifically, by clicking on the 'Settings' button found in the lower right hand corner of the user interface).

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>					<i>Data</i>				
D0	07	04	00	d	s	Chan Ident	MsgID		

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
MsgID	The message ID of the message containing the parameters to be saved.	word

Example:

TX D0, 07, 04, 00, D0, 01, 01, 00, 03, 07,

Header: D0, 07, 04, 00, D0, 01: Set_EEPROMPARAMS, 04 byte data packet, Generic USB Device.

Chan Ident: 01, 00: Channel 1

MsgID: Save parameters specified by message 0703 (SetOutputLUTParams).

MGMSG_PZ_SET_TPZ_DISPSETTINGS	0x07D1
MGMSG_PZ_REQ_TPZ_DISPSETTINGS	0x07D2
MGMSG_PZ_GET_TPZ_DISPSETTINGS	0x07D3

Function: Used to set the intensity of the LED display on the front of the TPZ unit.

SET:

Command structure (8 bytes)

6 byte header followed by 2 byte data packet as follows:

0	1	2	3	4	5	6	7
<i>header</i>							
D1	07	02	00	d	s	DisIntensity	

Data Structure:

field	description	format
DisIntensity	The intensity is set as a value from 0 (Off) to 255 (brightest).	word

Example: Set the input source to software and potentiometer.

TX D1, 07, 02, 00, D0, 01, 64, 00,

Header: D1, 07, 02, 00, D0, 01: Set_DISPSETTINGS, 02 byte data packet, Generic USB Device.

DisIntensity: 64, 00: Sets the display brightness to 100 (40%)

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
D2	07	01	00	d	s

Example: Request the display intensity

TX D2, 07, 01, 00, 50, 01

GET:

Command structure (8 bytes)

6 byte header followed by 2 byte data packet as follows:

0	1	2	3	4	5	6	7
<i>header</i>							
D3	07	02	00	d	s	DisIntensity	

See SET for data structure.

MGMSG_PZ_SET_TPZ_IOSETTINGS	0x07D4
MGMSG_PZ_REQ_TPZ_IOSETTINGS	0x07D5
MGMSG_PZ_GET_TPZ_IOSETTINGS	0x07D6

Function: This function is used to set various I/O settings as described below. The settings can be saved (persisted) to the EEPROM by calling the MGMSG_PZ_SET_EEPROMPARAMS function.

SET:

Command structure (16 bytes)

6 byte header followed by 10 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11		
<i>header</i>						<i>Data</i>							
D4	07	0A	00	d	s	Chan Ident	VoltageLimit	HubAnalogIP					
12	13	14	15										
<i>Data</i>													
Future Use	Future Use												

Data Structure:

field	description	format
Chan Ident	The channel being addressed is always P_MOD_CHAN1 (0x01) encoded as a 16-bit word (0x01 0x00)	word
VoltageLimit	The piezo actuator connected to the T-Cube has a specific maximum operating voltage range. This parameter sets the maximum output to the value specified as follows: 0x01 VOLTAGELIMIT_75V 75V limit 0x02 VOLTAGELIMIT_100V 100V limit 0x03 VOLTAGELIMIT_150V 150V limit	word
HubAnalogInput	When the T-Cube Piezo Driver unit is used in conjunction with the T-Cube Strain Gauge Reader (TSG001) on the T-Cube Controller Hub (TCH001), a feedback signal can be passed from the Strain Gauge Reader to the Piezo unit. High precision closed loop operation is then possible using our complete range of feedback-equipped piezo actuators. This parameter is used to select the way in which the feedback signal is routed to the Piezo unit as follows: 0x01 HUB_ANALOGUEIN_A the feedback signals run through all T-Cube bays. 0x02 HUB_ANALOGUEIN_B the feedback signals run between adjacent pairs of T-Cube bays (i.e. 1&2, 3&4, 5&6). This setting is useful when several pairs of Strain Gauge/Piezo Driver cubes are being used on the same hub. 0x03 EXTSIG_SMA the feedback signals run through the rear panel SMA connectors.	word

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
D5	07	01	00	d	s

GET:

Response structure (16 bytes)

6 byte header followed by 10 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
D4	07	0A	00	d	s	Chan Ident	VoltageLimit	HubAnalogIP			
<i>Data</i>											
12	13	14	15			Future Use	Future Us				

See SET message for structure.

MGMSG_PZ_SET_ZERO**0x0658**

Function: This function applies a voltage of zero volts to the actuator associated with the channel specified by the IChanID parameter, and then reads the position. This reading is then taken to be the zero reference for all subsequent position readings. This routine is typically called during the initialisation or re-initialisation of the piezo arrangement.

TX structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
58	06	Chan Ident	00	d	s

MGMSG_PZ_REQ_MAXTRAVEL
MGMSG_PZ_GET_MAXTRAVEL
0x0650
0x0651

Function: In the case of actuators with built in position sensing, the Piezoelectric Control Unit can detect the range of travel of the actuator since this information is programmed in the electronic circuit inside the actuator. This function retrieves the maximum travel for the piezo actuator associated with the channel specified by the Chan Ident parameter, and returns a value (in microns) in the Travel parameter.

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
50	06	01	00	d	s

Example: Request the max travel of the actuator associated with Channel 1, bay 2 (0x22)

TX 50, 06, 01, 00, 22, 01

GET:

Response structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
51	06	04	00	d	s	Chan ID	Travel		

Data Structure:

field	description	format
Chan Ident	The channel being addressed.	word
Travel	The max travel of the actuator associated with the specified channel in the range 0 to 65535 (0 to FFFF). The travel is read from a calibration resistor and is returned in real world units, steps of 100nm.	

Example: Get the maximum travel.

TX 51, 06, 04, 00, 01, A2, 01, 00, C8, 00

Header: 51, 06, 04, 00, A2, 01: Get_Max Travel, 04 byte data packet, d=A2 (i.e. 22 ORed with 80), s=01 (PC).

Channel 1: 01, 00:

Travel: 00C8 (200 i.e. 20 μm)

MGMSG_PZ_SET_IOSETTINGS	0x0670
MGMSG_PZ_REQ_IOSETTINGS	0x0671
MGMSG_PZ_GET_IOSETTINGS	0x0672

Function: This function is used to set various I/O settings as described below. The settings can be saved (persisted) to the EEPROM by calling the MGMSG_PZ_SET_EEPROMPARAMS function.

SET:

Command structure (16 bytes)

6 byte header followed by 10 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
70	06	0A	00	d	s	Chan Ident	AmpCurrentLim	AmpLPFilter			
12	13	14	15								
<i>Data</i>											
FeedbackSig	BNCTrigORLVOut										

Data Structure:

field	description	format
Chan Ident	The channel being addressed is always P_MOD_CHAN1 (0x01) encoded as a 16-bit word (0x01 0x00)	word
AmpCurrentLim	This parameter sets the maximum current output for the HV amplifier circuit as follows: CURRENTLIMIT_100MA 0x00 CURRENTLIMIT_250MA 0x01 CURRENTLIMIT_500MA 0x02	word
AmpLPFilter	This parameter sets the value of the hardware low pass filter applied to the HV amplifier output channels. It can be used to improve stability and reduce noise on the HV outputs. It is not channel specific and the Chan Ident parameter is ignored for this particular setting. Values are set as follows: OUTPUTLPFILTER_10HZ 0x00 OUTPUTLPFILTER_100HZ 0x01 OUTPUTLPFILTER_5KHZ 0x02 OUTPUTLPFILTER_NONE 0x03	word
FeedbackSig	For future use. The feedback signal type is locked at AC (strain gauge) and cannot be changed at this time.	
BNCTrigORLVOut	The Control IO BNC connectors on the rear panel are dual function. When set to Low Voltage (LV) outputs they mirror the voltage on the Piezo drive HV connectors and can be connected to an oscilloscope for monitoring purposes. When set to Trigger mode they provide the trigger input and output connections. This function is used to set the mode of the rear panel BNC connectors as follows: BNCMODE_TRIGGER Trigger Output 0x0000 BNCMODE_LVOUT LV Output 0xFFFF	

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
71	06	01	00	d	s

GET:

Response structure (16 bytes)

6 byte header followed by 10 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
72	06	0A	00	d	s	Chan Ident	AmpCurrentLim	AmpLPFilter			
12	13	14	15	<i>Data</i>							
FeedbackSig						BNCTrigORLVOut					

See SET message for structure.

MGMSG_PZ_SET_OUTPUTMAXVOLTS	0x0680
MGMSG_PZ_REQ_OUTPUTMAXVOLTS	0x0681
MGMSG_PZ_GET_OUTPUTMAXVOLTS	0x0682

Function: The piezo actuator connected to the unit has a specific maximum operating voltage range: 75, 100 or 150 V. This function sets the maximum voltage for the piezo actuator associated with the specified channel.

SET:

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
header						Data					
80	06	06	00	d	s	Chan Ident	Voltage	Flags			

Data Structure:

field	description	format
Chan Ident	The channel being addressed.	word
Voltage	This parameter sets the maximum output to the value specified, in 1/10 volt steps between 0 and 1500 (i.e. 0 to 150 V).	word
Flags	These flags tell the APT server certain parameters relating to the stage and controller combination. They are not relevant to the SET command and are only used in the GET_OUTPUTMAXVOLTS message	word

Note. When the SET_OUTPUTMAXVOLTS message is sent, a GET_OUTPUTMAXVOLTS message is automatically returned. This is to inform the server that the max output voltage has changed. Similarly, a GET_MAXTRAVEL message is also returned to tell the server the new max travel value.

Example: Set the max output voltage to 100V.

TX 80, 06, 06, 00, D0, 01, 00, E8, 03, 08, 00

Header: 80, 06, 06, 00, D0, 01: Set_OutputMaxVolts, 06 byte data packet, d=D0 (i.e. 50 ORed with 80 i.e. generic USB device), s=01 (PC).

Channel 1: 01, 00:

Voltage: 03E8 (1000 i.e. 100V)

Flags: N/A

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
header only					
81	06	01	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
82	06	06	00	d	s	Chan Ident	Voltage	Flags			

Data Structure:

field	description	format								
Chan Ident	The channel being addressed.	word								
Voltage	This parameter sets the maximum output to the value specified,either 750, 1000 or 1500 (i.e. 75, 100 or 150 V).	word								
Flags	<p>These flags tell the APT server certain parameters relating to the stage and controller combination.</p> <p>The meaning of the individual bits (flags) of the 16 bit integer value is as follows:</p> <table> <tr> <td>0x01</td> <td>For Future Use</td> </tr> <tr> <td>0x02</td> <td>VOLTAGELIMIT_75V 75V limit</td> </tr> <tr> <td>0x04</td> <td>VOLTAGELIMIT_100V 100V limit</td> </tr> <tr> <td>0x05</td> <td>VOLTAGELIMIT_150V 150V limit</td> </tr> </table>	0x01	For Future Use	0x02	VOLTAGELIMIT_75V 75V limit	0x04	VOLTAGELIMIT_100V 100V limit	0x05	VOLTAGELIMIT_150V 150V limit	word
0x01	For Future Use									
0x02	VOLTAGELIMIT_75V 75V limit									
0x04	VOLTAGELIMIT_100V 100V limit									
0x05	VOLTAGELIMIT_150V 150V limit									

Example: Set the max output voltage to 100V.

TX 82, 06, 06, 00, D0, 01, 01, 00, E8, 03, 08, 00

Header: 80, 06, 06, 00, D0, 01: Get_MaxOutputVolts, 06 byte data packet, d=D0 (i.e. 50 ORed with 80 i.e. generic USB device), s=01 (PC).

Channel 1: 01, 00:

Voltage: 03E8 (1000 i.e. 100V)

Flags: 08, 00: 150 V max voltage

MGMSG_PZ_SET_TPZ_SLEWRATES	0x0683
MGMSG_PZ_REQ_TPZ_SLEWRATES	0x0684
MGMSG_PZ_GET_TPZ_SLEWRATES	0x0685

Function: When stages with delicate internal mechanisms are being driven, it is possible that sudden large changes to the drive voltage could cause damage. This function is used to limit the rate of change of the drive voltage. Different limits may be set for open loop and closed loop operating modes.

Note. The controller is loaded at the factory with default values suitable for driving legacy piezo stages. For newer generation stages, the slew rate is read in automatically. Consequently, these parameters should not require adjustment under normal operating conditions.

SET:

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
83	06	06	00	d	s	Chan Ident	SlewOpen	SlewClosed			

Data Structure:

field	description	format
Chan Ident	The channel being addressed.	word
SlewOpen	This parameter sets the maximum slew rate when operating in open loop mode. Values are set in the range 0 to 32767, where 0 disables the limit, and 1 is the slowest rate. Values are calculated in V/ms as follows: $\text{Slew Rate} = \frac{\text{Value} \times \text{Max Voltage} (\text{i.e. } 75, 100 \text{ or } 150 \text{ V})}{19000}$	word
SlewClosed	This parameter sets the maximum slew rate when operating in closed loop mode. Values are calculated as above	word

Example: Set the open and closed max slew rates to 10V/ms for a 150V piezo.

TX 83, 06, 06, 00, D0, 01, 00, F2, 04, F2, 04

Header: 80, 06, 06, 00, D0, 01: Set_SlewRates, 06 byte data packet, d=D0 (i.e. 50 ORed with 80 i.e. generic USB device), s=01 (PC).

Channel 1: 01, 00:

SlewOpen: F2, 04 (10V/ms i.e. $1266 \times 150 / 19000$)

SlewClosed: F2, 04

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
84	06	01	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
85	06	06	00	d	s	Chan Ident	SlewOpen	SlewClosed			

See SET message for structure.

MGMSG_MOT_SET_PZSTAGEPARAMDEFAULTS**0x0686**

Function: If the system has become unstable, possibly due to multiple changes to parameter values, this message can be sent to the controller in order to reset parameters to the default values stored in the EEPROM.

TX structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
86	06	Chan Ident	00	d	s

MGMSG_PZ_SET_LUTVALUETYPE:**0x0708**

Function: It is possible to use the controller in an arbitrary Waveform Generator Mode (WGM). Rather than the unit outputting an adjustable but static voltage or position, the WGM allows the user to define a voltage or position sequence to be output, either periodically or a fixed number of times, with a selectable interval between adjacent samples. This waveform generation function is particularly useful for operations such as scanning over a particular area, or in any other application that requires a predefined movement sequence.

The waveform is stored as values in an array, with a maximum of 8000 samples per channel. The samples can have the meaning of voltage or position; if open loop operation is specified when the samples are output, then their meaning is voltage and vice versa, if the channel is set to closed loop operation, the samples are interpreted as position values. If the waveform to be output requires less than 8000 samples, it is sufficient to download the desired number of samples.

This message specifies whether the samples output from the LUT are voltage or position values.

TX structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
08	07	LUTType	00	d	s

Data Structure:

field	description	format
LUTType	The LUT value type: 0x01 LUT values are Voltage 0x02 LUT values are position	char

Example: Set the LUT value type to Volts.

TX, 08,07,01,00,50,01

Notes on using this message.

This method must be called BEFORE the LUT values are downloaded.

The LUT values are scaled to either voltage or position while the LUT is being downloaded. If the value type needs to be changed during operation (e.g. the system was in open loop with volts type selected, but now needs to change to closed loop with position type) the message must be called again, and the LUT values downloaded again.

MGMSG_PZ_SET_TSG_IOSETTINGS	0x07DA
MGMSG_PZ_REQ_TSG_IOSETTINGS	0x07DB
MGMSG_PZ_GET_TSG_IOSETTINGS	0x07DC

Function: When the T-Cube Strain Gauge Reader is used in conjunction with the T-Cube Piezo Driver unit (TPZ001) on the T-Cube Controller Hub (TCH001), a feedback signal can be passed from the Strain Gauge Reader to the Piezo unit. High precision closed loop operation is then possible using our complete range of feedback-equipped piezo actuators.

This method is used to select the way in which the feedback signal is routed back to the Piezo unit.

SET:

Command structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
DA	07	OE	00	d	s	Chan Ident	HubAnalogOP	DisplayMode			
12	13	14	15	16	17	18	19				
<i>Data</i>											
ForceCalib			Future Use		Future Use						

Data Structure:

field	description	format
Chan Ident	The channel being addressed is always (e.g. 0x01) encoded as a 16-bit word (0x01 0x00)	word
HubAnalogueOutput	When the T-Cube Strain Gauge Reader is used in conjunction with the T-Cube Piezo Driver unit (TPZ001) on the T-Cube Controller Hub (TCH001), a feedback signal can be passed from the Strain Gauge Reader to the Piezo unit. High precision closed loop operation is then possible using our complete range of feedback-equipped piezo actuators. This message is used to select the way in which the feedback signal is routed back to the Piezo unit If set to 0x01 HUB_ANALOGUEOUT_1, the feedback signals run through all T-Cube bays. If set to 0x02 HUB_ANALOGUEOUT_2, the feedback signals run between adjacent pairs of T-Cube bays (i.e. 1&2, 3&4, 5&6). This setting is useful when several pairs of Strain Gauge/Piezo Driver cubes are being used on the same hub.	word

Display Mode	The LED display window on the front of the unit (and the display on the GUI panel) can be set to display the strain gauge signal as a position (microns), a voltage (Volts) or as a force (Newtons). This parameter sets the display mode as follows If set to 0x01 DISPUNITS_POSITION, the display shows the strain gauge signal as a position in microns. If set to 0x02 DISPUNITS_VOLTAGE, the display shows the strain gauge signal as a voltage. If set to 0x03 DISPUNITS_FORCE, the display shows the strain gauge signal as a force	word
ForceCalib	If using a force sensor with the TSG001 unit, the Force Sensor has a specific maximum operating force. This parameter sets the force calibration factor in steps of 0.001 N between 1 and 1000. The default setting for this parameter is H7530 (30,000), to be compatible with our FSC102 force sensor, which is specified to read forces up to 30N.	word

Example: Set the IO settings as follows.

TX DA, 07, 0E, 00, D0, 01, 01, 00, 01, 00, 02, 00, 30, 75, 00, 00, 00, 00, 00

Header: DA, 07, 0E, 00, D0, 01: Set_TSG_IOSettings, 14 byte data packet, d=D0 (i.e. 50 ORed with 80 i.e. generic USB device), s=01 (PC).

Channel 1: 01, 00:

HubAnalogueOutput: 01, 00 (Hub Analogue Output A)

Display Mode: 02, 00 (Display Voltage)

Force Calibration: 30, 75 30,000 x 0.001 = 30 N

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
DB	07	01	00	d	s

GET:

Response structure (16 bytes)

6 byte header followed by 10 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
DC	07	0E	00	d	s	Chan Ident	HubAnalogOP	DisplayMode			
12	13	14	15	16	17	18	19				
<i>Data</i>											
ForceCalib			Future Use			Future Use					

See SET message for structure.

MGMSG_PZ_REQ_TSG_READING	0x07DD
MGMSG_PZ_GET_TSG_READING	0x07DE

Function: This message returns the current reading of the strain gauge
The units applicable are dependent on the current operating mode
(set using the DisplayMode parameter of the [SET_TSG_IOSETTINGS](#) message).

REQUEST:

Command structure (6 bytes)

0	1	2	3	4	5
<i>header only</i>					
DD	07	Chan	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
DE	07	06	00	d	s	Chan Ident	Reading	Smoothed			

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
Reading	The current reading of the strain gauge unit. If the unit is operating in Position mode, then the returned value is a position in microns. If the unit is in Voltage mode, then the returned reading is a Voltage. If the controller is in 'Force Sensing Mode' then the parameter returns a force value in Newtons. Values are returned in the range -32767 to 32768, which corresponds to -100% to 100% of the maximum voltage, travel or force. The returned data values are sampled at 500Hz. This is particularly useful in touch probe or force sensing applications where rapid polling of the force reading is important. Display mode and Max Force are described in the MGMSG_PZ_GET_TSG_IOSETTINGS message. Max Travel is described in the MGMSG_PZ_GET_MAXTRAVEL message.	short
Smoothed		word

Example: Get the readings for channel 1.

RX DE, 07, 06, 00, 81, 50, 01, 00, 52, 00, 50, 00,

Header: DE, 07, 06, 00, 81, 50: Get_TSG_Readings, 6 byte data packet, d=D0 (i.e. 01 ORed with 80 i.e. PC), s=50 (Generic USB device).

*Channel 1: 01, 00**Reading: 52, 00 (i.e. 82)**Smoothed: 52, 00*

NanoTrak Control Messages

Introduction

The 'NanoTrak' ActiveX Control provides the functionality required for a client application to control one or more NanoTrak auto-alignment controller products. The NanoTrak system comes in benchtop (BNT001), T-Cube (TNA001) and 19" rack modular (MNA601) formats, all of which are covered by the NanoTrak ActiveX Control.

The messages of the NanoTraks object can then be used to perform activities such as latching/unlatching, reading power levels, obtaining/setting circle size and position and determining if 'NanoTracking' is currently taking place.

For details on the use of the NanoTrak controller, and information on the principles of operation, refer to the NanoTrak Operating Guide.

NOTE. The NanoTrak can be set to operate as a piezo amplifier. When operated in this mode, some piezo control messages may also be sent or returned.

MGMSG_PZ_SET_NTMODE**0x0603**

Function: The NanoTrak unit can be used as a standard piezo amplifier, or as a NanoTrak Auto-alignment unit. This message sets the unit to piezo operation, or one of the NanoTrak operating modes as described below. The mode of operation is set in byte 2 of the message as follows:

SET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
03	06	State	00	d	s

Data Structure:

field	description	format
State	<p>01 Sets the unit to Piezo mode. Note. The hardware unit must be rebooted before changes to operating mode can take effect.</p> <p>Note. When the HW operating mode of a NanoTrak unit has been changed to Piezo operation, then the Piezo ActiveX control must be used to communicate with the unit. Use the same serial number as used on the NanoTrak control in order to establish communication with the unit.</p> <p>02 Latch mode. In this mode, scanning is disabled and the piezo drives are held at the present position.</p> <p>03 Track mode. In this mode, the NanoTrak detects any drop in signal strength resulting from misalignment of the input and output devices, and makes vertical and horizontal positional adjustments to maintain the maximum throughput.</p> <p>04 Horizontal Track mode. In this mode, the NanoTrak detects any drop in signal strength resulting from misalignment of the input and output devices, and makes horizontal positional adjustments to maintain the maximum throughput.</p> <p>05 Vertical Track mode. In this mode, the NanoTrak detects any drop in signal strength resulting from misalignment of the input and output devices, and makes vertical positional adjustments to maintain the maximum throughput.</p>	short

Example: Set the tracking mode to Latch

TX 03, 06, 02, 00, 50, 01,

MGMSG_PZ_REQ_NTMODE
MGMSG_PZ_GET_NTMODE
0x0604
0x0605

Function: The NanoTrak unit can be used as a standard piezo amplifier, or as a NanoTrak Auto-alignment unit. This message gets the present operating mode of the unit as described below. The mode of operation is returned in byte 2 of the message as follows:

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
04	06	00	00	d	s

GET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
05	06	State	Mode	d	s

Data Structure:

field	description	format
State	The Tracking state 01 NanoTracking off. The unit is in Piezo mode. 02 Latch mode. In this mode, scanning is disabled and the piezo drives are held at the present position. 03 Tracking ON No Signal. In this mode, the NanoTrak is tracking but the signal power is below the threshold power set by the user in the Set_NTTrackThreshold message. 04 Tracking ON, Signal Attained. In this mode, the threshold power has been detected and the NanoTrak is tracking normally.	short
Mode	The Tracking Mode. 01 Dual axis (X and Y) tracking. 02 Horizontal (X) axis tracking. 03 Vertical (Y) axis tracking.	

Example

TX 05, 06, 04, 01, 01, 50

Mode is Tracking Signal (0x04) and dual axis (Both X and Y tracking) (0x01)

MGMSG_PZ_SET_NTTRACKTHRESHOLD	0x0606
MGMSG_PZ_REQ_NTTRACKTHRESHOLD	0x0607
MGMSG_PZ_GET_NTTRACKTHRESHOLD	0x0608

Function: This message sets the tracking threshold of the NanoTrak. The value is set in Amps, and is dependent upon the application. Typically, the value is set to lie above the ‘noise floor’ of the particular physical arrangement. When the input signal level exceeds this value, the tracking LED is lit on the GUI panel. Note there is no guarantee that tracking is taking place if this threshold value is set inappropriately. E.g. if the tracking threshold is set to below the noise floor, then the GUI will show a lit tracking LED even though no tracking is taking place.

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
06	06	04	00	d	s	ThresholdAbsReading			

Data Structure:

field	description	format
ThresholdAbsReading	The tracking threshold of the NanoTrak. This is the absolute TIA reading (PIN current). The value set in Amps as a 4-byte floating point number in the range 1×10^{-9} to 1×10^{-3} (i.e. 1 nA to 1 mA).	Float

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
07	06	00	00	d	s

GET:

Command structure (10 bytes):

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
08	06	04	00	d	s	ThresholdAbsReading			

See SET for structure.

MGMSG_PZ_SET_NTCIRCHOMEPOS	0x0609
MGMSG_PZ_REQ_NTCIRCHOMEPOS	0x0610
MGMSG_PZ_GET_NTCIRCHOMEPOS	0x0611

Function: This message sets the circle home position to the horizontal and vertical coordinates specified in the CircHomePosA and CircHomePosB parameters respectively.
The home position is used when the [Move_NTCircToHomePos](#) message is called

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
06	06	04	00	d	s	CircHomePosA	CircHomePosB		

Data Structure:

field	description	format
CircHomePosA	The horizontal co-ordinate of the circle home position, in the range 0 to 65535 (0 to 100% of output voltage or 0 to 10 NanoTrak units).	word
CircHomePosB	The vertical co-ordinate of the circle home position, in the range 0 to 65535 (0 to 100% of output voltage or 0 to 10 NanoTrak units).	word

Example: Set the NanoTrak circle home position to be screen centre.

TX 09 06, 04, 00, D0, 01, FF, 7F, FF, 7F,

Header: 09, 06, 04, 00, D0, 01: Set_NTCircHomePos, 04 byte data packet, Generic USB Device.

CircHomePosA: FF, 7F: Sets the horizontal co-ordinate to 32767 (i.e. 50% of O/P Voltage or 5 NT units)

CircHomePosB: FF, 7F: Sets the vertical co-ordinate to 32767 (i.e. 50% of O/P Voltage or 5 NT units)

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
10	06	00	00	d	s

GET:

Command structure (10 bytes):

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
11	06	04	00	d	s	CircHomePosA	CircHomePosB		

See SET for structure.

MGMSG_PZ_MOVE_NTCIRCTOHOMEPOS**0x0612**

Function: This message moves the circle to the 'Home' position as set by the [Set_NTCircHomePos](#) message

SET:

Command structure (6 bytes)

0	1	2	3	4	5
<i>header</i>					
12	06	00	00	d	s

Example: Move the NanoTrak circle to the home position.

TX, 12, 06, 00, 00, 50, 01,

MGMSG_PZ_REQ_NTCIRC CENTREPOS
MGMSG_PZ_GET_NTCIRC CENTREPOS
0x0613
0x0614

Function: This message obtains the current horizontal and vertical position of the circle, together with other signal and range parameters relating to NanoTrak operation as described below.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
13	06	01	00	d	s

GET:

Command structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
06	06	0E	00	d	s	CircPosA	CircPosB		
10	11	12	13	14	15	16	17	18	19
<i>Data</i>									
AbsReading	RelReading	Range	UnderOverRead						

Data Structure:

field	description	format
CircPosA	The horizontal co-ordinate of the circle home position, in the range 0 to 65535 (0 to 100% of output voltage or 0 to 10 NanoTrak units).	word
CircPosB	The vertical co-ordinate of the circle home position, in the range 0 to 65535 (0 to 100% of output voltage or 0 to 10 NanoTrak units).	word
AbsReading	The absolute TIA (PIN) current or BNC voltage value at the current position. The value is returned as a 4 byte floating point value in the range 1×10^{-9} to 1×10^{-3} (i.e. 1 nA to 1 mA or 1 to 10 V). The input source, TIA or BNC is set in the Set_NTFeedbackSRC message.	float
RelReading	The relative signal strength at the current position, in the range 0 to 32767 (i.e. 0 to 100% of the range currently selected). This value matches the length of the input signal bargraph on the GUI panel. (e.g. if the 3 μ A range is currently selected, then a RelReading value of 16384 (50%) equates to 1.5 μ A).	word
Range	The NanoTrak unit is equipped with an internal trans-impedance amplifier (TIS) circuit (and associated range/power level displays and control buttons in the GUI). This amplifier operates when an external input signal is connected to the Optical/PIN connector on the rear panel. There are 14 range settings (1 - 14) that can be used to select the best range to measure the input signal	word

	(displayed on the GUI panel relative input signal bar and display). Note. Range 1 and 2 (3 nA and 10 nA) are not applicable to TNA001 T-Cube units. This parameter returns the input signal range currently selected, defined as follows: <table border="0"> <tr><td>Range 1</td><td>3 nA</td><td>0x03</td></tr> <tr><td>Range 2</td><td>10 nA</td><td>0x04</td></tr> <tr><td>Range 3</td><td>30 nA</td><td>0x05</td></tr> <tr><td>Range 4</td><td>100 nA</td><td>0x06</td></tr> <tr><td>Range 5</td><td>300 nA</td><td>0x07</td></tr> <tr><td>Range 6</td><td>1 µA</td><td>0x08</td></tr> <tr><td>Range 7</td><td>3 µA</td><td>0x09</td></tr> <tr><td>Range 8</td><td>10 µA</td><td>0x0A</td></tr> <tr><td>Range 9</td><td>30 µA</td><td>0x0B</td></tr> <tr><td>Range 10</td><td>100 µA</td><td>0x0C</td></tr> <tr><td>Range 11</td><td>300 µA</td><td>0x0D</td></tr> <tr><td>Range 12</td><td>1 mA</td><td>0x0E</td></tr> <tr><td>Range 13</td><td>3 mA</td><td>0x0F</td></tr> <tr><td>Range 14</td><td>10 mA</td><td>0x10</td></tr> </table>	Range 1	3 nA	0x03	Range 2	10 nA	0x04	Range 3	30 nA	0x05	Range 4	100 nA	0x06	Range 5	300 nA	0x07	Range 6	1 µA	0x08	Range 7	3 µA	0x09	Range 8	10 µA	0x0A	Range 9	30 µA	0x0B	Range 10	100 µA	0x0C	Range 11	300 µA	0x0D	Range 12	1 mA	0x0E	Range 13	3 mA	0x0F	Range 14	10 mA	0x10	
Range 1	3 nA	0x03																																										
Range 2	10 nA	0x04																																										
Range 3	30 nA	0x05																																										
Range 4	100 nA	0x06																																										
Range 5	300 nA	0x07																																										
Range 6	1 µA	0x08																																										
Range 7	3 µA	0x09																																										
Range 8	10 µA	0x0A																																										
Range 9	30 µA	0x0B																																										
Range 10	100 µA	0x0C																																										
Range 11	300 µA	0x0D																																										
Range 12	1 mA	0x0E																																										
Range 13	3 mA	0x0F																																										
Range 14	10 mA	0x10																																										
UnderOverRead	This parameter returns a value that identifies whether the unit is under reading or over reading the input signal as follows: 0x01 power signal is within current TIA range 0x02 power signal is under-reading for current TIA 0x03 power signal is over-reading for current TIA range e.g. if a user specified range of 3 µA is currently applied, this parameter returns '0x03' (Over read) for input signals greater than 3 µA.	word																																										

Example:

RX 14, 06, 0E, 00, 81, 50, 73, 63, 2A, F3, 00, 00, 00, 00, 00, 00, 05, 00, 02, 00

Header: 14, 06, 0E, 00, 81, 50: Get_NTCircCentrePos, 14 byte data packet, Generic USB Device.

CircPosA;	0x6373	25459 (25459/65535 = 39%)
CircPosB;	0xF32A	62250 (62250/65535 = 95%)
AbsReading;	0x00000000	0V
RelReading;	0x0000	0V
Range;	0x0005	Range 3 (i.e. 30 nA)
UnderOverRead;	0x0002	Signal is under reading for range.

MGMSG_PZ_SET_NTCIRCPARAMS	0x0618
MGMSG_PZ_REQ_NTCIRCPARAMS	0x0619
MGMSG_PZ_GET_NTCIRCPARAMS	0x0620

Function: This message obtains sets various scanning circle parameters as described below.

SET:

Command structure (18 bytes)

6 byte header followed by 12 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>					<i>Data</i>				
18	06	0C	00	d	s	CircDiaMode	CircDiaSW		
10	11	12	13	14	15	16	17		
<i>Data</i>									
CircOscFreq	AbsPwrMinCircDia	AbsPwrMaxCircDia	AbsPwrAdjustType						

Data Structure:

field	description	format
CircDiaMode	This parameter allows the different modes of circle diameter adjustment to be enabled and disabled as follows: 0x01 NTCIRCDIA_SW the circle diameter remains at the value set using the CircDiaSW parameter below. 0x02 NTCIRCDIA_ABSPWR the circle diameter is set by absolute power input value (depending on adjustment algorithm selected in the AbsPwrAdjustType parameter - see below) 0x03 NTCIRCDIA_LUT the circle diameter is adjusted automatically, using a table of TIA range dependent values (set using the SetCircDiaLUT message).	word
CircDiaSW	This parameter sets the NT circle diameter if NTCIRCDIA_SW (0x01) is selected in the CircDiaMode parameter above. The diameter is set in the range 0 to 65535, which relates to 0% to 100% output voltage -(i.e. 0 to 10 NT units).	word
CircOscFreq	This parameter contains the number of samples taken in one revolution of the scanning circle and is used to set the scanning frequency of the NanoTrak circle. The circle scanning frequency lies in the range 17.5 Hz to 87.5 Hz for TNA001 and 20 Hz to 190 Hz for the BNT001. The factory default setting for the scanning frequency is 43.75Hz. This means that a stage driven by the NanoTrak makes 43.75 circular movements per second. Different frequency settings allow more than one NanoTrak to be used in the same alignment scenario. The scanning frequency is derived from the NanoTrak sampling frequency of 7000 Hz and the CircOscFreq	word

	<p>value which is calculated as follows: $\text{CircOscFreq} = 7000 / \text{scanning frequency}$ Note. The CircOscFreq parameter must be entered as a multiple of '4'.</p>													
AbsPwrMinCircDia	The minimum circle diameter. Applicable only if the CircDiaMode parameter above is set to NTCIRCDIA_ABSPWR (0x02). The diameter is set in the range 0 to 32767, which relates to 0% to 50% output voltage -(i.e. 0 to 5 NT units).	word												
AbsPwrMaxCircDia	The maximum circle diameter. Applicable only if the CircDiaMode parameter above is set to NTCIRCDIA_ABSPWR (0x02). The diameter is set in the range 0 to 32767, which relates to 0% to 50% output voltage -(i.e. 0 to 5 NT units).	word												
AbsPwrAdjustType	<p>This parameter sets the adjustment type and is applicable only if CircDiaMode parameter above is set to NTCIRCDIA_ABSPWR (0x02).</p> <table> <tr> <td>0x01</td> <td>NTABSPWRCIRCADJUST_LIN</td> <td>inverse linear adjustment</td> </tr> <tr> <td>0x02</td> <td>NTABSPWRCIRCADJUST_LOG</td> <td>inverse log adjustment</td> </tr> <tr> <td>0x03</td> <td>NTABSPWRCIRCADJUST_X2</td> <td>inverse square adjustment</td> </tr> <tr> <td>0x04</td> <td>NTABSPWRCIRCADJUST_X3</td> <td>inverse cube adjustment</td> </tr> </table>	0x01	NTABSPWRCIRCADJUST_LIN	inverse linear adjustment	0x02	NTABSPWRCIRCADJUST_LOG	inverse log adjustment	0x03	NTABSPWRCIRCADJUST_X2	inverse square adjustment	0x04	NTABSPWRCIRCADJUST_X3	inverse cube adjustment	word
0x01	NTABSPWRCIRCADJUST_LIN	inverse linear adjustment												
0x02	NTABSPWRCIRCADJUST_LOG	inverse log adjustment												
0x03	NTABSPWRCIRCADJUST_X2	inverse square adjustment												
0x04	NTABSPWRCIRCADJUST_X3	inverse cube adjustment												

Example

TX 18, 06, 0C, 00, D0, 01, 01, 00, 9A, 19, A0, 00, CC, 0C, 99, 19, 01, 00

Header: 18, 06, 0C, 00, D0, 01: Set_NTCircParams, 12 byte data packet, Generic USB Device.

CircDiaMode;	0x0001	Software setting mode
CircDiaSW;	0x199A	6554 $6554/65535 = 10\%$ of O/P voltage (1 NT unit)
CircOscFreq;	0x00A0	160 $7000/160 = 43.75$ Hz
AbsPwrMinCircDia;	0x0CCC	3276 5% or 0.5 NT units
AbsPwrMaxCircDia;	0x1999	6553 10% or 1 NT unit
AbsPwrAdjustType;	0x0001	inverse linear adjust type.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
19	06	01	00	d	s

GET:

Command structure (18 bytes)

6 byte header followed by 12 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>					<i>Data</i>				
20	06	0C	00	d	s	CircDiaMode	CircDiaSW		
10	11	12	13	14	15	16	17		
<i>Data</i>									
CircOscFreq	AbsPwrMinCircDia	AbsPwrMaxCircDia	AbsPwrAdjustType						

See SET for structure

MGMSG_PZ_SET_NTCIRCDIA**0x061A**

Function: This message sets the NT circle diameter and can be used as an alternative to the [Set_NTCircParams](#) message described previously. The diameter is set in the range 0 to 65535, which relates to 0% to 100% output voltage (i.e. 0 to 10 NT units).

SET:

Command structure (6 bytes)

0	1	2	3	4	5
<i>header</i>					
1A	06	CircDia	00	d	s

Example: Set the NanoTrak circle diameter to 10% (i.e. 1 NT unit).

TX, 1A, 06, 99, 19, 50, 01,

H1999 = 6553 6553/65535 = 10%

MGMSG_PZ_SET_NTCIRCDIALUT	0x0621
MGMSG_PZ_REQ_NTCIRCDIALUT	0x0622
MGMSG_PZ_GET_NTCIRCDIALUT	0x0623

Function: This message enables a look up table (LUT) of circle diameter values to be specified as a function of input range. When automatic LUT diameter adjustment mode is enabled (using the CircDiaMode parameter in the [Set_NTCircParams](#) message), the system uses values in this LUT to modify circle diameter in relation to the input range currently selected.
This LUT diameter adjustment mode allows appropriate circle diameters to be applied on an application specific basis.

SET:

Command structure (38 bytes)

6 byte header followed by 32 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
21	06	20	00	d	s	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal

12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>											
LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal

24	25	26	27	28	29	30	31	32	33	34	35	36
<i>Data</i>												
LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	

Data Structure:

field	description	format
CircDias	This parameter contains the circle diameter values for each range of the NanoTrak. The values are entered in range order in a 32 byte array. Note. On the BNT001 unit bytes 1 through 4 of the array are ignored and Range 1 starts in Byte 5. Note. On the TNA001 unit bytes 1 through 8 of the array are ignored and Range 1 starts in Byte 9. The diameters are entered in the range 0 to 65535 (0 to FFFF), which relates to 0% to 100% output voltage (i.e. 0 to 10 NT units).	array

Example: Enter the NanoTrak circle diameter LUT values.

TX 21, 06, 20, 00, D0, 01, 00, 00, 00, 34, 33, A4, 30, 16, 2E, 86, 2B, F6, 28, 68, 26, D8, 23, 48, 21, B8, 1E, 2A, 1C, 9A, 19, 0A, 17, 7C, 14, EC, 11

*Header: 21, 06, 20, 00, D0, 01: Set_NTCircHomePos, 32 byte data packet, Generic USB Device.**CircDias: The various range related LUT values entered in range order)*

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
22	06	00	00	d	s

GET:

Command structure (38 bytes)

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
23	06	20	00	d	s	Not Used	Not Used	LUTVal			
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>						<i>Data</i>					
LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal
24	25	26	27	28	29	30	31	32	33	34	35
<i>Data</i>						<i>Data</i>					
LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal	LUTVal
36	37	38	39	40	41	42	43	44	45	46	47

See SET for structure.

MGMSG_PZ_SET_NTPHASECOMPPARAMS	0x0626
MGMSG_PZ_REQ_NTPHASECOMPPARAMS	0x0627
MGMSG_PZ_GET_NTPHASECOMPPARAMS	0x0628

Function: The feedback loop scenario in a typical NanoTrak application can involve the operation of various electronic and electromechanical components (e.g. power meters and piezo actuators) that could introduce phase shifts around the loop and thereby affect tracking efficiency and stability. These phase shifts can be cancelled by setting the 'Phase Compensation' factors.

This message sets the phase compensation for the horizontal and vertical components of the circle path in the range 0 to 360 degrees. Typically both phase offsets will be set the same, although some electromechanical systems may exhibit different phase lags in the different components of travel and so require different values.

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
26	06	06	00	d	s	PhaseCompMode	PhaseCompASW	PhaseCompBSW			

Data Structure:

field	description	format
PhaseCompMode	Currently, the phase compensation mode is not adjustable, and is locked at manual (software) adjustment.	word
PhaseCompASW	The horizontal axis phase compensation value, entered in real world units and calculated as follows:- value = (phase angle [degrees] / 360) * CircOscFreq See the PZ_SET_NTCIRCPARAMS message for details on the CircOscFreq parameter Note. Negative phase values must be made positive by subtraction from 360 before the calculation is made.	short
PhaseCompBSW	The vertical axis phase compensation value, entered in real world units and calculated as follows:- value = (phase angle [degrees] / 360) * CircOscFreq See the PZ_SET_NTCIRCPARAMS message for details on the CircOscFreq parameter Note. Negative phase values must be made positive by subtraction from 360 before the calculation is made.	short

Example: Set the NanoTrak circle home position to be screen centre.

TX 26, 06, 06, 00, D0, 01, 02, 00, 93, 00, 93, 00

Header: 26, 06, 06, 00, D0, 01: Set_NTPhaseCompParams, 06 byte data packet, Generic USB Device.

PhaseCompMode; 0x0002 Locked at Software Adjustment mode.
PhaseCompASW; 0x0093 147

Therefore, for circle scanning freq of 44, Phase Angle = $147/(7000/44) \times 360 = -30^\circ$

PhaseCompBSW 0x0093

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
27	06	00	00	d	s

GET:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
28	06	06	00	d	s	PhaseCompMode	PhaseCompASW	PhaseCompBSW			

See SET for structure.

MGMSG_PZ_SET_NTTIARANGEPARAMS	0x0630
MGMSG_PZ_REQ_NTTIARANGEPARAMS	0x0631
MGMSG_PZ_GET_NTTIARANGEPARAMS	0x0632

Function: This message is used to select manual (software) or auto ranging, and to modify the ranging characteristics in each case.

SET:

Command structure (18 bytes)

6 byte header followed by 12 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>					<i>Data</i>				
30	06	0C	00	d	s	RangeMode	RangeUpLimit		
10	11	12	13	14	15	16	17		
RangeDownLimit	SettleSamples	RangeChangeType	RangeSW						

Data Structure:

field	description	format												
RangeMode	<p>This parameter specifies the ranging mode of the unit as follows:</p> <table> <tr> <td>0x01</td> <td>RANGE_AUTO</td> <td>change to Auto ranging at the range currently selected</td> </tr> <tr> <td>0x02</td> <td>RANGE_SW</td> <td>change to manual ranging at the range currently selected</td> </tr> <tr> <td>0x03</td> <td>RANGE_SWSET</td> <td>change to manual ranging at the range set in the SetRange method (or the 'Settings' panel)</td> </tr> <tr> <td>0x04</td> <td>RANGE_AUTOSET</td> <td>change to Auto ranging at the range set in the RangeSW parameter below.</td> </tr> </table>	0x01	RANGE_AUTO	change to Auto ranging at the range currently selected	0x02	RANGE_SW	change to manual ranging at the range currently selected	0x03	RANGE_SWSET	change to manual ranging at the range set in the SetRange method (or the 'Settings' panel)	0x04	RANGE_AUTOSET	change to Auto ranging at the range set in the RangeSW parameter below.	word
0x01	RANGE_AUTO	change to Auto ranging at the range currently selected												
0x02	RANGE_SW	change to manual ranging at the range currently selected												
0x03	RANGE_SWSET	change to manual ranging at the range set in the SetRange method (or the 'Settings' panel)												
0x04	RANGE_AUTOSET	change to Auto ranging at the range set in the RangeSW parameter below.												
RangeUpLimit	<p>Only applicable if Auto Ranging is selected in the RangeMode parameter above.</p> <p>This parameter sets the upper range limit as a percentage of the present range, 0 to 1000 = 0 to 100%.</p> <p>When autoranging, the NanoTrak unit adjusts continually the TIA range as appropriate for the input signal level. When the relative signal rises above the limit specified in this parameter, the unit increments the range to the next higher setting.</p> <p>The relative signal is displayed on the NanoTrak GUI panel by a green horizontal bar.</p>	short												
RangeDownLimit	<p>Only applicable if Auto Ranging is selected in the RangeMode parameter above.</p> <p>This parameter sets the lower range limit as a percentage of the present range, 0 to 1000 = 0 to 100%.</p> <p>Similarly to RangeUpLimit, when the relative signal on a particular range drifts below the limit set in this parameter, the NanoTrak unit decrements the range to the next lower setting.</p>	short												

	The relative signal is displayed on the NanoTrak GUI panel by a green horizontal bar.																
SettleSamples	<p>Only applicable if Auto Ranging is selected in the RangeMode parameter above.</p> <p>This parameter determines the amount of averaging applied to the signal before autoranging takes place.</p> <p>Higher SettleSamples values improve the signal to noise ratio when dealing with noisy feedback signals.</p> <p>However, higher SettleSamples values also slow down the autoranging response. In a particular application, the SettleSamples value should be adjusted to obtain the best autoranging response combined with a noise free signal.</p> <p>Values are set in real world units, from '2' to '32', with a default setting value of '4'.</p>	short															
RangeChangeType	<p>Only applicable if Auto Ranging is selected in the RangeMode parameter above.</p> <p>This parameter specifies how range changes are implemented by the system.</p> <p>0x01 AUTORANGE_ALL the unit visits all ranges when ranging between two input signal levels.</p> <p>0x02 AUTORANGE_ODD only the odd numbered ranges between the two input signals levels will be visited.</p> <p>0x03 AUTORANGE_EVEN only the even numbered ranges between the two input signals levels will be visited.</p> <p>These latter two modes are useful when large rapid input signal fluctuations are anticipated, because the number of ranges visited is halved to give a more rapid response.</p>	word															
RangeSW	<p>Only applicable if Manual (SW) Ranging is selected in the RangeMode parameter above.</p> <p>The NanoTrak unit is equipped with an internal trans-impedance amplifier (TIA) circuit (and associated range/power level displays and control buttons in the GUI). This amplifier operates when an external input signal is connected to the Optical/PIN connector on the rear panel. There are 14 range settings (1 - 14) that can be used to select the best range to measure the input signal (displayed on the GUI panel relative input signal bar and display).</p> <p>Note. Range 1 and 2 (3 nA and 10 nA) are not applicable to TNA001 T-Cube units.</p> <p>This parameter returns the input signal range currently selected, defined as follows:</p> <table> <tbody> <tr> <td>Range 1</td> <td>3 nA</td> <td>0x03</td> </tr> <tr> <td>Range 2</td> <td>10 nA</td> <td>0x04</td> </tr> <tr> <td>Range 3</td> <td>30 nA</td> <td>0x05</td> </tr> <tr> <td>Range 4</td> <td>100 nA</td> <td>0x06</td> </tr> <tr> <td>Range 5</td> <td>300 nA</td> <td>0x07</td> </tr> </tbody> </table>	Range 1	3 nA	0x03	Range 2	10 nA	0x04	Range 3	30 nA	0x05	Range 4	100 nA	0x06	Range 5	300 nA	0x07	word
Range 1	3 nA	0x03															
Range 2	10 nA	0x04															
Range 3	30 nA	0x05															
Range 4	100 nA	0x06															
Range 5	300 nA	0x07															

Range 6	1 µA	0x08	
Range 7	3 µA	0x09	
Range 8	10 µA	0x0A	
Range 9	30 µA	0x0B	
Range 10	100 µA	0x0C	
Range 11	300 µA	0x0D	
Range 12	1 mA	0x0E	
Range 13	3 mA	0x0F	
Range 14	10 mA	0x10	

Example

TX 30, 06, 0C, 00, D0, 01, 01, 00, 52, 03, 96, 00, 04, 00, 01, 00, 05, 00

Header: 30, 06, 0C, 00, D0, 01: Set_NTTIARangeParams, 12 byte data packet, Generic USB Device.

wRangeMode;	0x0001	Auto Ranging mode
sRangeUpLimit;	0x0352	850 == 85%
sRangeDownLimit;	0x0096	150 == 15%
wSettleSamples;	0x0004	4
wRangeChangeType;	0x0001	Auto range through all ranges
wRangeSW;	0x0005	P_PZ_NTTIA_RANGE30NANO

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
31	06	01	00	d	s

GET:

Command structure (18 bytes)

6 byte header followed by 12 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
32	06	0C	00	d	s	RangeMode	RangeUpLimit		
10	11	12	13	14	15	16	17		
RangeDownLimit	SettleSamples	RangeChangeType	RangeSW						

See SET for structure

MGMSG_PZ_SET_NTGAINPARAMS	0x0633
MGMSG_PZ_REQ_NTGAINPARAMS	0x0634
MGMSG_PZ_GET_NTGAINPARAMS	0x0635

Function: This message sets the gain level of the NanoTrak control loop, and is used to ensure that the DC level of the input (feedback loop) signal lies within the dynamic range of the input. Increasing this value can lead to a more responsive NanoTrak behaviour as the signal variation around the circular path is enhanced. However, for a particular set up, if this value is too high, then unstable NanoTrak operation (indicated by a fluctuating circle) can result.

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
33	06	04	00	d	s	GainCtrlMode	NTGainSW		

Data Structure:

field	description	format
GainCtrlMode	This parameter is currently locked and cannot be changed: 0x02 GAIN_SW software setting gain control mode	word
NTGainSW	This parameter sets the loop gain, as a function of TIA range setting. The value is set between 100 and 10000 with a default value of 600. It is not normally necessary for anything other than minor adjustment from this default value.	short

Example: Set the NanoTrak circle home position to be screen centre.

TX 33, 06, 04, 00, D0, 01, 02, 00, 58, 02

Header: 33, 06, 04, 00, D0, 01: Set_NTGainParams, 04 byte data packet, Generic USB Device.

GainCtrlMode 0x0002: Software Setting

NTGainSW 0x0258: 600

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
34	06	00	00	d	s

GET:

Command structure (10 bytes):

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
35	06	04	00	d	s	GainCtrlMode	NTGainSW		

See SET for structure.

MGMSG_PZ_SET_NTTLALPFILTERPARAMS	0x0636
MGMSG_PZ_REQ_NTTLALPFILTERPARAMS	0x0637
MGMSG_PZ_GET_NTTLALPFILTERPARAMS	0x0638

Function: This message specifies the cut off frequency of the digital low pass (LP) filter applied to output readings of the internal amplifier (TIA) circuitry. If the readings displayed or returned are unstable, this setting can be used to remove any unwanted high frequency components and improve input signal stability.

SET:

Command structure (26 bytes)

6 byte header followed by 20 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
36	06	14	00	d	s	Param1				Param2			
14	15	16	17	18	19	20	21	22	23	24	25		
<i>Data</i>													
Param3			Param4			Param5							

Data Structure:

field	description	format
FilterParams	<p>This parameter contains low pass filter values which can be applied to the OUTPUT from the TIA, i.e. is applied to those reading params sent to the PC. It does NOT operate on the input to the TIA and does not operate on reading values used by the NanoTrak algorythms (these use a bandpass filter, effectively negating the need for a LP filter).</p> <p>The filter can be used to smooth out readings displayed in the GUI. It can also be used by client applications without affecting operation of the NanoTrak.</p> <p>Note. Although there are 5 parameters available, only the first parameter is used at this time.</p> <p>The filter can be set to OFF, or one of 5 frequency values as follows:</p> <p>Note. Only the first parameter is used at this time.</p> <ul style="list-style-type: none">0 LP_NONE Low pass filter inactive1 LP_1HZ Cut off all signals above 1Hz2 LP_3HZ Cut off all signals above 3Hz3 LP_10HZ Cut off all signals above 10Hz4 LP_30HZ Cut off all signals above 30Hz5 LP_100HZ Cut off all signals above 100Hz	long

Example: Set the LP filter to 1 Hz.

Header: 36, 06, 14, 00, D0, 01: Set_NTTIALPFilterParams, 20 byte data packet, Generic USB Device.

FilterParams: 05 LP_100HZ Cut off all signals above 100Hz

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
37	06	00	00	d	s

GET:

Command structure (26 bytes)

0	1	2	3	4	5	6	7	8	9	10	11	12	13				
<i>header</i>						<i>Data</i>											
38	06	14	00	d	s	Param1	Param2	Param3	Param4	Param5	Param6	Param7	Param8				
<i>Data</i>																	
Param3																	

See SET for structure.

MGMSG_PZ_REQ_NTTIAREADING
MGMSG_PZ_GET_NTTIAREADING
0x0639
0x063A

Function: This message obtains the absolute signal value at the current position, in units as displayed on the GUI panel.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
39	06	00	00	d	s

GET:

Command structure (16 bytes)

6 byte header followed by 10 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11		
<i>header</i>						<i>Data</i>							
3A	06	0A	00	d	s	AbsReading	RelReading						
12	13	14	15										
<i>Data</i>													
Range						UnderOverRead							

Data Structure:

field	description	format						
AbsReading	This parameter returns the absolute TIA (PIN) current or BNC voltage value at the current position. The value is returned as a 4 byte floating point value in the range 1×10^{-9} to 1×10^{-3} (i.e. 1 nA to 1 mA or 1 to 10 V). The input source, TIA or BNC is set in the Set_NTFeedbackSRC message.	float						
RelReading	The relative signal strength at the current position, in the range 0 to 32767 (i.e. 0 to 100% of the range currently selected). This value matches the length of the input signal bargraph on the GUI panel. (e.g. if the 3 μ A range is currently selected, then a RelReading value of 16384 (50%) equates to 1.5 μ A.).	word						
Range	<p>This parameter returns the input signal range currently selected. There are 14 range settings (1 - 14) that can be used to select the best range to measure the input signal (displayed on the GUI panel relative input signal bar and display).</p> <p>Note. Range 1 and 2 (3 nA and 10 nA) are not applicable to TNA001 T-Cube units.</p> <p>This parameter returns the input signal range currently selected, defined as follows:</p> <table> <tr> <td>Range 1</td> <td>3 nA</td> <td>0x03</td> </tr> <tr> <td>Range 2</td> <td>10 nA</td> <td>0x04</td> </tr> </table>	Range 1	3 nA	0x03	Range 2	10 nA	0x04	word
Range 1	3 nA	0x03						
Range 2	10 nA	0x04						

	Range 3 30 nA 0x05 Range 4 100 nA 0x06 Range 5 300 nA 0x07 Range 6 1 µA 0x08 Range 7 3 µA 0x09 Range 8 10 µA 0x0A Range 9 30 µA 0x0B Range 10 100 µA 0x0C Range 11 300 µA 0x0D Range 12 1 mA 0x0E Range 13 3 mA 0x0F Range 14 10 mA 0x10	
UnderOverRead	This parameter returns a value that identifies whether the unit is under reading or over reading the input signal as follows: 0x01 power signal is within current TIA range 0x02 power signal is under-reading for current TIA 0x03 power signal is over-reading for current TIA range e.g. if a user specified range of 3 µA is currently applied, this parameter returns '0x03' (Over read) for input signals greater than 3 µA.	word

Example: Get the NanoTrak reading.

RX 3A, 06, 0A, 00, D0, 01, 00, 00, 00, 00, 00, 05, 00, 01, 00

Header: 3A, 06, 0A, 00, D0, 01: Get_NTTIAResult, 10 byte data packet, Generic USB Device.

<i>AbsReading</i>	00, 00, 00, 00:	i.e. 20 nA
<i>RelReading</i>	00, 40:	16384, i.e. 50%
<i>Range</i>	05, 00	Range 3, i.e. 30 nA
<i>UnderOverRead</i>	01, 00	Within Range

MGMSG_PZ_SET_NTFEEDBACKSRC	0x063B
MGMSG_PZ_REQ_NTFEEDBACKSRC	0x063C
MGMSG_PZ_GET_NTFEEDBACKSRC	0x063D

Function: This message sets the input source of the NanoTrak.
The INPUT_BNC settings are used when NanoTraking to optimise a voltage feedback signal. Typically, these inputs are selected when an external power meter which generates a voltage output, is connected to the rear panel SIG IN connector.

Note. In this case the internal amplifier circuit is bypassed and the 'Range' bar on the GUI panel is switched off (autoranging functionality is not required). Furthermore, although tracking occurs as normal, the tracking indicator on the GUI panel is inoperative.

The INPUT_TIA setting is used when NanoTraking to optimise a PIN current feedback signal. The TIA (trans impedance amplifier) input source should be selected when using the rear panel OPTICAL/PIN I/P connector with either an integral detector, or an external detector head connected to the optional SMB adapter. This option uses the internal amplifier circuit and associated functionality (e.g. autoranging).

SET:

Command structure (6 bytes)

0	1	2	3	4	5
<i>header</i>					
3B	06	00	00	d	s

The input source is set in byte 2 as follows:

P_PZ_NTFBTIA	0x01	TIA input
P_PZ_NTFBBNC1V	0x02	BNC input (1V range)
P_PZ_NTFBBNC2V	0x03	BNC input (2V range)
P_PZ_NTFBBNC5V	0x04	BNC input (5V range)
P_PZ_NTFBBNC10V	0x05	BNC input (10V range)

Example: Set the input source to TIA input.

TX, 3B, 06, 01, 00, 50, 01,

REQ:

Command structure (6 bytes)

0	1	2	3	4	5
<i>header</i>					
3C	06	00	00	d	s

GET:

Command structure (6 bytes)

0	1	2	3	4	5
<i>header</i>					
3D	06	00	00	d	s

See SET command for structure

**MGMSG_PZ_REQ_NTSTATUSBITS
MGMSG_PZ_GET_NTSTATUSBITS**
**0x063E
0x063F**

Function: Returns a number of status flags pertaining to the operation of the NanoTrak controller channel specified in the Chan Ident parameter. These flags are returned in a single 32 bit integer parameter and can provide additional useful status information for client application development. The individual bits (flags) of the 32 bit integer value are described in the following tables.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
3E	06	Chan Ident	00	d	s

GET:

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
3F	06	0A	00	d	s	StatusBits					

Data Structure:

field	description	format
StatusBits	The status bits for the associated controller channel. The meaning of the individual bits (flags) of the 32 bit integer value will depend on the controller and are described in the following tables.	dword

TNA001 controller

Hex Value	Bit Number	Description
0x00000001	1	Tracking (1 - tracking, 0 - latched).
0x00000002	2	Tracking with Signal (1 – with signal, 0 – no signal)
0x00000004	3	Tracking Channel A (1 – Chan A only, 0 – Both channels)
0x00000008	4	Tracking Channel B (1 – Chan B only, 0 – Both channels)
0x00000010	5	Auto-ranging (1 – auto ranging, 0 manual ranging).
0x00000020	6	Under Read (1 – under reading, 0 – reading within range).
0x00000040	7	Over Read (1 – over reading, 0 – reading within range).
	8 to 16	For future use
0x00010000	17	Channel A Connected (1 – Connected, 0 – Not Connected)
0x00020000	18	Channel B Connected (1 – Connected, 0 – Not Connected)
0x00040000	19	Channel A Enabled (1 – Enabled, 0 – Disabled)
0x00080000	20	Channel B Enabled (1 – Enabled, 0 – Disabled)
0x00100000	21	Channel A Control Mode (1 – Closed Loop, 0 – Open Loop)
0x00200000	22	Channel B Control Mode (1 – Closed Loop, 0 – Open Loop)
	23 to 32	For future use

BNT series controllers

Hex Value	Bit Number	Description
0x00000001	1	Tracking (1 - tracking, 0 - latched).
0x00000002	2	Tracking with Signal (1 – with signal, 0 – no signal)
0x00000004	3	Tracking Channel A (1 – Chan A only, 0 – Both channels)
0x00000008	4	Tracking Channel B (1 – Chan B only, 0 – Both channels)
0x00000010	5	Auto-ranging (1 – auto ranging, 0 manual ranging).
0x00000020	6	Under Read (1 – under reading, 0 – reading within range).
0x00000040	7	Over Read (1 – over reading, 0 – reading within range).
	8 to 16	For future use
0x00010000	17	Channel A Connected (1 – Connected, 0 – Not Connected)
0x00020000		
0x00040000	19	Channel A Enabled (1 – Enabled, 0 – Disabled)
0x00080000	20	Channel B Enabled (1 – Enabled, 0 – Disabled)
0x00100000	21	Channel A Control Mode (1 – Closed Loop, 0 – Open Loop)
0x00200000	22	Channel B Control Mode (1 – Closed Loop, 0 – Open Loop)
Note. Bits 23 to 32 (Digital Input States) are only applicable if the associated digital input is fitted to your controller – see the relevant handbook for more details		
0x00100000	21	Digital input 1 state (1 - logic high, 0 - logic low).
0x00200000	22	Digital input 2 state (1 - logic high, 0 - logic low).
0x00400000	23	Digital input 3 state (1 - logic high, 0 - logic low).
0x00800000	24	Digital input 4 state (1 - logic high, 0 - logic low).
0x01000000	25	Digital input 5 state (1 - logic high, 0 - logic low).
0x02000000	26	Digital input 6 state (1 - logic high, 0 - logic low).
0x04000000	27	Digital input 7 state (1 - logic high, 0 - logic low).
0x08000000	28	Digital input 8 state (1 - logic high, 0 - logic low).
	29	For Future Use
0x20000000	30	Active (1 – indicates unit is active, 0 – not active)
0x40000000	31	For Future Use
0x80000000	32	Channel enabled (1 – enabled, 0- disabled)

**MGMSG_PZ_REQ_NTSTATUSUPDATE
MGMSG_PZ_GET_NTSTATUSUPDATE**
**0x0664
0x0665**

Function: This function is used in applications where spontaneous status messages (i.e. messages sent using the START_STATUSUPDATES command) must be avoided.
 Status update messages contain information about the position and status of the controller (for example position and O/P voltage). The response will be sent by the controller each time the function is requested.

REQUEST:**Command structure (6 bytes):**

0	1	2	3	4	5
<i>header only</i>					
64	06	Chan Ident	00	d	s

GET:

Status update messages are received with the following format:-

Response structure (32 bytes)

6 byte header followed by 26 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
65	06	1A	00	d	s	CircPosA	CircPosB	CircDia			
12	13	14	15	16	17	18	19	20	21	22	23
<i>Data</i>						AbsReading	RelReading	Range	UnderOverRead	StatusBits	
24	25	26	27	28	29	30	31				
<i>Data</i>						StatusBits	NTGain	PhaseCompA	PhaseCompB		

Data Structure:

field	description	format
CircPosA	The horizontal co-ordinate of the circle home position, in the range 0 to 65535 (0 to 100% of output voltage or 0 to 10 NanoTrak units).	word
CircPosB	The vertical co-ordinate of the circle home position, in the range 0 to 65535 (0 to 100% of output voltage or 0 to 10 NanoTrak units).	word
CircDia	This NanoTrak scanning circle diameter. The diameter is returned in the range 0 to 65535, which relates to 0% to 100% output voltage -(i.e. 0 to 10 NT units).	word
AbsReading	The absolute TIA (PIN) current or BNC voltage value at the current position. The value is returned as a 4 byte floating point value in the range 1×10^{-9} to 1×10^{-3} (i.e. 1 nA to 1 mA or 1 to 10 V). The input source, TIA or BNC is set in the	float

	Set_NTFeedbackSRC message.																																											
RelReading	The relative signal strength at the current position, in the range 0 to 32767 (i.e. 0 to 100% of the range currently selected). This value matches the length of the input signal bargraph on the GUI panel. (e.g. if the 3 μA range is currently selected, then a RelReading value of 16384 (50%) equates to 1.5 μA).	word																																										
Range	<p>The NanoTrak unit is equipped with an internal trans-impedance amplifier (TIA) circuit (and associated range/power level displays and control buttons in the GUI). This amplifier operates when an external input signal is connected to the Optical/PIN connector on the rear panel. There are 14 range settings (1 - 14) that can be used to select the best range to measure the input signal (displayed on the GUI panel relative input signal bar and display).</p> <p>Note. Range 1 and 2 (3 nA and 10 nA) are not applicable to TNA001 T-Cube units.</p> <p>This parameter returns the input signal range currently selected, defined as follows:</p> <table> <tbody> <tr><td>Range 1</td><td>3 nA</td><td>0x03</td></tr> <tr><td>Range 2</td><td>10 nA</td><td>0x04</td></tr> <tr><td>Range 3</td><td>30 nA</td><td>0x05</td></tr> <tr><td>Range 4</td><td>100 nA</td><td>0x06</td></tr> <tr><td>Range 5</td><td>300 nA</td><td>0x07</td></tr> <tr><td>Range 6</td><td>1 μA</td><td>0x08</td></tr> <tr><td>Range 7</td><td>3 μA</td><td>0x09</td></tr> <tr><td>Range 8</td><td>10 μA</td><td>0x0A</td></tr> <tr><td>Range 9</td><td>30 μA</td><td>0x0B</td></tr> <tr><td>Range 10</td><td>100 μA</td><td>0x0C</td></tr> <tr><td>Range 11</td><td>300 μA</td><td>0x0D</td></tr> <tr><td>Range 12</td><td>1 mA</td><td>0x0E</td></tr> <tr><td>Range 13</td><td>3 mA</td><td>0x0F</td></tr> <tr><td>Range 14</td><td>10 mA</td><td>0x10</td></tr> </tbody> </table>	Range 1	3 nA	0x03	Range 2	10 nA	0x04	Range 3	30 nA	0x05	Range 4	100 nA	0x06	Range 5	300 nA	0x07	Range 6	1 μA	0x08	Range 7	3 μA	0x09	Range 8	10 μA	0x0A	Range 9	30 μA	0x0B	Range 10	100 μA	0x0C	Range 11	300 μA	0x0D	Range 12	1 mA	0x0E	Range 13	3 mA	0x0F	Range 14	10 mA	0x10	word
Range 1	3 nA	0x03																																										
Range 2	10 nA	0x04																																										
Range 3	30 nA	0x05																																										
Range 4	100 nA	0x06																																										
Range 5	300 nA	0x07																																										
Range 6	1 μA	0x08																																										
Range 7	3 μA	0x09																																										
Range 8	10 μA	0x0A																																										
Range 9	30 μA	0x0B																																										
Range 10	100 μA	0x0C																																										
Range 11	300 μA	0x0D																																										
Range 12	1 mA	0x0E																																										
Range 13	3 mA	0x0F																																										
Range 14	10 mA	0x10																																										
UnderOverRead	<p>This parameter returns a value that identifies whether the unit is under reading or over reading the input signal as follows:</p> <p>0x01 power signal is within current TIA range 0x02 power signal is under-reading for current TIA 0x03 power signal is over-reading for current TIA range e.g. if a user specified range of 3 μA is currently applied, this parameter returns '0x03' (Over read) for input signals greater than 3 μA.</p>	word																																										
StatusBits	The meaning of the individual bits (flags) of the 32 bit integer value will depend on the controller and are described in the following tables.	dword																																										
NTGain	This parameter returns the loop gain, as a function of TIA range setting. The value is returned between 100 and 10000 (default value of 600).	short																																										
PhaseCompA	The horizontal axis phase compensation value, returned in real world units as follows:-	short																																										

	<p>value = (phase angle [degrees] / 360) * CircOscFreq See the PZ_SET_NTCIRCPARAMS message for details on the CircOscFreq parameter</p> <p>Note. Negative phase values must be made positive by subtraction from 360 before the calculation is made.</p>	
PhaseCompB	<p>The vertical axis phase compensation value, returned in real world units as follows:-</p> <p>value = (phase angle [degrees] / 360) * CircOscFreq See the PZ_SET_NTCIRCPARAMS message for details on the CircOscFreq parameter</p> <p>Note. Negative phase values must be made positive by subtraction from 360 before the calculation is made.</p>	short

TNA001 controller

Hex Value	Bit Number	Description
0x00000001	1	Tracking (1 - tracking, 0 - latched).
0x00000002	2	Tracking with Signal (1 – with signal, 0 – no signal)
0x00000004	3	Tracking Channel A (1 – Chan A only, 0 – Both channels)
0x00000008	4	Tracking Channel B (1 – Chan B only, 0 – Both channels)
0x00000010	5	Auto-ranging (1 – auto ranging, 0 manual ranging).
0x00000020	6	Under Read (1 – under reading, 0 – reading within range).
0x00000040	7	Over Read (1 – over reading, 0 – reading within range).
	8 to 16	For future use
0x00010000	17	Channel A Connected (1 – Connected, 0 – Not Connected)
0x00020000	18	Channel B Connected (1 – Connected, 0 – Not Connected)
0x00040000	19	Channel A Enabled (1 – Enabled, 0 – Disabled)
0x00080000	20	Channel B Enabled (1 – Enabled, 0 – Disabled)
0x00100000	21	Channel A Control Mode (1 – Closed Loop, 0 – Open Loop)
0x00200000	22	Channel B Control Mode (1 – Closed Loop, 0 – Open Loop)
	23 to 32	For future use

BPC series controllers

Hex Value	Bit Number	Description
0x00000001	1	Piezo actuator connected (1 - connected, 0 - not connected).
	2 to 4	For Future Use
0x00000010	5	Piezo channel has been zero'd (1 - zero'd, 0 not zero'd).
0x00000020	6	Piezo channel is zeroing (1 - zeroing, 0 - not zeroing).
0x00000040	7 to 8	For Future Use
0x00000100	9	Strain gauge feedback connected (1 - connected, 0 - not connected).
	10	For Future Use
0x00000400	11	Position control mode (1 - closed loop, 0 - open loop).
	12 to 20	For Future Use
Note. Bits 21 to 28 (Digital Input States) are only applicable if the associated digital input is fitted to your controller – see the relevant handbook for more details		
0x00100000	21	Digital input 1 state (1 - logic high, 0 - logic low).
0x00200000	22	Digital input 2 state (1 - logic high, 0 - logic low).
0x00400000	23	Digital input 3 state (1 - logic high, 0 - logic low).
0x00800000	24	Digital input 4 state (1 - logic high, 0 - logic low).

0x01000000	25	Digital input 5 state (1 - logic high, 0 - logic low).
0x02000000	26	Digital input 6 state (1 - logic high, 0 - logic low).
0x04000000	27	Digital input 7 state (1 - logic high, 0 - logic low).
0x08000000	28	Digital input 8 state (1 - logic high, 0 - logic low).
	29	For Future Use
0x20000000	30	Active (1 – indicates unit is active, 0 – not active)
0x40000000	31	For Future Use
0x80000000	32	Channel enabled (1 – enabled, 0- disabled)

MGMSG_PZ_ACK_NTSTATUSUPDATE**0x0666****Only Applicable If Using USB COMMS. Does not apply to RS-232 COMMS**

Function: If using the USB port, this message called "server alive" must be sent by the server to the controller at least once a second or the controller will stop responding after ~50 commands. The controller keeps track of the number of "status update" type of messages (e.g. move complete message) and if it has sent 50 of these without the server sending a "server alive" message, it will stop sending any more "status update" messages. This function is used by the controller to check that the PC/Server has not crashed or switched off. There is no response.

Structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
66	06	00	00	d	s

TX 66, 06, 00, 00, 50, 01

MGMSG_NT_SET_EEPROMPARAMS**0x07E7**

Function: Used to save the parameter settings for the specified message. These settings may have been altered either through the various method calls or through user interaction with the GUI (specifically, by clicking on the 'Settings' button found in the lower right hand corner of the user interface).

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>					<i>Data</i>				
E7	07	04	00	d	s	Chan Ident	MsgID		

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
MsgID	The message ID of the message containing the parameters to be saved.	word

Example:

TX E7, 07, 04, 00, D0, 01, 01, 00, 18, 06,

Header: E7, 07, 04, 00, D0, 01: Set_EEPROMPARAMS, 04 byte data packet, Generic USB Device.

*Chan Ident: 01, 00: Channel 1**MsgID: Save parameters specified by message 0618 (SetNTCircParams).*

MGMSG_NT_SET_TNA_DISPSETTINGS	0x07E8
MGMSG_NT_REQ_TNA_DISPSETTINGS	0x07E9
MGMSG_NT_GET_TNA_DISPSETTINGS	0x07EA

Function: Used to set the intensity of the LED display on the front of the TNA unit.

SET:

Command structure (8 bytes)

6 byte header followed by 2 byte data packet as follows:

0	1	2	3	4	5	6	7
<i>header</i>							
E8	07	02	00	d	s	DisIntensity	

Data Structure:

field	description	format
DisIntensity	The intensity is set as a value from 0 (Off) to 255 (brightest).	word

Example: Set the input source to software and potentiometer.

TX E8, 07, 02, 00, D0, 01, 64, 00,

Header: E8, 07, 02, 00, D0, 01: Set_DISPSETTINGS, 02 byte data packet, Generic USB Device.

DisIntensity: 64, 00: Sets the display brightness to 100 (40%)

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
E9	07	01	00	d	s

Example: Request the display intensity

TX E9, 07, 01, 00, 50, 01

GET:

Command structure (8 bytes)

6 byte header followed by 2 byte data packet as follows:

0	1	2	3	4	5	6	7
<i>header</i>							
EA	07	02	00	d	s	DisIntensity	

See SET for data structure.

MGMSG_NT_SET_TNAIOSETTINGS	0x07EB
MGMSG_NT_REQ_TNAIOSETTINGS	0x07EC
MGMSG_NT_GET_TNAIOSETTINGS	0x07ED

Function: This message is used to set parameters which control the NanoTrak output signal ranges and the way in which these signals are routed to the associated piezo drivers.

SET:

Command structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
EB	07	04	00	d	s	LVOutRange	LVOutRoute	Not Used	Not Used				

Data Structure:

field	description	format
LVOutRange	The output signals from the NanoTrak T-Cube are routed to the piezo drivers to position the piezo actuators. Earlier piezo T-cubes accept a 5V input while later cubes accept a 10V input. Other piezo amplifiers with 5V or 10V input ranges may be driven from the NanoTrak T-Cube. This parameter sets the LV output range as follows: 0x01 0 to 5V Output Range 0x02 0 to 10V Output Range	word
LVOutRoute	This parameter sets the way the signals are routed to the piezo T-Cubes as follows: 0x01 Rear panel SMA connectors only 0x02 Rear panel SMA connectors and Hub routing	word
Not Used		
Not Used		

Example

Tx EB,07,08,00,D0,01,01,00,01,00,00,00,00,00

Header: EB, 07, 08, 00, D0, 01: Set TNAIOSettings, 08 byte data packet, Generic USB Device.

LVOOutRange: 01, 00: 0 to 5V range

LVOutRoute: 01, 00: Signal routing via rear panel SMA connectors.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
EC	07	Chan Ident	00	d	s

GET:

Command structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
ED	07	04	00	d	s	LVOutRange	LVOutRoute	Not Used	Not Used				

See SET for structure.

Laser Control Messages

Introduction

The ‘Laser’ ActiveX Control provides the functionality required for a client application to control one or more T-Cube Laser Sources.

The methods of the Laser Control Object can then be used to control the T-Cube Laser Source and Laser Driver units, and activities such as switching between display modes, setting the laser power set point, reading the laser power or current and setting the LED display intensity can be performed.

For details on the use of the Laser Source, refer to the handbook supplied with the unit.

MGMSG_LA_SET_PARAMS	0x0800
MGMSG_LA_REQ_PARAMS	0x0801
MGMSG_LA_GET_PARAMS	0x0802

Function: This generic parameter set/request message is used to control all the functionality of the TLS001. The specific parameters to control are identified by the use of sub-messages. These sub messages comply with the general format of the APT message protocol but rather than having a unique first and second byte in the header carrying the “message identifier” information, the first and second byte remain the same.

Instead, for the SET and GET messages, the message identifier is carried in the first two bytes in the data packet part of the message, whilst for the REQ message it is encoded as the third byte of the header.

Likewise, when the TLS001 responds, the first two bytes of the response remain the same and the first two bytes of the data packet identify the sub-message to which the information returned in the remaining part of the data packet relates.

The following sub messages are applicable to the TLS001:

- [Set/Request/Get Laser Power Setpoint \(sub-message ID = 1\)](#)
- [Request/Get Laser Current and Power \(sub-message ID = 3\)](#)
- [Set/Request/Get Laser Power Control Source \(sub-message ID = 5\)](#)
- [Request/Get Status Bits \(sub-message ID = 7\)](#)
- [Request/Get Maximum Limits \(sub-message ID = 9\)](#)
- [Set/Request/Get Display Settings \(sub-message ID = 11\)](#)

To explain the principle, the following examples describe the first of these messages in more detail.

Example - Set/Request/Get Laser Power Setpoint (sub-message ID = 1)

This sub-command is used to set / read the laser power setpoint. The setpoint is the required laser power that the TLS001 will attempt to maintain. This is not necessarily the same as the actual laser power because if the current limit for the laser diode is exceeded, the setpoint will not be reached.

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
00	08	04	00	d	s	MsgID	SetPoint		

Data Structure:

field	description	format
MsgID	The message ID of the message containing the parameters	word
SetPoint	The Laser power setpoint (0 to 32767 -> 0% to 100% power).to be saved.	word

Example: Set the laser power setpoint to be set to 5% of the maximum power

TX 00, 08, 04, 00, D0, 01, 00, 66, 06,

Header: 00, 08, 04, 00, D0, 01: Set_PARAMS, 04 byte data packet, Generic USB Device.

MsgID: 01, 00: Set Laser Power Setpoint

SetPoint:.66, 06: the laser power setpoint, 0x0666 (1638 decimal), which is 5 % of the full power.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
01	08	01	00	d	s

TX 01, 08, 01, 00, 50, 01,

GET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
02	08	04	00	d	s	MsgID	SetPoint		

See SET message for data structure

Example - Request/Get Laser Current and Power (sub-message ID = 3)

This sub-command is used to read the actual laser power and the laser current. Note that there is no SET message as only the setpoint power can be set, not the actual power or current.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
01	08	03	00	d	s

TX 01, 08, 03, 00, 50, 01,

GET:

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
02	08	06	00	d	s	MsgID	LaserCurrent	LaserPower			

Data Structure:

field	description	format
MsgID	The message ID of the message containing the parameters	word
LaserCurrent	The Laser current (0 to 32767 -> 0 to max current in mA)	word
LaserPower	The Laser power (0 to 32767 -> 0% to 100% power)	word

Example: Get the laser current and power

RX 02, 08, 06, 00, D0, 01, 03, 00, 66, 06, 66, 06

Header: 00, 08, 06, 00, D0, 01: Set_PARAMS, 06 byte data packet, Generic USB Device.

MsgID: 03, 00: Get Laser Current and Power

LaserCurrent:.66, 06: the laser current, 0x0666 (1638 decimal), which is 5 mA for a 100 mA max current laser.

LaserPower:.66, 06: the laser power, 0x0666 (1638 decimal), which is 5% of the full power.

Example - Set/Request/Get the Laser Power Control Source (sub-message ID = 5)

This sub-command is used to set / read the laser power control source. The laser power can be controlled by APT commands, the potentiometer on the top of the unit or the external SMA input. Only one control source can be active at any time, the options are mutually exclusive.

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
00	08	04	00	d	s	MsgID	LaserSource		

Data Structure:

field	description	format
MsgID	The message ID of the message containing the parameters	word
LaserSource	The Laser power source. This can be one of the following three options: 0 = SW control; 1 = external SMA input; 4 = potentiometer.	word

Example: Set the laser power source to be external SMA input

TX 00, 08, 04, 00, D0, 01, 05, 00, 01, 00

Header: 00, 08, 04, 00, D0, 01: Set_PARAMS, 04 byte data packet, Generic USB Device.

MsgID: 05, 00: Set Laser Power Source

LaserSource::01, 00: the laser power source is the external SMA input.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
01	08	05	00	d	s

TX 01, 08, 01, 00, 50, 01,

GET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
02	08	04	00	d	s	MsgID	LaserSource		

See SET message for data structure

Request/Get Status Bits (sub-message ID = 7)

This sub command can be used to request the TLS001 status bits. The message only has a request/ get part.

REQUEST:**Command structure (6 bytes):**

0	1	2	3	4	5
<i>header only</i>					
01	08	07	00	d	s

TX 01, 08, 07, 00, 50, 01,

GET:

Status update messages are received with the following format:-

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
02	08	06	00	d	s	MsgID	StatusBits				

Data Structure:

field	description	format
MsgID	The message ID of the message containing the parameters	word
StatusBits	The meaning of the individual bits (flags) of the 32 bit integer value will depend on the controller and are described in the following tables.	dword

TLS001 controller

Hex Value	Bit Number	Description
0x00000001	1	Laser output enabled state (1 - enabled, 0 - disabled).
0x00000002	2	Keyswitch enabled state (1 - enabled, 0 – disabled)
0x00000004	3	Laser control mode (1 - power [closed loop], 0 - current [open loop])
0x00000008	4	Safety interlock, (1 - enabled, 0 – disabled)
0x00000010	5	Units mode (1 - mA, else 0).
0x00000020	6	Units mode (1 - mW, else 0).
0x00000040	7	Units mode (1 - dBm, else 0)
	8	For Future Use

Example

RX 02, 08, 06, 00, 81, 50, 07, 00, 2B, 00, 00, 00

Header: 02, 08, 06, 00, 81, 50: LA_Get_Parms, 06 byte data packet, Generic USB Device.

MsgID: 07, 00: Get Status Bits

StatusBits: 2B,00,00,00, i.e. 00101011 the display shows mW units, the safety interlock is enabled, the keyswitch is enabled and the output is enabled.

Request/Get Maximum Limits (sub-message ID = 9)

This sub command can be used to request the TLS001 maximum limits, such as maximum current, maximum power and the wavelength of the laser diode. The message only has a request/ get part.

REQUEST:**Command structure (6 bytes):**

0	1	2	3	4	5
<i>header only</i>					
01	08	09	00	d	s

TX 01, 08, 09, 00, 50, 01,

GET:

Status update messages are received with the following format:-

Response structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13				
<i>header</i>						<i>Data</i>											
02	08	08	00	d	s	MsgID	MaxCurrent	MaxPower	Wavelength								

Data Structure:

field	description	format
MsgID	The message ID of the message containing the parameters	word
MaxCurrent	The Laser max current (0 to 65535 -> 0 to 655.35 mA)	word
MaxPower	The Laser max power (0 to 65535 -> 0 to 6.5535 mW)	word
WaveLength	The Laser wavelength in nm (635 or 1550)	word

Example – Get Laser Limits

RX 02, 08, 08, 00, D0, 01, 09, 00, C8, 00, 05, 00, 0E, 06

Header: 00, 08, 06, 00, D0, 01: Set_PARAMS, 06 byte data packet, Generic USB Device.

MsgID: 09, 00: Get Laser Max Limits

MaxCurrent:.C8, 00:, 0x00C8 i.e. 200mA max current.

MaxPower:.05, 00:, 0x0005 i.e. 5 mW max power.

Wavelength:.0E, 06: the laser power, 0x060E (1550 decimal), wavelength 1550 nm.

Set/Request/Get Display Settings (sub-message ID = 11)

This message can be used to adjust or read the front panel LED display brightness and the display units.

SET:

Command structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
00	08	08	00	d	s	MsgID	DisplIntensity	DispUnits	Unused				

Data Structure:

field	description	format
MsgID	The message ID of the message containing the parameters	word
DisplIntensity	The intensity is set as a value from 0 (Off) to 255 (brightest).	word
DispUnits	The LED display window on the front of the unit can be set to display the laser output in mA, mW or dBm as follows. 1 display shows laser current in mA. 2 display shows laser power in mW. 3 display shows laser power in dBm (relative to 1 mW)	word
Unused	N/A	word

Example: Set the display to show the laser current in Amps and at max brightness:

TX 00, 08, 08, 00, D0, 01, 0B, 00, FF, 00, 01, 00, 00, 00

Header: 00, 08, 08, 00, D0, 01: Set_Params, 08 byte data packet, Generic USB Device.

MsgID: 0B, 00: Set Display Settings

DisplIntensity: FF, 00: Sets the display brightness to 255 (100%)

DispUnits: 01, 00: Sets the display units to mA

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
01	08	0B	00	d	s

Example: TX 01, 08, 0B, 00, 50, 01

GET:

Command structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
00	08	08	00	d	s	MsgID	DisplIntensity	DispUnits	Unused				

See SET for data structure.

MGMSG_LA_SET_EEPROMPARAMS**0x0810**

Function: Used to save the parameter settings for the specified message. These settings may have been altered either through the various method calls or through user interaction with the GUI (specifically, by clicking on the 'Settings' button found in the lower right hand corner of the user interface).

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>					<i>Data</i>				
10	08	04	00	d	s	Chan Ident	MsgID		

Data Structure:

field	description	format
Chan Ident	The channel being addressed	word
MsgID	The message ID of the message containing the parameters to be saved.	word

Example:

TX 10, 08, 04, 00, D0, 01, 01, 00, 18, 06,

Header: 10, 08, 04, 00, D0, 01: Set_EEPROMPARAMS, 04 byte data packet, Generic USB Device.

Chan Ident: 01, 00: Channel 1

MsgID: Save parameters specified by message 0821 (GetStatusUpdate).

**MGMSG_LA_ENABLEOUTPUT
MGMSG_LA_DISABLEOUTPUT****0x0811
0x0812**

Function These messages are sent to enable or disable the Laser output.
The 3rd and 4th bytes in the command header are unused and set to 0x00.

SET:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
11	08	00	00	d	s

Example: Enable the laser output

TX 11, 08, 00, 00, 50, 01

Disable the laser output

TX 12, 08, 00, 00, 50, 01

**MGMSG_LA_REQ_STATUSUPDATE
MGMSG_LA_GET_STATUSUPDATE**
**0x0820
0x0821**

Function: This function is used in applications where spontaneous status messages (i.e. messages sent using the START_STATUSUPDATES command) must be avoided. Status update messages contain information about the position and status of the controller (for example position and O/P voltage). The response will be sent by the controller each time the function is requested.

REQUEST:**Command structure (6 bytes):**

0	1	2	3	4	5
<i>header only</i>					
20	08	00	00	d	s

GET:

Status update messages are received with the following format:-

Response structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
21	08	08	00	d	s	LaserCurrent	LaserPower						StatusBits

Data Structure:

field	description	format
LaserCurrent	The laser current, in the range 0 to 32760 – (i.e. 0 to max current in mA)	word
LaserPower	The laser power, in the range 0 to 32760 – (i.e. 0 to 100% of max power)	word
StatusBits	The meaning of the individual bits (flags) of the 32 bit integer value will depend on the controller and are described in the following tables.	dword

TLS001 controller

Hex Value	Bit Number	Description
0x00000001	1	Laser output enabled state (1 - enabled, 0 - disabled).
0x00000002	2	Keyswitch enabled state (1 - enabled, 0 – disabled)
0x00000004	3	Laser control mode (1 - power [closed loop], 0 - current [open loop])
0x00000008	4	Safety interlock, (1 - enabled, 0 – disabled)
0x00000010	5	Units mode (1 - mA, else 0).
0x00000020	6	Units mode (1 - mW, else 0).
0x00000040	7	Units mode (1 - dBm, else 0)
	8	For Future Use

Example

RX 21, 08, 08, 00, 81, 50, 90, 19, 90, 19, 2B, 00, 00, 00

Header: 21, 08, 08, 00, 81, 50: LA_Get_StatusUpdate, 08 byte data packet, Generic USB Device.

LaserCurrent: 90, 19: 6544 = 20 % of the maximum current;

LaserPower: 90, 19: 6544 = 20 % of the maximum power;

StatusBits: 2B,00,00,00, i.e. 00101011 the display shows mW units, the safety interlock is enabled, the keyswitch is enabled and the output is enabled.

MGMSG_LA_ACK_STATUSUPDATE**0x0822****Only Applicable If Using USB COMMS. Does not apply to RS-232 COMMS**

Function: If using the USB port, this message called "server alive" must be sent by the server to the controller at least once a second or the controller will stop responding after ~50 commands. The controller keeps track of the number of "status update" type of messages (e.g. move complete message) and if it has sent 50 of these without the server sending a "server alive" message, it will stop sending any more "status update" messages. This function is used by the controller to check that the PC/Server has not crashed or switched off. There is no response.

Structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
22	08	00	00	d	s

TX 22, 08, 00, 00, 50, 01

Quad Control Messages

Introduction

The ‘Quad’ ActiveX Control provides the functionality required for a client application to control one or more T-Cube Quad Detector Readers or Position Aligners.

The methods of the Quad Control Object can then be used to control the TQD001 T-Cube Quad Reader and the TPA101 T-Cube Position Aligner, and activities such as switching between Monitor, Open Loop and Closed Loop operating modes, setting the position demand parameters, reading the present beam position and setting the LED display intensity.

For details on the use of the T-Cubes, refer to the handbook supplied for the unit.

MGMSG_QUAD_SET_PARAMS	0x0870
MGMSG_QUAD_REQ_PARAMS	0x0871
MGMSG_QUAD_GET_PARAMS	0x0872

Function: This generic parameter set/request message is used to control the functionality of the TQD001 or TPA101. The specific parameters to control are identified by the use of sub-messages. These sub messages comply with the general format of the APT message protocol but rather than having a unique first and second byte in the header carrying the “message identifier” information, the first and second byte remain the same.
 Instead, for the SET and GET messages, the message identifier is carried in the first two bytes in the data packet part of the message, whilst for the REQ message it is encoded as the third byte of the header.
 Likewise, when the TQD001 or TPA101 responds, the first two bytes of the response remain the same and the first two bytes of the data packet identify the sub-message to which the information returned in the remaining part of the data packet relates.

The following sub messages are applicable to the TQD001 and TPA101:

- [Set/Request/Get Quad_LoopParams \(sub-message ID = 01\)](#)
- [Request/Get Quad_ Readings \(sub-message ID = 03\)](#)
- [Set/Request/Get Quad Position Demand Params \(sub-message ID = 05\)](#)
- [Set/Request/Get Quad Operating Mode \(sub-message ID = 07\)](#)
- [Request/Get Quad Status Bits \(sub-message ID = 09\)](#)
- [Set/Request/Get Quad Display Settings \(sub-message ID = 0B\)](#)
- [Set/Request/Get Quad Position Demand Outputs \(sub-message ID = 0D\)](#)

The following sub message is applicable only to the TPA101:

- [Set/Request/Get Quad_LoopParams2 \(sub-message ID = 0E\)](#)

To explain the principle, the following examples describe these messages in more detail.

Set/Request/Get Quad_LoopParams (sub-message ID = 01)

Used to set the proportional, integration and differential feedback loop constants to the value specified in the PGain, IGain and DGain parameters respectively. They apply when the quad detector unit is operated in closed loop mode, and position demand signals are generated at the rear panel SMA connectors by the feedback loops. These position demand voltages act to move the beam steering elements (e.g. a piezo driven mirror) in order to centralize a beam at the centre of the PSD head.

When operating in closed loop mode, the proportional, integral and differential (PID) constants can be used to fine tune the behaviour of the dual feedback loops to adjust the response of the position demand output voltages. The feedback loop parameters need to be adjusted to suit the different types of sensor that can be connected to the system. The default values have been optimized for the PDQ80A sensor.

SET:

Command structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
70	08	08	00	d	s	SubMsgID	PGain	IGain	DGain				

Data Structure:

field	description	format
SubMsgID	The message ID (i.e. 0100) of the message containing the parameters	word
PGain	The proportional gain. This term provides the force used to drive the piezo to the demand position, reducing the positional error. Together with the Integral and Differential, these terms determine the system response characteristics and accept values in the range 0 to 32767 (i.e. 0 to 100 in APT User GUI).	word
IGain	The integral gain. This term provides the 'restoring' force that grows with time, ensuring that the positional error is eventually reduced to zero. Together with the Proportional and Differential, these terms determine the system response characteristics and accept values in the range 0 to 32767 (i.e. 0 to 100 in APT User GUI).	word
DGain	The differential gain. This term provides the 'damping' force proportional to the rate of change of the position. Together with the Proportional and Integral, these terms determine the system response characteristics and accept values in the range 0 to 32767 (i.e. 0 to 100 in APT User GUI).	word

Example: Set the PID parameters for TQD001 or TPA101 as follows:

Proportional: 65

Integral: 80

Differential: 60

TX 70, 08, 08, 00, D0, 01, 01, 00, 41, 00, 50, 00, 3C, 00,

Header: 70, 08, 08, 00, D0, 01: Quad_SetParams, 8 byte data packet, Generic USB Device.

SubMsgID: 01, 00 SetQuadControlLoopParams)

PGain: 32, 53, (32767x65/100): Set the proportional term to 65

IGain: 65, 66, (32767x80/100): Set the integral term to 80

DGain: CC, 4C, (32767x60/100): Set the differential term to 60

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
71	08	01	00	d	s

GET:

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
72	08	08	00	d	s	SubMsgID	PGain	IGain	DGain				

For structure see Set message above.

Request/Get Quad_ Readings (sub-message ID = 3)

The TQD001 Quad Detector T-Cube has been designed to operate with the PDQ80A Quad Detector. The detector consists of a 4-segment photodiode sensor array, which provides 'Bottom minus Top' (YDIFF) and 'Left minus Right' (XDIFF) difference signals, together with the SUM of the signals (total beam power) from all four quadrants of the photodiode array. This sub-message is used to read the actual SUM, XDIFF and YDIFF signals from the detector. Whether these signals are routed to the LV OUT/XDIFF and LV OUT/YDIFF SMA connectors on the rear panel depends on the operating mode selected (see the [Quad_OperMode](#) message) as follows.

In 'Closed Loop' mode, the signal from the detector is interpreted by the unit, and the feedback circuit sends position demand signals (XOut and YOut) to the rear panel LV OUT/XDIFF and LV OUT/YDIFF connectors, which can be used to drive a pair of positioning elements (e.g. piezo controllers) in order to position the light beam within the center of the detector array. This submessage is then used to read the actual values for the XPos and YPos position demand signals (-10 V to +10V). Note that in closed loop mode, with the beam central, the X and Y axis difference outputs from the photodiode array are zero. However, the position demand signals on the rear panel LV OUT XDIFF and YDIFF SMA connectors are whatever value is necessary to drive the positioning elements to centre the beam.

When the Quad Detector T-Cube is operated in 'open loop' mode, the signals on the rear panel LV OUT/XDIFF and LV OUT/YDIFF connectors are constant. They are either fixed at zero (0V), or held at the last Closed Loop value (depending on the '[QuadPosDemandParams](#)' message). This is useful when the system is being adjusted manually, to position the light beam within the detector array.

When operating in 'Monitor' mode, the X axis (XDIFF) and Y axis (YDIFF) difference signals from the detector, are fed through to the rear panel SMA connectors for use in a monitoring application.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
71	08	03	00	d	s

TX 71, 08, 03, 00, 50, 01,

GET:

Command structure (18 bytes)

6 byte header followed by 12 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
72	08	0C	00	d	s	SubMsgID	XDiff	YDiff			
<i>Data</i>											
Sum		XPos		YPos							

Data Structure:

field	description	format
SubMsgID	The message ID (i.e. 0300) of the message containing the parameters	word
XDiff	The present X axis difference (XDIFF) signal from the detector head. (-10V to 10V in the range -32768 to 32767)	short
YDiff	The present Y axis difference (YDIFF) signal value from the detector head. (-10V to 10V in the range -32768 to 32767)	short
Sum	The present Sum signal value from the detector head (0V to 10V in the range 0 to 65535)	word
XPos	The X axis position output value on the rear panel XDiff SMA connector (-10V to 10V in the range -32768 to 32767)	short
YPos	The Y axis position output value on the rear panel YDiff SMA connector (-10V to 10V in the range -32768 to 32767)	short

Example: Get the Quad Detector T-Cube readings (T-Cube in open loop mode)

RX 72, 08, 0C, 00, D0, 01, 03, 00, FF, 3F, FF, 3F, FF, 7F, 00, 00, 00, 00

Header: 72, 08, 0C, 00, D0, 01: Quad_GetPARAMS, 12 byte data packet, Generic USB Device.

MsgID: 03, 00: Get Quad Readings

XDiff: FF, 3F: 0x3FFF (16383 decimal), i.e. 5 V.

YDiff: FF, 3F: 0x3FFF (16383 decimal), i.e. 5 V.

Sum: FF, FF: 0x7FFF (65535 decimal), i.e. 10 V.

XPos: 00, 00 i.e. Zero

YPos: 00, 00 i.e. Zero

Set/Request/Get Quad_PosDemandParams (sub-message ID = 5)

The TQD001 or TPA101 Quad Detector T-Cube has been designed to operate with the PDQ80A Quad Detector. The detector consists of a 4-segment photodiode sensor array, which provides ‘Bottom minus Top’ (YDIFF) and ‘Left minus Right’ (XDIFF) difference signals, together with the SUM of the signals (total beam power) from all four quadrants of the photodiode array. Whether these signals are routed to the LV OUT/XDIFF and LV OUT/YDIFF SMA connectors on the rear panel depends on the operating mode selected – see the [Quad_OperMode](#) message.

This sub-message is used to control the signals on the rear panel LV OUT/XDIFF and LV OUT/YDIFF connectors.

SET:

Command structure (18 bytes)

6 byte header followed by 12 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
70	08	0C	00	d	s	SubMsgID	XPosDemMin	YPosDemMin			
<i>Data</i>											
XPosDemMax	YPosDemMax	LVOutRoute	OLPosDem	XPosFBSense	YPosFBSense						

Data Structure:

field	description	format
SubMsgID	The message ID (i.e. 0500) of the message containing the parameters	word
XPosDemandMin	The following four parameters are applicable only when operating in closed loop mode. The XOut and YOut values are the low voltage signals sent to the LV OUT/XDIFF and LV OUT/YDIFF connectors, which are then used to drive the positioning mechanism in order to keep the beam central in the detector. Under normal operating conditions, these values are between -10 V and +10 V, however some applications may require the limits to be less than this. The XPosDemandMin parameter is used to set the min limit for the XOut value, between -10V and +10V. (i.e. -32768 to 32767)	short
YPosDemandMin	As above. The YPosDemandMin parameter is used to set the min limit for the YOut value, between -10V and +10V. (i.e. -32768 to 32767)	short
XPosDemandMax	As above. The XPosDemandMax parameter is used to set the max limit for the XOut value, between -10V and +10V. (-32768 to 32767)	short
YPosDemandMax	As above. The YPosDemandMax parameter is used to set the max limit for the YOut value, between -10V and +10V. (-32768 to 32767)	short
LVOutRoute	When operating in closed loop mode, the Quad Detector position control signals are always output on the external SMA connectors (LV OUT XDiff and LV	word

	<p>OUT YDiff). In addition, they can also be routed to the TCH002 hub, which eliminates the need for external SMA to SMA cables. This parameter is used to set the LV Out signal routing as follows:</p> <ul style="list-style-type: none"> 1 SMA Only 2 SMA + Hub 	
OpenLoopPosDemands	<p>When the Quad Detector T-Cube is operated in 'open loop' mode, the position demand signals (on the XDIFF and YDIFF connectors) can either be set to zero, or held at their last closed loop value, according to the value entered in this parameter as follows:</p> <ul style="list-style-type: none"> 1 OpenLoopPosDemandsZero - the output is set to zero (0V). 2 OpenLoopPosDemandsHeld = the outputs are fixed at the values present when the unit is switched to open loop. 	word
XPosDemandFBSense	<p>Due to the choice of piezo amplifier/driver or the configuration of mirrors (or other optical components) it is possible that certain application set ups may require the sense of the X and Y axis position demand signals to be inverted. This parameter sets the signal sense and gain for the X axis output as follows:</p> <p>If XPosDemandFBSense is set to '10' (32767) the signals are positive when the beam is in the left hand quadrants of the detector array, and negative when in the right hand quadrants. The gain of the system is set to '1'.</p> <p>If XPosDemandFBSense is set to '-7' (-22938) the signals are positive when the beam is in the right hand quadrants of the detector array, and negative when in the left hand quadrants. The gain of the system is set to '0.7'.</p>	short
YPosDemandFBSense	<p>Similarly to the XPosDemandFBSense described above, this parameter sets the signal sense and gain for the Y axis output as follows:</p> <p>If YPosDemandFBSense is set to '10' (32767) the signals are positive when the beam is in the top quadrants of the detector array, and negative when in the bottom quadrants. The gain of the system is set to '1'.</p> <p>If YPosDemandFBSense is set to '-3' (-9830) the signals are positive when the beam is in the bottom quadrants of the detector array, and negative when in the top quadrants. The gain of the system is set to '0.3'.</p>	short

Example: Set the Quad Pos Demand Params

RX 70, 08, 12, 00, D0, 01, 05, 00, 01, 80, 01, 80, FF, 7F, 7F, 02, 00, 01, 00, 0A, 00, 0A, 00

Header: 70, 08, 12, 00, D0, 01: Quad_SetPARAMS, 18 byte data packet, Generic USB Device.

SubMsgID: 05, 00: Set Quad PosDemandParams

XPosDemandMin:.01, 80: 0x8001 (-32767 decimal), i.e. -10 V.

YPosDemandMin:. 01, 80: 0x8001 (-32767 decimal), i.e. -10 V.

XPosDemandMax: FF, 7F: 0x7FFF (32767 decimal), i.e. 10 V.

YPosDemandMax: FF, 7F: 0x7FFF (32767 decimal), i.e. 10 V.

LVOutRoute: 02, 00 i.e. SMA + Hub

OpenLoopPosDemand:.01, 00: i.e. Zero.

XPosDemandFBSense:. FF, 7F: i.e. Positive sense, gain = 1.

YPosDemandFBSense: 9A, D9: i.e. Positive sense, gain = 0.3.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
71	08	05	00	d	s

TX 71, 08, 05, 00, 50, 01,

GET:

Command structure (22 bytes)

6 byte header followed by 18 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
72	08	12	00	d	s	SubMsgID	XPosDemMin	YPosDemMin			
12	13	14	15	16	17						
<i>Data</i>						XPosDemMax	YPosDemMax	LVOutRoute	OLPosDem	XPosFBSense	YPosFBSense

See Set message for structure

Set/Request/Get Quad_OperMode (sub-message ID = 07)

Used to set the operating mode of the TQD001 Quad Detector T-Cube to either Monitor, Open Loop or Closed Loop mode as described below.

SET:

Command structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
70	08	08	00	d	s	SubMsgID	Mode		

Data Structure:

field	description	format
SubMsg ID	The message ID (i.e. 0700) of the message containing the parameters	word
Mode	<p>The operating mode of the unit.</p> <p>When operating in 'Monitor' mode, the X axis (XDIFF) and Y axis (YDIFF) difference signals from the detector, are fed through to the rear panel SMA connectors for use in a monitoring application.</p> <p>When in 'Open Loop' mode, the signals at the rear panel are fixed at zero (0V), or held at the last closed loop value, depending on the setting of the 'OpenLoopPosDemands' parameter in the QuadPosDemandParams message. This is useful when the system is being adjusted manually, to position the light beam within the detector array.</p> <p>In 'Closed Loop' mode, the feedback circuit sends position demand signals (XOut & YOut) to the rear panel XDIFF and YDIFF connectors, which can be used to drive a pair of positioning elements (e.g. piezo drivers) in order to position the light beam within the center of the detector array.</p> <p>The mode is set as follows:</p> <ul style="list-style-type: none"> 1 Monitor Mode 2 OpenLoop 3 ClosedLoop 	word

Example: Set the operating mode to closed loop

TX 70, 08, 04, 00, D0, 01, 07, 00, 03, 00,

Header: 70, 08, 04, 00, D0, 01: Quad_SetPARAMS, 04 byte data packet, Generic USB Device.

SubMsgID: 07, 00: SetQuadOperMode

Mode: 03, 00,: Set closed loop mode

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
71	08	Msg Ident	00	d	s

GET:

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
70	08	08	00	d	s	SubMsgID	Mode		

For structure see Set message above.

Request/Get Quad_Status Bits (sub-message ID = 9)

This sub command can be used to request the TQD001 or TPA101 status bits. The message only has a request/ get part.

REQUEST:**Command structure (6 bytes):**

0	1	2	3	4	5
<i>header only</i>					
71	08	09	00	d	s

TX 71, 08, 09, 00, 50, 01,

GET:

Status update messages are received with the following format:-

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
72	08	06	00	d	s	SubMsgID	StatusBits				

Data Structure:

field	description	format
MsgID	The message ID (0900) of the message containing the parameters	word
StatusBits	The individual bits (flags) of the 32 bit integer value are described in the following table.	dword

TQD001 or TPA101 controller

Hex Value	Bit Number	Description
0x00000001	1	Position Monitoring Mode (1 - enabled, 0 - disabled).
0x00000002	2	Open Loop Operating Mode (1 - enabled, 0 – disabled)
0x00000004	3	Closed Loop Operating Mode (1 - enabled, 0 – disabled)
0x00000008	4 to 32	For Future Use

Example

RX 72, 08, 06, 00, D0, 50, 09, 00, 2B, 00, 00, 00

Header: 02, 08, 06, 00, D0, 50: Quad_Get_Parms, 06 byte data packet, Generic USB Device.

MsgID: 09, 00: Get Status Bits

StatusBits: 04,00,00,00, i.e. 100 Closed Loop operating mode is enabled.

Set/Request/Get Quad Display Settings (sub-message ID = 0B)

This message can be used to adjust or read the front panel LED display brightness and the display units.

SET:

Command structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
70	08	08	00	d	s	SubMsgID	DisplIntensity	Unused	Unused				

Data Structure:

field	description	format
MsgID	The message ID (i.e. 0B00) of the message containing the parameters	word
DisplIntensity	The intensity is set as a value from 0 (Off) to 255 (brightest).	word
Reserved	N/A	word
Reserved	N/A	word

Example: Set the display to max brightness:

TX 70, 08, 08, 00, D0, 01, 0B, 00, FF, 00, 00, 00, 00, 00

Header: 70, 08, 08, 00, D0, 01: Quad_SetParams, 08 byte data packet, Generic USB Device.

SubMsgID: 0B, 00: Set Display Settings

DisplIntensity: FF, 00: Sets the display brightness to 255 (100%)

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
71	08	0B	00	d	s

Example: TX 71, 08, 0B, 00, 50, 01

GET:

Command structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
72	08	08	00	d	s	SubMsgID	DisplIntensity	Unused	Unused				

See SET for data structure.

Set/Request/Get Quad_PositionOutputs (sub-message ID = 0D)

This sub message can be used to set and get the position demand signals (on the XDIFF, YDIFF connectors).

When the quad detector unit is used with a beam steering device (e.g. a piezo mirror via piezo drivers), this message allows the beam to be positioned by entering a value (-10 V to +10V) in the XPos and YPos parameters.

SET:

Status update messages are received with the following format:-

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
70	08	06	00	d	s	SubMsgID	XPos	YPos			

Data Structure:

field	description	format
MsgID	The message ID (i.e. 0D00) of the message containing the parameters	word
XPos	The X axis position output value -10 V to 10 V (i.e. -32768 to 32767)	short
YPos	The Y axis position output value -10 V to 10 V (i.e. -32768 to 32767)	short

Example Set the XPos and YPos signals to be -10 V and 10V respectively.

TX 70, 08, 06, 00, D0, 01, 0D, 00, 01, 80, FF, 7F

Header: 70, 08, 06, 00, D0, 01: Quad_Get_Parms, 06 byte data packet, Generic USB Device.

MsgID: 0D, 00: Get Quad_PositionOutputs

XPos: 01, 80: 0x8001 (-32767 decimal), i.e. -10 V.

YPos: FF, 7F: 0xFFFF (32767 decimal), i.e. 10 V.

REQUEST:**Command structure (6 bytes):**

0	1	2	3	4	5
<i>header only</i>					
71	08	0D	00	d	s

TX 71, 08, 0D, 00, 50, 01,

GET:

Status update messages are received with the following format:-

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
72	08	06	00	d	s	SubMsgID	XPos	YPos			

Set/Request/Get Quad_LoopParams2 (sub-message ID = 0E)

This sub-message is applicable only to the TPA101 unit.

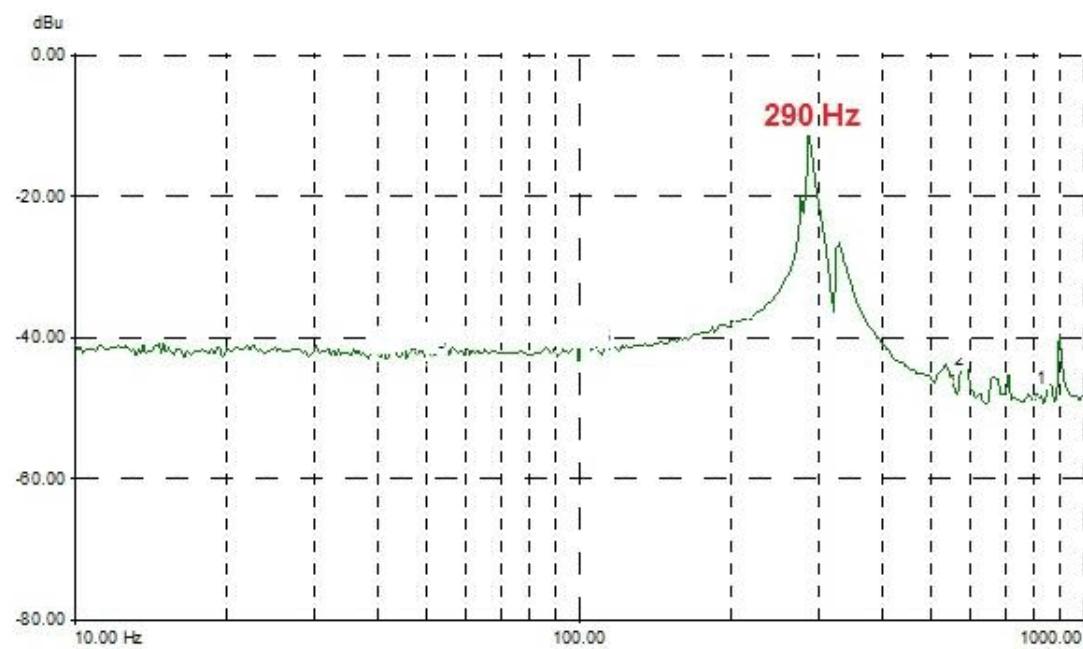
Used to set the proportional, integration and differential feedback loop constants and also to set the derivative cut off frequency and the notch filter center frequency.

PID Constants: The PID constants apply when the unit is operated in closed loop mode, and position demand signals are generated at the rear panel SMA connectors by the feedback loops. These position demand voltages act to move the beam steering elements (e.g. a piezo driven mirror) in order to centralize a beam at the centre of the PSD head.

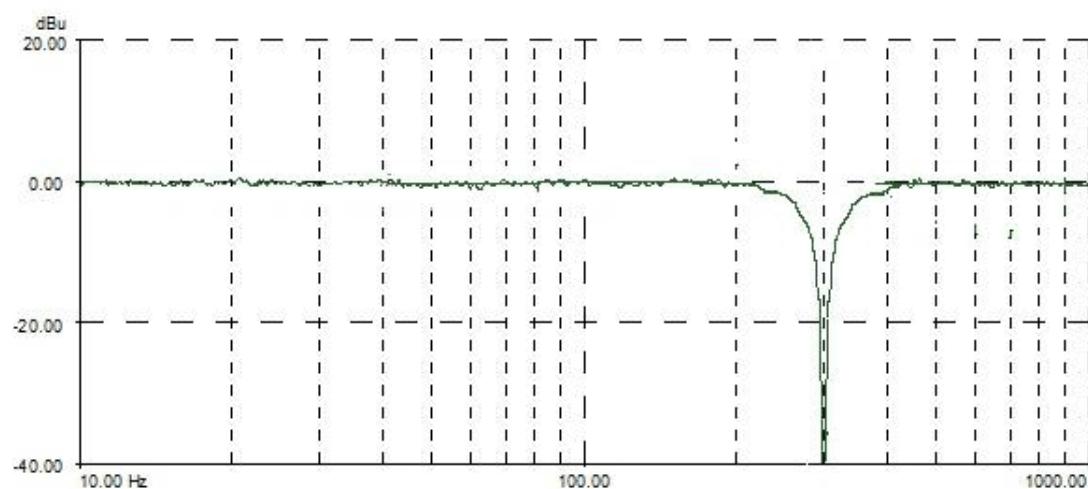
When operating in closed loop mode, the proportional, integral and differential (PID) constants can be used to fine tune the behaviour of the dual feedback loops to adjust the response of the position demand output voltages. The feedback loop parameters need to be adjusted to suit the different types of sensor that can be connected to the system. The default values have been optimized for the PDQ80A sensor.

Derivative Filter: The output of the derivative (differential) part of the PID controller can be passed through a tuneable low pass filter. Whilst the derivative component of the PID loop often improves stability (as it acts as a retaining force against abrupt changes in the system), it is prone to amplifying noise present in the system, as the derivative component is sensitive to changes between adjacent samples. To reduce this effect, a low pass filter can be applied to the samples. As noise often tends to contain predominantly high frequency components, the low pass filter can significantly decrease their contribution, often without diminishing the beneficial, stabilizing effect of the derivative action. In some applications enabling this filter can improve the overall closed loop performance.

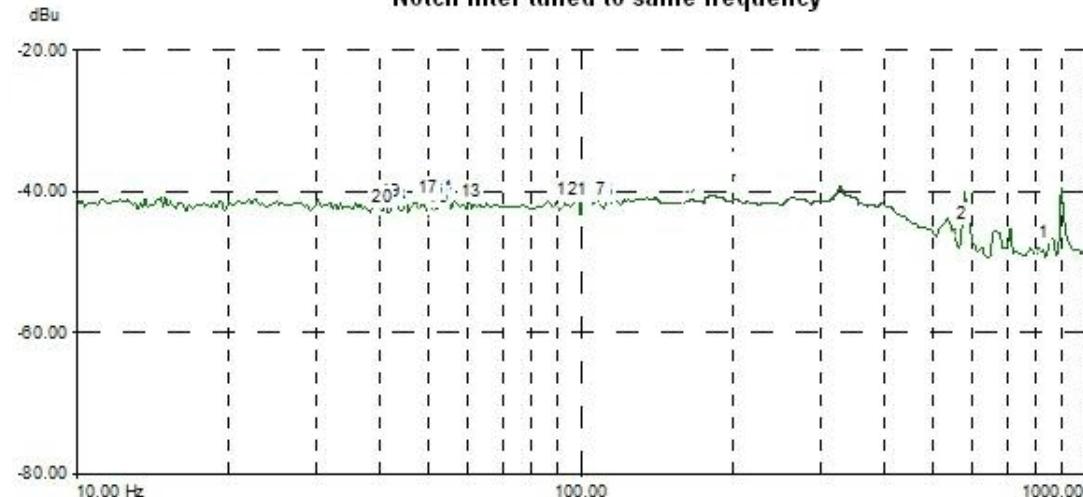
Notch Filter: Due to their construction, most actuators are prone to mechanical resonance at well-defined frequencies. The underlying reason is that all spring-mass systems are natural harmonic oscillators. This proneness to resonance can be a problem in closed loop systems because, coupled with the effect of the feedback, it can result in oscillations. With some actuators (for example the ASM003), the resonance peak is either weak enough or at a high enough frequency for the resonance not to be troublesome. With other actuators (for example the PGM100) the resonance peak is very significant and needs to be eliminated for operation in a stable closed loop system. The notch filter is an adjustable electronic anti-resonance that can be used to counteract the natural resonance of the mechanical system. As the resonance frequency of actuators varies with load in addition to the minor variations from product to product, the notch filter is tuneable so that its characteristics can be adjusted to match those of the actuator. In addition to its centre frequency, the bandwidth of the notch (or the equivalent quality factor, often referred to as the Q-factor) can also be adjusted. In simple terms, the Q factor is the centre frequency/bandwidth, and defines how wide the notch is, a higher Q factor defining a narrower ("higher quality") notch. Optimizing the Q factor requires some experimentation but in general a value of 5 to 10 is in most cases a good starting point.



Frequency response of actuator showing resonance at 290 Hz



Notch filter tuned to same frequency



The resonance is largely eliminated

SET:

Command structure (36 bytes)

6 byte header followed by 30 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
70	08	1E	00	d	s	SubMsgID	PIDConstsP				PIDConstsI		
14	15	16	17	18	19	20	21	22	23	24	25	26	27
<i>Data</i>													
PIDConstsI			PIDConstsD			PIDConstsDFc			FilterFc				
28	29	30	31	32	33	34	34						
<i>Data</i>													
FilterQ			NotchFilterOn			PIDDerivFilterOn							

Data Structure:

field	description	format
SubMsgID	The message ID (i.e. 0E,00) of the message containing the parameters	word
PIDConstsP	The proportional gain. This term provides the force used to drive the piezo to the demand position, reducing the positional error. Together with the Integral and Differential, these terms determine the system response characteristics and accept values in the range 0 to 10000.	float
PIDConstsI	The integral gain. This term provides the 'restoring' force that grows with time, ensuring that the positional error is eventually reduced to zero. Together with the Proportional and Differential, these terms determine the system response characteristics and accept values in the range 0 to 10000.	float
PIDConstsD	The differential gain. This term provides the 'damping' force proportional to the rate of change of the position. Together with the Proportional and Integral, these terms determine the system response characteristics and accept values in the range 0 to 10000.	float
PIDConstsDFc	The cut off frequency of the Derivative Low Pass Filter, in the range 0 to 10,000	float
FilterFc	The Notch Filter center frequency, in the range 0 to 10,000	float
FilterQ	The Notch Filter Q factor, in the range 0.1 to 100	float
NotchFilterOn	Turns the notch filter on (set to 1) and off (set to 2)	word
PIDDerivFilterOn	Turns the derivative filter on (set to 1) and off (set to 2)	word

Example: Set the PID parameters for TPA101 as follows:
 Proportional: 65.7
 Integral: 80.3
 Differential: 60.9
 Derivative LP Cutoff: 500 Hz
 Notch Filter Center Freq: 500Hz
 Q Factor: 5.0
 Notch Filter ON
 Derivative Filter ON

TX 70, 08, 1E, 00, D0, 01, 0E, 00, 66, 66, 83, 42, 9A, 99, A0, 42, 9A, 99, 73, 42, 00, 00, FA, 43, 00, 00, FA, 43, 00, 00, A0, 40, 01, 00, 01, 00

Header: 70, 08, 1E, 00, D0, 01: Quad_SetParams, 30 byte data packet, Generic USB Device.
SubMsgID: 0E, 00 SetQuadControlLoopParams2)
Prop: 66, 66, 83, 42: Set the proportional term to 65.7
Int: 9A, 99, A0, 42: Set the integral term to 80.3
Deriv: 9A, 99, 73, 42: Set the differential term to 60.9
Derivative LP Cut Off: 00, 00, FA, 43: Set the low pass cut off frequency to 500 Hz
Notch Filter Center: 00, 00, FA, 43: Set the notch filter center frequency to 500 Hz
Q Factor: 00, 00, A0, 40: Set the Q factor to 5.0
Notch Filter ON: 01, 00: Set the notch filter ON
Derivative Filter ON: 01, 00: Set the low pas filter ON.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
71	08	01	00	d	s

GET:

6 byte header followed by 30 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
72	08	1E	00	d	s	SubMsgID	PIDConstsP	PIDConstsI					
14	15	16	17	18	19	20	21	22	23	24	25	26	27
<i>Data</i>													
PIDConstsI	PIDConstsD				PIDConstsDFc				FilterFc				
28	29	30	31	32	33	34	35						
<i>Data</i>													
FilterQ	NotchFilterOn			PIDDerivFilterOn									

For structure see Set message above.

**MGMSG_QUAD_REQ_STATUSUPDATE
MGMSG_QUAD_GET_STATUSUPDATE**
**0x0880
0x0881**

Function: This function is used in applications where spontaneous status messages (i.e. messages sent using the START_STATUSUPDATES command) must be avoided.
 Status update messages contain information about the position and status of the controller (for example position and O/P voltage). The response will be sent by the controller each time the function is requested.

REQUEST:**Command structure (6 bytes):**

0	1	2	3	4	5
<i>header only</i>					
80	08	00	00	d	s

GET:

Status update messages are received with the following format:-

Response structure (20 bytes)

6 byte header followed by 14 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
81	08	0E	00	d	s	XDiff	YDiff	Sum	XPos				
<hr/>													
14	15	16	17	18	19								
<i>header only</i>													
YPos	Status Bits												

Data Structure:

field	description	format
XDiff	The present X axis difference (XDIFF) signal from the detector head. (-10V to 10V in the range -32768 to 32767)	short
YDiff	The present Y axis difference (YDIFF) signal from the detector head. (-10V to 10V in the range -32768 to 32767)	short
Sum	The present Sum signal value from the detector head (0V to 10V in the range 0 to 65535)	word
XPos	The X axis position output value -10 V to 10 V (i.e. -32768 to 32767)	short
YPos	The Y axis position output value -10 V to 10 V (i.e. -32768 to 32767)	short
StatusBits	The individual bits (flags) of the 32 bit integer value are described in the following table	dword

TQD001 or TPA101 controller Status Bits

Hex Value	Bit Number	Description
0x00000001	1	Position Monitoring Mode (1 - enabled, 0 - disabled).
0x00000002	2	Open Loop Operating Mode (1 - enabled, 0 – disabled)
0x00000004	3	Closed Loop Operating Mode (1 - enabled, 0 – disabled)
0x00000008	4 to 32	For Future Use

Example

RX 81, 08, 0E, 00, 81, 50, FF, 3F, FF, 3F, FF, 7F, 00, 00, 00, 00

Header: 81, 08, 0E, 00, 81, 50: QUAD_Get_StatusUpdate, 14 byte data packet, Generic USB Device.

XDiff..FF, 3F: 0x3FFF (16383 decimal), i.e. 5 V.

YDiff.. FF, 3F: 0x3FFF (16383 decimal), i.e. 5 V.

Sum: FF, FF: (65535 decimal), i.e. 10 V.

XPos: 00, 00 i.e. Zero

YPos: 00, 00 i.e. Zero

StatusBits: 04,00,00,00, i.e. 100 Closed Loop operating mode is enabled.

MGMSG_QUAD_ACK_STATUSUPDATE**0x0882**

Only Applicable If Using USB COMMS. Does not apply to RS-232 COMMS

Function: If using the USB port, this message called "server alive" must be sent by the server to the controller at least once a second or the controller will stop responding after ~50 commands.
 The controller keeps track of the number of "status update" type of messages (e.g. move complete message) and if it has sent 50 of these without the server sending a "server alive" message, it will stop sending any more "status update" messages.
 This function is used by the controller to check that the PC/Server has not crashed or switched off. There is no response.

Structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
82	08	00	00	d	s

TX 82, 08, 00, 00, 21, 01

MGMSG_QUAD_SET_EEPROMPARAMS**0x0875**

Function: Used to save the parameter settings for the TQD001 or TPA101 unit. These settings may have been altered either through the various method calls or through user interaction with the GUI (specifically, by clicking on the 'Settings' button found in the lower right hand corner of the user interface).

SET:

Command structure (8 bytes)

6 byte header followed by 2 byte data packet as follows:

0	1	2	3	4	5	6	7
<i>header</i>						<i>Data</i>	
75	08	02	00	d	s	SubMsgID	

Data Structure:

field	description	format
SubMsgID	For future use	word

Example:

TX 75, 08, 02, 00, D0, 01, 00, 00,

Header: E7, 07, 04, 00, D0, 01: Set_EEPROMPARAMS, 02 byte data packet, Generic USB Device.

TEC Control Messages

Introduction

The ActiveX functionality for the TEC Controller is accessed via the APTTEC Control Object, and provides the functionality required for a client application to control a number of T-Cube TEC Controller units.

Every hardware unit is factory programmed with a unique 8-digit serial number. This serial number is key to operation of the APT Server software and is used by the Server to enumerate and communicate independently with multiple hardware units connected on the same USB bus.

The serial number must be allocated using the HWSerialNum property, before an ActiveX control can communicate with the hardware unit. This can be done at design time or at run time.

The methods of the T-Cube TEC Controller can then be used to perform activities such as switching between display modes, reading the present TEC element temperature, and setting the LED display intensity.

For details on the use of the TEC T-Cube Controller, refer to the handbook supplied for the unit.

MGMSG_TEC_SET_PARAMS	0x0840
MGMSG_TEC_REQ_PARAMS	0x0841
MGMSG_TEC_GET_PARAMS	0x0842

Function: This generic parameter set/request message is used to control the functionality of the TEC001. The specific parameters to control are identified by the use of sub-messages. These sub messages comply with the general format of the APT message protocol but rather than having a unique first and second byte in the header carrying the “message identifier” information, the first and second byte remain the same.

Instead, for the SET and GET messages, the message identifier is carried in the first two bytes in the data packet part of the message, whilst for the REQ message it is encoded as the third byte of the header.

Likewise, when the TEC001 responds, the first two bytes of the response remain the same and the first two bytes of the data packet identify the sub-message to which the information returned in the remaining part of the data packet relates.

The following sub messages are applicable to the TEC001:

Set/Request/Get TEC_TempSetPoint (sub-message ID = 01)
Request/Get_TEC_Readings (sub-message ID = 03)
Set/Request/Get_IOSettings (sub-message ID = 05)
Request/Get_TEC_StatusBits (sub-message ID = 07)
Set/Request/Get_TEC_LoopParams (sub-message ID = 09)
Set/Request/Get_TEC_Disp_Settings (sub-message ID = 0B)

To explain the principle, the following examples describe these messages in more detail.

Set/Request/Get TEC_TempSetPoint (sub-message ID = 01)

Used to set the target temperature of the TEC element associated with the ActiveX control instance.

SET:

Command structure (10 bytes)

6 byte header followed by 4 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>					<i>Data</i>				
40	08	04	00	d	s	SubMsgID	TSet		

Data Structure:

field	description	format
SubMsgID	The message ID (i.e. 0100) of the message containing the parameters	word
TSet	Used to set the target temperature of the TEC element associated with the ActiveX control instance. Note. The units in which the temperature is returned are	word

	dependent upon the ‘Sensor Type’ selected (via the Settings panel or by calling the SetTempSetPoint submessage). If an IC type sensor is selected, the set point temperature is displayed in °C in the range -4500 to 14500 (45.0° to 145.0°). For a 20 kΩ.thermistor sensor, the set point is displayed in kΩ in the range 0 to 2000 (0 to 20 kΩ). For a 200 kΩ. sensor the range is 0 to20000 (0 to 200 kΩ.).	
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Example: Set the Temperature Setpoint for TEC001 as follows:

TSet: 65 °C

TX 40, 08, 04, 00, D0, 01, 01, 00, 64, 19

Header: 70, 08, 08, 00, D0, 01: TEC_SetTempSetPoint, 4 byte data packet, Generic USB Device.

SubMsgID: 01, 00 SetTempSetPoint

TSet: 64, 19 ,(6500): Set the set point to 65 °C

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
41	08	01	00	d	s

GET:

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9
<i>header</i>						<i>Data</i>			
42	08	04	00	d	s	SubMsgID	TSet		

For structure see Set message above.

Request/Get TEC_Readings (sub-message ID = 3)

This message returns the present readings of the TEC unit as follows:

ITec The TEC output current in mA. (0 to 2000mA in the range -0 to 2000)

TAct The actual temperature of the TEC element associated with the ActiveX control instance.

Note. The units in which the temperature is returned are dependent upon the ‘Sensor Type’ selected (via the Settings panel or by calling the SetTempSetPoint submessage). If an IC type sensor is selected, the set point temperature is displayed in °C in the range -4500 to 14500 (45.0° to 145.0°). For a 20 kΩ.thermistor sensor, the set point is displayed in kΩ in the range 0 to 2000 (0 to 20 kΩ). For a 200 kΩ sensor the range is 0 to20000 (0 to 200 kΩ).

TSet The temperature setpoint of the TEC element associated with the ActiveX control instance.

Note. The units in which the setpoint is returned are dependent upon the ‘Sensor Type’ selected (via the Settings panel or by calling the SetTempSetPoint submessage). If an IC type sensor is selected, the set point temperature is displayed in °C in the range -4500 to 14500 (45.0° to 145.0°). For a 20 kΩ thermistor sensor, the set point is displayed in kΩ in the range 0 to 2000 (0 to 20 kΩ). For a 200 kΩ sensor the range is 0 to20000 (0 to 200 kΩ).

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
41	08	03	00	d	s

TX 41, 08, 03, 00, 50, 01,

GET:

Command structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
42	08	08	00	d	s	SubMsgID	ITec	TAct	TSet				

Data Structure:

field	description	format
SubMsgID	The message ID (i.e. 0300) of the message containing the parameters	word
ITec	Returns the TEC output current in mA. (0 to 2000mA in the range -0 to 2000)	short
TAct	Returns the present temperature of the TEC element associated with the ActiveX control instance. Note. The units in which the temperature is returned are dependent upon the ‘Sensor Type’ selected (via the Settings panel or by calling the SetTempSetPoint submessage). If an IC type sensor is selected, the set point temperature is displayed in °C in the range -4500 to 14500 (45.0° to 145.0°). For a 20 kΩ.thermistor sensor, the set point is displayed in kΩ in the range 0 to 2000 (0 to 20 kΩ). For a 200 kΩ. sensor the range is 0 to20000 (0 to 200 kΩ.).	short

TSet	Returns the target temperature of the TEC element associated with the ActiveX control instance. Note. The units in which the temperature is returned are dependent upon the 'Sensor Type' selected (via the Settings panel or by calling the SetTempSetPoint submessage). If an IC type sensor is selected, the set point temperature is displayed in °C in the range -4500 to 14500 (45.0° to 145.0°). For a 20 kΩ.thermistor sensor, the set point is displayed in kΩ in the range 0 to 2000 (0 to 20 kΩ). For a 200 kΩ. sensor the range is 0 to20000 (0 to 200 kΩ.).	word
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Example: Get the Quad Detector T-Cube readings (T-Cube in open loop mode)

RX 42, 08, 08, 00, D0, 01, 03, 00, E8, 03, DC, 05, 40, 1F,

Header: 42, 08, 08, 00, D0, 01: TEC_GetPARAMS, 8 byte data packet, Generic USB Device.

MsgID: 03, 00: Get Quad Readings

ITec:.E8, 03: 0x03E8 (1000 decimal), i.e. 1 V.

TAct:. DC, 05: 0x05DC (1500 decimal), i.e. 1.5 V.

TSet: 40, 1F: 0x1F40 (8000 decimal), i.e. 80 °C.

Set/Request/Get IOSettings (sub-message ID = 5)

This message sets the type of TEC element associated with the ActiveX control instance. If an AD59x transducer is selected, the temperature is set and displayed in °C. If a 20kOhm or 200kOhm thermistor is selected, the temperature is set and displayed in kOhms.

SET:

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
40	08	06	00	d	s	SubMsgID	wSensor	slLim			

Data Structure:

field	description	format
SubMsgID	The message ID (i.e. 0500) of the message containing the parameters	word
wSensor	<p>This parameter contains constants that specify the type of TEC element controlled by the unit.</p> <p>0 SENSOR_IC_AD59X TEC element is a AD59x IC type transducer. 1 SENSOR_THERM20KOHM TEC element is a 20kOhm thermistor. 2 SENSOR_THERM200KOHM TEC element is a 200kOhm thermistor.</p>	word
slLim	This parameter returns the maximum current that the TEC controller associated with the ActiveX control instance can source into the TEC element. Values are set in the range 0 to 2000 (0 to 2000 mA).	short

Example: Set the TEC IO Settings as follows

RX 40, 08, 0C, 00, D0, 01, 05, 00, 01, 00, 01, 80

Header: 42, 08, 0C, 00, D0, 01: TEC_SetPARAMS, 6 byte data packet, Generic USB Device.

SubMsgID: 05, 00: Set TEC_IOSettings

wSensor:.01, 00: 0x0001 i.e. AD59x IC type transducer.

sILim:. E8, 03: 0x03E8 (10000 decimal), i.e. 1A.

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
41	08	05	00	d	s

TX 41, 08, 05, 00, 50, 01,

GET:

Command structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
42	08	06	00	d	s	SubMsgID	wSensor	sILim			

See Set message for structure

Request/Get TEC_Status Bits (sub-message ID = 7)

This sub command can be used to request the TEC001 status bits. The message only has a request/ get part.

REQUEST:**Command structure (6 bytes):**

0	1	2	3	4	5
<i>header only</i>					
41	08	07	00	d	s

TX 41, 08, 07, 00, 50, 01,

GET:

Status update messages are received with the following format:-

Response structure (12 bytes)

6 byte header followed by 6 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
42	08	06	00	d	s	SubMsgID	StatusBits				

Data Structure:

field	description	format
MsgID	The message ID (0700) of the message containing the parameters	word
StatusBits	The individual bits (flags) of the 32 bit integer value are described in the following table.	dword

TEC controller Status Bits

Hex Value	Bit Number	Description
0x00000001	1	TEC output enabled state (1 - enabled, 0 - disabled).
	2 to 4	For Future Use
0x00000010	5	Display mode (1 – TAct, 0 - else).
0x00000020	6	Display mode (1 – TSet, 0 - else).
0x00000040	7	Display mode (1 – TDelta, 0 - else).
0x00000080	8	Display mode (1 – ITec, 0 - else).
	9 to 30	For Future Use
0x40000000	31	Error
0x80000000	32	For Future Use

Example

RX 42, 08, 06, 00, 81, 50, E8, 03, DC, 05, 40, 1F, 11, 00, 00, 00

Header: 42, 08, 06, 00, 81, 50: TEC_SetParams, 6 byte data packet, Generic USB Device.

SubMsgID: 07, 00: Set TEC_StatusBits

StatusBits: 11,00,00,00, 0X00000011 (17 decimal) i.e. TEC is enabled with Tact display mode selected. No errors.

Set/Request/Get TEC_LoopParams (sub-message ID = 9)

Used to set the proportional, integration and differential feedback loop constants to the value specified in the PGain, IGain and DGain parameters respectively. They apply when the TEC unit is operated in closed loop mode, and demand signals are generated at the rear panel connectors by the feedback loops. These demand signals act to drive the heating element to the temperature required.

When operating in closed loop mode, the proportional, integral and differential (PID) constants can be used to fine tune the behaviour of the dual feedback loops to adjust the response of the temperature demand output current. The feedback loop parameters need to be adjusted to suit the different types of sensor that can be connected to the system.

SET:

Command structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
70	08	08	00	d	s	SubMsgID	PGain	IGain	DGain				

Data Structure:

field	description	format
SubMsgID	The message ID (i.e. 09,00) of the message containing the parameters	word
PGain	The proportional gain. This term provides the force used to drive the output to the demand set point, reducing the positional error. Together with the Integral and Differential, these terms determine the system response characteristics and accept values in the range 1 to 32767 (i.e. 1 to 100 in APT User GUI).	word
IGain	The integral gain. This term provides the 'restoring' force that grows with time, ensuring that the set point error is eventually reduced to zero. Together with the Proportional and Differential, these terms determine the system response characteristics and accept values in the range 0 to 32767 (i.e. 0 to 100 in APT User GUI).	word
DGain	The differential gain. This term provides the 'damping' force proportional to the rate of change of the temperature. Together with the Proportional and Integral, these terms determine the system response characteristics and accept values in the range 0 to 32767 (i.e. 0 to 100 in APT User GUI).	word

Example: Set the PID parameters for TEC001 as follows:

Proportional: 65

Integral: 80

Differential: 60

TX 40, 08, 08, 00, D0, 01, 09, 00, 41, 00, 50, 00, 3C, 00,

Header: 40, 08, 08, 00, D0, 01: TEC_SetParams, 8 byte data packet, Generic USB Device.

SubMsgID: 09, 00 Set_TECLoopParams)

PGain: 32, 53, (32767x65/100): Set the proportional term to 65

IGain: 65, 66, (32767x80/100): Set the integral term to 80

DGain: CC, 4C, (32767x60/100): Set the differential term to 60

REQUEST:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
41	08	09	00	d	s

GET:

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
72	08	08	00	d	s	SubMsgID	PGain	IGain	DGain				

For structure see Set message above.

Set/Request/Get TEC Display Settings (sub-message ID = 0B)

This message can be used to adjust or read the front panel LED display brightness and the display units.

SET:

Command structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
40	08	08	00	d	s	SubMsgID	DispIntensity	DispMode	Unused				

Data Structure:

field	description	format
MsgID	The message ID (i.e. 0B00) of the message containing the parameters	word
DispIntensity	The intensity is set as a value from 0 (Off) to 255 (brightest).	word
DispMode	The LED display window on the front of the unit can be set to display four different values; the actual temperature of the TEC element (TAct), the difference between the actual temperature and the set point (TDelta), the applied current (ITec), or the demanded set point value (TSet). 0 DISPMODE_TACT the display shows the actual temperature of the TEC element 1 DISPMODE_TSET the display shows the demanded set point value. 2 DISPMODE_DELTA the display shows the difference between the actual temperature (TAct) and the set point temperature (TSet).. 3 DISPMODE_ITEC the display shows the current (in Amps) sourced into the TEC element by the controller.	word
Reserved	N/A	word

Example: Set the display to max brightness and the display mode to TAct

TX 40, 08, 08, 00, D0, 01, 0B, 00, FF, 00, 01, 00, 00, 00

Header: 40, 08, 08, 00, D0, 01: TEC_SetParams, 08 byte data packet, Generic USB Device.

SubMsgID: 0B, 00: Set Display Settings

DispIntensity: FF, 00: Sets the display brightness to 255 (100%)

DispMode: 01, 00 Sets the display to show the actual temperature of the TEC element.

REQ:

Command structure (6 bytes):

0	1	2	3	4	5
<i>header only</i>					
41	08	0B	00	d	s

Example: TX 41, 08, 0B, 00, 50, 01

GET:

Command structure (14 bytes)

6 byte header followed by 8 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11	12	13
<i>header</i>						<i>Data</i>							
42	08	08	00	d	s	SubMsgID	DispIntensity	DispMode					Unused

See SET for data structure.

MGMSG_TEC_SET_EEPROMPARAMS**0x0850**

Function: Used to save the parameter settings for the TEC001 unit. These settings may have been altered either through the various method calls or through user interaction with the GUI (specifically, by clicking on the 'Settings' button found in the lower right hand corner of the user interface).

SET:

Command structure (8 bytes)

6 byte header followed by 2 byte data packet as follows:

0	1	2	3	4	5	6	7
<i>header</i>						<i>Data</i>	
50	08	02	00	d	s	SubMsgID	

Data Structure:

field	description	format
SubMsgID	For future use	word

Example:

TX 75, 08, 02, 00, D0, 01, 00, 00,

Header: E7, 07, 04, 00, D0, 01: Set_EEPROMPARAMS, 02 byte data packet, Generic USB Device.

MGMSG_TEC_REQ_STATUSUPDATE	0x0860
MGMSG_TEC_GET_STATUSUPDATE	0x0861

Function: This function is used in applications where spontaneous status messages (i.e. messages sent using the START_STATUSUPDATES command) must be avoided.
Status update messages contain information about the output current and actual temperature of the transducer. The response will be sent by the controller each time the function is requested.

REQUEST:**Command structure (6 bytes):**

0	1	2	3	4	5
<i>header only</i>					
60	08	00	00	d	s

GET:

Status update messages are received with the following format:-

Response structure (16 bytes)

6 byte header followed by 10 byte data packet as follows:

0	1	2	3	4	5	6	7	8	9	10	11
<i>header</i>						<i>Data</i>					
61	08	0E	00	d	s	ITec	TAct	TSet			
12	13	14	15	<i>header only</i>						Status Bits	

Data Structure:

field	description	format
ITec	The TEC output current in mA. (0 to 2000mA in the range -0 to 2000)	short
TAct	The actual temperature of the TEC element associated with the ActiveX control instance. Note. The units in which the temperature is returned are dependent upon the 'Sensor Type' selected (via the Settings panel or by calling the SetTempSetPoint submessage). If an IC type sensor is selected, the set point temperature is displayed in °C in the range -4500 to 14500 (45.0° to 145.0°). For a 20 kΩ.thermistor sensor, the set point is displayed in kΩ in the range 0 to 2000 (0 to 20 kΩ). For a 200 kΩ. sensor the range is 0 to20000 (0 to 200 k Ω.).	short
TSet	The temperature setpoint of the TEC element associated with the ActiveX control instance. Note. The units in which the setpoint is returned are dependent upon the 'Sensor Type' selected (via the Settings panel or by calling the SetTempSetPoint submessage). If an IC type sensor is selected, the set point temperature is displayed in °C in the range -4500 to 14500 (45.0° to 145.0°).	word

	For a 20 kΩ.thermistor sensor, the set point is displayed in kΩ in the range 0 to 2000 (0 to 20 kΩ). For a 200 kΩ. sensor the range is 0 to20000 (0 to 200 k Ω.).	
StatusBits	The individual bits (flags) of the 32 bit integer value are described in the following table	dword

TEC controller Status Bits

Hex Value	Bit Number	Description
0x00000001	1	TEC output enabled state (1 - enabled, 0 - disabled).
	2 to 4	For Future Use
0x00000010	5	Display mode (1 – TAct, 0 - else).
0x00000020	6	Display mode (1 – TSet, 0 - else).
0x00000040	7	Display mode (1 – TDelta, 0 - else).
0x00000080	8	Display mode (1 – ITec, 0 - else).
	9 to 30	For Future Use
0x40000000	31	Error
0x80000000	32	For Future Use

Example

RX 61, 08, 0A, 00, 81, 50, E8, 03, DC, 05, 40, 1F, 11, 00, 00, 00

Header: 61, 08, 0A, 00, 81, 50: TEC_Get_StatusUpdate, 10 byte data packet, Generic USB Device.

ITec::E8, 03: 0x03E8 (1000 decimal), i.e. 1 V.

TAct:: DC, 05: 0x05DC (1500 decimal), i.e. 1.5 V.

TSet:: 40, 1F: 0x1F40 (8000 decimal), i.e. 80 °C.

StatusBits:: 11,00,00,00, 0x00000011 (17 decimal) i.e. TEC is enabled with Tact display mode selected. No errors.

MMSG_TEC_ACK_STATUSUPDATE**0x0862****Only Applicable If Using USB COMMS. Does not apply to RS-232 COMMS**

Function: If using the USB port, this message called "server alive" must be sent by the server to the controller at least once a second or the controller will stop responding after ~50 commands.
 The controller keeps track of the number of "status update" type of messages (e.g.move complete message) and if it has sent 50 of these without the server sending a "server alive" message, it will stop sending any more "status update" messages.
 This function is used by the controller to check that the PC/Server has not crashed or switched off. There is no response.

Structure (6 bytes):

0	1	2	3	4	5
---	---	---	---	---	---

<i>header only</i>					
82	08	00	00	d	s

TX 62, 08, 00, 00, 21, 01

Message Cross Reference by Unit Part Number

This section lists the messages applicable to each controller part number

Messages Applicable to BPC20x Series

<u>MGMMSG_MOD_IDENTIFY</u>	0x0223	20
<u>MGMMSG_MOD_SET_CHANENABLESTATE</u>	0x0210	21
<u>MGMMSG_MOD_REQ_CHANENABLESTATE</u>	0x0211	21
<u>MGMMSG_MOD_GET_CHANENABLESTATE</u>	0x0212	21
<u>MGMMSG_HW_DISCONNECT</u>	0x0002	23
<u>MGMMSG_HW_RESPONSE</u>	0x0080	23
<u>MGMMSG_HW_RICHRESPONSE</u>	0x0081	24
<u>MGMMSG_HW_START_UPDATEMSGS</u>	0x0011	25
<u>MGMMSG_HW_STOP_UPDATEMSGS</u>	0x0012	25
<u>MGMMSG_HW_REQ_INFO</u>	0x0005	26
<u>MGMMSG_HW_GET_INFO</u>	0x0006	26
<u>MGMMSG_RACK_REQ_BAYUSED</u>	0x0060	28
<u>MGMMSG_RACK_GET_BAYUSED</u>	0x0061	28
<u>MGMMSG_RACK_REQ_STATUSBITS</u>	0x0226	30
<u>MGMMSG_RACK_GET_STATUSBITS</u>	0x0227	30
<u>MGMMSG_RACK_SET_DIGOUTPUTS</u>	0x0228	31
<u>MGMMSG_RACK_REQ_DIGOUTPUTS</u>	0x0229	31
<u>MGMMSG_RACK_GET_DIGOUTPUTS</u>	0x0230	31
<u>MGMMSG_PZ_SET_POSCONTROLMODE</u>	0x0640	120
<u>MGMMSG_PZ_REQ_POSCONTROLMODE</u>	0x0641	120
<u>MGMMSG_PZ_GET_POSCONTROLMODE</u>	0x0642	120
<u>MGMMSG_PZ_SET_OUTPUTVOLTS</u>	0x0643	122
<u>MGMMSG_PZ_REQ_OUTPUTVOLTS</u>	0x0644	122
<u>MGMMSG_PZ_GET_OUTPUTVOLTS</u>	0x0645	122
<u>MGMMSG_PZ_SET_OUTPUTPOS</u>	0x0646	123
<u>MGMMSG_PZ_REQ_OUTPUTPOS</u>	0x0647	123
<u>MGMMSG_PZ_GET_OUTPUTPOS</u>	0x0648	123
<u>MGMMSG_PZ_SET_INPUTVOLTSSRC</u>	0x0652	124
<u>MGMMSG_PZ_REQ_INPUTVOLTSSRC</u>	0x0653	124
<u>MGMMSG_PZ_GET_INPUTVOLTSSRC</u>	0x0654	124
<u>MGMMSG_PZ_SET_PICONSTS</u>	0x0655	126
<u>MGMMSG_PZ_REQ_PICONSTS</u>	0x0656	126
<u>MGMMSG_PZ_GET_PICONSTS</u>	0x0657	126
<u>MGMMSG_PZ_REQ_PZSTATUSBITS</u>	0x065B	127
<u>MGMMSG_PZ_GET_PZSTATUSBITS</u>	0x065C	127
<u>MGMMSG_PZ_GET_PZSTATUSUPDATE</u>	0x0661	129
<u>MGMMSG_PZ_SET_OUTPUTLUT</u>	0x0700	132
<u>MGMMSG_PZ_REQ_OUTPUTLUT</u>	0x0701	132
<u>MGMMSG_PZ_GET_OUTPUTLUT</u>	0x0702	132
<u>MGMMSG_PZ_SET_OUTPUTLUTPARAMS</u>	0x0703	134
<u>MGMMSG_PZ_REQ_OUTPUTLUTPARAMS</u>	0x0704	134
<u>MGMMSG_PZ_GET_OUTPUTLUTPARAMS</u>	0x0705	134
<u>MGMMSG_PZ_START_LUTOUTPUT</u>	0x0706	138
<u>MGMMSG_PZ_STOP_LUTOUTPUT</u>	0x0707	138
<u>MGMMSG_PZ_SET_ZERO</u>	0x0658	143
<u>MGMMSG_PZ_REQ_MAXTRAVEL</u>	0x0650	144
<u>MGMMSG_PZ_GET_MAXTRAVEL</u>	0x0651	144
<u>MGMMSG_PZ_SET_OUTPUTMAXVOLTS</u>	0x0680	147
<u>MGMMSG_PZ_REQ_OUTPUTMAXVOLTS</u>	0x0681	147
<u>MGMMSG_PZ_GET_OUTPUTMAXVOLTS</u>	0x0682	147

Messages Applicable to BPC30x Series

<u>MGMMSG_MOD_IDENTIFY</u>	0x0223	20
<u>MGMMSG_MOD_SET_CHANENABLESTATE</u>	0x0210	21
<u>MGMMSG_MOD_REQ_CHANENABLESTATE</u>	0x0211	21
<u>MGMMSG_MOD_GET_CHANENABLESTATE</u>	0x0212	21
<u>MGMMSG_HW_DISCONNECT</u>	0x0002	23
<u>MGMMSG_HW_RESPONSE</u>	0x0080	23
<u>MGMMSG_HW_RICHRESPONSE</u>	0x0081	24
<u>MGMMSG_HW_START_UPDATEMSGS</u>	0x0011	25
<u>MGMMSG_HW_STOP_UPDATEMSGS</u>	0x0012	25
<u>MGMMSG_HW_REQ_INFO</u>	0x0005	26
<u>MGMMSG_HW_GET_INFO</u>	0x0006	26
<u>MGMMSG_RACK_REQ_BAYUSED</u>	0x0060	28
<u>MGMMSG_RACK_GET_BAYUSED</u>	0x0061	28
<u>MGMMSG_RACK_REQ_STATUSBITS</u>	0x0226	30
<u>MGMMSG_RACK_GET_STATUSBITS</u>	0x0227	30
<u>MGMMSG_RACK_SET_DIGOUTPUTS</u>	0x0228	31
<u>MGMMSG_RACK_REQ_DIGOUTPUTS</u>	0x0229	31
<u>MGMMSG_RACK_GET_DIGOUTPUTS</u>	0x0230	31
<u>MGMMSG_PZ_SET_POSCONTROLMODE</u>	0x0640	120
<u>MGMMSG_PZ_REQ_POSCONTROLMODE</u>	0x0641	120
<u>MGMMSG_PZ_GET_POSCONTROLMODE</u>	0x0642	120
<u>MGMMSG_PZ_SET_OUTPUTVOLTS</u>	0x0643	122
<u>MGMMSG_PZ_REQ_OUTPUTVOLTS</u>	0x0644	122
<u>MGMMSG_PZ_GET_OUTPUTVOLTS</u>	0x0645	122
<u>MGMMSG_PZ_SET_OUTPUTPOS</u>	0x0646	123
<u>MGMMSG_PZ_REQ_OUTPUTPOS</u>	0x0647	123
<u>MGMMSG_PZ_GET_OUTPUTPOS</u>	0x0648	123
<u>MGMMSG_PZ_SET_INPUTVOLTSSRC</u>	0x0652	124
<u>MGMMSG_PZ_REQ_INPUTVOLTSSRC</u>	0x0653	124
<u>MGMMSG_PZ_GET_INPUTVOLTSSRC</u>	0x0654	124
<u>MGMMSG_PZ_SET_PICONSTS</u>	0x0655	126
<u>MGMMSG_PZ_REQ_PICONSTS</u>	0x0656	126
<u>MGMMSG_PZ_GET_PICONSTS</u>	0x0657	126
<u>MGMMSG_PZ_REQ_PZSTATUSBITS</u>	0x065B	127
<u>MGMMSG_PZ_GET_PZSTATUSBITS</u>	0x065C	127
<u>MGMMSG_PZ_GET_PZSTATUSUPDATE</u>	0x0661	129
<u>MGMMSG_PZ_ACK_PZSTATUSUPDATE</u>	0x0662	131
<u>MGMMSG_PZ_SET_OUTPUTLUT</u>	0x0700	132
<u>MGMMSG_PZ_REQ_OUTPUTLUT</u>	0x0701	132
<u>MGMMSG_PZ_GET_OUTPUTLUT</u>	0x0702	132
<u>MGMMSG_PZ_SET_OUTPUTLUTPARAMS</u>	0x0703	134
<u>MGMMSG_PZ_REQ_OUTPUTLUTPARAMS</u>	0x0704	134
<u>MGMMSG_PZ_GET_OUTPUTLUTPARAMS</u>	0x0705	134
<u>MGMMSG_PZ_START_LUTOOUTPUT</u>	0x0706	138
<u>MGMMSG_PZ_STOP_LUTOOUTPUT</u>	0x0707	138
<u>MGMMSG_PZ_SET_ZERO</u>	0x0658	143
<u>MGMMSG_PZ_SET_OUTPUTMAXVOLTS</u>	0x0680	147
<u>MGMMSG_PZ_REQ_OUTPUTMAXVOLTS</u>	0x0681	147
<u>MGMMSG_PZ_GET_OUTPUTMAXVOLTS</u>	0x0682	147
<u>MGMMSG_PZ_SET_SLEWRATES</u>	0x0683	149
<u>MGMMSG_PZ_REQ_SLEWRATES</u>	0x0684	149
<u>MGMMSG_PZ_GET_SLEWRATES</u>	0x0685	149
<u>MGMMSG_MOT_SET_PZSTAGEPARAMDEFAULTS</u>	0x0686	151

Messages Applicable to TPZ001

<u>MGMMSG_MOD_IDENTIFY</u>	0x0223	20
<u>MGMMSG_MOD_SET_CHANENABLESTATE</u>	0x0210	21
<u>MGMMSG_MOD_REQ_CHANENABLESTATE</u>	0x0211	21
<u>MGMMSG_MOD_GET_CHANENABLESTATE</u>	0x0212	21
<u>MGMMSG_HW_DISCONNECT</u>	0x0002	23
<u>MGMMSG_HW_RESPONSE</u>	0x0080	23
<u>MGMMSG_HW_RICHRESPONSE</u>	0x0081	24
<u>MGMMSG_HW_START_UPDATEMSGS</u>	0x0011	25
<u>MGMMSG_HW_STOP_UPDATEMSGS</u>	0x0012	25
<u>MGMMSG_HW_REQ_INFO</u>	0x0005	26
<u>MGMMSG_HW_GET_INFO</u>	0x0006	26
<u>MGMMSG_PZ_SET_POSCONTROLMODE</u>	0x0640	120
<u>MGMMSG_PZ_REQ_POSCONTROLMODE</u>	0x0641	120
<u>MGMMSG_PZ_GET_POSCONTROLMODE</u>	0x0642	120
<u>MGMMSG_PZ_SET_OUTPUTVOLTS</u>	0x0643	122
<u>MGMMSG_PZ_REQ_OUTPUTVOLTS</u>	0x0644	122
<u>MGMMSG_PZ_GET_OUTPUTVOLTS</u>	0x0645	122
<u>MGMMSG_PZ_SET_OUTPUTPOS</u>	0x0646	123
<u>MGMMSG_PZ_REQ_OUTPUTPOS</u>	0x0647	123
<u>MGMMSG_PZ_GET_OUTPUTPOS</u>	0x0648	123
<u>MGMMSG_PZ_SET_INPUTVOLTSSRC</u>	0x0652	124
<u>MGMMSG_PZ_REQ_INPUTVOLTSSRC</u>	0x0653	124
<u>MGMMSG_PZ_GET_INPUTVOLTSSRC</u>	0x0654	124
<u>MGMMSG_PZ_SET_PICONSTS</u>	0x0655	126
<u>MGMMSG_PZ_REQ_PICONSTS</u>	0x0656	126
<u>MGMMSG_PZ_GET_PICONSTS</u>	0x0657	126
<u>MGMMSG_PZ_GET_PZSTATUSUPDATE</u>	0x0661	129
<u>MGMMSG_PZ_SET_OUTPUTLUT</u>	0x0700	132
<u>MGMMSG_PZ_SET_OUTPUTLUTPARAMS</u>	0x0703	134
<u>MGMMSG_PZ_REQ_OUTPUTLUTPARAMS</u>	0x0704	134
<u>MGMMSG_PZ_GET_OUTPUTLUTPARAMS</u>	0x0705	134
<u>MGMMSG_PZ_START_LUTOUTPUT</u>	0x0706	138
<u>MGMMSG_PZ_STOP_LUTOUTPUT</u>	0x0707	138
<u>MGMMSG_PZ_SET_EEPROMPARAMS:</u>	0x07D0	139
<u>MGMMSG_PZ_SET_TPZ_DISPSETTINGS:</u>	0x07D1	140
<u>MGMMSG_PZ_REQ_TPZ_DISPSETTINGS:</u>	0x07D2	140
<u>MGMMSG_PZ_GET_TPZ_DISPSETTINGS;</u>	0x07D3	140
<u>MGMMSG_PZ_SET_TPZ_IOSETTINGS:</u>	0x07D4	141
<u>MGMMSG_PZ_REQ_TPZ_IOSETTINGS:</u>	0x07D5	141
<u>MGMMSG_PZ_GET_TPZ_IOSETTINGS;</u>	0x07D6	141

Messages Applicable to TSG001

<u>MGMMSG_MOD_IDENTIFY</u>	0x0223	20
<u>MGMMSG_MOD_SET_CHANENABLESTATE</u>	0x0210	21
<u>MGMMSG_MOD_REQ_CHANENABLESTATE</u>	0x0211	21
<u>MGMMSG_MOD_GET_CHANENABLESTATE</u>	0x0212	21
<u>MGMMSG_HW_DISCONNECT</u>	0x0002	23
<u>MGMMSG_HW_RESPONSE</u>	0x0080	23
<u>MGMMSG_HW_RICHRESPONSE</u>	0x0081	24
<u>MGMMSG_HW_START_UPDATEMSGS</u>	0x0011	25
<u>MGMMSG_HW_STOP_UPDATEMSGS</u>	0x0012	25
<u>MGMMSG_HW_REQ_INFO</u>	0x0005	26
<u>MGMMSG_HW_GET_INFO</u>	0x0006	26
<u>MGMMSG_HUB_REQ_BAYUSED</u>	0x0065	29
<u>MGMMSG_HUB_GET_BAYUSED</u>	0x0066	29
<u>MGMMSG_PZ_GET_PZSTATUSUPDATE</u>	0x0661	129
<u>MGMMSG_PZ_ACK_PZSTATUSUPDATE</u>	0x0662	131
<u>MGMMSG_PZ_SET_EEPROMPARAMS:</u>	0x07D0	139
<u>MGMMSG_PZ_SET_TPZ_DISPSETTINGS:</u>	0x07D1	140
<u>MGMMSG_PZ_REQ_TPZ_DISPSETTINGS:</u>	0x07D2	140
<u>MGMMSG_PZ_GET_TPZ_DISPSETTINGS;</u>	0x07D3	140
<u>MGMMSG_PZ_SET_ZERO</u>	0x0658	143
<u>MGMMSG_PZ_REQ_MAXTRAVEL</u>	0x0650	144
<u>MGMMSG_PZ_GET_MAXTRAVEL</u>	0x0651	144
<u>MGMMSG_PZ_SET_TSG_IOSETTINGS</u>	0x07DA	153
<u>MGMMSG_PZ_REQ_TSG_IOSETTINGS</u>	0x07DB	153
<u>MGMMSG_PZ_GET_TSG_IOSETTINGS</u>	0x07DC	153
<u>MGMMSG_PZ_REQ_TSG_READING</u>	0x07DD	155
<u>MGMMSG_PZ_GET_TSG_READING</u>	0x07DE	155

Messages Applicable to MPZ601

<u>MGMMSG_MOD_IDENTIFY</u>	0x0223	20
<u>MGMMSG_MOD_SET_CHANENABLESTATE</u>	0x0210	21
<u>MGMMSG_MOD_REQ_CHANENABLESTATE</u>	0x0211	21
<u>MGMMSG_MOD_GET_CHANENABLESTATE</u>	0x0212	21
<u>MGMMSG_HW_RESPONSE</u>	0x0080	23
<u>MGMMSG_HW_RICHRESPONSE</u>	0x0081	24
<u>MGMMSG_HW_START_UPDATEMSGS</u>	0x0011	25
<u>MGMMSG_HW_STOP_UPDATEMSGS</u>	0x0012	25
<u>MGMMSG_HW_REQ_INFO</u>	0x0005	26
<u>MGMMSG_HW_GET_INFO</u>	0x0006	26
<u>MGMMSG_RACK_REQ_BAYUSED</u>	0x0060	28
<u>MGMMSG_RACK_GET_BAYUSED</u>	0x0061	28
<u>MGMMSG_RACK_SET_DIGOUTPUTS</u>	0x0228	31
<u>MGMMSG_RACK_REQ_DIGOUTPUTS</u>	0x0229	31
<u>MGMMSG_RACK_GET_DIGOUTPUTS</u>	0x0230	31
<u>MGMMSG_PZ_SET_POSCONTROLMODE</u>	0x0640	120
<u>MGMMSG_PZ_REQ_POSCONTROLMODE</u>	0x0641	120
<u>MGMMSG_PZ_GET_POSCONTROLMODE</u>	0x0642	120
<u>MGMMSG_PZ_SET_OUTPUTVOLTS</u>	0x0643	122
<u>MGMMSG_PZ_REQ_OUTPUTVOLTS</u>	0x0644	122
<u>MGMMSG_PZ_GET_OUTPUTVOLTS</u>	0x0645	122
<u>MGMMSG_PZ_SET_OUTPUTPOS</u>	0x0646	123
<u>MGMMSG_PZ_REQ_OUTPUTPOS</u>	0x0647	123
<u>MGMMSG_PZ_GET_OUTPUTPOS</u>	0x0648	123
<u>MGMMSG_PZ_SET_INPUTVOLTSSRC</u>	0x0652	124
<u>MGMMSG_PZ_REQ_INPUTVOLTSSRC</u>	0x0653	124
<u>MGMMSG_PZ_GET_INPUTVOLTSSRC</u>	0x0654	124
<u>MGMMSG_PZ_SET_PICONSTS</u>	0x0655	126
<u>MGMMSG_PZ_REQ_PICONSTS</u>	0x0656	126
<u>MGMMSG_PZ_GET_PICONSTS</u>	0x0657	126
<u>MGMMSG_PZ_REQ_PZSTATUSBITS</u>	0x065B	127
<u>MGMMSG_PZ_GET_PZSTATUSBITS</u>	0x065C	127
<u>MGMMSG_PZ_GET_PZSTATUSUPDATE</u>	0x0661	129
<u>MGMMSG_PZ_ACK_PZSTATUSUPDATE</u>	0x0662	131
<u>MGMMSG_PZ_SET_OUTPUTLUT</u>	0x0700	132
<u>MGMMSG_PZ_REQ_OUTPUTLUT</u>	0x0701	132
<u>MGMMSG_PZ_GET_OUTPUTLUT</u>	0x0702	132
<u>MGMMSG_PZ_SET_OUTPUTLUTPARAMS</u>	0x0703	134
<u>MGMMSG_PZ_REQ_OUTPUTLUTPARAMS</u>	0x0704	134
<u>MGMMSG_PZ_GET_OUTPUTLUTPARAMS</u>	0x0705	134
<u>MGMMSG_PZ_START_LUTOOUTPUT</u>	0x0706	138
<u>MGMMSG_PZ_STOP_LUTOOUTPUT</u>	0x0707	138
<u>MGMMSG_PZ_SET_ZERO</u>	0x0658	143
<u>MGMMSG_PZ_REQ_MAXTRAVEL</u>	0x0650	144
<u>MGMMSG_PZ_GET_MAXTRAVEL</u>	0x0651	144
<u>MGMMSG_PZ_SET_IOSETTINGS:</u>	0x0670	145
<u>MGMMSG_PZ_REQ_IOSETTINGS:</u>	0x0671	145
<u>MGMMSG_PZ_GET_IOSETTINGS:</u>	0x0672	145
<u>MGMMSG_PZ_SET_LUTVALUETYPE:</u>	0x0708	152

Messages Applicable to TDC001

MGMSG_MOD_IDENTIFY	0x0223	20
MGMSG_MOD_SET_CHANENABLESTATE	0x0210	21
MGMSG_MOD_REQ_CHANENABLESTATE	0x0211	21
MGMSG_MOD_GET_CHANENABLESTATE	0x0212	21
MGMSG_HW_DISCONNECT	0x0002	23
MGMSG_HW_RESPONSE	0x0080	23
MGMSG_HW_RICHRESPONSE	0x0081	24
MGMSG_HW_START_UPDATEMSGS	0x0011	25
MGMSG_HW_STOP_UPDATEMSGS	0x0012	25
MGMSG_HW_REQ_INFO	0x0005	26
MGMSG_HW_GET_INFO	0x0006	26
MGMSG_HUB_REQ_BAYUSED	0x0065	29
MGMSG_HUB_GET_BAYUSED	0x0066	29
MGMSG_MOT_SET_POSCOUNTER	0x0410	36
MGMSG_MOT_REQ_POSCOUNTER	0x0411	36
MGMSG_MOT_GET_POSCOUNTER	0x0412	36
MGMSG_MOT_SET_ENCCOUNTER	0x0409	37
MGMSG_MOT_REQ_ENCCOUNTER	0x040A	37
MGMSG_MOT_GET_ENCCOUNTER	0x040B	37
MGMSG_MOT_SET_VELPARAMS	0x0413	39
MGMSG_MOT_REQ_VELPARAMS	0x0414	39
MGMSG_MOT_GET_VELPARAMS	0x0415	39
MGMSG_MOT_SET_JOGPARAMS	0x0416	41
MGMSG_MOT_REQ_JOGPARAMS	0x0417	41
MGMSG_MOT_GET_JOGPARAMS	0x0418	41
MGMSG_MOT_SET_GENMOVEPARAMS	0x043A	46
MGMSG_MOT_REQ_GENMOVEPARAMS	0x043B	46
MGMSG_MOT_GET_GENMOVEPARAMS	0x043C	46
MGMSG_MOT_SET_MOVERELPARAMS	0x0445	47
MGMSG_MOT_REQ_MOVERELPARAMS	0x0446	47
MGMSG_MOT_GET_MOVERELPARAMS	0x0447	47
MGMSG_MOT_SET_MOVEABSPARAMS	0x0450	48
MGMSG_MOT_REQ_MOVEABSPARAMS	0x0451	48
MGMSG_MOT_GET_MOVEABSPARAMS	0x0452	48
MGMSG_MOT_SET_HOMEPARAMS	0x0440	49
MGMSG_MOT_REQ_HOMEPARAMS	0x0441	49
MGMSG_MOT_GET_HOMEPARAMS	0x0442	49
MGMSG_MOT_SET_LIMSWITCHPARAMS	0x0423	51
MGMSG_MOT_REQ_LIMSWITCHPARAMS	0x0424	51
MGMSG_MOT_GET_LIMSWITCHPARAMS	0x0425	51
MGMSG_MOT_MOVE_HOME	0x0443	53
MGMSG_MOT_MOVE_HOMED	0x0444	53
MGMSG_MOT_MOVE_RELATIVE	0x0448	54
MGMSG_MOT_MOVE_COMPLETED	0x0464	56
MGMSG_MOT_MOVE_ABSOLUTE	0x0453	57
MGMSG_MOT_MOVE_JOG	0x046A	59
MGMSG_MOT_MOVE_VELOCITY	0x0457	60
MGMSG_MOT_MOVE_STOP	0x0465	61
MGMSG_MOT_MOVE_STOPPED	0x0466	62
MGMSG_MOT_SET_DCPIPPARAMS	0x04A0	66
MGMSG_MOT_REQ_DCPIPPARAMS	0x04A1	66
MGMSG_MOT_GET_DCPIPPARAMS	0x04A2	66
MGMSG_MOT_SET_AVMODES	0x04B3	68
MGMSG_MOT_REQ_AVMODES	0x04B4	68
MGMSG_MOT_GET_AVMODES	0x04B5	68

<u>MGMMSG_MOT_SET_POTPARAMS</u>	0x04B0	70
<u>MGMMSG_MOT_REQ_POTPARAMS</u>	0x04B1	70
<u>MGMMSG_MOT_GET_POTPARAMS</u>	0x04B2	70
<u>MGMMSG_MOT_SET_BUTTONPARAMS</u>	0x04B6	73
<u>MGMMSG_MOT_REQ_BUTTONPARAMS</u>	0x04B7	73
<u>MGMMSG_MOT_GET_BUTTONPARAMS</u>	0x04B8	73
<u>MGMMSG_MOT_SET_EEPROMPARAMS</u>	0x04B9	75
<u>MGMMSG_MOT_REQ_DCSTATUSUPDATE</u>	0x0490	98
<u>MGMMSG_MOT_GET_DCSTATUSUPDATE</u>	0x0491	97
<u>MGMMSG_MOT_ACK_DCSTATUSUPDATE</u>	0x0492	98
<u>MGMMSG_MOT_REQ_STATUSBITS</u>	0x0429	99
<u>MGMMSG_MOT_GET_STATUSBITS</u>	0x042A	99
<u>MGMMSG_MOT_SUSPEND_ENDOFMOVEMSGS</u>	0x046B	100
<u>MGMMSG_MOT_RESUME_ENDOFMOVEMSGS</u>	0x046C	101

Messages Applicable to TSC001

MGMSG_MOD_IDENTIFY	0x0223	20
MGMSG_MOD_SET_CHANENABLESTATE	0x0210	21
MGMSG_MOD_REQ_CHANENABLESTATE	0x0211	21
MGMSG_MOD_GET_CHANENABLESTATE	0x0212	21
MGMSG_HW_DISCONNECT	0x0002	23
MGMSG_HW_RESPONSE	0x0080	23
MGMSG_HW_RICHRESPONSE	0x0081	24
MGMSG_HW_START_UPDATEMSGS	0x0011	25
MGMSG_HW_STOP_UPDATEMSGS	0x0012	25
MGMSG_HW_REQ_INFO	0x0005	26
MGMSG_HW_GET_INFO	0x0006	26
MGMSG_HUB_REQ_BAYUSED	0x0065	29
MGMSG_HUB_GET_BAYUSED	0x0066	29
MGMSG_MOT_MOVE_COMPLETED	0x0464	56
MGMSG_MOT_MOVE_ABSOLUTE	0x0453	57
MGMSG_MOT_MOVE_STOP	0x0465	61
MGMSG_MOT_SET_AVMODES	0x04B3	68
MGMSG_MOT_REQ_AVMODES	0x04B4	68
MGMSG_MOT_GET_AVMODES	0x04B5	68
MGMSG_MOT_SET_BUTTONPARAMS	0x04B6	73
MGMSG_MOT_REQ_BUTTONPARAMS	0x04B7	73
MGMSG_MOT_GET_BUTTONPARAMS	0x04B8	73
MGMSG_MOT_SET_EEPROMPARAMS:	0x04B9	75
MGMSG_MOT_GET_STATUSUPDATE	0x0481	94
MGMSG_MOT_SET_SOL_OPERATINGMODE	0x04C0	111
MGMSG_MOT_REQ_SOL_OPERATINGMODE	0x04C1	111
MGMSG_MOT_GET_SOL_OPERATINGMODE	0x04C2	111
MGMSG_MOT_SET_SOL_CYCLEPARAMS	0x04C3	113
MGMSG_MOT_REQ_SOL_CYCLEPARAMS	0x04C4	113
MGMSG_MOT_GET_SOL_CYCLEPARAMS	0x04C5	113
MGMSG_MOT_SET_SOL_INTERLOCKMODE	0x04C6	115
MGMSG_MOT_REQ_SOL_INTERLOCKMODE	0x04C7	115
MGMSG_MOT_GET_SOL_INTERLOCKMODE	0x04C8	115
MGMSG_MOT_SET_SOL_STATE	0x04CB	117
MGMSG_MOT_REQ_SOL_STATE	0x04CC	117
MGMSG_MOT_GET_SOL_STATE	0x04CD	117

Messages Applicable to TST001 and TST101

<u>MGMMSG_MOD_IDENTIFY</u>	0x0223	20
<u>MGMMSG_MOD_SET_CHANENABLESTATE</u>	0x0210	21
<u>MGMMSG_MOD_REQ_CHANENABLESTATE</u>	0x0211	21
<u>MGMMSG_MOD_GET_CHANENABLESTATE</u>	0x0212	21
<u>MGMMSG_HW_START_UPDATEMSGS</u>	0x0011	25
<u>MGMMSG_HW_STOP_UPDATEMSGS</u>	0x0012	25
<u>MGMMSG_HW_REQ_INFO</u>	0x0005	26
<u>MGMMSG_HW_GET_INFO</u>	0x0006	26
<u>MGMMSG_MOT_SET_POSCOUNTER</u>	0x0410	36
<u>MGMMSG_MOT_REQ_POSCOUNTER</u>	0x0411	36
<u>MGMMSG_MOT_GET_POSCOUNTER</u>	0x0412	36
<u>MGMMSG_MOT_SET_ENCCOUNTER</u>	0x0409	37
<u>MGMMSG_MOT_REQ_ENCCOUNTER</u>	0x040A	37
<u>MGMMSG_MOT_GET_ENCCOUNTER</u>	0x040B	37
<u>MGMMSG_MOT_SET_VELPARAMS</u>	0x0413	39
<u>MGMMSG_MOT_REQ_VELPARAMS</u>	0x0414	39
<u>MGMMSG_MOT_GET_VELPARAMS</u>	0x0415	39
<u>MGMMSG_MOT_SET_JOGPARAMS</u>	0x0416	41
<u>MGMMSG_MOT_REQ_JOGPARAMS</u>	0x0417	41
<u>MGMMSG_MOT_GET_JOGPARAMS</u>	0x0418	41
<u>MGMMSG_MOT_SET_POWERPARAMS</u>	0x0426	43
<u>MGMMSG_MOT_REQ_POWERPARAMS</u>	0x0427	44
<u>MGMMSG_MOT_GET_POWERPARAMS</u>	0x0428	44
<u>MGMMSG_MOT_SET_GENMOVEPARAMS</u>	0x043A	46
<u>MGMMSG_MOT_REQ_GENMOVEPARAMS</u>	0x043B	46
<u>MGMMSG_MOT_GET_GENMOVEPARAMS</u>	0x043C	46
<u>MGMMSG_MOT_SET_MOVERELPARAMS</u>	0x0445	47
<u>MGMMSG_MOT_REQ_MOVERELPARAMS</u>	0x0446	47
<u>MGMMSG_MOT_GET_MOVERELPARAMS</u>	0x0447	47
<u>MGMMSG_MOT_SET_MOVEABSPARAMS</u>	0x0450	48
<u>MGMMSG_MOT_REQ_MOVEABSPARAMS</u>	0x0451	48
<u>MGMMSG_MOT_GET_MOVEABSPARAMS</u>	0x0452	48
<u>MGMMSG_MOT_SET_HOMEPARAMS</u>	0x0440	49
<u>MGMMSG_MOT_REQ_HOMEPARAMS</u>	0x0441	49
<u>MGMMSG_MOT_GET_HOMEPARAMS</u>	0x0442	49
<u>MGMMSG_MOT_SET_LIMSWITCHPARAMS</u>	0x0423	51
<u>MGMMSG_MOT_REQ_LIMSWITCHPARAMS</u>	0x0424	51
<u>MGMMSG_MOT_GET_LIMSWITCHPARAMS</u>	0x0425	51
<u>MGMMSG_MOT_MOVE_HOME</u>	0x0443	53
<u>MGMMSG_MOT_MOVE_HOMED</u>	0x0444	53
<u>MGMMSG_MOT_MOVE_RELATIVE</u>	0x0448	54
<u>MGMMSG_MOT_MOVE_COMPLETED</u>	0x0464	56
<u>MGMMSG_MOT_MOVE_ABSOLUTE</u>	0x0453	57
<u>MGMMSG_MOT_MOVE_JOG</u>	0x046A	59
<u>MGMMSG_MOT_MOVE_VELOCITY</u>	0x0457	60
<u>MGMMSG_MOT_MOVE_STOP</u>	0x0465	61
<u>MGMMSG_MOT_MOVE_STOPPED</u>	0x0466	62
<u>MGMMSG_MOT_SET_AVMODES</u>	0x04B3	68
<u>MGMMSG_MOT_REQ_AVMODES</u>	0x04B4	68
<u>MGMMSG_MOT_GET_AVMODES</u>	0x04B5	68
<u>MGMMSG_MOT_SET_POTPARAMS</u>	0x04B0	70
<u>MGMMSG_MOT_REQ_POTPARAMS</u>	0x04B1	70
<u>MGMMSG_MOT_GET_POTPARAMS</u>	0x04B2	70
<u>MGMMSG_MOT_SET_BUTTONPARAMS</u>	0x04B6	73
<u>MGMMSG_MOT_REQ_BUTTONPARAMS</u>	0x04B7	73

<u>MGMMSG MOT GET BUTTONPARAMS</u>	0x04B8	73
<u>MGMMSG MOT SET EEPROMPARAMS</u>	0x04B9	75
<u>MGMMSG MOT REQ STATUSBITS</u>	0x0429	99
<u>MGMMSG MOT GET STATUSBITS</u>	0x042A	99

Messages Applicable to TST101

<u>MGMMSG MOT SET TSTACTUATORTYPE</u>	0x04FE	94
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Messages Applicable to BSC10x and BSC20x

MGMSG_MOD_IDENTIFY	0x0223	20
MGMSG_MOD_SET_CHANENABLESTATE	0x0210	21
MGMSG_MOD_REQ_CHANENABLESTATE	0x0211	21
MGMSG_MOD_GET_CHANENABLESTATE	0x0212	21
MGMSG_HW_DISCONNECT	0x0002	23
MGMSG_HW_RESPONSE	0x0080	23
MGMSG_HW_RICHRESPONSE	0x0081	24
MGMSG_HW_START_UPDATEMSGS	0x0011	25
MGMSG_HW_STOP_UPDATEMSGS	0x0012	25
MGMSG_HW_REQ_INFO	0x0005	26
MGMSG_HW_GET_INFO	0x0006	26
MGMSG_RACK_REQ_BAYUSED	0x0060	28
MGMSG_RACK_GET_BAYUSED	0x0061	28
MGMSG_MOD_SET_DIGOUTPUTS	0x0213	32
MGMSG_MOD_REQ_DIGOUTPUTS	0x0214	32
MGMSG_MOD_GET_DIGOUTPUTS	0x0215	32
MGMSG_MOT_SET_POSCOUNTER	0x0410	36
MGMSG_MOT_REQ_POSCOUNTER	0x0411	36
MGMSG_MOT_GET_POSCOUNTER	0x0412	36
MGMSG_MOT_SET_ENCCOUNTER	0x0409	37
MGMSG_MOT_REQ_ENCCOUNTER	0x040A	37
MGMSG_MOT_GET_ENCCOUNTER	0x040B	37
MGMSG_MOT_SET_VELPARAMS	0x0413	39
MGMSG_MOT_REQ_VELPARAMS	0x0414	39
MGMSG_MOT_GET_VELPARAMS	0x0415	39
MGMSG_MOT_SET_JOGPARAMS	0x0416	41
MGMSG_MOT_REQ_JOGPARAMS	0x0417	41
MGMSG_MOT_GET_JOGPARAMS	0x0418	41
MGMSG_MOT_REQ_ADCINPUTS	0x042B	43
MGMSG_MOT_GET_ADCINPUTS	0x042C	43
MGMSG_MOT_SET_POWERPARAMS	0x0426	44
MGMSG_MOT_REQ_POWERPARAMS	0x0427	44
MGMSG_MOT_GET_POWERPARAMS	0x0428	44
MGMSG_MOT_SET_GENMOVEPARAMS	0x043A	46
MGMSG_MOT_REQ_GENMOVEPARAMS	0x043B	46
MGMSG_MOT_GET_GENMOVEPARAMS	0x043C	46
MGMSG_MOT_SET_MOVERELPARAMS	0x0445	47
MGMSG_MOT_REQ_MOVERELPARAMS	0x0446	47
MGMSG_MOT_GET_MOVERELPARAMS	0x0447	47
MGMSG_MOT_SET_MOVEABSPARAMS	0x0450	48
MGMSG_MOT_REQ_MOVEABSPARAMS	0x0451	48
MGMSG_MOT_GET_MOVEABSPARAMS	0x0452	48
MGMSG_MOT_SET_HOMEPARAMS	0x0440	49
MGMSG_MOT_REQ_HOMEPARAMS	0x0441	49
MGMSG_MOT_GET_HOMEPARAMS	0x0442	49
MGMSG_MOT_SET_LIMSWITCHPARAMS	0x0423	51
MGMSG_MOT_REQ_LIMSWITCHPARAMS	0x0424	51
MGMSG_MOT_GET_LIMSWITCHPARAMS	0x0425	51
MGMSG_MOT_MOVE_HOME	0x0443	53
MGMSG_MOT_MOVE_HOMED	0x0444	53
MGMSG_MOT_MOVE_RELATIVE	0x0448	54
MGMSG_MOT_MOVE_COMPLETED	0x0464	56
MGMSG_MOT_MOVE_ABSOLUTE	0x0453	57
MGMSG_MOT_MOVE_JOG	0x046A	59
MGMSG_MOT_MOVE_VELOCITY	0x0457	60

<u>MGMMSG_MOT_MOVE_STOP</u>	0x0465	61
<u>MGMMSG_MOT_MOVE_STOPPED</u>	0x0466	62
<u>MGMMSG_MOT_SET_EEPROMPARAMS</u>	0x04B9	75
<u>MGMMSG_MOT_GET_STATUSUPDATE</u>	0x0481	94
<u>MGMMSG_MOT_REQ_STATUSUPDATE</u>	0x0480	96
<u>MGMMSG_MOT_REQ_STATUSBITS</u>	0x0429	99
<u>MGMMSG_MOT_GET_STATUSBITS</u>	0x042A	99
<u>MGMMSG_MOT_SET_TRIGGER</u>	0x0500	102
<u>MGMMSG_MOT_REQ_TRIGGER</u>	0x0501	102
<u>MGMMSG_MOT_GET_TRIGGER</u>	0x0502	102

Messages Applicable to LTS150 and LTS300

<u>MGMMSG_MOD_IDENTIFY</u>	0x0223	20
<u>MGMMSG_MOD_SET_CHANENABLESTATE</u>	0x0210	21
<u>MGMMSG_MOD_REQ_CHANENABLESTATE</u>	0x0211	21
<u>MGMMSG_MOD_GET_CHANENABLESTATE</u>	0x0212	21
<u>MGMMSG_HW_START_UPDATEMSGS</u>	0x0011	25
<u>MGMMSG_HW_STOP_UPDATEMSGS</u>	0x0012	25
<u>MGMMSG_HW_REQ_INFO</u>	0x0005	26
<u>MGMMSG_HW_GET_INFO</u>	0x0006	26
<u>MGMMSG_MOT_SET_POSCOUNTER</u>	0x0410	36
<u>MGMMSG_MOT_REQ_POSCOUNTER</u>	0x0411	36
<u>MGMMSG_MOT_GET_POSCOUNTER</u>	0x0412	36
<u>MGMMSG_MOT_SET_VELPARAMS</u>	0x0413	39
<u>MGMMSG_MOT_REQ_VELPARAMS</u>	0x0414	39
<u>MGMMSG_MOT_GET_VELPARAMS</u>	0x0415	39
<u>MGMMSG_MOT_SET_JOGPARAMS</u>	0x0416	41
<u>MGMMSG_MOT_REQ_JOGPARAMS</u>	0x0417	41
<u>MGMMSG_MOT_GET_JOGPARAMS</u>	0x0418	41
<u>MGMMSG_MOT_SET_GENMOVEPARAMS</u>	0x043A	46
<u>MGMMSG_MOT_REQ_GENMOVEPARAMS</u>	0x043B	46
<u>MGMMSG_MOT_GET_GENMOVEPARAMS</u>	0x043C	46
<u>MGMMSG_MOT_SET_MOVERELPARAMS</u>	0x0445	47
<u>MGMMSG_MOT_REQ_MOVERELPARAMS</u>	0x0446	47
<u>MGMMSG_MOT_GET_MOVERELPARAMS</u>	0x0447	47
<u>MGMMSG_MOT_SET_MOVEABSPARAMS</u>	0x0450	48
<u>MGMMSG_MOT_REQ_MOVEABSPARAMS</u>	0x0451	48
<u>MGMMSG_MOT_GET_MOVEABSPARAMS</u>	0x0452	48
<u>MGMMSG_MOT_SET_HOMEPARAMS</u>	0x0440	49
<u>MGMMSG_MOT_REQ_HOMEPARAMS</u>	0x0441	49
<u>MGMMSG_MOT_GET_HOMEPARAMS</u>	0x0442	49
<u>MGMMSG_MOT_SET_LIMSWITCHPARAMS</u>	0x0423	51
<u>MGMMSG_MOT_REQ_LIMSWITCHPARAMS</u>	0x0424	51
<u>MGMMSG_MOT_GET_LIMSWITCHPARAMS</u>	0x0425	51
<u>MGMMSG_MOT_MOVE_HOME</u>	0x0443	53
<u>MGMMSG_MOT_MOVE_HOMED</u>	0x0444	53
<u>MGMMSG_MOT_MOVE_RELATIVE</u>	0x0448	54
<u>MGMMSG_MOT_MOVE_COMPLETED</u>	0x0464	56
<u>MGMMSG_MOT_MOVE_ABSOLUTE</u>	0x0453	57
<u>MGMMSG_MOT_MOVE_JOG</u>	0x046A	59
<u>MGMMSG_MOT_MOVE_VELOCITY</u>	0x0457	60
<u>MGMMSG_MOT_MOVE_STOP</u>	0x0465	61
<u>MGMMSG_MOT_MOVE_STOPPED</u>	0x0466	62
<u>MGMMSG_MOT_SET_BOWINDEX</u>	0x0450	63
<u>MGMMSG_MOT_REQ_BOWINDEX</u>	0x0451	63
<u>MGMMSG_MOT_GET_BOWINDEX</u>	0x0452	63
<u>MGMMSG_MOT_SET_EEPROMPARAMS</u>	0x04B9	75
<u>MGMMSG_MOT_GET_STATUSUPDATE</u>	0x0481	94
<u>MGMMSG_MOT_REQ_STATUSUPDATE</u>	0x0480	96
<u>MGMMSG_MOT_REQ_STATUSBITS</u>	0x0429	99
<u>MGMMSG_MOT_GET_STATUSBITS</u>	0x042A	99

Messages Applicable to MLJ050

<u>MGMMSG_MOD_IDENTIFY</u>	0x0223	20
<u>MGMMSG_MOD_SET_CHANENABLESTATE</u>	0x0210	21
<u>MGMMSG_HW_START_UPDATEMSGS</u>	0x0011	25
<u>MGMMSG_HW_STOP_UPDATEMSGS</u>	0x0012	25
<u>MGMMSG_HW_REQ_INFO</u>	0x0005	26
<u>MGMMSG_HW_GET_INFO</u>	0x0006	26
<u>MGMMSG_MOT_SET_POSCOUNTER</u>	0x0410	36
<u>MGMMSG_MOT_REQ_POSCOUNTER</u>	0x0411	36
<u>MGMMSG_MOT_GET_POSCOUNTER</u>	0x0412	36
<u>MGMMSG_MOT_SET_VELPARAMS</u>	0x0413	39
<u>MGMMSG_MOT_REQ_VELPARAMS</u>	0x0414	39
<u>MGMMSG_MOT_GET_VELPARAMS</u>	0x0415	39
<u>MGMMSG_MOT_SET_JOGPARAMS</u>	0x0416	41
<u>MGMMSG_MOT_REQ_JOGPARAMS</u>	0x0417	41
<u>MGMMSG_MOT_GET_JOGPARAMS</u>	0x0418	41
<u>MGMMSG_MOT_SET_GENMOVEPARAMS</u>	0x043A	46
<u>MGMMSG_MOT_REQ_GENMOVEPARAMS</u>	0x043B	46
<u>MGMMSG_MOT_GET_GENMOVEPARAMS</u>	0x043C	46
<u>MGMMSG_MOT_SET_MOVERELPARAMS</u>	0x0445	47
<u>MGMMSG_MOT_REQ_MOVERELPARAMS</u>	0x0446	47
<u>MGMMSG_MOT_GET_MOVERELPARAMS</u>	0x0447	47
<u>MGMMSG_MOT_SET_MOVEABSPARAMS</u>	0x0450	48
<u>MGMMSG_MOT_REQ_MOVEABSPARAMS</u>	0x0451	48
<u>MGMMSG_MOT_GET_MOVEABSPARAMS</u>	0x0452	48
<u>MGMMSG_MOT_SET_HOMEPARAMS</u>	0x0440	49
<u>MGMMSG_MOT_REQ_HOMEPARAMS</u>	0x0441	49
<u>MGMMSG_MOT_GET_HOMEPARAMS</u>	0x0442	49
<u>MGMMSG_MOT_SET_LIMSWITCHPARAMS</u>	0x0423	51
<u>MGMMSG_MOT_REQ_LIMSWITCHPARAMS</u>	0x0424	51
<u>MGMMSG_MOT_GET_LIMSWITCHPARAMS</u>	0x0425	51
<u>MGMMSG_MOT_MOVE_HOME</u>	0x0443	53
<u>MGMMSG_MOT_MOVE_HOMED</u>	0x0444	53
<u>MGMMSG_MOT_MOVE_RELATIVE</u>	0x0448	54
<u>MGMMSG_MOT_MOVE_COMPLETED</u>	0x0464	56
<u>MGMMSG_MOT_MOVE_ABSOLUTE</u>	0x0453	57
<u>MGMMSG_MOT_MOVE_JOG</u>	0x046A	59
<u>MGMMSG_MOT_MOVE_VELOCITY</u>	0x0457	60
<u>MGMMSG_MOT_MOVE_STOP</u>	0x0465	61
<u>MGMMSG_MOT_MOVE_STOPPED</u>	0x0466	62
<u>MGMMSG_MOT_SET_BOWINDEX</u>	0x0450	63
<u>MGMMSG_MOT_REQ_BOWINDEX</u>	0x0451	63
<u>MGMMSG_MOT_GET_BOWINDEX</u>	0x0452	63
<u>MGMMSG_MOT_SET_EEPROMPARAMS</u>	0x04B9	75
<u>MGMMSG_MOT_GET_STATUSUPDATE</u>	0x0481	94
<u>MGMMSG_MOT_REQ_STATUSUPDATE</u>	0x0480	96
<u>MGMMSG_MOT_REQ_STATUSBITS</u>	0x0429	99
<u>MGMMSG_MOT_GET_STATUSBITS</u>	0x042A	99

Messages Applicable to MFF101 and MFF102

<u>MGMSG_MOD_IDENTIFY</u>	0x0223	20
<u>MGMSG_HW_START_UPDATEMSGS</u>	0x0011	25
<u>MGMSG_HW_STOP_UPDATEMSGS</u>	0x0012	25
<u>MGMSG_HW_REQ_INFO</u>	0x0005	26
<u>MGMSG_HW_GET_INFO</u>	0x0006	26
<u>MGMSG_MOT_MOVE_JOG</u>	0x046A	59
<u>MGMSG_MOT_SET_EEPROMPARAMS</u>	0x04B9	75
<u>MGMSG_MOT_REQ_STATUSBITS</u>	0x0429	99
<u>MGMSG_MOT_GET_STATUSBITS</u>	0x042A	99
<u>MGMSG_MOT_SET_MFF_OPERPARAMS</u>	0x0510	106
<u>MGMSG_MOT_REQ_MFF_OPERPARAMS</u>	0x0511	106
<u>MGMSG_MOT_GET_MFF_OPERPARAMS</u>	0x0512	106

Messages Applicable to BBD10x, BBD20x and TBD001

MGMSG_MOD_IDENTIFY	0x0223	20
MGMSG_MOD_SET_CHANENABLESTATE	0x0210	21
MGMSG_MOD_REQ_CHANENABLESTATE	0x0211	21
MGMSG_MOD_GET_CHANENABLESTATE	0x0212	21
MGMSG_HW_DISCONNECT	0x0002	23
MGMSG_HW_RESPONSE	0x0080	23
MGMSG_HW_RICHRESPONSE	0x0081	24
MGMSG_HW_START_UPDATEMSGS	0x0011	25
MGMSG_HW_STOP_UPDATEMSGS	0x0012	25
MGMSG_HW_REQ_INFO	0x0005	26
MGMSG_HW_GET_INFO	0x0006	26
MGMSG_RACK_REQ_BAYUSED	0x0060	28
MGMSG_RACK_GET_BAYUSED	0x0061	28
MGMSG_MOD_SET_DIGOUTPUTS	0x0213	32
MGMSG_MOD_REQ_DIGOUTPUTS	0x0214	32
MGMSG_MOD_GET_DIGOUTPUTS	0x0215	32
MGMSG_MOT_SET_POSCOUNTER	0x0410	36
MGMSG_MOT_REQ_POSCOUNTER	0x0411	36
MGMSG_MOT_GET_POSCOUNTER	0x0412	36
MGMSG_MOT_SET_ENCCOUNTER	0x0409	37
MGMSG_MOT_REQ_ENCCOUNTER	0x040A	37
MGMSG_MOT_GET_ENCCOUNTER	0x040B	37
MGMSG_MOT_SET_VELPARAMS	0x0413	39
MGMSG_MOT_REQ_VELPARAMS	0x0414	39
MGMSG_MOT_GET_VELPARAMS	0x0415	39
MGMSG_MOT_SET_JOGPARAMS	0x0416	41
MGMSG_MOT_REQ_JOGPARAMS	0x0417	41
MGMSG_MOT_GET_JOGPARAMS	0x0418	41
MGMSG_MOT_SET_GENMOVEPARAMS	0x043A	46
MGMSG_MOT_REQ_GENMOVEPARAMS	0x043B	46
MGMSG_MOT_GET_GENMOVEPARAMS	0x043C	46
MGMSG_MOT_SET_MOVERELPARAMS	0x0445	47
MGMSG_MOT_REQ_MOVERELPARAMS	0x0446	47
MGMSG_MOT_GET_MOVERELPARAMS	0x0447	47
MGMSG_MOT_SET_MOVEABSPARAMS	0x0450	48
MGMSG_MOT_REQ_MOVEABSPARAMS	0x0451	48
MGMSG_MOT_GET_MOVEABSPARAMS	0x0452	48
MGMSG_MOT_SET_HOMEPARAMS	0x0440	49
MGMSG_MOT_REQ_HOMEPARAMS	0x0441	49
MGMSG_MOT_GET_HOMEPARAMS	0x0442	49
MGMSG_MOT_SET_LIMSWITCHPARAMS	0x0423	51
MGMSG_MOT_REQ_LIMSWITCHPARAMS	0x0424	51
MGMSG_MOT_GET_LIMSWITCHPARAMS	0x0425	51
MGMSG_MOT_MOVE_HOME	0x0443	53
MGMSG_MOT_MOVE_HOMED	0x0444	53
MGMSG_MOT_MOVE_RELATIVE	0x0448	54
MGMSG_MOT_MOVE_COMPLETED	0x0464	56
MGMSG_MOT_MOVE_ABSOLUTE	0x0453	57
MGMSG_MOT_MOVE_JOG	0x046A	59
MGMSG_MOT_MOVE_VELOCITY	0x0457	60
MGMSG_MOT_MOVE_STOP	0x0465	61
MGMSG_MOT_MOVE_STOPPED	0x0466	62
MGMSG_MOT_SET_EEPROMPARAMS	0x04B9	75

<u>MGMMSG_MOT_SET_PMDPOSITIONLOOPPARAMS</u>	<u>0x04D7</u>	76
<u>MGMMSG_MOT_REQ_PMDPOSITIONLOOPPARAMS</u>	<u>0x04D8</u>	76
<u>MGMMSG_MOT_GET_PMDPOSITIONLOOPPARAMS</u>	<u>0x04D9</u>	76
<u>MGMMSG_MOT_SET_PMDMOTOROUTPUTPARAMS</u>	<u>0x04DA</u>	79
<u>MGMMSG_MOT_REQ_PMDMOTOROUTPUTPARAMS</u>	<u>0x04DB</u>	79
<u>MGMMSG_MOT_GET_PMDMOTOROUTPUTPARAMS</u>	<u>0x04DC</u>	79
<u>MGMMSG_MOT_SET_PMDTRACKSETTLEPARAMS</u>	<u>0x04E0</u>	81
<u>MGMMSG_MOT_REQ_PMDTRACKSETTLEPARAMS</u>	<u>0x04E1</u>	81
<u>MGMMSG_MOT_GET_PMDTRACKSETTLEPARAMS</u>	<u>0x04E2</u>	81
<u>MGMMSG_MOT_SET_PMDPROFILEMODEPARAMS</u>	<u>0x04E3</u>	84
<u>MGMMSG_MOT_REQ_PMDPROFILEMODEPARAMS</u>	<u>0x04E4</u>	84
<u>MGMMSG_MOT_GET_PMDPROFILEMODEPARAMS</u>	<u>0x04E5</u>	84
<u>MGMMSG_MOT_SET_PMDJOYSTICKPPARAMS</u>	<u>0x04E6</u>	86
<u>MGMMSG_MOT_REQ_PMDJOYSTICKPPARAMS</u>	<u>0x04E7</u>	86
<u>MGMMSG_MOT_GET_PMDJOYSTICKPPARAMS</u>	<u>0x04E8</u>	86
<u>MGMMSG_MOT_SET_PMDCURRENTLOOPPARAMS</u>	<u>0x04D4</u>	88
<u>MGMMSG_MOT_REQ_PMDCURRENTLOOPPARAMS</u>	<u>0x04D5</u>	88
<u>MGMMSG_MOT_GET_PMDCURRENTLOOPPARAMS</u>	<u>0x04D6</u>	88
<u>MGMMSG_MOT_SET_PMDSETTLEDCURRENTLOOPPARAMS</u>	<u>0x04E9</u>	90
<u>MGMMSG_MOT_REQ_PMDSETTLEDCURRENTLOOPPARAMS</u>	<u>0x04EA</u>	90
<u>MGMMSG_MOT_GET_PMDSETTLEDCURRENTLOOPPARAMS</u>	<u>0x04EB</u>	90
<u>MGMMSG_MOT_SET_PMDSTAGEAXISPARAMS</u>	<u>0x04F0</u>	92
<u>MGMMSG_MOT_REQ_PMDSTAGEAXISPARAMS</u>	<u>0x04F1</u>	92
<u>MGMMSG_MOT_GET_PMDSTAGEAXISPARAMS</u>	<u>0x04F2</u>	92
<u>MGMMSG_MOT_GET_DCSTATUSUPDATE</u>	<u>0x0491</u>	97
<u>MGMMSG_MOT_REQ_DCSTATUSUPDATE</u>	<u>0x0490</u>	98
<u>MGMMSG_MOT_ACK_DCSTATUSUPDATE</u>	<u>0x0492</u>	98
<u>MGMMSG_MOT_REQ_STATUSBITS</u>	<u>0x0429</u>	99
<u>MGMMSG_MOT_SUSPEND_ENDOFMOVEMSGS</u>	<u>0x046B</u>	100
<u>MGMMSG_MOT_RESUME_ENDOFMOVEMSGS</u>	<u>0x046C</u>	101
<u>MGMMSG_MOT_SET_TRIGGER</u>	<u>0x0500</u>	102
<u>MGMMSG_MOT_REQ_TRIGGER</u>	<u>0x0501</u>	102
<u>MGMMSG_MOT_GET_TRIGGER</u>	<u>0x0502</u>	102

Messages Applicable to BNT001, MNA601 and TNA001

<u>MGMMSG_MOD_IDENTIFY</u>	0x0223	20
<u>MGMMSG_HW_DISCONNECT</u>	0x0002	23
<u>MGMMSG_HW_RESPONSE</u>	0x0080	23
<u>MGMMSG_HW_RICHRESPONSE</u>	0x0081	24
<u>MGMMSG_HW_START_UPDATEMSGS</u>	0x0011	25
<u>MGMMSG_HW_STOP_UPDATEMSGS</u>	0x0012	25
<u>MGMMSG_HW_REQ_INFO</u>	0x0005	26
<u>MGMMSG_HW_GET_INFO</u>	0x0006	26
<u>MGMMSG_HUB_REQ_BAYUSED</u>	0x0065	29
<u>MGMMSG_HUB_GET_BAYUSED</u>	0x0066	29
<u>MGMMSG_PZ_SET_NTMODE</u>	0x0603	157
<u>MGMMSG_PZ_REQ_NTMODE</u>	0x0604	158
<u>MGMMSG_PZ_GET_NTMODE</u>	0x0605	158
<u>MGMMSG_PZ_SET_NTTRACKTHRESHOLD</u>	0x0606	159
<u>MGMMSG_PZ_REQ_NTTRACKTHRESHOLD</u>	0x0607	159
<u>MGMMSG_PZ_GET_NTTRACKTHRESHOLD</u>	0x0608	159
<u>MGMMSG_PZ_SET_NTCIRCHOMEPOS</u>	0x0609	160
<u>MGMMSG_PZ_REQ_NTCIRCHOMEPOS</u>	0x0610	160
<u>MGMMSG_PZ_GET_NTCIRCHOMEPOS</u>	0x0611	160
<u>MGMMSG_PZ_MOVE_NTCIRCTOHOMEPOS</u>	0x0612	161
<u>MGMMSG_PZ_REQ_NTCIRCENTREPOS</u>	0x0613	162
<u>MGMMSG_PZ_GET_NTCIRCENTREPOS</u>	0x0614	162
<u>MGMMSG_PZ_SET_NTCIRCPARAMS</u>	0x0618	164
<u>MGMMSG_PZ_REQ_NTCIRCPARAMS</u>	0x0619	164
<u>MGMMSG_PZ_GET_NTCIRCPARAMS</u>	0x0620	164
<u>MGMMSG_PZ_SET_NTCIRCDIA</u>	0x061A	167
<u>MGMMSG_PZ_SET_NTCIRCDIALUT</u>	0x0621	168
<u>MGMMSG_PZ_REQ_NTCIRCDIALUT</u>	0x0622	168
<u>MGMMSG_PZ_GET_NTCIRCDIALUT</u>	0x0623	168
<u>MGMMSG_PZ_SET_NTPHASECOMPPARAMS</u>	0x0626	170
<u>MGMMSG_PZ_REQ_NTPHASECOMPPARAMS</u>	0x0627	170
<u>MGMMSG_PZ_GET_NTPHASECOMPPARAMS</u>	0x0628	170
<u>MGMMSG_PZ_SET_NTTIARANGEPARAMS</u>	0x0630	172
<u>MGMMSG_PZ_REQ_NTTIARANGEPARAMS</u>	0x0631	172
<u>MGMMSG_PZ_GET_NTTIARANGEPARAMS</u>	0x0632	172
<u>MGMMSG_PZ_SET_NTGAINPARAMS</u>	0x0633	175
<u>MGMMSG_PZ_REQ_NTGAINPARAMS</u>	0x0634	175
<u>MGMMSG_PZ_GET_NTGAINPARAMS</u>	0x0635	175
<u>MGMMSG_PZ_SET_NTTIALPFILTERPARAMS</u>	0x0636	176
<u>MGMMSG_PZ_REQ_NTTIALPFILTERPARAMS</u>	0x0637	176
<u>MGMMSG_PZ_GET_NTTIALPFILTERPARAMS</u>	0x0638	176
<u>MGMMSG_PZ_REQ_NTTIAREADING</u>	0x0639	178
<u>MGMMSG_PZ_GET_NTTIAREADING</u>	0x063A	178
<u>MGMMSG_PZ_SET_NTFEEDBACKSRC</u>	0x063B	180
<u>MGMMSG_PZ_REQ_NTFEEDBACKSRC</u>	0x063C	180
<u>MGMMSG_PZ_GET_NTFEEDBACKSRC</u>	0x063D	180
<u>MGMMSG_PZ_REQ_NTSTATUSBITS</u>	0x063E	182
<u>MGMMSG_PZ_GET_NTSTATUSBITS</u>	0x063F	182
<u>MGMMSG_PZ_REQ_NTSTATUSUPDATE</u>	0x0664	184
<u>MGMMSG_PZ_GET_NTSTATUSUPDATE</u>	0x0665	184
<u>MGMMSG_PZ_ACK_NTSTATUSUPDATE</u>	0x0666	188
<u>MGMMSG_NT_SET_EEPROMPARAMS</u>	0x07E7	189
<u>MGMMSG_NT_SET_TNA_DISPSETTINGS</u>	0x07E8	190
<u>MGMMSG_NT_REQ_TNA_DISPSETTINGS</u>	0x07E9	190
<u>MGMMSG_NT_GET_TNA_DISPSETTINGS</u>	0x07EA	190

<u>MGMMSG_NT_SET_TNA_IOSETTINGS</u>	0x07EB	191
<u>MGMMSG_NT_REQ_TNA_IOSETTINGS</u>	0x07EC	191
<u>MGMMSG_NT_GET_TNA_IOSETTINGS</u>	0x07ED	191

Messages Applicable to TLS001

<u>MGMMSG MOD IDENTIFY</u>	0x0223	20
<u>MGMMSG HW DISCONNECT</u>	0x0002	23
<u>MGMMSG HW START UPDATEMSGS</u>	0x0011	25
<u>MGMMSG HW STOP UPDATEMSGS</u>	0x0012	25
<u>MGMMSG HW REQ INFO</u>	0x0005	26
<u>MGMMSG HW GET INFO</u>	0x0006	26
<u>MGMMSG LA SET PARAMS</u>	0x0800	194
<u>MGMMSG LA REQ PARAMS</u>	0x0801	194
<u>MGMMSG LA GET PARAMS</u>	0x0802	194
<u>MGMMSG LA ENABLEOUTPUT</u>	0x0811	202
<u>MGMMSG LA DISABLEOUTPUT</u>	0x0812	202
<u>MGMMSG LA SET EEPROMPARAMS</u>	0x0810	201
<u>MGMMSG LA REQ STATUSUPDATE</u>	0x0820	203
<u>MGMMSG LA GET STATUSUPDATE</u>	0x0821	203
<u>MGMMSG LA ACK STATUSUPDATE</u>	0x0822	205

Messages Applicable to TQD001 and TPA101

<u>MGMMSG_MOD_IDENTIFY</u>	0x0223	20
<u>MGMMSG_HW_DISCONNECT</u>	0x0002	23
<u>MGMMSG_HW_START_UPDATEMSGS</u>	0x0011	25
<u>MGMMSG_HW_STOP_UPDATEMSGS</u>	0x0012	25
<u>MGMMSG_HW_REQ_INFO</u>	0x0005	26
<u>MGMMSG_HW_GET_INFO</u>	0x0006	26
<u>MGMMSG_QUAD_SET_PARAMS</u>	0x0870	207
<u>MGMMSG_QUAD_REQ_PARAMS</u>	0x0871	207
<u>MGMMSG_QUAD_GET_PARAMS</u>	0x0872	207

QUAD_PARAM Sub-Messages

<u>Set/Request/Get Quad_LoopParams (sub-message ID = 01)</u>
<u>Request/Get Quad_ Readings (sub-message ID = 03)</u>
<u>Set/Request/Get Quad Position Demand Params (sub-message ID = 05)</u>
<u>Set/Request/Get Quad Operating Mode (sub-message ID = 07)</u>
<u>Request/Get Quad Status Bits (sub-message ID = 09)</u>
<u>Set/Request/Get Quad Display Settings (sub-message ID = 0B)</u>
<u>Set/Request/Get Quad Position Demand Outputs (sub-message ID = 0D)</u>

<u>MGMMSG_QUAD_REQ_STATUSUPDATE</u>	0x0880	220
<u>MGMMSG_QUAD_GET_STATUSUPDATE</u>	0x0881	224
<u>MGMMSG_QUAD_SET_EEPROMPARAMS</u>	0x0875	226

Messages Applicable to TPA101 Only

QUAD_PARAM Sub-Messages

<u>Set/Request/Get Quad_LoopParams2 (sub-message ID = 0E)</u>
<u>MGMMSG_QUAD_ACK_STATUSUPDATE</u> 0x0882 224

Messages Applicable to TTC001

<u>MGMMSG_MOD_IDENTIFY</u>	0x0223	20
<u>MGMMSG_HW_DISCONNECT</u>	0x0002	23
<u>MGMMSG_HW_START_UPDATEMSGS</u>	0x0011	25
<u>MGMMSG_HW_STOP_UPDATEMSGS</u>	0x0012	25
<u>MGMMSG_HW_REQ_INFO</u>	0x0005	26
<u>MGMMSG_HW_GET_INFO</u>	0x0006	26
<u>MGMMSG_TEC_SET_PARAMS</u>	0x0840	228
<u>MGMMSG_TEC_REQ_PARAMS</u>	0x0841	228
<u>MGMMSG_TEC_GET_PARAMS</u>	0x0842	228

TEC_PARAM Sub-Messages

<u>Set/Request/Get TEC_TempSetPoint (sub-message ID = 01)</u>
<u>Request/Get TEC_ Readings (sub-message ID = 03)</u>
<u>Set/Request/Get IOSettings (sub-message ID = 05)</u>
<u>Request/Get TEC_StatusBits (sub-message ID = 07)</u>
<u>Set/Request/Get TEC_LoopParams (sub-message ID = 09)</u>
<u>Set/Request/Get TEC_Disp_Settings (sub-message ID = 0B)</u>

<u>MGMMSG_TEC_SET_EEPROMPARAMS</u>	<u>0x0850</u>	239
<u>MGMMSG_TEC_REQ_STATUSUPDATE</u>	<u>0x0860</u>	240
<u>MGMMSG_TEC_ACK_STATUSUPDATE</u>	<u>0x0862</u>	241