

NAME

`emc` – EMC (The Enhanced Machine Controller)

SYNOPSIS

`emc [-v] [-d] [INIFILE]`

DESCRIPTION

`emc` is used to start EMC (The Enhanced Machine Controller). It starts the realtime system and then initializes a number of EMC components (IO, Motion, GUI, HAL, etc). The most important parameter is *INIFILE*, which specifies the configuration name you would like to run. If *INIFILE* is not specified, the `emc` script presents a graphical wizard to let you choose one.

OPTIONS

- `-v` Be a little bit verbose. This causes the script to print information as it works.
- `-d` Print lots of debug information. All executed commands are echoed to the screen. This mode is useful when something is not working as it should.

INIFILE

The ini file is the main piece of an EMC configuration. It is not the entire configuration; there are various other files that go with it (NML files, HAL files, TBL files, VAR files). It is, however, the most important one, because it is the file that holds the configuration together. It can adjust a lot of parameters itself, but it also tells `emc` which other files to load and use.

There are several ways to specify which config to use:

Specify the absolute path to an ini, e.g.

`emc /usr/local/emc2/configs/sim/sim.ini`

Specify a relative path from the current directory, e.g.

`emc configs/sim/sim.ini`

Otherwise, in the case where the **INIFILE** is not specified, the behavior will depend on whether you configured `emc` with `--enable-run-in-place`. If so, the `emc` config chooser will search only the `configs` directory in your source tree. If not (or if you are using a packaged version of `emc`), it may search several directories. The config chooser is currently set to search the path:

`~/emc2/configs:/usr/src/emc2.4-docbuild/configs`

EXAMPLES

`emc`

`emc configs/sim/sim.ini`

`emc /etc/emc2/sample-configs/stepper/stepper_mm.ini`

SEE ALSO

`halcmd(1)`

Much more information about EMC2 and HAL is available in the EMC2 and HAL User Manuals, found at `/usr/share/doc/emc2/`.

HISTORY**BUGS**

None known at this time.

AUTHOR

This man page written by Alex Joni, as part of the Enhanced Machine Controller (EMC) project.

REPORTING BUGS

Report bugs to alex_joni AT users DOT sourceforge DOT net

COPYRIGHT

Copyright © 2006 Alex Joni.

This is free software; see the source for copying conditions. There is NO warranty; not even for MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE.

NAME

axis-remote – AXIS Remote Interface

SYNOPSIS

axis-remote [*--ping*] [*--reload*] [*--clear*] [*--quit*] [*--help*]

DESCRIPTION

axis-remote is a small script to control a running AXIS GUI. Use **axis-remote --help** for further information.

OPTIONS

- ping** Check whether AXIS is running.
- reload**
Make AXIS reload the currently loaded file.
- clear** Make AXIS clear the backplot.
- quit** Make AXIS quit.
- help** Display a list of valid parameters for **axis-remote**.

SEE ALSO

axis(1)

Much more information about EMC2 and HAL is available in the EMC2 and HAL User Manuals, found at </usr/share/doc/emc2/>.

HISTORY**BUGS**

None known at this time.

AUTHOR

This man page written by Alex Joni, as part of the Enhanced Machine Controller (EMC) project.

REPORTING BUGS

Report bugs to alex_joni AT users DOT sourceforge DOT net

COPYRIGHT

Copyright © 2007 Alex Joni.

This is free software; see the source for copying conditions. There is NO warranty; not even for MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE.

NAME

`axis` – AXIS EMC (The Enhanced Machine Controller) Graphical User Interface

SYNOPSIS

`axis -ini INIFILE`

DESCRIPTION

`axis` is one of the Graphical User Interfaces (GUI) for EMC (The Enhanced Machine Controller). It gets run by the runscrip usually.

OPTIONS**INIFILE**

The ini file is the main piece of an EMC configuration. It is not the entire configuration; there are various other files that go with it (NML files, HAL files, TBL files, VAR files). It is, however, the most important one, because it is the file that holds the configuration together. It can adjust a lot of parameters itself, but it also tells **emc** which other files to load and use.

SEE ALSO

`emc(1)`

Much more information about EMC2 and HAL is available in the EMC2 and HAL User Manuals, found at `/usr/share/doc/emc2/`.

HISTORY**BUGS**

None known at this time.

AUTHOR

This man page written by Alex Joni, as part of the Enhanced Machine Controller (EMC) project.

REPORTING BUGS

Report bugs to alex_joni AT users DOT sourceforge DOT net

COPYRIGHT

Copyright © 2007 Alex Joni.

This is free software; see the source for copying conditions. There is NO warranty; not even for MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE.

NAME

bfload – A program for loading a Xilinx Bitfile program into the FPGA of an Anything I/O board from Mesa Electronics.

SYNOPSIS

bfload help

bfload list

bfload BoardType[:BoardIdentifier]=BitFile

DESCRIPTION

This program loads a Xilinx bitfile-format FPGA program into the FPGA of an Anything I/O board from Mesa Electronics. Currently supported boards:

5i20

7i43 (both the 200K and 400K FPGA models)

OPTIONS

The first two command-line forms do not program an FPGA.

help Prints terse usage info.

list Lists all the supported PCI Anything I/O boards in the system.

The last command-line form tries to program the FPGA of an Anything I/O board.

BoardType specifies the model name of a supported Anything I/O board (see the DESCRIPTION section above).

BoardIdentifier is optional. Its format depends on the board type. For PCI boards, BoardIdentifier is an integer specifying the n'th discovered PCI board of that type. For EPP boards, BoardIdentifier is the I/O address of the parallel port to use, in the format "IOAddr[,IOAddrHigh]". If IOAddrHigh is omitted, it defaults to IOAddr + 0x400. If BoardIdentifier is omitted, it defaults to "0" for PCI boards and "0x378" for EPP boards.

BitFile is the name of the FPGA program file to send.

EXAMPLE

```
# send the file SV12.BIT to the first 5i20 board in the system
bfload 5i20=SV12.BIT
```

```
# send the file SV8B.BIT to the 7i43 at the specified address
bfload 7i43:0xdc48,0xdc50=SV8B.BIT
```

NAME

comp – Build, compile and install EMC HAL components

SYNOPSIS

```
comp [--compile|--preprocess|--document|--view-doc] compfile...
sudo comp [--install|--install-doc] compfile...
comp --compile --userspace cfile...
sudo comp --install --userspace cfile...
sudo comp --install --userspace pyfile...
```

DESCRIPTION

comp performs many different functions:

- Compile **.comp** and **.c** files into **.so** or **.ko** HAL realtime components (the **--compile** flag)
- Compile **.comp** and **.c** files into HAL userspace components (the **--compile --userspace** flag)
- Preprocess **.comp** files into **.c** files (the **--preprocess** flag)
- Extract documentation from **.comp** files into **.9** manpage files (the **--document** flag)
- Display documentation from **.comp** files onscreen (the **--view-doc** flag)
- Compile and install **.comp** and **.c** files into the proper directory for HAL realtime components (the **--install** flag), which may require *sudo* to write to system directories.
- Install **.c** and **.py** files into the proper directory for HAL userspace components (the **--install --userspace** flag), which may require *sudo* to write to system directories.
- Extract documentation from **.comp** files into **.9** manpage files in the proper system directory (the **--install** flag), which may require *sudo* to write to system directories.
- Preprocess **.comp** files into **.c** files (the **--preprocess** flag)

SEE ALSO

Comp: A tool for creating HAL components in the emc2 documentation for a full description of the **.comp** syntax, along with examples

pydoc hal and *Creating Userspace Python Components with the 'hal' module* for documentation on the Python interface to HAL components

comp(9) for documentation on the "two input comparator with hysteresis", a HAL realtime component with the same name as this program

NAME

emcrsh – text-mode interface for commanding emc2 over the network

SYNOPSIS

emcrsh [**OPTIONS**] [-- **EMC_OPTIONS**]

DESCRIPTION

emcrsh is a user interface for emc2. Instead of popping up a GUI window like axis(1) and touchy(1) do, it processes text-mode commands that it receives via the network. A human (or a program) can interface with **emcrsh** using telnet(1) or nc(1) or similar programs.

All features of emc2 are available via the **emcrsh** interface.

OPTIONS

-p,--port **PORT_NUMBER**

Specify the port for emcrsh to listen on. Defaults to 5007 if omitted.

-n,--name **SERVER_NAME**

Sets the server name that emcrsh will use to identify itself during handshaking with a new client. Defaults to EMCNETSVR if omitted.

-w,--connectpw **PASSWORD**

Specify the connection password to use during handshaking with a new client. Note that the password is sent in the clear, so it can be read by anyone who can read packets on the network between the server and the client. Defaults to EMC if omitted.

-e,--enablepw **PASSWORD**

Specify the password required to enable emc2 via emcrsh. Note that the password is sent in the clear, so it can be read by anyone who can read packets on the network between the server and the client. Defaults to EMCTOO if omitted.

-s,--sessions **MAX_SESSIONS**

Specify the maximum number of simultaneous connections. Defaults to -1 (no limit) if not specified.

In addition to the options listed above, emcrsh accepts an optional special EMC_OPTION at the end:

-ini **EMC_INI_FILE**

EMC .ini file to use. The -ini option **must** be preceded by two dashes: "--". Defaults to emc.ini if omitted.

Starting emcrsh

To use emcrsh instead of a normal emc2 GUI like axis or touch, specify it in your .ini file like this:

[DISPLAY]

DISPLAY=emcrsh

To use emcrsh in addition to a normal emc2 GUI, you can either start it at the end of your .hal file, or run it by hand in a terminal window.

To start it from hal, add a line like this to the end of your .hal file:

loadusr emcrsh [**OPTIONS**] [-- **EMC_OPTIONS**]

To start it from the terminal, run emcrsh manually like this:

emcrsh [**OPTIONS**] [-- **EMC_OPTIONS**]

Connecting

Once emc is up and emcrsh is running, you can connect to it using **telnet** or **nc** or similar:

telnet **HOST** **PORT**

HOST is the hostname or IP address of the computer running emcrsh, and PORT is the port it's listening on (5007 if you did not give emcrsh the --port option).

Network protocol

emcrsh accepts TCP connections on the port specified by the `--port` option, or 5007 if not specified.

The client sends requests, and the emcrsh server returns replies. Requests consist of a command word followed by optional command-specific parameters. Requests and most request parameters are case insensitive. The exceptions are passwords, file paths and text strings.

Requests and replies are terminated with the sequence `^r^n^`. `^n^` alone won't cut it.

The supported commands are as follows:

hello <password> <client> <version>

<password> must match emcrsh's connect password, or "EMC" if no `--connectpw` was supplied. The three arguments may not contain whitespace. If a valid password was entered the server will respond with:

HELLO ACK <ServerName> <ServerVersion>

If an invalid password or any other syntax error occurs then the server responds with:

HELLO NAK

get <subcommand> [<parameters>]

The `get` command takes one of the `emc` sub-commands (described in the section **EMC Subcommands**, below) and zero or more additional subcommand-specific parameters.

set <subcommand> <parameters>

The `set` command takes one of the `emc` sub-commands (described in the section **EMC Subcommands**, below) and one or more additional parameters.

quit

The `quit` command disconnects the associated socket connection.

shutdown

The `shutdown` command tells EMC to shutdown and disconnect the session. This command may only be issued if the Hello has been successfully negotiated and the connection has control of the CNC (see **enable** subcommand in the **EMC Subcommands** section, below).

help

The `help` command will return help information in text format over the connection. If no parameters are specified, it will itemize the available commands. If a command is specified, it will provide usage information for the specified command. Help will respond regardless of whether a "Hello" has been successfully negotiated.

EMC Subcommands

Subcommands for `get` and `set` are:

echo {on|off}

With `get`, any on/off parameter is ignored and the current echo state is returned. With `set`, sets the echo state as specified. Echo defaults to on when the connection is first established. When echo is on, all commands will be echoed upon receipt. This state is local to each connection.

verbose {on|off}

With `get`, any on/off parameter is ignored and the current verbose state is returned. With `set`, sets the verbose state as specified. When verbose mode is on, all `set` commands return positive acknowledgement in the form `SET <COMMAND> ACK`, and text error messages will be issued (FIXME: I don't know what this means). The verbose state is local to each connection, and starts out OFF on new connections.

enable {<passwd>|off}

The session's enable state indicates whether the current connection is enabled to perform control functions. With `get`, any parameter is ignored, and the current enable state is returned. With `set` and a valid password matching emcrsh's `--enablepw` (EMCTOO if not specified), the current connection is enabled for control functions. "OFF" may not be used as a password and disables control functions for this connection.

config [TBD]

Unused, ignore for now.

comm_mode {ascii|binary}

With get, any parameter is ignored and the current communications mode is returned. With set, will set the communications mode to the specified mode. The ascii mode is the text request/reply mode, the binary protocol is not currently designed or implemented.

comm_prot <version>

With get, any parameter is ignored and the current protocol version used by the server is returned. With set, sets the server to use the specified protocol version, provided it is lower than or equal to the highest version number supported by the server implementation.

infile

Not currently implemented! With get, returns the string "emc.ini". Should return the full path and file name of the current configuration infile. Setting this does nothing.

plat

With get, returns the string "Linux".

ini <var> <section>

Not currently implemented, do not use! Should return the string value of <var> in section <section> of the ini file.

debug <value>

With get, any parameter is ignored and the current integer value of EMC_DEBUG is returned. Note that the value of EMC_DEBUG returned is the from the UI's ini file, which may be different than emc's ini file. With set, sends a command to the EMC to set the new debug level, and sets the EMC_DEBUG global here to the same value. This will make the two values the same, since they really ought to be the same.

set_wait {none|received|done}

The set_wait setting controls the wait after receiving a command. It can be "none" (return right away), "received" (after the command was sent and received), or "done" (after the command was done). With get, any parameter is ignored and the current set_wait setting is returned. With set, set the set_wait setting to the specified value.

wait {received|done}

With set, force a wait for the previous command to be received, or done. This lets you wait in the event that "set_wait none" is in effect.

set_timeout <timeout>

With set, set the timeout for commands to return to <timeout> seconds. Timeout is a real number. If it's <= 0.0, it means wait forever. Default is 0.0, wait forever.

update {none|auto}

The update mode controls whether to return fresh or stale values for "get" requests. When the update mode is "none" it returns stale values, when it's "auto" it returns fresh values. Defaults to "auto" for new connections. Set this to "none" if you like to be confused.

error

With get, returns the current EMC error string, or "ok" if no error.

operator_display

With get, returns the current EMC operator display string, or "ok" if none.

operator_text

With get, returns the current EMC operator text string, or "ok" if none.

time

With get, returns the time, in seconds, from the start of the epoch. This starting time depends on the platform.

estop {on|off}

With get, ignores any parameters and returns the current estop setting as "on" or "off". With set, sets the estop as specified. Estop "on" means the machine is in the estop state and won't run.

machine {on|off}

With get, ignores any parameters and returns the current machine power setting as "on" or "off". With set, sets the machine on or off as specified.

mode {manual|auto|mdi}

With get, ignores any parameters and returns the current machine mode. With set, sets the machine mode as specified.

mist {on|off}

With get, ignores any parameters and returns the current mist coolant setting. With set, sets the mist setting as specified.

flood {on|off}

With get, ignores any parameters and returns the current flood coolant setting. With set, sets the flood setting as specified.

lube {on|off}

With get, ignores any parameters and returns the current lube pump setting. With set, sets the lube pump setting as specified.

lube_level

With get, returns the lubricant level sensor reading as "ok" or "low". With set, mocks you for wishful thinking.

spindle {forward|reverse|increase|decrease|constant|off}

With get, any parameter is ignored and the current spindle state is returned as "forward", "reverse", "increase", "decrease", or "off". With set, sets the spindle as specified. Note that "increase" and "decrease" will cause a speed change in the corresponding direction until a "constant" command is sent.

brake {on|off}

With get, any parameter is ignored and the current brake setting is returned. With set, the brake is set as specified.

tool

With get, returns the id of the currently loaded tool.

tool_offset

With get, returns the currently applied tool length offset.

load_tool_table <file>

With set, loads the tool table specified by <file>.

home {0|1|2|...}

With set, homes the indicated axis.

jog_stop {0|1|2|...}

With set, stop any in-progress jog on the specified axis.

jog {0|1|2|...} <speed>

With set, jog the specified axis at <speed>; sign of speed is direction.

jog_incr {0|1|2|...} <speed> <incr>

With set, jog the indicated axis by increment <incr> at the <speed>; sign of speed is direction.

feed_override <percent>

With get, any parameter is ignored and the current feed override is returned (as a percentage of commanded feed). With set, sets the feed override as specified.

spindle_override <percent>

With get, any parameter is ignored and the current spindle override is returned (as a percentage of

commanded speed). With set, sets the spindle override as specified.

abs_cmd_pos [{0|1|...}]

With get, returns the specified axis' commanded position in absolute coordinates. If no axis is specified, returns all axes' commanded absolute position.

abs_act_pos [{0|1|...}]

With get, returns the specified axis' actual position in absolute coordinates. If no axis is specified, returns all axes' actual absolute position.

rel_cmd_pos [{0|1|...}]

With get, returns the specified axis' commanded position in relative coordinates, including tool length offset. If no axis is specified, returns all axes' commanded relative position.

rel_act_pos [{0|1|...}]

With get, returns the specified axis' actual position in relative coordinates, including tool length offset. If no axis is specified, returns all axes' actual relative position.

joint_pos [{0|1|...}]

With get, returns the specified joint's actual position in absolute coordinates, excluding tool length offset. If no joint is specified, returns all joints' actual absolute position.

pos_offset [{X|Y|Z|R|P|W}]

With get, returns the position offset associated with the world coordinate provided.

joint_limit [{0|1|...}]

With get, returns limit status of the specified joint as "ok", "minsoft", "minhard", "maxsoft", or "maxhard". If no joint number is specified, returns the limit status of all joints.

joint_fault [{0|1|...}]

With get, returns the fault status of the specified joint as "ok" or "fault". If no joint number is specified, returns the fault status of all joints.

joint_homed [{0|1|...}]

With get, returns the homed status of the specified joint as "homed" or "not". If no joint number is specified, returns the homed status of all joints.

mdi <string>

With set, sends <string> as an MDI command.

task_plan_init

With set, initializes the program interpreter.

open <filename>

With set, opens the named file.

run [<StartLine>]

With set, runs the opened program. If no StartLine is specified, runs from the beginning. If a StartLine is specified, start line, runs from that line. A start line of -1 runs in verify mode.

pause

With set, pause program execution.

resume

With set, resume program execution.

abort

With set, abort program or MDI execution.

step

With set, step the program one line.

program

With get, returns the name of the currently opened program, or "none".

program_line

With get, returns the currently executing line of the program.

program_status

With get, returns "idle", "running", or "paused".

program_codes

With get, returns the string for the currently active program codes.

joint_type [<joint>]

With get, returns "linear", "angular", or "custom" for the type of the specified joint (or for all joints if none is specified).

joint_units [<joint>]

With get, returns "inch", "mm", "cm", or "deg", "rad", "grad", or "custom", for the corresponding native units of the specified joint (or for all joints if none is specified). The type of the axis (linear or angular) is used to resolve which type of units are returned. The units are obtained heuristically, based on the EMC_AXIS_STAT::units numerical value of user units per mm or deg. For linear joints, something close to 0.03937 is deemed "inch", 1.000 is "mm", 0.1 is "cm", otherwise it's "custom". For angular joints, something close to 1.000 is deemed "deg", $\text{PI}/180$ is "rad", $100/90$ is "grad", otherwise it's "custom".

program_units

Synonym for program_linear_units.

program_linear_units

With get, returns "inch", "mm", "cm", or "none", for the corresponding linear units that are active in the program interpreter.

program_angular_units

With get, returns "deg", "rad", "grad", or "none" for the corresponding angular units that are active in the program interpreter.

user_linear_units

With get, returns "inch", "mm", "cm", or "custom", for the corresponding native user linear units of the EMC trajectory level. This is obtained heuristically, based on the EMC_TRAJ_STAT::linearUnits numerical value of user units per mm. Something close to 0.03937 is deemed "inch", 1.000 is "mm", 0.1 is "cm", otherwise it's "custom".

user_angular_units

Returns "deg", "rad", "grad", or "custom" for the corresponding native user angular units of the EMC trajectory level. Like with linear units, this is obtained heuristically.

display_linear_units

With get, returns "inch", "mm", "cm", or "custom", for the linear units that are active in the display. This is effectively the value of linearUnitConversion.

display_angular_units

With get, returns "deg", "rad", "grad", or "custom", for the angular units that are active in the display. This is effectively the value of angularUnitConversion.

linear_unit_conversion {inch|mm|cm|auto}

With get, any parameter is ignored and the active unit conversion is returned. With set, sets the unit to be displayed. If it's "auto", the units to be displayed match the program units.

angular_unit_conversion {deg|rad|grad|auto}

With get, any parameter is ignored and the active unit conversion is returned. With set, sets the units to be displayed. If it's "auto", the units to be displayed match the program units.

probe_clear

With set, clear the probe tripped flag.

probe_tripped

With get, return the probe state - has the probe tripped since the last clear?

probe_value

With get, return the current value of the probe signal.

probe

With set, move toward a certain location. If the probe is tripped on the way stop motion, record the position and raise the probe tripped flag.

teleop_enable [on|off]

With get, any parameter is ignored and the current teleop mode is returned. With set, sets the teleop mode as specified.

kinematics_type

With get, returns the type of kinematics functions used (identity=1, serial=2, parallel=3, custom=4).

override_limits {on|off}

With get, any parameter is ignored and the override_limits setting is returned. With set, the override_limits parameter is set as specified. If override_limits is on, disables end of travel hardware limits to allow jogging off of a limit. If parameters is off, then hardware limits are enabled.

optional_stop {0|1}

With get, any parameter is ignored and the current "optional stop on M1" setting is returned. With set, the setting is set as specified.

Example Session

This section shows an example session. Bold items are typed by you, non-bold is machine output.

The user connects to emcrsh, handshakes with the server (hello), enables machine commanding from this session (set enable), brings the machine out of estop (set estop off) and turns it on (set machine on), homes all the axes, switches the machine to mdi mode, sends an MDI g-code command, then disconnects and shuts down emc.

```
> telnet localhost 5007
Trying 127.0.0.1...
Connected to 127.0.0.1
Escape character is '^]'.
hello EMC user-typing-at-telnet 1.0
HELLO ACK EMCNETSVR 1.1
set enable EMCTOO
set enable EMCTOO
set mode manual
set mode manual
set estop off
set estop off
set machine on
set machine on
set home 0
set home 0
set home 1
set home 1
set home 2
set home 2
set mode mdi
set mode mdi
set mdi g0x1
set mdi g0x1
shutdown
shutdown
Connection closed by foreign host.
```

NAME

gs2_vfd - HAL userspace component for Automation Direct GS2 VFD's

SYNOPSIS

gs2_vfd [OPTIONS]

DESCRIPTION

This manual page explains the **gs2_vfd** component. This component reads and writes to the GS2 via a modbus connection.

gs2_vfd is for use with EMC2

OPTIONS

-b -bits <n>

(default 8) Set number of data bits to <n>, where n must be from 5 to 8 inclusive

-d -device <path>

(default /dev/ttyS0) Set the name of the serial device node to use.

-g -debug

Turn on debugging messages. This will also set the verbose flag. Debug mode will cause all modbus messages to be printed in hex on the terminal.

-n -name <string>

(default gs2_vfd) Set the name of the HAL module. The HAL comp name will be set to <string>, and all pin and parameter names will begin with <string>.

-p -parity [even,odd,none]

(default odd) Set serial parity to even, odd, or none.

-r -rate <n>

(default 38400) Set baud rate to <n>. It is an error if the rate is not one of the following: 110, 300, 600, 1200, 2400, 4800, 9600, 19200, 38400, 57600, 115200

-s -stopbits [1,2]

(default 1) Set serial stop bits to 1 or 2

-t -target <n>

(default 1) Set MODBUS target (slave) number. This must match the device number you set on the GS2.

-v -verbose

Turn on debug messages. Note that if there are serial errors, this may become annoying. At the moment it doesn't make much difference most of the time.

PINS

<name>.DC-bus-volts (float, out)

from the VFD

<name>.at-speed (bit, out)

when drive is at commanded speed

<name>.err-reset (bit, in)

reset errors sent to VFD

<name>.firmware-revision (s32, out)

from the VFD

<name>.frequency-command (float, out)

from the VFD

- <name>.frequency-out (float, out)**
from the VFD
- <name>.is-stopped (bit, out)**
when the VFD reports 0 Hz output
- <name>.load-percentage (float, out)**
from the VFD
- <name>.motor-RPM (float, out)**
from the VFD
- <name>.output-current (float, out)**
from the VFD
- <name>.output-voltage (float, out)**
from the VFD
- <name>.power-factor (float, out)**
from the VFD
- <name>.scale-frequency (float, out)**
from the VFD
- <name>.speed-command (float, in)**
speed sent to VFD in RPM It is an error to send a speed faster than the Motor Max RPM as set in the VFD
- <name>.spindle-fwd (bit, in)**
1 for FWD and 0 for REV sent to VFD
- <name>.spindle-on (bit, in)**
1 for ON and 0 for OFF sent to VFD, only on when running
- <name>.spindle-rev (bit, in)**
1 for ON and 0 for OFF, only on when running
- <name>.status-1 (s32, out)**
Drive Status of the VFD (see the GS2 manual)
- <name>.status-2 (s32, out)**
Drive Status of the VFD (see the GS2 manual) Note that the value is a sum of all the bits that are on. So a 163 which means the drive is in the run mode is the sum of 3 (run) + 32 (freq set by serial) + 128 (operation set by serial).

PARAMETERS

- <name>.error-count (s32, RW)**
- <name>.loop-time (float, RW)**
how often the modbus is polled (default 0.1)
- <name>.nameplate-HZ (float, RW)**
Nameplate Hz of motor (default 60)
- <name>.nameplate-RPM (float, RW)**
Nameplate RPM of motor (default 1730)
- <name>.retval (s32, RW)**
the return value of an error in HAL
- <name>.tolerance (float, RW)**
speed tolerance (default 0.01)

<name>.ack-delay (s32, RW)

number of read/write cycles before checking at-speed (default 2)

USAGE

See the EMC2 Integrators Manual for more information.

BUGS**AUTHOR**

John Thornton

LICENSE

GPL

NAME

hal_input – control HAL pins with any Linux input device, including USB HID devices

SYNOPSIS

loadusr **hal_input** [-KRAL] *inputspec* ...

DESCRIPTION

hal_input is an interface between HAL and any Linux input device, including USB HID devices. For each device named, **hal_input** creates pins corresponding to its keys, absolute axes, and LEDs. At a fixed rate of approximately 10ms, it synchronizes the device and the HAL pins.

INPUT SPECIFICATION

The *inputspec* may be in one of several forms:

A string *S*

A substring or shell-style pattern match will be tested against the "name" of the device, the "phys" (which gives information about how it is connected), and the "id", which is a string of the form "Bus=... Vendor=... Product=... Version=...". You can view the name, phys, and id of attached devices by executing **less /proc/bus/input/devices**. Examples:

```
SpaceBall
"Vendor=001f Product=0001"
serio*/input0
```

A number *N*

This opens **/dev/input/eventN**. Except for devices that are always attached to the system, this number may change over reboots or when the device is removed. For this reason, using an integer is not recommended.

When several devices are identified by the same string, add ":*N*" where *N* is the index of the desired device. For example, if **Mouse** matches **input3** and **input10**, then **Mouse** and **Mouse:0** select **input3**. Specifying **mouse:1** selects input10.

For devices that appear as multiple entries in **/dev/input**, these indices are likely to stay the same every time. For multiple identical devices, these indices are likely to depend on the insertion order, but stay the same across reboots as long as the devices are not moved to different ports or unplugged while the machine is booted.

If the first character of the *inputspec* is a "+", then **hal_input** requests exclusive access to the device. The first device matching an *inputspec* is used. Any number of *inputspecs* may be used.

A *subset option* may precede each *inputspec*. The subset option begins with a dash. Each letter in the subset option specifies a device feature to **include**. Features that are not specified are excluded. For instance, to export keyboard LEDs to HAL without exporting keys, use

```
hal_input -L keyboard ...
```

DEVICE FEATURES SUPPORTED

- EV_KEY (buttons and keys). Subset -K
- EV_ABS (absolute analog inputs). Subset -A
- EV_REL (relative analog inputs). Subset -R
- EV_LED (LED outputs). Subset -L

HAL PINS AND PARAMETERS**For buttons**

input.N.btn-name bit out

input.N.btn-name-not bit out

Created for each button on the device.

For keys**input.N.key-name****input.N.key-name-not**

Created for each key on the device.

For absolute axes**input.N.abs-name-counts** s32 out**input.N.abs-name-position** float out**input.N.abs-name-scale** parameter float rw**input.N.abs-name-offset** parameter float rw**input.N.abs-name-fuzz** parameter s32 rw**input.N.abs-name-flat** parameter s32 rw**input.N.abs-name-min** parameter s32 r**input.N.abs-name-max** parameter s32 r

Created for each absolute axis on the device. Device positions closer than **flat** to **offset** are reported as **offset** in **counts**, and **counts** does not change until the device position changes by at least **fuzz**. The position is computed as $\text{position} = (\text{counts} - \text{offset}) / \text{scale}$. The default value of **scale** and **offset** map the range of the axis reported by the operating system to [-1,1]. The default values of **fuzz** and **flat** are those reported by the operating system. The values of **min** and **max** are those reported by the operating system.

For relative axes**input.N.rel-name-counts** s32 out**input.N.rel-name-position** float out**input.N.rel-name-reset** bit in**input.N.rel-name-scale** parameter float rw**input.N.rel-name-absolute** parameter s32 rw**input.N.rel-name-precision** parameter s32 rw**input.N.rel-name-last** parameter s32 rw

Created for each relative axis on the device. As long as **reset** is true, **counts** is reset to zero regardless of any past or current axis movement. Otherwise, **counts** increases or decreases according to the motion of the axis. **counts** is divided by position-scale to give **position**. The default value of **position** is 1. There are some devices, notably scroll wheels, which return signed values with less resolution than 32 bits. The default value of **precision** is 32. **precision** can be set to 8 for a device that returns signed 8 bit values, or any other value from 1 to 32. **absolute**, when set true, ignores duplicate events with the same value. This allows for devices that repeat events without any user action to work correctly. **last** shows the most recent count value returned by the device, and is used in the implementation of **absolute**.

For LEDs**input.N.led-name** bit out**input.N.led-name-invert** parameter bit rw

Created for each LED on the device.

PERMISSIONS AND UDEV

By default, the input devices may not be accessible to regular users--**hal_input** requires read-write access, even if the device has no outputs. To change the default permission of a device, add a new file to `/etc/udev/rules.d` to set the device's `GROUP` to "plugdev". You can do this for all input devices with this rule:

```
SUBSYSTEM=="input", mode="0660", group="plugdev"
```

You can also make more specific rules for particular devices. For instance, a SpaceBall input device uses the 'spaceball' kernel module, so a udev entry for it would read:

```
DRIVER=="spaceball", MODE="0660", GROUP="plugdev"
```

the next time the device is attached to the system, it will be accessible to the "plugdev" group.

For USB devices, the udev line would refer to the device's Vendor and Product values, such as

```
SYSFS{idProduct}=="c00e", SYSFS{idVendor}=="046d", MODE="0660", GROUP="plugdev"
```

for a particular logitech-brand mouse.

For more information on writing udev rules, see **udev(8)**.

BUGS

The initial state of keys, buttons, and absolute axes are erroneously reported as FALSE or 0 until an event is received for that key, button, or axis.

SEE ALSO

udev(8)

NAME

halcmd – manipulate the Enhanced Machine Controller HAL from the command line

SYNOPSIS

halcmd [*OPTIONS*] [*COMMAND*] [*ARG*]

halrun [*-I*] [*HALCMD OPTIONS*]

halrun [*-U*]

DESCRIPTION

halcmd is used to manipulate the HAL (Hardware Abstraction Layer) from the command line. **halcmd** can optionally read commands from a file, allowing complex HAL configurations to be set up with a single command.

halrun is a convenience script which sets up the realtime environment, executes **halcmd** with the given arguments, optionally runs an interactive **halcmd -kf** if *-I* is given, then tears down the realtime environment.

If the **readline** library is available when emc is compiled, then **halcmd** offers commandline editing and completion when running interactively. Use the up arrow to recall previous commands, and press tab to complete the names of items such as pins and signals.

OPTIONS

- I** Before tearing down the realtime environment, run an interactive **halcmd**. **halrun** only. **-I** must precede all other commandline arguments.
- f** [*file*] Ignore commands on command line, take input from *file* instead. If *file* is not specified, take input from *stdin*.
- i** *inifile* Use variables from *inifile* for substitutions. See **SUBSTITUTION** below.
- k** Keep going after failed command(s). The default is to stop and return failure if any command fails.
- q** display errors only (default)
- Q** display nothing, execute commands silently
- s** Script-friendly mode. In this mode, *show* will not output titles for the items shown. Also, module names will be printed instead of ID codes in pin, param, and funct listings. Threads are printed on a single line, with the thread period, FP usage and name first, followed by all of the functions in the thread, in execution order. Signals are printed on a single line, with the type, value, and signal name first, followed by a list of pins connected to the signal, showing both the direction and the pin name. No prompt will be printed if both **-s** and **-f** are specified.
- R** Release the HAL mutex. This is useful for recovering when a HAL component has crashed while holding the HAL mutex.
- U** Forcibly cause the realtime environment to exit. It releases the HAL mutex, requests that all HAL components unload, and stops the realtime system. **halrun** only. **-U** must be the only commandline argument.
- v** display results of each command
- V** display lots of debugging junk
- h** [*command*] display a help screen and exit, displays extended help on *command* if specified

COMMANDS

Commands tell **halcmd** what to do. Normally **halcmd** reads a single command from the command line and executes it. If the **'-f'** option is used to read commands from a file, **halcmd** reads each line of the file as a new command. Anything following **'#'** on a line is a comment.

loadrt *modname*

(*load* realtime module) Loads a realtime HAL module called *modname*. **halcmd** looks for the module in a directory specified at compile time.

In systems with realtime, **halcmd** calls the **emc_module_helper** to load realtime modules. **emc_module_helper** is a setuid program and is compiled with a whitelist of modules it is allowed to load. This is currently just a list of **EMC**-related modules. The **emc_module_helper** execs `insmod`, so return codes and error messages are those from `insmod`. Administrators who wish to restrict which users can load these **EMC**-related kernel modules can do this by setting the permissions and group on **emc_module_helper** appropriately.

In systems without realtime **halcmd** calls the **rtapi_app** which creates the simulated realtime environment if it did not yet exist, and then loads the requested component with a call to **dlopen(3)**.

unloadrt *modname*

(*unload* realtime module) Unloads a realtime HAL module called *modname*. If *modname* is "all", it will unload all currently loaded realtime HAL modules. **unloadrt** also works by execing **emc_module_helper** or **rtapi_app**, just like **loadrt**.

loadusr [*flags*] *unix-command*

(*load* Userspace component) Executes the given *unix-command*, usually to load a userspace component. [*flags*] may be one or more of:

- **-W** to wait for the component to become ready. The component is assumed to have the same name as the first argument of the command.
- **-Wn name** to wait for the component, which will have the given name.
- **-w** to wait for the program to exit
- **-i** to ignore the program return value (with `-w`)

waitusr *name*

(*wait* for Userspace component) Waits for user space component *name* to disconnect from HAL (usually on exit). The component must already be loaded. Usefull near the end of a HAL file to wait until the user closes some user interface component before cleaning up and exiting.

unloadusr *compname*

(*unload* Userspace component) Unloads a userspace component called *compname*. If *compname* is "all", it will unload all userspace components. **unloadusr** works by sending SIGTERM to all userspace components.

unload *compname*

Unloads a userspace component or realtime module. If *compname* is "all", it will unload all userspace components and realtime modules.

newsig *signame type*

(*new* signal) Creates a new HAL signal called *signame* that may later be used to connect two or more HAL component pins. *type* is the data type of the new signal, and must be one of "bit", "s32", "u32", or "float". Fails if a signal of the same name already exists.

delsig *signame*

(*delete* signal) Deletes HAL signal *signame*. Any pins currently linked to the signal will be unlinked. Fails if *signame* does not exist.

sets *signame value*

(*set* signal) Sets the value of signal *signame* to *value*. Fails if *signame* does not exist, if it already has a writer, or if *value* is not a legal value. Legal values depend on the signals's type.

stype *name*

(signal type) Gets the type of signal *name*. Fails if *name* does not exist as a signal.

gets *signame*

(get signal) Gets the value of signal *signame*. Fails if *signame* does not exist.

linkps *pinname* [*arrow*] *signame*

(link pin to signal) Establishes a link between a HAL component pin *pinname* and a HAL signal *signame*. Any previous link to *pinname* will be broken. *arrow* can be "=", "<=", "<=>", or omitted. **halcmd** ignores arrows, but they can be useful in command files to document the direction of data flow. Arrows should not be used on the command line since the shell might try to interpret them. Fails if either *pinname* or *signame* does not exist, or if they are not the same type type.

linksp *signame* [*arrow*] *pinname*

(link signal to pin) Works like **linkps** but reverses the order of the arguments. **halcmd** treats both link commands exactly the same. Use whichever you prefer.

linkpp *pinname1* [*arrow*] *pinname2*

(OBSOLETE - use **net** instead) (link pin to pin) Shortcut for **linkps** that creates the signal (named like the first pin), then links them both to that signal. **halcmd** treats this just as if it were:

```
halcmd newsig pinname1
halcmd linksp pinname1 pinname1
halcmd linksp pinname1 pinname2
```

net *signame* *pinname* ...

Create *signame* to match the type of *pinname* if it does not yet exist. Then, link *signame* to each *pinname* in turn. Arrows may be used as in **linkps**.

unlinkp *pinname*

(unlink pin) Breaks any previous link to *pinname*. Fails if *pinname* does not exist.

setp *name* *value*

(set parameter or pin) Sets the value of parameter or pin *name* to *value*. Fails if *name* does not exist as a pin or parameter, if it is a parameter that is not writable, if it is a pin that is an output, if it is a pin that is already attached to a signal, or if *value* is not a legal value. Legal values depend on the type of the pin or parameter. If a pin and a parameter both exist with the given name, the parameter is acted on.

paramname = *value*

pinname = *value*

Identical to **setp**. This alternate form of the command may be more convenient and readable when used in a file.

ptype *name*

(parameter or pin type) Gets the type of parameter or pin *name*. Fails if *name* does not exist as a pin or parameter. If a pin and a parameter both exist with the given name, the parameter is acted on.

getp *name*

(get parameter or pin) Gets the value of parameter or pin *name*. Fails if *name* does not exist as a pin or parameter. If a pin and a parameter both exist with the given name, the parameter is acted on.

addf *funcname* *threadname*

(add function) Adds function *funcname* to realtime thread *threadname*. *funcname* will run after any functions that were previously added to the thread. Fails if either *funcname* or *threadname* does not exist, or if they are incompatible.

delf *funcname* *threadname*

(delete function) Removes function *funcname* from realtime thread *threadname*. Fails if either *funcname* or *threadname* does not exist, or if *funcname* is not currently part of *threadname*.

- start** Starts execution of realtime threads. Each thread periodically calls all of the functions that were added to it with the **addf** command, in the order in which they were added.
- stop** Stops execution of realtime threads. The threads will no longer call their functions.
- show** [*item*]
Prints HAL items to *stdout* in human readable format. *item* can be one of "**comp**" (components), "**pin**", "**sig**" (signals), "**param**" (parameters), "**funct**" (functions), or "**thread**". The type "**all**" can be used to show matching items of all the preceding types. If *item* is omitted, **show** will print everything.
- item** This is equivalent to **show all** [*item*].
- save** [*item*]
Prints HAL items to *stdout* in the form of HAL commands. These commands can be redirected to a file and later executed using **halcmd -f** to restore the saved configuration. *item* can be one of the following: "**comp**" generates a **loadrt** command for realtime component. "**sig**" generates a **newsig** command for each signal, and "**sigu**" generates a **newsig** command for each unlinked signal (for use with **netl** and **netla**). "**link**" and "**linka**" both generate **linkps** commands for each link. (**linka** includes arrows, while **link** does not.) "**net**" and "**neta**" both generate one **newsig** command for each signal, followed by **linkps** commands for each pin linked to that signal. (**neta** includes arrows.) "**netl**" generates one **net** command for each linked signal, and "**netla**" generates a similar command using arrows. "**param**" generates one **setp** command for each parameter. "**thread**" generates one **addf** command for each function in each realtime thread. If *item* is omitted, **save** does the equivalent of **comp**, **sigu**, **link**, **param**, and **thread**.

source *filename.hal*

Execute the commands from *filename.hal*.

SUBSTITUTION

After a command is read but before it is executed, several types of variable substitution take place.

Environment Variables

Environment variables have the following formats:

\$ENVVAR followed by end-of-line or whitespace

\$(ENVVAR)

Infile Variables

Infile variables are available only when an infile was specified with the **halcmd -i** flag. They have the following formats:

[SECTION]VAR followed by end-of-line or whitespace

[SECTION](VAR)

EXAMPLES

SEE ALSO

HISTORY

BUGS

None known at this time.

AUTHOR

Original version by John Kasunich, as part of the Enhanced Machine Controller (EMC) project. Now includes major contributions by several members of the project.

REPORTING BUGS

Report bugs to the [emc bug tracker](http://sf.net/tracker/?group_id=6744&atid=106744) (http://sf.net/tracker/?group_id=6744&atid=106744).

COPYRIGHT

Copyright © 2003 John Kasunich.

This is free software; see the source for copying conditions. There is NO warranty; not even for

MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE.

NAME

halmeter – observe HAL pins, signals, and parameters

SYNOPSIS

halmeter [-s] [**pin**|**sig**|**param** *name*] [-g *X-position Y-position [Width]*]

DESCRIPTION

halmeter is used to observe HAL (Hardware Abstraction Layer) pins, signals, or parameters. It serves the same purpose as a multimeter does when working on physical systems.

OPTIONS

pin *name*

display the HAL pin *name*.

sig *name*

display the HAL signal *name*.

param *name*

display the HAL parameter *name*.

If neither **pin**, **sig**, or **param** are specified, the window starts out blank and the user must select an item to observe.

- s small window. Non-interactive, must be used with **pin**, **sig**, or **param** to select the item to display. The item name is displayed in the title bar instead of the window, and there are no "Select" or "Exit" buttons. Handy when you want a lot of meters in a small space.
- g geometry position. allows one to specify the initial starting position and optionally the width of the meter. Referenced from top left of screen in pixel units. Handy when you want to load a lot of meters in a script with out them displaying on top of each other.

USAGE

Unless -s is specified, there are two buttons, "Select" and "Exit". "Select" opens a dialog box to select the item (pin, signal, or parameter) to be observed. "Exit" does what you expect.

The selection dialog has "OK" "Apply", and "Cancel" buttons. OK displays the selected item and closes the dialog. "Apply" displays the selected item but keeps the selection dialog open. "Cancel" closes the dialog without changing the displayed item.

EXAMPLES

halmeter

Opens a meter window, with nothing initially displayed. Use the "Select" button to choose an item to observe. Does not return until the window is closed.

halmeter &

Open a meter window, with nothing initially displayed. Use the "Select" button to choose an item. Runs in the background leaving the shell free for other commands.

halmeter pin *parport.0.pin-03-out* &

Open a meter window, initially displaying HAL pin *parport.0.pin-03-out*. The "Select" button can be used to display other items. Runs in background.

halmeter -s pin *parport.0.pin-03-out* &

Open a small meter window, displaying HAL pin *parport.0.pin-03-out*. The displayed item cannot be changed. Runs in background.

halmeter -s pin *parport.0.pin-03-out -g 100 500* &

Open a small meter window, displaying HAL pin *parport.0.pin-03-out*. places it 100 pixels to the left and 500 pixels down from top of screen. The displayed item cannot be changed. Runs in background.

halmeter -s pin parport.0.pin-03-out -g 100 500 400 &

Open a small meter window, displaying HAL pin *parport.0.pin-03-out*. places it 100 pixels to the left and 500 pixels down from top of screen. The width will be 400 pixels (270 is default) The displayed item cannot be changed. Runs in background.

SEE ALSO**HISTORY****BUGS****AUTHOR**

Original version by John Kasunich, as part of the Enhanced Machine Controller (EMC) project. Improvements by several other members of the EMC development team.

REPORTING BUGS

Report bugs to [jmkasunich AT users DOT sourceforge DOT net](mailto:jmkasunich@users.sourceforge.net)

COPYRIGHT

Copyright © 2003 John Kasunich.

This is free software; see the source for copying conditions. There is NO warranty; not even for MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE.

NAME

halsampler – sample data from HAL in realtime

SYNOPSIS

halsampler [*options*]

DESCRIPTION

sampler(9) and **halsampler** are used together to sample HAL data in real time and store it in a file. **sampler** is a realtime HAL component that exports HAL pins and creates a FIFO in shared memory. It then begins sampling data from the HAL and storing it to the FIFO. **halsampler** is a user space program that copies data from the FIFO to stdout, where it can be redirected to a file or piped to some other program.

OPTIONS

-c *CHAN*

instructs **halsampler** to read from FIFO *CHAN*. FIFOs are numbered from zero, and the default value is zero, so this option is not needed unless multiple FIFOs have been created.

-n *COUNT*

instructs **halsampler** to read *COUNT* samples from the FIFO, then exit. If **-n** is not specified, **halsampler** will read continuously until it is killed.

-t instructs **halsampler** to tag each line by printing the sample number in the first column.

FILENAME

instructs **halsampler** to write to **FILENAME** instead of to stdout.

USAGE

A FIFO must first be created by loading **sampler**(9) with **halcmd loadrt** or a **loadrt** command in a .hal file. Then **halsampler** can be invoked to begin printing data from the FIFO to stdout.

Data is printed one line per sample. If **-t** was specified, the sample number is printed first. The data follows, in the order that the pins were defined in the config string. For example, if the **sampler** config string was "ffbs" then a typical line of output (without **-t**) would look like:

```
123.55 33.4 0 -12
```

halsampler prints data as fast as possible until the FIFO is empty, then it retries at regular intervals, until it is either killed or has printed *COUNT* samples as requested by **-n**. Usually, but not always, data printed by **halsampler** will be redirected to a file or piped to some other program.

The FIFO size should be chosen to absorb samples captured during any momentary disruptions in the flow of data, such as disk seeks, terminal scrolling, or the processing limitations of subsequent program in a pipeline. If the FIFO gets full and **sampler** is forced to overwrite old data, **halsampler** will print 'overrun' on a line by itself to mark each gap in the sampled data. If **-t** was specified, gaps in the sequential sample numbers in the first column can be used to determine exactly how many samples were lost.

The data format for **halsampler** output is the same as for **halstreamer**(1) input, so 'waveforms' captured with **halsampler** can be replayed using **halstreamer**. The **-t** option should not be used in this case.

EXIT STATUS

If a problem is encountered during initialization, **halsampler** prints a message to stderr and returns failure.

Upon printing *COUNT* samples (if **-n** was specified) it will shut down and return success. If it is terminated before printing the specified number of samples, it returns failure. This means that when **-n** is not specified, it will always return failure when terminated.

SEE ALSO

sampler(9) **streamer**(9) **halstreamer**(1)

HISTORY**BUGS****AUTHOR**

Original version by John Kasunich, as part of the Enhanced Machine Controller (EMC) project.
Improvements by several other members of the EMC development team.

REPORTING BUGS

Report bugs to jmkasunich AT users DOT sourceforge DOT net

COPYRIGHT

Copyright © 2006 John Kasunich.

This is free software; see the source for copying conditions. There is NO warranty; not even for MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE.

NAME

halstreamer – stream file data into HAL in real time

SYNOPSIS

halstreamer [*options*]

DESCRIPTION

streamer(9) and **halstreamer** are used together to stream data from a file into the HAL in real time. **streamer** is a realtime HAL component that exports HAL pins and creates a FIFO in shared memory. **hal_streamer** is a user space program that copies data from stdin into the FIFO, so that **streamer** can write it to the HAL pins.

OPTIONS

-c *CHAN*

instructs **halstreamer** to write to FIFO *CHAN*. FIFOs are numbered from zero, and the default value is zero, so this option is not needed unless multiple FIFOs have been created.

FILENAME

instructs **halsampler** to read from **FILENAME** instead of from stdin.

USAGE

A FIFO must first be created by loading **streamer**(9) with **halscmd loadrt** or a **loadrt** command in a .hal file. Then **halstreamer** can be invoked to begin writing data into the FIFO.

Data is read from stdin, and is almost always either redirected from a file or piped from some other program, since keyboard input would be unable to keep up with even slow streaming rates.

Each line of input must match the pins that are attached to the FIFO, for example, if the **streamer** config string was "ffbs" then each line of input must consist of two floats, a bit, and a signed integer, in that order and separated by whitespace. Floats must be formatted as required by **strtod**(3), signed and unsigned integers must be formatted as required by **strtoul**(3) and **strtol**(3), and bits must be either '0' or '1'.

halstreamer transfers data to the FIFO as fast as possible until the FIFO is full, then it retries at regular intervals, until it is either killed or reads **EOF** from stdin. Data can be redirected from a file or piped from some other program.

The FIFO size should be chosen to ride through any momentary disruptions in the flow of data, such as disk seeks. If the FIFO is big enough, **halstreamer** can be restarted with the same or a new file before the FIFO empties, resulting in a continuous stream of data.

The data format for **halstreamer** input is the same as for **halsampler**(1) output, so 'waveforms' captured with **halsampler** can be replayed using **halstreamer**.

EXIT STATUS

If a problem is encountered during initialization, **halstreamer** prints a message to stderr and returns failure.

If a badly formatted line is encountered while writing to the FIFO, it prints a message to stderr, skips the line, and continues (this behavior may be revised in the future).

Upon reading **EOF** from the input, it returns success. If it is terminated before the input ends, it returns failure.

SEE ALSO

streamer(9) **sampler**(9) **halsampler**(1)

HISTORY

BUGS**AUTHOR**

Original version by John Kasunich, as part of the Enhanced Machine Controller (EMC) project.
Improvements by several other members of the EMC development team.

REPORTING BUGS

Report bugs to jmkasunich AT users DOT sourceforge DOT net

COPYRIGHT

Copyright © 2006 John Kasunich.

This is free software; see the source for copying conditions. There is NO warranty; not even for MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE.

NAME

halui – observe HAL pins and command EMC through NML

SYNOPSIS

halui [-ini <path-to-ini>]

DESCRIPTION

halui is used to build a User Interface using hardware knobs and switches. It exports a big number of pins, and acts accordingly when these change.

OPTIONS**-ini name**

use the *name* as the configuration file. Note: halui must find the nml file specified in the ini, usually that file is in the same folder as the ini, so it makes sense to run halui from that folder.

USAGE

When run, **halui** will export a large number of pins. A user can connect those to his physical knobs & switches & leds, and when a change is noticed halui triggers an appropriate event.

halui expects the signals to be debounced, so if needed (bad knob contact) connect the physical button to a HAL debounce filter first.

EXPORTED PINS**abort**

halui.abort
pin for clearing most errors

home

halui.home-all
pin for requesting home-all

axis

halui.axis.N.pos-commanded
Commanded axis position in machine coordinates

halui.axis.N.pos-feedback
Feedback axis position in machine coordinates

halui.axis.N.pos-relative
Commanded axis position in relative coordinates

estop

halui.estop.activate
pin for setting Estop (emc internal) On

halui.estop.is-activated
pin for displaying Estop state (emc internal) On/Off

halui.estop.reset
pin for resetting Estop (emc internal) Off

feed override

halui.feed-override.count-enable (default: **TRUE**)
When TRUE, modify feed override when counts changes.

halui.feed-override.counts
counts from an encoder to change FO

halui.feed-override.decrease
pin for decreasing the FO (==scale)

halui.feed-override.increase
pin for increasing the FO (+=scale)

halui.feed-override.scale
pin for setting the scale on changing the FO

halui.feed-override.value
current Feed Override value

flood

halui.flood.is-on
pin for flood is on

halui.flood.off
pin for stopping flood

halui.flood.on
pin for starting flood

jog

halui.jog.deadband
pin for setting jog analog deadband (where not to move)

halui.jog.speed
pin for setting jog speed. will be used for minus/plus jogging.

halui.jog.N.analog
pin for jogging the axis N using an float value (e.g. joystick)

halui.jog.N.minus
pin for jogging axis N in negative direction at the *halui.jog.speed* velocity

halui.jog.N.plus
pin for jogging axis N in positive direction at the *halui.jog.speed* velocity

halui.jog.selected.minus
pin for jogging the selected axis in negative direction at the *halui.jog.speed* velocity

halui.jog.selected.plus
pin for jogging the selected axis in positive direction at the *halui.jog.speed* velocity

joint

halui.joint.N.has-fault
status pin telling that joint N has a fault

halui.joint.N.home
pin for homing joint N

halui.joint.N.is-homed
status pin telling that joint N is homed

halui.joint.N.is-selected
status pin that joint N is selected

halui.joint.N.on-hard-max-limit
status pin telling that joint N is on the positive hardware limit

halui.joint.N.on-hard-min-limit
status pin telling that joint N is on the negative hardware limit

halui.joint.N.on-soft-max-limit
status pin telling that joint N is on the positive software limit

halui.joint.N.on-soft-min-limit
status pin telling that joint N is on the negative software limit

halui.joint.N.select
pin for selecting joint N

halui.joint.N.unhome
pin for unhoming joint N

halui.joint.selected
selected joint

halui.joint.selected.has-fault
status pin selected joint is faulted

halui.joint.select
select joint

halui.joint.selected.home
pin for homing the selected joint

halui.joint.selected.is-homed
status pin telling that the selected joint is homed

halui.joint.selected.on-hard-max-limit
status pin telling that the selected joint is on the positive hardware limit

halui.joint.selected.on-hard-min-limit
status pin telling that the selected joint is on the negative hardware limit

halui.joint.selected.on-soft-max-limit
status pin telling that the selected joint is on the positive software limit

halui.joint.selected.on-soft-min-limit
status pin telling that the selected joint is on the negative software limit

halui.joint.selected.unhome
pin for unhoming the selected joint

lube

halui.lube.is-on
pin for lube is on

halui.lube.off
pin for stopping lube

halui.lube.on
pin for starting lube

machine

halui.machine.is-on
pin for machine is On/Off

halui.machine.off
pin for setting machine Off

halui.machine.on
pin for setting machine On

max-velocity

halui.max-velocity.count-enable (default: **TRUE**)
When TRUE, modify max velocity when counts changes.

halui.max-velocity.counts
counts from an encoder for example to change maximum velocity

halui.max-velocity.decrease
pin for decreasing the maximum velocity (==scale)

halui.max-velocity.increase
pin for increasing the maximum velocity (+=scale)

halui.max-velocity.scale
pin for setting the scale on changing the maximum velocity

halui.max-velocity.value
Current value for maximum velocity

mist

halui.mist.is-on
pin for mist is on

halui.mist.off
pin for stopping mist

halui.mist.on
pin for starting mist

mode

halui.mode.auto
pin for requesting auto mode

halui.mode.is-auto
pin for auto mode is on

halui.mode.is-joint
pin showing joint by joint jog mode is on

halui.mode.is-manual
pin for manual mode is on

halui.mode.is-mdi
pin for mdi mode is on

halui.mode.is-teleop
pin showing coordinated jog mode is on

halui.mode.joint
pin for requesting joint by joint jog mode

halui.mode.manual
pin for requesting manual mode

halui.mode.mdi
pin for requesting mdi mode

halui.mode.teleop
pin for requesting coordinated jog mode

program

halui.program.block-delete.is-on
status pin telling that block delete is on

halui.program.block-delete.off
pin for requesting that block delete is off

halui.program.block-delete.on
pin for requesting that block delete is on

halui.program.is-idle
status pin telling that no program is running

halui.program.is-paused
status pin telling that a program is paused

halui.program.is-running
status pin telling that a program is running

halui.program.optional-stop.is-on
status pin telling that the optional stop is on

halui.program.optional-stop.off
pin requesting that the optional stop is off

halui.program.optional-stop.on
pin requesting that the optional stop is on

halui.program.pause
pin for pausing a program

halui.program.resume
pin for resuming a program

halui.program.run
pin for running a program

halui.program.stop
pin for stopping a program (note: this pin does the same thing as *halui.abort*)

halui.program.step
pin for stepping in a program

spindle override

halui.spindle-override.count-enable (default: **TRUE**)
When TRUE, modify spindle override when counts changes.

halui.spindle-override.counts
counts from an encoder for example to change SO

halui.spindle-override.decrease
pin for decreasing the SO (-=scale)

halui.spindle-override.increase
pin for increasing the SO (+=scale)

halui.spindle-override.scale
pin for setting the scale on changing the SO

halui.spindle-override.value
current FO value

spindle

halui.spindle.brake-is-on
status pin that tells us if brake is on

halui.spindle.brake-off
pin for deactivating the spindle brake

halui.spindle.brake-on
pin for activating the spindle brake

halui.spindle.decrease
pin for making the spindle go slower

halui.spindle.forward
a rising edge on this pin makes the spindle go forward

halui.spindle.increase
pin for making the spindle go faster

halui.spindle.in-on
status pin telling if the spindle is on

halui.spindle.reverse
a rising edge on this pin makes the spindle go reverse

halui.spindle.runs-backward
status pin telling if the spindle is running backward

halui.spindle.runs-forward
status pin telling if the spindle is running forward

halui.spindle.start
a rising edge on this pin starts the spindle

halui.spindle.stop
a rising edge on this pin stops the spindle

tool

halui.tool.length-offset.a
current applied tool-length-offset

halui.tool.length-offset.b
current applied tool-length-offset

halui.tool.length-offset.c
current applied tool-length-offset

halui.tool.length-offset.u
current applied tool-length-offset

halui.tool.length-offset.v
current applied tool-length-offset

halui.tool.length-offset.w
current applied tool-length-offset

halui.tool.length-offset.x
current applied tool-length-offset

halui.tool.length-offset.y
current applied tool-length-offset

halui.tool.length-offset.z
current applied tool-length-offset

halui.tool.number
current selected tool

SEE ALSO**HISTORY****BUGS**

none known at this time.

AUTHOR

Written by Alex Joni, as part of the Enhanced Machine Controller (EMC2) project. Updated by John Thornton

REPORTING BUGS

Report bugs to alex_joni AT users DOT sourceforge DOT net

COPYRIGHT

Copyright © 2006 Alex Joni.

This is free software; see the source for copying conditions. There is NO warranty; not even for MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE.

NAME

iocontrol – accepts NML I/O commands, interacts with HAL in userspace

SYNOPSIS

loadusr io [-ini *infile*]

DESCRIPTION

These pins are created by the userspace IO controller, usually found in \$EMC2_HOME/bin/io

The signals are turned on and off in userspace - if you have strict timing requirements or simply need more i/o, consider using the realtime synchronized i/o provided by **motion**(9) instead.

The infile is searched for in the directory from which halcmd was run, unless an absolute path is specified.

PINS**iocontrol.0.coolant-flood**

(Bit, Out) TRUE when flood coolant is requested

iocontrol.0.coolant-mist

(Bit, Out) TRUE when mist coolant is requested

iocontrol.0.emc-enable-in

(Bit, In) Should be driven FALSE when an external estop condition exists.

iocontrol.0.lube

(Bit, Out) TRUE when lube is requested

iocontrol.0.lube_level

(Bit, In) Should be driven FALSE when lubrication tank is empty.

iocontrol.0.tool-change

(Bit, Out) TRUE when a tool change is requested

iocontrol.0.tool-changed

(Bit, In) Should be driven TRUE when a tool change is completed.

iocontrol.0.tool-number

(s32, Out) Current tool number

iocontrol.0.tool-prep-number

(s32, Out) The number of the next tool, from the RS274NGC T-word

iocontrol.0.tool-prep-pocket

(s32, Out) The pocket number (location in tool storage mechanism) of the next tool, as described in the tool table

iocontrol.0.tool-prepare

(Bit, Out) TRUE when a T_n tool prepare is requested

iocontrol.0.tool-prepared

(Bit, In) Should be driven TRUE when a tool prepare is completed.

iocontrol.0.user-enable-out

(Bit, Out) FALSE when an internal estop condition exists

iocontrol.0.user-request-enable

(Bit, Out) TRUE when the user has requested that estop be cleared

SEE ALSO

motion(9)

NAME

pyvcp – Virtual Control Panel for EMC2

SYNOPSIS

pyvcp [-g *WxH+X+Y*] [-c *component-name*] *myfile.xml*

OPTIONS

-g *WxH+X+Y*

This sets the initial geometry of the root window. Use 'WxH' for just size, '+X+Y' for just position, or 'WxH+X+Y' for both. Size / position use pixel units. Position is referenced from top left.

-c *component-name*

Use *component-name* as the HAL component name. If the component name is not specified, the basename of the xml file is used.

SEE ALSO

Virtual Control Panels in the emc2 documentation for a description of the xml syntax, along with examples

NAME

hal – Introduction to the HAL API

DESCRIPTION

HAL stands for Hardware Abstraction Layer, and is used by EMC to transfer realtime data to and from I/O devices and other low-level modules.

hal.h defines the API and data structures used by the HAL. This file is included in both realtime and non-realtime HAL components. HAL uses the RTPAI real time interface, and the #define symbols RTAPI and ULAPI are used to distinguish between realtime and non-realtime code. The API defined in this file is implemented in `hal_lib.c` and can be compiled for linking to either realtime or user space HAL components.

The HAL is a very modular approach to the low level parts of a motion control system. The goal of the HAL is to allow a systems integrator to connect a group of software components together to meet whatever I/O requirements he (or she) needs. This includes realtime and non-realtime I/O, as well as basic motor control up to and including a PID position loop. What these functions have in common is that they all process signals. In general, a signal is a data item that is updated at regular intervals. For example, a PID loop gets position command and feedback signals, and produces a velocity command signal.

HAL is based on the approach used to design electronic circuits. In electronics, off-the-shelf components like integrated circuits are placed on a circuit board and their pins are interconnected to build whatever overall function is needed. The individual components may be as simple as an op-amp, or as complex as a digital signal processor. Each component can be individually tested, to make sure it works as designed. After the components are placed in a larger circuit, the signals connecting them can still be monitored for testing and troubleshooting.

Like electronic components, HAL components have pins, and the pins can be interconnected by signals.

In the HAL, a *signal* contains the actual data value that passes from one pin to another. When a signal is created, space is allocated for the data value. A *pin* on the other hand, is a pointer, not a data value. When a pin is connected to a signal, the pin's pointer is set to point at the signal's data value. This allows the component to access the signal with very little run-time overhead. (If a pin is not linked to any signal, the pointer points to a dummy location, so the realtime code doesn't have to deal with null pointers or treat unlinked variables as a special case in any way.)

There are three approaches to writing a HAL component. Those that do not require hard realtime performance can be written as a single user mode process. Components that need hard realtime performance but have simple configuration and init requirements can be done as a single kernel module, using either pre-defined init info, or `insmod-time` parameters. Finally, complex components may use both a kernel module for the realtime part, and a user space process to handle ini file access, user interface (possibly including GUI features), and other details.

HAL uses the RTAPI/ULAPI interface. If RTAPI is #defined `hal_lib.c` would generate a kernel module `hal_lib.o` that is `insmoded` and provides the functions for all kernel module based components. The same source file compiled with the ULAPI #define would make a user space `hal_lib.o` that is statically linked to user space code to make user space executables. The variable lists and link information are stored in a block of shared memory and protected with mutexes, so that kernel modules and any of several user mode programs can access the data.

REALTIME CONSIDERATIONS

For an explanation of realtime considerations, see **intro(3rtapi)**.

HAL STATUS CODES

Except as noted in specific manual pages, HAL returns negative errno values for errors, and nonnegative values for success.

SEE ALSO

intro(3rtapi)

NAME

hal_add_funct_to_thread – cause a function to be executed at regular intervals

SYNTAX

```
int hal_add_funct_to_thread(const char *funct_name, const char *thread_name,
                           int position)
```

```
int hal_del_funct_from_thread(const char *funct_name, const char *thread_name)
```

ARGUMENTS

funct_name

The name of the function

thread_name

The name of the thread

position

The desired location within the thread. This determines when the function will run, in relation to other functions in the thread. A positive number indicates the desired location as measured from the beginning of the thread, and a negative is measured from the end. So +1 means this function will become the first one to run, +5 means it will be the fifth one to run, -2 means it will be next to last, and -1 means it will be last. Zero is illegal.

DESCRIPTION

hal_add_funct_to_thread adds a function exported by a realtime HAL component to a realtime thread. This determines how often and in what order functions are executed.

hal_del_funct_from_thread removes a function from a thread.

RETURN VALUE

Returns a HAL status code.

REALTIME CONSIDERATIONS

Call only from realtime init code, not from user space or realtime code.

SEE ALSO

hal_thread_new(3hal), **hal_export_funct(3hal)**

NAME

hal_create_thread – Create a HAL thread

SYNTAX

```
int hal_create_thread(const char *name, unsigned long period, int uses_fp)
```

```
int hal_thread_delete(const char *name)
```

ARGUMENTS

name The name of the thread

period The interval, in nanoseconds, between iterations of the thread

uses_fp Must be nonzero if a function which uses floating-point will be attached to this thread.

DESCRIPTION

hal_create_thread establishes a realtime thread that will execute one or more HAL functions periodically.

All thread periods are rounded to integer multiples of the hardware timer period, and the timer period is based on the first thread created. Threads must be created in order, from the fastest to the slowest. HAL assigns decreasing priorities to threads that are created later, so creating them from fastest to slowest results in rate monotonic priority scheduling.

hal_delete_thread deletes a previously created thread.

REALTIME CONSIDERATIONS

Call only from realtime init code, not from user space or realtime code.

RETURN VALUE

Returns a HAL status code.

SEE ALSO

hal_export_funct(3hal)

NAME

hal_exit – Shut down HAL

SYNTAX

```
int hal_exit(int comp_id)
```

ARGUMENTS

comp_id

A HAL component identifier returned by an earlier call to **hal_init**.

DESCRIPTION

hal_exit shuts down and cleans up HAL and RTAPI. It must be called prior to exit by any module that called **hal_init**.

REALTIME CONSIDERATIONS

Call only from within user or init/cleanup code, not from realtime tasks.

RETURN VALUE

Returns a HAL status code.

NAME

hal_export_funct – create a realtime function callable from a thread

SYNTAX

```
typedef void(*hal_funct_t)(void * arg, long period)
int hal_export_funct(const char *name, hal_funct_t funct, void *arg, int uses_fp, int reentrant, int comp_id)
```

ARGUMENTS

name The name of the function.

funct The pointer to the function

arg The argument to be passed as the first parameter of *funct*

uses_fp Nonzero if the function uses floating-point operations, including assignment of floating point values with "=".

reentrant

If *reentrant* is non-zero, the function may be preempted and called again before the first call completes. Otherwise, it may only be added to one thread.

comp_id

A HAL component identifier returned by an earlier call to **hal_init**.

DESCRIPTION

hal_export_funct makes a realtime function provided by a component available to the system. A subsequent call to **hal_add_funct_to_thread** can be used to schedule the execution of the function as needed by the system.

When this function is placed on a HAL thread, and HAL threads are started, *funct* is called repeatedly with two arguments: *void *arg* is the same value that was given to **hal_export_funct**, and *long period* is the interval between calls in nanoseconds.

Each call to the function should do a small amount of work and return.

RETURN VALUE

Returns a HAL status code.

SEE ALSO

hal_create_thread(3hal), **hal_add_funct_to_thread(3hal)**

NAME

hal_init – Sets up HAL and RTAPI

SYNTAX

```
int hal_init(const char *modname)
```

ARGUMENTS

modname

The name of this hal module

DESCRIPTION

hal_init sets up HAL and RTAPI. It must be called by any module that intends to use the API, before any other RTAPI calls.

modname can optionally point to a string that identifies the module. The string will be truncated at **RTAPI_NAME_LEN** characters. If *modname* is **NULL**, the system will assign a name.

REALTIME CONSIDERATIONS

Call only from within user or init/cleanup code, not from realtime tasks.

RETURN VALUE

On success, returns a positive integer module ID, which is used for subsequent calls to hal and rtapi APIs. On failure, returns a HAL error code.

NAME

hal_malloc – Allocate space in the HAL shared memory area

SYNTAX

```
void *hal_malloc(long int size)
```

ARGUMENTS

size Gives the size, in bytes, of the block

DESCRIPTION

hal_malloc allocates a block of memory from the main HAL shared memory area. It should be used by all components to allocate memory for HAL pins and parameters. It allocates ‘size’ bytes, and returns a pointer to the allocated space, or NULL (0) on error. The returned pointer will be properly aligned for any type HAL supports. A component should allocate during initialization all the memory it needs.

The allocator is very simple, and there is no ‘free’. The entire HAL shared memory area is freed when the last component calls **hal_exit**. This means that if you continuously install and remove one component while other components are present, you eventually will fill up the shared memory and an install will fail. Removing all components completely clears memory and you start fresh.

RETURN VALUE

A pointer to the allocated space, which is properly aligned for any variable HAL supports. Returns NULL on error.

NAME

hal_param_new – Create a HAL parameter

SYNTAX

```
int hal_param_bit_new(const char *name, hal_param_dir_t dir, hal_bit_t * data_addr, int comp_id)
```

```
int hal_param_float_new(const char *name, hal_param_dir_t dir, hal_float_t * data_addr, int comp_id)
```

```
int hal_param_u32_new(const char *name, hal_param_dir_t dir, hal_u32_t * data_addr, int comp_id)
```

```
int hal_param_s32_new(const char *name, hal_param_dir_t dir, hal_s32_t * data_addr, int comp_id)
```

```
int hal_param_bit_newf(hal_param_dir_t dir, hal_bit_t * data_addr, int comp_id, const char *fmt, ...)
```

```
int hal_param_float_newf(hal_param_dir_t dir, hal_float_t * data_addr, int comp_id, const char *fmt, ...)
```

```
int hal_param_u32_newf(hal_param_dir_t dir, hal_u32_t * data_addr, int comp_id, const char *fmt, ...)
```

```
int hal_param_s32_newf(hal_param_dir_t dir, hal_s32_t * data_addr, int comp_id, const char *fmt, ...)
```

```
int hal_param_new(const char *name, hal_type_t type, hal_in_dir_t dir, void *data_addr, int comp_id)
```

ARGUMENTS

name The name to give to the created parameter

dir The direction of the parameter, from the viewpoint of the component. It may be one of **HAL_RO**, or **HAL_RW**. A component may assign a value to any parameter, but other programs (such as hal-cmd) may only assign a value to a parameter that is **HAL_RW**.

data_addr

The address of the data, which must lie within memory allocated by **hal_malloc**.

comp_id

A HAL component identifier returned by an earlier call to **hal_init**.

fmt, ... A printf-style format string and arguments

type The type of the parameter, as specified in **hal_type_t(3hal)**.

DESCRIPTION

The **hal_param_new** family of functions create a new *param* object.

There are functions for each of the data types that the HAL supports. Pins may only be linked to signals of the same type.

RETURN VALUE

Returns a HAL status code.

SEE ALSO

hal_type_t(3hal)

NAME

hal_pin_new – Create a HAL pin

SYNTAX

```
int hal_pin_bit_new(const char *name, hal_pin_dir_t dir, hal_bit_t ** data_ptr_addr, int comp_id)
```

```
int hal_pin_float_new(const char *name, hal_pin_dir_t dir, hal_float_t ** data_ptr_addr, int comp_id)
```

```
int hal_pin_u32_new(const char *name, hal_pin_dir_t dir, hal_u32_t ** data_ptr_addr, int comp_id)
```

```
int hal_pin_s32_new(const char *name, hal_pin_dir_t dir, hal_s32_t ** data_ptr_addr, int comp_id)
```

```
int hal_pin_bit_newf(hal_pin_dir_t dir, hal_bit_t ** data_ptr_addr, int comp_id, const char *fmt, ...)
```

```
int hal_pin_float_newf(hal_pin_dir_t dir, hal_float_t ** data_ptr_addr, int comp_id, const char *fmt, ...)
```

```
int hal_pin_u32_newf(hal_pin_dir_t dir, hal_u32_t ** data_ptr_addr, int comp_id, const char *fmt, ...)
```

```
int hal_pin_s32_newf(hal_pin_dir_t dir, hal_s32_t ** data_ptr_addr, int comp_id, const char *fmt, ...)
```

```
int hal_pin_new(const char *name, hal_type_t type, hal_in_dir_t dir, void **data_ptr_addr, int comp_id)
```

ARGUMENTS

name The name of the pin

dir

The direction of the pin, from the viewpoint of the component. It may be one of **HAL_IN**, **HAL_OUT**, or **HAL_IO**. Any number of **HAL_IN** or **HAL_IO** pins may be connected to the same signal, but at most one **HAL_OUT** pin is permitted. A component may assign a value to a pin that is **HAL_OUT** or **HAL_IO**, but may not assign a value to a pin that is **HAL_IN**.

data_ptr_addr

The address of the pointer-to-data, which must lie within memory allocated by **hal_malloc**.

comp_id

A HAL component identifier returned by an earlier call to **hal_init**.

fmt,

A printf-style format string and arguments

type

The type of the param, as specified in **hal_type_t(3hal)**.

DESCRIPTION

The **hal_pin_new** family of functions create a new *pin* object. Once a pin has been created, it can be linked to a signal object using **hal_link**. A pin contains a pointer, and the component that owns the pin can dereference the pointer to access whatever signal is linked to the pin. (If no signal is linked, it points to a dummy signal.)

There are functions for each of the data types that the HAL supports. Pins may only be linked to signals of the same type.

RETURN VALUE

Returns a HAL status code.

SEE ALSO

hal_type_t(3hal), **hal_link(3hal)**

NAME

`hal_ready` – indicates that this component is ready

SYNTAX

```
hal_ready(int comp_id)
```

ARGUMENTS

comp_id

A HAL component identifier returned by an earlier call to **hal_init**.

DESCRIPTION

hal_ready indicates that this component is ready (has created all its pins, parameters, and functions). This must be called in any realtime HAL component before its **rtapi_app_init** exits, and in any userspace component before it enters its main loop.

RETURN VALUE

Returns a HAL status code.

NAME

hal_set_constructor – Set the constructor function for this component

SYNTAX

```
typedef int (*hal_constructor_t)(const char *prefix, const char *arg); int hal_set_constructor(int comp_id,  
hal_constructor_t constructor)
```

ARGUMENTS

comp_id A HAL component identifier returned by an earlier call to **hal_init**.

prefix The prefix to be given to the pins, parameters, and functions in the new instance

arg An argument that may be used by the component to customize this instance.

DESCRIPTION

As an experimental feature in HAL 2.1, components may be *constructable*. Such a component may create pins and parameters not only at the time the module is loaded, but it may create additional pins and parameters, and functions on demand.

RETURN VALUE

Returns a HAL status code.

SEE ALSO

halcmd(1)

NAME

hal_set_lock, hal_get_lock – Set or get the HAL lock level

SYNTAX

```
int hal_set_lock(unsigned char lock_type)
```

```
int hal_get_lock()
```

ARGUMENTS

lock_type

The desired lock type, which may be a bitwise combination of: **HAL_LOCK_LOAD**, **HAL_LOCK_CONFIG**, **HAL_LOCK_PARAMS**, or **HAL_LOCK_PARAMS**. **HAL_LOCK_NONE** or 0 locks nothing, and **HAL_LOCK_ALL** locks everything.

DESCRIPTION**RETURN VALUE**

hal_set_lock Returns a HAL status code. **hal_get_lock** returns the current HAL lock level or a HAL status code.

NAME

hal_signal_new, hal_signal_delete, hal_link, hal_unlink – Manipulate HAL signals

SYNTAX

```
int hal_signal_new(const char *signal_name, hal_type_t type)
```

```
int hal_signal_delete(const char *signal_name)
```

```
int hal_link(const char *pin_name, const char *signal_name)
```

```
int hal_unlink(const char *pin_name)
```

ARGUMENTS

signal_name

The name of the signal

pin_name

The name of the pin

type The type of the signal, as specified in **hal_type_t(3hal)**.

DESCRIPTION

hal_signal_new creates a new signal object. Once a signal has been created, pins can be linked to it with **hal_link**. The signal object contains the actual storage for the signal data. Pin objects linked to the signal have pointers that point to the data. 'name' is the name of the new signal. If longer than HAL_NAME_LEN it will be truncated. If there is already a signal with the same name the call will fail.

hal_link links a pin to a signal. If the pin is already linked to the desired signal, the command succeeds. If the pin is already linked to some other signal, it is an error. In either case, the existing connection is not modified. (Use 'hal_unlink' to break an existing connection.) If the signal already has other pins linked to it, they are unaffected - one signal can be linked to many pins, but a pin can be linked to only one signal.

hal_unlink unlinks any signal from the specified pin.

hal_signal_delete deletes a signal object. Any pins linked to the object are unlinked.

RETURN VALUE

Returns a HAL status code.

SEE ALSO

hal_type_t(3hal)

NAME

hal_start_threads – Allow HAL threads to begin executing

SYNTAX

```
int hal_start_threads()
```

```
int hal_stop_threads()
```

ARGUMENTS**DESCRIPTION**

hal_start_threads starts all threads that have been created. This is the point at which realtime functions start being called.

hal_stop_threads stops all threads that were previously started by **hal_start_threads**. It should be called before any component that is part of a system exits.

RETURN VALUE

Returns a HAL status code.

SEE ALSO

hal_export_funct(3hal), hal_create_thread(3hal), hal_add_funct_to_thread(3hal)

NAME

hal_type_t – typedefs for HAL datatypes

DESCRIPTION

typedef ... **hal_bit_t**;

A volatile type which may have a value of 0 or nonzero.

typedef ... **hal_s32_t**;

A volatile type which may have a value from -2147483648 to 2147483647.

typedef ... **hal_u32_t**;

A volatile type which may have a value from 0 to 4294967295.

typedef ... **hal_float_t**;

A volatile floating-point type, which typically has the same precision and range as the C type **double**.

typedef ... **real_t**;

A nonvolatile floating-point type with at least as much precision as **hal_float_t**.

typedef ... **ireal_t**;

A nonvolatile unsigned integral type the same size as **hal_float_t**.

typedef enum **hal_type_t**;

HAL_BIT

Corresponds to the type **hal_bit_t**.

HAL_FLOAT

Corresponds to the type **hal_float_t**.

HAL_S32

Corresponds to the type **hal_s32_t**.

HAL_U32

Corresponds to the type **hal_u32_t**.

NOTES

hal_bit_t is typically a typedef to an integer type whose range is larger than just 0 and 1. When testing the value of a **hal_bit_t**, never compare it to 1. Prefer one of the following:

- if(b)
- if(b != 0)

SEE ALSO

hal_pin_new(3hal), **hal_param_new(3hal)**

NAME

undocumented – undocumented functions in HAL

SEE ALSO

The header file *hal.h*. Most hal functions have documentation in that file.

NAME

rtapi – Introduction to the RTAPI API

DESCRIPTION

RTAPI is a library providing a uniform API for several real time operating systems. As of ver 2.1, RTLinux, RTAI, and a pure userspace simulator are supported.

HEADER FILES

rtapi.h

The file **rtapi.h** defines the RTAPI for both realtime and non-realtime code. This is a change from Rev 2, where the non-realtime (user space) API was defined in `ulapi.h` and used different function names. The symbols `RTAPI` and `ULAPI` are used to determine which mode is being compiled, `RTAPI` for realtime and `ULAPI` for non-realtime.

rtapi_math.h

The file `rtapi_math.h` defines floating-point functions and constants. It should be used instead of `<math.h>` in `rtapi` real-time components.

rtapi_string.h

The file `rtapi_string.h` defines string-related functions. It should be used instead of `<string.h>` in `rtapi` real-time components.

REALTIME CONSIDERATIONS

Userspace code

Certain functions are not available in userspace code. This includes functions that perform direct device access such as **rtapi_inb(3)**.

Init/cleanup code

Certain functions may only be called from realtime init/cleanup code. This includes functions that perform memory allocation, such as **rtapi_shmem_new(3)**.

Realtime code

Only a few functions may be called from realtime code. This includes functions that perform direct device access such as **rtapi_inb(3)**. It excludes most Linux kernel APIs such as `do_gettimeofday(3)` and many `rtapi` APIs such as `rtapi_shmem_new(3)`.

Simulator

For an RTAPI module to be buildable in the "sim" environment (fake realtime system without special privileges), it must not use **any** linux kernel APIs, and must not use the RTAPI APIs for direct device access such as **rtapi_inb(3)**. This automatically includes any hardware device drivers, and also devices which use Linux kernel APIs to do things like create special devices or entries in the **/proc** filesystem.

RTAPI STATUS CODES

Except as noted in specific manual pages, RTAPI returns negative `errno` values for errors, and nonnegative values for success.

NAME

rtapi_app_exit – User-provided function to shut down a component

SYNTAX

```
void rtapi_app_exit(void) { ... }
```

ARGUMENTS

None

DESCRIPTION

The body of **rtapi_app_exit**, which is provided by the component author, generally consists of a call to **rtapi_exit** or **hal_exit**, preceded by other component-specific shutdown code.

This code is called when unloading a component which successfully initialized (i.e., returned zero from its **rtapi_app_main**). It is not called when the component did not successfully initialize.

RETURN CODE

None.

REALTIME CONSIDERATIONS

Called automatically by the rtapi infrastructure in an initialization (not realtime) context.

SEE ALSO

rtapi_app_main(3rtapi), **rtapi_exit(3rtapi)**, **hal_exit(3hal)**

NAME

rtapi_app_main – User-provided function to initialize a component

SYNTAX

```
#include "rtapi_app.h" int rtapi_app_main(void) { ... }
```

ARGUMENTS

None

DESCRIPTION

The body of **rtapi_app_main**, which is provided by the component author, generally consists of a call to **rtapi_init** or **hal_init**, followed by other component-specific initialization code.

RETURN VALUE

Return 0 for success. Return a negative errno value (e.g., -EINVAL) on error. Existing code also returns RTAPI or HAL error values, but using negative errno values gives better diagnostics from insmod.

REALTIME CONSIDERATIONS

Called automatically by the rtapi infrastructure in an initialization (not realtime) context.

SEE ALSO

rtapi_app_exit(3rtapi), **rtapi_init(3rtapi)**, **hal_init(3hal)**

NAME

rtapi_clock_set_period – set the basic time interval for realtime tasks

SYNTAX

```
rtapi_clock_set_period(long int nsec)
```

ARGUMENTS

nsec The desired basic time interval for realtime tasks.

DESCRIPTION

rtapi_clock_set_period sets the basic time interval for realtime tasks. All periodic tasks will run at an integer multiple of this period. The first call to **rtapi_clock_set_period** with *nsec* greater than zero will start the clock, using *nsec* as the clock period in nano-seconds. Due to hardware and RTOS limitations, the actual period may not be exactly what was requested. On success, the function will return the actual clock period if it is available, otherwise it returns the requested period. If the requested period is outside the limits imposed by the hardware or RTOS, it returns **-EINVAL** and does not start the clock. Once the clock is started, subsequent calls with non-zero *nsec* return **-EINVAL** and have no effect. Calling **rtapi_clock_set_period** with *nsec* set to zero queries the clock, returning the current clock period, or zero if the clock has not yet been started.

REALTIME CONSIDERATIONS

Call only from within init/cleanup code, not from realtime tasks. This function is not available from user (non-realtime) code.

RETURN VALUE

The actual period provided by the RTOS, which may be different than the requested period, or a RTAPI status code.

NAME

rtapi_delay – Busy-loop for short delays

SYNTAX

void rtapi_delay(long int *nsec*)

void rtapi_delay_max()

ARGUMENTS

nsec The desired delay length in nanoseconds

DESCRIPTION

rtapi_delay is a simple delay. It is intended only for short delays, since it simply loops, wasting CPU cycles.

rtapi_delay_max returns the max delay permitted (usually approximately 1/4 of the clock period). Any call to **rtapi_delay** requesting a delay longer than the max will delay for the max time only.

rtapi_delay_max should be called before using **rtapi_delay** to make sure the required delays can be achieved. The actual resolution of the delay may be as good as one nano-second, or as bad as a several microseconds.

REALTIME CONSIDERATIONS

May be called from init/cleanup code, and from within realtime tasks.

RETURN VALUE

rtapi_delay_max returns the maximum delay permitted.

SEE ALSO

rtapi_clock_set_period(3rtapi)

NAME

rtapi_exit – Shut down RTAPI

SYNTAX

```
int rtapi_exit(int module_id)
```

ARGUMENTS

module_id

An rtapi module identifier returned by an earlier call to **rtapi_init**.

DESCRIPTION

rtapi_exit shuts down and cleans up the RTAPI. It must be called prior to exit by any module that called **rtapi_init**.

REALTIME CONSIDERATIONS

Call only from within user or init/cleanup code, not from realtime tasks.

RETURN VALUE

Returns a RTAPI status code.

NAME

rtapi_get_time – get the current time

SYNTAX

```
long long rtapi_get_time()
long long rtapi_get_clocks()
```

DESCRIPTION

rtapi_get_time returns the current time in nanoseconds. Depending on the RTOS, this may be time since boot, or time since the clock period was set, or some other time. Its absolute value means nothing, but it is monotonically increasing and can be used to schedule future events, or to time the duration of some activity. Returns a 64 bit value. The resolution of the returned value may be as good as one nano-second, or as poor as several microseconds. May be called from init/cleanup code, and from within realtime tasks.

Experience has shown that the implementation of this function in some RTOS/Kernel combinations is horrible. It can take up to several microseconds, which is at least 100 times longer than it should, and perhaps a thousand times longer. Use it only if you **MUST** have results in seconds instead of clocks, and use it sparingly. In most cases, **rtapi_get_clocks** should be used instead.

rtapi_get_clocks returns the current time in CPU clocks. It is fast, since it just reads the TSC in the CPU instead of calling a kernel or RTOS function. Of course, times measured in CPU clocks are not as convenient, but for relative measurements this works fine. Its absolute value means nothing, but it is monotonically increasing and can be used to schedule future events, or to time the duration of some activity. (on SMP machines, the two TSC's may get out of sync, so if a task reads the TSC, gets swapped to the other CPU, and reads again, the value may decrease. RTAPI tries to force all RT tasks to run on one CPU.) Returns a 64 bit value. The resolution of the returned value is one CPU clock, which is usually a few nanoseconds to a fraction of a nanosecond.

Note that *long long* math may be poorly supported on some platforms, especially in kernel space. Also note that `rtapi_print()` will NOT print *long longs*. Most time measurements are relative, and should be done like this:

```
deltat = (long int)(end_time - start_time);
```

where `end_time` and `start_time` are `longlong` values returned from `rtapi_get_time`, and `deltat` is an ordinary `long int` (32 bits). This will work for times up to a second or so, depending on the CPU clock frequency. It is best used for millisecond and microsecond scale measurements though.

RETURN VALUE

Returns the current time in nanoseconds or CPU clocks.

NOTES

Certain versions of the Linux kernel provide a global variable **cpu_khz**. Computing

```
deltat = (end_clocks - start_clocks) / cpu_khz;
```

gives the duration measured in milliseconds. Computing

```
deltat = (end_clocks - start_clocks) * 1000000 / cpu_khz;
```

gives the duration measured in nanoseconds for deltas less than about 9 trillion clocks (e.g., 3000 seconds at 3GHz).

REALTIME CONSIDERATIONS

May be called from init/cleanup code and from within realtime tasks. Not available in userspace components.

NAME

rtapi_init – Sets up RTAPI

SYNTAX

```
int rtapi_init(const char *modname)
```

ARGUMENTS

modname

The name of this rtapi module

DESCRIPTION

rtapi_init sets up the RTAPI. It must be called by any module that intends to use the API, before any other RTAPI calls.

modname can optionally point to a string that identifies the module. The string will be truncated at **RTAPI_NAME_LEN** characters. If *modname* is **NULL**, the system will assign a name.

REALTIME CONSIDERATIONS

Call only from within user or init/cleanup code, not from realtime tasks.

RETURN VALUE

On success, returns a positive integer module ID, which is used for subsequent calls to `rtapi_xxx_new`, `rtapi_xxx_delete`, and `rtapi_exit`. On failure, returns an RTAPI error code.

NAME

rtapi_module_param – Specifying module parameters

SYNTAX

RTAPI_MP_INT(*var, description*)

RTAPI_MP_LONG(*var, description*)

RTAPI_MP_STRING(*var, description*)

RTAPI_MP_ARRAY_INT(*var, num, description*)

RTAPI_MP_ARRAY_LONG(*var, num, description*)

RTAPI_MP_ARRAY_STRING(*var, num, description*)

MODULE_LICENSE(*license*)

MODULE_AUTHOR(*author*)

MODULE_DESCRIPTION(*description*)

EXPORT_FUNCTION(*function*)

ARGUMENTS

var The variable where the parameter should be stored

description

A short description of the parameter or module

num The maximum number of values for an array parameter

license The license of the module, for instance "GPL"

author The author of the module

function

The pointer to the function to be exported

DESCRIPTION

These macros are portable ways to declare kernel module parameters. They must be used in the global scope, and are not followed by a terminating semicolon. They must be used after the associated variable or function has been defined.

NOTES

EXPORT_FUNCTION makes a symbol available for use by a subsequently loaded component. It is unrelated to hal functions, which are described in hal_export_funct(3hal)

REALTIME CONSIDERATIONS

Not available in userspace code.

NAME

rtapi_mutex – Mutex-related functions

SYNTAX

```
int rtapi_mutex_try(unsigned long *mutex)
```

```
void rtapi_mutex_get(unsigned long *mutex)
```

```
void rtapi_mutex_give(unsigned long *mutex)
```

ARGUMENTS

mutex A pointer to the mutex.

DESCRIPTION

rtapi_mutex_try makes a non-blocking attempt to get the mutex. If the mutex is available, it returns 0, and the mutex is no longer available. Otherwise, it returns a nonzero value.

rtapi_mutex_get blocks until the mutex is available.

rtapi_mutex_give releases a mutex acquired by **rtapi_mutex_try** or **rtapi_mutex_get**.

REALTIME CONSIDERATIONS

rtapi_mutex_give and **rtapi_mutex_try** may be used from user, init/cleanup, and realtime code.

rtapi_mutex_get may not be used from realtime code.

RETURN VALUE

rtapi_mutex_try returns 0 for if the mutex was claimed, and nonzero otherwise.

rtapi_mutex_get and **rtapi_mutex_gif** have no return value.

NAME

rtapi_outb, rtapi_inb – Perform hardware I/O

SYNTAX

void rtapi_outb(unsigned char *byte*, unsigned int *port*)

unsigned char rtapi_inb(unsigned int *port*)

ARGUMENTS

port The address of the I/O port

byte The byte to be written to the port

DESCRIPTION

rtapi_outb writes a byte to a hardware I/O port. **rtapi_inb** reads a byte from a hardware I/O port.

REALTIME CONSIDERATIONS

May be called from init/cleanup code and from within realtime tasks. Not available in userspace components.

RETURN VALUE

rtapi_inb returns the byte read from the given I/O port

NOTES

The I/O address should be within a region previously allocated by **rtapi_request_region**. Otherwise, another real-time module or the Linux kernel might attempt to access the I/O region at the same time.

SEE ALSO

rtapi_region(3rtapi)

NAME

rtapi_print, rtapi_print_msg – print diagnostic messages

SYNTAX

```
void rtapi_print(const char *fmt, ...)
```

```
void rtapi_print_msg(int level, const char *fmt, ...)
```

```
typedef void(*rtapi_msg_handler_t)(msg_level_t level, const char *msg);
```

```
void rtapi_set_msg_handler(rtapi_msg_handler_t handler);
```

```
rtapi_msg_handler_t rtapi_set_msg_handler(void);
```

ARGUMENTS

level A message level: One of **RTAPI_MSG_ERR**, **RTAPI_MSG_WARN**, **RTAPI_MSG_INFO**, or **RTAPI_MSG_DBG**.

handler

A function to call from **rtapi_print** or **rtapi_print_msg** to actually output the message.

fmt

... Other arguments are as for *printf(3)*.

DESCRIPTION

rtapi_print and **rtapi_print_msg** work like the standard C printf functions, except that a reduced set of formatting operations are supported.

Depending on the RTOS, the default may be to print the message to stdout, stderr, a kernel log, etc. In RTAPI code, the action may be changed by a call to **rtapi_set_msg_handler**. A **NULL** argument to **rtapi_set_msg_handler** restores the default handler. **rtapi_msg_get_handler** returns the current handler. When the message came from **rtapi_print**, *level* is **RTAPI_MSG_ALL**.

rtapi_print_msg works like **rtapi_print** but only prints if *level* is less than or equal to the current message level.

REALTIME CONSIDERATIONS

rtapi_print and **rtapi_print_msg** May be called from user, init/cleanup, and realtime code. **rtapi_get_msg_handler** and **rtapi_set_msg_handler** may be called from realtime init/cleanup code. A message handler passed to **rtapi_set_msg_handler** may only call functions that can be called from real-time code.

RETURN VALUE

None.

rtapi_print(3rtapi)

RTAPI

rtapi_print(3rtapi)

SEE ALSO

rtapi_set_msg_level(3rtapi), rtapi_get_msg_level(3rtapi), printf(3)

NAME

rtapi_prio – thread priority functions

SYNTAX

int rtapi_prio_highest()

int rtapi_prio_lowest()

int rtapi_prio_next_higher(int *prio*)

int rtapi_prio_next_lower(int *prio*)

ARGUMENTS

prio A value returned by a prior **rtapi_prio_xxx** call

DESCRIPTION

The **rtapi_prio_xxxx** functions provide a portable way to set task priority. The mapping of actual priority to priority number depends on the RTOS. Priorities range from **rtapi_prio_lowest** to **rtapi_prio_highest**, inclusive. To use this API, use one of two methods:

- 1) Set your lowest priority task to **rtapi_prio_lowest**, and for each task of the next lowest priority, set their priorities to **rtapi_prio_next_higher(previous)**.
- 2) Set your highest priority task to **rtapi_prio_highest**, and for each task of the next highest priority, set their priorities to **rtapi_prio_next_lower(previous)**.

N.B. A high priority task will pre-empt or interrupt a lower priority task. Linux is always the lowest priority!

REALTIME CONSIDERATIONS

Call these functions only from within init/cleanup code, not from realtime tasks.

RETURN VALUE

Returns an opaque real-time priority number.

SEE ALSO

rtapi_task_new(3rtapi)

NAME

rtapi_region – functions to manage I/O memory regions

SYNTAX

```
void *rtapi_request_region(unsigned long base, unsigned long int size, const char *name)
```

```
void rtapi_release_region(unsigned long base, unsigned long int size)
```

ARGUMENTS

base The base address of the I/O region

size The size of the I/O region

name The name to be shown in /proc/ioports

DESCRIPTION

rtapi_request_region reserves I/O memory starting at *base* and going for *size* bytes.

REALTIME CONSIDERATIONS

May be called from realtime init/cleanup code only.

BUGS

On kernels before 2.4.0, **rtapi_request_region** always succeeds.

RETURN VALUE

rtapi_request_region returns NULL if the allocation fails, and a non-NULL value otherwise.

rtapi_release_region has no return value.

NAME

rtapi_get_msg_level, rtapi_set_msg_level – Get or set the logging level

SYNTAX

```
int rtapi_set_msg_level(int level)
```

```
int rtapi_get_msg_level()
```

ARGUMENTS

level The desired logging level

DESCRIPTION

Get or set the RTAPI message level used by **rtapi_print_msg**. Depending on the RTOS, this level may apply to a single RTAPI module, or it may apply to a group of modules.

REALTIME CONSIDERATIONS

May be called from user, init/cleanup, and realtime code.

RETURN VALUE

rtapi_set_msg_level returns a status code, and **rtapi_get_msg_level** returns the current level.

SEE ALSO

rtapi_print_msg(3rtapi)

NAME

rtapi_shmem – Functions for managing shared memory blocks

SYNTAX

```
int rtapi_shmem_new(int key, int module_id, unsigned long int size)
```

```
int rtapi_shmem_delete(int shmem_id, int module_id)
```

```
int rtapi_shmem_getptr(int shmem_id, void ** ptr)
```

ARGUMENTS

key Identifies the memory block. Key must be nonzero. All modules wishing to use the same memory must use the same key.

module_id
Module identifier returned by a prior call to **rtapi_init**.

size The desired size of the shared memory block, in bytes

ptr The pointer to the shared memory block. Note that the block may be mapped at a different address for different modules.

DESCRIPTION

rtapi_shmem_new allocates a block of shared memory. *key* identifies the memory block, and must be nonzero. All modules wishing to access the same memory must use the same key. *module_id* is the ID of the module that is making the call (see **rtapi_init**). The block will be at least *size* bytes, and may be rounded up. Allocating many small blocks may be very wasteful. When a particular block is allocated for the first time, the first 4 bytes are zeroed. Subsequent allocations of the same block by other modules or processes will not touch the contents of the block. Applications can use those bytes to see if they need to initialize the block, or if another module already did so. On success, it returns a positive integer ID, which is used for all subsequent calls dealing with the block. On failure it returns a negative error code.

rtapi_shmem_delete frees the shared memory block associated with *shmem_id*. *module_id* is the ID of the calling module. Returns a status code.

rtapi_shmem_getptr sets **ptr* to point to shared memory block associated with *shmem_id*.

REALTIME CONSIDERATIONS

rtapi_shmem_getptr may be called from user code, init/cleanup code, or realtime tasks.

rtapi_shmem_new and **rtapi_shmem_dete** may not be called from realtime tasks.

RETURN VALUE

NAME

rtapi_sprintf, rtapi_vsnprintf – Perform sprintf-like string formatting

SYNTAX

```
int rtapi_sprintf(char *buf, unsigned long int size, const char *fmt, ...)
```

```
int rtapi_vsnprintf(char *buf, unsigned long int size, const char *fmt, va_list apfB)
```

ARGUMENTS

As for *sprintf(3)* or *vsnprintf(3)*.

DESCRIPTION

These functions work like the standard C printf functions, except that a reduced set of formatting operations are supported.

REALTIME CONSIDERATIONS

May be called from user, init/cleanup, and realtime code.

RETURN VALUE

The number of characters written to *buf*.

SEE ALSO

printf(3)

NAME

`rtapi_task_new` – create a realtime task

SYNTAX

```
int rtapi_task_new(void (*taskcode)(void*), void *arg,          int prio, unsigned long stacksize, int
                   uses_fp)
int rtapi_task_delete(int task_id)
```

ARGUMENTS

taskcode

A pointer to the function to be called when the task is started

arg

An argument to be passed to the *taskcode* function when the task is started

prio

A task priority value returned by **rtapi_prio_xxxx**

uses_fp

A flag that tells the OS whether the task uses floating point or not.

task_id

A task ID returned by a previous call to **rtapi_task_new**

DESCRIPTION

rtapi_task_new creates but does not start a realtime task. The task is created in the "paused" state. To start it, call either **rtapi_task_start** for periodic tasks, or **rtapi_task_resume** for free-running tasks.

REALTIME CONSIDERATIONS

Call only from within init/cleanup code, not from realtime tasks.

RETURN VALUE

On success, returns a positive integer task ID. This ID is used for all subsequent calls that need to act on the task. On failure, returns an RTAPI status code.

SEE ALSO

rtapi_prio(3rtapi), **rtapi_task_start(3rtapi)**, **rtapi_task_wait(3rtapi)**, **rtapi_task_resume(3rtapi)**

NAME

rtapi_task_pause, rtapi_task_resume – pause and resume real-time tasks

SYNTAX

void rtapi_task_pause(int *task_id*)

void rtapi_task_resume(int *task_id*)

ARGUMENTS

task_id An RTAPI task identifier returned by an earlier call to **rtapi_task_new**.

DESCRIPTION

rtapi_task_resume starts a task in free-running mode. The task must be in the "paused" state.

A free running task runs continuously until either:

- 1) It is preempted by a higher priority task. It will resume as soon as the higher priority task releases the CPU.
- 2) It calls a blocking function, like **rtapi_sem_take**. It will resume when the function unblocks.
- 3) It is returned to the "paused" state by **rtapi_task_pause**. May be called from init/cleanup code, and from within realtime tasks.

rtapi_task_pause causes a task to stop execution and change to the "paused" state. The task can be free-running or periodic. Note that **rtapi_task_pause** may called from any task, or from init or cleanup code, not just from the task that is to be paused. The task will resume execution when either **rtapi_task_resume** or **rtapi_task_start** (depending on whether this is a free-running or periodic task) is called.

REALTIME CONSIDERATIONS

May be called from init/cleanup code, and from within realtime tasks.

RETURN VALUE

An RTAPI status code.

SEE ALSO

rtapi_task_new(3rtapi), **rtapi_task_start(3rtapi)**

NAME

rtapi_task_start – start a realtime task in periodic mode

SYNTAX

int rtapi_task_start(int *task_id*, unsigned long *period_nsec*)

ARGUMENTS

task_id A task ID returned by a previous call to **rtapi_task_new**

period_nsec

The clock period in nanoseconds between iterations of a periodic task

DESCRIPTION

rtapi_task_start starts a task in periodic mode. The task must be in the *paused* state.

REALTIME CONSIDERATIONS

Call only from within init/cleanup code, not from realtime tasks.

RETURN VALUE

Returns an RTAPI status code.

SEE ALSO

rtapi_task_new(3rtapi), **rtapi_task_pause(3rtapi)**, **rtapi_task_resume(3rtapi)**

NAME

rtapi_task_wait – suspend execution of this periodic task

SYNTAX

```
void rtapi_task_wait()
```

DESCRIPTION

rtapi_task_wait suspends execution of the current task until the next period. The task must be periodic. If not, the result is undefined.

REALTIME CONSIDERATIONS

Call only from within a periodic realtime task

RETURN VALUE

None

SEE ALSO

rtapi_task_start(3rtapi), **rtapi_task_pause(3rtapi)**

NAME

undocumented – undocumented functions in RTAPI

SEE ALSO

The header file *rtapi.h*. Most rtapi functions have documentation in that file.

NAME

abs – Compute the absolute value and sign of the input signal

SYNOPSIS

loadrt abs [count=N]names=name1[,name2...]

FUNCTIONS

abs.N (requires a floating-point thread)

PINS

abs.N.in float in
Analog input value

abs.N.out float out
Analog output value, always positive

abs.N.sign bit out
Sign of input, false for positive, true for negative

LICENSE

GPL

NAME

and2 – Two-input AND gate

SYNOPSIS

loadrt and2 [count=*N*|names=*name1*[,*name2*...]]

FUNCTIONS

and2.*N*

PINS

and2.*N*.in0 bit in

and2.*N*.in1 bit in

and2.*N*.out bit out

out is computed from the value of **in0** and **in1** according to the following rule:

in0=TRUE in1=TRUE

out=TRUE

Otherwise,

out=FALSE

LICENSE

GPL

NAME

`at_pid` – proportional/integral/derivative controller with auto tuning

SYNOPSIS

```
loadrt at_pid num_chan=num [debug=dbg]
```

DESCRIPTION

`at_pid` is a classic Proportional/Integral/Derivative controller, used to control position or speed feedback loops for servo motors and other closed-loop applications.

`at_pid` supports a maximum of sixteen controllers. The number that are actually loaded is set by the `num_chan` argument when the module is loaded. If `numchan` is not specified, the default value is three. If `debug` is set to 1 (the default is 0), some additional HAL parameters will be exported, which might be useful for tuning, but are otherwise unnecessary.

`at_pid` has a built in auto tune mode. It works by setting up a limit cycle to characterize the process. From this, `Pgain/Igain/Dgain` or `Pgain/Igain/FF1` can be determined using Ziegler-Nichols. When using `FF1`, scaling must be set so that `output` is in user units per second.

During auto tuning, the `command` input should not change. The limit cycle is setup around the commanded position. No initial tuning values are required to start auto tuning. Only `tune-cycles`, `tune-effort` and `tune-mode` need be set before starting auto tuning. When auto tuning completes, the tuning parameters will be set. If running from EMC, the `FERROR` setting for the axis being tuned may need to be loosened up as it must be larger than the limit cycle amplitude in order to avoid a following error.

To perform auto tuning, take the following steps. Move the axis to be tuned, to somewhere near the center of it's travel. Set `tune-cycles` (the default value should be fine in most cases) and `tune-mode`. Set `tune-effort` to a small value. Set `enable` to true. Set `tune-mode` to true. Set `tune-start` to true. If no oscillation occurs, or the oscillation is too small, slowly increase `tune-effort`. Auto tuning can be aborted at any time by setting `enable` or `tune-mode` to false.

FUNCTIONS

`pid.N.do-pid-calcs` (uses floating-point)

Does the PID calculations for control loop `N`.

PINS

`pid.N.command` float in

The desired (commanded) value for the control loop.

`pid.N.feedback` float in

The actual (feedback) value, from some sensor such as an encoder.

`pid.N.error` float out

The difference between command and feedback.

`pid.N.output` float out

The output of the PID loop, which goes to some actuator such as a motor.

`pid.N.enable` bit in

When true, enables the PID calculations. When false, `output` is zero, and all internal integrators, etc, are reset.

`pid.N.tune-mode` bit in

When true, enables auto tune mode. When false, normal PID calculations are performed.

`pid.N.tune-start` bit io

When set to true, starts auto tuning. Cleared when the auto tuning completes.

PARAMETERS

pid.N.Pgain float rw

Proportional gain. Results in a contribution to the output that is the error multiplied by **Pgain**.

pid.N.Igain float rw

Integral gain. Results in a contribution to the output that is the integral of the error multiplied by **Igain**. For example an error of 0.02 that lasted 10 seconds would result in an integrated error (**errorI**) of 0.2, and if **Igain** is 20, the integral term would add 4.0 to the output.

pid.N.Dgain float rw

Derivative gain. Results in a contribution to the output that is the rate of change (derivative) of the error multiplied by **Dgain**. For example an error that changed from 0.02 to 0.03 over 0.2 seconds would result in an error derivative (**errorD**) of 0.05, and if **Dgain** is 5, the derivative term would add 0.25 to the output.

pid.N.bias float rw

bias is a constant amount that is added to the output. In most cases it should be left at zero. However, it can sometimes be useful to compensate for offsets in servo amplifiers, or to balance the weight of an object that moves vertically. **bias** is turned off when the PID loop is disabled, just like all other components of the output. If a non-zero output is needed even when the PID loop is disabled, it should be added with an external HAL sum2 block.

pid.N.FF0 float rw

Zero order feed-forward term. Produces a contribution to the output that is **FF0** multiplied by the commanded value. For position loops, it should usually be left at zero. For velocity loops, **FF0** can compensate for friction or motor counter-EMF and may permit better tuning if used properly.

pid.N.FF1 float rw

First order feed-forward term. Produces a contribution to the output that **FF1** multiplied by the derivative of the commanded value. For position loops, the contribution is proportional to speed, and can be used to compensate for friction or motor CEMF. For velocity loops, it is proportional to acceleration and can compensate for inertia. In both cases, it can result in better tuning if used properly.

pid.N.FF2 float rw

Second order feed-forward term. Produces a contribution to the output that is **FF2** multiplied by the second derivative of the commanded value. For position loops, the contribution is proportional to acceleration, and can be used to compensate for inertia. For velocity loops, it should usually be left at zero.

pid.N.deadband float rw

Defines a range of "acceptable" error. If the absolute value of **error** is less than **deadband**, it will be treated as if the error is zero. When using feedback devices such as encoders that are inherently quantized, the deadband should be set slightly more than one-half count, to prevent the control loop from hunting back and forth if the command is between two adjacent encoder values. When the absolute value of the error is greater than the deadband, the deadband value is subtracted from the error before performing the loop calculations, to prevent a step in the transfer function at the edge of the deadband. (See **BUGS**.)

pid.N.maxoutput float rw

Output limit. The absolute value of the output will not be permitted to exceed **maxoutput**, unless **maxoutput** is zero. When the output is limited, the error integrator will hold instead of integrating, to prevent windup and overshoot.

pid.N.maxerror float rw

Limit on the internal error variable used for P, I, and D. Can be used to prevent high **Pgain** values from generating large outputs under conditions when the error is large (for example, when the command makes a step change). Not normally needed, but can be useful when tuning non-linear systems.

pid.N.maxerrorD float rw

Limit on the error derivative. The rate of change of error used by the **Dgain** term will be limited to this value, unless the value is zero. Can be used to limit the effect of **Dgain** and prevent large output spikes due to steps on the command and/or feedback. Not normally needed.

pid.N.maxerrorI float rw

Limit on error integrator. The error integrator used by the **Igain** term will be limited to this value, unless it is zero. Can be used to prevent integrator windup and the resulting overshoot during/after sustained errors. Not normally needed.

pid.N.maxcmdD float rw

Limit on command derivative. The command derivative used by **FF1** will be limited to this value, unless the value is zero. Can be used to prevent **FF1** from producing large output spikes if there is a step change on the command. Not normally needed.

pid.N.maxcmdDD float rw

Limit on command second derivative. The command second derivative used by **FF2** will be limited to this value, unless the value is zero. Can be used to prevent **FF2** from producing large output spikes if there is a step change on the command. Not normally needed.

pid.N.tune-type u32 rw

When set to 0, **Pgain/Igain/Dgain** are calculated. When set to 1, **Pgain/Igain/FF1** are calculated.

pid.N.tune-cycles u32 rw

Determines the number of cycles to run to characterize the process. **tune-cycles** actually sets the number of half cycles. More cycles results in a more accurate characterization as the average of all cycles is used.

pid.N.tune-effort float rw

Determines the effort used in setting up the limit cycle in the process. **tune-effort** should be set to a positive value less than **maxoutput**. Start with something small and work up to a value that results in a good portion of the maximum motor current being used. The smaller the value, the smaller the amplitude of the limit cycle.

pid.N.errorI float ro (only if debug=1)

Integral of error. This is the value that is multiplied by **Igain** to produce the Integral term of the output.

pid.N.errorD float ro (only if debug=1)

Derivative of error. This is the value that is multiplied by **Dgain** to produce the Derivative term of the output.

pid.N.commandD float ro (only if debug=1)

Derivative of command. This is the value that is multiplied by **FF1** to produce the first order feed-forward term of the output.

pid.N.commandDD float ro (only if debug=1)

Second derivative of command. This is the value that is multiplied by **FF2** to produce the second order feed-forward term of the output.

pid.N.ultimate-gain float ro (only if debug=1)

Determined from process characterization. **ultimate-gain** is the ratio of **tune-effort** to the limit cycle amplitude multiplied by 4.0 divided by Pi. **pid.N.ultimate-period** float ro (only if debug=1)

Determined from process characterization. **ultimate-period** is the period of the limit cycle.

BUGS

Some people would argue that deadband should be implemented such that error is treated as zero if it is within the deadband, and be unmodified if it is outside the deadband. This was not done because it would cause a step in the transfer function equal to the size of the deadband. People who prefer that behavior are welcome to add a parameter that will change the behavior, or to write their own version of **at_pid**. However, the default behavior should not be changed.

NAME

biquad – Biquad IIR filter

SYNOPSIS

loadrt biquad [**count**=*N*]**names**=*name1*[,*name2*...]

DESCRIPTION

Biquad IIR filter. Implements the following transfer function: $H(z) = (n_0 + n_1z^{-1} + n_2z^{-2}) / (1 + d_1z^{-1} + d_2z^{-2})$

FUNCTIONS

biquad.N (requires a floating-point thread)

PINS

biquad.N.in float in
Filter input.

biquad.N.out float out
Filter output.

biquad.N.enable bit in (default: 0)
Filter enable. When false, the in is passed to out without any filtering. A transition from false to true causes filter coefficients to be calculated according to parameters

biquad.N.valid bit out (default: 0)
When false, indicates an error occurred when calculating filter coefficients.

PARAMETERS

biquad.N.type u32 rw (default: 0)
Filter type determines the type of filter coefficients calculated. When 0, coefficients must be loaded directly. When 1, a low pass filter is created. When 2, a notch filter is created.

biquad.N.f0 float rw (default: 250.0)
The corner frequency of the filter.

biquad.N.Q float rw (default: 0.7071)
The Q of the filter.

biquad.N.d1 float rw (default: 0.0)
1st-delayed denominator coef

biquad.N.d2 float rw (default: 0.0)
2nd-delayed denominator coef

biquad.N.n0 float rw (default: 1.0)
non-delayed numerator coef

biquad.N.n1 float rw (default: 0.0)
1st-delayed numerator coef

biquad.N.n2 float rw (default: 0.0)
2nd-delayed numerator coef

biquad.N.s1 float rw (default: 0.0)

biquad.N.s2 float rw (default: 0.0)

LICENSE

GPL

NAME

`bldc_hall3` – 3-wire Bipolar trapezoidal commutation BLDC motor driver using Hall sensors

SYNOPSIS

`loadrt bldc_hall3 [count=N]names=name1[,name2...]`

DESCRIPTION

This component produces a 3-wire bipolar output. This suits upstream drivers that interpret a negative input as a low-side drive and positive as a high-side drive. This includes the Hostmot2 3pwmgen function, which is likely to be the most common application of this component.

FUNCTIONS

bldc-hall3.N (requires a floating-point thread)

Interpret Hall sensor patterns and set 3-phase amplitudes

PINS

bldc-hall3.N.hall1 bit in

Hall sensor signal 1

bldc-hall3.N.hall2 bit in

Hall sensor signal 2

bldc-hall3.N.hall3 bit in

Hall sensor signal 3

bldc-hall3.N.value float in

PWM master amplitude input

bldc-hall3.N.dir bit in

Forwards / reverse selection. Negative PWM amplitudes will also reverse the motor and there will generally be a pattern that runs the motor in each direction too.

bldc-hall3.N.A-value float out

Output amplitude for phase A

bldc-hall3.N.B-value float out

Output amplitude for phase B

bldc-hall3.N.C-value float out

Output amplitude for phase C

PARAMETERS

bldc-hall3.N.pattern u32 rw (default: 25)

Commutation pattern to use, from 0 to 47. Default is type 25. Every plausible combination is included. The table shows the excitation pattern along the top, and the pattern code on the left hand side. The table entries are the hall patterns in H1, H2, H3 order. Common patterns are: 0 (30 degree commutation) and 26, its reverse. 17 (120 degree). 18 (alternate 60 degree). 21 (300 degree, Bodine). 22 (240 degree). 25 (60 degree commutation).

Note that a number of incorrect commutations will have non-zero net torque which might look as if they work, but don't really.

If your motor lacks documentation it might be worth trying every pattern.

Phases, Source - Sink						
pat	B-A	C-A	C-B	A-B	A-C	B-C
0	000	001	011	111	110	100
1	001	000	010	110	111	101
2	000	010	011	111	101	100
3	001	011	010	110	100	101
4	010	011	001	101	100	110
5	011	010	000	100	101	111
6	010	000	001	101	111	110
7	011	001	000	100	110	111
8	000	001	101	111	110	010
9	001	000	100	110	111	011
10	000	010	110	111	101	001
11	001	011	111	110	100	000
12	010	011	111	101	100	000
13	011	010	110	100	101	001
14	010	000	100	101	111	011
15	011	001	101	100	110	010
16	000	100	101	111	011	010
17	001	101	100	110	010	011
18	000	100	110	111	011	001
19	001	101	111	110	010	000
20	010	110	111	101	001	000
21	011	111	110	100	000	001
22	010	110	100	101	001	011
23	011	111	101	100	000	010
24	100	101	111	011	010	000
25	101	100	110	010	011	001
26	100	110	111	011	001	000
27	101	111	110	010	000	001
28	110	111	101	001	000	010
29	111	110	100	000	001	011
30	110	100	101	001	011	010
31	111	101	100	000	010	011
32	100	101	001	011	010	110
33	101	100	000	010	011	111
34	100	110	010	011	001	101
35	101	111	011	010	000	100
36	110	111	011	001	000	100
37	111	110	010	000	001	101
38	110	100	000	001	011	111
39	111	101	001	000	010	110
40	100	000	001	011	111	110
41	101	001	000	010	110	111
42	100	000	010	011	111	101
43	101	001	011	010	110	100
44	110	010	011	001	101	100
45	111	011	010	000	100	101
46	110	010	000	001	101	111
47	111	011	001	000	100	110

SEE ALSO

bldc_hall6 6-wire unipolar driver for BLDC motors.

AUTHOR

Andy Pugh

LICENSE

GPL

NAME

`bldc_sine` – Sinusoidal Brushless DC motor drive, with optional self-zeroing

SYNOPSIS

`loadrt bldc_sine [count=N|names=name1[,name2...]]`

FUNCTIONS

`bldc-sine.N` (uses floating-point)

PINS

`bldc-sine.N.rawcounts` s32 in
Encoder counts input

`bldc-sine.N.init` bit in

A rising edge on this pin starts the motor alignment sequence. This pin should be connected in such a way that the motors re-align any time that encoder monitoring has been interrupted. Typically this will only be at machine power-off. The alignment process involves powering the motor phases in such a way as to put the motor in a known position. The encoder counts are then stored in the **offset** parameter. The alignment process will tend to cause a following error if it is triggered while the axis is enabled, so should be set before the matching `axis.N.enable` pin. The complementary **init-done** pin can be used to handle the required sequencing.

Both pins can be ignored if the encoder offset is known explicitly, such as is the case with an absolute encoder. In that case the **offset** parameter can be set directly in the HAL file

`bldc-sine.N.init-done` bit out (default: 0)

indicates that the motor alignment process is completed

`bldc-sine.N.dir` float in (default: 1)

The peak output of the three ***-value** pins will be the product of the **value** pin and the **dir** pin. The main purpose of the pin is to invert the the motor direction sense using a scale of -1, but there is no restriction on the valid values. Typically the component will take a bipolar +/- fullscale input from a pid function and in that case this pin will not be wired

`bldc-sine.N.value` float in
PWM demand

`bldc-sine.N.angle` float in (default: 90)

The phase lead between the electrical vector and the rotor position

`bldc-sine.N.initvalue` float in (default: .1)

The PWM demand to use for motor initialisation

`bldc-sine.N.A-value` float out (default: 0)

Output amplitude for phase A

`bldc-sine.N.B-value` float out (default: 0)

Output amplitude for phase B

`bldc-sine.N.C-value` float out (default: 0)

Output amplitude for phase C

PARAMETERS

`bldc-sine.N.offset` s32 rw (default: 0)

The offset in encoder counts between the encoder zero position and motor electrical zero. Can be set directly for use in absolute feedback systems or will be initialised by the **init** pin.

`bldc-sine.N.scale` float rw (default: 512)

The number of encoder counts per electrical revolution. eg counts/2 for a 4-pole motor, counts/3 for a 6 pole etc. There is a 50% chance that this parameter will need to be negative for proper function.

AUTHOR

Andy Pugh

LICENSE

GPL

NAME

blend – Perform linear interpolation between two values

SYNOPSIS

loadrt blend [**count=N**]**names=name1[,name2...]**

FUNCTIONS

blend.N (requires a floating-point thread)

PINS

blend.N.in1 float in

First input. If select is equal to 0.0, the output is equal to in1

blend.N.in2 float in

Second input. If select is equal to 1.0, the output is equal to in2

blend.N.select float in

Select input. For values between 0.0 and 1.0, the output changes linearly from in1 to in2

blend.N.out float out

Output value.

PARAMETERS

blend.N.open bit rw

If true, select values outside the range 0.0 to 1.0 give values outside the range in1 to in2. If false, outputs are clamped to the the range in1 to in2

LICENSE

GPL

NAME

charge_pump – Create a square-wave for the 'charge pump' input of some controller boards

SYNOPSIS

loadrt charge_pump

FUNCTIONS

charge-pump

Toggle the output bit (if enabled)

PINS

charge-pump.out bit out

Square wave if 'enable' is TRUE or unconnected, low if 'enable' is FALSE

charge-pump.enable bit in (default: *TRUE*)

If FALSE, forces 'out' to be low

LICENSE

GPL

NAME

clarke2 – Two input version of Clarke transform

SYNOPSIS

loadrt clarke2 [**count**=*N* | **names**=*name1* [, *name2* ...]]

DESCRIPTION

The Clarke transform can be used to translate a vector quantity from a three phase system (three components 120 degrees apart) to a two phase Cartesian system.

clarke2 implements a special case of the Clarke transform, which only needs two of the three input phases. In a three wire three phase system, the sum of the three phase currents or voltages must always be zero. As a result only two of the three are needed to completely define the current or voltage. **clarke2** assumes that the sum is zero, so it only uses phases A and B of the input. Since the H (homopolar) output will always be zero in this case, it is not generated.

FUNCTIONS

clarke2.N (requires a floating-point thread)

PINS

clarke2.N.a float in

clarke2.N.b float in

first two phases of three phase input

clarke2.N.x float out

clarke2.N.y float out

cartesian components of output

SEE ALSO

clarke3 for the general case, **clarkeinv** for the inverse transform.

LICENSE

GPL

NAME

clarke3 – Clarke (3 phase to cartesian) transform

SYNOPSIS

loadrt clarke3 [**count**=*N* | **names**=*name1* [, *name2* ...]]

DESCRIPTION

The Clarke transform can be used to translate a vector quantity from a three phase system (three components 120 degrees apart) to a two phase Cartesian system (plus a homopolar component if the three phases don't sum to zero).

clarke3 implements the general case of the transform, using all three phases. If the three phases are known to sum to zero, see **clarke2** for a simpler version.

FUNCTIONS

clarke3.N (requires a floating-point thread)

PINS

clarke3.N.a float in

clarke3.N.b float in

clarke3.N.c float in

three phase input vector

clarke3.N.x float out

clarke3.N.y float out

cartesian components of output

clarke3.N.h float out

homopolar component of output

SEE ALSO

clarke2 for the 'a+b+c=0' case, **clarkeinv** for the inverse transform.

LICENSE

GPL

NAME

clarkeinv – Inverse Clarke transform

SYNOPSIS

loadrt clarkeinv [**count**=*N* | **names**=*name1* [, *name2* ...]]

DESCRIPTION

The inverse Clarke transform can be used to translate a vector quantity from Cartesian coordinate system to a three phase system (three components 120 degrees apart).

FUNCTIONS

clarkeinv.N (requires a floating-point thread)

PINS

clarkeinv.N.x float in

clarkeinv.N.y float in

cartesian components of input

clarkeinv.N.h float in

homopolar component of input (usually zero)

clarkeinv.N.a float out

clarkeinv.N.b float out

clarkeinv.N.c float out

three phase output vector

SEE ALSO

clarke2 and **clarke3** for the forward transform.

LICENSE

GPL

NAME

classicladder – realtime software plc based on ladder logic

SYNOPSIS

loadrt classicladder_rt [numRungs=*N*] [numBits=*N*] [numWords=*N*] [numTimers=*N*] [numMonostables=*N*] [numCounters=*N*] [numPhysInputs=*N*] [numPhysOutputs=*N*] [numArithmExpr=*N*] [numSections=*N*] [numSymbols=*N*] [numS32in=*N*] [numS32out=*N*]

DESCRIPTION

These pins and parameters are created by the realtime **classicladder_rt** module. Each period (minimum 1000000 ns), classicladder reads the inputs, evaluates the ladder logic defined in the GUI, and then writes the outputs.

PINS

classicladder.0.in-*N* IN bit

These bit signal pins map to **%I*NNN*** variables in classicladder

classicladder.0.out-*N* OUT bit

These bit signal pins map to **%Q*nNN*** variables in classicladder Output from classicladder

classicladder.0.in-*N* IN s32

Integer input from classicladder These s32 signal pins map to **%IW*NNN*** variables in classicladder

classicladder.0.out-*N* OUT s32

Integer output from classicladder These s32 signal pins map to **%QW*NNN*** variables in classicladder

PARAMETERS

classicladder.0.refresh.time RO s32

Tells you how long the last refresh took

classicladder.0.refresh.tmax RW s32

Tells you how long the longest refresh took

classicladder.0.ladder-state RO s32

Tells you if the program is running or not

FUNCTIONS

classicladder.0.refresh FP

The rung update rate. Add this to the servo thread. You can added it to a faster thread but it Will update no faster than once every 1 millisecond (1000000 ns).

BUGS

See http://wiki.linuxcnc.org/cgi-bin/emcinfo.pl?ClassicLadder_Ver_7.124 for the latest.

SEE ALSO

see the integrator manual and http://wiki.linuxcnc.org/cgi-bin/emcinfo.pl?ClassicLadder_Ver_7.124

NAME

comp – Two input comparator with hysteresis

SYNOPSIS

loadrt comp [**count**=*N*]**names**=*name1*[,*name2*...]

FUNCTIONS

comp.N (requires a floating-point thread)
Update the comparator

PINS

comp.N.in0 float in
Inverting input to the comparator

comp.N.in1 float in
Non-inverting input to the comparator

comp.N.out bit out
Normal output. True when **in1** > **in0** (see parameter **hyst** for details)

comp.N.equal bit out
Match output. True when difference between **in1** and **in0** is less than **hyst/2**

PARAMETERS

comp.N.hyst float rw (default: *0.0*)
Hysteresis of the comparator (default 0.0)

With zero hysteresis, the output is true when **in1** > **in0**. With nonzero hysteresis, the output switches on and off at two different values, separated by distance **hyst** around the point where **in1** = **in0**. Keep in mind that floating point calculations are never absolute and it is wise to always set **hyst** if you intend to use equal

LICENSE

GPL

NAME

constant – Use a parameter to set the value of a pin

SYNOPSIS

loadrt constant [**count**=*N*]**names**=*name1*[,*name2*...]

FUNCTIONS

constant.N (requires a floating-point thread)

PINS

constant.N.out float out

PARAMETERS

constant.N.value float rw

LICENSE

GPL

NAME

conv_bit_s32 – Convert a value from bit to s32

SYNOPSIS

loadrt conv_bit_s32 [**count**=*N* | **names**=*name1* [, *name2* ...]]

FUNCTIONS

conv-bit-s32.N

Update 'out' based on 'in'

PINS

conv-bit-s32.N.in bit in

conv-bit-s32.N.out s32 out

LICENSE

GPL

NAME

conv_bit_u32 – Convert a value from bit to u32

SYNOPSIS

loadrt conv_bit_u32 [**count=N** | **names=name1[,name2...]**]

FUNCTIONS

conv-bit-u32.N

Update 'out' based on 'in'

PINS

conv-bit-u32.N.in bit in

conv-bit-u32.N.out u32 out

LICENSE

GPL

NAME

conv_float_s32 – Convert a value from float to s32

SYNOPSIS

loadrt conv_float_s32 [**count=N**names=*name1*[,*name2*...]]

FUNCTIONS

conv-float-s32.N (requires a floating-point thread)
Update 'out' based on 'in'

PINS

conv-float-s32.N.in float in
conv-float-s32.N.out s32 out
conv-float-s32.N.out-of-range bit out
TRUE when 'in' is not in the range of s32

PARAMETERS

conv-float-s32.N.clamp bit rw
If TRUE, then clamp to the range of s32. If FALSE, then allow the value to "wrap around".

LICENSE

GPL

NAME

conv_float_u32 – Convert a value from float to u32

SYNOPSIS

loadrt conv_float_u32 [count=*N*][names=*name1*[,*name2*...]]

FUNCTIONS

conv-float-u32.N (requires a floating-point thread)
Update 'out' based on 'in'

PINS

conv-float-u32.N.in float in
conv-float-u32.N.out u32 out
conv-float-u32.N.out-of-range bit out
TRUE when 'in' is not in the range of u32

PARAMETERS

conv-float-u32.N.clamp bit rw
If TRUE, then clamp to the range of u32. If FALSE, then allow the value to "wrap around".

LICENSE

GPL

NAME

`conv_s32_bit` – Convert a value from s32 to bit

SYNOPSIS

`loadrt conv_s32_bit [count=N|names=name1[,name2...]]`

FUNCTIONS

`conv-s32-bit.N`

Update 'out' based on 'in'

PINS

`conv-s32-bit.N.in` s32 in

`conv-s32-bit.N.out` bit out

`conv-s32-bit.N.out-of-range` bit out

TRUE when 'in' is not in the range of bit

PARAMETERS

`conv-s32-bit.N.clamp` bit rw

If TRUE, then clamp to the range of bit. If FALSE, then allow the value to "wrap around".

LICENSE

GPL

NAME

conv_s32_float – Convert a value from s32 to float

SYNOPSIS

loadrt conv_s32_float [count=N|names=name1[,name2...]]

FUNCTIONS

conv-s32-float.N (requires a floating-point thread)
Update 'out' based on 'in'

PINS

conv-s32-float.N.in s32 in
conv-s32-float.N.out float out

LICENSE

GPL

NAME

conv_s32_u32 – Convert a value from s32 to u32

SYNOPSIS

loadrt conv_s32_u32 [**count=N**]**names=name1[,name2...]**

FUNCTIONS

conv-s32-u32.N

Update 'out' based on 'in'

PINS

conv-s32-u32.N.in s32 in

conv-s32-u32.N.out u32 out

conv-s32-u32.N.out-of-range bit out

TRUE when 'in' is not in the range of u32

PARAMETERS

conv-s32-u32.N.clamp bit rw

If TRUE, then clamp to the range of u32. If FALSE, then allow the value to "wrap around".

LICENSE

GPL

NAME

conv_u32_bit – Convert a value from u32 to bit

SYNOPSIS

loadrt conv_u32_bit [count=N|names=name1[,name2...]]

FUNCTIONS

conv-u32-bit.N

Update 'out' based on 'in'

PINS

conv-u32-bit.N.in u32 in

conv-u32-bit.N.out bit out

conv-u32-bit.N.out-of-range bit out

TRUE when 'in' is not in the range of bit

PARAMETERS

conv-u32-bit.N.clamp bit rw

If TRUE, then clamp to the range of bit. If FALSE, then allow the value to "wrap around".

LICENSE

GPL

NAME

conv_u32_float – Convert a value from u32 to float

SYNOPSIS

loadrt conv_u32_float [count=*N*|names=*name1*[,*name2*...]]

FUNCTIONS

conv-u32-float.*N* (requires a floating-point thread)
Update 'out' based on 'in'

PINS

conv-u32-float.*N*.in u32 in
conv-u32-float.*N*.out float out

LICENSE

GPL

NAME

conv_u32_s32 – Convert a value from u32 to s32

SYNOPSIS

loadrt conv_u32_s32 [count=*N* | names=*name1* [, *name2* ...]]

FUNCTIONS

conv-u32-s32.*N*

Update 'out' based on 'in'

PINS

conv-u32-s32.*N*.in u32 in

conv-u32-s32.*N*.out s32 out

conv-u32-s32.*N*.out-of-range bit out

TRUE when 'in' is not in the range of s32

PARAMETERS

conv-u32-s32.*N*.clamp bit rw

If TRUE, then clamp to the range of s32. If FALSE, then allow the value to "wrap around".

LICENSE

GPL

NAME

counter – counts input pulses (**DEPRECATED**)

SYNOPSIS

loadrt counter [num_chan=N]

DESCRIPTION

counter is a deprecated HAL component and will be removed in a future release. Use the **encoder** component with `encoder.X.counter-mode` set to `TRUE`.

counter is a HAL component that provides software- based counting that is useful for spindle position sensing and maybe other things. Instead of using a real encoder that outputs quadrature, some lathes have a sensor that generates a simple pulse stream as the spindle turns and an index pulse once per revolution. This component simply counts up when a "count" pulse (phase-A) is received, and if reset is enabled, resets when the "index" (phase-Z) pulse is received.

This is of course only useful for a unidirectional spindle, as it is not possible to sense the direction of rotation.

counter conforms to the "canonical encoder" interface described in the HAL manual.

FUNCTIONS

counter.capture-position (uses floating-point)

Updates the counts, position and velocity outputs based on internal counters.

counter.update-counters

Samples the phase-A and phase-Z inputs and updates internal counters.

PINS

counter.N.phase-A bit in

The primary input signal. The internal counter is incremented on each rising edge.

counter.N.phase-Z bit in

The index input signal. When the **index-enable** pin is `TRUE` and a rising edge on **phase-Z** is seen, **index-enable** is set to `FALSE` and the internal counter is reset to zero.

counter.N.index-enable bit io

counter.N.reset bit io

counter.N.counts signed out

counter.N.position float out

counter.N.velocity float out

These pins function according to the canonical digital encoder interface.

counter.N.position-scale float rw

This parameter functions according to the canonical digital encoder interface.

counter.N.rawcounts signed ro

The internal counts value, updated from **update-counters** and reflected in the output pins at the next call to **capture-position**.

SEE ALSO

encoder(9). The HAL User Manual.

NAME

ddt – Compute the derivative of the input function

SYNOPSIS

loadrt ddt [**count=N**|**names=name1[,name2...]**]

FUNCTIONS

ddt.N (requires a floating-point thread)

PINS

ddt.N.in float in

ddt.N.out float out

LICENSE

GPL

NAME

deadzone – Return the center if within the threshold

SYNOPSIS

loadrt deadzone [**count**=*N* | **names**=*name1* [, *name2* ...]]

FUNCTIONS

deadzone.N (requires a floating-point thread)

Update **out** based on **in** and the parameters.

PINS

deadzone.N.in float in

deadzone.N.out float out

PARAMETERS

deadzone.N.center float rw (default: *0.0*)

The center of the dead zone

deadzone.N.threshold float rw (default: *1.0*)

The dead zone is **center** \pm (**threshold**/2)

LICENSE

GPL

NAME

debounce – filter noisy digital inputs

SYNOPSIS

loadrt debounce [cfg=size[,size,...]]

Creates filter groups each with the given number of filters (*size*). Each filter group has the same sample rate and delay.

DESCRIPTION

The debounce filter works by incrementing a counter whenever the input is true, and decrementing the counter when it is false. If the counter decrements to zero, the output is set false and the counter ignores further decrements. If the counter increments up to a threshold, the output is set true and the counter ignores further increments. If the counter is between zero and the threshold, the output retains its previous state. The threshold determines the amount of filtering: a threshold of 1 does no filtering at all, and a threshold of N requires a signal to be present for N samples before the output changes state.

FUNCTIONS

debounce.G

Sample all the input pins in group G and update the output pins.

PINS

debounce.G.F.in bit in

The F'th input pin in group G.

debounce.G.F.out bit out

The F'th output pin in group G. Reflects the last "stable" input seen on the corresponding input pin.

debounce.G.delay signed rw

Sets the amount of filtering for all pins in group G.

NAME

edge – Edge detector

SYNOPSIS

loadrt edge [count=*N*|names=*name1*[,*name2*...]]

FUNCTIONS

edge.*N* Produce output pulses from input edges

PINS

edge.*N*.in bit in

edge.*N*.out bit out

Goes high when the desired edge is seen on 'in'

edge.*N*.out-invert bit out

Goes low when the desired edge is seen on 'in'

PARAMETERS

edge.*N*.in-edge bit rw (default: *TRUE*)

Selects the desired edge: *TRUE* means falling, *FALSE* means rising

edge.*N*.out-width-ns s32 rw (default: *0*)

Time in nanoseconds of the output pulse

edge.*N*.time-left-ns s32 r

Time left in this output pulse

edge.*N*.last-in bit r

Previous input value

LICENSE

GPL

NAME

encoder – software counting of quadrature encoder signals

SYNOPSIS

loadrt encoder num_chan=*num*

DESCRIPTION

encoder is used to measure position by counting the pulses generated by a quadrature encoder. As a software-based implementation it is much less expensive than hardware, but has a limited maximum count rate. The limit is in the range of 10KHz to 50KHz, depending on the computer speed and other factors. If better performance is needed, a hardware encoder counter is a better choice. Some hardware-based systems can count at MHz rates.

encoder supports a maximum of eight channels. The number of channels actually loaded is set by the **num_chan** argument when the module is loaded. If **numchan** is not specified, the default value is three.

encoder has a one-phase, unidirectional mode called *counter*. In this mode, the **phase-B** input is ignored; the counts increase on each rising edge of **phase-A**. This mode may be useful for counting a unidirectional spindle with a single input line, though the noise-resistant characteristics of quadrature are lost.

FUNCTIONS

encoder.update-counters (no floating-point)

Does the actual counting, by sampling the encoder signals and decoding the quadrature waveforms. Must be called as frequently as possible, preferably twice as fast as the maximum desired count rate. Operates on all channels at once.

encoder.capture-position (uses floating point)

Captures the raw counts from **update-counters** and performs scaling and other necessary conversion, handles counter rollover, etc. Can (and should) be called less frequently than **update-counters**. Operates on all channels at once.

PINS

encoder.N.counter-mode bit i/o

Enables counter mode. When true, the counter counts each rising edge of the phase-A input, ignoring the value on phase-B. This is useful for counting the output of a single channel (non-quadrature) sensor. When false (the default), it counts in quadrature mode.

encoder.N.counts s32 out

Position in encoder counts.

encoder.N.index-enable bit i/o

When true, **counts** and **position** are reset to zero on the next rising edge of **Phase-Z**. At the same time, **index-enable** is reset to zero to indicate that the rising edge has occurred.

encoder.N.phase-A bit in

Quadrature input for encoder channel *N*.

encoder.N.phase-B bit in

Quadrature input.

encoder.N.phase-Z bit in

Index pulse input.

encoder.N.position float out

Position in scaled units (see **position-scale**)

encoder.N.position-interpolated float out

Position in scaled units, interpolated between encoder counts. Only valid when velocity is approximately constant and above **min-velocity-estimate**. Do not use for position control.

- encoder.N.position-scale** float i/o
Scale factor, in counts per length unit. For example, if **position-scale** is 500, then 1000 counts of the encoder will be reported as a position of 2.0 units.
- encoder.N.rawcounts** s32 out
The raw count, as determined by **update-counters**. This value is updated more frequently than **counts** and **position**. It is also unaffected by **reset** or the index pulse.
- encoder.N.reset** bit in
When true, **counts** and **position** are reset to zero immediately.
- encoder.N.velocity** float out
Velocity in scaled units per second. **encoder** uses an algorithm that greatly reduces quantization noise as compared to simply differentiating the **position** output. When the magnitude of the true velocity is below **min-velocity-estimate**, the velocity output is 0.
- encoder.N.x4-mode** bit i/o
Enables times-4 mode. When true (the default), the counter counts each edge of the quadrature waveform (four counts per full cycle). When false, it only counts once per full cycle. In **counter-mode**, this parameter is ignored.
- encoder.N.latch-input** bit in
encoder.N.latch-falling bit in (default: **TRUE**)
encoder.N.latch-rising bit in (default: **TRUE**)
encoder.N.counts-latched s32 out
encoder.N.position-latched float out
Update **counts-latched** and **position-latched** on the rising and/or falling edges of **latch-input** as indicated by **latch-rising** and **latch-falling**.
- encoder.N.counter-mode** bit rw
Enables counter mode. When true, the counter counts each rising edge of the phase-A input, ignoring the value on phase-B. This is useful for counting the output of a single channel (non-quadrature) sensor. When false (the default), it counts in quadrature mode. **encoder.N.capture-position.tmax** s32 rw Maximum number of CPU cycles it took to execute this function.

PARAMETERS

- encoder.N.min-velocity-estimate** float rw (default: 1.0)
Determine the minimum true velocity magnitude at which **velocity** will be estimated as nonzero and **position-interpolated** will be interpolated. The units of **min-velocity-estimate** are the same as the units of **velocity**. Scale factor, in counts per length unit. Setting this parameter too low will cause it to take a long time for **velocity** to go to 0 after encoder pulses have stopped arriving.

NAME

encoder_ratio – an electronic gear to synchronize two axes

SYNOPSIS

loadrt encoder_ratio [num_chan=*N*]

DESCRIPTION

encoder_ratio can be used to synchronize two axes (like an "electronic gear"). It counts encoder pulses from both axes in software, and produces an error value that can be used with a PID loop to make the slave encoder track the master encoder with a specific ratio.

This module supports up to eight axis pairs. The number of pairs is set by the module parameter **num_chan**.

FUNCTIONS**encoder_ratio.sample**

Read all input pins. Must be called at twice the maximum desired count rate.

encoder_ratio.update (uses floating-point)

Updates all output pins. May be called from a slower thread.

PINS

encoder_ratio.N.master-A bit in

encoder_ratio.N.master-B bit in

encoder_ratio.N.slave-A bit in

encoder_ratio.N.slave-B bit in

The encoder channels of the master and slave axes

encoder_ratio.N.enable bit in

When the enable pin is FALSE, the error pin simply reports the slave axis position, in revolutions. As such, it would normally be connected to the feedback pin of a PID block for closed loop control of the slave axis. Normally the command input of the PID block is left unconnected (zero), so the slave axis simply sits still. However when the enable input goes TRUE, the error pin becomes the slave position minus the scaled master position. The scale factor is the ratio of master teeth to slave teeth. As the master moves, error becomes non-zero, and the PID loop will drive the slave axis to track the master.

encoder_ratio.N.error float out

The error in the position of the slave (in revolutions)

PARAMETERS

encoder_ratio.N.master-ppr unsigned rw

encoder_ratio.N.slave-ppr unsigned rw

The number of pulses per revolution of the master and slave axes

encoder_ratio.N.master-teeth unsigned rw

encoder_ratio.N.slave-teeth unsigned rw

The number of "teeth" on the master and slave gears.

SEE ALSO

encoder(9)

NAME

`estop_latch` – ESTOP latch which sets ok-out true and fault-out false only if ok-in is true, fault-in is false, and a rising edge is seen on reset. While ok-out is true, watchdog toggles, and can be used for chargepumps or similar needs.

SYNOPSIS

```
loadrt estop_latch [count=Nnames=name1[,name2...]]
```

FUNCTIONS

`estop-latch.N`

PINS

`estop-latch.N.ok-in` bit in
`estop-latch.N.fault-in` bit in
`estop-latch.N.reset` bit in
`estop-latch.N.ok-out` bit out
`estop-latch.N.fault-out` bit out
`estop-latch.N.watchdog` bit out

LICENSE

GPL

NAME

feedcomp – Multiply the input by the ratio of current velocity to the feed rate

SYNOPSIS

loadrt feedcomp [count=*N*][names=*name1*[,*name2*...]]

FUNCTIONS

feedcomp.N (requires a floating-point thread)

PINS

feedcomp.N.out float out
Proportionate output value

feedcomp.N.in float in
Reference value

feedcomp.N.enable bit in
Turn compensation on or off

feedcomp.N.vel float in
Current velocity

PARAMETERS

feedcomp.N.feed float rw
Feed rate reference value

NOTES

Note that if enable is false, out = in

LICENSE

GPL

NAME

flipflop – D type flip-flop

SYNOPSIS

loadrt flipflop [**count**=*N*]**names**=*name1*[,*name2*...]

FUNCTIONS

flipflop.N

PINS

flipflop.N.data bit in
data input

flipflop.N.clk bit in
clock, rising edge writes data to out

flipflop.N.set bit in
when true, force out true

flipflop.N.reset bit in
when true, force out false; overrides set

flipflop.N.out bit io
output

LICENSE

GPL

NAME

freqgen – software step pulse generation

OBSOLETE - see **stepgen**'s 'ctrl_type=v' option.

SYNOPSIS

loadrt freqgen step_type=type0[,type1...]

DESCRIPTION

freqgen is used to control stepper motors. The maximum step rate depends on the CPU and other factors, and is usually in the range of 10KHz to 50KHz. If higher rates are needed, a hardware step generator is a better choice.

freqgen runs the motor at a commanded velocity, subject to acceleration and velocity limits. It does not directly control position.

freqgen can control a maximum of eight motors. The number of motors/channels actually loaded depends on the number of *type* values given. The value of each *type* determines the outputs for that channel. **freqgen** supports 15 possible step types.

By far the most common step type is '0', standard step and direction. Others include up/down, quadrature, and a wide variety of three, four, and five phase patterns that can be used to directly control some types of motor windings. (When used with appropriate buffers of course.)

Some of the stepping types are described below, but for more details (including timing diagrams) see the **stepgen** section of the HAL reference manual.

type 0: step/dir

Two pins, one for step and one for direction. **make-pulses** must run at least twice for each step (once to set the step pin true, once to clear it). This limits the maximum step rate to half (or less) of the rate that can be reached by types 2-14. The parameters **steplen** and **stepspace** can further lower the maximum step rate. Parameters **dirsetup** and **dirhold** also apply to this step type.

type 1: up/down

Two pins, one for 'step up' and one for 'step down'. Like type 0, **make-pulses** must run twice per step, which limits the maximum speed.

type 2: quadrature

Two pins, phase-A and phase-B. For forward motion, A leads B. Can advance by one step every time **make-pulses** runs.

type 3: three phase, full step

Three pins, phase-A, phase-B, and phase-C. Three steps per full cycle, then repeats. Only one phase is high at a time - for forward motion the pattern is A, then B, then C, then A again.

type 4: three phase, half step

Three pins, phases A through C. Six steps per full cycle. First A is high alone, then A and B together, then B alone, then B and C together, etc.

types 5 through 8: four phase, full step

Four pins, phases A through D. Four steps per full cycle. Types 5 and 6 are suitable for use with unipolar steppers, where power is applied to the center tap of each winding, and four open-collector transistors drive the ends. Types 7 and 8 are suitable for bipolar steppers, driven by two H-bridges.

types 9 and 10: four phase, half step

Four pins, phases A through D. Eight steps per full cycle. Type 9 is suitable for unipolar drive, and type 10 for bipolar drive.

types 11 and 12: five phase, full step

Five pins, phases A through E. Five steps per full cycle. See HAL reference manual for the patterns.

types 13 and 14: five phase, half step

Five pins, phases A through E. Ten steps per full cycle. See HAL reference manual for the patterns.

FUNCTIONS

freqgen.make-pulses (no floating-point)

Generates the step pulses, using information computed by **update-freq**. Must be called as frequently as possible, to maximize the attainable step rate and minimize jitter. Operates on all channels at once.

freqgen.capture-position (uses floating point)

Captures position feedback value from the high speed code and makes it available on a pin for use elsewhere in the system. Operates on all channels at once.

freqgen.update-freq (uses floating point)

Accepts a velocity command and converts it into a form usable by **make-pulses** for step generation. Operates on all channels at once.

PINS

freqgen.N.counts s32 out

The current position, in counts, for channel *N*. Updated by **capture-position**.

freqgen.N.position-fb float out

The current position, in length units (see parameter **position-scale**). Updated by **capture-position**.

freqgen.N.velocity float in (**freqgen** only)

Commanded velocity, in length units per second (see parameter **velocity-scale**).

freqgen.N.step bit out (step type 0 only)

Step pulse output.

freqgen.N.dir bit out (step type 0 only)

Direction output: low for forward, high for reverse.

freqgen.N.up bit out (step type 1 only)

Count up output, pulses for forward steps.

freqgen.N.down bit out (step type 1 only)

Count down output, pulses for reverse steps.

freqgen.N.phase-A thru **phase-E** bit out (step types 2-14 only)

Output bits. **phase-A** and **phase-B** are present for step types 2-14, **phase-C** for types 3-14, **phase-D** for types 5-14, and **phase-E** for types 11-14. Behavior depends on selected stepping type.

PARAMETERS

freqgen.N.frequency float ro

The current step rate, in steps per second, for channel *N*.

freqgen.N.maxaccel float rw

The acceleration/deceleration limit, in steps per second squared.

freqgen.N.maxfreq float rw (**freqgen** only)

The maximum allowable velocity, in steps per second. If the requested maximum velocity cannot be reached with the current **make-pulses** thread period, it will be reset to the highest attainable value.

freqgen.N.position-scale float rw

The scaling for position feedback, in steps per length unit.

- freqgen.N.velocity-scale** float rw
The scaling for the velocity command, in steps per length unit.
- freqgen.N.rawcounts** s32 ro
The position in counts, as updated by **make-pulses**. (Note: this is updated more frequently than the **counts** pin.)
- freqgen.N.steplen** u32 rw (step type 0 only)
The length of the step pulses, in **make-pulses** periods. Measured from rising edge to falling edge.
- freqgen.N.stepspace** u32 rw (step type 0 only)
The minimum space between step pulses, in **make-pulses** periods. Measured from falling edge to rising edge. The actual time depends on the step rate and can be much longer.
- freqgen.N.dirsetup** u32 rw (step type 0 only)
The minimum setup time from direction to step, in **make-pulses** periods. Measured from change of direction to rising edge of step.
- freqgen.N.dirhold** u32 rw (step type 0 only)
The minimum hold time of direction after step, in **make-pulses** periods. Measured from falling edge of step to change of direction.

BUGS

- freqgen** should have an **enable** pin.
- freqgen**'s command pin should be called **velocity-cmd**, not **velocity**, for clarity and consistency with **stepgen**.
- freqgen** should use **maxvel**, not **maxfreq**. (In other words, the velocity limit should be scaled in length units per second, not steps per second. The scale parameter can be set to 1.0 if it is desired to work in steps instead of length units.)
- freqgen**'s **maxaccel** parameter should be in length units per second squared, not steps per second squared, for consistency with **stepgen**.
- freqgen** should use **position-scale** for scaling both command and feedback, **velocity-scale** is redundant and should be eliminated.
- Step type 1 (up/down) should respect the **steplen** and **stepspace** limits.
- Timing parameters **steplen**, **stepspace**, **dirsetup**, and **dirhold** should be in nano-seconds, not **make-pulses** periods. That would allow the period to be changed without requiring the parameters to be recalculated.
- All of these bugs have been fixed in **stepgen**. Only **stepgen** will continue to be maintained, since **freqgen** contains large amounts of code that duplicates code in **stepgen**. Since **stepgen** can provide the same functionality, there is no reason to maintain the duplicate code. **freqgen** may be eliminated at any time, and almost certainly **will** be eliminated for the version 2.2 release of EMC.

SEE ALSO

stepgen(9)

NAME

gantrykins – A kinematics module that maps one axis to multiple joints

SYNOPSIS

loadrt gantrykins coordinates=axisletters

Specifying gantry joint mapping via loadrt

The **coordinates=** parameter specifies the initial gantry joint mapping. Each axis letter is mapped to a joint, starting from 0. So **coordinates=XYYZ** maps the X axis to joint 0, the Y axis to joint 1 and 2, and the Z axis to joint 3. If not specified, the default mapping is **coordinates=XYZABC**. Coordinate letters may be specified in uppercase or lowercase.

A note about joints and axes

EMC2 makes a distinction between joints and axes: a joint is something controlled by a motor, and an axis is a coordinate you can move via G-code. You can also jog joints or jog axes.

A gantry has two joints controlling one axis, and this requires a bit of special care.

Homing always happens in joint mode (aka Free mode). The two joints of a gantry's axis must be homed together, so they must have the same [AXIS_n]HOME_SEQUENCE in the .ini file.

Jogging of a gantry must happen in world mode (aka Teleop mode). If you jog a gantry in joint mode (Free mode), you will move just one of the joints, and the gantry will rack. In contrast, if you jog a gantry in world mode (Teleop mode), it's the axis that jogs: emc2 will coordinate the motion of the two joints that make up the axis, both joints will move together, and the gantry will stay square.

The Axis GUI has provisions for jogging in joint mode (Free) and in world mode (Teleop). Use the "\$" hotkey, or the View menu to switch between them.

Joint-mode (aka Free mode) supports continuous and incremental jogging. World-mode (aka Teleop mode) only supports continuous jogging.

KINEMATICS

In the inverse kinematics, each joint gets the value of its corresponding axis. In the forward kinematics, each axis gets the value of the highest numbered corresponding joint. For example, with **coordinates=XYYZ** the Y axis position comes from joint 2, not joint 1.

FUNCTIONS

None.

PINS

None.

PARAMETERS

gantrykins.joint-N (s32)

Specifies the axis mapped to joint *N*. The values 0 through 8 correspond to the axes XYZ-ABCUVW. It is preferable to use the "coordinates=" parameter at loadrt-time rather than setting the joint-N parameters later, because the gantrykins module prints the joint-to-axis mapping at loadrt-time, and having that output correct is nice.

NOTES

gantrykins must be loaded before **motion**.

SEE ALSO

kins(9), The Kinematics section of the EMC2 Developer Manual

LICENSE

GPL

NAME

gearchange – Select from one two speed ranges

SYNOPSIS

The output will be a value scaled for the selected gear, and clamped to the min/max values for that gear. The scale of gear 1 is assumed to be 1, so the output device scale should be chosen accordingly. The scale of gear 2 is relative to gear 1, so if gear 2 runs the spindle 2.5 times as fast as gear 1, scale2 should be set to 2.5.

FUNCTIONS

gearchange.N (requires a floating-point thread)

PINS

gearchange.N.sel bit in

Gear selection input

gearchange.N.speed-in float in

Speed command input

gearchange.N.speed-out float out

Speed command to DAC/PWM

gearchange.N.dir-in bit in

Direction command input

gearchange.N.dir-out bit out

Direction output - possibly inverted for second gear

PARAMETERS

gearchange.N.min1 float rw (default: 0)

Minimum allowed speed in gear range 1

gearchange.N.max1 float rw (default: 100000)

Maximum allowed speed in gear range 1

gearchange.N.min2 float rw (default: 0)

Minimum allowed speed in gear range 2

gearchange.N.max2 float rw (default: 100000)

Maximum allowed speed in gear range 2

gearchange.N.scale2 float rw (default: 1.0)

Relative scale of gear 2 vs. gear 1 Since it is assumed that gear 2 is "high gear", **scale2** must be greater than 1, and will be reset to 1 if set lower.

gearchange.N.reverse bit rw (default: 0)

Set to 1 to reverse the spindle in second gear

LICENSE

GPL

NAME

hm2_7i43 – EMC2 HAL driver for the Mesa Electronics 7i43 EPP Anything IO board with HostMot2 firmware.

SYNOPSIS

```
loadrt hm2_7i43 [ioaddr=N] [ioaddr_hi=N] [epp_wide=N] [config="str[,str...]"] [debug_epp=N]
```

ioaddr [default: 0x378]

The base address of the parallel port.

ioaddr_hi [default: 0]

The secondary address of the parallel port, used to set EPP mode. 0 means to use ioaddr + 0x400.

epp_wide [default: 1]

Set to zero to disable the "wide EPP mode". "Wide" mode allows a 16- and 32-bit EPP transfers, which can reduce the time spent in the read and write functions. However, this may not work on all EPP parallel ports.

config [default: ""]

HostMot2 config strings, described in the hostmot2(9) manpage.

debug_epp [default: 0]

Developer/debug use only! Enable debug logging of most EPP transfers.

DESCRIPTION

hm2_7i43 is a device driver that interfaces the Mesa 7i43 board with the HostMot2 firmware to the EMC2 HAL. Both the 200K and the 400K FPGAs are supported.

The driver talks with the 7i43 over the parallel port, not over USB. USB can be used to power the 7i43, but not to talk to it. USB communication with the 7i43 will not be supported any time soon, since USB has poor real-time qualities.

The driver programs the board's FPGA with firmware when it registers the board with the hostmot2 driver. The old bload(1) firmware loading method is not used anymore. Instead the firmware to load is specified in the **config** modparam, as described in the hostmot2(9) manpage, in the *config modparam* section.

Some parallel ports require special initialization before they can be used. EMC2 provides a kernel driver that does this initialization called probe_parport. Load this driver before loading hm2_7i43, by putting "loadrt probe_parport" in your .hal file.

Jumper settings

To send the FPGA configuration from the PC, the board must be configured to get its firmware from the EPP port. To do this, jumpers W4 and W5 must both be down, ie toward the USB connector.

The board must be configured to power on whether or not the USB interface is active. This is done by setting jumper W7 up, ie away from the edge of the board.

Communicating with the board

The 7i43 communicates with the EMC computer over EPP, the Enhanced Parallel Port. This provides about 1 MBps of throughput, and the communication latency is very predictable and reasonably low.

The parallel port must support EPP 1.7 or EPP 1.9. EPP 1.9 is preferred, but EPP 1.7 will work too. The EPP mode of the parallel port is sometimes a setting in the BIOS.

Note that the popular "NetMOS" aka "MosChip 9805" PCI parport cards **do not work**. They do not meet the EPP spec, and cannot be reliably used with the 7i43. You have to find another card, sorry.

EPP is very reliable under normal circumstances, but bad cabling or excessively long cabling runs may cause communication timeouts. The driver exports a parameter named hm2_7i43.<BoardNum>.io_error to

inform HAL of this condition. When the driver detects an EPP timeout, it sets `io_error` to `True` and stops communicating with the 7i43 board. Setting `io_error` back to `False` makes the driver start trying to communicate with the 7i43 again.

Access to the EPP bus is not threadsafe: only one realtime thread may access the EPP bus.

SEE ALSO

`hostmot2(9)`

LICENSE

GPL

NAME

hm2_pci – EMC2 HAL driver for the Mesa Electronics PCI-based Anything IO boards, with HostMot2 firmware.

SYNOPSIS

```
loadrt hm2_pci [config="str[,str...]"]
```

```
    config [default: ""]
```

HostMot2 config strings, described in the hostmot2(9) manpage.

DESCRIPTION

hm2_pci is a device driver that interfaces Mesa's PCI and PC-104/Plus based Anything I/O boards (with the HostMot2 firmware) to the EMC2 HAL.

The supported boards are: the 5i20, 5i22, and 5i23 (all on PCI); the 4i65 and 4i68 (on PC-104/Plus), and the 3x20 (on PCI Express, probably using a 6i68 or 7i68 carrier card).

The driver programs the board's FPGA with firmware when it registers the board with the hostmot2 driver. The firmware to load is specified in the **config** modparam, as described in the hostmot2(9) manpage, in the *config modparam* section.

SEE ALSO

hostmot2(9)

LICENSE

GPL

NAME

hostmot2 – EMC2 HAL driver for the Mesa Electronics HostMot2 firmware.

SYNOPSIS

loadrt hostmot2 [**debug_idrom**=*N*] [**debug_module_descriptors**=*N*] [**debug_pin_descriptors**=*N*] [**debug_modules**=*N*]

debug_idrom [default: 0]

Developer/debug use only! Enable debug logging of the HostMot2 IDROM header.

debug_module_descriptors [default: 0]

Developer/debug use only! Enable debug logging of the HostMot2 Module Descriptors.

debug_pin_descriptors [default: 0]

Developer/debug use only! Enable debug logging of the HostMot2 Pin Descriptors.

debug_modules [default: 0]

Developer/debug use only! Enable debug logging of the HostMot2 Modules used.

DESCRIPTION

hostmot2 is a device driver that interfaces the Mesa HostMot2 firmware to the EMC2 HAL. This driver by itself does nothing, the boards that actually run the firmware require their own drivers before anything can happen. Currently drivers are available for the 5i20, 5i22, 5i23, 3x20, 4i65, and 4i68 (all using the hm2_pci module) and the 7i43 (using the hm2_7i43 module).

The HostMot2 firmware provides encoders, PWM generators, step/dir generators, and general purpose I/O pins (GPIOs). These things are called "Modules". The firmware is configured, at firmware compile time, to provide zero or more instances of each of these four Modules.

Board I/O Pins

The HostMot2 firmware runs on an FPGA board. The board interfaces with the computer via PCI, PC-104/Plus, or EPP, and interfaces with motion control hardware such as servos and stepper motors via I/O pins on the board.

Each I/O pin can be configured, at board-driver load time, to serve one of two purposes: either as a particular I/O pin of a particular Module instance (encoder, pwmgen, or stepgen), or as a general purpose digital I/O pin. By default all Module instances are enabled, and all the board's pins are used by the Module instances.

The user can disable Module instances at board-driver load time, by specifying a hostmot2 config string modparam. Any pins which belong to Module instances that have been disabled automatically become GPIOs.

All IO pins have some HAL presence, whether they belong to an active module instance or are full GPIOs. GPIOs can be changed (at run-time) between inputs, normal outputs, and open drains, and have a flexible HAL interface. IO pins that belong to active Module instances are constrained by the requirements of the owning Module, and have a more limited interface in HAL. This is described in the General Purpose I/O section below.

config modparam

All the board-driver modules (hm2_pci and hm2_7i43) accept a load-time modparam of type string array, named "config". This array has one config string for each board the driver should use. Each board's config string is passed to and parsed by the hostmot2 driver when the board-driver registers the board.

The config string can contain spaces, so it is usually a good idea to wrap the whole thing in double-quotes (the " character).

The comma character (,) separates members of the config array from each other.

For example, if your control computer has one 5i20 and one 5i23 you might load the hm2_pci driver with a HAL command (in halcmd) something like this:

```
loadrt hm2_pci config="firmware=hm2/5i20/SVST8_4.BIT num_encoders=3 num_pwmgens=3 num_stepgens=0,firmw
```

Note: this assumes that the hm2_pci driver detects the 5i20 first and the 5i23 second. If the detection order does not match the order of the config strings, the hostmot2 driver will refuse to load the firmware and the board-driver (hm2_pci or hm2_7i43) will fail to load. To the best of my knowledge, there is no way to predict the order in which PCI boards will be detected by the driver, but the detection order will be consistent as long as PCI boards are not moved around. Best to try loading it and see what the detection order is.

The format of each board's config string is:

```
[firmware=F] [num_encoders=N] [num_pwmgens=N] [num_stepgens=N] [enable_raw]
```

firmware [optional]

Load the firmware specified by *F* into the FPGA on this board. If no "firmware=*F*" string is specified, the FPGA will not be programmed, and had better have a valid configuration already.

The requested firmware *F* is fetched by udev. udev searches for the firmware in the system's firmware search path, usually /lib/firmware. *F* typically has the form "hm2/<BoardType>/file.bit"; a typical value for *F* might be "hm2/5i20/SVST8_4.BIT". The firmware files are distributed separately from EMC2/LinuxCNC, in the hostmot2-firmware packages available from linuxcnc.org.

num_encoders [optional, default: -1]

Only enable the first *N* encoders. If *N* is -1, all encoders are enabled. If *N* is 0, no encoders are enabled. If *N* is greater than the number of encoders available in the firmware, the board will fail to register.

num_pwmgens [optional, default: -1]

Only enable the first *N* pwmgens. If *N* is -1, all pwmgens are enabled. If *N* is 0, no pwmgens are enabled. If *N* is greater than the number of pwmgens available in the firmware, the board will fail to register.

num_stepgens [optional, default: -1]

Only enable the first *N* stepgens. If *N* is -1, all stepgens are enabled. If *N* is 0, no stepgens are enabled. If *N* is greater than the number of stepgens available in the firmware, the board will fail to register.

enable_raw [optional]

If specified, this turns on a raw access mode, whereby a user can peek and poke the firmware from HAL. See Raw Mode below.

encoder

Encoders have names like "hm2-<BoardType>.<BoardNum>.encoder.<Instance>". "Instance" is a two-digit number that corresponds to the HostMot2 encoder instance number. There are 'num_encoders' instances, starting with 00.

So, for example, the HAL pin that has the current position of the second encoder of the first 5i20 board is: hm2_5i20.0.encoder.01.position (this assumes that the firmware in that board is configured so that this HAL object is available)

Each encoder uses three or four input IO pins, depending on how the firmware was compiled. Three-pin encoders use A, B, and Index (sometimes also known as Z). Four-pin encoders use A, B, Index, and Index-mask.

The hm2 encoder representation is similar to the one described by the Canonical Device Interface (in the

HAL General Reference document), and to the software encoder component. Each encoder instance has the following pins and parameters:

Pins:

(s32 out) count: Number of encoder counts since the previous reset.

(float out) position: Encoder position in position units (count / scale).

(float out) velocity: Estimated encoder velocity in position units per second.

(bit in) reset: When this pin is TRUE, the count and position pins are set to 0. (The value of the velocity pin is not affected by this.) The driver does not reset this pin to FALSE after resetting the count to 0, that is the user's job.

(bit in/out) index-enable: When this pin is set to True, the count (and therefore also position) are reset to zero on the next Index (Phase-Z) pulse. At the same time, index-enable is reset to zero to indicate that the pulse has occurred.

(s32 out) rawcount: Total number of encoder counts since the start, not adjusted for index or reset.

Parameters:

(float r/w) scale: Converts from 'count' units to 'position' units.

(bit r/w) index-invert: If set to True, the rising edge of the Index input pin triggers the Index event (if index-enable is True). If set to False, the falling edge triggers.

(bit r/w) index-mask: If set to True, the Index input pin only has an effect if the Index-Mask input pin is True (or False, depending on the index-mask-invert pin below).

(bit r/w) index-mask-invert: If set to True, Index-Mask must be False for Index to have an effect. If set to False, the Index-Mask pin must be True.

(bit r/w) counter-mode: Set to False (the default) for Quadrature. Set to True for Step/Dir (in which case Step is on the A pin and Dir is on the B pin).

(bit r/w) filter: If set to True (the default), the quadrature counter needs 15 clocks to register a change on any of the three input lines (any pulse shorter than this is rejected as noise). If set to False, the quadrature counter needs only 3 clocks to register a change. The encoder sample clock runs at 33 MHz on the PCI AnyIO cards and 50 MHz on the 7i43.

(float r/w) vel-timeout: When the encoder is moving slower than one pulse for each time that the driver reads the count from the FPGA (in the hm2_read() function), the velocity is harder to estimate. The driver can wait several iterations for the next pulse to arrive, all the while reporting the upper bound of the encoder velocity, which can be accurately guessed. This parameter specifies how long to wait for the next pulse, before reporting the encoder stopped. This parameter is in seconds.

pwmgen

pwmgens have names like "hm2_<BoardType>.<BoardNum>.pwmgen.<Instance>". "Instance" is a two-digit number that corresponds to the HostMot2 pwmgen instance number. There are 'num_pwmgen' instances, starting with 00.

So, for example, the HAL pin that enables output from the fourth pwmgen of the first 7i43 board is: hm2_7i43.0.pwmgen.03.enable (this assumes that the firmware in that board is configured so that this HAL

object is available)

In HM2, each pwmgen uses three output IO pins: Not-Enable, Out0, and Out1.

The function of the Out0 and Out1 IO pins varies with output-type parameter (see below).

The hm2 pwmgen representation is similar to the software pwmgen component. Each pwmgen instance has the following pins and parameters:

Pins:

(bit input) enable: If true, the pwmgen will set its Not-Enable pin false and output its pulses. If 'enable' is false, pwmgen will set its Not-Enable pin true and not output any signals.

(float input) value: The current pwmgen command value, in arbitrary units.

Parameters:

(float rw) scale: Scaling factor to convert 'value' from arbitrary units to duty cycle: $dc = value / scale$. Duty cycle has an effective range of -1.0 to +1.0 inclusive, anything outside that range gets clipped.

(s32 rw) output-type: This emulates the output_type load-time argument to the software pwmgen component. This parameter may be changed at runtime, but most of the time you probably want to set it at startup and then leave it alone. Accepted values are 1 (PWM on Out0 and Direction on Out1), 2 (Up on Out0 and Down on Out1), 3 (PDM mode, PDM on Out0 and Dir on Out1), and 4 (Direction on Out0 and PWM on Out1, "for locked antiphase").

In addition to the per-instance HAL Parameters listed above, there are a couple of HAL Parameters that affect all the pwmgen instances:

(u32 rw) pwm_frequency: This specifies the PWM frequency, in Hz, of all the pwmgen instances running in the PWM modes (modes 1 and 2). This is the frequency of the variable-duty-cycle wave. Its effective range is from 1 Hz up to 193 KHz. Note that the max frequency is determined by the ClockHigh frequency of the Anything IO board; the 5i20 and 7i43 both have a 100 MHz clock, resulting in a 193 KHz max PWM frequency. Other boards may have different clocks, resulting in different max PWM frequencies. If the user attempts to set the frequency too high, it will be clipped to the max supported frequency of the board. Frequencies below about 5 Hz are not terribly accurate, but above 5 Hz they're pretty close.

(u32 rw) pdm_frequency: This specifies the PDM frequency, in Hz, of all the pwmgen instances running in PDM mode (mode 3). This is the "pulse slot frequency"; the frequency at which the pdm generator in the AnyIO board chooses whether to emit a pulse or a space. Each pulse (and space) in the PDM pulse train has a duration of $1/pdm_frequency$ seconds. For example, setting the pdm_frequency to 2e6 (2 MHz) and the duty cycle to 50% results in a 1 MHz square wave, identical to a 1 MHz PWM signal with 50% duty cycle. The effective range of this parameter is from about 1525 Hz up to just under 100 MHz. Note that the max frequency is determined by the ClockHigh frequency of the Anything IO board; the 5i20 and 7i43 both have a 100 MHz clock, resulting in a 100 Mhz max PDM frequency. Other boards may have different clocks, resulting in different max PDM frequencies. If the user attempts to set the frequency too high, it will be clipped to the max supported frequency of the board.

stepgen

stepgens have names like "hm2_<BoardType>.<BoardNum>.stepgen.<Instance>". "Instance" is a two-digit number that corresponds to the HostMot2 stepgen instance number. There are 'num_stepgens' instances, starting with 00.

So, for example, the HAL pin that has the current position feedback from the first stepgen of the second

5i22 board is: hm2_5i22.1.stepgen.00.position-fb (this assumes that the firmware in that board is configured so that this HAL object is available)

Each stepgen uses 2 IO pins. The signals on these pins depends on the step_type parameter (described below).

The stepgen representation is modeled on the stepgen software component. Each stepgen instance has the following pins and parameters:

Pins:

(float input) position-cmd: Target position of stepper motion, in arbitrary position units. This pin is only used when the stepgen is in position control mode (control-type=0).

(float input) velocity-cmd: Target velocity of stepper motion, in arbitrary position units per second. This pin is only used when the stepgen is in velocity control mode (control-type=1).

(s32 output) counts: Feedback position in counts (number of steps).

(float output) position-fb: Feedback position in arbitrary position units. This is similar to "counts/position_scale", but has finer than step resolution.

(float output) velocity-fb: Feedback velocity in arbitrary position units per second.

(bit input) enable: This pin enables the step generator instance. When True, the stepgen instance works as expected. When False, no steps are generated and velocity-fb goes immediately to 0. If the stepgen is moving when enable goes false it stops immediately, without obeying the maxaccel limit.

(bit input) control-type: Switches between position control mode (0) and velocity control mode (1). Defaults to position control (0).

Parameters:

(float r/w) position-scale: Converts from counts to position units. $position = counts / position_scale$

(float r/w) maxvel: Maximum speed, in position units per second. If set to 0, the driver will always use the maximum possible velocity based on the current step timings and position-scale. The max velocity will change if the step timings or position-scale changes. Defaults to 0.

(float r/w) maxaccel: Maximum acceleration, in position units per second per second. Defaults to 1.0. If set to 0, the driver will not limit its acceleration at all - this requires that the position-cmd or velocity-cmd pin is driven in a way that does not exceed the machine's capabilities. This is probably what you want if you're going to be using the EMC2 trajectory planner to jog or run G-code.

(u32 r/w) steplen: Duration of the step signal, in nanoseconds.

(u32 r/w) stepspace: Minimum interval between step signals, in nanoseconds.

(u32 r/w) dirsetup: Minimum duration of stable Direction signal before a step begins, in nanoseconds.

(u32 r/w) dirhold: Minimum duration of stable Direction signal after a step ends, in nanoseconds.

(u32 r/w) step_type: Output format, like the step_type modparam to the software stepgen(9) component. 0 = Step/Dir, 1 = Up/Down, 2 = Quadrature. In Quadrature mode (step_type=2), the stepgen outputs one

complete Gray cycle (00 -> 01 -> 11 -> 10 -> 00) for each "step" it takes.

General Purpose I/O

I/O pins on the board which are not used by a module instance are exported to HAL as "full" GPIO pins. Full GPIO pins can be configured at run-time to be inputs, outputs, or open drains, and have a HAL interface that exposes this flexibility. IO pins that are owned by an active module instance are constrained by the requirements of the owning module, and have a restricted HAL interface.

GPIOs have names like "hm2_<BoardType>.<BoardNum>.gpio.<IONum>". IONum is a three-digit number. The mapping from IONum to connector and pin-on-that-connector is written to the syslog when the driver loads, and it's documented in Mesa's manual for the Anything I/O boards.

So, for example, the HAL pin that has the current inverted input value read from GPIO 012 of the second 7i43 board is: hm2_7i43.1.gpio.012.in-not (this assumes that the firmware in that board is configured so that this HAL object is available)

The HAL parameter that controls whether the last GPIO of the first 5i22 is an input or an output is: hm2_5i22.0.gpio.095.is_output (this assumes that the firmware in that board is configured so that this HAL object is available)

The hm2 GPIO representation is modeled after the Digital Inputs and Digital Outputs described in the Canonical Device Interface (part of the HAL General Reference document). Each GPIO can have the following HAL Pins:

(bit out) in & in_not: State (normal and inverted) of the hardware input pin. Both full GPIO pins and IO pins used as inputs by active module instances have these pins.

(bit in) out: Value to be written (possibly inverted) to the hardware output pin. Only full GPIO pins have this pin.

Each GPIO can have the following Parameters:

(bit r/w) is_output: If set to 0, the GPIO is an input. The IO pin is put in a high-impedance state (weakly pulled high), to be driven by other devices. The logic value on the IO pin is available in the "in" and "in_not" HAL pins. Writes to the "out" HAL pin have no effect. If this parameter is set to 1, the GPIO is an output; its behavior then depends on the "is_opendrain" parameter. Only full GPIO pins have this parameter.

(bit r/w) is_opendrain: This parameter only has an effect if the "is_output" parameter is true. If this parameter is false, the GPIO behaves as a normal output pin: the IO pin on the connector is driven to the value specified by the "out" HAL pin (possibly inverted), and the value of the "in" and "in_not" HAL pins is undefined. If this parameter is true, the GPIO behaves as an open-drain pin. Writing 0 to the "out" HAL pin drives the IO pin low, writing 1 to the "out" HAL pin puts the IO pin in a high-impedance state. In this high-impedance state the IO pin floats (weakly pulled high), and other devices can drive the value; the resulting value on the IO pin is available on the "in" and "in_not" pins. Only full GPIO pins and IO pins used as outputs by active module instances have this parameter.

(bit r/w) invert_output: This parameter only has an effect if the "is_output" parameter is true. If this parameter is true, the output value of the GPIO will be the inverse of the value on the "out" HAL pin. Only full GPIO pins and IO pins used as outputs by active module instances have this parameter.

Watchdog

The HostMot2 firmware may include a watchdog Module; if it does, the hostmot2 driver will use it. The HAL representation of the watchdog is named "hm2_<BoardType>.<BoardNum>.watchdog".

The watchdog must be petted by EMC2 periodically or it will bite.

When the watchdog bites, all the board's I/O pins are disconnected from their Module instances and become high-impedance inputs (pulled high), and all communication with the board stops. The state of the HostMot2 firmware modules is not disturbed (except for the configuration of the IO Pins). Encoder instances keep counting quadrature pulses, and pwm- and step-generators keep generating signals (which are **not** relayed to the motors, because the IO Pins have become inputs).

Resetting the watchdog resumes communication and resets the I/O pins to the configuration chosen at load-time.

If the firmware includes a watchdog, the following HAL objects will be exported:

Pins:

(bit in/out) `has_bit`: True if the watchdog has bit, False if the watchdog has not bit. If the watchdog has bit and the `has_bit` bit is True, the user can reset it to False to resume operation.

Parameters:

(u32 read/write) `timeout_ns`: Watchdog timeout, in nanoseconds. This is initialized to 1,000,000,000 (1 second) at module load time. If more than this amount of time passes between calls to the `pet_watchdog()` function, the watchdog will bite.

Functions:

`pet_watchdog()`: Calling this function resets the watchdog timer and postpones the watchdog biting until `timeout_ns` nanoseconds later.

Raw Mode

If the "enable_raw" config keyword is specified, some extra debugging pins are made available in HAL. The raw mode HAL pin names begin with "hm2_<BoardType>.<BoardNum>.raw".

With Raw mode enabled, a user may peek and poke the firmware from HAL, and may dump the internal state of the hostmot2 driver to the syslog.

Pins:

(u32 in) `read_address`: The bottom 16 bits of this is used as the address to read from.

(u32 out) `read_data`: Each time the `hm2_read()` function is called, this pin is updated with the value at `.read_address`.

(u32 in) `write_address`: The bottom 16 bits of this is used as the address to write to.

(u32 in) `write_data`: This is the value to write to `.write_address`.

(bit in) `write_strobe`: Each time the `hm2_write()` function is called, this pin is examined. If it is True, then value in `.write_data` is written to the address in `.write_address`, and `.write_strobe` is set back to False.

(bit in/out) `dump_state`: This pin is normally False. If it gets set to True the hostmot2 driver will write its representation of the board's internal state to the syslog, and set the pin back to False.

FUNCTIONS

hm2_<BoardType>.<BoardNum>.read

This reads the encoder counters, stepgen feedbacks, and GPIO input pins from the FPGA.

hm2_<BoardType>.<BoardNum>.write

This updates the PWM duty cycles, stepgen rates, and GPIO outputs on the FPGA. Any changes to configuration pins such as stepgen timing, GPIO inversions, etc, are also effected by this function.

hm2_<BoardType>.<BoardNum>.pet-watchdog

Pet the watchdog to keep it from biting us for a while.

hm2_<BoardType>.<BoardNum>.read_gpio

Read the GPIO input pins. Note that the effect of this function is a subset of the effect of the .read() function described above. Normally only .read() is used. The only reason to call this function is if you want to do GPIO things in a faster-than-servo thread. (This function is not available on the 7i43 due to limitations of the EPP bus.)

hm2_<BoardType>.<BoardNum>.write_gpio

Write the GPIO control registers and output pins. Note that the effect of this function is a subset of the effect of the .write() function described above. Normally only .write() is used. The only reason to call this function is if you want to do GPIO things in a faster-than-servo thread. (This function is not available on the 7i43 due to limitations of the EPP bus.)

SEE ALSO

hm2_7i43(9)

hm2_pci(9)

Mesa's documentation for the Anything I/O boards, at <<http://www.mesanet.com>>

LICENSE

GPL

NAME

hypot – Three-input hypotenuse (Euclidean distance) calculator

SYNOPSIS

loadrt hypot [count=*N*]names=*name1*[,*name2*...]

FUNCTIONS

hypot.*N* (requires a floating-point thread)

PINS

hypot.*N*.in0 float in

hypot.*N*.in1 float in

hypot.*N*.in2 float in

hypot.*N*.out float out

out = sqrt(in0² + in1² + in2²)

LICENSE

GPL

NAME

ilowpass – Low-pass filter with integer inputs and outputs

SYNOPSIS

loadrt ilowpass [count=*N*]names=*name1* [,*name2*...]

DESCRIPTION

While it may find other applications, this component was written to create smoother motion while jogging with an MPG.

In a machine with high acceleration, a short jog can behave almost like a step function. By putting the **ilowpass** component between the MPG encoder **counts** output and the axis jog-counts input, this can be smoothed.

Choose **scale** conservatively so that during a single session there will never be more than about $2e9/\text{scale}$ pulses seen on the MPG. Choose **gain** according to the smoothing level desired. Divide the axis.*N*.jog-scale values by **scale**.

FUNCTIONS

ilowpass.*N* (requires a floating-point thread)

Update the output based on the input and parameters

PINS

ilowpass.*N*.in s32 in

ilowpass.*N*.out s32 out

out tracks **in**scale*** through a low-pass filter of **gain** per period.

PARAMETERS

ilowpass.*N*.scale float rw (default: *1024*)

A scale factor applied to the output value of the low-pass filter.

ilowpass.*N*.gain float rw (default: *.5*)

Together with the period, sets the rate at which the output changes. Useful range is between 0 and 1, with higher values causing the input value to be tracked more quickly. For instance, a setting of 0.9 causes the output value to go 90% of the way towards the input value in each period

AUTHOR

Jeff Epler <jepler@unpythonic.net>

LICENSE

GPL

NAME

integ – Integrator with gain pin and windup limits

SYNOPSIS

loadrt integ [**count**=*N*][**names**=*name1*[,*name2*...]]

FUNCTIONS

integ.N (requires a floating-point thread)

PINS

integ.N.in float in

integ.N.gain float in (default: *1.0*)

integ.N.out float out

The discrete integral of 'gain * in' since 'reset' was deasserted

integ.N.reset bit in

When asserted, set out to 0

integ.N.max float in (default: *1e20*)

integ.N.min float in (default: *-1e20*)

LICENSE

GPL

NAME

invert – Compute the inverse of the input signal

SYNOPSIS

The output will be the mathematical inverse of the input, ie $\mathbf{out} = 1/\mathbf{in}$. The parameter **deadband** can be used to control how close to 0 the denominator can be before the output is clamped to 0. **deadband** must be at least 1e-8, and must be positive.

FUNCTIONS

invert.N (requires a floating-point thread)

PINS

invert.N.in float in
Analog input value

invert.N.out float out
Analog output value

PARAMETERS

invert.N.deadband float rw
The **out** will be zero if **in** is between **-deadband** and **+deadband**

LICENSE

GPL

NAME

joyhandle – sets nonlinear joystick movements, deadbands and scales

SYNOPSIS

loadrt joyhandle [count=*N* | names=*name1* [, *name2* ...]]

DESCRIPTION

The component **joyhandle** uses the following formula for a non linear joystick movements:

$$y = (\text{scale} * (a * x^{\text{power}} + b * x)) + \text{offset}$$

The parameters *a* and *b* are adjusted in such a way, that the function starts at (deadband,offset) and ends at (1,scale+offset).

Negative values will be treated point symmetrically to origin. Values $-\text{deadband} < x < +\text{deadband}$ will be set to zero.

Values $x > 1$ and $x < -1$ will be skipped to $\pm(\text{scale} + \text{offset})$. Invert transforms the function to a progressive movement.

With *power* one can adjust the nonlinearity (default = 2). Default for deadband is 0.

Valid values are: *power* ≥ 1.0 (reasonable values are 1.x .. 4-5, take higher *power*-values for higher deadbands (>0.5), if you want to start with a nearly horizontal slope), $0 \leq \text{deadband} < 0.99$ (reasonable 0.1).

An additional offset component can be set in special cases (default = 0).

All values can be adjusted for each instance separately.

FUNCTIONS

joyhandle.*N* (requires a floating-point thread)

PINS

joyhandle.*N*.in float in

joyhandle.*N*.out float out

PARAMETERS

joyhandle.*N*.power float rw (default: 2.0)

joyhandle.*N*.deadband float rw (default: 0.)

joyhandle.*N*.scale float rw (default: 1.)

joyhandle.*N*.offset float rw (default: 0.)

joyhandle.*N*.inverse bit rw (default: 0)

LICENSE

GPL

NAME

kins – kinematics definitions for emc2

SYNOPSIS

loadrt trivkins

loadrt rotatekins

loadrt tripodkins

loadrt genhexkins

loadrt maxkins

loadrt genserkins

loadrt pumakins

loadrt scarakins

DESCRIPTION

Rather than exporting HAL pins and functions, these components provide the forward and inverse kinematics definitions for emc2.

trivkins – Trivial Kinematics

There is a 1:1 correspondence between joints and axes. Most standard milling machines and lathes use the trivial kinematics module.

rotatekins – Rotated Kinematics

The X and Y axes are rotated 45 degrees compared to the joints 0 and 1.

tripodkins – Tripod Kinematics

The joints represent the distance of the controlled point from three predefined locations (the motors), giving three degrees of freedom in position (XYZ)

tripodkins.Bx

tripodkins.Cx

tripodkins.Cy

The location of the three motors is (0,0), (Bx,0), and (Cx,Cy)

genhexkins – Hexapod Kinematics

Gives six degrees of freedom in position and orientation (XYZABC). The location of the motors is defined at compile time.

maxkins – 5-axis kinematics example

Kinematics for Chris Radek's tabletop 5 axis mill named 'max' with tilting head (B axis) and horizontal rotary mounted to the table (C axis). Provides UVW motion in the rotated coordinate system. The source file, maxkins.c, may be a useful starting point for other 5-axis systems.

genserkins – generalized serial kinematics

Kinematics that can model a general serial-link manipulator with up to 6 angular joints.

The kinematics use Denavit-Hartenberg definition for the joint and links. The DH definitions are the ones used by John J Craig in "Introduction to Robotics: Mechanics and Control" The parameters for the manipulator are defined by hal pins.

genserkins.A-N

genserkins.ALPHA-N

genserkins.D-N

Parameters describing the *N*th joint's geometry.

pumakins – kinematics for puma typed robots

Kinematics for a puma-style robot with 6 joints

pumakins.A2
pumakins.A3
pumakins.D3
pumakins.D4

Describe the geometry of the robot

scarakins – kinematics for SCARA-type robots

scarakins.D1

Vertical distance from the ground plane to the center of the inner arm.

scarakins.D2

Horizontal distance between joint[0] axis and joint[1] axis, ie. the length of the inner arm.

scarakins.D3

Vertical distance from the center of the inner arm to the center of the outer arm. May be positive or negative depending on the structure of the robot.

scarakins.D4

Horizontal distance between joint[1] axis and joint[2] axis, ie. the length of the outer arm.

scarakins.D5

Vertical distance from the end effector to the tooltip. Positive means the tooltip is lower than the end effector, and is the normal case.

scarakins.D6

Horizontal distance from the centerline of the end effector (and the joints 2 and 3 axis) and the tooltip. Zero means the tooltip is on the centerline. Non-zero values should be positive, if negative they introduce a 180 degree offset on the value of joint[3].

SEE ALSO

gantrykins(9), The Kinematics section of the EMC2 Developer Manual

NAME

knob2float – Convert counts (probably from an encoder) to a float value

SYNOPSIS

loadrt knob2float [**count**=*N*][**names**=*name1*[,*name2*...]]

FUNCTIONS

knob2float.N (requires a floating-point thread)

PINS

knob2float.N.counts s32 in
Counts

knob2float.N.enable bit in
When TRUE, output is controlled by count, when FALSE, output is fixed

knob2float.N.scale float in
Amount of output change per count

knob2float.N.out float out
Output value

PARAMETERS

knob2float.N.max-out float rw (default: *1.0*)
Maximum output value, further increases in count will be ignored

knob2float.N.min-out float rw (default: *0.0*)
Minimum output value, further decreases in count will be ignored

LICENSE

GPL

NAME

limit1 – Limit the output signal to fall between min and max

SYNOPSIS

loadrt limit1 [**count**=*N* | **names**=*name1* [, *name2* ...]]

FUNCTIONS

limit1.N (requires a floating-point thread)

PINS

limit1.N.in float in

limit1.N.out float out

PARAMETERS

limit1.N.min float rw (default: *-1e20*)

limit1.N.max float rw (default: *1e20*)

LICENSE

GPL

NAME

limit2 – Limit the output signal to fall between min and max and limit its slew rate to less than maxv per second. When the signal is a position, this means that position and velocity are limited.

SYNOPSIS

loadrt limit2 [**count**=*N* | **names**=*name1* [, *name2* ...]]

FUNCTIONS

limit2.N (requires a floating-point thread)

PINS

limit2.N.in float in

limit2.N.out float out

limit2.N.load bit in

When TRUE, immediately set **out to in**, ignoring maxv

PARAMETERS

limit2.N.min float rw (default: *-1e20*)

limit2.N.max float rw (default: *1e20*)

limit2.N.maxv float rw (default: *1e20*)

LICENSE

GPL

NAME

limit3 – Limit the output signal to fall between min and max, limit its slew rate to less than maxv per second, and limit its second derivative to less than maxa per second squared. When the signal is a position, this means that the position, velocity, and acceleration are limited.

SYNOPSIS

loadrt limit3 [**count**=*N* | **names**=*name1* [, *name2* ...]]

FUNCTIONS

limit3.N (requires a floating-point thread)

PINS

limit3.N.in float in

limit3.N.out float out

limit3.N.load bit in

When TRUE, immediately set **out to in**, ignoring maxv and maxa

PARAMETERS

limit3.N.min float rw (default: *-1e20*)

limit3.N.max float rw (default: *1e20*)

limit3.N.maxv float rw (default: *1e20*)

limit3.N.maxa float rw (default: *1e20*)

LICENSE

GPL

NAME

logic – EMC2 HAL component providing experimental logic functions

SYNOPSIS

loadrt logic [**count**=*N*][**names**=*name1*[,*name2*...]] [**personality**=*P,P*,...]

DESCRIPTION

Experimental general ‘logic function’ component. Can perform ‘and’, ‘or’ and ‘xor’ of up to 16 inputs. Determine the proper value for ‘personality’ by adding:

- The number of input pins, usually from 2 to 16
- 256 (0x100) if the ‘and’ output is desired
- 512 (0x200) if the ‘or’ output is desired
- 1024 (0x400) if the ‘xor’ (exclusive or) output is desired

FUNCTIONS

logic.N

PINS

logic.N.in-MM bit in (MM=00..personality & 0xff)

logic.N.and bit out [if personality & 0x100]

logic.N.or bit out [if personality & 0x200]

logic.N.xor bit out [if personality & 0x400]

LICENSE

GPL

NAME

lowpass – Low-pass filter

SYNOPSIS

loadrt lowpass [**count**=*N* | **names**=*name1* [, *name2* ...]]

FUNCTIONS

lowpass.N (requires a floating-point thread)

PINS

lowpass.N.in float in

lowpass.N.out float out

out += (in - out) * gain

lowpass.N.load bit in

When TRUE, copy **in** to **out** instead of applying the filter equation.

PARAMETERS

lowpass.N.gain float rw

NOTES

The effect of a specific **gain** value is dependent on the period of the function that **lowpass.N** is added to

LICENSE

GPL

NAME

lut5 – Arbitrary 5-input logic function based on a look-up table

SYNOPSIS

```
loadrt lut5 [count=N]names=name1[,name2...]
```

DESCRIPTION

lut5 constructs an arbitrary logic function with up to 5 inputs using a **look-up table**. The function is specified by **function**. The necessary value for **function** can be determined by writing the truth table, and computing the sum of the **weights** for which the output value should be TRUE.

Example Functions

A 5-input *and* function is TRUE only when all the inputs are true, so the correct value for **function** is **0x80000000**.

A 5-input *or* function is TRUE whenever any of the inputs are true, so the correct value for **function** is **0xffffffe**.

A 2-input *xor* function is TRUE whenever exactly one of the inputs is true, so the correct value for **function** is **0x6**. Only **in-0** and **in-1** should be connected to signals, because if any other bit is **TRUE** then the output will be **FALSE**.

Weights for each line of truth table					
Bit 4	Bit 3	Bit 2	Bit 1	Bit 0	Weight
0	0	0	0	0	0x1
0	0	0	0	1	0x2
0	0	0	1	0	0x4
0	0	0	1	1	0x8
0	0	1	0	0	0x10
0	0	1	0	1	0x20
0	0	1	1	0	0x40
0	0	1	1	1	0x80
0	1	0	0	0	0x100
0	1	0	0	1	0x200
0	1	0	1	0	0x400
0	1	0	1	1	0x800
0	1	1	0	0	0x1000
0	1	1	0	1	0x2000
0	1	1	1	0	0x4000
0	1	1	1	1	0x8000
1	0	0	0	0	0x10000
1	0	0	0	1	0x20000
1	0	0	1	0	0x40000
1	0	0	1	1	0x80000
1	0	1	0	0	0x100000
1	0	1	0	1	0x200000
1	0	1	1	0	0x400000
1	0	1	1	1	0x800000
1	1	0	0	0	0x1000000
1	1	0	0	1	0x2000000
1	1	0	1	0	0x4000000
1	1	0	1	1	0x8000000
1	1	1	0	0	0x10000000
1	1	1	0	1	0x20000000
1	1	1	1	0	0x40000000
1	1	1	1	1	0x80000000

FUNCTIONS**lut5.N****PINS****lut5.N.in-0** bit in**lut5.N.in-1** bit in**lut5.N.in-2** bit in**lut5.N.in-3** bit in**lut5.N.in-4** bit in**lut5.N.out** bit out**PARAMETERS****lut5.N.function** u32 rw**LICENSE**

GPL

NAME

maj3 – Compute the majority of 3 inputs

SYNOPSIS

loadrt maj3 [count=*N*|names=*name1*[,*name2*...]]

FUNCTIONS

maj3.*N*

PINS

maj3.*N*.in1 bit in

maj3.*N*.in2 bit in

maj3.*N*.in3 bit in

maj3.*N*.out bit out

PARAMETERS

maj3.*N*.invert bit rw

LICENSE

GPL

NAME

match8 – 8-bit binary match detector

SYNOPSIS

loadrt match8 [**count**=*N*][**names**=*name1*[,*name2*...]]

FUNCTIONS

match8.N

PINS

match8.N.in bit in (default: *TRUE*)

cascade input - if false, output is false regardless of other inputs

match8.N.a0 bit in

match8.N.a1 bit in

match8.N.a2 bit in

match8.N.a3 bit in

match8.N.a4 bit in

match8.N.a5 bit in

match8.N.a6 bit in

match8.N.a7 bit in

match8.N.b0 bit in

match8.N.b1 bit in

match8.N.b2 bit in

match8.N.b3 bit in

match8.N.b4 bit in

match8.N.b5 bit in

match8.N.b6 bit in

match8.N.b7 bit in

match8.N.out bit out

true only if in is true and a[m] matches b[m] for m = 0 thru 7

LICENSE

GPL

NAME

minmax – Track the minimum and maximum values of the input to the outputs

SYNOPSIS

loadrt minmax [**count**=*N*]**names**=*name1*[,*name2*...]

FUNCTIONS

minmax.N (requires a floating-point thread)

PINS

minmax.N.in float in

minmax.N.reset bit in

When reset is asserted, 'in' is copied to the outputs

minmax.N.max float out

minmax.N.min float out

LICENSE

GPL

NAME

motion – accepts NML motion commands, interacts with HAL in realtime

SYNOPSIS

```
loadrt motmod [base_period_nsec=period] [servo_period_nsec=period] [traj_period_nsec=period]
[num_joints=[0-9]] ([num_dio=[1-64]] [num_aio=[1-16]])
```

DESCRIPTION

These pins and parameters are created by the realtime **motmod** module. This module provides a HAL interface for EMC's motion planner. Basically **motmod** takes in a list of waypoints and generates a nice blended and constraint-limited stream of joint positions to be fed to the motor drives.

Optionally the number of Digital I/O is set with num_dio. The number of Analog I/O is set with num_aio. The default is 4 each.

Pin names starting with "**axis**" are actually joint values, but the pins and parameters are still called "**axis.N**". They are read and updated by the motion-controller function.

PINS

axis.N.amp-enable-out OUT bit

TRUE if the amplifier for this joint should be enabled

axis.N.amp-fault-in IN bit

Should be driven TRUE if an external fault is detected with the amplifier for this joint

axis.N.home-sw-in IN bit

Should be driven TRUE if the home switch for this joint is closed

axis.N.homing OUT bit

TRUE if the joint is currently homing

axis.N.index-enable IO BIT

Should be attached to the index-enable pin of the joint's encoder to enable homing to index pulse

axis.N.jog-counts IN s32

Connect to the "counts" pin of an external encoder to use a physical jog wheel.

axis.N.jog-enable IN bit

When TRUE (and in manual mode), any change to "jog-counts" will result in motion. When false, "jog-counts" is ignored.

axis.N.jog-scale IN float

Sets the distance moved for each count on "jog-counts", in machine units.

axis.N.jog-vel-mode IN bit

When FALSE (the default), the jogwheel operates in position mode. The axis will move exactly jog-scale units for each count, regardless of how long that might take. When TRUE, the wheel operates in velocity mode - motion stops when the wheel stops, even if that means the commanded motion is not completed.

axis.N.joint-pos-cmd OUT float

The joint (as opposed to motor) commanded position. There may be several offsets between the joint and motor coordinates: backlash compensation, screw error compensation, and home offsets.

axis.N.joint-pos-fb OUT float

The joint feedback position. This value is computed from the actual motor position minus joint offsets. Useful for machine visualization.

axis.N.motor-pos-probed IN float

The joint position for this joint when the probe input last changed.

axis.N.motor-pos-cmd OUT float

The commanded position for this joint.

axis.N.motor-pos-fb IN float

The actual position for this joint.

axis.N.motor-pos-probed IN float

The actual position for this joint when the probe input last changed. For drivers that support high-resolution probing, connect its latched position output to this pin. For other drivers, connect the same thing that is connected to **joint-pos-fb**.

axis.N.neg-lim-sw-in IN bit

Should be driven TRUE if the negative limit switch for this joint is tripped.

axis.N.pos-lim-sw-in IN bit

Should be driven TRUE if the positive limit switch for this joint is tripped.

motion.adaptive-feed IN float

When adaptive feed is enabled with M52 P1, the commanded velocity is multiplied by this value. This effect is multiplicative with the NML-level feed override value and motion.feed-hold.

motion.analog-in-NN IN float

These pins are used by M66 Enn wait-for-input mode.

motion.analog-out-NN OUT float

These pins are used by M67-68.

motion.coord-error OUT bit

TRUE when motion has encountered an error, such as exceeding a soft limit

motion.coord-mode OUT bit

TRUE when motion is in "coordinated mode", as opposed to "teleop mode"

motion.current-vel

Current cartesian velocity

motion.digital-in-*NN* IN bit

These pins are used by M66 Pnn wait-for-input mode.

motion.digital-out-*NN* OUT bit

These pins are controlled by the M62 through M65 words.

motion.distance-to-go OUT float

Distance remaining in the current move

motion.enable IN bit

If this bit is driven FALSE, motion stops, the machine is placed in the "machine off" state, and a message is displayed for the operator. For normal motion, drive this bit TRUE.

motion.feed-hold IN bit

When Feed Stop Control is enabled with M53 P1, and this bit is TRUE, the feed rate is set to 0.

motion.motion-inpos OUT bit

TRUE if the machine is in position.

motion.motion-enabled IN bit

TRUE when motion is enabled

motion.on-soft-limit OUT bit**motion.probe-input** IN bit

G38.x uses the value on this pin to determine when the probe has made contact. TRUE for probe contact closed (touching), FALSE for probe contact open.

motion.program-line OUT S32**motion.requested-vel** OUT float

The requested velocity with no adjustments for feed override

motion.spindle-at-speed IN bit

Motion will pause until this pin is TRUE, under the following conditions: before the first feed move after each spindle start or speed change; before the start of every chain of spindle-synchronized moves; and if in CSS mode, at every rapid->feed transition.

motion.spindle-brake OUT bit

TRUE when the spindle brake should be applied

motion.spindle-forward OUT bit

TRUE when the spindle should rotate forward

motion.spindle-index-enable I/O bit

For correct operation of spindle synchronized moves, this signal must be hooked to the index-enable pin of the spindle encoder.

motion.spindle-on OUT bit

TRUE when spindle should rotate

motion.spindle-reverse OUT bit

TRUE when the spindle should rotate backward

motion.spindle-revs IN float

For correct operation of spindle synchronized moves, this signal must be hooked to the position pin of the spindle encoder.

motion.spindle-speed-in IN float

Actual spindle speed feedback in revolutions per second; used for G96 feed-per-revolution and constant surface speed modes.

motion.spindle-speed-out OUT float

Desired spindle speed in rotations per minute

motion.spindle-speed-out-rps OUT float

Desired spindle speed in rotations per second

motion.teleop-mode OUT bit**motion.tooloffset.w** OUT float**motion.tooloffset.x** OUT float**motion.tooloffset.z** OUT float**DEBUGGING PINS**

Many of the pins below serve as debugging aids, and are subject to change or removal at any time.

axis.N.active

TRUE when this joint is active

axis.N.backlash-corr

Backlash or screw compensation raw value

axis.N.backlash-filt

Backlash or screw compensation filtered value (respecting motion limits)

axis.N.backlash-vel

Backlash or screw compensation velocity

axis.N.coarse-pos-cmd

axis.N.error

TRUE when this joint has encountered an error, such as a limit switch closing

axis.N.f-error

The actual following error

axis.N.f-error-lim

The following error limit

axis.N.f-errored

TRUE when this joint has exceeded the following error limit

axis.N.faulted**axis.N.free-pos-cmd**

The "free planner" commanded position for this joint.

axis.N.free-tp-enable

TRUE when the "free planner" is enabled for this joint

axis.N.free-vel-lim

The velocity limit for the free planner

axis.N.home-state

Reflects the step of homing currently taking place

axis.N.homed

TRUE if the joint has been homed

axis.N.in-position

TRUE if the joint is using the "free planner" and has come to a stop

axis.N.joint-vel-cmd

The joint's commanded velocity

axis.N.kb-jog-active**axis.N.neg-hard-limit**

The negative hard limit for the joint

axis.N.pos-hard-limit

The positive hard limit for the joint

axis.N.wheel-jog-active

motion.in-position

Same as the pin motion.motion-inpos

motion.motion-enabled**motion.on-soft-limit****motion.program-line****motion.teleop-mode**

TRUE when motion is in "teleop mode", as opposed to "coordinated mode"

PARAMETERS

Many of the parameters serve as debugging aids, and are subject to change or removal at any time.

motion-command-handler.time**motion-command-handler.tmax****motion-controller.time****motion-controller.tmax**

Show information about the execution time of these HAL functions in CPU cycles

motion.debug-*

These values are used for debugging purposes.

motion.servo.last-period

The number of CPU cycles between invocations of the servo thread. Typically, this number divided by the CPU speed gives the time in seconds, and can be used to determine whether the realtime motion controller is meeting its timing constraints

motion.servo.overruns

By noting large differences between successive values of motion.servo.last-period, the motion controller can determine that there has probably been a failure to meet its timing constraints. Each time such a failure is detected, this value is incremented.

FUNCTIONS

Generally, these functions are both added to the servo-thread in the order shown.

motion-command-handler

Processes motion commands coming from user space

motion-controller

Runs the emc motion controller

BUGS

This manual page is horribly incomplete.

SEE ALSO

iocontrol(1)

NAME

mult2 – Product of two inputs

SYNOPSIS

loadrt mult2 [**count**=*N* | **names**=*name1* [, *name2* ...]]

FUNCTIONS

mult2.N (requires a floating-point thread)

PINS

mult2.N.in0 float in

mult2.N.in1 float in

mult2.N.out float out

out = in0 * in1

LICENSE

GPL

NAME

`mux16` – Select from one of sixteen input values

SYNOPSIS

`loadrt mux16 [count=N][names=name1[,name2...]]`

FUNCTIONS

`mux16.N` (uses floating-point)

PINS

`mux16.N.suppress-no-input` bit in

This suppresses changing the output if all select lines are false. This stops unwanted jumps in output between transitions of input.

`mux16.N.sel0` bit in

`mux16.N.sel1` bit in

`mux16.N.sel2` bit in

`mux16.N.sel3` bit in

Together, these determine which `in N` value is copied to `out`.

`mux16.N.out-f` float out

`mux16.N.out-s` s32 out

Follows the value of one of the `in N` values according to the four `sel` values. The s32 value will be truncated and limited to the max and min values of signed values.

`sel3=FALSE, sel2=FALSE, sel1=FALSE, sel0=FALSE`

`out` follows `in0`

`sel3=FALSE, sel2=FALSE, sel1=FALSE, sel0=TRUE`

`out` follows `in1`

etc.

`mux16.N.in00` float in

`mux16.N.in01` float in

`mux16.N.in02` float in

`mux16.N.in03` float in

`mux16.N.in04` float in

`mux16.N.in05` float in

`mux16.N.in06` float in

`mux16.N.in07` float in

`mux16.N.in08` float in

`mux16.N.in09` float in

`mux16.N.in10` float in

`mux16.N.in11` float in

`mux16.N.in12` float in

`mux16.N.in13` float in

`mux16.N.in14` float in

`mux16.N.in15` float in

LICENSE

GPL

NAME

`mux2` – Select from one of two input values

SYNOPSIS

`loadrt mux2 [count=N]names=name1 [,name2...]`

FUNCTIONS

`mux2.N` (requires a floating-point thread)

PINS

`mux2.N.sel` bit in

`mux2.N.out` float out

Follows the value of `in0` if `sel` is FALSE, or `in1` if `sel` is TRUE

`mux2.N.in1` float in

`mux2.N.in0` float in

LICENSE

GPL

NAME

`mux4` – Select from one of four input values

SYNOPSIS

`loadrt mux4 [count=N]names=name1[,name2...]`

FUNCTIONS

`mux4.N` (requires a floating-point thread)

PINS

`mux4.N.sel0` bit in

`mux4.N.sel1` bit in

Together, these determine which `in N` value is copied to `out`.

`mux4.N.out` float out

Follows the value of one of the `in N` values according to the two `sel` values

`sel1=FALSE, sel0=FALSE`

`out` follows `in0`

`sel1=FALSE, sel0=TRUE`

`out` follows `in1`

`sel1=TRUE, sel0=FALSE`

`out` follows `in2`

`sel1=TRUE, sel0=TRUE`

`out` follows `in3`

`mux4.N.in0` float in

`mux4.N.in1` float in

`mux4.N.in2` float in

`mux4.N.in3` float in

LICENSE

GPL

NAME

mux8 – Select from one of eight input values

SYNOPSIS

loadrt mux8 [count=*N*]names=*name1*[,*name2*...]

FUNCTIONS

mux8.*N* (requires a floating-point thread)

PINS

mux8.*N*.sel0 bit in

mux8.*N*.sel1 bit in

mux8.*N*.sel2 bit in

Together, these determine which **in N** value is copied to **out**.

mux8.*N*.out float out

Follows the value of one of the **in N** values according to the three **sel** values

sel2=FALSE, sel1=FALSE, sel0=FALSE

out follows **in0**

sel2=FALSE, sel1=FALSE, sel0=TRUE

out follows **in1**

sel2=FALSE, sel1=TRUE, sel0=FALSE

out follows **in2**

sel2=FALSE, sel1=TRUE, sel0=TRUE

out follows **in3**

sel2=TRUE, sel1=FALSE, sel0=FALSE

out follows **in4**

sel2=TRUE, sel1=FALSE, sel0=TRUE

out follows **in5**

sel2=TRUE, sel1=TRUE, sel0=FALSE

out follows **in6**

sel2=TRUE, sel1=TRUE, sel0=TRUE

out follows **in7**

mux8.*N*.in0 float in

mux8.*N*.in1 float in

mux8.*N*.in2 float in

mux8.*N*.in3 float in

mux8.*N*.in4 float in

mux8.*N*.in5 float in

mux8.*N*.in6 float in

mux8.*N*.in7 float in

LICENSE

GPL

NAME

near – Determine whether two values are roughly equal.

SYNOPSIS

loadrt near [**count**=*N* | **names**=*name1* [, *name2* ...]]

FUNCTIONS

near.N (requires a floating-point thread)

PINS

near.N.in1 float in

near.N.in2 float in

near.N.out bit out

out is true if **in1** and **in2** are within a factor of **scale** (i.e., for in1 positive, $\text{in1}/\text{scale} \leq \text{in2} \leq \text{in1} * \text{scale}$), OR if their absolute difference is no greater than **difference** (i.e., $|\text{in1} - \text{in2}| \leq \text{difference}$). **out** is false otherwise.

PARAMETERS

near.N.scale float rw (default: *1*)

near.N.difference float rw (default: *0*)

LICENSE

GPL

NAME

not – Inverter

SYNOPSIS

loadrt not [**count=N**|**names=name1[,name2...]**]

FUNCTIONS

not.N

PINS

not.N.in bit in

not.N.out bit out

LICENSE

GPL

NAME

offset – Adds an offset to an input, and subtracts it from the feedback value

SYNOPSIS

loadrt offset [count=*N*]names=*name1* [,*name2*...]

FUNCTIONS

offset.*N*.update-output (requires a floating-point thread)

Updated the output value by adding the offset to the input

offset.*N*.update-feedback (requires a floating-point thread)

Update the feedback value by subtracting the offset from the feedback

PINS

offset.*N*.offset float in

The offset value

offset.*N*.in float in

The input value

offset.*N*.out float out

The output value

offset.*N*.fb-in float in

The feedback input value

offset.*N*.fb-out float out

The feedback output value

LICENSE

GPL

NAME

oneshot – one-shot pulse generator

SYNOPSIS

loadrt oneshot [**count**=*N*][**names**=*name1*[,*name2*...]]

FUNCTIONS

oneshot.N (requires a floating-point thread)

Produce output pulses from input edges

PINS

oneshot.N.in bit in

Trigger input

oneshot.N.out bit out

Active high pulse

oneshot.N.out-not bit out

Active low pulse

oneshot.N.width float in (default: 0)

Pulse width in seconds

oneshot.N.time-left float out

Time left in current output pulse

PARAMETERS

oneshot.N.retriggerable bit rw (default: *TRUE*)

Allow additional edges to extend pulse

oneshot.N.rising bit rw (default: *TRUE*)

Trigger on rising edge

oneshot.N.falling bit rw (default: *FALSE*)

Trigger on falling edge

LICENSE

GPL

NAME

opto_ac5 – Realtime driver for opto22 PCI-AC5 cards

SYNOPSIS

```
loadrt opto_ac5 [portconfig0=0xN] [portconfig1=0xN]
```

DESCRIPTION

These pins and parameters are created by the realtime **opto_ac5** module. The portconfig0 and portconfig1 variables are used to configure the two ports of each card. The first 24 bits of a 32 bit number represent the 24 i/o points of each port. The lowest (rightmost) bit would be HAL pin 0 which is header connector pin 47. Then next bit to the left would be HAL pin 1, header connector pin 45 and so on, until bit 24 would be HAL pin 23, header connector pin 1. "1" bits represent output points. So channel 0..11 as inputs and 12..23 as outputs would be represented by (in binary) 111111111110000000000000 which is 0xfff000 in hexadecimal. That is the number you would use Eg. loadrt opto_ac5 portconfig0=0xfff000

If no portconfig variable is specified the default configuration is 12 inputs then 12 outputs.

Up to 4 boards are supported. Boards are numbered starting at 0.

Portnumber can be 0 or 1. Port 0 is closest to the card bracket.

PINS

opto_ac5.[BOARDNUMBER].port[PORTNUMBER].in-[PINNUMBER] OUT bit

opto_ac5.[BOARDNUMBER].port[PORTNUMBER].in-[PINNUMBER]-not OUT bit

Connect a hal bit signal to this pin to read an i/o point from the card. The PINNUMBER represents the position in the relay rack. Eg. PINNUMBER 0 is position 0 in a opto22 relay rack and would be pin 47 on the 50 pin header connector. The **-not** pin is inverted so that LOW gives TRUE and HIGH gives FALSE.

opto_ac5.[BOARDNUMBER].port[PORTNUMBER].out-[PINNUMBER] IN bit

Connect a hal bit signal to this pin to write to an i/o point of the card. The PINNUMBER represents the position in the relay rack. Eg. PINNUMBER 23 is position 23 in a opto22 relay rack and would be pin 1 on the 50 pin header connector.

opto_ac5.[BOARDNUMBER].led[NUMBER] OUT bit

Turns one of the on board LEDS on/off. LEDS are numbered 0 to 3.

PARAMETERS

opto_ac5.[BOARDNUMBER].port[PORTNUMBER].out-[PINNUMBER]-invert W bit

When TRUE, invert the meaning of the corresponding **-out** pin so that TRUE gives LOW and FALSE gives HIGH.

FUNCTIONS

opto_ac5.0.digital-read

Add this to a thread to read all the input points.

opto_ac5.0.digital-write

Add this to a thread to write all the output points and LEDS.

BUGS

All boards are loaded with the same port configurations as the first board.

SEE ALSO

<http://wiki.linuxcnc.org/cgi-bin/emcinfo.pl?OptoPciAc5>

NAME

or2 – Two-input OR gate

SYNOPSIS

loadrt or2 [count=N]names=name1[,name2...]

FUNCTIONS

or2.N

PINS

or2.N.in0 bit in

or2.N.in1 bit in

or2.N.out bit out

out is computed from the value of **in0** and **in1** according to the following rule:

in0=FALSE in1=FALSE

out=FALSE

Otherwise,

out=TRUE

LICENSE

GPL

NAME

`pid` – proportional/integral/derivative controller

SYNOPSIS

```
loadrt pid num_chan=num [debug=dbg]
```

DESCRIPTION

`pid` is a classic Proportional/Integral/Derivative controller, used to control position or speed feedback loops for servo motors and other closed-loop applications.

`pid` supports a maximum of sixteen controllers. The number that are actually loaded is set by the `num_chan` argument when the module is loaded. If `numchan` is not specified, the default value is three. If `debug` is set to 1 (the default is 0), some additional HAL parameters will be exported, which might be useful for tuning, but are otherwise unnecessary.

FUNCTIONS

`pid.N.do-pid-calcs` (uses floating-point)
Does the PID calculations for control loop *N*.

PINS

`pid.N.command` float in
The desired (commanded) value for the control loop.

`pid.N.feedback` float in
The actual (feedback) value, from some sensor such as an encoder.

`pid.N.error` float out
The difference between command and feedback.

`pid.N.output` float out
The output of the PID loop, which goes to some actuator such as a motor.

`pid.N.enable` bit in
When true, enables the PID calculations. When false, **output** is zero, and all internal integrators, etc, are reset.

`pid.N.index-enable` bit in
On the falling edge of **index-enable**, `pid` does not update the internal command derivative estimate. On systems which use the encoder index pulse, this pin should be connected to the index-enable signal. When this is not done, and FF1 is nonzero, a step change in the input command causes a single-cycle spike in the PID output.

`pid.N.saturated` bit out
When true, the current PID output is saturated. That is,
output = ± **maxoutput**.

`pid.N.saturated-s` float out

`pid.N.saturated-count` s32 out

When true, the output of PID was continually saturated for this many seconds (**saturated-s**) or periods (**saturated-count**).

PARAMETERS

`pid.N.Pgain` float rw
Proportional gain. Results in a contribution to the output that is the error multiplied by **Pgain**.

`pid.N.Igain` float rw
Integral gain. Results in a contribution to the output that is the integral of the error multiplied by **Igain**. For example an error of 0.02 that lasted 10 seconds would result in an integrated error (**errorI**) of 0.2, and if **Igain** is 20, the integral term would add 4.0 to the output.

pid.N.Dgain float rw

Derivative gain. Results in a contribution to the output that is the rate of change (derivative) of the error multiplied by **Dgain**. For example an error that changed from 0.02 to 0.03 over 0.2 seconds would result in an error derivative (**errorD**) of 0.05, and if **Dgain** is 5, the derivative term would add 0.25 to the output.

pid.N.bias float rw

bias is a constant amount that is added to the output. In most cases it should be left at zero. However, it can sometimes be useful to compensate for offsets in servo amplifiers, or to balance the weight of an object that moves vertically. **bias** is turned off when the PID loop is disabled, just like all other components of the output. If a non-zero output is needed even when the PID loop is disabled, it should be added with an external HAL sum2 block.

pid.N.FF0 float rw

Zero order feed-forward term. Produces a contribution to the output that is **FF0** multiplied by the commanded value. For position loops, it should usually be left at zero. For velocity loops, **FF0** can compensate for friction or motor counter-EMF and may permit better tuning if used properly.

pid.N.FF1 float rw

First order feed-forward term. Produces a contribution to the output that **FF1** multiplied by the derivative of the commanded value. For position loops, the contribution is proportional to speed, and can be used to compensate for friction or motor CEMF. For velocity loops, it is proportional to acceleration and can compensate for inertia. In both cases, it can result in better tuning if used properly.

pid.N.FF2 float rw

Second order feed-forward term. Produces a contribution to the output that is **FF2** multiplied by the second derivative of the commanded value. For position loops, the contribution is proportional to acceleration, and can be used to compensate for inertia. For velocity loops, it should usually be left at zero.

pid.N.deadband float rw

Defines a range of "acceptable" error. If the absolute value of **error** is less than **deadband**, it will be treated as if the error is zero. When using feedback devices such as encoders that are inherently quantized, the deadband should be set slightly more than one-half count, to prevent the control loop from hunting back and forth if the command is between two adjacent encoder values. When the absolute value of the error is greater than the deadband, the deadband value is subtracted from the error before performing the loop calculations, to prevent a step in the transfer function at the edge of the deadband. (See **BUGS**.)

pid.N.maxoutput float rw

Output limit. The absolute value of the output will not be permitted to exceed **maxoutput**, unless **maxoutput** is zero. When the output is limited, the error integrator will hold instead of integrating, to prevent windup and overshoot.

pid.N.maxerror float rw

Limit on the internal error variable used for P, I, and D. Can be used to prevent high **Pgain** values from generating large outputs under conditions when the error is large (for example, when the command makes a step change). Not normally needed, but can be useful when tuning non-linear systems.

pid.N.maxerrorD float rw

Limit on the error derivative. The rate of change of error used by the **Dgain** term will be limited to this value, unless the value is zero. Can be used to limit the effect of **Dgain** and prevent large output spikes due to steps on the command and/or feedback. Not normally needed.

pid.N.maxerrorI float rw

Limit on error integrator. The error integrator used by the **Igain** term will be limited to this value, unless it is zero. Can be used to prevent integrator windup and the resulting overshoot during/after sustained errors. Not normally needed.

pid.N.maxcmdD float rw

Limit on command derivative. The command derivative used by **FF1** will be limited to this value, unless the value is zero. Can be used to prevent **FF1** from producing large output spikes if there is a step change on the command. Not normally needed.

pid.N.maxcmdDD float rw

Limit on command second derivative. The command second derivative used by **FF2** will be limited to this value, unless the value is zero. Can be used to prevent **FF2** from producing large output spikes if there is a step change on the command. Not normally needed.

pid.N.errorI float ro (only if debug=1)

Integral of error. This is the value that is multiplied by **Igain** to produce the Integral term of the output.

pid.N.errorD float ro (only if debug=1)

Derivative of error. This is the value that is multiplied by **Dgain** to produce the Derivative term of the output.

pid.N.commandD float ro (only if debug=1)

Derivative of command. This is the value that is multiplied by **FF1** to produce the first order feed-forward term of the output.

pid.N.commandDD float ro (only if debug=1)

Second derivative of command. This is the value that is multiplied by **FF2** to produce the second order feed-forward term of the output.

BUGS

Some people would argue that deadband should be implemented such that error is treated as zero if it is within the deadband, and be unmodified if it is outside the deadband. This was not done because it would cause a step in the transfer function equal to the size of the deadband. People who prefer that behavior are welcome to add a parameter that will change the behavior, or to write their own version of **pid**. However, the default behavior should not be changed.

NAME

pluto_servo – Hardware driver and firmware for the Pluto-P parallel-port FPGA, for use with servo machines.

SYNOPSIS

loadrt pluto_servo [ioaddr=*N*] [ioaddr_hi=*N*] [epp_wide=*N*] [watchdog=*N*] [test_encoder=*N*]

ioaddr [default: 0x378]

The base address of the parallel port.

ioaddr_hi [default: 0]

The secondary address of the parallel port, used to set EPP mode. 0 means to use ioaddr + 0x400. -1 means there is no secondary address. The secondary address is used to set the port to EPP mode.

epp_wide [default: 1]

Set to zero to disable the "wide EPP mode". "Wide" mode allows a 16- and 32-bit EPP transfers, which can reduce the time spent in the read and write functions. However, this may not work on all EPP parallel ports.

watchdog [default: 1]

Set to zero to disable the "hardware watchdog". "Watchdog" will tristate all outputs approximately 6ms after the last execution of **pluto_servo.write**, which adds some protection in the case of emc crashes.

test_encoder [default: 0]

Internally connect dout0..2 to QA0, QB0, QZ0 to test quadrature counting

DESCRIPTION

Pluto_servo is an emc2 software driver and associated firmware that allow the Pluto-P board to be used to control a servo-based CNC machine.

The driver has 4 PWM channels, 4 quadrature channels with index pulse, 18 digital outputs (8 shared with PWM), and 20 digital inputs (12 shared with quadrature).

Encoders

The encoder pins and parameters conform to the 'canonical encoder' interface described in the HAL manual. It operates in 'x4 mode'.

The sample rate of the encoder is 40MHz. The maximum number quadrature rate is 8191 counts per emc2 servo cycle. For correct handling of the index pulse, the number of encoder counts per revolution must be less than 8191.

PWM

The PWM pins and parameters conform to the 'canonical analog output' interface described in the HAL manual. The output pins are 'up/down' or 'pwm/dir' pins as described in the documentation of the 'pwm-gen' component.

Internally the PWM generator is based on a 12-bit, 40MHz counter, giving 4095 duty cycles from -100% to +100% and a frequency of approximately 19.5kHz. In PDM mode, the duty periods are approximately 100ns long.

Digital I/O

The digital output pins conform to the 'canonical digital output' interface described in the HAL manual.

The digital input pins conform to the 'canonical digital input' interface described in the HAL manual.

FUNCTIONS

- pluto-servo.read** (requires a floating-point thread)
Read all the inputs from the pluto-servo board
- pluto-servo.write** (requires a floating-point thread)
Write all the outputs on the pluto-servo board

PINS

- pluto-servo.encoder.M.count** s32 out (M=0..3)
- pluto-servo.encoder.M.position** float out (M=0..3)
- pluto-servo.encoder.M.velocity** float out (M=0..3)
- pluto-servo.encoder.M.reset** bit in (M=0..3)
- pluto-servo.encoder.M.index-enable** bit io (M=0..3)
encoder.M corresponds to the pins labeled QAM, QBM, and QZM on the pinout diagram
- pluto-servo.pwm.M.value** float in (M=0..3)
- pluto-servo.pwm.M.enable** bit in (M=0..3)
pwm.M corresponds to the pins labeled UPM and DNM on the pinout diagram
- pluto-servo.dout.MM** bit in (MM=00..19)
dout.0M corresponds to the pin labeled OUTM on the pinout diagram. Other pins are shared with the PWM function, as follows:

Pin	Shared
Label	with
dout.10	UP0
dout.10	UP0
dout.12	UP1
dout.14	UP2
dout.18	UP3
dout.11	DOWN0
dout.13	DOWN1
dout.15	DOWN2
dout.19	DOWN3

- pluto-servo.din.MM** bit out (MM=00..19)
- pluto-servo.din.MM-not** bit out (MM=00..19)
For M=0 through 7, din.0M corresponds to the pin labeled INM on the pinout diagram. Other pins are shared with the encoder function, as follows:

Pin	Shared
Label	with
din.8	QZ0
din.9	QZ1
din.10	QZ2
din.11	QZ3
din.12	QB0
din.13	QB1
din.14	QB2
din.15	QB3
din.16	QA0

din.17	QA1
din.18	QA2
din.19	QA3

PARAMETERS

pluto-servo.encoder.M.scale float rw (M=0..3) (default: 1)

pluto-servo.encoder.z-polarity bit rw

Set to TRUE if the index pulse is active low, FALSE if it is active high. Affects all encoders.

pluto-servo.pwm.M.offset float rw (M=0..3)

pluto-servo.pwm.M.scale float rw (M=0..3) (default: 1)

pluto-servo.pwm.M.max-dc float rw (M=0..3) (default: 1)

pluto-servo.pwm.M.min-dc float rw (M=0..3) (default: 0)

pluto-servo.pwm.M.pwmdir bit rw (M=0..3) (default: 0)

Set to TRUE use PWM+direction mode. Set to FALSE to use Up/Down mode.

pluto-servo.pwm.is-pdm bit rw

Set to TRUE to use PDM (also called interleaved PWM) mode. Set to FALSE to use traditional PWM mode. Affects all PWM outputs.

pluto-servo.dout.MM-invert bit rw (MM=00..19)

If TRUE, the output on the corresponding **dout.MM** is inverted.

pluto-servo.communication-error u32 rw

Incremented each time `pluto-servo.read` detects an error code in the EPP status register. While this register is nonzero, new values are not being written to the Pluto-P board, and the status of digital outputs and the PWM duty cycle of the PWM outputs will remain unchanged. If the watchdog is enabled, it will activate soon after the communication error is detected. To continue after a communication error, set this parameter back to zero.

pluto-servo.debug-0 s32 rw

pluto-servo.debug-1 s32 rw

These parameters can display values which are useful to developers or for debugging the driver and firmware. They are not useful for integrators or users.

SEE ALSO

The `pluto_servo` section in the HAL User Manual, which shows the location of each physical pin on the pluto board.

LICENSE

GPL

NAME

pluto_step – Hardware driver and firmware for the Pluto-P parallel-port FPGA, for use with stepper machines.

SYNOPSIS

```
loadrt pluto_step ioaddr=addr ioaddr_hi=addr epp_wide=[0/1]
```

ioaddr [default: 0x378]

The base address of the parallel port.

ioaddr_hi [default: 0]

The secondary address of the parallel port, used to set EPP mode. 0 means to use ioaddr + 0x400. -1 means there is no secondary address.

epp_wide [default: 1]

Set to zero to disable "wide EPP mode". "Wide" mode allows 16- and 32-bit EPP transfers, which can reduce the time spent in the read and write functions. However, this mode may not work on all EPP parallel ports.

watchdog [default: 1]

Set to zero to disable the "hardware watchdog". "Watchdog" will tristate all outputs approximately 6ms after the last execution of **pluto_step.write**, which adds some protection in the case of emc crashes.

speedrange [default: 0]

Selects one of four speed ranges:

- 0: Top speed 312.5kHz; minimum speed 610Hz
- 1: Top speed 156.25kHz; minimum speed 305Hz
- 2: Top speed 78.125kHz; minimum speed 153Hz
- 3: Top speed 39.06kHz; minimum speed 76Hz

Choosing the smallest maximum speed that is above the maximum for any one axis may give improved step regularity at low step speeds.

DESCRIPTION

Pluto_step is an emc2 software driver and associated firmware that allow the Pluto-P board to be used to control a stepper-based CNC machine.

The driver has 4 step+direction channels, 14 dedicated digital outputs, and 16 dedicated digital inputs.

Step generators

The step generator takes a position input and output.

The step waveform includes step length/space and direction hold/setup time. Step length and direction setup/hold time is enforced in the FPGA. Step space is enforced by a velocity cap in the driver.

(all the following numbers are subject to change) In *speedrange=0*, the maximum step rate is 312.5kHz. For position feedback to be accurate, the maximum step rate is 512 pulses per servo cycle (so a 1kHz servo cycle does not impose any additional limitation). The maximum step rate may be lowered by the step length and space parameters, which are rounded up to the nearest multiple of 1600ns.

In successive speedranges the maximum step rate is divided in half, as is the maximum steps per servo cycle, and the minimum nonzero step rate.

Digital I/O

The digital output pins conform to the ‘canonical digital output’ interface described in the HAL manual.

The digital input pins conform to the ‘canonical digital input’ interface described in the HAL manual.

FUNCTIONS

pluto-step.read (requires a floating-point thread)

Read all the inputs from the pluto-step board

pluto-step.write (requires a floating-point thread)

Write all the outputs on the pluto-step board

PINS

pluto-step.stepgen.M.position-cmd float in (M=0..3)

pluto-step.stepgen.M.velocity-fb float out (M=0..3)

pluto-step.stepgen.M.position-fb float out (M=0..3)

pluto-step.stepgen.M.counts s32 out (M=0..3)

pluto-step.stepgen.M.enable bit in (M=0..3)

pluto-step.stepgen.M.reset bit in (M=0..3)

When TRUE, reset position-fb to 0

pluto-step.dout.MM bit in (MM=00..13)

dout.MM corresponds to the pin labeled OUTM on the pinout diagram.

pluto-step.din.MM bit out (MM=00..15)

pluto-step.din.MM-not bit out (MM=00..15)

din.MM corresponds to the pin labeled INM on the pinout diagram.

PARAMETERS

pluto-step.stepgen.M.scale float rw (M=0..3) (default: 1.0)

pluto-step.stepgen.M.maxvel float rw (M=0..3) (default: 0)

pluto-step.stepgen.step-polarity bit rw

pluto-step.stepgen.steplen u32 rw

Step length in ns.

pluto-step.stepgen.stepspace u32 rw

Step space in ns

pluto-step.stepgen.dirtime u32 rw

Dir hold/setup in ns. Refer to the pdf documentation for a diagram of what these timings mean.

pluto-step.dout.MM-invert bit rw (MM=00..13)

If TRUE, the output on the corresponding **dout.MM** is inverted.

pluto-step.communication-error u32 rw

Incremented each time pluto-step.read detects an error code in the EPP status register. While this register is nonzero, new values are not being written to the Pluto-P board, and the status of digital outputs and the PWM duty cycle of the PWM outputs will remain unchanged. If the hardware watchdog is enabled, it will activate shortly after the communication error is detected by emc. To continue after a communication error, set this parameter back to zero.

pluto-step.debug-0 s32 rw

pluto-step.debug-1 s32 rw

pluto-step.debug-2 float rw (default: .5)

pluto-step.debug-3 float rw (default: 2.0)

Registers that hold debugging information of interest to developers

SEE ALSO

The *pluto_step* section in the HAL User Manual, which shows the location of each physical pin on the pluto board.

LICENSE
GPL

NAME

`pwmgen` – software PWM/PDM generation

SYNOPSIS

```
loadrt pwmgen output_type=type0[,type1...]
```

DESCRIPTION

pwmgen is used to generate PWM (pulse width modulation) or PDM (pulse density modulation) signals. The maximum PWM frequency and the resolution is quite limited compared to hardware-based approaches, but in many cases software PWM can be very useful. If better performance is needed, a hardware PWM generator is a better choice.

pwmgen supports a maximum of eight channels. The number of channels actually loaded depends on the number of *type* values given. The value of each *type* determines the outputs for that channel.

type 0: single output

A single output pin, **pwm**, whose duty cycle is determined by the input value for positive inputs, and which is off (or at **min-dc**) for negative inputs. Suitable for single ended circuits.

type 1: pwm/direction

Two output pins, **pwm** and **dir**. The duty cycle on **pwm** varies as a function of the input value. **dir** is low for positive inputs and high for negative inputs.

type 2: up/down

Two output pins, **up** and **down**. For positive inputs, the PWM/PDM waveform appears on **up**, while **down** is low. For negative inputs, the waveform appears on **down**, while **up** is low. Suitable for driving the two sides of an H-bridge to generate a bipolar output.

FUNCTIONS

pwmgen.make-pulses (no floating-point)

Generates the actual PWM waveforms, using information computed by **update**. Must be called as frequently as possible, to maximize the attainable PWM frequency and resolution, and minimize jitter. Operates on all channels at once.

pwmgen.update (uses floating point)

Accepts an input value, performs scaling and limit checks, and converts it into a form usable by **make-pulses** for PWM/PDM generation. Can (and should) be called less frequently than **make-pulses**. Operates on all channels at once.

PINS

pwmgen.N.enable bit in

Enables PWM generator *N* - when false, all **pwmgen.N** output pins are low.

pwmgen.N.value float in

Commanded value. When **value** = 0.0, duty cycle is 0%, and when **value** = +/-**scale**, duty cycle is +/- 100%. (Subject to **min-dc** and **max-dc** limitations.)

pwmgen.N.pwm bit out (output types 0 and 1 only)

PWM/PDM waveform.

pwmgen.N.dir bit out (output type 1 only)

Direction output: low for forward, high for reverse.

pwmgen.N.up bit out (output type 2 only)

PWM/PDM waveform for positive input values, low for negative inputs.

pwmgen.N.down bit out (output type 2 only)

PWM/PDM waveform for negative input values, low for positive inputs.

PARAMETERS

pwmgen.N.curr-dc float ro

The current duty cycle, after all scaling and limits have been applied. Range is from -1.0 to +1.0.

pwmgen.N.max-dc float rw

The maximum duty cycle. A value of 1.0 corresponds to 100%. This can be useful when using transistor drivers with bootstrapped power supplies, since the supply requires some low time to recharge.

pwmgen.N.min-dc float rw

The minimum duty cycle. A value of 1.0 corresponds to 100%. Note that when the pwm generator is disabled, the outputs are constantly low, regardless of the setting of **min-dc**.

pwmgen.N.scale float rw

pwmgen.N.offset float rw

These parameters provide a scale and offset from the **value** pin to the actual duty cycle. The duty cycle is calculated according to $dc = (value/scale) + offset$, with 1.0 meaning 100%.

pwmgen.N.pwm-freq float rw

PWM frequency in Hz. The upper limit is half of the frequency at which **make-pulses** is invoked, and values above that limit will be changed to the limit. If **dither-pwm** is false, the value will be changed to the nearest integer submultiple of the **make-pulses** frequency. A value of zero produces Pulse Density Modulation instead of Pulse Width Modulation.

pwmgen.N.dither-pwm bit rw

Because software-generated PWM uses a fairly slow timebase (several to many microseconds), it has limited resolution. For example, if **make-pulses** is called at a 20KHz rate, and **pwm-freq** is 2KHz, there are only 10 possible duty cycles. If **dither-pwm** is false, the commanded duty cycle will be rounded to the nearest of those values. Assuming **value** remains constant, the same output will repeat every PWM cycle. If **dither-pwm** is true, the output duty cycle will be dithered between the two closest values, so that the long-term average is closer to the desired level. **dither-pwm** has no effect if **pwm-freq** is zero (PDM mode), since PDM is an inherently dithered process.

NAME

sample_hold – Sample and Hold

SYNOPSIS

loadrt sample_hold [count=*N*names=*name1*[,*name2*...]]

FUNCTIONS

sample_hold.*N*

PINS

sample_hold.*N*.in s32 in

sample_hold.*N*.hold bit in

sample_hold.*N*.out s32 out

LICENSE

GPL

NAME

sampler – sample data from HAL in real time

SYNOPSIS

loadrt sampler depth=depth1[,depth2...] cfg=string1[,string2...]

DESCRIPTION

sampler and **halsampler**(1) are used together to sample HAL data in real time and store it in a file. **sampler** is a realtime HAL component that exports HAL pins and creates a FIFO in shared memory. It then begins sampling data from the HAL and storing it to the FIFO. **halsampler** is a user space program that copies data from the FIFO to stdout, where it can be redirected to a file or piped to some other program.

OPTIONS

depth=depth1[,depth2...]

sets the depth of the realtime->user FIFO that **sampler** creates to buffer the realtime data. Multiple values of *depth* (separated by commas) can be specified if you need more than one FIFO (for example if you want to sample data from two different realtime threads).

cfg=string1[,string2...]

defines the set of HAL pins that **sampler** exports and later samples data from. One *string* must be supplied for each FIFO, separated by commas. **sampler** exports one pin for each character in *string*. Legal characters are:

F, f (float pin)

B, b (bit pin)

S, s (s32 pin)

U, u (u32 pin)

FUNCTIONS

sampler.N

One function is created per FIFO, numbered from zero.

PINS

sampler.N.pin.M input

Pin for the data that will wind up in column *M* of FIFO *N* (and in column *M* of the output file). The pin type depends on the config string.

sampler.N.curr-depth s32 output

Current number of samples in the FIFO. When this reaches *depth* new data will begin overwriting old data, and some samples will be lost.

sampler.N.full bit output

TRUE when the FIFO *N* is full, FALSE when there is room for another sample.

sampler.N.enable bit input

When TRUE, samples are captured and placed in FIFO *N*, when FALSE, no samples are acquired. Defaults to TRUE.

PARAMETERS

sampler.N.overruns s32 read/write

The number of times that **sampler** has tried to write data to the HAL pins but found no room in the FIFO. It increments whenever **full** is true, and can be reset by the **setp** command.

sampler.N.sample-num s32 read/write

A number that identifies the sample. It is automatically incremented for each sample, and can be reset using the **setp** command. The sample number can optionally be printed in the first column of the output from **halsampler**, using the **-t** option. (see **man 1 halsampler**)

SEE ALSO

halsampler(1) **streamer(9)** **halstreamer(1)**

HISTORY

BUGS

Should an **enable** HAL pin be added, to allow sampling to be turned on and off?

AUTHOR

Original version by John Kasunich, as part of the Enhanced Machine Controller (EMC) project. Improvements by several other members of the EMC development team.

REPORTING BUGS

Report bugs to [jmkasunich AT users DOT sourceforge DOT net](mailto:jmkasunich@users.sourceforge.net)

COPYRIGHT

Copyright © 2006 John Kasunich.

This is free software; see the source for copying conditions. There is NO warranty; not even for MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE.

NAME

scale – EMC2 HAL component that applies a scale and offset to its input

SYNOPSIS

loadrt scale [**count**=*N*][**names**=*name1*[,*name2*...]]

FUNCTIONS

scale.N (requires a floating-point thread)

PINS

scale.N.in float in

scale.N.gain float in

scale.N.offset float in

scale.N.out float out

out = in * gain + offset

LICENSE

GPL

NAME

select8 – 8-bit binary match detector

SYNOPSIS

loadrt select8 [count=*N*|names=*name1*[,*name2*...]]

FUNCTIONS

select8.*N*

PINS

select8.*N*.sel s32 in

The number of the output to set TRUE. All other outputs will be set FALSE

select8.*N*.out M bit out ($M=0..7$)

Output bits. If enable is set and the sel input is between 0 and 7, then the corresponding output bit will be set true

PARAMETERS

select8.*N*.enable bit rw (default: *TRUE*)

Set enable to FALSE to cause all outputs to be set FALSE

LICENSE

GPL

NAME

serport – Hardware driver for the digital I/O bits of the 8250 and 16550 serial port.

SYNOPSIS

loadrt serport io=addr[,addr...]

The pin numbers refer to the 9-pin serial pinout. Keep in mind that these ports generally use rs232 voltages, not 0/5V signals.

Specify the I/O address of the serial ports using the module parameter **io=addr[,addr...]**. These ports must not be in use by the kernel. To free up the I/O ports after bootup, install setserial and execute a command like:

```
sudo setserial /dev/ttyS0 uart none
```

but it is best to ensure that the serial port is never used or configured by the Linux kernel by setting a kernel commandline parameter or not loading the serial kernel module if it is a modularized driver.

FUNCTIONS

serport.N.read

serport.N.write

PINS

serport.N.pin-1-in bit out

Also called DCD (data carrier detect); pin 8 on the 25-pin serial pinout

serport.N.pin-6-in bit out

Also called DSR (data set ready); pin 6 on the 25-pin serial pinout

serport.N.pin-8-in bit out

Also called CTS (clear to send); pin 5 on the 25-pin serial pinout

serport.N.pin-9-in bit out

Also called RI (ring indicator); pin 22 on the 25-pin serial pinout

serport.N.pin-1-in-not bit out

Inverted version of pin-1-in

serport.N.pin-6-in-not bit out

Inverted version of pin-6-in

serport.N.pin-8-in-not bit out

Inverted version of pin-8-in

serport.N.pin-9-in-not bit out

Inverted version of pin-9-in

serport.N.pin-3-out bit in

Also called TX (transmit data); pin 2 on the 25-pin serial pinout

serport.N.pin-4-out bit in

Also called DTR (data terminal ready); pin 20 on the 25-pin serial pinout

serport.N.pin-7-out bit in

Also called RTS (request to send); pin 4 on the 25-pin serial pinout

PARAMETERS

serport.N.pin-3-out-invert bit rw

serport.N.pin-4-out-invert bit rw

serport.N.pin-7-out-invert bit rw

serport.N.ioaddr u32 r

LICENSE

GPL

NAME

siggen – signal generator

SYNOPSIS

loadrt siggen num_chan=num

DESCRIPTION

siggen is a signal generator that can be used for testing and other applications that need simple waveforms. It produces sine, cosine, triangle, sawtooth, and square waves of variable frequency, amplitude, and offset, which can be used as inputs to other HAL components.

siggen supports a maximum of sixteen channels. The number of channels actually loaded is set by the **num_chan** argument when the module is loaded. If **numchan** is not specified, the default value is one.

FUNCTIONS

siggen.N.update (uses floating-point)

Updates output pins for signal generator *N*. Each time it is called it calculates a new sample. It should be called many times faster than the desired signal frequency, to avoid distortion and aliasing.

PINS

siggen.N.frequency float in

The output frequency for signal generator *N*, in Hertz. The default value is 1.0 Hertz.

siggen.N.amplitude float in

The output amplitude for signal generator *N*. If **offset** is zero, the outputs will swing from **-amplitude** to **+amplitude**. The default value is 1.00.

siggen.N.offset float in

The output offset for signal generator *N*. This value is added directly to the output signal. The default value is zero.

siggen.N.square float out

The square wave output. Positive while **triangle** and **cosine** are ramping upwards, and while **sine** is negative.

siggen.N.sine float out

The sine output. Lags **cosine** by 90 degrees.

siggen.N.cosine float out

The cosine output. Leads **sine** by 90 degrees.

siggen.N.triangle float out

The triangle wave output. Ramps up while **square** is positive, and down while **square** is negative. Reaches its positive and negative peaks at the same time as **cosine**.

siggen.N.sawtooth float out

The sawtooth output. Ramps upwards to its positive peak, then instantly drops to its negative peak and starts ramping again. The drop occurs when **triangle** and **cosine** are at their positive peaks, and coincides with the falling edge of **square**.

PARAMETERS

None

NAME

`sim_encoder` – simulated quadrature encoder

SYNOPSIS

`loadrt sim_encoder num_chan=num`

DESCRIPTION

sim_encoder can generate quadrature signals as if from an encoder. It also generates an index pulse once per revolution. It is mostly used for testing and simulation, to replace hardware that may not be available. It has a limited maximum frequency, as do all software based pulse generators.

sim_encoder supports a maximum of eight channels. The number of channels actually loaded is set by the **num_chan** argument when the module is loaded. If **numchan** is not specified, the default value is one.

FUNCTIONS

sim-encoder.make-pulses (no floating-point)

Generates the actual quadrature and index pulses. Must be called as frequently as possible, to maximize the count rate and minimize jitter. Operates on all channels at once.

sim-encoder.update-speed (uses floating-point)

Reads the **speed** command and other parameters and converts the data into a form that can be used by **make-pulses**. Changes take effect only when **update-speed** runs. Can (and should) be called less frequently than **make-pulses**. Operates on all channels at once.

PINS

sim-encoder.N.phase-A bit out

One of the quadrature outputs.

sim-encoder.N.phase-B bit out

The other quadrature output.

sim-encoder.N.phase-Z bit out

The index pulse.

sim-encoder.N.speed float in

The desired speed of the encoder, in user units per per second. This is divided by **scale**, and the result is used as the encoder speed in revolutions per second.

PARAMETERS

sim-encoder.N.ppr u32 rw

The pulses per revolution of the simulated encoder. Note that this is pulses, not counts, per revolution. Each pulse or cycle from the encoder results in four counts, because every edge is counted. Default value is 100 ppr, or 400 counts per revolution.

sim-encoder.N.scale float rw

Scale factor for the **speed** input. The **speed** value is divided by **scale** to get the actual encoder speed in revolutions per second. For example, if **scale** is set to 60, then **speed** is in revolutions per minute (RPM) instead of revolutions per second. The default value is 1.00.

NAME

sphereprobe – Probe a pretend hemisphere

SYNOPSIS

loadrt sphereprobe [count=*N* | names=*name1* [, *name2* ...]]

FUNCTIONS

sphereprobe.*N*

update probe-out based on inputs

PINS

sphereprobe.*N.px* s32 in

sphereprobe.*N.py* s32 in

sphereprobe.*N.pz* s32 in

rawcounts position from software encoder

sphereprobe.*N.cx* s32 in

sphereprobe.*N.cy* s32 in

sphereprobe.*N.cz* s32 in

Center of sphere in counts

sphereprobe.*N.r* s32 in

Radius of hemisphere in counts

sphereprobe.*N.probe-out* bit out

AUTHOR

Jeff Epler

LICENSE

GPL

NAME

stepgen – software step pulse generation

SYNOPSIS

```
loadrt stepgen step_type=type0[,type1...] [ctrl_type=type0[,type1...]]
```

DESCRIPTION

stepgen is used to control stepper motors. The maximum step rate depends on the CPU and other factors, and is usually in the range of 5KHz to 25KHz. If higher rates are needed, a hardware step generator is a better choice.

stepgen has two control modes, which can be selected on a channel by channel basis using **ctrl_type**. Possible values are "p" for position control, and "v" for velocity control. The default is position control, which drives the motor to a commanded position, subject to acceleration and velocity limits. Velocity control drives the motor at a commanded speed, again subject to accel and velocity limits. Usually, position mode is used for machine axes. Velocity mode is reserved for unusual applications where continuous movement at some speed is desired, instead of movement to a specific position. (Note that velocity mode replaces the former component **freqgen**.)

stepgen can control a maximum of eight motors. The number of motors/channels actually loaded depends on the number of *type* values given. The value of each *type* determines the outputs for that channel. Position or velocity mode can be individually selected for each channel. Both control modes support the same 15 possible step types.

By far the most common step type is '0', standard step and direction. Others include up/down, quadrature, and a wide variety of three, four, and five phase patterns that can be used to directly control some types of motor windings. (When used with appropriate buffers of course.)

Some of the stepping types are described below, but for more details (including timing diagrams) see the **stepgen** section of the HAL reference manual.

type 0: step/dir

Two pins, one for step and one for direction. **make-pulses** must run at least twice for each step (once to set the step pin true, once to clear it). This limits the maximum step rate to half (or less) of the rate that can be reached by types 2-14. The parameters **steplen** and **stepspace** can further lower the maximum step rate. Parameters **dirsetup** and **dirhold** also apply to this step type.

type 1: up/down

Two pins, one for 'step up' and one for 'step down'. Like type 0, **make-pulses** must run twice per step, which limits the maximum speed.

type 2: quadrature

Two pins, phase-A and phase-B. For forward motion, A leads B. Can advance by one step every time **make-pulses** runs.

type 3: three phase, full step

Three pins, phase-A, phase-B, and phase-C. Three steps per full cycle, then repeats. Only one phase is high at a time - for forward motion the pattern is A, then B, then C, then A again.

type 4: three phase, half step

Three pins, phases A through C. Six steps per full cycle. First A is high alone, then A and B together, then B alone, then B and C together, etc.

types 5 through 8: four phase, full step

Four pins, phases A through D. Four steps per full cycle. Types 5 and 6 are suitable for use with unipolar steppers, where power is applied to the center tap of each winding, and four open-collector transistors drive the ends. Types 7 and 8 are suitable for bipolar steppers, driven by two H-bridges.

types 9 and 10: four phase, half step

Four pins, phases A through D. Eight steps per full cycle. Type 9 is suitable for unipolar drive, and type 10 for bipolar drive.

types 11 and 12: five phase, full step

Five pins, phases A through E. Five steps per full cycle. See HAL reference manual for the patterns.

types 13 and 14: five phase, half step

Five pins, phases A through E. Ten steps per full cycle. See HAL reference manual for the patterns.

FUNCTIONS

stepgen.make-pulses (no floating-point)

Generates the step pulses, using information computed by **update-freq**. Must be called as frequently as possible, to maximize the attainable step rate and minimize jitter. Operates on all channels at once.

stepgen.capture-position (uses floating point)

Captures position feedback value from the high speed code and makes it available on a pin for use elsewhere in the system. Operates on all channels at once.

stepgen.update-freq (uses floating point)

Accepts a velocity or position command and converts it into a form usable by **make-pulses** for step generation. Operates on all channels at once.

PINS

stepgen.N.counts s32 out

The current position, in counts, for channel *N*. Updated by **capture-position**.

stepgen.N.position-fb float out

The current position, in length units (see parameter **position-scale**). Updated by **capture-position**. The resolution of **position-fb** is much finer than a single step. If you need to see individual steps, use **counts**.

stepgen.N.enable bit in

Enables output steps - when false, no steps are generated.

stepgen.N.velocity-cmd float in (velocity mode only)

Commanded velocity, in length units per second (see parameter **position-scale**).

stepgen.N.position-cmd float in (position mode only)

Commanded position, in length units (see parameter **position-scale**).

stepgen.N.step bit out (step type 0 only)

Step pulse output.

stepgen.N.dir bit out (step type 0 only)

Direction output: low for forward, high for reverse.

stepgen.N.up bit out (step type 1 only)

Count up output, pulses for forward steps.

stepgen.N.down bit out (step type 1 only)

Count down output, pulses for reverse steps.

stepgen.N.phase-A thru **phase-E** bit out (step types 2-14 only)

Output bits. **phase-A** and **phase-B** are present for step types 2-14, **phase-C** for types 3-14, **phase-D** for types 5-14, and **phase-E** for types 11-14. Behavior depends on selected stepping type.

PARAMETERS

stepgen.N.frequency float ro

The current step rate, in steps per second, for channel *N*.

stepgen.N.maxaccel float rw

The acceleration/deceleration limit, in length units per second squared.

stepgen.N.maxvel float rw

The maximum allowable velocity, in length units per second. If the requested maximum velocity cannot be reached with the current combination of scaling and **make-pulses** thread period, it will be reset to the highest attainable value.

stepgen.N.position-scale float rw

The scaling for position feedback, position command, and velocity command, in steps per length unit.

stepgen.N.rawcounts s32 ro

The position in counts, as updated by **make-pulses**. (Note: this is updated more frequently than the **counts** pin.)

stepgen.N.steplen u32 rw

The length of the step pulses, in nanoseconds. Measured from rising edge to falling edge.

stepgen.N.stepspace u32 rw (step types 0 and 1 only) The minimum

space between step pulses, in nanoseconds. Measured from falling edge to rising edge. The actual time depends on the step rate and can be much longer. If **stepspace** is 0, then **step** can be asserted every period. This can be used in conjunction with **hal_parpport**'s auto-resetting pins to output one step pulse per period. In this mode, **steplen** must be set for one period or less.

stepgen.N.dirsetup u32 rw (step type 0 only)

The minimum setup time from direction to step, in nanoseconds periods. Measured from change of direction to rising edge of step.

stepgen.N.dirhold u32 rw (step type 0 only)

The minimum hold time of direction after step, in nanoseconds. Measured from falling edge of step to change of direction.

stepgen.N.dirdelay u32 rw (step types 1 and higher only)

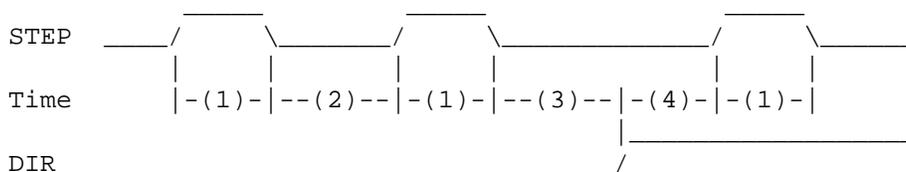
The minimum time between a forward step and a reverse step, in nanoseconds.

TIMING

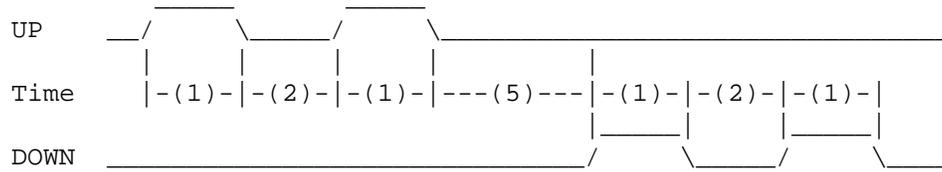
There are five timing parameters which control the output waveform. No step type uses all five, and only those which will be used are exported to HAL. The values of these parameters are in nano-seconds, so no recalculation is needed when changing thread periods. In the timing diagrams that follow, they are identified by the following numbers:

- (1) **stepgen.n.steplen**
- (2) **stepgen.n.stepspace**
- (3) **stepgen.n.dirhold**
- (4) **stepgen.n.dirsetup**
- (5) **stepgen.n.dirdelay**

For step type 0, timing parameters 1 thru 4 are used. The following timing diagram shows the output waveforms, and what each parameter adjusts.



For step type 1, timing parameters 1, 2, and 5 are used. The following timing diagram shows the output waveforms, and what each parameter adjusts.



For step types 2 and higher, the exact pattern of the outputs depends on the step type (see the HAL manual for a full listing). The outputs change from one state to another at a minimum interval of **steplen**. When a direction change occurs, the minimum time between the last step in one direction and the first in the other direction is the sum of **steplen** and **dirdelay**.

SEE ALSO

The HAL User Manual.

NAME

steptest – Used by Stepconf to allow testing of acceleration and velocity values for an axis.

SYNOPSIS

loadrt steptest [count=N|names=name1[,name2...]]

FUNCTIONS

steptest.N (requires a floating-point thread)

PINS

steptest.N.jog-minus bit in

Drive TRUE to jog the axis in its minus direction

steptest.N.jog-plus bit in

Drive TRUE to jog the axis in its positive direction

steptest.N.run bit in

Drive TRUE to run the axis near its current position_fb with a trapezoidal velocity profile

steptest.N.maxvel float in

Maximum velocity

steptest.N.maxaccel float in

Permitted Acceleration

steptest.N.amplitude float in

Approximate amplitude of positions to command during 'run'

steptest.N.dir s32 in

Direction from central point to test: 0 = both, 1 = positive, 2 = negative

steptest.N.position-cmd float out

steptest.N.position-fb float in

steptest.N.running bit out

steptest.N.run-target float out

steptest.N.run-start float out

steptest.N.run-low float out

steptest.N.run-high float out

steptest.N.pause s32 in (default: 0)

pause time for each end of run in seconds

PARAMETERS

steptest.N.epsilon float rw (default: .001)

steptest.N.elapsed float r

Current value of the internal timer

LICENSE

GPL

NAME

streamer – stream file data into HAL in real time

SYNOPSIS

loadrt streamer depth=depth1[,depth2...] cfg=string1[,string2...]

DESCRIPTION

streamer and **halstreamer**(1) are used together to stream data from a file into the HAL in real time. **streamer** is a realtime HAL component that exports HAL pins and creates a FIFO in shared memory. **hal_streamer** is a user space program that copies data from stdin into the FIFO, so that **streamer** can write it to the HAL pins.

OPTIONS

depth=depth1[,depth2...]

sets the depth of the user->realtime FIFO that **streamer** creates to receive data from **halstreamer**. Multiple values of *depth* (separated by commas) can be specified if you need more than one FIFO (for example if you want to stream data from two different realtime threads).

cfg=string1[,string2...]

defines the set of HAL pins that **streamer** exports and later writes data to. One *string* must be supplied for each FIFO, separated by commas. **streamer** exports one pin for each character in *string*. Legal characters are:

F, f (float pin)

B, b (bit pin)

S, s (s32 pin)

U, u (u32 pin)

FUNCTIONS

streamer.N

One function is created per FIFO, numbered from zero.

PINS

streamer.N.pin.M output

Data from column *M* of the data in FIFO *N* appears on this pin. The pin type depends on the config string.

streamer.N.curr-depth s32 output

Current number of samples in the FIFO. When this reaches zero, new data will no longer be written to the pins.

streamer.N.empty bit output

TRUE when the FIFO *N* is empty, FALSE when valid data is available.

streamer.N.enable bit input

When TRUE, data from FIFO *N* is written to the HAL pins. When false, no data is transferred. Defaults to TRUE.

streamer.N.underruns s32 read/write

The number of times that **sampler** has tried to write data to the HAL pins but found no fresh data in the FIFO. It increments whenever **empty** is true, and can be reset by the **setp** command.

SEE ALSO

halstreamer(1) **sampler**(9) **halsampler**(1)

HISTORY**BUGS**

Should an **enable** HAL pin be added, to allow streaming to be turned on and off?

AUTHOR

Original version by John Kasunich, as part of the Enhanced Machine Controller (EMC) project.
Improvements by several other members of the EMC development team.

REPORTING BUGS

Report bugs to [jmkasunich AT users DOT sourceforge DOT net](mailto:jmkasunich@users.sourceforge.net)

COPYRIGHT

Copyright © 2006 John Kasunich.

This is free software; see the source for copying conditions. There is NO warranty; not even for MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE.

NAME

sum2 – Sum of two inputs (each with a gain) and an offset

SYNOPSIS

loadrt sum2 [**count**=*N*]**names=***name1*[,*name2*...]

FUNCTIONS

sum2.N (requires a floating-point thread)

PINS

sum2.N.in0 float in

sum2.N.in1 float in

sum2.N.out float out

$out = in0 * gain0 + in1 * gain1 + offset$

PARAMETERS

sum2.N.gain0 float rw (default: *1.0*)

sum2.N.gain1 float rw (default: *1.0*)

sum2.N.offset float rw

LICENSE

GPL

NAME

supply – set output pins with values from parameters (obsolete)

SYNOPSIS

loadrt supply num_chan=*num*

DESCRIPTION

supply was used to allow the inputs of other HAL components to be manipulated for testing purposes. When it was written, the only way to set the value of an input pin was to connect it to a signal and connect that signal to an output pin of some other component, and then let that component write the pin value. **supply** was written to be that "other component". It reads values from parameters (set with the HAL command **setp**) and writes them to output pins.

Since **supply** was written, the **setp** command has been modified to allow it to set unconnected pins as well as parameters. In addition, the **sets** command was added, which can directly set HAL signals, as long as there are no output pins connected to them. Therefore, **supply** is obsolete.

supply supports a maximum of eight channels. The number of channels actually loaded is set by the **num_chan** argument when the module is loaded. If **numchan** is not specified, the default value is one.

FUNCTIONS

supply.N.update (uses floating-point)
Updates output pins for channel *N*.

PINS

supply.N.q bit out
Output bit, copied from parameter **supply.N.d**.

supply.N._q bit out
Output bit, inverted copy of parameter **supply.N.d**.

supply.N.variable float out
Analog output, copied from parameter **supply.N.value**.

supply.N._variable float out
Analog output, equal to -1.0 times parameter **supply.N.value**.

supply.N.d bit rw
Data source for **q** and **_q** output pins.

supply.N.value bit rw
Data source for **variable** and **_variable** output pins.

NAME

thc – Torch Height Control

SYNOPSIS

loadrt thc

DESCRIPTION

Torch Height Control Mesa THC > Mesa 5i20 Encoder > EMC THC The Mesa THC sends a frequency based on the voltage detected to the encoder. The velocity from the encoder is converted to volts with the velocity scale parameter. The THCAD card sends a frequency at 0 volts so the scale offset parameter is used to correct this.

Component Functions If enabled and torch is on and X + Y velocity is within tolerance of set speed allow the THC to offset the Z axis as needed to maintain voltage.

If enabled and torch is off and the Z axis is moving up remove any correction at a rate not to exceed the rate of movement of the Z axis.

If enabled and torch is off and there is no correction pass the Z position and feed back untouched.

If not enabled pass the Z position and feed back untouched.

Physical Connections Plasma Torch Arc Voltage Signal => 6 x 487k 1% resistors => THC Arc Voltage In
THC Frequency Signal => Encoder #0, pin A (Input) Plasma Torch Arc OK Signal => parport.0.pin-15-in
parport.0.pin-16-out => Plasma Torch Start Arc Contacts

HAL Plasma Connections hm2_5i20.0.encoder.00.velocity => thc.encoder-vel (tip voltage) motion.spindle-on => parport.0.pin-16-out (start the arc) thc.arc-ok <= motion.digital-in-00 <= parport.0.pin-15-in (arc ok signal)

HAL Motion Connections thc.requested-vel <= motion.requested-vel thc.current-vel <= motion.current-vel

FUNCTIONS

thc (requires a floating-point thread)

PINS

thc.encoder-vel float in
Connect to hm2_5i20.0.encoder.00.velocity

thc.current-vel float in
Connect to motion.current-vel

thc.requested-vel float in
Connect to motion.requested-vel

thc.volts-requested float in
Tip Volts current_vel >= min_velocityrequested (SP)

thc.vel-tol float in
Velocity Tolerance (Corner Lock)

thc.torch-on bit in
Connect to motion.spindle-on

thc.arc-ok bit in
Arc OK from Plasma Torch

- thc.enable** bit in
Enable the THC, if not enabled Z position is passed through
- thc.z-pos-in** float in
Z Motor Position Command in from axis.n.motor-pos-cmd
- thc.z-pos-out** float out
Z Motor Position Command Out
- thc.z-fb-out** float out
Z Position Feedback to Axis
- thc.volts** float out
The Calculated Volts
- thc.vel-status** bit out
When the THC thinks we are at requested speed

PARAMETERS

- thc.vel-scale** float rw
The scale to convert the Velocity signal to Volts
- thc.scale-offset** float rw
The offset of the velocity input at 0 volts
- thc.velocity-tol** float rw
The deviation percent from planned velocity
- thc.voltage-tol** float rw
The deviation of Tip Voltage before correction takes place
- thc.correction-vel** float rw
The amount of change in user units per period to move Z to correct

AUTHOR

John Thornton

LICENSE

GPLv2 or greater

NAME

threads – creates hard realtime HAL threads

SYNOPSIS

```
loadrt threads name1=name period1=period [fp1=<0|1>] [<thread-2-info>] [<thread-3-info>]
```

DESCRIPTION

threads is used to create hard realtime threads which can execute HAL functions at specific intervals. It is not a true HAL component, in that it does not export any functions, pins, or parameters of its own. Once it has created one or more threads, the threads stand alone, and the **threads** component can be unloaded without affecting them. In fact, it can be unloaded and then reloaded to create additional threads, as many times as needed.

threads can create up to three realtime threads. Threads must be created in order, from fastest to slowest. Each thread is specified by three arguments. **name1** is used to specify the name of the first thread (thread 1). **period1** is used to specify the period of thread 1 in nanoseconds. Both *name* and *period* are required. The third argument, **fp1** is optional, and is used to specify if thread 1 will be used to execute floating point code. If not specified, it defaults to **1**, which means that the thread will support floating point. Specify **0** to disable floating point support, which saves a small amount of execution time by not saving the FPU context. For additional threads, **name2**, **period2**, **fp2**, **name3**, **period3**, and **fp3** work exactly the same. If more than three threads are needed, unload threads, then reload it to create more threads.

FUNCTIONS

None

PINS

None

PARAMETERS

None

BUGS

The existence of **threads** might be considered a bug. Ideally, creation and deletion of threads would be done directly with **halcmd** commands, such as "**newthread name period**", "**delthread name**", or similar. However, limitations in the current HAL implementation require thread creation to take place in kernel space, and loading a component is the most straightforward way to do that.

NAME

threadtest – EMC2 HAL component for testing thread behavior

SYNOPSIS

loadrt threadtest [count=*N*|names=*name1* [,*name2*...]]

FUNCTIONS

threadtest.*N*.increment

threadtest.*N*.reset

PINS

threadtest.*N*.count u32 out

LICENSE

GPL

NAME

timedelay – The equivalent of a time-delay relay

SYNOPSIS

loadrt timedelay [**count**=*N*][**names**=*name1*[,*name2*...]]

FUNCTIONS

timedelay.N (requires a floating-point thread)

PINS

timedelay.N.in bit in

timedelay.N.out bit out

Follows the value of **in** after applying the delays **on-delay** and **off-delay**.

timedelay.N.on-delay float in (default: 0.5)

The time, in seconds, for which **in** must be **true** before **out** becomes **true**

timedelay.N.off-delay float in (default: 0.5)

The time, in seconds, for which **in** must be **false** before **out** becomes **false**

timedelay.N.elapsed float out

Current value of the internal timer

AUTHOR

Jeff Epler, based on works by Stephen Wille Padnos and John Kasunich

LICENSE

GPL

NAME

timedelta – EMC2 HAL component that measures thread scheduling timing behavior

SYNOPSIS

loadrt timedelta [**count**=*N* | **names**=*name1* [, *name2* ...]]

FUNCTIONS

timedelta.N

PINS

timedelta.N.out s32 out

timedelta.N.err s32 out (default: 0)

timedelta.N.min s32 out (default: 0)

timedelta.N.max s32 out (default: 0)

timedelta.N.jitter s32 out (default: 0)

timedelta.N.avg-err float out (default: 0)

timedelta.N.reset bit in

LICENSE

GPL

NAME

toggle – 'push-on, push-off' from momentary pushbuttons

SYNOPSIS

loadrt toggle [**count**=*N* | **names**=*name1* [, *name2* ...]]

FUNCTIONS

toggle.N

PINS

toggle.N.in bit in
button input

toggle.N.out bit io
on/off output

PARAMETERS

toggle.N.debounce u32 rw (default: 2)
debounce delay in periods

LICENSE

GPL

NAME

toggle2nist – toggle button to nist logic

SYNOPSIS

loadrt toggle2nist [count=*N*|names=*name1*[,*name2*...]]

DESCRIPTION

toggle2nist can be used with a momentary push button connected to a toggle component to control a device that has separate on and off inputs and has an is-on output. If in changes states via the toggle output

If is-on is true then on is false and off is true.

If is-on is false the on true and off is false.

FUNCTIONS

toggle2nist.*N* (requires a floating-point thread)

PINS

toggle2nist.*N.in* bit in

toggle2nist.*N.is-on* bit in

toggle2nist.*N.on* bit out

toggle2nist.*N.off* bit out

LICENSE

GPL

NAME

tristate_bit – Place a signal on an I/O pin only when enabled, similar to a tristate buffer in electronics

SYNOPSIS

```
loadrt tristate_bit [count=N]names=name1[,name2...]
```

FUNCTIONS

tristate-bit.*N*

If **enable** is TRUE, copy **in** to **out**.

PINS

tristate-bit.*N*.in bit in

Input value

tristate-bit.*N*.out bit io

Output value

tristate-bit.*N*.enable bit in

When TRUE, copy in to out

LICENSE

GPL

NAME

tristate_float – Place a signal on an I/O pin only when enabled, similar to a tristate buffer in electronics

SYNOPSIS

```
loadrt tristate_float [count=N | names=name1 [, name2 ...]]
```

FUNCTIONS

tristate-float.*N* (requires a floating-point thread)

If **enable** is TRUE, copy **in** to **out**.

PINS

tristate-float.*N*.in float in

Input value

tristate-float.*N*.out float io

Output value

tristate-float.*N*.enable bit in

When TRUE, copy in to out

LICENSE

GPL

NAME

updown – Counts up or down, with optional limits and wraparound behavior

SYNOPSIS

loadrt updown [**count**=*N*][**names**=*name1*[,*name2*...]]

FUNCTIONS**updown.N**

Process inputs and update count if necessary

PINS**updown.N.countup** bit in

Increment count when this pin goes from 0 to 1

updown.N.countdown bit in

Decrement count when this pin goes from 1 to 0

updown.N.reset bit in

Reset count when this pin goes from 1 to 0

updown.N.count s32 out

The current count

PARAMETERS**updown.N.clamp** bit rw

If TRUE, then clamp the output to the min and max parameters.

updown.N.wrap bit rw

If TRUE, then wrap around when the count goes above or below the min and max parameters.
Note that wrap implies (and overrides) clamp.

updown.N.max s32 rw (default: *0x7FFFFFFF*)

If clamp or wrap is set, count will never exceed this number

updown.N.min s32 rw

If clamp or wrap is set, count will never be less than this number

LICENSE

GPL

NAME

wcomp – Window comparator

SYNOPSIS

loadrt wcomp [**count**=*N* | **names**=*name1* [, *name2* ...]]

FUNCTIONS

wcomp.N (requires a floating-point thread)

PINS

wcomp.N.in float in

Value being compared

wcomp.N.min float in

Low boundary for comparison

wcomp.N.max float in

High boundary for comparison

wcomp.N.out bit out

True if **in** is strictly between **min** and **max**

wcomp.N.under bit out

True if **in** is less than or equal to **min**

wcomp.N.over bit out

True if **in** is greater than or equal to **max**

NOTES

If **max** <= **min** then the behavior is undefined.

LICENSE

GPL

NAME

weighted_sum – convert a group of bits to an integer

SYNOPSIS

loadrt weighted_sum wsum_sizes=size[,size,...]

Creates weighted sum groups each with the given number of input bits (*size*).

DESCRIPTION

This component is a "weighted summer": Its output is the offset plus the sum of the weight of each TRUE input bit. The default value for each weight is 2^n where n is the bit number. This results in a binary to unsigned conversion.

There is a limit of 8 weighted summers and each may have up to 16 input bits.

FUNCTIONS**process_wsums**

Read all input values and update all output values.

PINS**wsum.N.bit.M.in** bit in

The m 'th input of weighted summer n .

wsum.N.hold bit in

When TRUE, the *sum* output does not change. When FALSE, the *sum* output tracks the *bit* inputs according to the weights and offset.

wsum.N.sum signed out

The output of the weighted summer

wsum.N.bit.M.weight signed rw

The weight of the m 'th input of weighted summer n . The default value is 2^m .

wsum.N.offset signed rw

The offset is added to the weights corresponding to all TRUE inputs to give the final sum.

NAME

xor2 – Two-input XOR (exclusive OR) gate

SYNOPSIS

loadrt xor2 [**count**=*N* | **names**=*name1* [, *name2* ...]]

FUNCTIONS

xor2.N

PINS

xor2.N.in0 bit in

xor2.N.in1 bit in

xor2.N.out bit out

out is computed from the value of **in0** and **in1** according to the following rule:

in0=TRUE in1=FALSE

in0=FALSE in1=TRUE

out=TRUE

Otherwise,

out=FALSE

LICENSE

GPL